Contents

Abbreviations xv

1 Introduction 1
1.1 Embedded System Overview 1
1.2 Hypothetical Robot Control System 2
1.3 Digital Design Platforms 4
1.3.1 Microprocessor-based Design 5
1.3.2 Single-chip Computer/Microcontroller-based Design 7
1.3.3 Application Specific Standard Products (ASSPs) 8
1.3.4 Design Using FPGA 10
1.4 Organization of the Book 12
Problems 14
References 15
Further Reading 16

2 Hardware Description Language: Verilog 17
2.1 Software and Hardware Description Languages 17
2.2 Let's Use Verilog as Our HDL! 19
2.3 Design Examples Using Verilog 19
2.3.1 Gate Level Model 20
2.3.2 Combinational Circuits Using Data Flow Modelling 21
2.3.3 Behavioural Logic 24
2.3.4 Finite State Machine (FSM) 27
2.3.5 Arithmetic Using HDL 35
2.4 Pipelining 40
2.5 Module Instantiation and Port Mapping 40
2.6 Use of Pre-designed HDL Codes 45
2.7 Simulating Digital Logic Using Verilog 47
2.7.1 EDA Tool Flow for Simulation 47
2.7.2 Creating a Test Bench for HDL-based Digital Logic 49
2.7.3 Post Place and Route Simulation 49
2.7.4 Simulation of Algorithm Using Pre-designed Codes 51

Problems 51
Further Reading…….. 51

3 FPGA Devices 53
3.1 FPGA and CPLD 53
3.2 Architecture of a FPGA 54
3.2.1 FPGA Interconnect Technology 54
3.2.2 Logic Cell 56
3.2.3 FPGA Memory 61
3.2.4 Clock Distribution and Scaling 67
3.2.5 I/O Standards 70
3.2.6 Multipliers 71
3.3 Floor Plan and Routing 72
3.4 Timing Model for a FPGA 74
3.5 FPGA Power Usage 75
Problems 79
Further Reading……. 80

4 FPGA-based Embedded Processor 81
4.1 Hardware–Software Task Partitioning 81
4.2 FPGA Fabric Immersed Processors 82
4.2.1 Soft Processors 82
4.2.2 Hard Processors 84
4.2.3 Tool Flow for Hardware–Software Co-design 84
4.3 Interfacing Memory to the Processor 85
4.4 Interfacing Processor with Peripherals 86
4.4.1 Types of On-chip Interfaces 88
4.4.2 Wishbone Interface 89
4.4.3 Avalon Switch Matrix 90
4.4.4 OPB Bus Interface 90
4.5 Design Re-use Using On-chip Bus Interface 92
4.6 Creating a Customized Microcontroller 94
4.7 Robot Axis Position Control 98
Problems 100
References……. 101
Further Reading……. 101

5 FPGA-based Signal Interfacing and Conditioning 103
5.1 Serial Data Communication 103
5.2 Physical Layer for Serial Communication 106
5.2.1 RS-232-based Point-to-Point Communication 106
5.2.2 RS-485-based Multi-point Communication 106
5.3 Serial Peripheral Interface (SPI) 109
5.4 Signal Conditioning with FPGAs 111
Problems 113
References……. 114

6 Motor Control Using FPGA 115
6.1 Introduction to Motor Drives 115
6.2 Digital Block Diagram for Robot Axis Control 115
6.2.1 Position Loop 116
6.2.2 Speed Loop 117
6.2.3 Power Module 118
6.3 Case Studies for Motor Control 119
6.3.1 Stepper Motor Controller 119
6.3.2 Permanent Magnet DC Motor 122
6.3.3 Brushless DC Motor 125
6.3.4 Permanent Magnet Rotor (PMR) Synchronous Motor 126
6.3.5 Permanent Magnet Synchronous Motor (PMSM) 131
Problems 135
Further Reading…… 136

7 Prototyping Using FPGA 139
7.1 Prototyping Using FPGAs 139
7.2 Test Environment for the Robot Controller 142
7.3 FPGA Design Test Methodology 143
7.3.1 UART for Software Testing 143
7.3.2 FPGA Hardware Testing Methodology 144
Problems 151
References……. 152

Index 153