CoreCORDIC v4.0

Handbook

Microsemi

Revision History

Date	Revision	Change
15 June 2015	V6	Sixth release

Confidentiality Status

This is a non-confidential document.

Microsemi

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Preface

About this Document

This handbook provides details about Microsemi® CoreCORDIC and how to use it.

Intended Audience

Microsemi FPGA designers using Libero® System-on-Chip (SoC) or Libero Integrated Design Environment (IDE).

References

Third Party Publications

- Ray Andraka, “A survey of CORDIC algorithms for FPGA based computers“
  http://www.andraka.com/files/crdcsrvy.pdf
- http://www.dspguru.com/dsp/faqs/cordic
- J.S.Walther, “A unified algorithm for elementary functions”
  http://www.computer.org/csdl/proceedings/afips/1971/5077/00/50770379.pdf
- Clive Maxfield, “Rounding algorithms 101 Redux”
  http://www.eetimes.com/document.asp?doc_id=1274515

Introduction

Overview

CoreCORDIC produces Microsemi field programmable gate array (FPGA)-optimized COordinate Rotation DIgital Computer (CORDIC) logic based on user-defined parameters. The CORDIC algorithm is commonly used for multiplierless vector rotation, conversion from polar to rectangular coordinates and vice-versa, trigonometric function calculation.

The IP core can be configured for one of the following functions:

- General vector rotation
- Polar to rectangular coordinate translation
- Rectangular to polar coordinate translation
- Sine and cosine computation
- Arctangent computation

You can select one of two architecture options to implement the CORDIC functionality—parallel and word-serial. The parallel architecture provides a single-clock data throughput but takes more device resources. The word-serial architecture is smaller but takes multiple clock cycles to generate desired output data.

The core extends valid range of the input angle (phase) values to the full circle by supporting an optional coarse rotation mode.

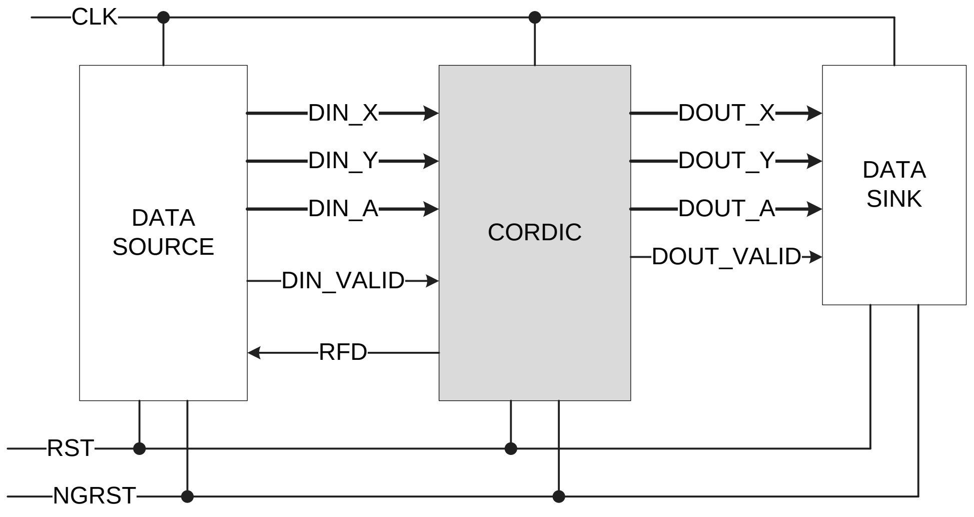


Figure 1 CORDIC Use Example

An example of using the word-serial CORDIC engine is shown in Figure 1. In response to CoreCORDIC request for data, a Data Source supplies input coordinate data DIN_X, DIN_Y, and DIN_A accompanied with validity bit DIN_VALID. The CORDIC engine then deasserts the RFD signal and starts processing the data. On completion, the CORDIC generates the rotated or translated vector coordinates DOUT_X, DOUT_Y, and DOUT_A followed by the validity bit DOUT_VALID. The input and output data depend on a CoreCORDIC functional mode and described below. The core uses the single clock signal CLK, and can be optionally reset by negative asynchronous NGRST or synchronous RST signals.

The parallel CORDIC engine does not generate the request RFD signal, as it is ready to accept new input data on every clock cycle.

Key Features

Following are the key features of CoreCORDIC:

- Parameterizable RTL generator
- Functional modes:
  - General vector rotation
  - Conversion from Polar to Rectangular coordinates
  - Translation from Rectangular to Polar coordinates
  - Sine and Cosine calculation
  - Arctangent (angle) calculation
- Configurable 8 to 48 bits input and output data bit resolution
- Automatic or user-controllable precision of internal calculations up to 48 bits
- Variety of output rounding options:
  - Truncation
  - Convergent rounding (round to nearest even)
  - Symmetric rounding (round to positive or negative infinity)
  - Round up (round to positive infinity)
- Word-serial architecture for smaller area
- Parallel architecture for high throughput
- Configurable number of iterations up to 48
- Synchronous design using a single-clock

Core Version

This handbook supports CoreCORDIC v4.0.

Supported Families

The CoreCORDIC v4.0 supports the following families:

- SmartFusion®2
- IGLOO®2
- IGLOO®
- IGLOOe
- IGLOO PLUS
- RTG4™
- ProASIC®3
- ProASIC3E
- ProASIC3L
- ProASICPLUS
- SmartFusion®
- Fusion
- Axcelerator®
- RTAX-S/SL and RTAX-DSP

Device Utilization and Performance

CoreCORDIC has been implemented in Microsemi SmartFusion2, RTAX-S, and ProASIC3 devices. The core data are listed in Table 1, Table 2, Table 3, and Table 4. Test configurations are listed in Table 5. In all cases, typical synthesis settings were used. Timing driven high effort five passes layout was used.

Table 1 ·SmartFusion2 Utilization and Performance for the M2S050 Device at Speed Grade -1

Function	**Architecture**	**Coarse**	**Device Utilization**		**Max Clock Rate, MHz**	**Transformation Time, ns**
			4-LUT	**DFF**		
General Rotation	Word-serial	No	508	300	187.5	90.7
		Yes	570	345	170.5	99.7
	Parallel	No	1053	1066	243.4	4.1
		Yes	1147	1105	238	4.2
Rectangular to Polar Conversion	Word-serial	No	484	281	185.6	91.6
		Yes	616	367	188	90.4
	Parallel	No	999	1025	243	4.1
		Yes	1168	1145	245	4.1

Table 2 RTG4 Utilization and Performance for the RT4G150 Device at Speed Grade -1

Function	**Architecture**	**Coarse**	**Device Utilization**		**Max Clock Rate, MHz**	**Transformation Time, ns**
			4-LUT	**DFF**		
General Rotation	Word-serial	No	502	298	143.6	118.4
		Yes	574	341	145.3	117
	Parallel	No	1015	1071	199	5
		Yes	1111	1110	195	5.1
Rectangular to Polar Conversion	Word-serial	No	485	284	143.8	118.2
		Yes	602	367	142	119.7
	Parallel	No	979	1035	216	4.6
		Yes	1145	1154	200	5

Table 3 RTAX-S Utilization and Performance for the RTAX250S Device at Speed Grade -1

Function	Architecture	Coarse	Device Utilization			Max Clock Rate, MHz	Transformation Time, ns
			Sequential	Combinatorial	Total		
General Rotation	Word-serial	No	297	339	636	98.8	172.1
		Yes	347	489	836	96.8	175.6
	Parallel	No	1108	2164	3272	86.7	11.5
		Yes	1149	2311	3460	89.1	11.2
Rectangular to Polar Conversion	Word-serial	No	275	328	603	98.4	172.8
		Yes	382	493	875	95.2	178.6
	Parallel	No	1092	2098	3190	86.1	11.6
		Yes	1215	2302	3517	83.3	12

Table 4 ProASIC3 Utilization and Performance for the A3P600 Device at Speed Grade -2

Function	Architecture	Coarse	Device Utilization			Max Clock Rate, MHz	Transformation Time, ns
			Sequential	Combinatorial	Total		
General Rotation	Word-serial	No	249	930	1179	66.1	257.2
		Yes	312	1136	1448	62.8	270.7
	Parallel	No	1090	4050	5140	81.7	12.2
		Yes	1129	4154	5283	83.8	11.9
Rectangular to Polar Conversion	Word-serial	No	249	986	1235	63	269.8
		Yes	345	1200	1545	64	265.6
	Parallel	No	1041	3915	4956	81.5	12.3
		Yes	1163	4148	5311	85.1	11.8

Table 5 CoreCORDIC Test Configuration

Parameter	Value
In/Out data width	16 bits
Data Path Control	Auto
Number of Iterations	16
Rounding	Truncation
HDL language	Verilog

Functional Block Description

Block Diagram

Figure 2 shows the block diagram of CoreCORDIC.

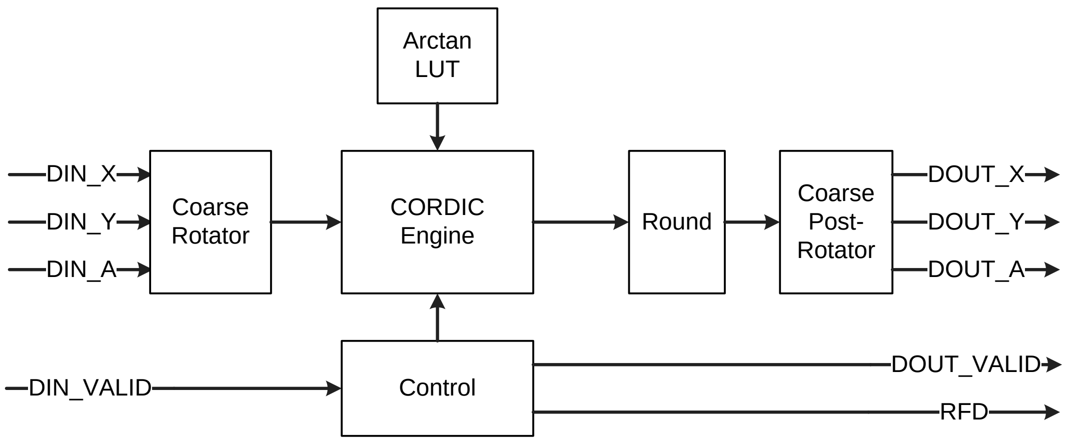


Figure 2 CoreCORDIC Block Diagram

CORDIC engine implements the CORDIC algorithm that calculates trigonometry functions using additions, subtractions, and the pre-computed elementary rotation angle look-up table, Arctan LUT. The CORDIC algorithm works properly when a rotation angle is within the range from –π/2 to π/2. The optional Coarse Rotator puts an arbitrary rotation angle within the valid range. Then the Coarse Post-Rotator applies a similar rotation in the opposite direction thus, negating the coarse vector rotation applied earlier.

A bit width of the CORDIC engine arithmetic unit is often larger than a required output bit width. The Round block applies one of four available truncation or rounding techniques to reduce the data width.

The word-serial architecture asserts the RFD signal once it calculates a previous vector output. Upon obtaining the DIN_VALID signal, the core deactivates the RFD flag and runs a user-selected number of CORDIC iterations; one iteration per clock cycle. As soon as the core is ready to accept a new input vector, it raises the RFD flag and soon after the DOUT_VALID signal.

The parallel architecture does not generate the RFD flag, as it is always ready to accept a new vector.

CORDIC algorithm applies a processing gain *K*. Its value approaches *K*=1.646760 as the number of iterations goes up. In other words, the CORDIC output vectors are multiplied by the gain factor *K*.

Core Description

Architectures

The core implements two CORDIC architectures—word-serial and parallel. You can select the one that suits your overall design needs.

Word-Serial Architecture

The word-serial architecture takes relatively small amount of chip resources. It runs CORDIC iterations on the same hardware sequentially, one by one. Every iteration takes a clock cycle. Overall it takes *Number of Iterations+3* clock cycles to complete CORDIC computations when coarse rotation is disabled. Figure 3 shows the full computation cycle as a delay between DIN_VALID and DOUT_VALID signals.

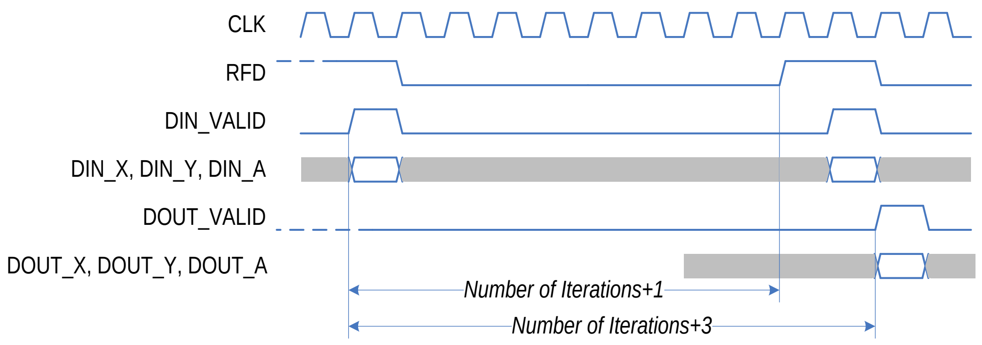


Figure 3 Word-Serial CORDIC Timing (Coarse Rotation Disabled)

Fresh data however, can come to the CORDIC input in *Number of Iterations+1* clock cycles that is, by the time when the next RFD signal gets asserted (Figure 3). Thus the minimal distance between consecutive DIN_VALID pulses equals the delay between the DIN_VALID and the next positive edge of the RFD signal. This distance defines the minimal CORDIC cycle for the word-serial architecture.

Figure 4 shows the CORDIC delays when coarse rotation enabled. The minimal CORDIC cycle there equals *Number of Iterations+2* and the CORDIC delay is *Number of Iterations+6*.

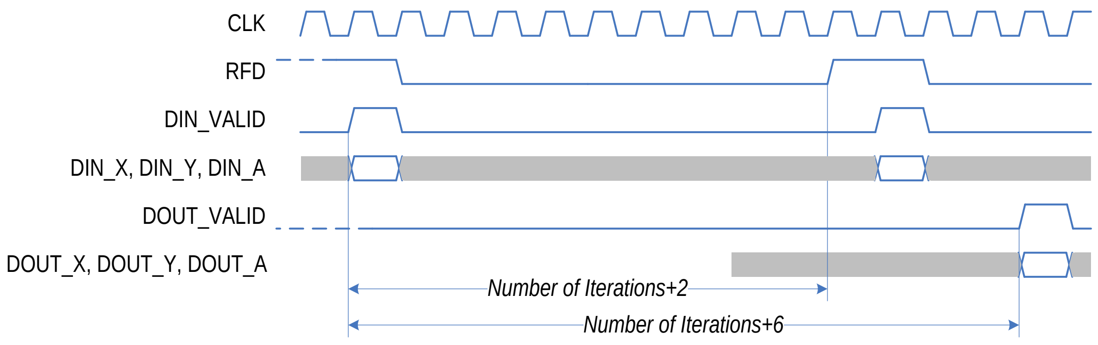


Figure 4 Word-Serial Timing (Coarse Rotation Enabled)

The DIN_VALID signals not qualified by active RFD signal are neglected.

Parallel Architecture

The parallel architecture can take fresh input data on every clock cycle. It has dedicated hardware for each iteration so, that all iterations run concurrently. The core does not generate RFD flag, as it is always ready to accept fresh input data and a data source can supply data unconditionally.

There is latency between input and output CORDIC data, as shown in Figure 5.

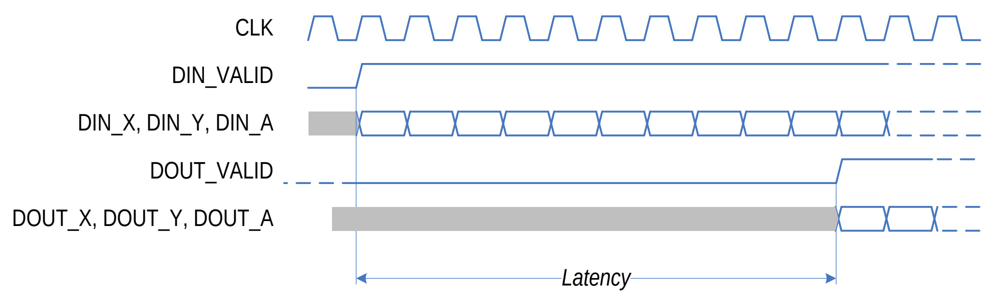


Figure 5 Parallel CORDIC Timing

The latency equals *Number of Iterations+2* clock cycles at disabled coarse rotator. Once enabled, coarse rotator adds two clock cycles to result in the latency of *Number of Iterations+4*.

Data Path

The CORDIC engine data path can differ of input or output data path widths. You can control the bit resolution of the engine by setting the DP_OPTION parameter. It offers three options: automatic, manual, and full precision data path width. The automatic option sets the engine data path width two bits more than the input data width, IN_BITS up to 48 bits maximum. This setting is recommended for the most common case when input and output data are of the same bit width, and the number of iterations equals the width.

You can manually set the CORDIC engine bit resolution by selecting appropriate option and indicating the desired width as DP_WIDTH parameter value. Finally you can get maximal achievable calculation precision by selecting full precision option. The engine data path width is defined as IN_BITS+ITERATIONS+$\log_2$ (ITERATIONS) up to 48 bits.

Note: The core only supports the engine data path widths that are equal or greater than the Output Data bit width OUT_BITS.

Rounding

The core applies rounding at the CORDIC engine output to cut the extra bits the CORDIC engine possibly uses. CoreCORDIC provides a choice of four rounding techniques:

- Truncation of the extra bits. The technique applies when Output Data width OUT_BITS is less than the one of the CORDIC engine
- Convergent rounding otherwise called Banker's rounding or Round-Half-Even applies when the difference between the engine and Output Data widths is at least two bits
- Symmetric rounding (Symmetric Round-Half-Up or Rounding-Away-from-Zero) applies when the difference between the engine and Output Data widths is at least two bits
- Round up (asymmetric Round-Half-Up) applies when the engine bit width is at least one more than the OUT_BITS

Core user interface warns you when this or other rounding technique does not apply due to the small difference between the CORDIC engine and Output Data bit widths. A few examples of rounding floating-point numbers using various techniques are shown in Table 6.

Table 6 Rounding Techniques

Floating-point number	Truncation	Convergent rounding	Symmetric rounding	Round up
0.7	0	1	1	1
-0.7	-1	-1	-1	-1
1.4	1	1	1	1
-1.4	-2	-1	-1	-1
1.5	1	2	2	2
-1.5	-2	-2	-2	-1
2.5	2	2	3	3
-2.5	-3	-2	-3	-2

Functional Modes

The CoreCORDIC v4.0 supports five functional modes.

General Vector Rotation

In this mode, the core rotates the input vector (X, Y) by the input angle A to produce the output vector (X’, Y’). Figure 6 shows the vector rotation. Note, the output vector (X’, Y’) is scaled up by the CORDIC gain *K*.

Refer to the Function-Dependent Input and Output Values section for the core input and output data values in this mode.

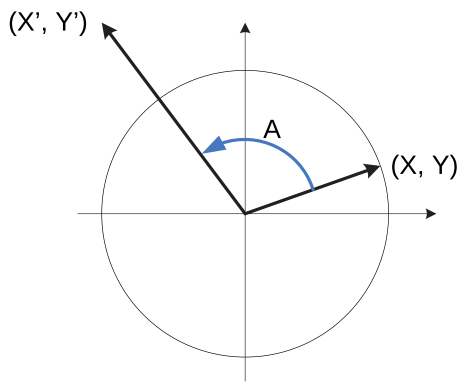


Figure 6 General Vector Rotation

Polar to Rectangular Coordinate Translation

In this functional mode, CoreCORDIC rotates a specific vector with initial ordinate value Y=0. Figure 7 shows the vector rotation. Polar coordinates, magnitude R and angle A get translated into Cartesian pair (X’, Y’):

$$X' = K * R * \cos(A)$$

EQ1

$$Y' = K * R * \sin(A)$$

EQ2

Note: The output vector (X’, Y’) is scaled up by the CORDIC gain *K*.

Refer to the Function-Dependent Input and Output Values section for the core input and output data values in this mode.

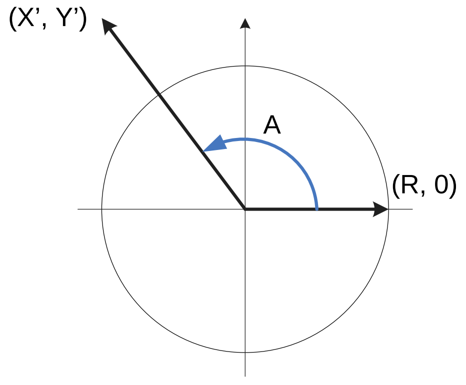


Figure 7 Polar to Rectangular Coordinate Translation

Rectangular to Polar Coordinate Translation

In this functional mode, CORDIC rotates the input vector (X, Y) until it aligns with x-axis, refer to Figure 8. A pair of Cartesian coordinates (X, Y) gets translated into magnitude and phase of the vector:

$$X' = K * \sqrt{X^2 + Y^2}$$

EQ3

$$A' = \arctan\left(\frac{Y}{X}\right)$$

EQ4

Note:

1. The output vector (X', 0) is scaled up by the CORDIC gain K.
2. The Equation EQ4 applicable when the input vector (X, Y) is located in the first quadrant. For the full description, refer to the Appendix - Four-Quadrant Arctangent Function.

Refer to the Function-Dependent Input and Output Values section for the core input and output data values in this mode.

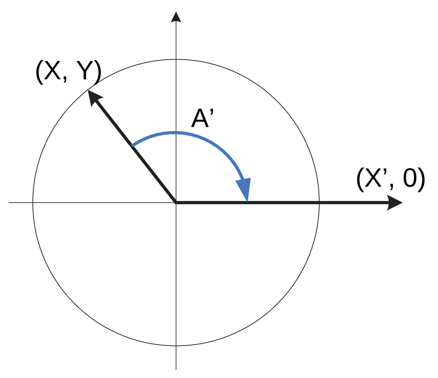


Figure 8 Rectangular to Polar Coordinate Translation

Sine and Cosine

In this functional mode, the vector rotation is used to calculate sine and cosine values. Provided the input magnitude is set to be R = 1/K, refer to Figure 9. The Vector Rotation equations yield the following values:

$$X' = K * \frac{1}{K} * cos\theta = cos\theta$$

EQ5

$$Y' = K * \frac{1}{K} * sin\theta = sin\theta$$

EQ6

The core automatically supplies the magnitude value of 1/K to the DIN_X input as well, as 0 to the DIN_Y input. Only the angle argument A needs to be provided to the core. In the Sine and Cosine mode, the results are not scaled by the CORDIC gain factor.

Refer to the Function-Dependent Input and Output Values section for the core input and output data values in this mode.

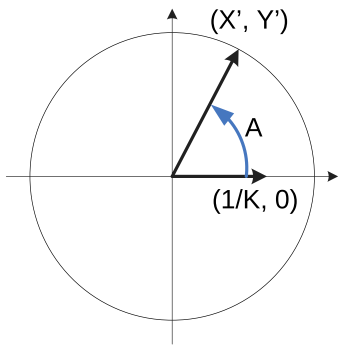


Figure 9 Sine and Cosine Functional Mode

Arctangent

The Arctangent function is similar to the Rectangular to Polar translation. It only outputs the arctangent value, which does not introduce the CORDIC gain.

Refer to the Function-Dependent Input and Output Values section for the core input and output data values in this mode.

Function-Dependent Input and Output Values

Table 7 shows CoreCORDIC input and output signal meanings in every functional mode. K denotes the CORDIC processing gain. Table 7 shows the available data inputs and outputs in every functional mode, in bold.

Table 7 ·CORDIC Input and Output Values

Functional Mode	CORDIC Input Values	CORDIC Output Values
General Rotation	**DIN_X**: Abscissa X	**DOUT_X** = K*(X*cos(A) – Y*sin(A))
	DIN_Y: Ordinate Y	**DOUT_Y** = K*(Y*cos(A) + X*sin(A))
	DIN_A: Angle A	DOUT_A = No meaning
Polar to Rectangular Translation	**DIN_X**: Magnitude R	**DOUT_X** = K*R*cos(A)
	DIN_Y: 0	**DOUT_Y** = K*R*sin(A)
	DIN_A: Angle A	DOUT_A = No meaning
Rectangular to Polar Translation	**DIN_X**: Abscissa X	**DOUT_X** = K*sqrt(X^2 + Y^2)
	DIN_Y: Ordinate Y	DOUT_Y = No meaning
	DIN_A: 0	**DOUT_A** = arctan(Y/X)
Sine and Cosine	DIN_X: 0	**DOUT_X** = cos(A)
	DIN_Y: 0	**DOUT_Y** = sin(A)
	DIN_A: Angle A	DOUT_A = No meaning
Arctangent	**DIN_X**: Abscissa X	DOUT_X = No meaning
	DIN_Y: Ordinate Y	DOUT_Y = No meaning
	DIN_A: 0	**DOUT_A** = arctan(Y/X)

Data Formats

CoreCORDIC uses different data formats for linear (X and Y) and angular (A) data.

Linear Formats

The CORDIC input data signals in the floating-point domain must be in the range [-1.0; 1.0]. An input signal that falls outside of the range can produce incorrect results.

CoreCORDIC accepts fixed-point IN_BITS-wide input signals DIN_X and DIN_Y with the most significant bit (MSB) representing the sign and the next bit representing the integer part of the input signal. Conversion from floating to fixed-point follows the formula:

$$\text{Fixed-point X} = 2^{\text{IN\_BITS-2}} * \text{Floating-point x} \qquad \textit{EQ7}$$

The following examples show the correspondence between floating and fixed-point numbers at IN_BITS = 10:

1.0	<>	01.00000000	<>	“01 0000 0000”
-1.0	<>	11.00000000	<>	“11 0000 0000”
0.75	<>	00.11000000	<>	“00 1100 0000”
-0.75	<>	11.01000000	<>	“11 0100 0000”
0.25	<>	00.01000000	<>	“00 0100 0000”
-0.25	<>	11.11000000	<>	“11 1100 0000”
0.1	<>	00.00011010	<>	“00 0001 1010”
-0.1	<>	11.11100110	<>	“11 1110 0110”

Due to the CORDIC algorithm’s gain, the output linear data (DOUT_X, DOUT_Y) signal range is approximately [-2.32; 2.32]. This requires a different fixed-point format capable of representing the wider range. The MSB of the output linear data identifies the sign, and the next two bits represent the integer part of the output signal. Conversion from linear output fixed-point format to floating point follows the formula:

$$\text{Floating-point } x_{out} = \text{Fixed-point Xout}/2^{\text{OUT\_BITS-3}} \qquad \textit{EQ8}$$

The following example show the correspondence between floating and fixed-point numbers at OUT_BITS = 10:

“01 0010 1001”	<>	010.0101001	<>	2.32
“10 1101 0111”	<>	101.1010111	<>	-2.32
“01 0000 0000”	<>	010.0000000	<>	2.0
“11 0000 0000	<>	110.0000000	<>	-2.0
“00 1000 0000	<>	001.0000000	<>	1.0
“11 1000 0000	<>	111.0000000	<>	-1.0
“00 0100 0000	<>	000.1000000	<>	0.5
“11 1100 0000	<>	111.1000000	<>	-0.5
“00 0000 1101	<>	000.0001101	<>	0.1
“11 1111 0011	<>	111.1110011	<>	-0.1

Angular Format

The CORDIC input angle in the floating-point domain must be in the range [-π; π] when coarse rotator is enabled. With disabled coarse rotator, the valid angular range is [-π/2; π/2]. Output range for the angular data is the same.

CoreCORDIC uses a single fixed-point angular format for input and output angle signals DIN_A and DOUT_A. The input and output angles are expressed as a fraction of π, that is the angle value of 1.0 represents π, value of 0.5 represents π/2, etc. The fixed-point MSB identifies the angle sign, and the next bit presents the integer part of the angle. Angle conversion from floating to fixed-point follows the formula:

$$\text{Fixed-point A} = 2^{\text{IN\_BITS-2}} * \text{Floating-point a} / \pi \qquad \textit{EQ9}$$

Where, Floating-point a is expressed in radians.

The following examples show the correspondence between floating and fixed-point angles at IN_BITS=10 or OUT_BITS=10:

π	<>	01.00000000	<>	“01 0000 0000”
-π	<>	11.00000000	<>	“11 0000 0000”
0.75*π	<>	00.11000000	<>	“00 1100 0000”
-0.75*π	<>	11.01000000	<>	“11 0100 0000”
0.5*π	<>	00.10000000	<>	“00 1000 0000”
-0.5*π	<>	11.10000000	<>	“11 1000 0000”
0.25*π	<>	00.01000000	<>	“00 0100 0000”
-0.25*π	<>	11.11000000	<>	“11 1100 0000”
0.1*π	<>	00.00011010	<>	“00 0001 1010”
-0.1*π	<>	11.11100110	<>	“11 1110 0110”

Interface Description

RTL Parameters/Generics

Table 8 shows verilog parameters and VHDL generics.

Table 8 CoreCORDIC Parameters and Generics

Parameter	User Interface Name	Valid Range	Default Value	Description
ARCHITECT	Architecture	1, 2	1	CORDIC implementation architecture: 1: Word-serial 2: Parallel
MODE	Mode	0-4	0	0: General vector rotation 1: Polar to Rectangular Coordinate Translation 2: Rectangular to Polar Coordinate Translation 3: Sin and Cos 4: Arctangent
IN_BITS	Input Data	8-48	16	Input signal bit widths. All input signals have the same bit width of IN_BITS
OUT_BITS	Output Data	8-48	16	Output signal bit widths. All output signals have the same bit width of OUT_BITS
ROUND	Rounding	0-3	0	0: Truncation 1: Convergent rounding (Rounding to the nearest even) 2: Symmetric rounding (rounding away from 0) 3: Rounding up to positive infinity
ITERATIONS	Number of Iterations	8-48	16	Number of iterations
COARSE	Coarse Rotator	0, 1	0	0: Do not build optional coarse rotator 1: Build optional coarse rotator
DP_OPTION	Data Path Control	0-2	0	0: Set automatic data path bit width based on input width, IN_BITS 1: Set data path bit width equal to DP_WIDTH 2: Set full precision data path bit width
DP_WIDTH	Data Path	8-48	16	Data path bit width used when DP_OPTION=1 is set

I/O Ports

Figure 10 shows the core ports and tab provides information on every port.

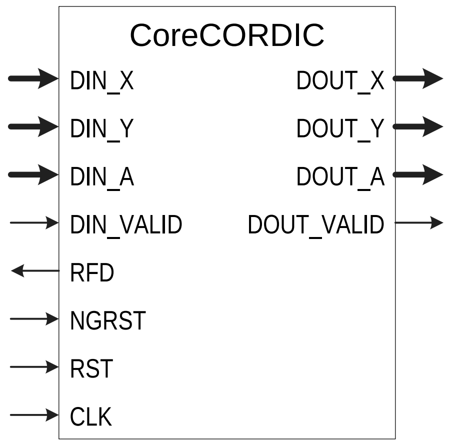


Figure 10 CoreCORDIC I/O Ports

Data on I/O buses are present in 2’s complement formats described in Data Formats section.

Table 9 I/O Ports

Port Name	Type	Width	Description
DIN_X	In	IN_BITS	Input data bus X. Meaning of the signal X in every particular mode is described in Table 7
DIN_Y	In	IN_BITS	Input data bus Y. Meaning of the signal Y in every particular mode is described in Table 7
DIN_A	In	IN_BITS	Input data bus A. Meaning of the signal A in every particular mode is described in Table 7
DIN_VALID	In	1	Input bus signals are valid. Indicates the set of input signals is ready for the CORDIC to process. The Word-serial CORDIC only accepts the DIN_VALID signal when the output signal RFD is active. The parallel CORDIC accepts any DIN_VALID signal.
DOUT_X	Out	OUT_BITS	Output data bus X. Meaning of the signal DOUT_X in every particular mode is described in Table 7
DOUT_Y	Out	OUT_BITS	Output data bus Y. Meaning of the signal DOUT_Y in every particular mode is described in Table 7
DOUT_A	Out	OUT_BITS	Output data bus A. Meaning of the signal DOUT_A in every particular mode is described in Table 7
DOUT_VALID	Out	1	The core signals a fresh set of output data is ready to be read
RFD	Out	1	Request For Data. The port is present on the Word-serial architecture only. The core generates the RFD signal when it is ready to start processing the next set of input data. On parallel architecture, the core is always ready to accept a fresh data set.

Port Name	Type	Width	Description
CLK	In	1	System clock with active positive edge
NGRST	In	1	Optional asynchronous reset. Resets all registers and state machines. At least one of the two signals, NGRST or RST need to be supplied after powering on an FPGA device.
RST	In	1	Optional synchronous reset. Resets all registers and state machines. At least one of the two signals, NGRST or RST need to be supplied after powering on an FPGA device.

Tool Flows

License

CoreCORDIC is included in the Libero catalog and does not require a separate license to be instantiated and used in the Microsemi devices. Complete source code and a user testbench are provided for the core.

RTL

Complete RTL source code is provided for the core.

SmartDesign

CoreCORDIC is available for download to the Libero IP catalog through the web repository. Once it is listed on the catalog, the core can be instantiated using the SmartDesign flow. Figure 11 shows an example of instantiated CoreCORDIC.

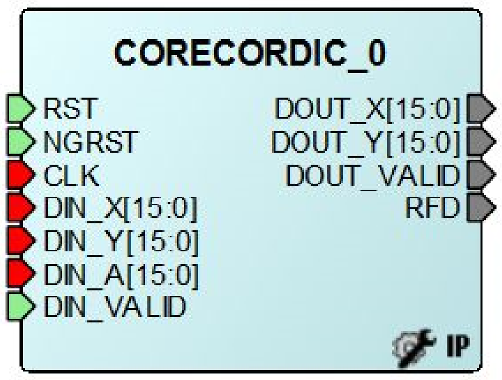
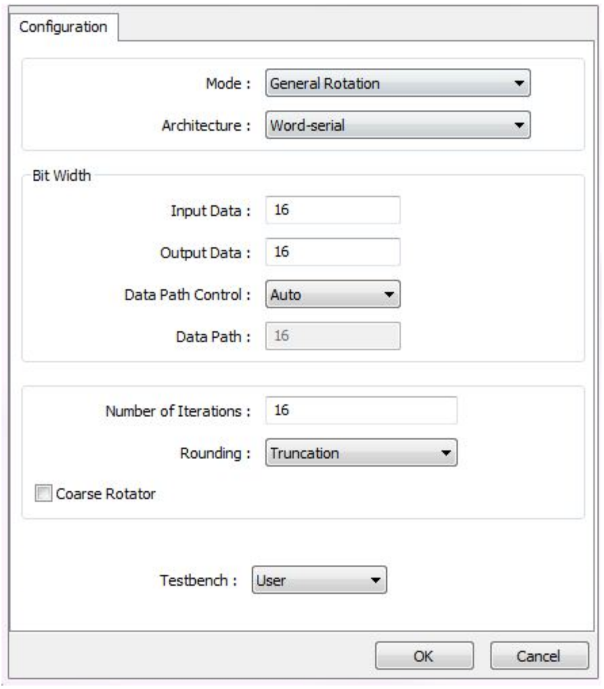


Figure 11 SmartDesign CoreCORDIC Instance View

The core can be configured using the configuration window in the SmartDesign, as shown in Figure 12. For information on using the SmartDesign to configure, connect, and generate cores, refer to the Libero online help.



Mode : General Rotation
Architecture : Word-serial

Bit Width
Input Data : 16
Output Data : 16
Data Path Control : Auto
Data Path : 16

Number of Iterations : 16
Rounding : Truncation
☐ Coarse Rotator

Testbench : User

Figure 12 SmartDesign CoreCORDIC Configuration Window

Simulation Flows

To run simulations, select the User Testbench in the core configuration interface. Along with generating the core, the Libero installs the pre-synthesis testbench HDL files. Set the design root to a top-level component of the core. Then run the simulation tool from the Libero Design Flow pane

Synthesis in Libero

To run synthesis on the core, set the design root to the SmartDesign component instance and run the synthesis tool from the Libero software Design Flow pane.

Place-and-Route in Libero

After the design has been synthesized, run **Compile** and then place-and-route tools.

Testbench Operation and Modification

This release of CoreCORDIC includes a user testbench that verifies operation of the core. The user testbench automatically adjusts itself to the selected configuration of the core.

A simplified block diagram of the user testbench is shown in Figure 13. The user testbench instantiates the configured CORDIC design, as well as behavioral non-synthesizable models of an input test vector generator, golden behavioral CORDIC (Golden output vector generator), comparator, and a signal generator that provides necessary clock and reset signals.

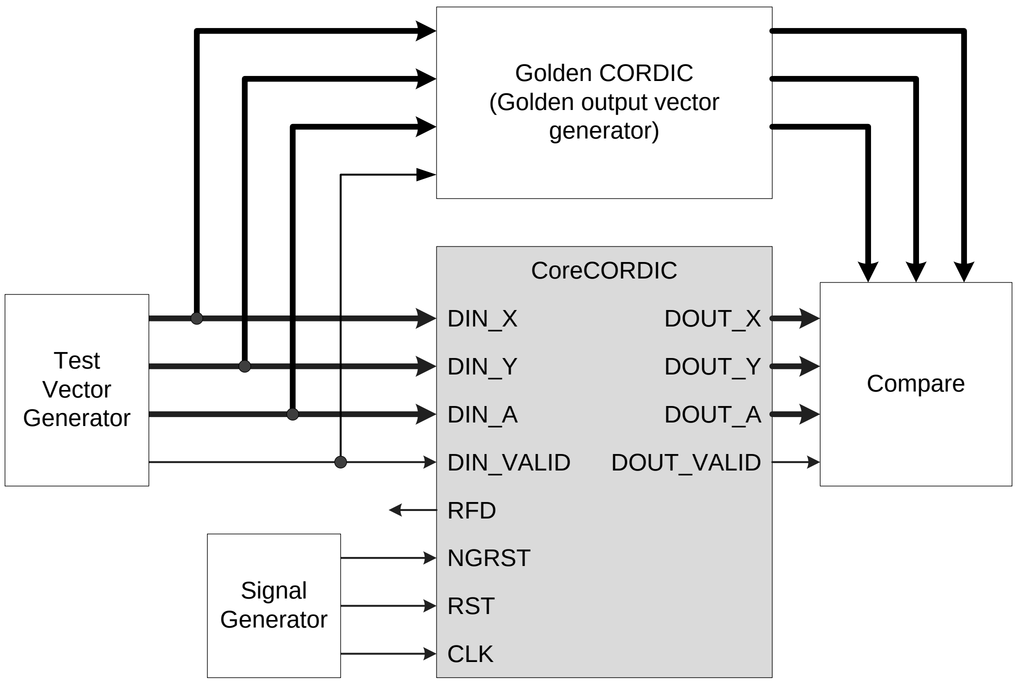


Figure 13 User Testbench

The testbench compares the actual CORDIC output data DOUT_X, DOUT_Y, and DOUT_A against the golden output vectors. In case of mismatch during simulation, it prints out an error message. CoreCORDIC automatically generates the Verilog or VHDL testbench behavioral code based on the selected core language.

Ordering Information

Ordering Codes

CoreCORDIC can be ordered through your local Microsemi sales representative. It should be ordered using the following numbering scheme: CoreCORDIC-XX, where XX is listed in Table 10.

Table 10 Ordering Codes

XX	Description
RM	RTL for RTL source — Multiple-use license
Note: CoreCORDIC-RM is included free in the Libero software Catalog if you have a valid Libero software license.	

Appendix - Four-Quadrant Arctangent Function

In the Coarse mode (COARSE=1), CoreCORDIC implements the full circle Rectangular to Polar Coordinate Translation Conversion where the vector phase is defined as four-quadrant arctangent similar to atan2 function found in C and Matlab. The first quadrant vector phase indicates:

$$\text{arctan}_{q1} = \text{arctan}(Y/X) \quad \textit{EQ10}$$

Then CoreCORDIC calculates the phases of the vectors in the other quadrants as follows:

$$\text{arctan}_{q2} = \pi - \text{arctan}_{q1} \quad \textit{EQ11}$$

$$\text{arctan}_{q3} = -\pi + \text{arctan}_{q1} \quad \textit{EQ12}$$

$$\text{arctan}_{q4} = -\ \text{arctan}_{q1} \quad \textit{EQ13}$$

Figure 14 shows examples of the four-quadrant arctangent calculations.

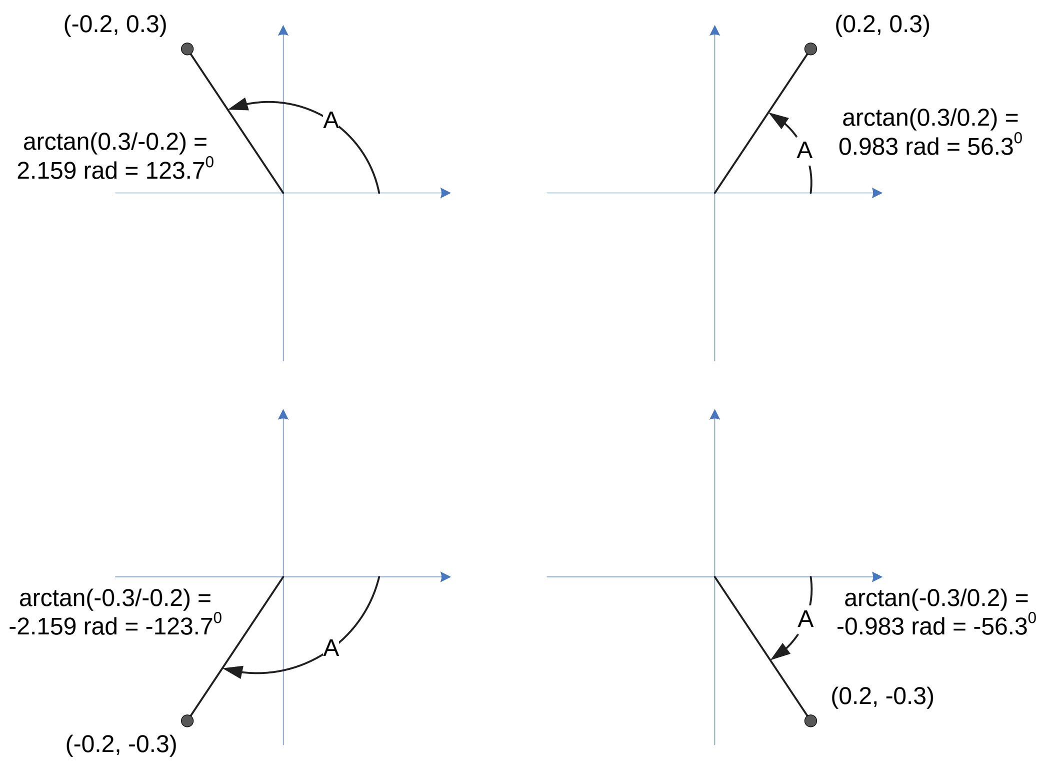


Figure 14 Examples of Four-Quadrant Phase Calculations

List of Changes

The following table shows important changes made in this document for each revision.

Date	Change	Page
Revision 6 (June 2015)	Updated the document as per the new HB specifications.	NA

Product Support

Microsemi SoC Products Group backs its products with various support services, including Customer Service, Customer Technical Support Center, a website, electronic mail, and worldwide sales offices. This appendix contains information about contacting Microsemi SoC Products Group and using these support services.

Customer Service

Contact Customer Service for non-technical product support, such as product pricing, product upgrades, update information, order status, and authorization.

From North America, call **800.262.1060**
From the rest of the world, call **650.318.4460**
Fax, from anywhere in the world **650. 318.8044**

Customer Technical Support Center

Microsemi SoC Products Group staffs its Customer Technical Support Center with highly skilled engineers who can help answer your hardware, software, and design questions about Microsemi SoC Products. The Customer Technical Support Center spends a great deal of time creating application notes, answers to common design cycle questions, documentation of known issues and various FAQs. So, before you contact us, please visit our online resources. It is very likely we have already answered your questions.

Technical Support

For Microsemi SoC Products Support, visit http://www.microsemi.com/products/fpga-soc/design-support/fpga-soc-support.

Website

You can browse a variety of technical and non-technical information on the Microsemi SoC Products Group home page, at http://www.microsemi.com/soc/.

Contacting the Customer Technical Support Center

Highly skilled engineers staff the Technical Support Center. The Technical Support Center can be contacted by email or through the Microsemi SoC Products Group website.

Email

You can communicate your technical questions to our email address and receive answers back by email, fax, or phone. Also, if you have design problems, you can email your design files to receive assistance. We constantly monitor the email account throughout the day. When sending your request to us, please be sure to include your full name, company name, and your contact information for efficient processing of your request.

The technical support email address is soc_tech@microsemi.com.

My Cases

Microsemi SoC Products Group customers may submit and track technical cases online by going to My Cases.

Outside the U.S.

Customers needing assistance outside the US time zones can either contact technical support via email (soc_tech@microsemi.com) or contact a local sales office. Sales office listings can be found at www.microsemi.com/soc/company/contact/default.aspx.

ITAR Technical Support

For technical support on RH and RT FPGAs that are regulated by International Traffic in Arms Regulations (ITAR), contact us via soc_tech_itar@microsemi.com. Alternatively, within My Cases, select **Yes** in the ITAR drop-down list. For a complete list of ITAR-regulated Microsemi FPGAs, visit the ITAR web page.

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