



**Verilog-AMS  
Language Reference Manual**

**Analog & Mixed-Signal Extensions  
to  
Verilog HDL**

**Version 2.2**

**November 2004**

**Accellera**

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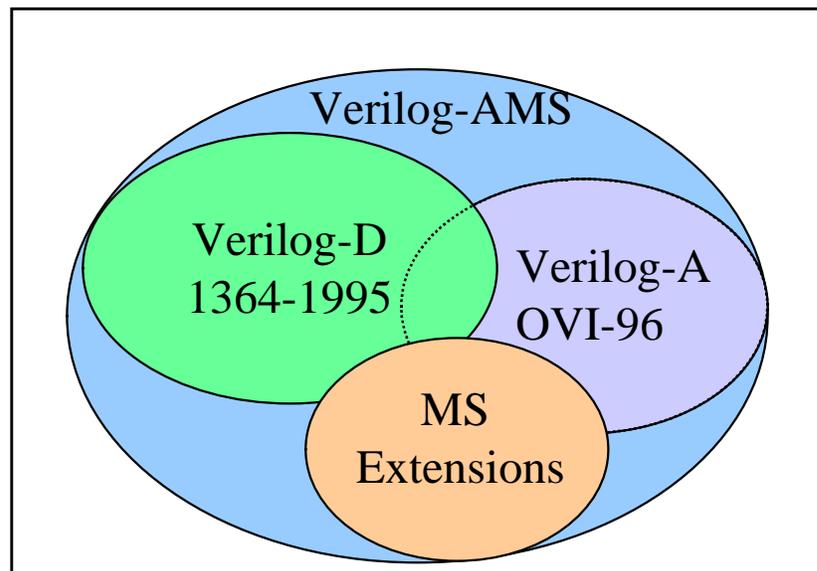
# Section 1

## Verilog-AMS introduction

### 1.1 Overview

This Verilog-AMS Hardware Description Language (HDL) language reference manual defines a behavioral language for analog and mixed-signal systems. Verilog-AMS HDL is derived from *IEEE 1364-1995 Verilog HDL*. This document is intended to cover the definition and semantics of Verilog-AMS HDL as proposed by Accellera.

Figure 1-1 shows the components and architecture of Verilog-AMS HDL, which consists of the complete *IEEE 1364-1995 Verilog HDL* specification (noted as Verilog-D in the figure), an analog equivalent for describing analog systems (noted as Verilog-A), and extensions to both for specifying the full Verilog-AMS HDL (noted as MS Extensions).



**Figure 1-1 Verilog-AMS architecture**

Verilog-AMS HDL lets designers of analog and mixed-signal systems and integrated circuits create and use modules which encapsulate high-level behavioral descriptions as well as structural descriptions of systems and components. The behavior of each module can be described mathematically in terms of its ports and external parameters applied to the module. The structure of each component can be described in terms of interconnected sub-components. These descriptions can be used in many disciplines such as electrical, mechanical, fluid dynamics, and thermodynamics.

For continuous systems, Verilog-AMS HDL is defined to be applicable to both electrical and non-electrical systems description. It supports *conservative* and *signal-flow* descriptions by using the concepts of *nets*, *nodes*, *branches*, and *ports* as terminology for these descriptions. The solution of analog behaviors which obey the laws of conservation fall within the generalized form of Kirchhoff's Potential and Flow Laws (KPL and KFL). Both of these are defined in terms of the quantities (e.g., voltage and current) associated with the analog behaviors.

Verilog-AMS HDL can also be used to describe discrete (digital) systems (per *IEEE 1364-1995 Verilog HDL*) and mixed-signal systems using both discrete and continuous descriptions as defined in this LRM.

## 1.2 Mixed-signal language features

Verilog-AMS HDL extends the features of the digital modeling language (*IEEE 1364-1995 Verilog HDL*) to provide a single unified language with both analog and digital semantics with backward compatibility. Below is a list of salient features of the resulting language:

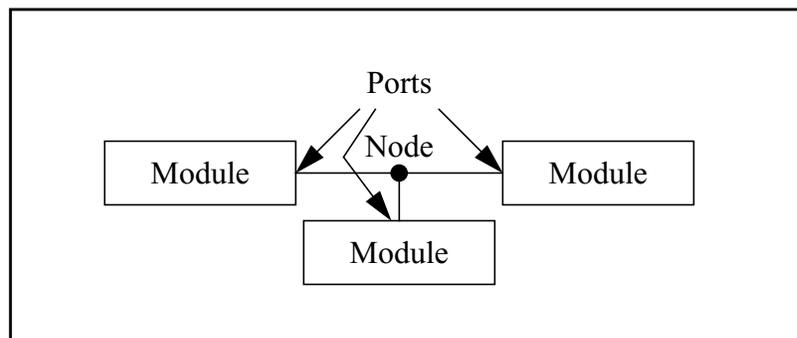
- signals of both analog and digital types can be declared in the same module
- `initial`, `always`, and `analog` procedural blocks can appear in the same module
- both analog and digital signal values can be accessed (read operations) from any context (analog or digital) in the same module
- digital signal values can be set (write operations) from any context outside of an `analog` procedural block
- analog potentials and flows can only receive contributions (write operations) from inside an `analog` procedural block
- the semantics of the `initial` and `always` blocks remain the same as in *IEEE 1364-2001 Verilog HDL*; the semantics for the `analog` block are described in this manual
- the `discipline` declaration is extended to digital signals
- a new construct, `connect` statement, is added to facilitate auto-insertion of user-defined connection modules between the analog and digital domains
- when hierarchical connections are of mixed type (i.e., analog signal connected to digital port or digital signal connected to analog port), user-defined connection modules are automatically inserted to perform signal value conversion

## 1.3 Systems

A *system* is considered to be a collection of interconnected *components* which are acted upon by a stimulus and produce a response. The components themselves can also be systems, in which case a *hierarchical system* is defined. If a component does not have any subcomponents, it is considered to be a *primitive component*. Each primitive component connects to zero or more nets. Each net connects to a signal which can traverse multiple levels of the hierarchy. The behavior of each component is defined in terms of values at each net.

A *signal* is a hierarchical collection of nets which, because of port connections, are contiguous. If all the nets which make up a signal are in the discrete domain, the signal is a *digital signal*. If, on the other hand, all the nets which make up a signal are in the continuous domain, the signal is an *analog signal*. A signal which consists of nets from both domains is called a *mixed signal*.

Similarly, a port whose connections are both analog is an *analog port*, a port whose connections are both digital is a *digital port*, and a port whose connections are both analog and digital is a *mixed port*. The components connect to nodes through ports and nets to build a hierarchy, as shown in Figure 1-2.



**Figure 1-2 Components connect to nodes through ports**

If a signal is analog or mixed, it is associated with a node (see Section 3.4), while a purely digital signal is not associated with a node. Regardless of the number of analog nets in an analog or mixed signal or how the analog nets in a mixed signal are interspersed with digital nets, the analog portion of an analog or mixed signal is represented by only a single node. This guarantees a mixed or analog signal has only one value which represents its potential with respect to the global reference voltage (*ground*).

In order to simulate systems, it is necessary to have a complete description of the system and all of its components. Descriptions of systems are usually given structurally. That is, the description of a system contains instances of components and how they are interconnected. Descriptions of components are given using behavior and or structure. A behavior is a mathematical description which relates the signals at the ports of the components.

### 1.3.1 Conservative systems

An important characteristic of conservative systems is there are two values associated with every node, the *potential* (also known as the *across value* or *voltage* in electrical systems) and the *flow* (the *through value* or *current* in electrical systems). The potential of the node is shared with all continuous ports and nets connected to the node so all continuous ports and nets see the same potential. The flow is shared so flow from all continuous ports and nets at a node shall sum to zero (0). In this way, the node acts as an infinitesimal point of interconnection in which the potential is the same everywhere on the node and on which no flow can accumulate. Thus, the node embodies Kirchhoff's Potential and Flow Laws (KPL and KFL). When a component connects to a node through a conservative port or net, it can either affect, or be affected by, either the potential at the node, and/or the flow onto the node through the port or net.

With conservative systems it is also useful to define the concept of a branch. A branch is a path of flow between two nodes through a component. Every branch has an associated potential (the potential difference between the two nodes) and flow.

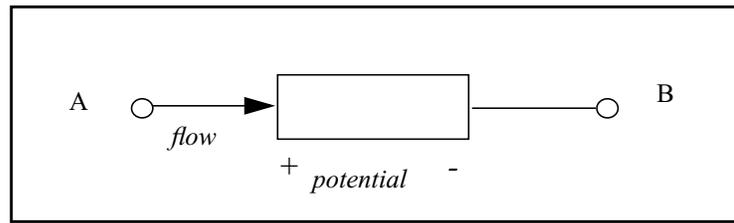
A behavioral description of a conservative component is constructed as a collection of interconnected branches. The constitutive equations of the component are formulated as to relate the branch potentials and flows. In the probe/source approach (see Section 5.1.2), the branch potential or flow is specified as a function of branch potentials and flows. If the branch potential and flow are left unspecified, not on the left-hand side of a contribution statement, then the branch acts as a probe. In this case, if the branch flow is used in an expression, the branch potential is forced to zero (0). Otherwise the branch flow is assumed to be zero (0) and the branch potential is available for use in an expression. Using both the potential and flow of a 'probe' branch in an expression is not allowed. Nor is specifying both the branch potential and flow at the same time. (While these last two conditions are not really necessary, they do eliminate conditions which are useless and confusing.)

#### 1.3.1.1 Reference nodes

The potential of a single node is given with respect to a reference node. The potential of the reference node, which is called **ground** in electrical systems, is always zero (0). Any net of continuous discipline can be declared to be **ground**. In this case, the node associated with the net shall be the global reference node in the circuit. This is compatible with all analog disciplines and can be used to bind a port of an instantiated module to the reference node.

#### 1.3.1.2 Reference directions

The reference directions for a generic branch are shown in Figure 1-3.



**Figure 1-3 Reference directions**

The *reference direction* for a potential is indicated by the plus and minus symbols near each port. Given the chosen reference direction, the branch potential is positive whenever the potential of the port marked with a plus sign (A) is larger than the potential of the port marked with a minus sign (B). Similarly, the flow is positive whenever it moves in the direction of the arrow (in this case from + to -).

Verilog-AMS HDL uses associated reference directions. A positive flow enters a branch through the port marked with the plus sign and exits the branch through the port marked with the minus sign.

### 1.3.2 Kirchhoff's Laws

In formulating continuous system equations, Verilog-AMS HDL uses two sets of relationships. The first are the constitutive relationships which describe the behavior of each component. Constitutive relationships can be kept inside the simulator as built-in primitives or they can be provided by Verilog-AMS HDL module definitions.

The second set of relationships, interconnection relationships, describe the structure of the network. Interconnection relationships, which contain information on how the components are connected to each other, are only a function of the system topology. They are independent of the nature of the components.

A Verilog-AMS HDL simulator uses Kirchhoff's Laws to define the relationships between the nodes and the branches. Kirchhoff's Laws are typically associated with electrical circuits that relate voltages and currents. However, by generalizing the concepts of voltages and currents to potentials and flows, Kirchhoff's Laws can be used to formulate interconnection relationships for any type of system.

Kirchhoff's Laws provide the following properties relating the quantities present on nodes and branches, as shown in Figure 1-4.

- Kirchhoff's Flow Law (KFL)  
The algebraic sum of all flows out of a node at any instant is zero (0).
- Kirchhoff's Potential Law (KPL)  
The algebraic sum of all the branch potentials around a loop at any instant is zero (0).

These laws imply a node is infinitely small; so there is negligible difference in potential between any two points on the node and a negligible accumulation of flow.

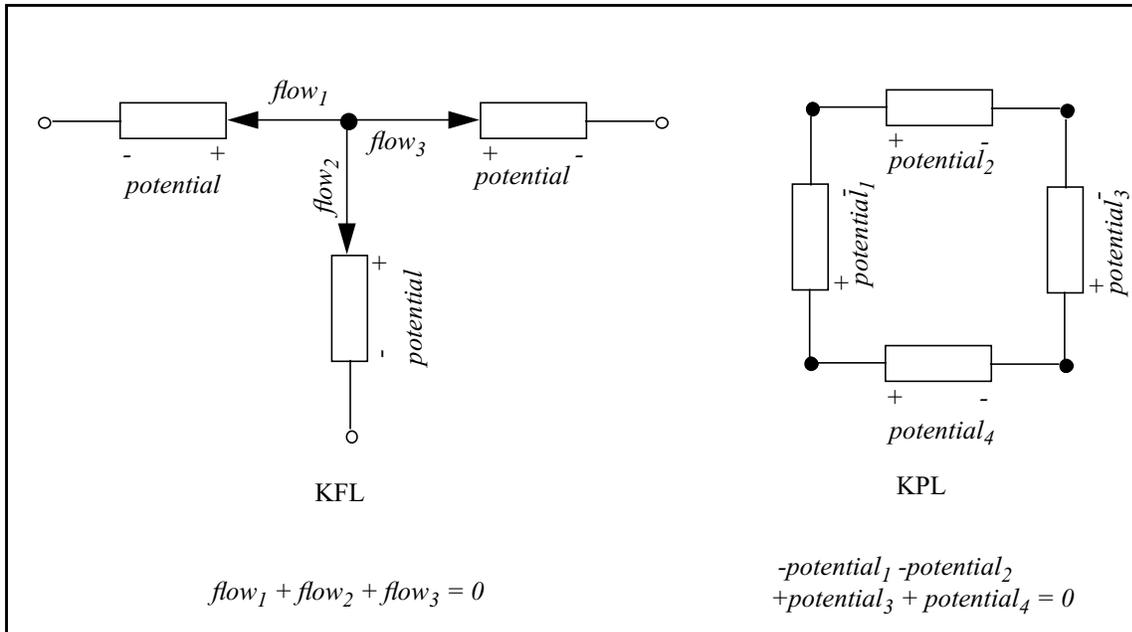


Figure 1-4 Kirchhoff's Flow Law (KFL) and Potential Law (KPL)

### 1.3.3 Natures, disciplines, and nets

Verilog-AMS HDL allows definition of nets based on disciplines. The disciplines associate potential and flow natures for conservative systems or only potential nature for signal-flow systems. The natures are a collection of attributes, including user-defined attributes, which describes the units (meter, gram, newton, etc.), absolute tolerance for convergence, and the names of potential and flow access functions.

The disciplines and natures can be shared by many nets. The compatibility rules help enforce the legal operations between nets of different disciplines.

### 1.3.4 Signal-flow systems

A discipline may specify two nature bindings, `potential` and `flow`, or it may specify only a single binding, `potential`. Disciplines with two natures are known as *conservative disciplines* because nodes which are bound to them exhibit Kirchhoff's Flow Law, and thus, conserve charge (in the electrical case). A discipline with only a potential nature is known as a *signal flow discipline*.

As a result of port connections of analog nets, a single node may be bound to a number of nets of different disciplines. If a node is bound only to disciplines which have potential

nature only, current contributions to that node are not legal. Flow for such a node is not defined.

Signal flow models may be written so potentials of module outputs are purely functions of potentials at the inputs without taking flow into account.

The following example is a level shifting voltage follower:

```

module shiftPlus5(in, out);
input in;
output out;
voltage in, out; //voltage is a signal flow
                 //discipline compatible with
                 //electrical, but having a
                 //potential nature only

analog begin
    V(out) <+ 5.0 + V(in);
end
endmodule

```

If a number of such modules were cascaded in series, it would not be necessary to conserve charge (i.e., sum the flows) at any intervening node.

If, on the other hand, the output of this device were bound to a node of a conservative discipline (e.g., `electrical`), then the output of the device would appear to be a controlled voltage source to ground at that node. In that case, the flow (i.e., current) through the source would contribute to charge conservation at the node. If the input of this device were bound to a node of a conservative discipline then the input would act as a voltage probe to ground. Thus, when a net of signal flow discipline with potential nature only is bound to a conservative node, contributions made to that net behave as voltage sources to ground.

Nets of signal flow disciplines in modules may only be bound to `input` or `output` ports of the module, not to `inout` ports. Potential contributions may not be made to `inputs`.

### 1.3.5 Mixed conservative/signal flow systems

When practicing the top-down design style, it is extremely useful to mix conservative and signal-flow components in the same system. Users typically use signal-flow models early in the design cycle when the system is described in abstract terms, and gradually convert component models to conservative form as the design progresses. Thus, it is important to be able to initially describe a component using a signal-flow model, and later convert it to a conservative model, with minimum changes. It is also important to allow conservative and signal-flow components to be arbitrarily mixed in the same system.

The approach taken is to write component descriptions using conservative semantics, except port and net declarations only require types for those values which are actually used in the description. Thus, signal-flow ports only require the type of potential to be

specified, whereas conservative ports require types for both values (the potential and flow).

*Examples:*

For example, consider a differential voltage amplifier, a differential current amplifier, and a resistor. The amplifiers are written using signal-flow ports and the resistor uses conservative ports.

```

module voltage_amplifier (out, in) ;
input in ;
output out ;
voltage out ,    // Discipline voltage defined elsewhere
           in ;  // with access function V()
parameter real GAIN_V = 10.0 ;

analog
    V(out) <+ GAIN_V * V(in) ;

endmodule

```

In this case, only the voltage on the ports are declared because only voltage is used in the body of the model.

```

module current_amplifier (out, in) ;
input in ;
output out ;
current out ,    // Discipline current defined elsewhere
           in ;  // with access function I()
parameter real GAIN_I = 10.0 ;

analog
    I(out) <+ GAIN_I * I(in) ;

endmodule

```

Here, only current is used in the body of the model, so only current need be declared at the ports.

```

module resistor (a, b) ;
inout a, b ;
electrical a, b ;          // access functions are V() and I()
parameter real R = 1.0 ;

analog
    V(a,b) <+ R * I(a,b) ;

endmodule

```

The description of the resistor relates both the voltage and current on the ports. Both are defined in the conservative discipline `electrical`.

In summary, only those signals types declared on the ports are accessible in the body of the model. Conversely, only those signals types used in the body need be declared.

This approach provides all of the power of the conservative formulation for both signal-flow and conservative ports, without forcing types to be declared for unused signals on signal-flow nets and ports. In this way, the first benefit of the traditional signal-flow formulation is provided without the restrictions.

The second benefit, that of a smaller, more efficient set of equations to solve, is provided in a manner which is hidden from the user. The simulator begins by treating all ports as being conservative, which allows the connection of signal-flow and conservative ports. This results in additional unnecessary equations for those nodes which only have signal-flow ports. This situation can be recognized by the simulator and those equations eliminated.

Thus, this approach to allowing mixed conservative/signal-flow descriptions provides the following benefits:

- Conservative components and signal-flow components can be freely mixed. In addition, signal-flow components can be converted to conservative components, and vice versa, by modifying only the component behavioral description.
- Many of the capabilities of conservative ports, such as the ability to access flow and the ability to access floating potentials, are available with signal-flow ports.
- Natures only have to be given for potentials and flows if they are accessed in a behavioral description.
- If nets and ports are used only in a structural description (only in instance statements), then no natures need be specified.

## 1.4 Conventions used in this document

This document is organized into sections, each of which focuses on some specific area of the language. There are subsections within each section to discuss individual constructs and concepts. The discussion begins with an introduction and an optional rationale for the construct or the concept, followed by syntax and semantic description, followed by some examples and notes.

The formal syntax of Verilog-AMS HDL is described using Backus-Naur Form (BNF). The following conventions are used:

1. Lower case words, some containing embedded underscores, are used to denote syntactic categories. For example:

```
module_declaration
```

2. Bold face words are used to denote reserved keywords, operators and punctuation marks as required part of the syntax. For example:

```
module = ;
```

3. A vertical bar separates alternative items. For example:

```
attribute ::=
    abstol | units | identifier
```

4. Square brackets enclose optional items. For example:

```
input_declaration ::=
    input [range] list_of_ports ;
```

5. Braces enclose a repeated item unless the braces appear in bold face, in which case it stands for itself. The item can appear zero or more times; the repetitions occur from left to right as with an equivalent left-recursive rule. Thus, the following two rules are equivalent:

```
list_of_port_def ::=
    port_def { , port_def }

list_of_port_def ::=
    port_def
    | list_of_port_def , port_def
```

6. If the name of any category starts with an *italicized* part, it is equivalent to the category name without the italicized part. The italicized part is intended to convey some semantic information. For example, *msb\_constant\_expression* and *lsb\_constant\_expression* are equivalent to *constant\_expression*, and *node\_identifier* is an *identifier* which is used to identify (declare or reference) a *node*.

The main text uses italicized font when a *term* is being defined, and constant-width font for examples, file names, and while referring to constants.

## 1.5 Contents

This document contains the following sections and annexes:

1. Verilog-AMS introduction  
This section gives the overview of analog modeling, defines basic concepts, and describes Kirchhoff's Potential and Flow Laws.
2. Lexical conventions  
This section defines the lexical tokens used in Verilog-AMS HDL.
3. Data types  
This section describes the data types: integer, real, parameter, nature, discipline, and net, used in Verilog-AMS HDL.
4. Expressions  
This section describes expressions, mathematical functions, and time domain functions used in Verilog-AMS HDL.
5. Signals  
This section describes signals and branches, access to signals and branches, and various transformation functions.
6. Analog behavior  
This section describes the basic analog block and procedural language constructs available in Verilog-AMS HDL for behavioral modeling.
7. Hierarchical structures  
This section describes how to build hierarchical descriptions using Verilog-AMS HDL.
8. Mixed signal  
This section describes the mixed-signal aspects of the Verilog-AMS HDL language.
9. Scheduling semantics  
This section describes the basic simulation cycle as applicable to Verilog-AMS HDL.
10. System tasks and functions  
This section describes the system tasks and functions in Verilog-AMS HDL.

11. Compiler directives  
This section describes the compiler directives in Verilog-AMS HDL.
12. Using VPI routines  
This section describes how the VPI routines are used.
13. VPI routine definitions  
This section defines each of the VPI routines in alphabetical order.
  - A. Syntax  
This annex describes formal syntax for all Verilog-AMS HDL constructs in Backus-Naur Form (BNF).
  - B. Keywords  
This annex lists all the words which are recognized in Verilog-AMS HDL as keywords.
  - C. Analog language subset  
This annex describes the analog subset of Verilog-AMS HDL.
  - D. Standard definitions  
This annex provides the definitions of several natures, disciplines, and constants which are useful for writing models in Verilog-AMS HDL.
  - E. SPICE compatibility  
This annex describes the SPICE compatibility with Verilog-AMS HDL.
  - F. Discipline resolution methods  
This annex provides the semantics for two methods of resolving the discipline of undeclared interconnect.
  - G. Open issues  
This annex lists unresolved issues.
  - H. Glossary  
This annex describes various terms used in this document.

# Section 2

## Lexical conventions

This section describes the lexical tokens used in Verilog-AMS HDL source text and their conventions. This section is based on Section 2, Lexical conventions, of *IEEE 1364-1995 Verilog HDL*. The changes specific to Verilog-AMS HDL can be found in Section 2.5.3, Section 2.7.2, and Section 2.8.1.

### 2.1 Lexical tokens

A Verilog-AMS HDL source text file is a stream of lexical tokens. A *lexical token* consists of one or more characters. The layout of tokens in a source file is free format—spaces and newlines are not syntactically significant other than being token separators, except escaped identifiers (see Section 2.7.1).

The types of lexical tokens in the language are as follows:

- white space
- comment
- operator
- number
- string
- identifier
- keyword

### 2.2 White space

White space token type contains the characters for spaces, tabs, newlines, and formfeeds. These characters are ignored except when they serve to separate other lexical tokens.

## 2.3 Comments

Verilog-AMS HDL has two forms to introduce comments, as shown in Syntax 2-1. A *one-line comment* starts with the two characters `//` and ends with a newline. *Block comments* start with `/*` and ends with `*/`. Block comments can not be nested. The one-line comment token `//` does not have any special meaning in a block comment.

```
comment ::=
    short_comment
    | long_comment
short_comment ::=
    // { any_ASCII_characters_except_end_of_line } \n
long_comment ::=
    /* { any_ASCII_characters } */
comment_text ::=
    { Any_ASCII_character }
```

Syntax 2-1—Syntax for comments

## 2.4 Operators

Operators are single, double, or triple character sequences and are used in expressions. Section 4 discusses the use of operators in expressions.

*Unary operators* appear to the left of their operand. *Binary operators* appear between their operands. A *conditional operator* has two operator characters which separate three operands.

## 2.5 Numbers

*Constant numbers* can be specified as integer constants or real constants. The syntax for constants is shown in Syntax 2-2.

```

number ::=
    decimal_number
    | digital_octal_number
    | digital_binary_number
    | digital_hex_number
    | real_number

decimal_number ::=
    [ sign ] unsigned_num

sign ::=
    + | -

unsigned_num ::=
    decimal_digit { _ | decimal_digit }

decimal_digit ::=
    0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9

digital_number ::=
    number

real_number ::=
    [ sign ] unsigned_num . unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] e [ sign ] unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] E [ sign ] unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] scale_factor

scale_factor ::=
    T | G | M | K | k | m | u | n | p | f | a

```

Syntax 2-2—Syntax for integer and real constants

### 2.5.1 Integer constants

*Integer constants* are specified in decimal format as a sequence of digits 0 through 9, optionally starting with a plus or minus unary operator. The underscore character (`_`) is legal anywhere in a decimal number except as the first character. The underscore character is ignored. This feature can be used to break up long numbers for readability purposes.

*Examples:*

```

27_195_000 // same as 27195000
-659

```

### 2.5.2 Real constants

The *real constant numbers* are represented as described by *IEEE STD-754-1985*, an IEEE standard for double precision floating point numbers (64-bits).

Real numbers can be specified in either decimal notation (e.g., `14.72`) or in scientific notation (e.g., `39e8`, which indicates 39 multiplied by 10 to the 8<sup>th</sup> power). Real numbers

expressed with a decimal point shall have at least one digit on each side of the decimal point. The underscore character is legal anywhere in a real constant except as the first character of the constant or the first character after the decimal point. The underscore character is ignored.

*Examples:*

```
1.2
0.1
2394.26331
1.2E12 // the exponent symbol can be e or E
1.30e-2
0.1e-0
23E10
29E-2
236.123_763_e-12 // underscores are ignored
```

The following are invalid forms of real numbers because they do not have at least one digit on each side of the decimal point:

```
.12
9.
4.E3
.2e-7
```

### 2.5.3 Scale factors for real constants

Floating-point numbers can be specified using the following letter symbols for the scale factors indicated. Scale factors and scientific notation are not allowed to be used together in describing a real number.

Largest	————▶	Smallest
$T = 10^{12}$		$m = 10^{-3}$
$G = 10^9$		$u = 10^{-6}$
$M = 10^6$		$n = 10^{-9}$
$K = 10^3; k = 10^3$		$p = 10^{-12}$
		$f = 10^{-15}$
		$a = 10^{-18}$

No space is permitted between the number and the symbol. Scale factors are not allowed to be used in defining digital delays (e.g., #5u).

This form of floating-point number specification is provided in Verilog-AMS HDL in addition to the two methods for writing floating-point numbers described in Section 2.5.2.

*Example:*

Short form	Expanded form
1.3u	1.3e-6 or 0.0000013
5.46K	5460

## 2.6 Strings

A *string* is a sequence of characters enclosed by double quotes (") and contained on a single line. Strings used as operands in expressions and assignments shall be treated as unsigned integer constants represented by a sequence of 8-bit ASCII values, with one 8-bit ASCII value representing one character. String parameters are treated differently and are described in Section 3.2.6.

### 2.6.1 String variable declaration

String variables are variables of type `reg` (see *IEEE 1364-1995 Verilog HDL*) with the width equal to the number of characters in the string multiplied by eight (8).

*Example:*

To store the twelve-character string "Hello world!" requires a `reg`  $8 * 12$  or 96 bits wide

```
reg [8*12:1] stringvar;
initial begin
    stringvar = "Hello world!";
end
```

### 2.6.2 String manipulation

String variables can be manipulated using the Verilog HDL operators. The value being manipulated by the operator is the sequence of 8-bit ASCII values.

Example:

```

module string_test;
reg [8*14:1] stringvar;
initial begin
    stringvar = "Hello world";
    $display("%s is stored as %h", stringvar,stringvar);
    stringvar = {stringvar,"!!!"};
    $display("%s is stored as %h", stringvar,stringvar);
end
endmodule

```

The output is:

```

Hello world is stored as 00000048656c6c6f20776f726c64
Hello world!!! is stored as 48656c6c6f20776f726c64212121

```

**Note:** When a variable is larger than required to hold a value being assigned, the contents on the left are padded with zeros (0) after the assignment. This is consistent with the padding which occurs during assignment of nonstring values. If a string is larger than the destination string variable, the string is truncated to the left and the leftmost characters are lost.

### 2.6.3 Special characters in strings

Certain characters can only be used in strings when preceded by an introductory character called an *escape character*. Table 2-1 lists these characters in the right-hand column, with the escape sequence that represents the character in the left-hand column.

**Table 2-1—Specifying special characters in string**

Escape string	Character produced by escape string
\n	New line character
\t	Tab character
\\	\ character
\"	" character
\ddd	A character specified in 1–3 octal digits (0 ≤ d ≤ 7)

## 2.7 Identifiers, keywords, and system names

An *identifier* is used to give an object a unique name so it can be referenced. An identifier can be any sequence of letters, digits, dollar signs (\$), and the underscore characters (\_).

The first character of an identifier can not be a digit or \$; it can be a letter or an underscore. Identifiers are case sensitive.

*Examples:*

```
shiftreg_a
busa_index
error_condition
merge_ab
_bus3
n$657
```

### 2.7.1 Escaped identifiers

*Escaped identifiers* start with the backslash character (\) and end with white space (space, tab, newline, or formfeed). They provide a means of including any of the printable ASCII characters in an identifier (the decimal values 33 through 126 or 21 through 7E in hexadecimal).

Neither the leading back-slash character nor the terminating white space is considered to be part of the identifier. Therefore, an escaped identifier `\cpu3` is treated the same as a non-escaped identifier `cpu3`.

*Examples:*

```
\busa+index
\clock
\***error-condition***
\net1/\net2
\{a,b}
\a*(b+c)
```

### 2.7.2 Keywords

*Keywords* are predefined non-escaped identifiers which are used to define the language constructs. Preceding a keyword with an escape character (\) causes it to be interpreted as an escaped identifier.

All keywords are defined in lowercase only. Annex B lists all defined Verilog-AMS HDL keywords (including those from *IEEE 1364-1995 Verilog HDL*).

### 2.7.3 System tasks and functions

The `$` character introduces a language construct which enables development of user-defined tasks and functions. A name following the `$` is interpreted as a *system task* or a *system function*.

The syntax for a system task or function is given in Syntax 2-3.

```

system_task_or_function ::=
    $system_task_identifier [ ( list_of_arguments ) ] ;
    | $system_function_identifier [ ( list_of_arguments ) ] ;

list_of_arguments ::=
    argument { , [ argument ] }

argument ::=
    expression

```

Syntax 2-3—Syntax for system tasks and functions

Section 10 lists the standard system tasks and functions for Verilog-AMS HDL.

Any valid identifier, including keywords already in use in contexts other than this construct can be used as a system task or function name.

*Examples:*

```

$display ("display a message");
$finish;

```

## 2.7.4 Compiler directives

The ``` character (the ASCII value 60, called open quote or accent grave) introduces a language construct used to implement compiler directives. The compiler behavior dictated by a compiler directive takes effect as soon as the compiler reads the directive. The directive remains in effect for the rest of the compilation unless a different compiler directive specifies otherwise. A compiler directive in one description file can therefore control compilation behavior in multiple description files.

Section 11 lists the Verilog-AMS HDL compiler directives and their syntax.

Any valid identifier, including keywords already in use in contexts other than this construct can be used as a compiler directive name.

*Example:*

```

`define wordsize 8

```

## 2.8 Attributes

Attributes are provided by *IEEE 1364-2001 Verilog HDL* as a mechanism for specifying properties about objects, statements and groups of statements in the HDL source that may be used by various tools, including simulators, to control the operation or behavior of the tool. *IEEE 1364-2001 Verilog HDL* specifies only the syntactic mechanism that shall be used for specifying attributes, without standardizing on any particular attributes. The syntax is found in Syntax 2-4.

```
attribute_instance ::=  
    (* attr_spec {, attr_spec } *)  
  
attr_spec ::=  
    attr_name = constant_expression  
    | attr_name  
  
attr_name ::=  
    identifier
```

Syntax 2-4—Syntax for attributes

An `attribute_instance` can appear in the Verilog-AMS description as a prefix attached to certain module item declarations.

If a value is not specifically assigned to the attribute, then its value shall be 1. If the same attribute name is defined more than once for the same language element, the last attribute value shall be used and a tool can give a warning that a duplicate attribute specification has occurred.

### 2.8.1 Standard attributes

The Verilog-AMS HDL standardizes two attributes, `description` and `units`. The `description` attribute uses the identifier `desc` and the `units` attribute uses the identifier `units`. Both attributes must be assigned a value, which must be a string. When attached to certain declarations, these attributes are used for generating help messages for the module, as described in Section 3.1.1, Section 3.2.3, Section 3.4.3.1, and Section 7.1.



## Section 3

# Data types

Verilog-AMS HDL supports `integer`, `real`, and `parameter` data types as found in *IEEE 1364-2001 Verilog HDL*. It also modifies the `parameter` data types and introduces *array of real* as an extension of the `real` data type. Plus, it extends the `net` data types to support a new type called `wreal` to model real value nets.

Verilog-AMS HDL introduces a new data type, called *net\_discipline*, for representing analog nets and declaring *disciplines* of all `nets` and `regs`. The *disciplines* define the domain and the natures of `potential` and `flow` and their associated attributes for *continuous* domains. A new data type called *genvar* is also introduced for use with behavioral loops.

### 3.1 Integer and real data types

The syntax for declaring `integer` and `real` is shown in Syntax 3-1.

```
integer_declaration ::=
    integer list_of_identifiers ;

real_declaration ::=
    real list_of_identifiers ;

list_of_identifiers ::=
    var_name { , var_name }

var_name ::=
    variable_identifier
    | array_identifier array_range

array_range ::=
    [ upper_limit_constant_expression : lower_limit_constant_expression ]
```

Syntax 3-1—Syntax for integer and real declarations

An *integer* declaration declares one or more variables of type `integer`. These variables can hold values ranging from  $-2^{31}$  to  $2^{31}-1$ . Arrays of integers can be declared using a range which defines the upper and lower indices of the array. Both indices shall be constant expressions and shall evaluate to a positive integer, a negative integer, or zero (0).

Arithmetic operations performed on integer variables produce 2's complement results.

A *real* declaration declares one or more variables of type real. The real variables are stored as 64-bit quantities, as described by *IEEE STD-754-1985*, an IEEE standard for double precision floating point numbers.

Arrays of real can be declared using a range which defines the upper and lower indices of the array. Both indices shall be constant expressions and shall evaluate to a positive integer, a negative integer, or zero (0).

Integers are initialized at the start of a simulation depending on how they are used. Integer variables whose values are assigned in an analog context default to an initial value of zero (0). Integer variables whose values are assigned in a digital context default to an initial value of x. Real variables are initialized to zero (0) at the start of a simulation.

*Examples:*

```
integer a[1:64]; // an array of 64 integer values
real float ; // a variable to store real value
real gain_factor[1:30] ;// array of 30 gain multipliers
// with floating point values
```

### 3.1.1 Output variables

The standard attributes for descriptions and units, described in Section 2.8.1, have a special meaning for variables declared at module scope. Module scope variables with a description or units attribute, or both, shall be known as output variables, and Verilog-AMS simulators shall provide access to their values. SPICE-like simulators print the names, values, units, and descriptions of output variables for SPICE primitives along with voltages and currents when displaying operating-point information, and these variables are available for plotting as a function of time (or the swept variable of a dc sweep).

*Example:*

A module for a MOS transistor with the following declaration at module scope provides the output variable `cgs`.

```
(* desc="gate-source capacitance", units="F" *)
real cgs;
```

An operating-point display from the simulator might include the following information:

```
cgs = 4.21e-15 F gate-source capacitance
```

See also the examples in Section 4.4.7.

Units and descriptions specified for block-level variables shall be ignored by the simulator, but can be used for documentation purposes.

## 3.2 Parameters

The syntax for parameter declarations is shown in Syntax 3-2.

The list of parameter assignments shall be a comma-separated list of assignments, where the right hand side of the assignment shall be a constant expression, that is, an expression containing only constant numbers and previously defined parameters.

For parameters defined as arrays, the initializer shall be a `constant_param_arrayinit` expression which is a list of constant expressions containing only constant numbers and previously defined parameters within { and } delimiters.

Parameters represent constants, hence it is illegal to modify their value at runtime. However, parameters can be modified at compilation time to have values which are different from those specified in the declaration assignment. This allows customization of module instances. A parameter can be modified with the `defparam` statement or in the `module_instance` statement. It is not legal to use hierarchical name referencing (from within the analog block) to access external analog variables or parameters.

```

parameter_declaration ::=
    parameter [opt_type] list_of_param_assignments ;

local_parameter_declaration ::=
    localparam [opt_type] list_of_param_assignments ;

opt_type ::=
    real
    | integer

list_of_param_assignments ::=
    declarator_init {, declarator_init}

declarator_init ::=
    parameter_identifier = constant_expression { opt_value_range }
    | parameter_array_identifier range = constant_param_arrayinit { opt_value_range }

opt_value_range ::=
    from value_range_specifier
    | exclude value_range_specifier
    | exclude value_constant_expression

value_range_specifier ::=
    start_paren expression1 : expression2 end_paren

start_paren ::=
    [ | (

end_paren ::=
    ] | )

expression1 ::=
    constant_expression | -inf

expression2 ::=
    constant_expression | inf

constant_param_arrayinit ::=
    { param_arrayinit_element_list }

param_arrayinit_element_list ::=
    param_arrayinit_element {, param_arrayinit_element }

param_arrayinit_element ::=
    constant_expression
    | { replicator_constant_expression {constant_expression} }

string_parameter_declaration ::=
    parameter string parameter_identifier = string_constant_expression [ string_list ] ;

local_string_parameter_declaration ::=
    localparam string parameter_identifier = string_constant_expression [ string_list ] ;

string_list ::=
    [ from { string {, string} } ][ exclude { string {, string} } ]

aliasparam_declaration ::=
    aliasparam alias_identifier = parameter_identifier ;

```

Syntax 3-2—Syntax for parameter declaration

By nature, analog behavioral specifications are characterized more extensively in terms of parameters than their digital counterparts. There are four fundamental extensions to the parameter declarations defined in *IEEE 1364-1995 Verilog HDL*:

- An optional type for the parameter can be specified in Verilog-AMS HDL. In *IEEE 1364-1995 Verilog HDL*, the type of a parameter defaults to the type of the default expression.
- A range of permissible values can be defined for each parameter. In *IEEE 1364-1995 Verilog HDL*, this check had to be done in user's model or was left as an implementation specific detail.
- Parameter arrays of basic integer and real data types can be specified.
- String parameters may be declared.

### 3.2.1 Type specification

The parameter declaration can contain an optional *type* specification. In this sense, the **parameter** keyword acts more as a type qualifier than a type specifier. A default value for the parameter shall be specified.

*Examples:*

The following examples illustrate this concept:

```
parameter real slew_rate = 1e-3 ;
parameter integer size = 16 ;
```

If the *type* of a parameter is not specified, it is derived from the type of the value of the constant expression as in *IEEE 1364-1995 Verilog HDL*. Note that the *type* of a string parameter (see Section 3.2.6) is mandatory.

If the type of the parameter is specified as **integer** or **real**, and the value assigned to the parameter conflicts with the type of the parameter, the value is coerced to the type of the parameter (see Section 4.1.1.1). No coercion shall be applied for strings; it shall be an error to assign a numeric value to a parameter declared as **string** or to assign a string value to an **integer** or **real** parameter, whether that parameter was declared as **integer** or **real** or had its type derived from the type of the value of the constant expression.

*Example:*

```
parameter real size = 10 ;
```

Here, `size` is coerced to 10.0.

### 3.2.2 Value range specification

A parameter declaration can contain optional specifications of the permissible range of the values of a parameter. More than one range can be specified for inclusion or exclusion of values as legal values for the parameter.

The use of brackets, [ and ], indicate inclusion of the end points in the valid range. The use of parenthesis, ( and ), indicate exclusion of the end points from the valid range. It is possible to include one end point and not the other using [ ) and ( ]. The first expression in the range shall be numerically smaller than the second expression in the range.

*Examples:*

```
parameter real neg_rail = -15 from [-50:0) ;
parameter integer pos_rail = 15 from (0:50) ;
parameter real gain = 1 from [1:1000] ;
```

Here, the default value for `neg_rail` is -15 and it is only allowed to acquire values within the range of  $-50 \leq \text{neg\_rail} < 0$ . Similarly, the default value for parameter `pos_rail` is 15 and it is only allowed to acquire values within the range of  $0 < \text{pos\_rail} < 50$ . And, the default value for `gain` is 1 and it is allowed to acquire values within the range of  $1 \leq \text{gain} \leq 1000$ .

The keyword `inf` can be used to indicate infinity. If preceded by a negative sign, it indicates negative infinity.

*Example:*

```
parameter real val3=0 from [0:inf) exclude (10:20) exclude (30:40];
```

A single value can be excluded from the possible valid values for a parameter.

*Example:*

```
parameter real res = 1.0 exclude 0 ;
```

Here, the value of a parameter is checked against the specified range. Range checking applies to the value of the parameter for the instance and not against the default values specified in the device. It shall be an error only if the value of the parameter is out of range during simulation.

Valid values of string parameters are indicated differently. The `from` keyword may be used with a list of valid string values, or the `exclude` keyword may be used with a list of invalid string values. In either case, the list is enclosed in braces, { and }, and the items are separated by commas.

*Examples:*

```
parameter string type = "NMOS" from { "NMOS", "PMOS" };
parameter string filename = "output.dat" exclude { " " };
```

### 3.2.3 Parameter units and descriptions

The standard attributes for descriptions and units, described in Section 2.8.1, can be used for parameters.

*Example:*

```
(* desc="Resistance", units="Ohms" *)
parameter real res = 1.0 from [0:inf);
```

The units and descriptions are only for documentation of the module; in particular, no dimensional analysis is performed on the units. However, it is often important for the user to know the units of a parameter, such as an angle that could be specified in radians or degrees. It should be noted that the `timescale` directive of *IEEE 1364-1995 Verilog HDL* also affects units throughout the module, which can be confusing to the user.

The units and descriptions are of particular value for compact models, where the number of parameters is large and the description is not always clear from the parameter name. Simulators can use this information when generating help messages for a module; many SPICE-like simulators can generate help messages with this information for built-in primitives.

Units and descriptions specified for block-level parameters shall be ignored by the simulator, but can be used for documentation purposes.

### 3.2.4 Parameter arrays

Verilog-AMS HDL includes behavioral extensions which utilize arrays. It requires these arrays be initialized in their definitions and allow overriding their values as with other parameter types. The declaration of arrays of parameters is in a similar manner to those of parameters and register arrays of reals and integers in *IEEE 1364-1995 Verilog HDL*.

Parameter arrays have the following restrictions. Failure to follow these restrictions shall result in an error.

- A type of a parameter array shall be given in the declaration.
- An array assigned to an instance of a module shall be of the exact size of the array bounds of that instance.
- If the array size is changed via a parameter assignment, the parameter array shall be assigned an array of the new size from the same module as the parameter assignment that changed the parameter array size.

*Example:*

```
parameter real poles[0:3] = { 1.0, 3.198, 4.554, 2.00 };
```

### 3.2.5 Local parameters

*IEEE 1364-2001 Verilog HDL* local parameters, identified by the `localparam` keyword, are identical to parameters except that they cannot directly be modified with the `defparam` statement or by the ordered or named parameter value assignment, as described in Section 7.2. Local parameters can be assigned to a constant expression containing a parameter which can be modified with the `defparam` statement or by the ordered or named parameter value assignment.

### 3.2.6 String parameters

String parameters can be declared. Strings are useful for parameters that act as flags, where the correspondence between numerical values and the flag values may not be obvious. The set of allowed values for the string can be specified as a comma-separated list of strings inside curly braces.

The valid operators for string parameters are listed in Table 3-1.

**Table 3-1 String parameter operations**

Operator	Semantics
==	Equality. Checks if the two strings are equal. Result is 1 if they are equal and 0 if they are not. Both operands can be string parameters, or one can be a string parameter and the other a constant string.
!=	Inequality. Logical negation of ==.

*Example:*

```

module ebersmoll (c,b,e);
  inout c, b, e;
  electrical c, b, e;
  parameter string type = "NPN" from { "NPN", "PNP" };
  parameter real alphaf = 0.99 from (0:inf);
  parameter real alphas = 0.5 from (0:inf);
  parameter real ies = 1.0e-17 from (0:inf);
  parameter real ics = 1.0e-17 from (0:inf);
  real sign, ifor, irev;
  analog begin
    sign = ((type == "NPN")) ? 1.0 : -1.0;
    ifor = ies * (limexp(sign*V(b,e)/$vt)-1);
    irev = ics * (limexp(sign*V(b,c)/$vt)-1);
    I(b,e) <+ sign*(ifor - alphas * irev);
    I(b,c) <+ sign*(irev - alphaf * ifor);
  end
endmodule

```

Note how the string parameter `type` associates the string “PNP” with a negative one (-1) value for the variable `sign`. It is common in compact modeling of transistors for the equations to be formulated for NPN or NMOS devices, and behavior of a PNP or PMOS can be described by multiplying all the voltages and currents by -1, even though the “p” denotes positively-charged carriers in the channel of the PMOS.

### 3.2.7 Parameter aliases

Aliases can be defined for parameters. This allows an alternate name to be used when overriding module parameter values as described in Section 7.2. Parameters with different names may be used for the same purpose in different simulators; some compact models accept parameter names with the letter “O” in place of the number “0.”

Parameter aliases are subject to the following rules.

- The type of an alias (**real**, **integer**, or **string**) shall be determined by the original parameter, as is its range of allowed values, if specified.
- The *alias\_identifier* shall not occur anywhere else in the module; in particular, it shall not conflict with a different *parameter\_identifier*, and the equations in the module shall reference the parameter by its original name, not the alias.
- Multiple aliases can point to the same parameter.
- When overriding parameters, it shall be an error to specify an override for parameter by its original name and one or more aliases, or by more than one alias, regardless of how the override is done (by name or using the **defparam** statement).
- When the simulator generates a list of parameter values used, such as for an operating point analysis, only the original name shall appear in the list.

*Example:*

Suppose a module named `nmos` has the following declarations in the module:

```
parameter real dtemp = 0 from [-`P_CELSIUS0:inf);
aliasparam trise = dtemp;
```

Then the following two instantiations of the module are valid:

```
nmos #(.trise(5)) m1(.d(d), .g(g), .s(s), .b(b));
nmos #(.dtemp(5)) m2(.d(d), .g(g), .s(s), .b(b));
```

and the value of the parameter `dtemp`, as used in the module equations for both instances, is 5. This last instantiation is an error:

```
nmos #(.trise(5), .dtemp(5)) m3(.d(d), .g(g), .s(s), .b(b)); //error
```

because an override is specified for the parameter `dtemp` and its alias, even though the values are equal.

### 3.3 Genvars

*Genvars* are integer-valued variables which compose static expressions for instantiating structure behaviorally such as accessing analog signals within behavioral looping constructs. The syntax for declaring genvar variables is shown in Syntax 3-3.

```

genvar_declaration ::=
    genvar list_of_genvar_identifiers ;

list_of_genvar_identifiers ::=
    genvar_identifier { , genvar_identifier }

```

Syntax 3-3—Syntax for genvar declaration

The static nature of genvar variables is derived from the limitations upon the contexts in which their values can be assigned.

*Examples:*

```

genvar i;
analog begin
    ...
    for (i = 0; i < 8; i = i + 1) begin
        V(out[i]) <+ transition(value[i], td, tr);
    end
    ...
end

```

The genvar variable *i* can only be assigned within the for-loop control. Assignments to the genvar variable *i* can consist only of expressions of static values, e.g., parameters, literals, and other genvar variables.

## 3.4 Net\_discipline

In addition to the data types supported by *IEEE 1364-1995 Verilog HDL*, an additional data type, *net\_discipline*, is introduced in Verilog-AMS HDL for continuous time and mixed-signal simulation. *net\_discipline* is used to declare analog nets, as well as declaring the domains of digital nets and regs.

A signal can be digital, analog, or mixed, and is a hierarchical collection of nets which are contiguous (because of port connections). For analog and mixed signals, a single node is associated with all continuous nets segments of the signal. The fundamental characteristic of analog and mixed signals is the values of the associated node are determined by the simultaneous solution of equations defined by the instances connected to the node using Kirchhoff's conservation laws. In general, a node represents a point of physical connections between nets of continuous-time description and it obeys conservation-law semantics.

A net is characterized by the discipline it follows. For example, all low-voltage nets have certain common characteristics, all mechanical nets have certain common characteristics, etc. Therefore, a *net* is always declared as a type of discipline. In this sense, a discipline is a user-defined type for declaring a net.

A *discipline* is characterized by the domain and the attributes defined in the *natures* for potential and flow.

### 3.4.1 Natures

A *nature* is a collection of attributes. In Verilog-AMS HDL, there are several pre-defined attributes. In addition, user-defined attributes can be declared and assigned constant values in a nature.

The nature declarations are at the same level as discipline and module declarations in the source text. That is, natures are declared at the top level and nature declarations do not nest inside other nature declarations, discipline declarations, or module declarations.

The syntax for defining a nature is shown in Syntax 3-4.

```

nature_declaration ::=
    nature nature_name
        [ nature_descriptions ]
    endnature

nature_name ::=
    nature_identifier
    | nature_identifier : parent_identifier

parent_identifier ::=
    nature_identifier
    | discipline_identifier.flow
    | discipline_identifier.potential

nature_descriptions ::=
    nature_description { nature_description }

nature_description ::=
    attribute = constant_expression ;

attribute ::=
    abstol
    | access
    | ddt_nature
    | idt_nature
    | units
    | attribute_identifier

```

Syntax 3-4—Syntax for nature declaration

A nature shall be defined between the keywords **nature** and **endnature**. Each nature definition shall have a unique identifier as the name of the nature and shall include all the required attributes specified in 3.4.1.2.

*Examples:*

```

nature current
  units = "A" ;
  access = I ;
  idt_nature = charge ;
  abstol = 1u ;
endnature

nature voltage
  units = "V" ;
  access = V;
  abstol = 1u ;
endnature

```

### 3.4.1.1 Derived natures

A nature can be derived from an already declared nature. This allows the new nature to have the same attributes as the attributes of the existing nature. The new nature is called a *derived nature* and the existing nature is called a *parent nature*. If a nature is not derived from any other nature, it is called a *base nature*.

In order to derive a new nature from an existing nature, the new nature name shall be followed by a colon (:) and the name of the parent nature in the nature definition.

A derived nature can declare additional attributes or override attribute values of the parent nature, with certain restrictions (as outlined in Section 3.4.1.2) for the predefined attributes.

The attributes of the derived nature are accessed in the same manner as accessing attributes of any other nature.

*Examples:*

```

nature Ttl_curr
  units = "A" ;
  access = I ;
  abstol = 1u ;
endnature

// An alias

nature Ttl_net_curr : Ttl_curr
endnature

nature New_curr : Ttl_curr // derived, but different
  abstol = 1m ; // modified for this nature
  maxval = 12.3 ; // new attribute for this nature
endnature

```

### 3.4.1.2 Attributes

Attributes define the value of certain quantities which characterize the nature. There are five predefined attributes — **abstol**, **access**, **idt\_nature**, **ddt\_nature**, and **units**. In addition, user-defined attributes can be defined in a nature (see Section 3.4.1.3). Attribute

declaration assigns a constant expression to the attribute name, as shown in the example in Section 3.4.1.1.

#### **abstol**

The **abstol** attribute provides a tolerance measure (metric) for convergence of potential or flow calculations. It specifies the maximum negligible for signals associated with the nature.

This attribute is required for all base natures. It is legal for a derived nature to change **abstol**, but if left unspecified it shall inherit the `abstol` from its parent nature. The constant expression assigned to it shall evaluate to a real value.

#### **access**

The **access** attribute identifies the name for the access function. When the nature is used to bind a potential, the name is used as an access function for the potential; when the nature is used to bind a flow, the name is used as an access function for the flow. The usage of access functions is described further in Section 4.3.

This attribute is required for all base natures. It is illegal for a derived nature to change the access attribute; the derived nature always inherits the access attribute of its parent nature. If specified, the constant expression assigned to it shall be an identifier (by name, not as a string).

#### **idt\_nature**

The **idt\_nature** attribute provides a relationship between a nature and the nature representing its time integral.

**idt\_nature** can be used to reduce the need to specified tolerances on the `idt()` operator. If this operator is applied directly on nets, the tolerance can be taken from the node, which eliminates the need to give a tolerance with the operator.

If specified, the constant expression assigned to `idt_nature` shall be the name (not a string) of a nature which is defined elsewhere. It is possible for a nature to be self-referencing with respect to its `idt_nature` attribute. In other words, the value of `idt_nature` can be the nature that the attribute itself is associated with.

The **idt\_nature** attribute is optional; the default value is the nature itself. While it is possible to override the parent's value of `idt_nature` using a derived nature, the nature thus specified shall be related (share the same base nature) to the nature the parent uses for its `idt_nature`.

#### **ddt\_nature**

The **ddt\_nature** attribute provides a relationship between a nature and the nature representing its time derivative.

**ddt\_nature** can be used to reduce the need to specified tolerances on the **ddt()** operator. If this operator is applied directly on nets, the tolerance can be taken from the node, eliminating the need to give a tolerance with the operator.

If specified, the constant expression assigned to `ddt_nature` shall be the name (not a string) of a nature which is defined elsewhere. It is possible for a nature to be self-referencing with respect to its `ddt_nature` attribute. In other words, the value of `ddt_nature` can be the nature that the attribute itself is associated with.

The **ddt\_nature** attribute is optional; the default value is the nature itself. While it is possible to override the parent's value of `ddt_nature` using a derived nature, the nature thus specified shall be related (share the same base nature) to the nature the parent uses for its `ddt_nature`.

### units

The **units** attribute provides a binding between the value of the access function and the units for that value. The **units** field is provided so simulators can annotate the continuous signals with their units and is also used in the *net compatibility rule check*.

This attribute is required for all base natures. It is illegal for a derived nature to define or change the `units`; the derived nature always inherits its parent nature `units`. If specified, the constant expression assigned to it shall be a string.

#### 3.4.1.3 User-defined attributes

In addition to the predefined attributes listed above, a nature can specify other attributes which can be useful for analog modeling. Typical examples include certain maximum and minimum values to define a valid range.

A user-defined attribute can be declared in the same manner as any predefined attribute. The name of the attribute shall be unique in the nature being defined and the value being assigned to the attribute shall be constant.

### 3.4.2 Disciplines

A *discipline* description consists of specifying a domain type and binding any natures to potential or flow.

The syntax for declaring a discipline is shown in Syntax 3-5.

```

discipline_declaration ::=
    discipline discipline_identifier
    [ discipline_descriptions ]
    enddiscipline

discipline_descriptions ::=
    discipline_description { discipline_description }

discipline_description ::=
    nature_binding
    | domain_binding
    | attr_override
    | attribute_identifier = constant_expression;

nature_binding ::=
    pot_or_flow nature_identifier ;

pot_or_flow ::=
    potential
    | flow

domain_binding ::=
    domain continuous ;
    | domain discrete ;

attr_override ::=
    pot_or_flow . attribute_identifier = constant_expression ;

```

Syntax 3-5—Syntax for discipline declaration

A *discipline* shall be defined between the keywords **discipline** and **enddiscipline**. Each discipline shall have a unique identifier as the name of the discipline.

The discipline declarations are at the same level as *nature* and *module* declarations in the source text. That is, disciplines are declared at the top level and discipline declarations do not nest inside other discipline declarations, nature declarations, or module declarations. Analog behavioral nets (nodes) must have a discipline defined for them but interconnect and digital nets do not. It is possible to set the discipline of interconnect and digital nets through discipline declaration with hierarchical references to these nets. It shall be an error to hierarchically override the discipline of a net that was explicitly declared unless it is a compatible discipline.

#### 3.4.2.1 Nature binding

Each discipline can bind a *nature* to its `potential` and `flow`.

Only the name of the nature is specified in the discipline. The nature binding for potential is specified using the keyword **potential**. The nature binding for flow is specified using the keyword **flow**.

The access function defined in the nature bound to potential is used in the model to describe the signal-flow which obeys Kirchhoff's Potential Law (KPL). This access function is called the *potential access function*.

The access function defined in the nature bound to flow is used in the model to describe a quantity which obeys Kirchhoff's Flow Law (KFL). This access function is called the *flow access function*.

Disciplines with two natures are called *conservative disciplines* and the nets associated with conservative disciplines are called *conservative nets*. Conservative disciplines shall not have the same *nature* specified for both the `potential` and the `flow`. Disciplines with a single potential nature are called *signal-flow disciplines* and the nets with signal-flow disciplines are called *signal-flow nets*. Only a `potential` nature is allowed to be specified for a signal-flow discipline, as shown in the following examples.

*Examples:*

Conservative discipline

```
discipline electrical
  potential Voltage ;
  flow Current ;
enddiscipline
```

Signal-flow disciplines

```
discipline voltage
  potential Voltage ;
enddiscipline

discipline current
  potential Current ;
enddiscipline
```

### Multi-disciplinary example

Disciplines in Verilog-AMS HDL allow designs of multi-disciplinaries to be easily defined and simulated. Disciplines can be used to allow unique tolerances based on the size of the signals and outputs displayed in the actual units of the discipline. This example shows how an application spanning multiple disciplines can be modeled in Verilog-AMS HDL. It models a DC-motor driven by a voltage source.

```
module motorckt;
  parameter real freq=100;
  ground gnd;

  electrical drive;
  rotational shaft;

  motor m1 (drive, gnd, shaft);
  vsource #(.freq(freq), .ampl(1.0)) v1 (drive, gnd);

endmodule
```

```

// vp:   positive terminal [V,A] vn:negative terminal [V,A]
// shaft: motor shaft [rad,Nm]
// INSTANCE parameters
// Km = motor constant [Vs/rad] Kf = flux constant [Nm/A]
// j = inertia factor [Nms^2/rad] D= drag (friction) [Nms/rad]
// Rm = motor resistance [Ohms] Lm = motor inductance [H]
// A model of a DC motor driving a shaft

module motor(vp, vn, shaft);
  inout vp, vn, shaft;
  electrical vp, vn ;
  rotational shaft ;

  parameter real Km = 4.5, Kf = 6.2;
  parameter real j = .004, D = 0.1;
  parameter real Rm = 5.0, Lm = .02;

  analog begin
    V(vp, vn) <+ Km*Theta(shaft) + Rm*I(vp, vn) +
      ddt(Lm*I(vp, vn));
    Tau(shaft) <+ Kf*I(vp, vn) - D*Theta(shaft) -
      ddt(j*Theta(shaft));
  end
endmodule

```

### 3.4.2.2 Domain binding

Analog signal values are represented in continuous time, whereas digital signal values are represented in discrete time. The **domain** attribute of the discipline stores this property of the signal. It takes two possible values, **discrete** or **continuous**. Signals with continuous-time domains are real valued. Signals with discrete-time domains can either be binary (0, 1, x, or z), integer or real values.

*Examples:*

```

discipline electrical
  domain continuous;
  potential Voltage;
  flow Current;
enddiscipline

discipline logic
  domain discrete ;
enddiscipline

```

The **domain** attribute is optional. The default value for domain is **continuous** for non-empty disciplines, e.g., those which specify nature bindings.

### 3.4.2.3 Empty disciplines

It is possible to define a discipline with no nature bindings. These are known as *empty disciplines* and they can be used in structural descriptions to let the components connected to a net determine which natures are to be used for the net.

Such disciplines may have a domain binding or they may be domain-less, thus allowing the domain to be determined by the connectivity of the net (see Section 8.4).

*Example:*

```
discipline interconnect
    domain continuous ;
enddiscipline
```

#### 3.4.2.4 Discipline of wires and undeclared nets

It is possible for a module to have nets where there are no discipline declarations. If such a net appears bound only to ports in module instantiations, it may have no declaration at all or may be declared to have a wire type such as `wire`, `tri`, `wand`, `wor`, etc. If it is referenced in behavioral code, then it must have a wire type.

In these cases, the net shall be treated as having an empty discipline. If the net is referenced in behavioral code, then it shall be treated as having empty discipline with a domain binding of `discrete`, otherwise it shall be treated as having empty discipline with no domain binding. If a net has a wiretype but is not connected to behavioral code (interconnect) and it resolved to domain discrete then its wiretype shall be used in any nettype resolution steps per IEEE 1364-2001.

This allows *netlists* (modules that describe connectivity only, with no behavior) that use wire as an interconnect to be valid in both *IEEE 1364-1995 Verilog HDL* and Verilog-AMS HDL. The domain shall be determined by the connectivity of the net (see Section 8.4).

#### 3.4.2.5 Overriding nature attributes from discipline

A discipline can override the value of the bound nature for the pre-defined attributes (except as restricted by Section 3.4.1.2), as shown for the flow `t11_curr` in the example below. To do so from a discipline declaration, the bound nature and attribute needs to be defined, as shown for the `abstol` value within the discipline `t11` in the example below. The general form is shown as the *attr\_override* terminal in Syntax 3-5: the keyword **flow** or **potential**, then the hierarchical separator `.` and the attribute name, and, finally, set all of this equal to (`=`) the new value (e.g., `flow.abstol = 10u`).

*Examples:*

```
nature t11_curr
    units = "A" ;
    access = I ;
    abstol = 1u ;
endnature

nature t11_volt
    units = "V" ;
    access = V ;
    abstol = 100u ;
endnature
```

```

discipline ttl
  potential ttl_volt ;
  flow ttl_curr ;
  flow.abstol = 10u ;
enddiscipline

```

### 3.4.2.6 Deriving natures from disciplines

A nature can be derived from the *nature* bound to the `potential` or `flow` in a discipline. This allows the new nature to have the same attributes as the attributes for the nature bound to the `potential` or the `flow` of the discipline.

If the nature binding to the `potential` or the `flow` of a discipline changes, the new nature shall automatically inherit the attributes for the changed nature.

In order to derive a new nature from `flow` or `potential` of a discipline, the nature declaration shall also include the discipline name followed by the hierarchical separator (`.`) and the keyword **flow** or **potential**, as shown for `Ttl_net_curr` in the example below.

A nature derived from the `flow` or `potential` of a discipline can declare additional attributes or override values of the attributes already declared.

*Examples:*

```

nature Ttl_net_curr : Ttl.flow // from the example in Section 3.4.2.5
endnature           // abstol = 10u as modified in ttl

nature Ttl_net_volt : Ttl.potential // from the example in
// Section 3.4.2.5
  abstol = 1m ;// modified for this nature
  maxval = 12.3 ;// new attribute for this nature
endnature

```

### 3.4.2.7 User-defined attributes

Like natures, a discipline can specify user-defined attributes. Discipline user-defined attributes are useful for the same reasons as nature user-defined attributes (see Section 3.4.1.3).

## 3.4.3 Net discipline declaration

Each *net\_discipline* declaration associates nets and regs with an already declared discipline. Syntax 3-6 shows how to declare disciplines of nets and regs.

```

net_discipline_declaration ::=
    discipline_identifier [ range ] list_of_nets ;
range ::=
    [ constant_expression : constant_expression ]

list_of_nets ::=
    net_type {, net_type}

net_type ::=
    net_identifier [range] [= constant_expression | constant_array_expression]

```

Syntax 3-6—Syntax for net discipline declaration

If a range is specified for a net, the net is called a *vector net*; otherwise it is called a *scalar net*. A vector net is also called an *bus*.

*Examples:*

```

electrical [MSB:LSB] n1 ; // MSB and LSB are parameters
voltage [5:0] n2, n3 ;
magnetic inductor ;
logic [10:1] connector1 ;

```

Nets represent the abstraction of information about signals. As with ports, nets represent component interconnections. Nets declared in the module interface define the ports to the module (see Section 7.4.4).

A net used for modeling a conservative system shall have a discipline with both access functions (`potential` and `flow`) defined. When modeling a signal-flow system, the discipline of a net can have only `potential` access functions. When modeling a discrete system, the discipline of a net can only have a domain of `discrete` defined.

Nets declared with an empty discipline do not have declared natures, so such nets can not be used in analog behavioral descriptions (because the access functions are not known). However, such nets can be used in structural descriptions, where they inherit the natures from the ports of the instances of modules that connect to them.

### 3.4.3.1 Net descriptions

Nets can be declared with a description attribute. This information can be used by the simulator to generate help messages for a module.

*Example:*

```

(* desc="drain terminal" *) electrical d;

```

If a net is also a module port, the description attribute may also be specified on the port declaration line (in which the net is declared as `input`, `inout`, or `output`). If the description attribute is specified for the same `net_identifier` in both the net discipline declaration and the port declaration, then the last attribute value shall be used and the tool can give a warning that a duplicate attribute specification has occurred.

### 3.4.3.2 Net Discipline Initial (Nodeset) Values

Nets with continuous disciplines are allowed to have initializers on their net discipline declarations; however, nets of non-continuous disciplines are not.

*Examples:*

```
electrical a = 5.0;
electrical [0:4] bus = {2.3,4.5,,6.0};
mechanical top.foo.w = 250.0;
```

The initializer will be used as a nodeset value for the potential of the net by the analog solver. In the case of analog buses, a constant array expression is used as an initializer. A null value in the constant array indicates that no nodeset value is being specified for this element of the bus.

If different nets of a node have conflicting initializers, then initializers on hierarchical net declarations win. If there are multiple hierarchical declarations, then the declaration on the highest level wins. If there are multiple hierarchical declarations on the highest level, then it is a race condition for which the initializer wins. If the multiple conflicting initializers are not hierarchical, then it is also a race condition for which the initializer wins.

### 3.4.4 Ground declaration

Each ground declaration is associated with an already declared net of continuous discipline. The node associated with the net will be the global reference node in the circuit. If used in behavioral code, the net shall be used in only the differential source and probe forms, e.g.,  $V(\text{gnd})$  is not allowed. The net must be assigned a continuous discipline to be declared ground.

Syntax 3-7 shows the syntax used for declaring the global reference node (*ground*).

<pre>ground_declaration ::=     <b>ground</b> [ range ] list_of_nets;</pre>
---

Syntax 3-7—Syntax for declaring ground

*Examples:*

```
module loadedsrc(in, out);
    input in;
    output out;
    electrical in, out;
    electrical gnd;
    ground gnd;
    parameter real srcval = 5.0;
```

```

    resistor #(.r(10K)) r1(out,gnd);
analog begin
    V(out) <+ V(in,gnd)*2;
end
endmodule

```

### 3.4.5 Implicit nets

Nets can be used in a structural descriptions without being declared. In this case, the net is implicitly declared to be a scalar net with the empty discipline and undefined domain.

*Examples:*

```

module top(i1, i2, o1, o2, o3);
    input i1, i2;
    output o1, o2, o3;
    electrical i1, i2, o1, o2, o3;

    // ab1, ab2, cb1, cb2 are implicit nets, not declared
    blk_a a1( i1, ab1 );
    blk_a a2( i2, ab2 );
    blk_b b1( ab1, cb1 );
    blk_b b2( ab2, cb2 );
    blk_c c1( o1, o2, o3, cb1, cb2);
endmodule

```

## 3.5 Real net declarations

The **wreal**, or real net data type, represents a real-valued physical connection between structural entities. A **wreal** net shall not store its value. A **wreal** net can be used for real-valued nets which are driven by a single driver, such as a continuous assignment. If no driver is connected to a **wreal** net, its value shall be zero (0.0). Unlike other digital nets which have an initial value of 'x', **wreal** nets shall have an initial value of zero.

**wreal** nets can only be connected to compatible interconnect and other **wreals** or real expressions. They cannot be connected to any other wires, although connection to explicitly declared 64-bit wires can be done via system tasks \$realtobits and \$bitstoreal. Compatible interconnect are nets of type wire, tri, and **wreal** where the IEEE 1364-2001 net resolution is extended for **wreal**. When the two nets connected by a port are of net type **wreal** and wire/tri, the resulting single net will be assigned as **wreal**. Connection to other nettypes will result in an error.

Syntax 3-8 shows the syntax for declaring digital nets.

```
digital_net_declaration ::=
    digital_net_declaration
    | wreal [range] list_of_identifiers ;
```

Syntax 3-8—Syntax for declaring digital nets

*Examples:*

```
module foo(in, out);
    input in;
    output out;
    wreal in;
    electrical out;
    analog begin
        V(out) <+ in;
    end
endmodule

module top();
    real stim;
    electrical load;
    wreal wrstim;
    assign wrstim = stim;
    foo f1(wrstim, load);
    always begin
        #1 stim = stim + 0.1;
    end
endmodule
```

## 3.6 Default discipline

Verilog-AMS HDL supports the ``default_discipline` compiler directive. This directive specifies a default discrete discipline to be applied to any discrete net which does not have an explicit discipline declaration. A description and its syntax are shown in Section 11.1.

### 3.6.1 Disciplines of primitives

With internal simulator primitives the discipline of the vpiLoConn to be used in discipline resolution during a mixed-signal simulation must be known. For digital primitives the domain is discrete and thus the discipline is set via the `default_discipline` directive as it is for digital modules. If the discipline of digital connections (vpiLoConn) to a mixed net are unknown then the `default_discipline` must be specified (via the directive or other vendor specific method). If not specified, an error will result during discipline resolution.

For analog primitives, the discipline will be defined by the attribute `port_discipline` on that instance. If no attribute is found then it will acquire the discipline of other compatible continuous disciplines connected to that net segment. If no disciplines are connected to that net, then the default discipline is set to electrical. This is further described in section E.3.3.

### 3.7 Discipline precedence

While a net itself can be declared only in the module to which it belongs, the discipline of the net can be specified in a number of ways.

- The discipline name can appear in the declaration of the net.
- The discipline name can be used in a declaration which makes an out of context reference to the net from another module.
- The discipline name can be used in a ``default_discipline` compiler directive.

Discipline conflicts can arise if more than one of these methods is applied to the same net. Discipline conflicts shall be resolved using the following order of precedence:

1. A declaration from a module other than the module to which the net belongs using an out of module reference, e.g.,

```
module example1;
    electrical example2.net;
endmodule
```

2. The local declaration of the net in the module to which it belongs, e.g.,

```
module example2;
    electrical net;
endmodule
```

3. ``default_discipline` with qualifier, e.g.,

```
`default_discipline logic trireg;
```

4. ``default_discipline` without qualifier, e.g.,

```
`default_discipline logic;
```

It is not legal to have two different disciplines at the same level of precedence for the same net.

## 3.8 Net compatibility

Certain operations can be done on nets only if the two (or more) nets are compatible. For example, if an access function has two nets as arguments, they must be compatible. The following rules shall apply to determine the compatibility of two (or more) nets:

*Discrete Domain Rule:* Digital nets with the same signal value type (i.e., bit, real, integer) are compatible with each other if their disciplines are compatible (i.e., the discipline has a discrete domain or is empty).

*Signal Domain Rule:* It shall be an error to connect two ports or nets of different domains unless there is a connect statement (see Section 8.4) defined between the disciplines of the nets or ports.

*Signal Connection Rule:* It shall be an error to connect two ports or nets of the same domain with incompatible disciplines.

### 3.8.1 Discipline and Nature Compatibility

The following rules shall apply to determine discipline compatibility:

*Self Rule (Discipline):* A discipline is compatible with itself.

*Empty Discipline Rule:* An empty discipline is compatible with all other disciplines, regardless of domain.

*Domain Incompatibility Rule:* Disciplines with different domain attributes are incompatible.

*Potential Incompatibility Rule:* Disciplines with incompatible potential natures are incompatible.

*Flow Incompatibility Rule:* Disciplines with incompatible flow natures are incompatible.

The following rules shall apply to determine nature compatibility:

*Self Rule (Nature):* A nature is compatible with itself.

*Non-Existent Binding Rule:* A nature is compatible with a non-existent discipline binding.

*Base Nature Rule:* A derived nature is compatible with its base nature.

*Derived Nature Rule:* Two natures are compatible if they are derived from the same base nature.

*Units Value Rule:* Two natures are compatible if they have the same value for the units attribute.

The following examples illustrates these rules.

*Examples:*

```

nature Voltage
  access = V;
  units = "V";
  abstol = 1u;
endnature

nature Current
  access = I;
  units = "A";
  abstol = 1p;
endnature

nature highvoltage: Voltage
  abstol = 1;
endnature

discipline electrical
  potential Voltage;
  nature Current;
endnature

discipline highvolt
  potential highvoltage;
  nature Current;
endnature

discipline sig_flow_v
  potential Voltage;
enddiscipline

discipline sig_flow_i
  potential Current;
enddiscipline

nature Position
  access = X;
  units = "m";
  abstol = 1u;
endnature

nature Force
  access = F;
  units = "N";
  abstol = 1n;
endnature

discipline rotational
  potential Position;
  flow Force;
enddiscipline

discipline sig_flow_x
  potential Position;
enddiscipline

discipline sig_flow_f
  potential Force;
enddiscipline

discipline empty
enddiscipline

discipline logic
  domain discrete;
enddiscipline

discipline continuous_elec
  domain continuous;
  potential Voltage;
  nature Current;
endnature

```

The following compatibility observations can be made from the above example:

- Voltage and highvoltage are compatible natures because they both exist and are derived from the same base natures.
- electrical and highvolt are compatible disciplines because the natures for both potential and flow exist and are derived from the same base natures.
- electrical and sig\_flow\_v are compatible disciplines because the nature for potential is same for both disciplines and the nature for flow does not exist in sig\_flow\_v.

- `electrical` and `rotational` are incompatible disciplines because the natures for both potential and flow are not derived from the same base natures.
- `electrical` and `sig_flow_x` are incompatible disciplines because the nature for both potentials are not derived from the same base nature.
- An *empty discipline* is compatible with all other disciplines of the same domain (determined independently) because it does not have a potential or a flow nature. Without natures, there can be no conflicting natures.
- `electrical` and `logic` are incompatible disciplines because the domains are different. A connect statement must be used to connect nets or ports of these disciplines together.
- `electrical` and `continuous_elec` are compatible disciplines because the default domain for discipline `electrical` is `continuous` and the specified natures for potential and flow are the same.

### 3.9 Branches

A *branch* is a path between two nets. If both nets are conservative, then the branch is a *conservative branch* and it defines a branch potential and a branch flow. If one net is a signal-flow net, then the branch is a *signal-flow branch* and it defines either a branch potential or a branch flow, but not both.

Each branch declaration is associated with two nets from which it derives a discipline. These nets are referred to as the *branch terminals*. Only one net need be specified, in which case the second net defaults to `ground` and the discipline for the branch is derived from the specified net. The disciplines for the specified nets shall be compatible (see Section 3.8).

The syntax for declaring branches is shown in Syntax 3-9.

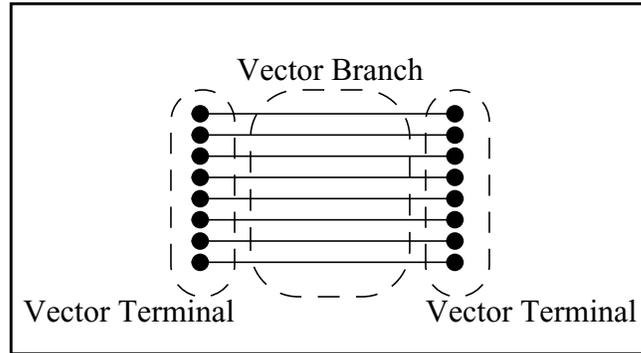
```

branch_declaration ::=
    branch list_of_branches ;
list_of_branches ::=
    terminals list_of_branch_identifiers
terminals ::=
    ( net_or_port_scalar_expression )
    | ( net_or_port_scalar_expression , net_or_port_scalar_expression )
list_of_branch_identifiers ::=
    branch_identifier [ range ]
    | branch_identifier [ range ] , list_of_branch_identifiers

```

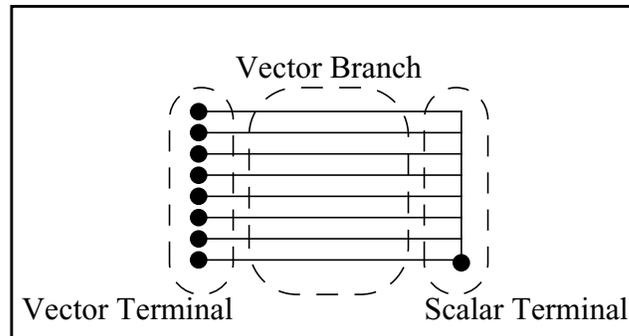
Syntax 3-9—Syntax for branch declaration

If one of the terminals of a branch is a vector net, then the other terminal shall either be a scalar net or a vector net of the same size. In the latter case, the branch is referred to as a *vector branch*. When both terminals are vectors, the scalar branches that make up the vector branch connect to the corresponding scalar nets of the vector terminals, as shown in Figure 3-1.



**Figure 3-1 Two vector terminals**

When one terminal is a vector and the other is a scalar, a singular scalar branch connects to each scalar net in the vector terminal and each terminal of the vector branch connects to the scalar terminal, as shown in Figure 3-2.



**Figure 3-2 One vector and one scalar terminal**

## 3.10 Namespace

The following subsections define the namespace.

### 3.10.1 Nature and discipline

Natures and disciplines are defined at the same level of scope as modules. Thus, identifiers defined as natures or disciplines have a global scope, which allows nets to be declared inside any module in the same manner as an instance of a module.

### 3.10.2 Access functions

Each access function name, defined before a module is parsed, is automatically added to that module's name space unless there is another identifier defined with the same name as the access function in that module's name space. Furthermore, the access function of each base nature shall be unique.

### 3.10.3 Net

The scope rules for net identifiers are the same as the scope rules for any other identifier declarations, except nets can not be declared anywhere other than in the port of a module or in the module itself. A net can only be declared inside a module block; a net can not be declared local to a block.

Access functions are uniquely defined for each net based on the discipline of the net. Each access function is used with the name of the net as its argument and a net can only be accessed through its access functions.

The hierarchical reference character (.) can be used to reference a net across the module boundary according to the rules specified in *IEEE 1364-1995 Verilog HDL*.

### 3.10.4 Branch

The scope rules for branch identifiers are the same as the scope rules for net identifiers. A branch can only be declared inside a module block; there is no local declaration for a branch.

Access functions are uniquely defined for each branch based on the discipline of the branch. The access function is used with the name of the branch as its argument and a branch can only be accessed through its access functions.

The hierarchical reference character (.) can be used to reference a net across the module boundary according to the rules specified in *IEEE 1364-1995 Verilog HDL*.



# Section 4

## Expressions

This section describes the operators and operands available in the Verilog-AMS HDL, and how to use them to form expressions.

An *expression* is a construct which combines *operands* with *operators* to produce a result which is a function of the values of the operands and the semantic meaning of the operator. Any legal operand, such as an integer or an indexed element from an array of reals, without a operator is also considered an expression. Wherever a value is needed in a Verilog-AMS HDL statement, an expression can be used.

Some statement constructs require an expression to be a *constant expression*. The operands of a constant expression consists of constant numbers and parameter names, but they can use any of the operators defined in Table 4-1, Table 4-17, and Table 4-18.

### 4.1 Operators

The symbols for the Verilog-AMS HDL operators are similar to those in the C programming language. Table 4-1 lists these operators.

**Table 4-1—Operators**

+ - * /	Arithmetic
%	Modulus
> >= < <=	Relational
!== ==	Case equality
!= ==	Logical equality
!	Logical negation
&&	Logical and
	Logical or
~	Bit-wise negation
& ~&	Bit-wise and, nand
~	Bit-wise inclusive or, nor
^	Bit-wise exclusive or
^^ ~^	Bit-wise equivalence

**Table 4-1—Operators, *continued***

<<	Left shift
>>	Right shift
?:	Conditional
or	Event or
{ } {{}}	Concatenation, replication

### 4.1.1 Operators with real operands

The operators shown in Table 4-2 are legal when applied to real operands. All other operators are considered illegal when used with real operands.

**Table 4-2—Legal operators for use in real expressions**

unary + unary -	Unary operators
+ - * /	Arithmetic
%	Modulus
> >= < <=	Relational
== !=	Logical equality
! &&	Logical
?:	Conditional
or	Event or

The result of using logical or relational operators on real numbers is an integer value 0 (*false*) or 1 (*true*).

Table 4-2 lists those operators which shall not be used to operate on real numbers.

**Table 4-3—Operators not allowed for real expressions**

=== !==	Case equality
~ & ~&   ^ ^ ~ ^	Bit-wise
<< >>	Shift
{ } {{}}	Concatenation, replication

#### 4.1.1.1 Real to integer conversion

Real numbers are converted to integers by rounding the real number to the nearest integer, rather than by truncating it. Implicit conversion takes place when a real number is assigned to an integer. The ties are rounded away from zero (0).

*Examples:*

```
// The real numbers 35.7 and 35.5 both become 36 when
// converted to an integer and 35.2 becomes 35.

// Converting -1.5 to integer yields -2, converting 1.5 to
// integer yields 2.
```

#### 4.1.1.2 Arithmetic conversion

For operands, a common data type for each operand is determined before the operator is applied. If either operand is real, the other operand is converted to real. Implicit conversion takes place when a integer number is used with a real number in an operand.

*Examples:*

```
a = 3 + 5.0;
// The expression "3 + 5.0" is evaluated by "casting" the
// integer 3 to the real 3.0, and the result of the expression is 8.0.

b = 1 / 2;
// The above is integer division and the result is 0.

c = 8.0 + (1/2);
// (1/2) is treated as integer division, but the result is cast to a
// real (0.0) during the addition, and the result of the
// expression is 8.0.
```

#### 4.1.2 Binary operator precedence

The precedence order of *binary operators* and the *conditional operator* (?:) is shown in Table 4-4.

**Table 4-4—Precedence rules for binary operators**

+ - ! ~(unary)	Highest precedence	
* / %		
+ -(binary)		
<< >>		
< <= > >=		
== != === !==		
& ~&		
^ ^~ ~^		
~		
&&		
?: (conditional operator)		Lowest precedence

Operators shown on the same row in Table 4-4 have the same precedence. Rows are arranged in order of decreasing precedence for the operators. For example,  $*$ ,  $/$ , and  $\%$  all have the same precedence, which is higher than that of the binary  $+$  and  $-$  operators.

All operators associate left to right with the exception of the conditional operator which associates right to left. Associativity refers to the order in which the operators having the same precedence are evaluated.

*Example:*

In the following example  $B$  is added to  $A$  and then  $C$  is subtracted from the result of  $A+B$ .

$$A + B - C$$

When operators differ in precedence, the operators with higher precedence associate first.

*Examples:*

In the following example,  $B$  is divided by  $C$  (division has higher precedence than addition) and then the result is added to  $A$ .

$$A + B / C$$

Parentheses can be used to change the operator precedence.

$$(A + B) / C$$

// not the same as  $A + B / C$

### 4.1.3 Expression evaluation order

The operators follow the associativity rules while evaluating an expression as described in Section 4.1.2. However, if the final result of an expression can be determined early, the entire expression need not be evaluated, as long as the remaining expression does not contain analog expressions. This is called *short-circuiting* an expression evaluation.

*Examples:*

```
integer A, B, C, result ;
result = A & (B | C) ;
```

If  $A$  is known to be zero (0), the result of the expression can be determined as zero (0) without evaluating the sub-expression  $B | C$ .

### 4.1.4 Arithmetic operators

Table 4-5 shows the binary arithmetic operators.

**Table 4-5—Arithmetic operators defined**

$a + b$	a plus b
$a - b$	a minus b
$a * b$	a multiply by b

**Table 4-5—Arithmetic operators defined, *continued***

a / b	a divide by b
a % b	a modulo b

Integer division truncates any fractional part toward zero (0).

The unary arithmetic operators take precedence over the binary operators. Table 4-6 shows the unary operators.

**Table 4-6—Unary operators defined**

+m	Unary plus m (same as m)
-m	Unary minus m

The *modulus* operator, for example  $y \% z$ , gives the remainder when the first operand is divided by the second, and thus is zero (0) when  $z$  divides  $y$  exactly. The result of a modulus operation takes the sign of the first operand.

For the case of the modulus operator where either argument is real, the operation performed is

$$a \% b = a - \text{floor}(a/b) * b;$$

Table 4-7 gives examples of modulus operations.

**Table 4-7—Examples of modulus operations**

Modulus expression	Result	Comments
11 % 3	2	11/3 yields a remainder of 2.
12 % 3	0	12/3 yields no remainder.
-10 % 3	-1	The result takes the sign of the first operand.
11 % -3	2	The result takes the sign of the first operand.
10 % 3.75	2.5	[10 - floor(10/3.75)*3.75 ] yields a remainder of 2.5.

#### 4.1.5 Relational operators

Table 4-8 lists and defines the relational operators.

**Table 4-8—The relational operators defined**

a < b	a less than b
a > b	a greater than b
a <= b	a less than or equal to b
a >= b	a greater than or equal to b

An expression using these *relational operators* yields the value zero (0) if the specified relation is *false* or the value one (1) if it is *true*.

All the relational operators have the same precedence. Relational operators have lower precedence than arithmetic operators.

*Examples:*

The following examples illustrate the implications of this precedence rule:

```
a < foo - 1 // this expression is the same as
a < (foo - 1)// this expression, but . . .
foo - (1 < a)// this one is not the same as
foo - 1 < a // this expression
```

When `foo - (1 < a)` is evaluated, the relational expression is evaluated first and then either zero (0) or one (1) is subtracted from `foo`. When `foo - 1 < a` is evaluated, the value of `foo` operand is reduced by one (1) and then compared with `a`.

#### 4.1.6 Case equality operators

The *case equality operators* share the same level of precedence as the *logical equality operators*. These operators have limited support in the analog block (see Section 8.3.2). Additional information on these operators can also be found in the *IEEE 1364-1995 Verilog HDL*.

#### 4.1.7 Logical equality operators

The *logical equality operators* rank lower in precedence than the relational operators. Table 4-9 lists and defines the equality operators.

**Table 4-9—The equality operators defined**

<code>a == b</code>	a equal to b
<code>a != b</code>	a not equal to b

Both equality operators have the same precedence. These operators compare the value of the operands. As with the relational operators, the result shall be zero (0) if comparison fails, one (1) if it succeeds.

#### 4.1.8 Logical operators

The operators *logical and* (`&&`) and *logical or* (`||`) are logical connectives. The result of the evaluation of a logical comparison can be one (1) (defined as *true*) or zero (0) (defined as *false*). The precedence of `&&` is greater than that of `||` and both are lower than relational and equality operators.

A third logical operator is the unary *logical negation* operator (`!`). The negation operator converts a non-zero or true operand into zero (0) and a zero or false operand into one (1).

*Examples:*

The following expression performs a logical and of three sub-expressions without needing any parentheses:

```
a < param1 && b != c && index != lastone
```

However, parentheses can be used to clearly show the precedence intended, as in the following rewrite of the above example:

```
(a < param1) && (b != c) && (index != lastone)
```

### 4.1.9 Bit-wise operators

The *bit-wise operators* perform bit-wise manipulations on the operands—that is, the operator combines a bit in one operand with its corresponding bit in the other operand to calculate one bit for the result. The following logic tables (Table 4-10 — Table 4-16) show the results for each possible calculation.

**Table 4-10—Bit-wise binary and operator**

&	0	1
0	0	0
1	0	1

**Table 4-11—Bit-wise binary or operator**

	0	1
0	0	1
1	1	1

**Table 4-12—Bit-wise binary nand operator**

~&	0	1
0	1	1
1	1	0

**Table 4-13—Bit-wise binary nor operator**

~	0	1
0	1	0
1	0	0

**Table 4-14—Bit-wise binary exclusive or operator**

^	0	1
0	0	1
1	1	0

**Table 4-15—Bit-wise binary exclusive nor operator**

^^	0	1
0	1	0
1	0	1

**Table 4-16—Bit-wise unary negation operator**

~	
0	1
1	0

#### 4.1.10 Shift operators

The *shift operators*, `<<` and `>>`, perform left and right shifts of their left operand by the number of bit positions given by the right operand. Both shift operators fill the vacated bit positions with zeroes (0). The right operand is always treated as an unsigned number.

*Examples:*

```
integer start, result;
analog begin
    start = 1;
    result = (start << 2);
end
```

In this example, the register `result` is assigned the binary value 0100, which is 0001 shifted to the left two positions and zero-filled.

#### 4.1.11 Conditional operator

The *conditional operator*, also known as *ternary operator*, is right associative and shall be constructed using three operands separated by two operators, as shown in Syntax 4-1.

<pre>conditional_expression ::=     expression1 ? expression2 : expression3</pre>
---

Syntax 4-1—Syntax for conditional operator

The evaluation of a conditional operator begins with the evaluation of `expression1`. If `expression1` evaluates to *false* (0), then `expression3` is evaluated and used as the result of the conditional expression. If `expression1` evaluates to *true* (any value other than zero (0)), then `expression2` is evaluated and used as the result.

#### 4.1.12 Event or

The event `or` operator performs an or of events. See Section 6.7.2 for events and triggering of events.

#### 4.1.13 Concatenations

A concatenation is used for joining scalar elements into compound elements (buses or arrays) for the built-in types `integer` or `real`, or for elements declared of type `net_discipline`. The concatenation shall be expressed using the brace characters (`{ }`), with commas separating the expressions within.

*Examples:*

```

module x;
  parameter real p1[0:2] = { 1.0, 2.0, 3.0 };
  ...
endmodule

module y;
  parameter real pole1 = 0, pole2 = 0, pole3 = 0;
  x #(.p1({pole1, pole2, pole3}) x1;
  ...
endmodule

```

Module `x` defines a real-array parameter `p1`. Module `y` instantiates `x` and overrides the array value of the parameter `p1` of module `x` via the concatenation of the scalar parameters `pole1`, `pole2`, and `pole3`.

Concatenations can be expressed using a replication multiplier.

*Example:*

```
{c, {2{a, b}}}
```

// equivalent to: {c, a, b, a, b}

The replication multiplier shall be a constant expression.

## 4.2 Built-in mathematical functions

Verilog-AMS HDL supports the following standard mathematical functions.

### 4.2.1 Standard mathematical functions

The standard mathematical functions supported by Verilog-AMS HDL are shown in Table 4-17. The operands shall be numeric (`integer` or `real`). For `min()`, `max()`, and `abs()`, if either operand is real, both are converted to real, as is the result. All other arguments are converted to real.

**Table 4-17—Standard functions**

Function	Description	Domain
<code>ln(x)</code>	Natural logarithm	$x > 0$
<code>log(x)</code>	Decimal logarithm	$x > 0$
<code>exp(x)</code>	Exponential	All $x$
<code>sqrt(x)</code>	Square root	$x \geq 0$
<code>min(x, y)</code>	Minimum	All $x$ , all $y$
<code>max(x, y)</code>	Maximum	All $x$ , all $y$
<code>abs(x)</code>	Absolute	All $x$

Table 4-17—Standard functions, *continued*

Function	Description	Domain
<b>pow</b> ( $x, y$ )	Power ( $x^y$ )	if $x > 0$ , all $y$ ; if $x = 0$ , $y > 0$ ; if $x < 0$ , <b>int</b> ( $y$ )
<b>floor</b> ( $x$ )	Floor	All $x$
<b>ceil</b> ( $x$ )	Ceiling	All $x$

The **min**( $x, y$ ), **max**( $x, y$ ), and **abs**( $x$ ) functions have discontinuous derivatives; it is necessary to define the behavior of the derivative of these functions at the point of the discontinuity. In this context, these functions are defined so:

**min**( $x, y$ ) is equivalent to  $(x < y) ? x : y$

**max**( $x, y$ ) is equivalent to  $(x > y) ? x : y$

**abs**( $x$ ) is equivalent to  $(x > 0) x : -x$

#### 4.2.2 Transcendental functions

The trigonometric and hyperbolic functions supported by Verilog-AMS HDL are shown in Table 4-18. All operands shall be numeric (**integer** or **real**) and are converted to real if necessary. Arguments to the trigonometric functions (**sin**, **cos**, **tan**) and return values of the inverse trigonometric functions (**asin**, **acos**, **atan**, **atan2**) are in radians.

Table 4-18—Trigonometric and hyperbolic functions

Function	Description	Domain
<b>sin</b> ( $x$ )	Sine	All $x$
<b>cos</b> ( $x$ )	Cosine	All $x$
<b>tan</b> ( $x$ )	Tangent	$x \neq n(\pi / 2)$ , $n$ is odd
<b>asin</b> ( $x$ )	Arc-sine	$-1 \leq x \leq 1$
<b>acos</b> ( $x$ )	Arc-cosine	$-1 \leq x \leq 1$
<b>atan</b> ( $x$ )	Arc-tangent	All $x$
<b>atan2</b> ( $x, y$ )	Arc-tangent of $x/y$	All $x$ , All $y$
<b>hypot</b> ( $x, y$ )	<b>sqrt</b> ( $x^2 + y^2$ )	All $x$ , All $y$
<b>sinh</b> ( $x$ )	Hyperbolic sine	All $x$
<b>cosh</b> ( $x$ )	Hyperbolic cosine	All $x$
<b>tanh</b> ( $x$ )	Hyperbolic tangent	All $x$
<b>asinh</b> ( $x$ )	Arc-hyperbolic sine	All $x$
<b>acosh</b> ( $x$ )	Arc-hyperbolic cosine	$x \geq 1$
<b>atanh</b> ( $x$ )	Arc-hyperbolic tangent	$-1 < x < 1$

### 4.2.3 Error handling

All values outside of the domain for these math functions shall report an error.

## 4.3 Signal access functions

Access functions are used to access signals on nets, ports, and branches. There are two types of access functions, *branch access functions* and *port access functions*. The name of the access function for a signal is taken from the discipline of the net, port, or branch where the signal or port is associated and utilizes the () operator. A port access function also takes its name from the discipline of the port to which it is associated but utilizes the port access (<>) operator.

If the signal or port access function is used in an expression, the access function returns the value of the signal. If the signal access function is being used on the left side of a branch assignment or contribution statement, it assigns a value to the signal. A port access function can not be used on the left side of a branch assignment or contribution statement.

Table 4-19 shows how access functions can be applied to branches, nets, and ports. In this table, *b1* refers to a branch, *n1* and *n2* represent either nets or ports, and *p1* represents a port. These branches, nets, and ports are assumed to belong to the electrical discipline, where *V* is the name of the access function for the voltage (potential) and *I* is the name of the access function for the current (flow).

**Table 4-19—Access functions examples**

Example	Comments
V( <i>b1</i> )	Accesses the voltage across branch <i>b1</i> .
V( <i>n1</i> )	Accesses the voltage of <i>n1</i> (a net or a port) relative to ground.
V( <i>n1</i> , <i>n2</i> )	Accesses the voltage difference between <i>n1</i> and <i>n2</i> (nets or ports).
I( <i>b1</i> )	Accesses the current flowing in branch <i>b1</i> .
I( <i>n1</i> )	Accesses the current flowing in the unnamed branch from <i>n1</i> to ground.
I( <i>n1</i> , <i>n2</i> )	Accesses the current flowing in the unnamed branch between <i>n1</i> and <i>n2</i> .
I( <i>n1</i> , <i>n1</i> )	Error
I(< <i>p1</i> >)	Accesses the current flow into the module through port <i>p1</i> .

The argument expression list for signal access functions shall be a branch identifier, or a list of one or two nets or port expressions. If two net expressions are given as arguments to a flow access function, they shall not evaluate to the same signal. The net identifiers shall be scalar or resolve to a constant net of a composite net type (array or bus) accessed by a genvar expression.

The operands of an expression shall be unique to define a valid branch. The access function name shall match the discipline declaration for the nets, ports, or branch given in the argument expression list. In this case, `v` and `i` are used as examples of access functions for electrical potential and flow.

For port access functions, the expression list is a single port of the module. The port identifier shall be scalar or resolve to a constant net of a bus port accessed by a genvar expression. The access function name shall match the discipline declaration for the port identifier.

## 4.4 Analog operators

Analog operators operate on an expression and return a value. They are functions which operate on more than just the current value of their arguments. Instead, they maintain their internal state and their output is a function of both the input and the internal state.

Analog operators are also referred to as *filters*. They include the time derivative, time integral, and delay operators from calculus. They also include the transition and slew filters, which are used to remove discontinuity from piecewise constant and piecewise continuous waveforms. Finally, they include more traditional filters, such as those described with Laplace and Z-transform descriptions.

One special analog operator is the `limexp()` function, which is a version of the `exp()` function with built-in limits to improve convergence.

### 4.4.1 Restrictions on analog operators

Analog operators are subject to several important restrictions because they maintain their internal state.

- Analog operators shall not be used inside conditional (`if` and `case`) or looping (`for`) statements unless the conditional expression controlling the statement consists of terms which can not change their value during the course of an analysis, i.e., unless the conditional expression is a genvar expression.
- Analog operators are not allowed in the `repeat` and `while` looping statements.
- Analog operators can only be used inside an `analog` block; they can not be used inside an `initial` or `always` block, or inside a user-defined function.
- It is illegal to specify a null argument in the argument list of an analog operator, except as specified elsewhere in this document.

These restrictions help prevent usage which could cause the internal state to be corrupted or become out-of-date, which results in anomalous behavior.

#### 4.4.2 Vector or array arguments to analog operators

Certain analog operators require arrays or vectors to be passed as arguments: Laplace filters, Z-transform filters, and `noise_table`. An array can be passed as:

- *array\_identifier*
- *const\_array\_expression*

A *const\_array\_expression* allows the arrays to be passed within the argument list without explicit declaration of the array object, as shown in Syntax 4-2.

```
constant_array_expression ::=
    { constant_arrayinit_element { , constant_arrayinit_element } }

constant_arrayinit_element ::=
    constant_expression
    | integer_constant_expression { constant_expression }
```

Syntax 4-2—Syntax for constant array expression

#### 4.4.3 Analog operators and equations

Generally, simulators formulate the mathematical description of the system in terms of first-order differential equations and solve them numerically. There is no direct way to solve a set of nonlinear differential equations so iterative approaches are used. When using iterative approaches, some criteria (*tolerances*) is needed to determine when the algorithm knows when it is close enough to the solution and then stops the iteration. Thus, each equation, at a minimum, shall have a tolerance defined and associated with it.

Occasionally, analog operators require new equations and new unknowns be introduced by the simulator to convert a module description into a set of first-order differential equations. In this case, the simulator attempts to determine from context which tolerance to associate with the new equation and new unknown. Alternatively, these operators can be used to specify tolerances.

Specifying natures also directly enforces reusability and allows other signal attributes to be accessed by the simulator.

#### 4.4.4 Time derivative operator

The `ddt` operator computes the time derivative of its argument, as shown in Table 4-20.

**Table 4-20—Time derivative**

Operator	Comments
<b>ddt</b> ( <i>expr</i> )	Returns $\frac{d}{dt}x(t)$ , the time-derivative of <i>x</i> , where <i>x</i> is <i>expr</i> .
<b>ddt</b> ( <i>expr</i> , <i>abstol</i> )	Same as above, except absolute tolerance is specified explicitly.
<b>ddt</b> ( <i>expr</i> , <i>nature</i> )	Same as above, except nature is specified explicitly.

In DC analysis, **ddt**() returns zero (0). The optional parameter *abstol* is used as an absolute tolerance if needed. Whether an absolute tolerance is needed depends on the context where **ddt**() is used. See Section 4.4.3 for more information on the application of tolerances to equations. The absolute tolerance, *abstol* or derived from *nature*, applies to the output of the **ddt** operator and is the largest signal level that is considered negligible.

#### 4.4.5 Time integral operator

The **idt** operator computes the time-integral of its argument, as shown in Table 4-21.

**Table 4-21—Time integral**

Operator	Comments
<b>idt</b> ( <i>expr</i> )	Returns $\int_0^t x(\tau)d\tau$ , the time-integral of <i>x</i> from 0 to <i>t</i> with the initial condition being computed in the DC analysis. Where <i>x</i> is <i>expr</i> .
<b>idt</b> ( <i>expr</i> , <i>ic</i> )	Returns $\int_0^t x(\tau)d\tau + ic$ , the time-integral of <i>x</i> from 0 to <i>t</i> with the initial condition <i>ic</i> . In DC analysis, <i>ic</i> is returned. Where <i>x</i> is <i>expr</i> .
<b>idt</b> ( <i>expr</i> , <i>ic</i> , <i>assert</i> )	Returns $\int_{t_0}^t x(\tau)d\tau + ic$ , the time-integral of <i>x</i> from <i>t</i> <sub>0</sub> to <i>t</i> with initial condition <i>ic</i> . <i>assert</i> is a integer-valued expression. <b>idt</b> returns <i>ic</i> when <i>assert</i> is non-zero. <i>t</i> <sub>0</sub> is the time when <i>assert</i> last became 0. Where <i>x</i> is <i>expr</i> .
<b>idt</b> ( <i>expr</i> , <i>ic</i> , <i>assert</i> , <i>abstol</i> )	Same as above, except absolute tolerance is specified explicitly.
<b>idt</b> ( <i>expr</i> , <i>ic</i> , <i>assert</i> , <i>nature</i> )	Same as above, except nature is specified explicitly.

When specified with initial conditions, **idt**() returns the value of the initial condition in DC and IC analyses whenever *assert* is given and is non-zero. Without initial conditions, **idt**() multiplies its argument by infinity in DC analysis. Hence, without initial conditions, it can only be used in a system with feedback which forces its argument to zero (0).

The optional parameter *abstol* or *nature* is used to derive an absolute tolerance if needed. Whether an absolute tolerance is needed depends on the context where **idt**() is used. (See Section 4.4.3 for more information.) The absolute tolerance applies to the input of the **idt** operator and is the largest signal level that is considered negligible.

#### 4.4.6 Circular integrator operator

The **idtmod** operator, also called the *circular integrator*, converts an expression argument into its indefinitely integrated form similar to the **idt** operator, as shown in Table 4-22.

**Table 4-22—Circular integrator**

Operator	Comments
<b>idtmod</b> ( <i>expr</i> )	Returns $\int_0^t x(\tau) d\tau$ , the time-integral of <i>x</i> from 0 to <i>t</i> with the initial condition being computed in the DC analysis. Where <i>x</i> is <i>expr</i> .
<b>idtmod</b> ( <i>expr,ic</i> )	Returns $\int_0^t x(\tau) d\tau + ic$ , the time-integral of <i>x</i> from 0 to <i>t</i> with the initial condition <i>ic</i> . In DC analysis, <i>ic</i> is returned. Where <i>x</i> is <i>expr</i> .
<b>idtmod</b> ( <i>expr,ic,modulus</i> )	Returns <i>k</i> , where $0 \leq k < \text{modulus}$ and <i>k</i> is $\int_0^t x(\tau) d\tau + ic = n \times \text{modulus} + k$ , $n = \dots -3, -2, -1, 0, 1, 2, 3, \dots$ . Where <i>x</i> is <i>expr</i> .
<b>idtmod</b> ( <i>expr,ic,modulus,offset</i> )	Returns <i>k</i> , where $\text{offset} \leq k < \text{offset} + \text{modulus}$ and <i>k</i> is $\int_0^t x(\tau) d\tau + ic = n \times \text{modulus} + k$ . Where <i>x</i> is <i>expr</i> .
<b>idtmod</b> ( <i>expr,ic,modulus,offset, abstol</i> )	Same as above, except absolute tolerance is specified explicitly.
<b>idtmod</b> ( <i>expr,ic,modulus,offset, nature</i> )	Same as above, except nature is specified explicitly.

The initial condition is optional. If the initial condition is not specified, it defaults to zero (0). Regardless, the initial condition shall force the DC solution to the system.

If **idtmod()** is used in a system with feedback configuration which forces *expr* to zero (0), the initial condition can be omitted without any unexpected behavior during simulation. For example, an operational amplifier alone needs an initial condition, but the same amplifier with the right external feedback circuitry does not need a forced DC solution.

The output of the **idtmod()** function shall remain in the range

$$\text{offset} \leq \text{idtmod} < \text{offset} + \text{modulus}$$

The *modulus* shall be an expression which evaluates to a positive value. If the *modulus* is not specified, then **idtmod()** shall behave like **idt()** and not limit the output of the integrator.

The default for *offset* shall be zero (0).

The following relationship between **idt()** and **idtmod()** shall hold at all times.

*Examples:*

If

```
y = idt(expr, ic) ;
z = idtmod(expr, ic, modulus, offset) ;
```

then

```
y = n * modulus + z ;// n is an integer
```

where

```
offset ≤ z < modulus + offset
```

In this example, the circular integrator is useful in cases where the integral can get very large, such as a VCO. In a VCO we are only interested in the output values in the range  $[0, 2\pi]$ , e.g.,

```
phase = idtmod(fc + gain*V(in), 0, 1, 0);
V(OUT) <+ sin(2*`M_PI*phase);
```

Here, the circular integrator returns a value in the range  $[0, 1]$ .

#### 4.4.7 Derivative operator

**ddx()** provides access to symbolically-computed partial derivatives of expressions in the analog block. The analog simulator computes symbolic derivatives of expressions used in contribution statements in order to use Newton-Raphson iteration to solve the system of equations. In many cases in compact modeling, the values of these derivatives are useful quantities for design, such as the transconductance of a transistor (*gm*) or the capacitance of a nonlinear charge-storage element such as a varactor. The syntax for this operator is shown in Syntax 4-3.

```
ddx_call ::=
  ddx ( expression, potential_access_identifier ( net_or_port_scalar_expression ) )
  | ddx ( expression, flow_access_identifier ( branch_identifier ) )
```

Syntax 4-3—Syntax for the *random\_function*

The operator returns the partial derivative of its first argument with respect to the unknown indicated by the second argument, holding all other unknowns fixed and evaluated at the current operating point. The second argument shall be the potential of a scalar net or port or the flow through a branch, because these are the unknown variables in the system of equations for the analog solver. For the modified nodal analysis used in most SPICE-like simulators, these unknowns are the node voltages and certain branch currents.

If the expression does not depend explicitly on the unknown, then **ddx()** returns zero (0). Care must be taken when using implicit equations or indirect assignments, for which the simulator may create internal unknowns; derivatives with respect to these internal unknowns cannot be accessed with **ddx()**.

Unlike the **ddt()** operator, no tolerance is required because the partial derivative is computed symbolically and evaluated at the current operating point.

*Examples:*

This first example uses `ddx()` to obtain the conductance of the diode. The variable `gdio` is declared as an output variable (see Section 3.1.1) so that its value is available for inspection by the designer.

```

module diode(a,c);
    electrical a, c;
    inout a, c;
    parameter real IS = 1.0e-14;
    real idio;
    (*desc="small-signal conductance"*)
    real gdio;
    analog begin
        idio = IS * (limexp(V(a,c)/$vt) - 1);
        gdio = ddx(idio, V(a));
        I(a,c) <+ idio;
    end
endmodule

```

The next example adds a series resistance to the diode using an implicit equation. Note that `gdio` does not represent the total conductance because the flow access `I(a,c)` requires introduction of another unknown in the system of equations. The conductance of the diode is properly reported as `geff`, which includes the effects of `RS` and the nonlinear equation.

```

module diode(a,c);
    electrical a, c;
    inout a, c;
    parameter real IS = 1.0e-14;
    parameter real RS = 0.0;
    real idio, gdio;
    (*desc="effective conductance"*)
    real geff;
    analog begin
        idio = IS * (limexp((V(a,c)-RS*I(a,c))/ $vt) - 1);
        gdio = ddx(idio, V(a));
        geff = gdio / (RS * gdio + 1.0);
        I(a,c) <+ idio;
    end
endmodule

```

The final example implements a voltage-controlled dependent current source and is used to illustrate the computations of partial derivatives.

```

module vccs(pout,nout, pin,nin);
    electrical pout, nout, pin, nin;
    inout pout, nout, pin, nin;
    parameter real k = 1.0;
    real vin, one, minusone, zero;
    analog begin
        vin = V(pin,nin);
        one = ddx(vin, V(pin));
        minusone = ddx(vin, V(nin));
        zero = ddx(vin, V(pout));
        I(pout,nout) <+ k * vin;
    end
endmodule

```

The names of the variables indicate the values of the partial derivatives: +1, -1, or 0. A SPICE-like simulator would use these values (scaled by the parameter  $\kappa$ ) in the Newton-Raphson solution method.

#### 4.4.8 Absolute delay operator

**absdelay()** implements the absolute transport delay for continuous waveforms (use the **transition** operator to delay discrete-valued waveforms). The general form is

```
absdelay( input, td [, maxdelay ] )
```

*input* is delayed by the amount *td*. In all cases *td* shall be a positive number. If the optional *maxdelay* is specified, then *td* can vary; but it shall be an error if it becomes larger than *maxdelay*. If *maxdelay* is not specified, changes to *td* shall be ignored. If *maxdelay* is specified, changes to *td* are ignored and the initial value of *maxdelay* is used.

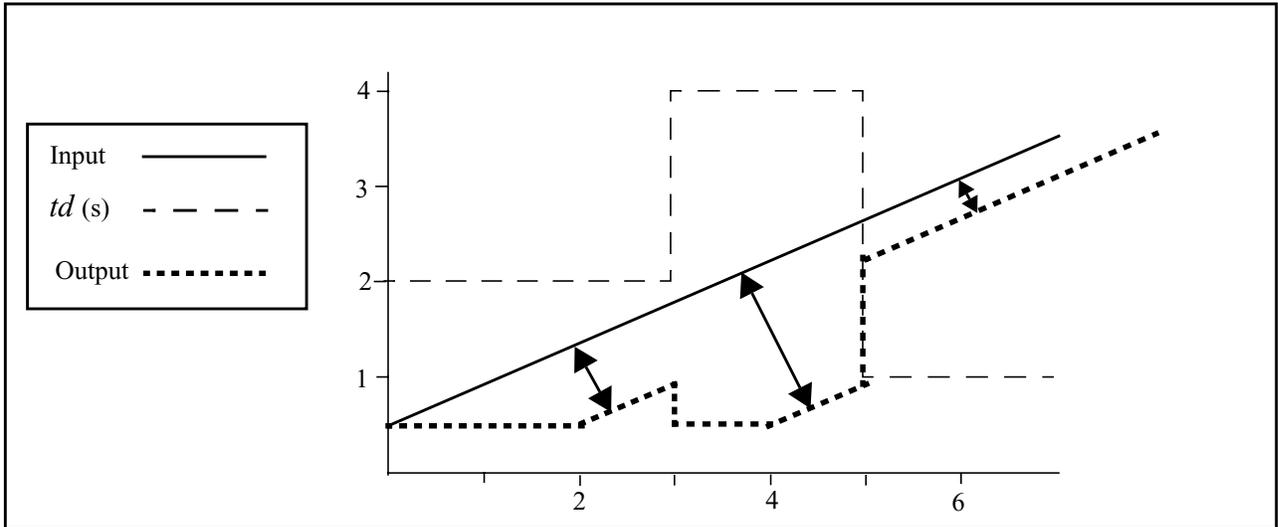
In DC and operating point analyses, **absdelay()** returns the value of its *input*. In AC and other small-signal analyses, the **absdelay** operator phase-shifts the input expression to the output of the delay operator based on the following formula.

$$Output(\omega) = Input(\omega) \cdot e^{-j\omega td}$$

*td* is evaluated as a constant at a particular time for any small signal analysis. In time-domain analyses, **absdelay()** introduces a transport delay equal to the instantaneous value of *td* based on the following formula.

$$Output(t) = Input(\max(t - td, 0))$$

The transport delay *td* can be either constant (typical case) or vary as a function of time (when *maxdelay* is defined). A time-dependent transport delay is shown in Figure 4-1, with a ramp input to the **absdelay** operator for both positive and negative changes in the transport delay *td* and a *maxdelay* of 5.

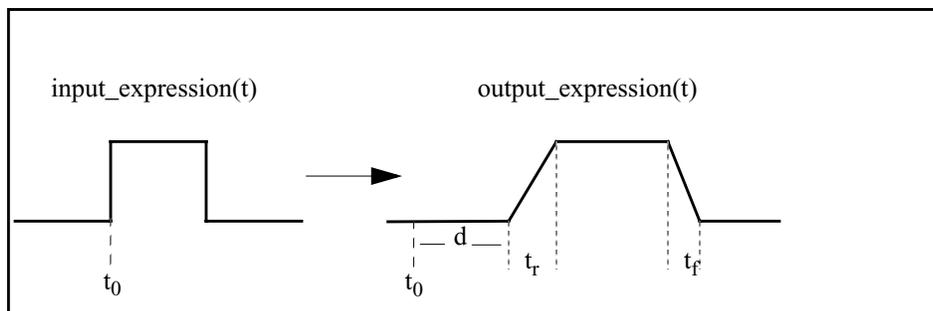


**Figure 4-1 Transport delay example**

From time 0 until 2s, the output remains at  $input(0)$ . With a delay of 2s, the output then starts tracking  $input(t - 2)$ . At 3s, the transport delay changes from 2s to 4s, switching the output back to  $input(0)$ , since  $input(\max(t-td, 0))$  returns 0. The output remains at this level until 4s when it once again starts tracking the input from  $t = 0$ . At 5s the transport delay goes to 1s and the output correspondingly jumps from its current value to the value defined by  $input(t - 1)$ .

#### 4.4.9 Transition filter

**transition()** smooths out piecewise constant waveforms. The transition filter is used to imitate transitions and delays on digital signals (for non-piecewise constant signals, see Section 4.4.10). This function provides controlled transitions between discrete signal levels by setting the rise time and fall time of signal transitions, as shown in Figure 4-2.



**Figure 4-2 Transition filter example**

**transition()** stretches instantaneous changes in signals over a finite amount of time and can delay the transitions, as shown in Figure 4-3.

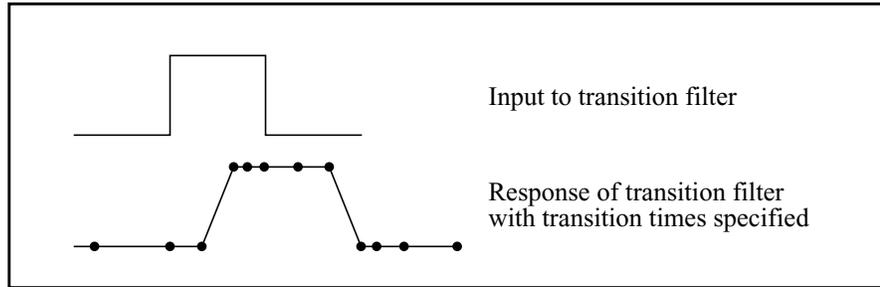


Figure 4-3 Shifting the transition filter

#### 4.4.9.1 Syntax

The general form is

```
transition( expr [ , td [ , rise_time [ , fall_time [ , time_tol ] ] ] ] )
```

**transition()** takes the following arguments (all real-valued expressions):

- the input expression
- the delay time (shall be non-negative)
- the rise time (shall be greater than or equal to 0)
- the fall time (shall be greater than or equal to 0)
- the `time_tol` (shall be positive)

The input expression is expected to evaluate over time to a piecewise constant waveform. When applied, **transition()** forces all positive transitions of *expr* to occur over *rise\_time* and all negative transitions to occur in *fall\_time* (after an initial delay of *td*). Thus, *td* models transport delay and *rise\_time* and *fall\_time* model inertial delay.

**transition()** returns a *real* number which describes a piecewise linear function over time. The transition function causes the simulator to place time-points at both corners of a transition. If *time\_tol* is not specified, the transition function causes the simulator to assure each transition is adequately resolved.

*td*, *rise\_time*, *fall\_time*, and *time\_tol* are optional. If *td* is not specified, it is taken to be zero (0.0). If only a positive *rise\_time* value is specified, the simulator uses it for both rise and fall times. If neither rise nor fall time are specified or are equal to zero (0.0), the rise and fall time default to the value defined by `\default_transition`.

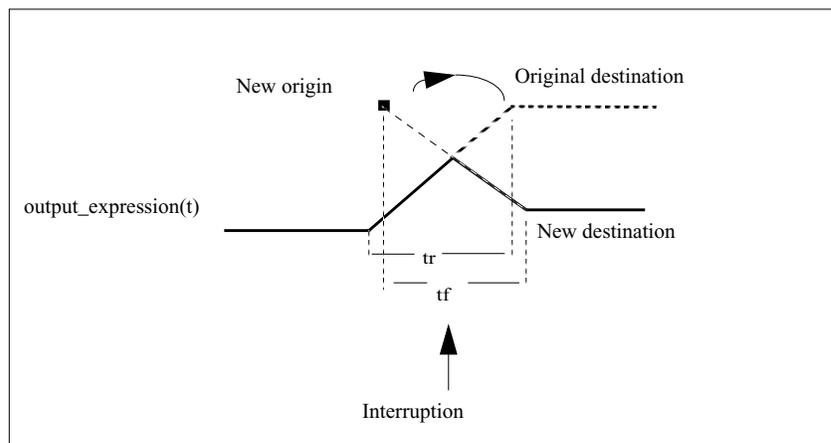
If `\default_transition` is not specified the default behavior approximates the ideal behavior of a zero-duration transition. Forcing a zero-duration transition is undesirable because it could cause convergence problems. Instead, a negligible, but non-zero, transition time is used. The small non-zero transition time allows the simulator to shrink the timestep small enough so a smooth transition occurs and any convergence problems are avoided. The simulator does not force a time point at the trailing corner of a transition

to avoid causing the simulator to take very small time steps, which would result in poor performance.

In DC analysis, `transition()` passes the value of the *expr* directly to its output. The `transition` filter is designed to smooth out piecewise constant waveforms. When applied to waveforms which vary smoothly, the simulation results are generally unsatisfactory. In addition, applying the transition function to a continuously varying waveform can cause the simulator to run slowly. Use `transition()` for discrete signals and `slew()` (see Section 4.4.10) for continuous signals.

If interrupted on a rising transition, `transition()` tries to complete the transition in the specified time.

- If the new final value level is below the value level at the point of the interruption (the current value), `transition()` uses the old destination as the origin.
- If the new destination is above the current level, the first origin is retained.



**Figure 4-4 Completing the transition**

Figure 4-4 shows a rising transition is interrupted near its midpoint and the new destination level of the value below the current value. For the new origin and destination, `transition()` computes the slope which completes the transition from the origin (not the current value) in the specified transition time. It then uses the computed slope to transition from the current value to the new destination.

With different delays, it is possible for a new transition to be specified before a previously specified transition starts. The transition function handles this by deleting any transitions which would follow a newly scheduled transition. A transition function can have an arbitrary number of transitions pending. A transition function can be used in this way to implement transport delay for discrete-valued signals.

Because the transition function can not be linearized in general, it is not possible to accurately represent a transition function in AC analysis. The AC transfer function is approximately modeled as having unity transmission for all frequencies in all situations.

Because the transition function is intended to handle discrete-valued signals, the small signals present in AC analysis rarely reach transition functions. As a result, the approximation used is generally sufficient.

#### 4.4.9.2 Examples

##### *Example 1 - QAM modulator*

In this example, the transition function is used to control the rate of change of the modulation signal in a QAM modulator.

```

module qam16(out, in) ;
parameter freq=1.0, ampl=1.0, dly=0, ttime=1.0/freq ;
input [0:4] in ;
output out ;
electrical [0:4] in;
electrical out ;
real x, y, thresh;
integer row, col ;

analog begin
  row = 2*(V(in[3]) > thresh) + (V(in[2]) > thresh) ;
  col = 2*(V(in[1]) > thresh) + (V(in[0]) > thresh) ;
  x = transition(row - 1.5, dly, ttime) ;
  y = transition(col - 1.5, dly, ttime) ;
  V(out) <+ ampl*x*cos(2*`M_PI*freq*$abstime)
    + ampl*y*sin(2*`M_PI*freq*$abstime) ;
  $bound_step(0.1/freq) ;
end
endmodule

```

##### *Example 2 - A/D converter*

In this example, an analog behavioral N-bit analog to digital converter, demonstrates the ability of the transition function to handle vectors.

```

module adc(in, clk, out) ;
parameter bits = 8, fullscale = 1.0, dly = 0, ttime = 10n ;
input in, clk ;
output [0:bits-1] out ;
electrical in, clk;
electrical [0:bits-1] out;
real sample, thresh ;
integer result[0:bits-1];
genvar i;

analog begin
  @(cross(V(clk)-2.5, +1)) begin
    sample = V(in);
    thresh = fullscale/2.0;
    for (i = bits - 1; i >= 0; i = i - 1) begin
      if (sample > thresh)

```

```

    begin
    result[i] = 1.0;
    sample = sample - thresh ;
    end else begin
    result[i] = 0.0;
    end
    sample = 2.0*sample;
end
end
for (i = 0; i < bits; i = i + 1) begin
    V(out[i]) <+ transition(result[i], dly, ttime);
end
end
endmodule

```

#### 4.4.10 Slew filter

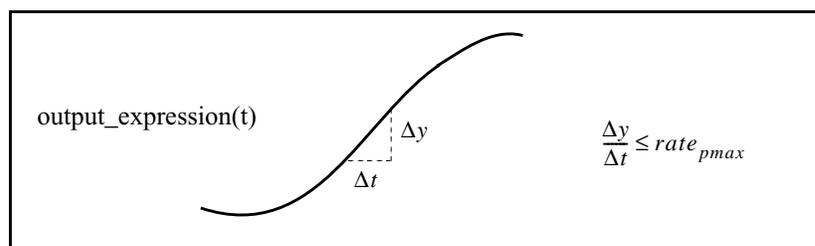
The **slew** analog operator bounds the rate of change (slope) of the waveform. A typical use for **slew()** is generating continuous signals from piecewise continuous signals. (For discrete-valued signals, see Section 4.4.9.) The general form is

```
slew( expr [ , max_pos_slew_rate [ , max_neg_slew_rate ] ] )
```

**slew()** takes the following arguments (all *real* numbers):

- the input expression
- the maximum positive slew rate
- the maximum negative slew rate

When applied, **slew()** forces all transitions of *expression* faster than *max\_pos\_slew\_rate* to change at *max\_pos\_slew\_rate* rate for positive transitions and limits negative transitions to *max\_neg\_slew\_rate* rate as shown in Figure 4-5.



**Figure 4-5 Slew filter transition**

The two rate values are optional. *max\_pos\_slew\_rate* shall be greater than zero (0) and *max\_neg\_slew\_rate* shall be less than zero (0). If the *max\_neg\_slew\_rate* is not specified, it defaults to the inverse of the *max\_pos\_slew\_rate*. If no rates are specified, **slew()** passes the signal through unchanged. If the rate of change of *expr* is less than the specified maximum slew rates, **slew()** returns the value of *expr*.

In DC analysis, `slew()` simply passes the value of the destination to its output. In AC small-signal analyses, the `slew()` function has unity transfer function except when slewing, in which case it has zero transmission through the function.

#### 4.4.11 `last_crossing` function

Related to the `cross()` function, the `last_crossing()` function returns a real value representing the simulation time when a signal expression last crossed zero (0). The general form is

```
last_crossing( expr , direction ) ;
```

The *direction* flag is interpreted in the same way as in the `cross()` function. The `last_crossing()` function is subject to the same usage restrictions as the `cross()` function.

The `last_crossing()` function does not control the timestep to get accurate results; it uses linear interpolation to estimate the time of the last crossing. However, it can be used with the `cross` function for improved accuracy.

*Examples:*

The following example measures the period of its input signal using the `cross()` and `last_crossing()` functions.

```
module period(in) ;
  input in ;
  voltage in ;
  integer crossings ;
  real latest, previous ;

  analog begin
    @(initial_step) begin
      crossings = 0 ;
      previous = 0 ;
    end

    @(cross(V(in), +1)) begin
      crossings = crossings + 1 ;
      previous = latest ;
    end
    latest = last_crossing(V(in), +1) ;

    @(final_step) begin
      if (crossings < 2)
        $strobe("Could not measure period.") ;
      else
        $strobe("period = %g, crossings = %d",
          latest-previous, crossings) ;
      end
    end
  endmodule
```

Before the expression crosses zero (0) for the first time, the `last_crossing()` function returns a negative value.

#### 4.4.12 Laplace transform filters

The Laplace transform filters implement lumped linear continuous-time filters. Each filter takes an optional parameter  $\epsilon$ , which is a real number or a nature used for deriving an absolute tolerance (if needed). Whether an absolute tolerance is needed depends on the context where the filter is used. The zeros argument may be represented as a null argument. The null argument is characterized by two adjacent commas ( , , ) in the argument list.

##### 4.4.12.1 `laplace_zp`

`laplace_zp()` implements the zero-pole form of the Laplace transform filter. The general form is

`laplace_zp( expr ,  $\zeta$  ,  $\rho$  [ ,  $\epsilon$  ] )`

where  $\zeta$  (zeta) is a vector of  $M$  pairs of real numbers. Each pair represents a zero, the first number in the pair is the real part of the zero and the second is the imaginary part. Similarly,  $\rho$  (rho) is the vector of  $N$  real pairs, one for each pole. The poles are given in the same manner as the zeros. The transfer function is

$$H(s) = \frac{\prod_{k=0}^{M-1} \left( 1 - \frac{s}{\zeta_k^r + j\zeta_k^i} \right)}{\prod_{k=0}^{N-1} \left( 1 - \frac{s}{\rho_k^r + j\rho_k^i} \right)}$$

where  $\zeta_k^r$  and  $\zeta_k^i$  are the real and imaginary parts of the  $k^{th}$  zero ( $0$ ), while  $\rho_k^r$  and  $\rho_k^i$  are the real and imaginary parts of the  $k^{th}$  pole. If a root (a pole or zero) is real, the imaginary part shall be specified as zero ( $0$ ). If a root is complex, its conjugate shall also be present. If a root is zero, then the term associated with it is implemented as  $s$ , rather than  $(1 - s/r)$  (where  $r$  is the root).

##### 4.4.12.2 `laplace_zd`

`laplace_zd()` implements the zero-denominator form of the Laplace transform filter. The general form is

`laplace_zd( expr ,  $\zeta$  ,  $d$  [ ,  $\epsilon$  ] )`

where  $\zeta$  (zeta) is a vector of  $M$  pairs of real numbers. Each pair represents a zero, the first number in the pair is the real part of the zero and the second is the imaginary part.

Similarly,  $d$  is the vector of  $N$  real numbers containing the coefficients of the denominator. The transfer function is

$$H(s) = \frac{\prod_{k=0}^{M-1} \left(1 - \frac{s}{\zeta_k^r + j\zeta_k^i}\right)}{\sum_{k=0}^{N-1} d_k s^k}$$

where  $\zeta_k^r$  and  $\zeta_k^i$  are the real and imaginary parts of the  $k^{\text{th}}$  zero, while  $d_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the denominator. If a zero is real, the imaginary part shall be specified as zero (0). If a zero is complex, its conjugate shall also be present. If a zero is zero (0), then the term associated with it is implemented as  $s$ , rather than  $(1 - s/\zeta)$ .

#### 4.4.12.3 `laplace_np`

`laplace_np()` implements the numerator-pole form of the Laplace transform filter. The general form is

`laplace_np( expr , n , ρ [ , ε ] )`

where  $n$  is a vector of  $M$  real numbers containing the coefficients of the numerator. Similarly,  $\rho$  (rho) is a vector of  $N$  pairs of real numbers. Each pair represents a pole, the first number in the pair is the real part of the pole and the second is the imaginary part. The transfer function is

$$H(s) = \frac{\sum_{k=0}^{M-1} n_k s^k}{\prod_{k=0}^{N-1} \left(1 - \frac{s}{\rho_k^r + j\rho_k^i}\right)}$$

where  $n_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the numerator, while  $\rho_k^r$  and  $\rho_k^i$  are the real and imaginary parts of the  $k^{\text{th}}$  pole. If a pole is real, the imaginary part shall be specified as zero (0). If a pole is complex, its conjugate shall also be present. If a pole is zero (0), then the term associated with it is implemented as  $s$ , rather than  $(1 - s/\rho)$ .

#### 4.4.12.4 `laplace_nd`

`laplace_nd()` implements the numerator-denominator form of the Laplace transform filter.

The general form is

`laplace_nd( expr , n , d [ , ε ] )`

where  $n$  is an vector of  $M$  real numbers containing the coefficients of the numerator and  $d$  is a vector of  $N$  real numbers containing the coefficients of the denominator. The transfer function is

$$H(s) = \frac{\sum_{k=0}^M n_k s^k}{\sum_{k=0}^N d_k s^k}$$

where  $n_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the numerator and  $d_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the denominator.

#### 4.4.12.5 Examples

`V(out) <+ laplace_zp(V(in), {-1,0}, {-1,-1,-1,1});`  
implements

$$H(s) = \frac{1+s}{\left(1+\frac{s}{1+j}\right)\left(1+\frac{s}{1-j}\right)}$$

and

`V(out) <+ laplace_nd(V(in), {0,1}, {-1,0,1});`  
implements

$$H(s) = \frac{s}{s^2-1}$$

This example

`V(out) <+ laplace_zp(white_noise(k), , {1,0,1,0,-1,0,-1,0});`  
implements a band-limited white noise source as

$$\overline{v_{out}^2} = \frac{k}{|s^2-1|^2}$$

#### 4.4.13 Z-transform filters

The *Z-transform* filters implement linear discrete-time filters. Each filter supports a parameter  $T$  which specifies the sampling period of the filter. A filter with unity transfer function acts like a simple sample-and-hold which samples every  $T$  seconds and exhibits

no delay. The zeros argument may be represented as a null argument. The null argument is characterized by two adjacent commas ( , , ) in the argument list.

All Z-transform filters share three common arguments:  $T$ ,  $\tau$ , and  $t_0$ .  $T$  specifies the period of the filter, is mandatory, and shall be positive.  $\tau$  specifies the transition time, is optional, and shall be nonnegative.

If the transition time is specified and is non-zero, the timestep is controlled to accurately resolve both the leading and trailing corner of the transition. If it is not specified, the transition time is taken to be one (1) unit of time (as defined by the ``default_transition` compiler directive) and the timestep is not controlled to resolve the trailing corner of the transition. If the transition time is specified as zero (0), then the output is abruptly discontinuous. A Z-filter with zero (0) transition time shall not be directly assigned to a branch.

Finally  $t_0$  specifies the time of the first transition, and is also optional. If not given, the first transition occurs at  $t=0$ .

#### 4.4.13.1 `zi_zp`

`zi_zp()` implements the zero-pole form of the Z-transform filter. The general form is

`zi_zp( expr ,  $\zeta$  ,  $\rho$  ,  $T$  [ ,  $\tau$  [ ,  $t_0$  ] ] )`

where  $\zeta$  (zeta) is a vector of  $M$  pairs of real numbers. Each pair represents a zero, the first number in the pair is the real part of the zero (0) and the second is the imaginary part. Similarly,  $\rho$  (rho) is the vector of  $N$  real pairs, one for each pole. The poles are given in the same manner as the zeros. The transfer function is

$$H(z) = \frac{\prod_{k=0}^{M-1} 1 - z^{-1}(\zeta_k^r + j\zeta_k^i)}{\prod_{k=0}^{N-1} 1 - z^{-1}(\rho_k^r + j\rho_k^i)}$$

where  $\zeta_k^r$  and  $\zeta_k^i$  are the real and imaginary parts of the  $k^{th}$  zero, while  $\rho_k^r$  and  $\rho_k^i$  are the real and imaginary parts of the  $k^{th}$  pole. If a root (a pole or zero) is real, the imaginary part shall be specified as zero. If a root is complex, its conjugate shall also be present. If a root is zero (0), then the term associated with it is implemented as  $z$ , rather than  $(1 - z/r)$  (where  $r$  is the root).

#### 4.4.13.2 `zi_zd`

`zi_zd()` implements the zero-denominator form of the Z-transform filter.

The form is

`zi_zd( expr ,  $\zeta$  ,  $d$  ,  $T[ , \tau[ , t_0] ]$  )`

where  $\zeta$  (zeta) is a vector of  $M$  pairs of real numbers. Each pair represents a zero, the first number in the pair is the real part of the zero and the second is the imaginary part. Similarly,  $d$  is the vector of  $N$  real numbers containing the coefficients of the denominator. The transfer function is

$$H(z) = \frac{\prod_{k=0}^{M-1} 1 - z^{-1}(\zeta_k^r + j\zeta_k^i)}{\sum_{k=0}^{N-1} d_k z^{-k}}$$

where  $\zeta_k^r$  and  $\zeta_k^i$  are the real and imaginary parts of the  $k^{th}$  zero, while  $d_k$  is the coefficient of the  $k^{th}$  power of  $s$  in the denominator. If a zero is real, the imaginary part shall be specified as zero (0). If a zero is complex, its conjugate shall also be present. If a zero is zero (0), then the term associated with it is implemented as  $z$ , rather than  $(1 - z/\zeta)$ .

#### 4.4.13.3 `zi_np`

`zi_np()` implements the numerator-pole form of the Z-transform filter. The general form is

`zi_np( expr ,  $n$  ,  $\rho$  ,  $T[ , \tau[ , t_0] ]$  )`

where  $n$  is a vector of  $M$  real numbers containing the coefficients of the numerator. Similarly,  $\rho$  (rho) is a vector of  $N$  pairs of real numbers. Each pair represents a pole, the first number in the pair is the real part of the pole and the second is the imaginary part. The transfer function is

$$H(z) = \frac{\sum_{k=0}^{M-1} n_k z^{-k}}{\prod_{k=0}^{N-1} 1 - z^{-1}(\rho_k^r + j\rho_k^i)}$$

where  $n_k$  is the coefficient of the  $k^{th}$  power of  $s$  in the numerator, while  $\rho_k^r$  and  $\rho_k^i$  are the real and imaginary parts of the  $k^{th}$  pole. If a pole is real, the imaginary part shall be specified as zero (0). If a pole is complex, its conjugate shall also be present. If a pole is zero (0), then the term associated with it is implemented as  $z$ , rather than  $(1 - z/\rho)$ .

#### 4.4.13.4 `zi_nd`

`zi_nd()` implements the numerator-denominator form of the Z-transform filter. The general form is

`zi_nd( expr , n , d , T [ , τ [ , t0 ] ] )`

where  $n$  is a vector of  $M$  real numbers containing the coefficients of the numerator and  $d$  is a vector of  $N$  real numbers containing the coefficients of the denominator. The transfer function is

$$H(z) = \frac{\sum_{k=0}^{M-1} n_k z^{-k}}{\sum_{k=0}^{N-1} d_k z^{-k}}$$

where  $n_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the numerator and  $d_k$  is the coefficient of the  $k^{\text{th}}$  power of  $s$  in the denominator.

#### 4.4.14 Limited exponential

The `limexp()` function is an operator whose internal state contains information about the argument on previous iterations. It returns a real value which is the exponential of its single real argument, however, it internally limits the change of its output from iteration to iteration in order to improve convergence. On any iteration where the change in the output of the `limexp()` function is bounded, the simulator is prevented from terminating the iteration. Thus, the simulator can only converge when the output of `limexp()` equals the exponential of the input. The general form is

`limexp ( expr )`

The apparent behavior of `limexp()` is not distinguishable from `exp()`, except using `limexp()` to model semiconductor junctions generally results in dramatically improved convergence. There are different ways of implementing limiting algorithms for the exponential<sup>1 2</sup>.

Other nonlinearities besides the exponential may be in behavioral models. The `$limit()` system function described in Section 10.9 provides a method to indicate these nonlinearities to the simulator to improve convergence.

---

1. Laurence W. Nagel, "SPICE2: A computer program to simulate semiconductor circuits," Memorandum No. ERL-M520, University of California, Berkeley, California, May 1975.

2. W. J. McCalla, *Fundamentals of Computer-Aided Circuit Simulation*. Kluwer Academic Publishers, 1988.

#### 4.4.15 Constant versus dynamic arguments

Some of the arguments to the analog operators described in this section, the events described in Section 6, and the \$limit() function in Section 10.9 expect dynamic expressions and others expect constant expressions. The dynamic expressions can be functions of circuit quantities and can change during an analysis. The constant expressions remain static throughout an analysis.

Table 4-23 summarizes the arguments of the analog operators defined in this section.

**Table 4-23—Analog operator arguments**

Operator	Constant expression arguments	Dynamic expression arguments
<b>above</b>	expr_tol, time_tol	expr
<b>ddt</b>	abstol	expr
<b>ddx</b>	wrt_what	expr
<b>idt</b>	abstol	expr, ic, assert
<b>idtmod</b>	abstol	expr, ic, modulus, offset
<b>cross</b>	expr_tol, time_tol	expr, dir
<b>last_crossing</b>		expr, dir
<b>absdelay</b>	maxdelay	expr, td
<b>transition</b>		expr, td, rise_time, fall_time
<b>slew</b>		expr, max_pos_slew_rate, max_neg_slew_rate
<b>zi_zp</b> <b>zi_zd</b> <b>zi_np</b> <b>zi_nd</b>	zeros, poles, $T$ , $t_0$	expr, $\tau$
<b>laplace_zp</b> <b>laplace_zd</b> <b>laplace_np</b> <b>laplace_nd</b>	poles, abstol, zero	expr
<b>timer</b>	time_tol	start_time, period
<b>limexp</b>		expr
<b>\$limit</b>	string, analog_function_identifier	access_function_reference, arg_list

If a dynamic expression is passed as an argument which expects a constant expression, the value of the dynamic expression at the start of the analysis defaults to the constant value of the argument. Any further change in value of that expression is ignored during the iterative analysis.

## 4.5 Analysis dependent functions

This section describes the `analysis()` function, which is used to determine what type of analysis is being performed, and the small-signal source functions. The small-signal source functions only affect the behavior of a module during small-signal analyses. The small-signal analyses provided by SPICE include the AC and noise analyses, but others are possible. When not active, the small-signal source functions return zero (0).

### 4.5.1 Analysis

The `analysis()` function takes one or more string arguments and returns one (1) if any argument matches the current analysis type. Otherwise it returns zero (0). The general form is

```
analysis( analysis_list )
```

There is no fixed set of analysis types. Each simulator can support its own set. However, simulators shall use the names listed in Table 4-24 to represent analyses which are similar to those provided by SPICE .

**Table 4-24—Analysis types**

Name	Analysis description
"ac"	.AC analysis
"dc"	.OP or .DC analysis (single point or dc sweep analysis)
"noise"	.NOISE analysis
"tran"	.TRAN analysis
"ic"	The initial-condition analysis which precedes a transient analysis.
"static"	Any equilibrium point calculation, including a DC analysis as well as those that precede another analysis, such as the DC analysis which precedes an AC or noise analysis, or the IC analysis which precedes a transient analysis.
"nodeset"	The phase during an equilibrium point calculation where nodesets are forced.

Any unsupported type names are assumed to not be a match.

Table 4-25 describes the implementation of the analysis function. Each column shows the return value of the function. A status of one (1) represents *True* and zero (0) represents *False*.

**Table 4-25—Return values for the analysis function**

Analysis	Argument	DC	Sweep <sup>a</sup>			TRAN		AC		NOISE	
			d1	d2	dN	op	Tran	op	AC	op	AC
First part of "static" when nodesets are enforced	"nodeset"	1	1	0	0	1	0	1	0	1	0
Initial DC state	"static"	1	1	1	1	1	0	1	0	1	0

**Table 4-25—Return values for the analysis function, *continued***

Analysis	Argument	DC	Sweep <sup>a</sup>			TRAN		AC		NOISE	
			d1	d2	dN	op	Tran	op	AC	op	AC
Initial condition	"ic"	0	0	0	0	1	0	0	0	0	0
DC	"dc"	1	1	1	1	0	0	0	0	0	0
Transient	"tran"	0	0	0	0	1	1	0	0	0	0
Small-signal	"ac"	0	0	0	0	0	0	1	1	0	0
Noise	"noise"	0	0	0	0	0	0	0	0	1	1

a. Sweep refers to a dc analysis in which a parameter is swept through multiple values. d1, d2 and dN above refer to dc points within the same sweep analysis.

Using the `analysis()` function, it is possible to have a module behave differently depending on which analysis is being run.

*Examples:*

To implement nodesets or initial conditions using the analysis function and switch branches, use the following.

```

if ( analysis("ic") )
    V(cap) <+ initial_value;
else
    I(cap) <+ ddt(C*V(cap));

```

## 4.5.2 DC analysis

Verilog-AMS supports a single-point dc analysis and also a multipoint dc sweep analysis in which multiple dc points are computed over a sweep of parameter values. An operating point analysis is done for each dc point in the sweep. A single-point dc analysis is the same as an operating point analysis. The `analysis("dc")` and `analysis("static")` function calls shall return true for a single-point dc analysis and also for every dc point in a sweep analysis. The `analysis("nodeset")` function call shall return true only during the phase of an operating point analysis in which nodeset values are enforced; that phase may occur in a single-point dc analysis or the first point of a multipoint dc sweep analysis, but does not occur for subsequent points of a dc sweep.

During a dc sweep analysis, the values of variables at the conclusion of the operating point analysis for one dc point shall be used as the starting values for those variables for the next dc point. However, variable values shall not be carried over between two independent dc sweep analyses (from the last dc point of one analysis to the first dc point of the next analysis). Variables shall be re-initialized to zero (or x, for integers whose values are assigned in a digital context) at the start of each new analysis.

### 4.5.3 AC stimulus

A small-signal analysis computes the steady-state response of a system which has been linearized about its operating point and is driven by a small sinusoid. The sinusoidal stimulus is provided using the `ac_stim()` function. The general form is

```
ac_stim( [analysis_name [ , mag [ , phase ] ] ] )
```

The AC stimulus function returns zero (0) during large-signal analyses (such as DC and transient) as well as on all small-signal analyses using names which do not match *analysis\_name*. The name of a small-signal analysis is implementation dependent, although the expected name (of the equivalent of a SPICE AC analysis) is "ac", which is the default value of *analysis\_name*. When the name of the small-signal analysis matches *analysis\_name*, the source becomes active and models a source with magnitude *mag* and phase *phase*. The default magnitude is one (1) and the default phase is zero (0). *phase* is given in radians.

### 4.5.4 Noise

Several functions are provided to support noise modeling during small-signal analyses. To model large-signal noise during transient analyses, use the `$random()` system task. The noise functions are often referred to as noise sources. There are three noise functions, one models white noise processes, another models  $1/f$  or flicker noise processes, and the last interpolates a vector to model a process where the spectral density of the noise varies as a piecewise linear function of frequency. The noise functions are only active in small-signal noise analyses and return zero (0) otherwise.

#### 4.5.4.1 white\_noise

White noise processes are those whose current value is completely uncorrelated with any previous or future values. This implies their spectral density does not depend on frequency. They are modeled using

```
white_noise(pwr [ , name ] )
```

which generates white noise with a power of *pwr*.

*Examples:*

The thermal noise of a resistor could be modelled using

```
I(a,b) <+ V(a,b)/R +
white_noise(4 * `P_K * $temperature/R, "thermal");
```

The optional *name* argument acts as a label for the noise source used when the simulator outputs the individual contribution of each noise source to the total output noise. The contributions of noise sources with the same *name* from the same instance of a module are combined in the noise contribution summary.

#### 4.5.4.2 flicker\_noise

The `flicker_noise()` function models flicker noise. The general form is

```
flicker_noise( pwr , exp [ , name ] )
```

which generates pink noise with a power of  $pwr$  at 1Hz which varies in proportion to  $1/f^{exp}$ .

The optional *name* argument acts as a label for the noise source used when the simulator outputs the individual contribution of each noise source to the total output noise. The contributions of noise sources with the same *name* from the same instance of a module are combined in the noise contribution summary.

#### 4.5.4.3 noise\_table

The `noise_table()` function interpolates a vector to model a process where the spectral density of the noise varies as a piecewise linear function of frequency. The general form is

```
noise_table( vector [ , name ] )
```

where *vector* contains pairs of real numbers: the first number in each pair is the frequency in Hertz and the second is the power. Noise pairs are specified in the order of ascending frequencies. `noise_table()` performs piecewise linear interpolation to compute the power spectral density generated by the function at each frequency.

The optional *name* argument acts as a label for the noise source used when the simulator outputs the individual contribution of each noise source to the total output noise. The contributions of noise sources with the same *name* from the same instance of a module are combined in the noise contribution summary.

#### 4.5.4.4 Noise model for diode

The noise of a junction diode could be modelled as shown in the following example.

```
I(a,c) <+ is*(exp(V(a,c) / (n * $vt)) - 1)
+ white_noise(2*'P_Q*I(<a>))
+ flicker_noise(kf*pow(abs(I(<a>)), af), ef);
```

#### 4.5.4.5 Correlated noise

Each noise function generates noise which is uncorrelated with the noise generated by other functions. *Perfectly correlated noise* is generated by using the output of one noise function for more than one noise source. *Partially correlated noise* is generated by combining the output of shared and unshared noise functions.

*Examples:*

Example 1 - Two noise voltages are perfectly correlated.

```
n = white_noise(pwr);
V(a,b) <+ c1*n;
V(c,d) <+ c2*n;
```

Example 2 - Partially correlated noise sources can also be modelled.

```
n1 = white_noise(1-corr);
n2 = white_noise(1-corr);
n12 = white_noise(corr);
V(a,b) <+ Kv*(n1 + n12);
I(b,c) <+ Ki*(n2 + n12);
```

## 4.6 User-defined functions

A user-defined function can be used to return a value (for an expression). All functions are defined within modules. Each function can be an analog function or a digital function (as defined in *IEEE 1364-1995 Verilog HDL*).

### 4.6.1 Defining an analog function

The syntax for defining an analog function is shown in Syntax 4-4.

```
analog_function_declaration ::=
    analog function [ type ] function_identifier ;
    function_item_declaration { function_item_declaration }
    statement
    endfunction

type ::=
    integer
    | real

function_item_declaration ::=
    input_declaration
    | inout_declaration
    | output_declaration
    | block_item_declaration

block_item_declaration ::=
    parameter_declaration
    | integer_declaration
    | real_declaration
```

Syntax 4-4—Syntax for an analog function declaration

An analog function declaration shall begin with the keywords **analog function**, optionally followed by the type of the return value from the function, then the name of the function and a semicolon, and ending with the keyword **endfunction**.

*type* specifies the return value of the function; its use is optional. *type* can be a `real` or an `integer`; if unspecified, the default is `real`.

An analog function:

- can use any statements available for conditional execution (see Section 6.1);
- shall not use access functions;
- shall not use contribution statements or event control statements;
- shall have at least one input declared; the block item declaration shall declare the type of the inputs as well as local variables used in the function; if any outputs or inouts are declared, the block item declaration shall also declare their types;
- shall not use named blocks; and
- shall only reference locally-defined variables or variables passed as arguments.

*Examples:*

The following example defines an analog function called `maxValue`, which returns the potential of whichever signal is larger.

```

analog function real maxValue;
input n1, n2 ;
real n1, n2 ;
begin
    // code to compare potential of two signal
    maxValue = (n1 > n2) ? n1 : n2 ;
end
endfunction

```

The next example defines an analog function called `geomcalc`, which returns both the area and perimeter of a rectangle.

```

analog function real geomcalc;
input l, w ;
output area, perim ;
real l, w, area, perim ;
begin
    area = l * w ;
    perim = 2 * ( l + w );
end
endfunction

```

#### 4.6.2 Returning a value from an analog function

The analog function definition implicitly declares a variable, internal to the analog function, with the same name as the analog function. This variable has the same type as the type specified in the analog function declaration. The analog function definition initializes the return value from the analog function by assigning the analog function result to the internal variable with the same name as the analog function. This variable

can be read and assigned within the flow; its last assigned value is passed back on the return call. An analog user-defined function shall always return a scalar value.

*Example:*

The following line (from the first example in Section 4.6.1) illustrates this concept:

```
maxValue = (n1 > n2) ? n1 : n2 ;
```

If the internal variable is not assigned, the function shall return zero (0). Because `geomcalc` is not assigned in the second example in Section 4.6.1, its return value is zero.

If a function computes more than one value, output or inout arguments can be used to pass these values back to the calling context. These variables can be read and assigned within the flow; the last value assigned during function evaluation is then assigned to the corresponding expression in the argument list for the function, which shall be an integer or real identifier or an element of an integer or real array.

*Example:*

The following lines (from the second example in Section 4.6.1) illustrate this concept:

```
area = l * w ;
perim = 2 * ( l + w );
```

### 4.6.3 Calling an analog function

An analog function call is an operand within an expression. Syntax 4-5 shows the analog function call.

<pre>analog_function_call ::=   function_identifier ( expression { , expression } )</pre>
---

*Syntax 4-5—Syntax for function call*

The order of evaluation of the arguments to an analog function call is undefined. The argument expressions are assigned to the declared inputs, outputs, and inouts in the order of their declaration.

An analog function:

- shall not call itself directly or indirectly, i.e., recursive functions are not permitted;
- shall only be called within an analog block; and
- can be called outside of their immediate scope.

*Examples:*

The following example uses the `maxValue` function defined in Section 4.6.1.

```
V(out) <+ maxValue(val1, val2) ;
```

The following example uses the `geomcalc` function defined in Section 4.6.1.

```
dummy = geomcalc(l-dl, w-dw, ar, per) ;
```

Note that the first two arguments are expressions, and match up with the inputs `l` and `w` for the function; the second two arguments must be real identifiers because they match up with the function outputs.



# Section 5

## Signals

### 5.1 Analog signals

Analog signals are distinguished from digital signals in that an *analog signal* has a discipline with a continuous domain. Disciplines, nets, nodes, and branches are described in Section 3 and ports are described in Section 7.

This section describes analog branch assignments, signal access mechanisms, and operators in Verilog-AMS HDL.

#### 5.1.1 Access functions

Flows and potentials on nets, ports, and branches are accessed using *access functions*. The name of the access function is taken from the discipline of the net, port, or branch associated with the signal.

*Examples:*

*Example 1*

For example, consider a named electrical branch  $b$  where *electrical* is a discipline with  $V$  as the access function for the potential and  $I$  as the access function for the flow. The potential (voltage) is accessed via  $v(b)$  and the flow (current) is accessed via  $i(b)$ .

- There can be any number of named branches between any two signals.
- Unnamed branches are accessed in a similar manner, except the access functions are applied to net names or port names rather than branch names.

*Example 2*

If  $n1$  and  $n2$  are electrical nets or ports, then  $v(n1, n2)$  creates an unnamed branch from  $n1$  to  $n2$  (if it does not already exist) and then accesses the branch potential (or the potential difference between  $n1$  to  $n2$ ), and  $v(n1)$  does the same from  $n1$  to the global reference node (*ground*).

- In other words, accessing the potential from a net or port to a net or port defines an unnamed branch. Accessing the potential on a single net or port defines an unnamed branch from that net or port to the global reference node (*ground*). There can only be one unnamed branch between any two nets.
- An analogous access method is used for flows.

*Example 3*

$I(n1, n2)$  creates an unnamed branch from  $n1$  to  $n2$  (if it does not already exist) and then accesses the branch flow, and  $I(n1)$  does the same from  $n1$  to the global reference node (*ground*).

- Thus, accessing the flow from a net or port to a net or port defines an unnamed branch. Accessing the potential on a single net or port defines an unnamed branch from that net or port to the global reference node (*ground*).
- It is also possible to access the flow passing through a port into a module. The name of the access function is derived from the flow nature of the discipline of the port. In this case, ( $\langle \rangle$ ) is used to delimit the port name rather than ( $\langle \rangle$ ).

*Example 4*

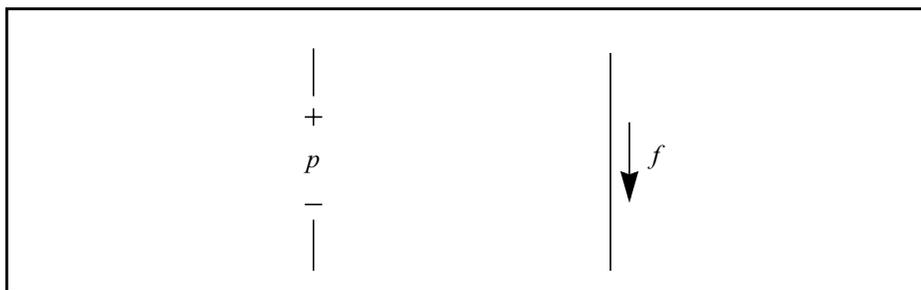
$I(\langle p1 \rangle)$  is used to access the current flow into the module through the electrical port  $p1$ . This capability is discussed further in Section 5.1.4.

## 5.1.2 Probes and sources

An analog component can be represented using a network of probes and controlled sources. The Verilog-AMS HDL uses the concept of *probes* and *sources* as a means of unambiguously representing a network. The mapping between these representations are defined in following subsections.

### 5.1.2.1 Probes

If no value is specified for either the potential or the flow, the branch is a *probe*. If the flow of the branch is used in an expression anywhere in the module, the branch is a *flow probe*, otherwise the branch is a *potential probe*. Using both the potential and the flow of a probe branch is illegal. The models for probe branches are shown in Figure 5-1.



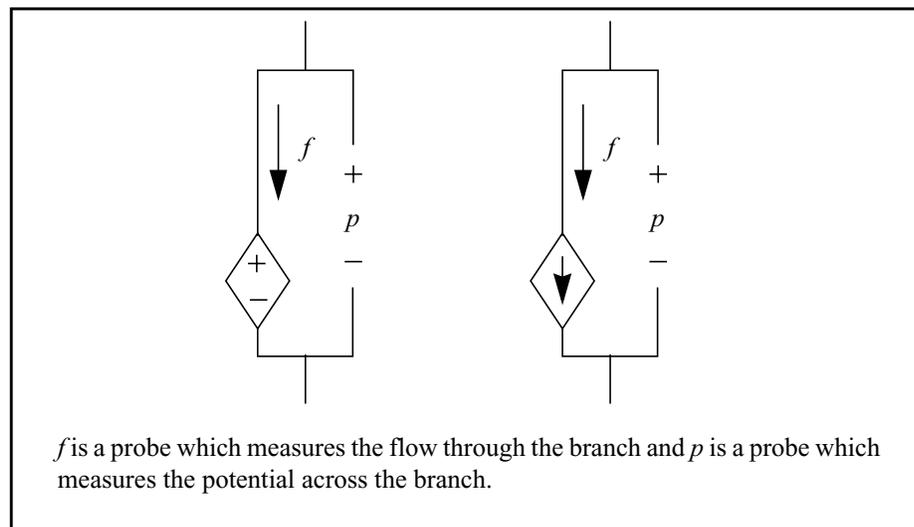
**Figure 5-1 Equivalent circuit models for probe branches**

The branch potential of a flow probe is zero (0). The branch flow of a potential probe is zero (0).

### 5.1.2.2 Sources

A branch, either named or unnamed, is a *source branch* if either the potential or the flow of that branch is assigned a value by a contribution statement (see Section 5.3) anywhere in the module. It is a *potential source* if the branch potential is specified and is a *flow source* if the branch flow is specified. A branch cannot simultaneously be both a potential and a flow source, although it can switch between them (a *switch branch*).

Both the potential and the flow of a source branch are accessible in expressions anywhere in the module. The models for potential and flow sources are shown in Figure 5-2.



**Figure 5-2** Equivalent circuit models for source branches

### 5.1.3 Examples

The following examples demonstrate how to formulate models and the correspondence between the behavioral description and the equivalent probe/source model.

#### 5.1.3.1 The four controlled sources

The following example is used with each of the four behavioral statements listed below. Each statement creates a unique controlled source when inserted into this example.

```

module control_source (p, n, ps, ns);
  electrical p, n, ps, ns;
  parameter A=1;
  branch (ps,ns) in;
  branch (p,n) out;
  analog begin
    // add behavioral statement here
  end
endmodule

```

The model for a voltage controlled voltage source is

$$V(\text{out}) \leftarrow A * V(\text{in});$$

The model for a voltage controlled current source is

$$I(\text{out}) \leftarrow A * V(\text{in});$$

The model for a current controlled voltage source is

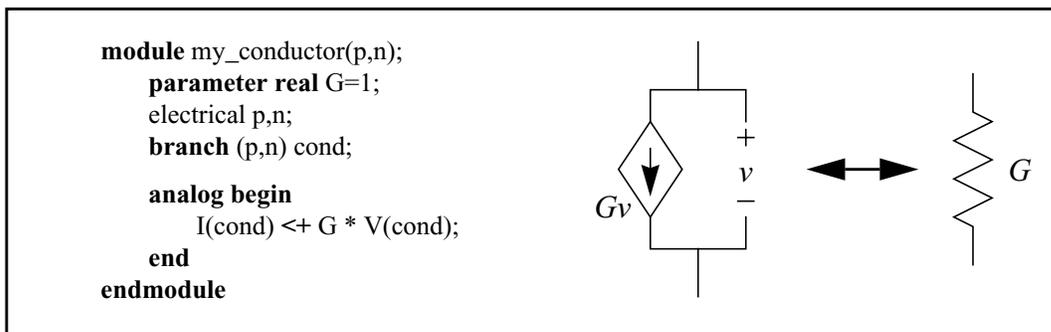
$$V(\text{out}) \leftarrow A * I(\text{in});$$

The model for a current controlled current source is

$$I(\text{out}) \leftarrow A * I(\text{in});$$

### 5.1.3.2 Resistor and conductor

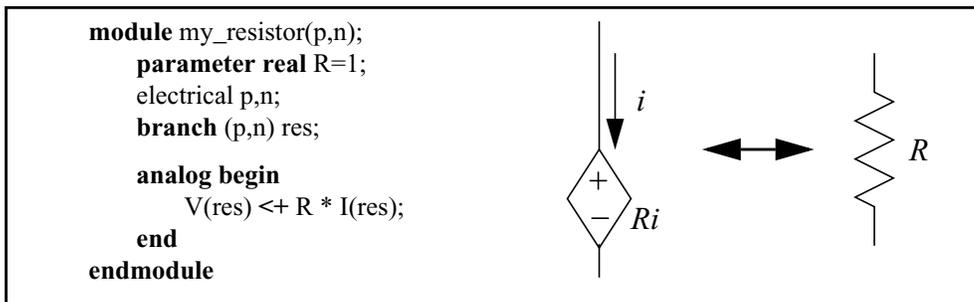
Figure 5-3 shows the model for a linear conductor.



**Figure 5-3 Linear conductor model**

The assignment to `I(cond)` makes `cond` a current source branch and `V(cond)` simply accesses the potential probe built into the current source branch.

Figure 5-4 shows the model for a linear resistor.



**Figure 5-4 Linear resistor model**

The assignment to `V(res)` makes `res` a potential source branch and `I(res)` simply accesses the optional flow probe built into the potential source branch.

### 5.1.3.3 RLC circuits

A series RLC circuit is formulated by summing the voltage across its three components,

$$v(t) = Ri(t) + L\frac{d}{dt}i(t) + \frac{1}{C}\int_{-\infty}^t i(\tau)d\tau$$

which can be defined as

$$V(p, n) <+ R*I(p, n) + L*ddt(I(p, n)) + idt(I(p, n))/C;$$

A parallel RLC circuit is formulated by summing the currents through its three components,

$$i(t) = \frac{v(t)}{R} + C\frac{d}{dt}v(t) + \frac{1}{L}\int_{-\infty}^t v(\tau)d\tau$$

which can be defined as

$$I(p, n) <+ V(p, n)/R + C*ddt(V(p, n)) + idt(V(p, n))/L;$$

### 5.1.3.4 Simple implicit diode

Verilog-AMS HDL allows components to be described with implicit equations.

*Example:*

In the following example, which is a simple diode with a series resistor, the model is implicit because the diode current  $I(a, c)$  appears on both sides of the contribution operator. The current of the diode branch is specified, making it a flow source branch. In addition, both the voltage and current of diode branch is used in the behavioral description.

$$I(a, c) <+ is*(\text{limexp}((V(a, c) - rs*I(a, c))/Svt) - 1);$$

## 5.1.4 Port branches

The port access function accesses the flow into a port of a module. The name of the access function is derived from the flow nature of the discipline of the port. However (<>) is used to delimit the port name, e.g.,  $I(<a>)$  accesses the current through module port  $a$ .

*Examples:*

Consider rewriting the *junction diode* so the total diode current is monitored and a message is issued if it exceeds a given value.

```

module diode (a, c);
  electrical a, c;
  branch (a, c) i_diode, junc_cap;
  parameter real is = 1e-14, tf = 0, cjo = 0, imax = 1, phi = 0.7 ;

```

```

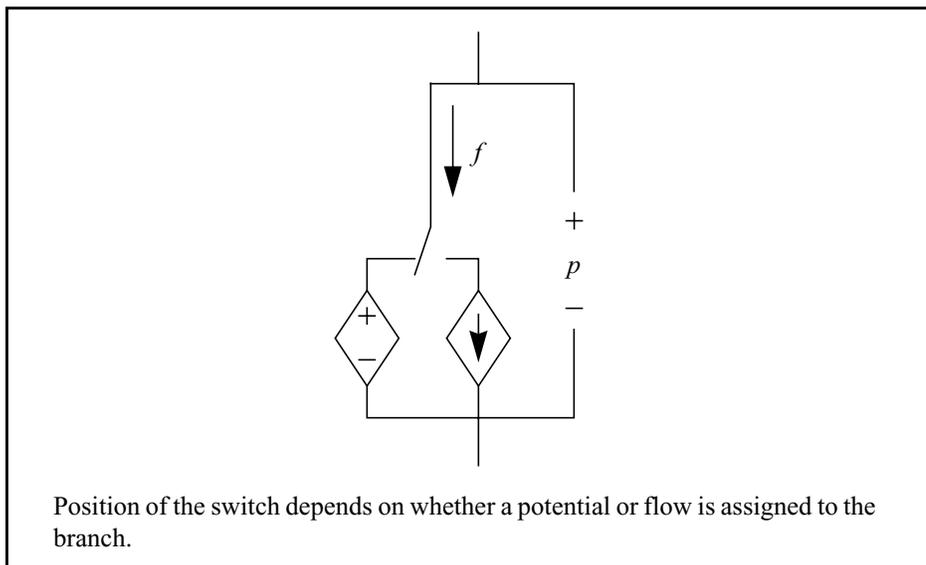
analog begin
  I(i_diode) <+ is*(limexp(V(i_diode)/$vt) - 1);
  I(junc_cap) <+
    ddt(tf*I(i_diode) - 2*cjo*sqrt(phi*(phi*V(junc_cap))));
  if (I(<a>) > imax)
    $strobe( "Warning: diode is melting!" );
end
endmodule

```

The expression  $v(\langle a \rangle)$  is invalid for ports and nets, where  $v$  is a potential access function. The port branch  $I(\langle a \rangle)$  can not be used on the left side of a contribution operator  $\langle + \rangle$ .

### 5.1.5 Switch branches

Source branches have the ability to switch between being potential and flow sources. To switch a branch to being a potential source, assign to its potential. To switch a branch to being a flow source, assign to its flow. This type of branch is useful when modeling ideal switches and mechanical stops. The full circuit model for a switched branch is shown in Figure 5-5.



**Figure 5-5 Circuit model for a switched source branch**

*Examples:*

An ideal relay (a controlled switch) can be implemented as

```

module relay (p, n, ps, ns);
electrical p, n, ps, ns;
parameter vth=0.5;
integer closed;
analog begin
    closed = (V(ps,ns) >vth ? 1 : 0);

    if (closed)
        V(p,n) <+ 0;
    else
        I(p,n) <+ 0;
end
endmodule

```

A discontinuity of order zero (0) is assumed to occur when the branch switches and so it is not necessary to use the `$discontinuity` function with switch branches.

### 5.1.6 Unassigned sources

If a value is not assigned to a branch, the branch flow is set to zero (0).

*Examples:*

```

if (closed)
    V(p,n) <+ 0;

```

is equivalent to

```

if (closed)
    V(p,n) <+ 0;
else
    I(p,n) <+ 0;

```

## 5.2 Signal access for vector branches

Verilog-AMS HDL allows ports, nets, and branches to be arranged as vectors, however, the access functions can only be applied to scalars or individual elements of a vector. The scalar element of a vector is selected with an index, e.g., `V(in[1])` accesses the voltage `in[1]`.

The index must be a genvar expression which is an expression consisting of literals and/or genvar variables. Genvar variables can only be assigned to as the iteration index of for loops; they allow signal access within looping constructs.

*Examples:*

The following examples illustrate applications of access functions to elements of an analog signal vector or bus. In the `N-bit DAC` example, the analog vector `in` is accessed within an `analog for` loop containing the genvar variable `i`. In the following `fixed-width DAC` example, literal values are used to access elements of the bus directly.

```

//
// N-bit DAC example.
//

module dac(out, in, clk);
parameter integer width = 8 from [2:24];
  parameter real fullscale = 1.0, vth = 2.5, td = 1n, tt = 1n;
  output out;
  input [0:width-1] in;
  input clk;
  electrical out;
  electrical [0:width-1] in;
  electrical clk;

  real aout;
  genvar i;

  analog begin
    @(cross(V(clk) - vth, +1)) begin
      aout = 0;
      for (i = width - 1; i >= 0; i = i - 1) begin
        if (V(in[i]) > vth) begin
          aout = aout + fullscale/pow(2, width - i);
        end
      end
    end
    V(out) <+ transition(aout, td, tt);
  end
endmodule

//
// 8-bit fixed-width DAC example.
//

module dac8(out, in, clk);
  parameter real fullscale = 1.0, vth = 2.5, td = 1n, tt = 1n;
  output out;
  input [0:7] in;
  input clk;
  electrical out;
  electrical [0:7] in;
  electrical clk;

  real aout;

  analog begin
    @(cross(V(clk) - 2.5, +1)) begin
      aout = 0;
      aout = aout + ((V(in[7]) > vth) ? fullscale/2.0 : 0.0);
      aout = aout + ((V(in[6]) > vth) ? fullscale/4.0 : 0.0);
      aout = aout + ((V(in[5]) > vth) ? fullscale/8.0 : 0.0);
      aout = aout + ((V(in[4]) > vth) ? fullscale/16.0 : 0.0);
    end
  end
endmodule

```

```

        aout = aout + ((V(in[3]) > vth) ? fullscale/32.0 : 0.0);
        aout = aout + ((V(in[2]) > vth) ? fullscale/64.0 : 0.0);
        aout = aout + ((V(in[1]) > vth) ? fullscale/128.0 : 0.0);
        aout = aout + ((V(in[0]) > vth) ? fullscale/256.0 : 0.0);
    end

    V(out) <+ transition(aout, td, tt);
end

endmodule

```

The syntax for analog signal access is shown in Syntax 5-1.

```

access_function_reference ::=
    bvalue
    | pvalue
bvalue ::=
    access_identifier ( analog_signal_list )
analog_signal_list ::=
    branch_identifier
    | array_branch_identifier [ genvar_expression ]
    | net_or_port_scalar_expression
    | net_or_port_scalar_expression , net_or_port_scalar_expression
net_or_port_scalar_expression ::=
    net_or_port_identifier
    | array_net_or_port_identifier [ genvar_expression ]
    | vector_net_or_port_identifier [ genvar_expression ]
pvalue ::=
    flow_access_identifier (< port_scalar_expression >)
port_scalar_expression ::=
    port_identifier
    | array_port_identifier [ genvar_expression ]
    | vector_port_identifier [ genvar_expression ]

```

Syntax 5-1—Syntax for scalar selection of vector signals

### 5.2.1 Accessing net and branch signals

Signals on nets and branches can be accessed only by the access functions of the discipline associated with them. The name of the net or the branch shall be specified as the argument to the access function.

*Examples:*

```

electrical out, in ;// as defined in Section 3.4.2.1
parameter real gm = 1 ;

analog
    I(out) <+ gm*V(in) ;

```

```

electrical p, n;
branch (p,n) res;
parameter real R = 50;

analog
    V(res) <+ R*I(res);

```

## 5.2.2 Accessing attributes

Attributes are attached to the nature of a potential or flow. Therefore, the attributes for a net or a branch can be accessed by using the hierarchical referencing operator (.) to the potential or flow for the net or branch.

*Examples:*

```

electrical a, b, n1, n2;
branch (n1, n2) cap ;
parameter real c= 1p;

analog begin
    I(a,b) <+ c*ddt(V(a,b), a.potential.abstol) ;
    I(cap) <+ c*ddt(V(cap), n1.potential.abstol) ;
end

```

The syntax for referencing access attributes is shown in Syntax 5-2.

```

attribute_reference ::=
    net_identifier . pot_or_flow . attribute_identifier

```

Syntax 5-2—Syntax for referencing attributes of a net

## 5.3 Contribution statements

Verilog-AMS HDL uses the *branch contribution operator* <+ to describe analog behavior. This operator is only valid within an *analog block*. Branch contribution statements are statements which use the branch contribution operators to describe behavior in terms of a mathematical mapping of input signals to output signals.

### 5.3.1 Branch contribution statements

In general, a branch contribution statement consists of two parts, a left-hand side and a right-hand side, separated by a branch contribution operator. The right-hand side can be any expression which evaluates to or can be promoted to a real value. The left-hand side specifies the source branch signal where the right-hand side shall be assigned. It shall consist of a signal access function applied to a branch.

Analog behaviors can be described using:

```

V(n1, n2) <+ expression ;

```

or

```
I(n1, n2) <+ expression ;
```

where  $(n1, n2)$  represents an unnamed source branch and  $V(n1, n2)$  refers to the potential on the branch, while  $I(n1, n2)$  refers to the flow through the branch. The expression can be linear, nonlinear, or dynamic in nature. The left-hand side can not use a port access function.

*Examples:*

The following modules model a resistor and a capacitor.

```

module resistor(p, n);
    electrical p, n;
    parameter real r = 0;

    analog
        V(p,n) <+ r*I(p, n);

endmodule

module capacitor(p, n);
    electrical p, n;
    parameter real c = 0;

    analog
        I(p,n) <+ c*ddt(V(p, n));

endmodule

```

### 5.3.1.1 Relations

Branch contribution statements implicitly define source branch relations. The branch is directed from the first net of the access function to the second net. If the second net is not specified, the global reference node (*ground*) is used as the reference net.

A branch relation is a path of the flow between two nets in a module. Each net has two quantities associated with it—the potential of the net and the flow out of the net. In electrical circuits, the potential of a net is its voltage, whereas the flow out of the net is its current. Similarly, each branch has two quantities associated with it—the potential across the branch and the flow through the branch.

*Examples:*

The following module models a simple single-ended amplifier.

```

module amp(out, in);

    input in;
    output out;
    electrical out, in;
    parameter real Gain = 1;

    analog
        V(out) <+ Gain*V(in);

endmodule

```

### 5.3.1.2 Evaluation

A statement is evaluated as follows for source branch contributions:

1. The simulator evaluates the right-hand side.
2. The simulator adds the value of the right-hand side to any previously retained value of the branch for later assignment to the branch. If there are no previously retained values, the value of the right-hand side itself is retained.
3. At the end of the simulation cycle, the simulator assigns the retained value to the source branch.

Parasitics are added to the amplifier shown in Section 5.3.1.1 by simply adding additional contribution statements to model the input admittance and output impedance.

*Examples:*

```

module amp(out, in);
  inout out, in;
  electrical out, in;
  parameter real Gain = 1, Rin = 1, Cin = 1, Rout = 1, Lout = 1;

  analog begin
    // gain of amplifier
    V(out) <+ Gain*V(in);

    // model input admittance
    I(in) <+ V(in)/Rin;
    I(in) <+ Cin*ddt(V(in));

    // model output impedance
    V(out) <+ Rout*I(out);
    V(out) <+ Lout*ddt(I(out));
  end
endmodule

```

### 5.3.1.3 Value retention

Contributing a flow to a branch which already has a value retained for the potential results in the potential being discarded and the branch being converted to a flow source. Conversely, contributing a potential to a branch which already has a value retained for the flow results in the flow being discarded and the branch being converted into a potential source. This is used to model switches. It is illegal to contribute to an external switch branch from within an analog block.

*Examples:*

```

module switch(p, n, cp, cn);
  electrical p, n, cp, cn;
  parameter real thresh = 0;

```

```

analog begin
    // stop to resolve threshold crossings
    @(cross(V(cp,cn) - thresh, 0));

    if (V(cp,cn) > thresh)
        V(p,n) <+ 0;
    else
        I(p,n) <+ 0;
    end
endmodule

```

The syntax for source contribution statement is shown in Syntax 5-3.

```

analog_branch_contribution ::=
    bvalue <+ analog_expression ;

```

Syntax 5-3—Syntax for branch contribution

### 5.3.2 Indirect branch assignments

Verilog-AMS HDL allows descriptions which implicitly specify a branch voltage or current in fixed-point form. The branch voltage or current is assigned a value by an expression which uses the branch voltage or current. This occurred in the simple implicit diode model in Section 5.1.3.4, where  $I(a, c)$  appeared on both sides of the contribution operator.

*Examples:*

Consider the model for an ideal *opamp*. In this model, the output is driven to the voltage which results in the input voltage being zero (0). The constitutive equation is

$$V(\text{in}) == 0$$

which can be formulated as

$$V(\text{out}) <+ V(\text{out}) + V(\text{in});$$

This statement defines the output of the *opamp* to be a controlled voltage source by assigning to  $V(\text{out})$  and defines the input to be high impedance by only probing the input voltage. The desired behavior results because the description is formulated in such a way it reduces to  $V(\text{in}) = 0$ . This approach does not result in the right tolerances being applied to the equation if *out* and *in* have different disciplines.

Verilog-AMS HDL includes a special syntax to use in this situation. The above branch contribution can be rewritten using an *indirect branch assignment*:

$$V(\text{out}): V(\text{in}) == 0;$$

which reads “find  $V(\text{out})$  so  $V(\text{in}) == 0$ ”.

This indicates *out* is driven with a voltage source and the source voltage needs to satisfy the given equation. Any branches referenced in the equation are only probed and not driven. In particular,  $V(\text{in})$  acts as a voltage probe.

*Examples:*

A complete description of an ideal *opamp* is:

```

module opamp(out, pin, nin);
    electrical out, pin, nin;

    analog
        V(out):V(pin,nin) == 0;

    endmodule

```

Syntax 5-4 shows the syntax for an indirect assignment statement.

```

analog_indirect_branch_assignment ::=
    bvalue : nexpr == analog_expression ;

nexpr ::=
    bvalue
    | pvalue
    | ddt ( bvalue | pvalue )
    | idt ( bvalue | pvalue )

```

Syntax 5-4—Syntax for indirect branch assignment

### 5.3.2.1 Multiple indirect assignments

For multiple indirect assignments statements, the targets frequently can be paired with any equation.

*Examples:*

The following ordinary differential equation,

$$\frac{dx}{dt} = f(x, y, z)$$

$$\frac{dy}{dt} = g(x, y, z)$$

$$\frac{dz}{dt} = h(x, y, z)$$

can be written as

```

V(x): ddt(V(x)) == f(V(x), V(y), V(z));
V(y): ddt(V(y)) == g(V(x), V(y), V(z));
V(z): ddt(V(z)) == h(V(x), V(y), V(z));

```

or

```
V(y): ddt(V(x)) == f(V(x), V(y), V(z));  
V(z): ddt(V(y)) == g(V(x), V(y), V(z));  
V(x): ddt(V(z)) == h(V(x), V(y), V(z));
```

or

```
V(z): ddt(V(x)) == f(V(x), V(y), V(z));  
V(x): ddt(V(y)) == g(V(x), V(y), V(z));  
V(y): ddt(V(z)) == h(V(x), V(y), V(z));
```

without affecting the results.

### 5.3.2.2 Indirect assignment and contribution

Indirect assignment is incompatible with contribution. Once a value is indirectly assigned to a branch, it cannot be contributed to using the branch contribution operator `<+.`

It is illegal to indirectly assign to an external branch or contribute to an external branch which has an indirect branch assignment.



# Section 6

## Analog behavior

The description of an analog behavior consists of setting up contributions (see Section 5.3) for various signals under certain procedural or timing control. This section describes an analog procedural block, procedural control statements, and analog timing control functions.

### 6.1 Analog procedural block

Discrete time behavioral definitions within *IEEE 1364-1995 Verilog HDL* are encapsulated within the **initial** and **always** procedural blocks. Every **initial** and **always** block starts a separate concurrent activity flow. For continuous time simulation, the behavioral description is encapsulated within the analog procedural block. Verilog-AMS HDL allows one analog procedural block in a module definition.

The analog procedural block defines the behavior as a procedural sequence of statements. The conditional and looping constructs are available for defining behaviors within the analog procedural block. Because the description is a continuous-time behavioral description, no blocking event control statements (such as blocking delays, events, or waits) are supported.

The statements allowed within the analog block are separated into two categories, *analog\_statements* and *(non analog) statements*. The *analog\_statements* are restricted to the analog block whereas the *(non analog) statements* can appear anywhere within the module scope, including an analog block. The distinction is based upon the visibility and usage of these behavioral constructs within a Verilog-AMS HDL module definition.

The syntax for analog block is shown in Syntax 6-1.

```

analog_block ::=
    analog analog_statement ;

analog_statement ::=
    analog_seq_block
    | analog_branch_contribution
    | analog_indirect_branch_assignment
    | analog_procedural_assignment
    | analog_conditional_statement
    | analog_for_statement
    | analog_case_statement
    | analog_event_controlled_statement
    | system_task_enable
    | statement

statement ::=
    seq_block
    | procedural_assignment
    | conditional_statement
    | loop_statement
    | case_statement

```

Syntax 6-1—Syntax for analog procedural block

The statements within the analog block are used to define the continuous-time behavior of the module. The behavioral description is a mathematical mapping of input signals to output signals. The mapping is done with contribution statements using the form

```
signal <+ analog_expression ;
```

or by an indirect branch assignment. The *analog\_expression* can be any combination of linear, nonlinear, or differential expressions of module signals, constants, and parameters (see Section 5).

All analog blocks contained in various modules in a design are considered to be executing concurrent with respect to each other.

## 6.2 Block statements

The *block statements*, also referred to as *sequential blocks*, are a means of grouping two or more statements together so they act syntactically like a single statement. The block statements are delimited by the keywords **begin** and **end**. The procedural statements in a block statement are executed sequentially in the given order.

### 6.2.1 Sequential blocks

The syntax for sequential blocks is shown in Syntax 6-2.

```
seq_block ::=
    begin [ : block_identifier { block_item_declaration } ]
        { statement }
    end

analog_seq_block ::=
    begin [ : block_identifier { block_item_declaration } ]
        { analog_statement }
    end

block_item_declaration ::=
    parameter_declaration
    | integer_declaration
    | real_declaration
```

Syntax 6-2—Syntax for the sequential blocks

An *analog\_seq\_block* is a *seq\_block* which encapsulates one or more *analog\_statements*.

### 6.2.2 Block names

A sequential block can be named by adding a *block\_identifier* after the keyword **begin**. The naming of a block allows local variables to be declared for that block.

All local variables are static—that is, a unique location exists for all variables and leaving or entering blocks do not affect the values stored in them.

The block names give a means of uniquely identifying all variables at any simulation time.

## 6.3 Procedural assignments

In Verilog-AMS HDL, branch contributions and indirect branch assignments are used for modifying signals. Procedural assignments are used for modifying integer and real variables. The syntax for procedural assignments shown in Syntax 6-3.

```

procedural_assignment ::=
    lexpr = expression ;

analog_procedural_assignment ::=
    lexpr = analog_expression ;

lexpr ::=
    integer_identifier
    | real_identifier
    | array_element

array_element ::=
    integer_identifier [ expression ]
    | real_identifier [ expression ]

```

Syntax 6-3—Syntax for procedural assignments

The left-hand side of a procedural assignment shall be an integer or real identifier or an element of an integer or real array. The right-hand side expression can be any arbitrary expression constituted from legal operands and operators as described in Section 4.

An *analog\_procedural\_assignment* is defined as a procedural assignment whose right-hand side *expression* is an *analog\_expression* involving analog operators.

## 6.4 Conditional statement

The *conditional statement* (*if-else* statement) is used to determine whether a statement is executed or not. The syntax of a conditional statement is shown in Syntax 6-4.

```

conditional_statement ::=
    if ( expression ) true_statement_or_null
    [ else false_statement_or_null ]

```

Syntax 6-4—Syntax of conditional statement

If the expression evaluates to *True* (that is, has a non-zero value), the *true\_statement* shall be executed. If it evaluates to *False* (has a zero value (0)), the *true\_statement* shall not be executed. If there is an *else false\_statement* and expression is *False*, the *false\_statement* shall be executed.

Since the numeric value of the *if* expression is tested for being zero (0), certain shortcuts are possible (see Section 4.1).

### 6.4.1 Examples

For example, the following two statements express the same logic:

```

    if (expression)
    if (expression != 0)

```

Because the *else* part of an *if-else* is optional, there can be confusion when an *else* is omitted from a nested *if()* sequence. This is resolved by always associating the *else* with the closest previous *if()* which lacks an *else*.

In the example below, the *else* goes with the inner *if()*, as shown by indentation.

```

if(index > 0)
  if (i > j)
    result = i;
  else // else applies to preceding if
    result = j;

```

If that association is not desired, a *begin-end* shall be used to force the proper association, as shown below.

```

if (index > 0) begin
  if (i > j)
    result = i;
end
else result = j;

```

Nesting of *if* statements (known as an *if-else-if* construct) is the most general way of writing a multi-way decision. The expressions are evaluated in order; if any expression is *True*, the statement associated with it shall be executed and this action shall terminate the whole chain. Each statement is either a single statement or a sequential block of statements.

## 6.4.2 Analog conditional statements

Analog conditional statements are syntactically equivalent to conditional statements except the *True* and/or *False* statement are *analog\_statements*, as shown in Syntax 6-5. The conditional expression shall be a *genvar\_expression*. (See the discussion in Section 4.4.1 regarding restrictions on the usage of analog operators.)

```

analog_conditional_statement ::=
  if ( genvar_expression ) true_analog_statement_or_null
  [ else false_analog_statement_or_null ]

```

Syntax 6-5—Syntax of analog conditional statement

## 6.5 Case statement

The *case statement* is a multi-way decision statement which tests if an expression matches one of a number of other expressions, and if so, branches accordingly. The case statement has the syntax shown in Syntax 6-6.

```

case_statement ::=
    case ( expression ) case_item { case_item } endcase
    | casex ( expression ) case_item { case_item } endcase
    | casez ( expression ) case_item { case_item } endcase
case_item ::=
    expression { , expression } : statement_or_null
    | default [ : ] statement_or_null

```

Syntax 6-6—Syntax for case statement

The *default-statement* is optional. Use of multiple default statements in one case statement is illegal.

The *case-expression* and the *case\_item* expression can be computed at runtime; neither expression is required to be a constant expression.

The *case\_item* expressions are evaluated and compared in the exact order in which they are given. During this linear search, if one of the *case\_item* expressions matches the *case-expression* given in parentheses, then the statement associated with that *case\_item* is executed. If all comparisons fail, and the default item is given, then the default item statement is executed; otherwise none of the *case\_item* statements are executed.

The **casex** and the **casez** versions of the *case* statement are described in Section 8.3.2 and *IEEE 1364-1995 Verilog HDL*.

### 6.5.1 Analog case statements

Analog case statements are syntactically equivalent to case statements except the case item statements can also be *analog\_statements*, as shown in Syntax 6-7. The conditional expression shall be a *genvar* expression. See the discussion in Section 4.4.1 regarding restrictions on the usage of analog operators.

```

analog_case_statement ::=
    case ( genvar_expression ) analog_case_item { analog_case_item } endcase
    | casex ( genvar_expression ) analog_case_item { analog_case_item } endcase
    | casez ( genvar_expression ) analog_case_item { analog_case_item } endcase
analog_case_item ::=
    genvar_expression { , genvar_expression } : analog_statement_or_null
    | default [ : ] analog_statement_or_null

```

Syntax 6-7—Syntax for analog case statement

The **casex** and the **casez** versions of the case statement are described in Section 8.3.2 and *IEEE 1364-1995 Verilog HDL*.

## 6.5.2 Constant expression in case statement

A *constant* expression can be used for a *case* expression. The value of the *constant* expression shall be compared against *case\_item* expressions.

*Examples:*

The following example demonstrates the usage by modeling a 3-bit priority encoder.

```
integer encode [2:0];

case (1)
  encode[2] : $display("Select Line 2") ;
  encode[1] : $display("Select Line 1") ;
  encode[0] : $display("Select Line 0") ;
  default $strobe("Error: One of the bits expected ON");
endcase
```

The *case* expression here is a *constant* expression (1). The *case\_items* are expressions (array elements) and are compared against the constant expression for a match.

## 6.6 Looping statements

There are several types of looping statements: **repeat()**, **while()**, and **for()**. These statements provide a means of controlling the execution of a statement zero (0), one (1), or more times.

The **for()** looping statements can be used to describe analog behaviors using analog operators.

Analog operators are not allowed in the **repeat()**, **while()**, and **for()** looping statements. They are allowed in *analog\_for* and *generate* statements.

### 6.6.1 Repeat and while statements

**repeat()** executes a statement a fixed number of times. Evaluation of the expression decides how many times a statement is executed.

**while()** executes a statement until an expression becomes *False*. If the expression starts out *False*, the statement is not executed at all.

The *repeat* and *while* expressions shall be evaluated once before the execution of any statement in order to determine the number of times, if any, the statements are executed. The syntax for **repeat()** and **while()** statements is shown in Syntax 6-8.

```
repeat_statement ::=
    repeat ( expression ) statement

while_statement ::=
    while ( expression ) statement
```

Syntax 6-8—Syntax for repeat and while statements

## 6.6.2 For statements

The **for()** statement is a looping construct which controls execution of its associated statement(s) using an index variable. If the associated statement is an *analog\_statement*, then the control mechanism shall consist of *genvar\_assignments* and *genvar\_expressions* to adhere to the restrictions associated with the use of analog operators. If the associated statements are not *analog\_statements*, the **for()** statement can use procedural assignments and expressions, including *genvar\_expressions*.

The **for()** statement controls execution of its associated statement(s) by a three-step process:

1. it executes an assignment normally used to initialize an integer which controls the number of loops executed.
2. it evaluates an expression—if the result is zero (0), the *for-loop* exits; otherwise, the *for-loop* executes its associated statement(s) and then performs Step 3.
3. it executes an assignment normally used to modify the value of the loop-control variable and repeats Step 2.

Syntax 6-9 shows the syntax for the two forms of the **for()** statements.

```
for_statement ::=
    for ( procedural_assignment ; expression ;
          procedural_assignment ) statement

analog_for_statement ::=
    for ( genvar_assignment ; genvar_expression ;
          genvar_assignment ) analog_statement
```

Syntax 6-9—Syntax for the for statements

*analog\_for* statements are syntactically equivalent to **for()** statements except the associated statement is also an analog statement (which contains analog operations). The analog statement puts the additional restriction upon the procedural assignment and conditional expressions of the *for-loop* to be statically evaluable. Verilog-AMS HDL provides *genvar*-derived expressions for this purpose.

*Examples:*

```

module genvarexp(out, dt);
  parameter integer width = 1;
  output out;
  input dt[1:width];
  electrical out;
  electrical dt[1:width];
  genvar k;
  real tmp;

  analog begin
    tmp = 0.0;
    for (k = 1; k <= width; k = k + 1) begin
      tmp = tmp + V(dt[k]);
      V(out) <+ ddt(V(dt[k]));
    end
  end
endmodule

```

See the discussion in Section 4.4.1 regarding other restrictions on the usage of analog operators.

## 6.7 Events

The analog behavior of a component can be controlled using *events*. *events* have the following characteristics:

- events have no time duration
- events can be triggered and detected in different parts of the behavioral model
- events do not block the execution of an analog block
- events can be detected using the @ operator
- events do not hold any data
- there can be both digital and analog events

There are two types of analog events, *global events* (Section 6.7.4) and *monitored events* (Section 6.7.5). Null arguments are not allowed in analog events.

### 6.7.1 Event detection

Analog event detection consist of an event expression followed by a procedural statement, as shown in Syntax 6-10.

```

event_control_statement ::=
    event_control statement_or_null

event_control ::=
    @ event_identifier
    | @ ( event_expression )

analog_event_expression ::=
    global_event
    | event_function
    | digital_expression
    | event_identifier
    | posedge digital_expression
    | negedge digital_expression
    | event_expression or event_expression

digital_event_expression ::=
    digital_expression
    | event_identifier
    | posedge digital_expression
    | negedge digital_expression
    | event_function
    | digital_event_expression or digital_event_expression

```

Syntax 6-10—Syntax for event detection

The procedural statement following the event expression is executed whenever the event described by the expression changes. The analog event detection is non-blocking, meaning the execution of the procedural statement is skipped unless the analog event has occurred. The event expression consists of one or more signal names, global events, or monitored events separated by the **or** operator.

The parenthesis around the event expression are required.

### 6.7.2 Event OR operator

The “OR-ing” of events indicates the occurrence of any one of the events specified shall trigger the execution of the procedural statement following the event. The keyword **or** is used as an event OR operator.

*Examples:*

```

analog begin
    @(initial_step or cross(V(smpl)-2.5,+1)) begin
        vout = (V(in) > 2.5);
    end
    V(out) <+ vout;
end

```

Here, **initial\_step** is a global event and **cross()** returns a monitored event. The variable `vout` is set to zero (0) or one (1) whenever either event occurs.

### 6.7.3 Event triggered statements

The following two restrictions apply to statements which are evaluated as a result of an event being triggered.

- The statement can not have expressions which use analog operators. This statement can not maintain its internal state since it is only executed intermittently when the corresponding event is triggered.
- The statement can not be a contribution statement because it can generate discontinuity in analog signals.

### 6.7.4 Global events

Global events are generated by a simulator at various stages of simulation. The user model can not generate these events. These events are detected by using the name of the global event in an event expression with the @ operator.

Global events are pre-defined in Verilog-AMS HDL. These events can not be redefined in a model.

The pre-defined global events are shown in Syntax 6-11.

```
global_event ::=
    initial_step [ ( analysis_list ) ]
    | final_step [ ( analysis_list ) ]

analysis_list ::=
    analysis_name { , analysis_name }

analysis_name ::=
    " analysis_identifier "
```

Syntax 6-11—Global events

**initial\_step** and **final\_step** generate global events on the first and the last point in an analysis respectively. They are useful when performing actions which should only occur at the beginning or the end of an analysis. Both global events can take an optional argument, consisting of an analysis list for the active global event.

*Examples:*

For example,

```
@(initial_step("ac", "dc")) // active for dc and ac only
@(initial_step("tran")) // active for transient only
```

Table 6-1 describes the return value of **initial\_step** and **final\_step** for standard analysis types. Each column shows the return-on-event status. One (1) represents *Yes* and zero (0) represents *No*. A Verilog-AMS HDL simulator can use any or all of these

typical analysis types. Additional analysis names can also be used as necessary for specific implementations. (See Section 4.5.1 for further details.)

**Table 6-1—Return Values for `initial_step` and `final_step`**

Analysis <sup>a</sup>	DCOP	Sweep <sup>b</sup>			TRAN			AC			NOISE		
	OP	d1	d2	dN	OP	p1	pN	OP	p1	pN	OP	p1	pN
<code>initial_step</code>	1	1	0	0	1	0	0	1	0	0	1	0	0
<code>initial_step("ac")</code>	0	0	0	0	0	0	0	1	0	0	0	0	0
<code>initial_step("noise")</code>	0	0	0	0	0	0	0	0	0	0	1	0	0
<code>initial_step("tran")</code>	0	0	0	0	1	0	0	0	0	0	0	0	0
<code>initial_step("dc")</code>	1	1	0	0	0	0	0	0	0	0	0	0	0
<code>initial_step(unknown)</code>	0	0	0	0	0	0	0	0	0	0	0	0	0
<code>final_step</code>	1	0	0	1	0	0	1	0	0	1	0	0	1
<code>final_step("ac")</code>	0	0	0	0	0	0	0	0	0	1	0	0	0
<code>final_step("noise")</code>	0	0	0	0	0	0	0	0	0	0	0	0	1
<code>final_step("tran")</code>	0	0	0	1	0	0	1	0	0	0	0	0	0
<code>final_step("dc")</code>	1	0	0	1	0	0	0	0	0	0	0	0	0
<code>final_step(unknown)</code>	0	0	0	0	0	0	0	0	0	0	0	0	0

- a.  $pX$  Table 6-1 designates frequency/time analysis point  $X$ ,  $X = 1$  to  $N$ ;  $OP$  designates the Operating Point.
- b. Sweep refers to a dc analysis in which a parameter is swept through multiple values and an operating point analysis is performed for each value. d1 refers to the first point in the sweep; d2 through dN are subsequent points.

*Examples:*

The following example measures the bit-error rate of a signal and prints the result at the end of the simulation.

```

module bitErrorRate (in, ref) ;
  input in, ref ;
  electrical in, ref ;
  parameter real period=1, thresh=0.5 ;
  integer bits, errors ;

  analog begin
    @(initial_step) begin
      bits = 0 ;
      errors = 0 ;
    end
  end

```

```

@(timer(0, period)) begin
  if ((V(in) > thresh) != (V(ref) > thresh))
    errors = errors + 1 ;
    bits = bits + 1 ;
  end

@(final_step)
  $strobe("bit error rate = %f%%", 100.0 * errors / bits ) ;
end
endmodule

```

**initial\_step** and **final\_step** take a list of quoted strings as optional arguments. The strings are compared to the name of the analysis being run. If any string matches the name of the current analysis name, the simulator generates an event on the first point and the last point of that particular analysis, respectively.

If no analysis list is specified, the **initial\_step** global event is active during the solution of the first point (or initial DC analysis) of every analysis. The **final\_step** global event, without an analysis list, is only active during the solution of the last point of every analyses.

## 6.7.5 Monitored events

Monitored events are detected using event functions (see Syntax 6-12) with the **@** operator. The triggering of a monitored event is implicit due to change in signals, simulation time, or other runtime conditions.

```

event_function ::=
  cross_function
  | above_function
  | timer_function

```

Syntax 6-12—Monitored events

### 6.7.5.1 cross function

The **cross()** function is used for generating a monitored analog event to detect threshold crossings in analog signals when the expression crosses zero (0) in the specified direction. In addition, **cross()** controls the timestep to accurately resolve the crossing.

The general form is

```

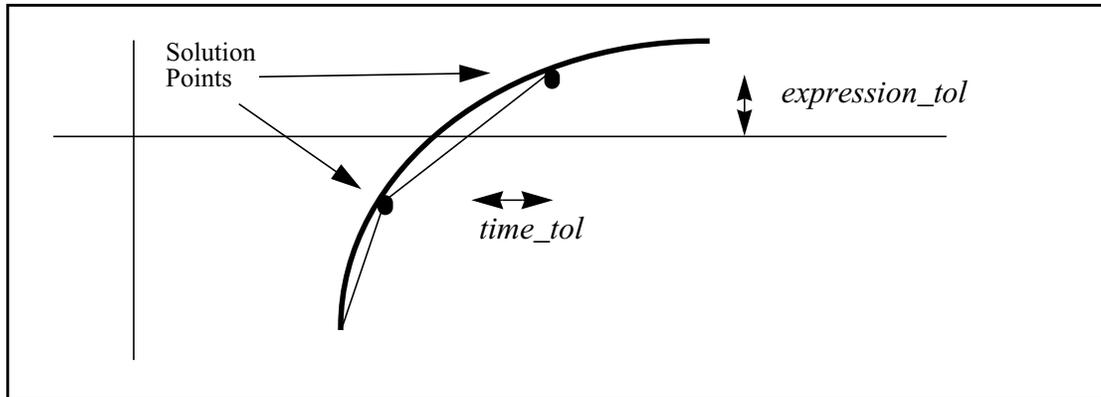
cross( expr [ , dir [ , time_tol [ , expr_tol ] ] ] );

```

where *expr* is required, and *dir*, *time\_tol*, and *expr\_tol* are optional. All arguments are real expressions, except *dir* (which is an integer expression). If the tolerances are not defined, then the tool (e.g., the simulator) sets them. If either or both tolerances are defined, then the direction shall also be defined.

The direction indicator can only evaluate to +1, -1, or 0. If it is set to 0 or is not specified, the event and timestep control occur on both positive and negative crossings of the signal. If *dir* is +1 (or -1), the event and timestep control only occur on rising edge (falling edge) transitions of the signal. For any other transitions of the signal, the `cross()` function does not generate an event.

*expr\_tol* and *time\_tol* are defined as shown in Figure 6-1. They represent the maximum allowable error between the estimated crossing point and the true crossing point.



**Figure 6-1 Relationship between time tolerance and expression tolerance**

If *expr\_tol* is defined, *time\_tol* shall also be defined and both tolerances shall be satisfied at the crossing.

*Example:*

The following description of a sample-and-hold illustrates how the `cross()` function can be used.

```

module sh (in, out, smpl) ;
  output out ;
  input in, smpl ;
  electrical in, out, smpl ;
  real state ;

  analog begin
    @(cross(V(smpl) - 2.5, +1))
      state = V(in) ;
    V(out) <+ transition(state, 0, 10n) ;
  end
endmodule

```

The `cross()` function maintains its internal state and has the same restrictions as analog operators. In particular, it shall not be used inside an `if()`, `case()`, `casex()`, or `casez()` statement unless the conditional expression is a genvar expression. In addition, `cross()` is not allowed in the `repeat()` and `while()` iteration statements. It is allowed in the `analog_for` statements.

### 6.7.5.2 above function

The `above()` function is almost identical to the `cross()` function, except that it also triggers during initialization or dc analysis. It generates a monitored analog event to detect threshold crossings in analog signals when the expression crosses zero (0) from below. As with the `cross()` function, `above()` controls the timestep to accurately resolve the crossing during transient analysis.

The general form is

```
above ( expr [ , time_tol [ , expr_tol ] ] );
```

where *expr* is required, and *time\_tol* and *expr\_tol* are optional. All arguments are real expressions. If the tolerances are not defined, then the tool (e.g., the simulator) sets them.

The `above()` function can generate an event during initialization. If the expression is positive at the conclusion of the initial condition analysis that precedes a transient analysis, the `above()` function shall generate an event. In contrast, the `cross()` function can only generate an event after the simulation time has advanced from zero. The `cross()` function will not generate events for non-transient analyses, such as ac, dc, or noise analyses of SPICE (see Section 4.5.1), but the `above()` function can. During a dc sweep, the `above()` function shall also generate an event when the expression crosses zero from below; however, the step size of the dc sweep is not controlled to accurately resolve the crossing.

*Example:*

The following example uses the `above()` function in place of the `cross()` function in the description of a sample-and-hold module introduced in the previous section. If the voltage on the `smp1` port is above 2.5V initially (at `time=0`), then use of the `above()` function ensures that the input is sampled and passed to the output when solving for the initial state of the circuit. If the voltage on the `smp1` port never crosses 2.5V in the positive direction, then the `cross()` function of the previous example would never trigger, even if the voltage on the `smp1` port is always above 2.5V.

```
module sh (in, out, smp1) ;
  output out ;
  input in, smp1 ;
  electrical in, out, smp1 ;
  real state ;

  analog begin
    @(above(V(smp1) - 2.5))
      state = V(in) ;
    V(out) <+ transition(state, 0, 10n) ;
  end
endmodule
```

The `above()` function maintains its internal state and has the same restrictions on its use as the `cross()` function.

### 6.7.5.3 timer function

The `timer()` function is used to generate analog events to detect specific points in time.

The general form is

```
timer( start_time [ , period [ , time_tol ] ] );
```

where *start\_time* is required; *period* and *time\_tol* are optional arguments. All arguments are real expressions.

The `timer()` function schedules an event which occurs at an absolute time (*start\_time*). The analog simulator places a time point within *timetol* of an event. At that time point, the event evaluates to *True*.

If *time\_tol* is not specified, the default time point is at, or just beyond, the time of the event. If the *period* is specified as greater than zero (0), the timer function schedules subsequent events at multiples of *period*.

*Example:*

A pseudo-random bit stream generator is an example how the timer function can be used.

```
module bitStream (out) ;
  output out ;
  electrical out ;
  parameter period = 1.0 ;
  integer x ;

  analog begin
    @(timer(0, period))
      x = $random + 0.5 ;
      V(out) <+ transition( x, 0.0, period/100.0 ) ;
  end
endmodule
```

## Section 7

# Hierarchical structures

Verilog-AMS HDL supports a hierarchical hardware description by allowing modules to be embedded within other modules. Higher-level modules create instances of lower-level modules and communicate with them through input, output, and bidirectional ports.

Verilog-AMS HDL provides a mechanism to customize the behavior of embedded modules using parameters. The embedded module parameter default value can be modified through a higher-level module's parameter override or a hierarchy independent `defparam` statement.

To describe a hierarchy of modules, the user provides textual definitions of various modules. Each module definition stands alone; the definitions are not nested. Statements within the module definitions create instances of other modules, thus describing the hierarchy.

### 7.1 Modules

A module definition is enclosed between the keywords **module** and **endmodule**, as shown in Syntax 7-1. The identifier following the keyword **module** is the name of the module being defined. The optional list of ports specify an ordered list of the module's ports. The order used can be significant when instantiating the module (see Section 7.1.2). The identifiers in this list shall be declared in `input`, `output`, or `inout` declaration statements within the module definition. The module items define what constitutes a module and include many different types of declarations and definitions. A module definition can have at most one analog block.

A module can have a description attribute, which shall be used by the simulator when generating help messages for the module.

The keyword **macromodule** can be used interchangeably with the keyword **module** to define a module. An implementation can choose to treat module definitions beginning with the **macromodule** keyword differently.

```

module_declaration ::=
    {attribute_instance} module_keyword module_identifier [ digital_list_of_ports ] ;
    [ module_items ]
    endmodule

module_keyword ::=
    module
    | macromodule

list_of_ports ::=
    ( port { , port } )

port ::=
    port_expression
    | .port_identifier ( [ port_expression ] )

port_expression ::=
    port_identifier
    | port_identifier [ constant_expression ]
    | port_identifier [ constant_range ]

constant_range ::=
    msb_constant_expression : lsb_constant_expression

module_items ::=
    { module_item }
    | analog_block

module_item ::=
    module_item_declaration
    | parameter_override
    | module_instantiation
    | digital_continuous_assignment
    | digital_gate_instantiation
    | digital_udp_instantiation
    | digital_specify_block
    | digital_initial_construct
    | digital_always_construct

```

Syntax 7-1—Syntax for module

The definitions for *module\_item\_declaration* and *parameter\_override* are shown in Syntax 7-2.

The definition of *module\_instantiation* is shown in Syntax 7-3.

```

module_item_declaration ::=
    {attribute_instance} parameter_declaration
  | {attribute_instance} local_parameter_declaration
  | {attribute_instance} string_parameter_declaration
  | {attribute_instance} local_string_parameter_declaration
  | aliasparam_declaration
  | {attribute_instance} digital_input_declaration
  | {attribute_instance} digital_output_declaration
  | {attribute_instance} digital_inout_declaration
  | ground declaration
  | {attribute_instance} integer_declaration
  | {attribute_instance} real_declaration
  | {attribute_instance} net_discipline_declaration
  | genvar_declaration
  | branch_declaration
  | analog_function_declaration
  | digital_function_declaration
  | digital_net_declaration
  | digital_reg_declaration
  | digital_time_declaration
  | digital_realtime_declaration
  | digital_event_declaration
  | digital_task_declaration

parameter_override ::=
    defparam list_of_param_assignments ;

```

Syntax 7-2—Syntax for *module\_item\_declaration* and *parameter\_override*

### 7.1.1 Top-level modules

*Top-level modules* are modules which are included in the source text but are not instantiated, as described in Section 7.1.2.

### 7.1.2 Module instantiation

Instantiation allows one module to incorporate a copy of another module into itself. Module definitions do not nest. That is, one module definition does not contain the text of another module definition within its **module-endmodule** keyword pair. A module definition nests another module by *instantiating* it.

Syntax 7-3 shows the syntax for specifying instantiations of modules.

```

module_instantiation ::=
    module_or_paramset_identifier [ parameter_value_assignment ] instance_list

parameter_value_assignment ::=
    # ( ordered_param_override_list )
    | # ( named_param_override_list )

ordered_param_override_list ::=
    expression { , expression }

named_param_override_list ::=
    named_param_override { , named_param_override }

named_param_override ::=
    .parameter_identifier ( constant_expression )
    | $.system_parameter_identifier ( constant_expression )

instance_list ::=
    module_instance { , module_instance } ;

module_instance ::=
    name_of_instance ( [ list_of_module_connections ] )

name_of_instance ::=
    module_instance_identifier [ range ]

list_of_module_connections ::=
    ordered_port_connection { , ordered_port_connection }
    | named_port_connection { , named_port_connection }

ordered_port_connection ::=
    [ expression ]

named_port_connection ::=
    .port_identifier ( [ expression ] )

range ::=
    [ constant_expression : constant_expression ]

```

*Syntax 7-3—Syntax for module instantiation*

The following concepts apply:

- The instantiations of modules can contain a range specification. This allows an array of instances to be created.
- One or more module instances (identical copies of a module definition) can be specified in a single module instantiation statement.
- The list of module connections can be provided only for modules defined with ports. The parentheses, however, are always required. When a list of module connections is given, the first element in the list connects to the first port, the second element to the second port, and so on. See Section 7.4 for a more detailed discussion of ports and port connection rules.

- A connection can be a simple reference to a net identifier or a sub-range of a vector net.

*Examples:*

The example below illustrates a comparator and an integrator (lower-level modules) which are instantiated in sigma-delta A/D converter module (the higher-level module).

```

module comparator(cout, inp, inm);
output cout;
input inp, inm;
ground gnd;
electrical cout, inp, inm;
parameter real td = 1n, tr = 1n, tf = 1n;
real vcout;

analog begin
    @(cross(V(inp) - V(inm), 0))
        vcout = ((V(inp) > V(inm)) ? 1 : 0);
    V(vcout) <+ transition(vcout, td, tr, tf);
end
endmodule

module integrator(out, in);
output out;
input in;
electrical in, out;
parameter real gain = 1.0;
parameter real ic = 0.0;

analog begin
    V(out) <+ gain*idt(V(in), ic);
end
endmodule

module sigmadelta(out, ref, in);
output out;
input ref, in;

comparator C1(.cout(aa0), .inp(in), .inm(aa2));
integrator #(1.0) I1(.out(aa1), .in(aa0));
comparator C2(out, aa1, gnd);
d2a #(.width(1)) D1(aa2, ref, out); // A D/A converter

endmodule

```

The comparator instance C1 and the integrator instance I1 in Figure 7-1 use named port connections, whereas the comparator instance C2 and the d2a (not described here) instance D1 use ordered port connections. Note the integrator instance I1 overrides gain parameter positionally, whereas the d2a instance D1 overrides width parameter by named association.

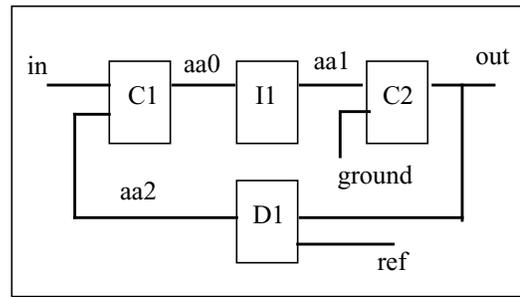


Figure 7-1 Comparator and integrator modules

## 7.2 Overriding module parameter values

When one module instantiates another module, it can alter the values of any parameters declared within the instantiated module, as well as the values of various system parameters that are implicitly declared for all modules. There are three ways to alter parameter values: the *defparam* statement, which allows assignment to parameters using their hierarchical names, the *module instance parameter value assignment*, which allows values to be assigned inline during module instantiation, and the *paramset*, which is described in Section 7.3. If a *defparam* assignment conflicts with a module instance parameter, the parameter in the module shall take the value specified by the *defparam*.

The module instance parameter value assignment comes in two forms, by ordered list or by name. The first form is *module instance parameter value assignment by order*, which allows values to be assigned in-line during module instantiation in the order of their declaration. The second form is *module instance parameter value assignment by name*, which allows values to be assigned in-line during module instantiation by explicitly associating parameter names with the overriding values.

### 7.2.1 Defparam statement

Using the *defparam statement*, parameter values can be changed in any module instance throughout the design using the hierarchical name of the parameter. See Section 7.5 for details about hierarchical names.

The expression on the right-hand side of a *defparam* assignments shall be a constant expression involving only constant numbers and references to parameters. The referenced parameters (on the right-hand side of a *defparam*) shall be declared in the same module as the *defparam* statement.

The *defparam* statement is particularly useful for grouping all of the parameter value override assignments together in one module. Its syntax is shown in Syntax 7-4.

```

parameter_override ::=
    defparam list_of_defparam_assignments ;

list_of_defparam_assignments ::=
    defparam_assign
    | list_of_defparam_assignments , defparam_assign

defparam_assign ::=
    parameter_identifier = constant_expression
    | $system_parameter_identifier = constant_expression
    | parameter_array_identifier [ range ] = constant_param_arrayinit

constant_param_arrayinit ::=
    { param_arrayinit_element_list }

param_arrayinit_element_list ::=
    param_arrayinit_element
    | param_arrayinit_element_list , param_arrayinit_element

param_arrayinit_element ::=
    constant_expression
    | { replicator_constant_expression {constant_expression} }

```

*Syntax 7-4—Syntax for defparam*

*Examples:*

```

module tgate;
    electrical io1,io2,control,control_bar;
    mosn m1 (io1, io2, control);
    mosp m2 (io1, io2, control_bar);
endmodule

module mosp (source,drain,gate);
    inout source, drain, gate;
    electrical source, drain, gate;
    parameter gate_length = 0.3e-6,
                gate_width = 4.0e-6;

    spice_pmos #(.l(gate_length),.w(gate_width)) p(gate,source,drain);
endmodule

module mosn (source,drain,gate);
    inout source, drain, gate;
    electrical source, drain, gate;
    parameter gate_length = 0.3e-6,
                gate_width = 4.0e-6;

    spice_nmos #(.l(gate_length),.w(gate_width)) n(gate,source,drain);
endmodule

```

```

module annotate;
defparam
    tgate.m1.gate_width = 5e-6,
    tgate.m2.gate_width = 10e-6;
endmodule

```

### 7.2.2 Module instance parameter value assignment by order

The order of the assignments in module instance parameter value assignment shall follow the order of declaration of the parameters within the module. Local parameter declarations are not considered when assigning by order; parameter alias declarations are also skipped. It is not necessary to assign values to all of the parameters within a module when using this method. However, the left-most parameter assignment(s) can not be skipped. Therefore, to assign values to a subset of the parameters declared within a module, the declarations of the parameters which make up this subset shall precede the declarations of the remaining (optional) parameters. An alternative is to assign values to all of the parameters, but use the default value (the same value assigned in the declaration of the parameter within the module definition) for those parameters which do not need new values.

*Examples:*

Consider the following example, where the parameters within module instance `weakp` are changed during instantiation.

```

module m;
    electrical clk;
    electrical out_a, in_a;
    electrical out_b, in_b;

    // create an instance and set parameters
    mosp #(2e-6,1e-6) weakp(out_a, in_a, clk);
    // create an instance leaving default values
    mosp plainp(out_b, in_b, clk);
endmodule

```

### 7.2.3 Module instance parameter value assignment by name

Parameter assignment by name consists of explicitly linking the parameter name and its value. The name of the parameter shall be the name specified in the instantiated module. It is not necessary to assign values to all the parameters within a module when using this method. Only those parameters which are assigned new values need to be specified.

The parameter expression is optional so the instantiating module can document the existence of a parameter without assigning anything to it. The parentheses are required and in this case the parameter retains its default value. Once a parameter is assigned a value, there shall not be another assignment to this parameter name.

*Example:*

In the following example of instantiating a voltage-controlled oscillator, the parameters are specified on a named-association basis much as they are for ports.

```

module n(lo_out, rf_in):
    electrical lo_out, rf_in;

    //create an instance and set parameters
    vco #(.centerFreq(5000), .convGain(1000)) vco1(lo_out, rf_in);
endmodule

```

Here, the name of the instantiated `vco` module is `vco1`. The `centerFreq` parameter is passed a value of 5000 and the `convGain` parameter is passed a value of 1000. The positional assignment mechanism for ports assigns `lo_out` as the first port and `rf_in` as the second port of `vco1`.

## 7.2.4 Parameter dependence

A parameter (for example, `gate_cap`) can be defined with an expression containing another parameter (for example, `gate_width` or `gate_length`). Since `gate_cap` depends on the value of `gate_width` and `gate_length`, a modification of `gate_width` or `gate_length` changes the value of `gate_cap`.

*Examples:*

In the following parameter declaration, an update of `gate_width`, whether by a *defparam* statement or in an instantiation statement for the module which defined these parameters, automatically updates `gate_cap`.

```

parameter
    gate_width = 0.3e-6,
    gate_length = 4.0e-6,
    gate_cap = gate_length * gate_width * `COX;

```

## 7.2.5 Detecting parameter overrides

In some cases, it is important to be able to determine whether a parameter value was obtained from the default value in its declaration statement or if that value was overridden. In such a case, the `$param_given()` function described in Section 10.11 can be used.

## 7.2.6 Hierarchical system parameters

In addition to the parameters explicitly declared in a module's header, there are six system parameters that are implicitly declared for every module: `$mfactor`, `$xposition`, `$yposition`, `$angle`, `$hflip`, and `$vflip`. The values of these parameters may be accessed in a module or paramset using these names, as described in Section 10.10. The value of these parameters may be overridden using the *defparam* statement, module instance parameter

value assignment by name, or a paramset; in all three methods, the system parameter identifier is prefixed by a period (`.`), just as for explicitly-declared parameters.

If an instance of a module has a non-unity value of `$mfactor`, then the following rules are applied automatically by the simulator:

- All contributions to a branch flow quantity in the analog block shall be multiplied by `$mfactor`
- The value returned by any branch flow probe in the analog block, including those used in indirect assignments, shall be divided by `$mfactor`
- Contributions to a branch flow quantity using the noise functions of Section 4.5.4 (`white_noise`, `flicker_noise`, and `noise_table`) shall have the noise power multiplied by `$mfactor`
- Contributions to a branch potential quantity using the noise functions of Section 4.5.4 shall have the noise power divided by `$mfactor`
- The module's value of `$mfactor` is also propagated to any module instantiated by the original module, according to the rules found in Section 10.10.

Application of these rules guarantees that the behavior of the module in the design is identical to the behavior of a quantity `$mfactor` of identical modules with the same connections; however, the simulator only has to evaluate the module once.

Verilog-AMS does not provide a method to disable the automatic `$mfactor` scaling. The simulator shall issue a warning if it detects a misuse of the `$mfactor` in a manner that would result in double-scaling.

*Examples:*

The two resistor modules below show ways that the `$mfactor` might be used in a module. The first example, `badres`, misuses the `$mfactor` such that the contributed current would be multiplied by `$mfactor` twice, once by the explicit multiplication and once by the automatic scaling rule. The simulator will generate an error for this module.

```

module badres(a,b);
  inout a, b;
  electrical a, b;
  parameter real r = 1.0 from (0:inf);
  analog begin
    I(a,b) <+ V(a,b) / r * $mfactor; // ERROR
  end
endmodule

```

In this second example, `parares`, `$mfactor` is used only in the conditional expression and does not scale the output. No error will be generated for this module. In cases where the effective resistance  $r/\$mfactor$  would be too small, the resistance is simply shorted out, and the simulator may collapse the node to reduce the size of the system of equations.

```

module parares(a,b);
  inout a, b;
  electrical a, b;
  parameter real r = 1.0 from (0:inf);
  analog begin
    if (r / $mfactor < 1.0e-3)
      V(a,b) <+ 0.0;
    else
      I(a,b) <+ V(a,b) / r;
    end
  endmodule

```

The values of the five geometrical system parameters, **\$xposition**, **\$yposition**, **\$angle**, **\$hflip**, and **\$vflip**, do not have any automatic effect on the simulation. The paramset or module may use these values to compute geometric layout-dependent effects, as shown in the following example.

*Example:*

In this example, it is assumed that a top-level module named `processinfo` contains values for the properties of polysilicon resistors in the manufacturing process, including the nominal value `processinfo.rho` and the gradients `processinfo.drho_dx` and `processinfo.drho_dy`, in the x and y direction respectively.

```

module polyres(a,b);
  inout a, b;
  electrical a, b;
  parameter real length = 1u from (0:inf);
  parameter real width = 1u from (0:inf);
  real rho, reff;
  analog begin
    rho = processinfo.rho
      + $xposition * processinfo.drho_dx
      + $yposition * processinfo.drho_dy;
    reff = rho * length / width;
    I(a,b) <+ V(a,b) / reff;
  end
endmodule

```

The resistor just defined could be instantiated in the following manner so as to cancel out the process gradients:

```

module matchedres(a,b);
  inout a, b;
  electrical a, b;
  parameter real length = 1u from (0:inf);
  parameter real width = 1u from (0:inf);
  polyres #(.width(width/4.0), .length(length),
    .$xposition(-1u), .$yposition(-1u)) R1(a,b);

```

```

polyres #(.width(width/4.0), .length(length),
          .$xposition(+1u), .$yposition(-1u)) R2(a,b);
polyres #(.width(width/4.0), .length(length),
          .$xposition(-1u), .$yposition(+1u)) R3(a,b);
polyres #(.width(width/4.0), .length(length),
          .$xposition(+1u), .$yposition(+1u)) R4(a,b);
endmodule

```

Unfortunately, if the module `matchedres` is itself instantiated off-center, then the process gradients will not be canceled.

## 7.3 Paramssets

A paramset definition is enclosed between the keywords **paramset** and **endparamset**, as shown in Syntax 7-5. The first identifier following the keyword **paramset** is the name of the paramset being defined. The second identifier will usually be the name of a module with which the paramset is associated. The second identifier may instead be the name of a second paramset; a chain of paramsets may be defined in this way, but the last paramset in the chain shall reference a module.

```

paramset_declaration ::=
  {attribute_instance} paramset paramset_identifier module_or_paramset_identifier ;
  paramset_item_declaration {paramset_item_declaration}
  paramset_statement { paramset_statement }
  endparamset
paramset_item_declaration ::=
  {attribute_instance} parameter_declaration
  | {attribute_instance} local_parameter_declaration
  | {attribute_instance} string_parameter_declaration
  | {attribute_instance} local_string_parameter_declaration
  | aliasparam_declaration
  | {attribute_instance} integer_declaration
  | {attribute_instance} real_declaration

paramset_statement ::=
  .module_parameter_identifier = constant_expression ;
  .$system_parameter_identifier = constant_expression ;
  | statement

```

Syntax 7-5—Syntax for paramset

The paramset itself contains no behavioral code; all of the behavior is determined by the associated module. The restrictions on statements in the paramset are described in Section 7.3.1.

The paramset provides a convenient way to collect parameter values for a particular module, such that an instance need only provide overrides for a smaller number of

parameters. A simulator can use this information to optimize data storage for the instances: multiple instances may share a paramset, and the simulator can share storage of parameters of the underlying module. The shared storage of paramsets makes them similar to the SPICE model card. Also like the SPICE model card, paramsets may be overloaded, as described in Section 7.3.2.

A paramset can have a description attribute, which shall be used by the simulator when generating help messages for the paramset.

*Example:*

The following example shows how one might convert a SPICE model card into a Verilog-AMS paramset. Suppose one has the following lines in a SPICE netlist:

```
m1 d1 g 0 0 nch l=1u w=10u
m2 d2 g 0 0 nch l=1u w=5u
.model nch nmos (level=3 kp=5e-5 tox=3e-8 u0=650 nsub=1.3e17
+ vmax=0 tpg=1 nfs=0.8e12)
```

These lines could be written in Verilog-AMS as follows, assuming that `nmos` is a behavioral module that contains the same equations as the SPICE primitive.

```
nch #(.l(1u), .w(10u)) m1(.d(d1), .g(g), .s(0), .b(0));
nch #(.l(1u), .w(5u)) m2(.d(d2), .g(g), .s(0), .b(0));

paramset nch nmos; // default paramset
parameter real l=1u from [0.25u:inf);
parameter real w=1u from [0.2u:inf);
.l=1; .w=w; .ad=w*0.5u; .as=w*0.5u;
.level=3; .kp=5e-5; .tox=3e-8; .u0=650; .nsub=1.3e17;
.vmax=0; .tpg=1; .nfs=0.8e12;
endparamset
```

Note that the paramset has only two parameters, `l` and `w`; an instance of the paramset that attempts to override any of the other parameters of the underlying module `nmos` would generate an error. Analog simulators are expected to optimize the storage of paramset values in a manner similar to the way SPICE optimizes model parameter storage.

### 7.3.1 Paramset statements

The restrictions on statements or assignments allowed in a paramset are similar to the restrictions for analog functions. Specifically, a paramset:

- can use any statements available for conditional execution (see Section 6.1);
- shall not use access functions;
- shall not use contribution statements or event control statements; and
- shall not use named blocks.

### The special syntax

```
.module_parameter_identifier = constant_expression ;
```

is used to assign values to the parameters of the associated module. The expression on the right-hand side can be composed of numbers, parameters, and hierarchical out-of-module references to parameters of a different module. The expression may also use the **\$random** function from Section 10.2 and the **\$rdist\_** functions from Section 10.3, so long as the arguments to these functions are constant.

Paramset statements may assign values to variables declared in the paramset; the values need not be constant expressions. However, these variables shall not be used to assign values to the module's parameters. Paramset variables may be used to provide output variables for instances that use the paramset; see Section 7.3.3.

#### Example:

The following example shows how to use the **\$rdist\_normal** function of Section 10.3 to model two kinds of statistical variation.

```

module semicoCMOS;
  localparam real tox = 3e-8;
  localparam real dtox_g = $rdist_normal(1,0,1n,"global");
  localparam real dtox_mm = $rdist_normal(2,0,5n,"instance");
endmodule

paramset nch nmos; // mismatch paramset
  parameter real l=1u from [0.25u:inf);
  parameter real w=1u from [0.2u:inf);
  parameter integer mm=0 from (0:1];
  .l=l; .w=w; .ad=w*0.5u; .as=w*0.5u;
  .level=3; .kp=5e-5; .u0=650; .nsub=1.3e17;
  .vmax=0; .tpg=1; .nfs=0.8e12;
  .tox = semicoCMOS.tox + semicoCMOS.dtox_g + semicoCMOS.dtox_mm;
endparamset

nch #(.l(1u), .w(5u), .mm(1)) m1(.d(d1), .g(g), .s(0), .b(0));
nch #(.l(1u), .w(5u), .mm(1)) m2(.d(d2), .g(g), .s(0), .b(0));
resistor #(.r(1k)) R1 (vdd, d1);
resistor #(.r(1k)) R2 (vdd, d2);
vsine #(.dc(2.5)) Vdd (vdd, 0);
vsine #(.dc(0), .ampl(1.0), .offset(1.5), .freq(1k)) Vg (g, gnd);

```

Because the local parameter `dtox_mm` is obtained from **\$rdist\_normal** with the string “instance,” the instances `m1` and `m2` will get different values of `tox`. Though the local variation has a smaller standard deviation than the global variation, only the local variation will affect the differential voltage between nodes `d1` and `d2`.

### 7.3.2 Paramset overloading

Paramset identifiers need not be unique: multiple paramsets can be declared using the same *paramset\_identifier*, and they may refer to different modules. During elaboration, the simulator shall choose an appropriate paramset from the set that shares a given name for every instance that references that name.

When choosing an appropriate paramset, the following rules shall be enforced:

- All parameters overridden on the instance shall be parameters of the paramset
- The parameters of the paramset, with overrides and defaults, shall be all within the allowed ranges specified in the paramset parameter declaration.
- The local parameters of the paramset, computed from parameters, shall be within the allowed ranges specified in the paramset.

The rules above may not be sufficient for the simulator to pick a unique paramset, in which case the following rules shall be applied in order until a unique paramset has been selected:

- The paramset with the fewest number of un-overridden parameters shall be selected.
- The paramset with the greatest number of local parameters with specified ranges shall be selected.

It shall be an error if there are still more than one applicable paramset for an instance after application of these rules.

If a paramset assigns a value to a module parameter and this value is outside the range specified for that module parameter, it shall be an error. The simulator shall consider only the ranges of the paramset's own parameters when choosing a paramset.

*Example:*

The following example illustrates some of the rules for paramset selection. Consider a design that includes the two paramsets defined previously (in the examples of Section 7.3 and Section 7.3.1) as well as the following paramsets:

```

paramset nch nmos; // short-channel paramset
  parameter real l=0.25u from [0.25u:1u);
  parameter real w=1u from [0.2u:inf);
  parameter real ad=0.5*w from (0:inf);
  parameter real as=0.5*w from (0:inf);
  .l=l; .w=w; .ad=ad; .as=as;
  .level=3; .kp=5e-5; .tox=3e-8; .u0=650; .nsub=1.3e17;
  .vmax=0; .tpg=1; .nfs=0.8e12;
endparamset

```

```

paramset nch nmos; // long-channel paramset
  parameter real l=1u from [1u:inf);
  parameter real w=1u from [0.2u:inf);
  parameter real ad=0.4*w from (0:inf);
  parameter real as=0.4*w from (0:inf);
  .l=1; .w=w; .ad=ad; .as=as;
  .level=3; .kp=5e-5; .tox=3e-8; .u0=640; .nsub=1.3e17;
  .vmax=0; .tpg=1; .nfs=0.7e12;
endparamset

```

The following instances might exist in the design:

```

nch #(.l(1u), .w(5u), .mm(1)) m1(.d(d1), .g(g), .s(0), .b(0));
nch #(.l(1u), .w(5u), .mm(1)) m2(.d(d2), .g(g), .s(0), .b(0));
nch #(.l(1u), .w(10u)) m3 (.d(g), .g(g), .s(0), .b(0));
nch #(.l(3u), .w(5u), .ad(1.2p), .as(1.3p))
    m4 (.d(d1), .g(g2), .s(d2), .b(0));

```

The instances `m1` and `m2` will use the mismatch paramset from Section 7.3.1, because it is the only one for which `mm` is a parameter. The instance `m4` will use the long-channel paramset defined in this example, because while the short-channel paramset also has `ad` and `as` as parameters, the length of `m4` is only allowed by the range for `l` in the long-channel paramset. The instance `m3` will use the default paramset defined in Section 7.3: it cannot use the mismatch paramset because the default value of `mm` for that paramset is not allowed by the range, and it discriminates against the long-channel paramset because that paramset would have two un-overridden parameters.

### 7.3.3 Paramset output variables

As with modules, integer or real variables in the paramset that are declared with descriptions are considered output variables; see Section 3.1.1. A few special rules apply to paramset output variables and output variables of modules referenced by a paramset:

- If a paramset output variable has the same name as an output variable of the module, the value of the paramset output variable is the value reported for any instance that uses the paramset.
- If a paramset variable without a description has the same name as an output variable of the module, the module output variable of that name shall not be available for instances that use the paramset.
- A paramset output variable's value may be computed from values of any output parameters of the module by using the special syntax `.module_output_variable_identifier`

*Example:*

The following example declares an output variable `ft` for instances of the paramset `smnnpn`. The module is assumed to have output variables named `gm`, `cpi`, and `cmu`. If the

module `nnpn` had an output variable named `ft`, the paramset's output variable would replace it.

```

paramset smnnpn nnpn; // small nnpn paramset
  (*desc="cut-off frequency"*) real ft;
  .is=2.0e-17; .bf=120.0; .br=10; rb=145; .rc=75; .re=12;
  .cje=2.0e-14; .vje=0.9; .mje=0.4;
  .cjc=3.0e-14; .vjc=0.6; .mjc=0.3; .xcjc=0.2;
  ft = .gm/(`M_TWO_PI*(.cpi + .cmu));
endparamset

```

## 7.4 Ports

Ports provide a means of interconnecting instances of modules. For example, if a module `A` instantiates module `B`, the ports of module `B` are associated with either the ports or the internal nets of module `A`.

### 7.4.1 Port association

The syntax for a port association is shown in Syntax 7-6.

```

port ::=
  port_expression
  | .port_identifier ( [ port_expression ] )

port_expression ::=
  port_identifier
  | port_identifier [ constant_expression ]
  | port_identifier [ constant_range ]

constant_range ::=
  msb_constant_expression : lsb_constant_expression

```

Syntax 7-6—Syntax for port

The port expression in the port definition can be one of the following:

- a simple net identifier
- a scalar member of a vector net or port declared within the module
- a sub-range of a vector net or port declared within the module

The two types of module port definitions cannot be mixed; the ports of a particular module definition shall all be defined by order or by name. The port expression is optional because ports can be defined which do not connect to anything internal to the module.

## 7.4.2 Port declarations

The type and direction of each port listed in the module definition's list of ports are declared in the body of the module.

### 7.4.2.1 Port type

The type of a port is declared by giving its discipline, as shown in Syntax 7-7. If the type of a port is not declared, the port can only be used in a structural description. (It can be passed to instances of modules, but cannot be accessed in a behavioral description.)

```
net_discipline_declaration ::=
    discipline_identifier [ range ] list_net_identifiers;

list_net_identifiers ::=
    net_identifier { , net_identifier }
```

Syntax 7-7—Syntax for port type declarations

### 7.4.2.2 Port direction

Each port listed in the list of ports for the module definition shall be declared in the body of the module as an **input**, **output**, or **inout** (*bidirectional*). This is in addition to any other declaration for a particular port — for example, a *net\_discipline*, *reg*, or *wire*. The syntax for port declarations is shown in Syntax 7-8.

```
input_declaration ::=
    input [ range ] list_of_port_identifiers ;

output_declaration ::=
    output [ range ] list_of_port_identifiers ;

inout_declaration ::=
    inout [ range ] list_of_port_identifiers ;
```

Syntax 7-8—Syntax for port direction declarations

A port can be declared in both a *port type* declaration and a *port direction* declaration. If a port is declared as a *vector*, the range specification between the two declarations of a port shall be identical.

**Note:** Implementations can limit the maximum number of ports in a module definition, but this shall be a minimum of 256 ports per implementation.

### 7.4.3 Real valued ports

Verilog-AMS HDL supports ports which are declared to be real-valued and have a discrete-time discipline. This is done using the net type `wreal` (defined in Section 3.5). There can be a maximum of one driver of a real-valued net.

*Examples:*

```

module top();
  wreal stim;
  reg clk;
  wire [1:8] out;

  testbench tb1 (stim, clk);
  a2d dut (out, stim, clk);

  initial clk = 0;
  always #1 clk = ~clk;
endmodule

module testbench(wout, clk);
  output wout;
  input clk;
  real out;
  wire clk;
  wreal wout;
  assign wout = out;

  always @(posedge clk) begin
    out = out + $abstime;
  end
endmodule

module a2d(dout, in, clk);
  output [1:8] dout;
  input in, clk;
  wreal in;
  wire clk;
  reg [1:8] dout;
  real residue;
  integer i;

  always @(negedge clk) begin
    residue = in;
    for (i = 8; i >= 1; i = i - 1) begin
      if (residue > 0.5) begin
        dout[i] = 1'b1;
        residue = residue - 0.5;
      end else begin
        dout[i] = 1'b0;
      end
      residue = residue*2;
    end
  end
endmodule

```

#### 7.4.4 Connecting module ports by ordered list

One way to connect the ports listed in a module instantiation with the ports defined by the instantiated module is via an ordered list—that is, the ports listed for the module instance shall be in the same order as the ports listed in the module definition.

*Examples:*

```

module adc4 (out, rem, in);
output [3:0] out ; output rem;
input in;
electrical [3:0] out;
electrical in, rem, rem_chain;

adc2 hi2 (out[3:2], rem_chain, in) ;
adc2 lo2 (out[1:0], rem, rem_chain) ;
endmodule

module adc2 (out, remainder, in);
output [1:0] out ; output remainder;
input in;
electrical [1:0] out ;
electrical in, remainder, r;

adc hi1 (out[1], r, in) ;
adc lo1 (out[0], remainder, r) ;
endmodule

module adc (out, remainder, in);
output out, remainder;
input in;
electrical out, in, remainder;
integer d;

    analog begin
        d = (V(in) > 0.5) ;
        V(out) <+ transition(d) ;
        V(remainder) <+ 2.0 * V(in) ;
        if (d)
            V(remainder) <+ -1.0 ;
    end
endmodule

```

#### 7.4.5 Connecting module ports by name

The second way to connect module ports consists of explicitly linking the two names for each side of the connection — specify the name used in the module definition, followed by the name used in the instantiating module. This compound name is then placed in the list of module connections.

The following rules apply:

- The name of port shall be the name specified in the module definition.

- The name of port cannot be a bit select or a part select.
- The port expression shall be the name used by the instantiating module and can be one of the following:
  - a simple net identifier
  - a scalar member of a vector net or port declared within the module
  - a sub-range of a vector net or port declared within the module
  - a vector net formed as a result of the concatenation operator
- The port expression is optional so the instantiating module can document the existence of the port without connecting it to anything. The parentheses are required.
- The two types of module port connections can not be mixed; connections to the ports of a particular module instance shall be all by order or all by name.

*Examples:*

```

module adc4 (out, rem, in);
input in;
output [3:0] out; output rem;
electrical [3:0] out;
electrical in, rem, rem_chain;

adc2 hi (.in(in), .out(out[3:2]), .remainder(rem_chain)) ;
adc2 lo (.in(rem_chain), .out(out[1:0]), .remainder(rem)) ;
endmodule

module adc2 (out, in, remainder);
output [1:0] out; output remainder;
input in;
electrical [1:0] out;
electrical in, remainder, r;

adc hi1 (out[1], r, in) ; // adc is same as defined in Section 7.4.4
adc lo1 (out[0], remainder, r) ;
endmodule

```

Since these connections were made by port name, the order in which the connections appear is irrelevant.

#### 7.4.6 Detecting port connections

When a module is instantiated, all of its ports need not be connected. For example, a clock module may provide outputs `c1k` and `c1kbar`, but a design may only need `c1k`. In some cases, it may be important to know whether a particular port is connected. For example, if the `transition()` filter of Section 4.4.9 is used on the outputs, it might speed up the simulation if the filter is only used when the port is connected. The `$port_connected()`

function described in Section 10.11 can be used to determine whether a port is connected.

### 7.4.7 Port connection rules

All digital ports connected to a net shall be of compatible disciplines, as shall all analog ports connected to a net. Ports of both analog and digital discipline may be connected to a net provided the appropriate connect statements exist (see Section 8.7).

#### 7.4.7.1 Matching size rule

A scalar port can be connected to a scalar net and a vector port can be connected to a vector net or concatenated net expression of the matching width. In other words, the sizes of the ports and net need to match.

#### 7.4.7.2 Resolving discipline of undeclared interconnect signal

Verilog-AMS HDL supports undeclared interconnects between module instances when describing hierarchical structures. That is, a signal appearing in the connection list of a module instantiation need not appear in any port declaration or discipline declaration (see Section 8.4).

### 7.4.8 Inheriting port natures

A net of continuous discipline shall have a potential nature and may have a flow nature. Because of hierarchical connections, an analog node may be associated with a number of analog nets, and thus, a number of continuous disciplines. The node shall be treated as having a `potential abstol` with a value equal to the smallest `abstol` of all the potential natures of all the disciplines with which it is associated. The node shall be treated as having a `flow abstol` with a value equal to the smallest `abstol` of all the flow natures, if any, of all the disciplines with which it is associated.

## 7.5 Hierarchical names

Every identifier in Verilog-AMS HDL has a unique *hierarchical path name*. The hierarchy of modules and the definition of items such as named blocks within the modules define these names. The hierarchy of names can be viewed as a tree structure, where each module instance or a named begin-end block defines a new hierarchical level, or as a scope (of a particular branch of the tree).

At the top of the name hierarchy are the names of modules where no instances have been created. This is the *root* of the hierarchy. Inside any module, each module instance and named begin-end block define a new branch of the hierarchy. Named blocks within named blocks also create new branches.

Each net in the hierarchical name tree is treated as a separate scope with respect to identifiers. A particular identifier can be declared only once in any scope.

Any named object can be referenced uniquely in its full form by concatenating the names of the module instance or named blocks that contain it. The period character (.) is used to separate names in the hierarchy. The complete path name to any object starts at a top-level module. This path name can be used from any level in the description. The first name in a path name can also be the top of a hierarchy which starts at the level where the path is being used.

*Examples:*

```

module samplehold (in, cntrl, out );
input in, cntrl ;
output out ;
electrical in, cntrl, out ;
electrical store, sample ;
parameter real vthresh = 0.0 ;
parameter real cap = 10e-9 ;
    amp op1 (in, sample, sample);
    amp op2 (store, out, out) ;

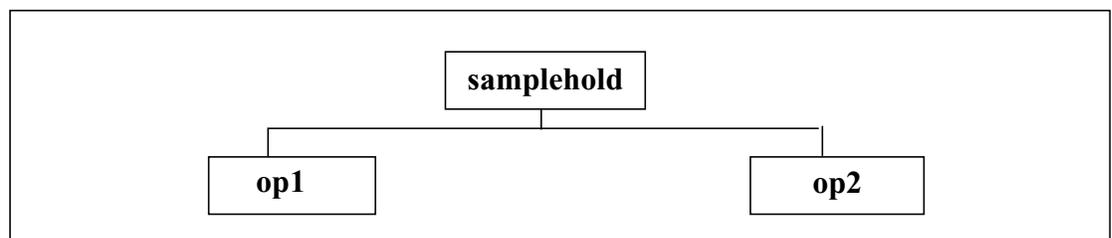
analog begin
    I(store) <+ cap * ddt(V(store)) ;
    if (V(cntrl) > vthresh)
        V(store, sample) <+ 0 ;
    else
        I(store, sample) <+ 0 ;
    end
endmodule

module amp(inp, inm, out) ;
input inp, inm ;
output out ;
electrical inp, inm, out ;
parameter real gain=1e5;

    analog begin
        V(out) <+ gain*V(inp,inm) ;
    end
endmodule

```

Figure 7-2 illustrates the hierarchy implicit in the example code.



**Figure 7-2 Hierarchy in a model**

Figure 7-3 is a list of the hierarchical forms of the names of all the object defined in the example code.

samplehold	in, cntrl, out, sample, store, vthresh, cap
op1	op1.inp, op1.inm, op1.out, op1.gain
op2	op2.inp, op2.inm, op2.out, op2.gain

**Figure 7-3 Hierarchical path names in a design**

From within an analog block, it is possible to use hierarchical name referencing to access signals on an external branch, but not external analog variables or parameters. When accessing external branches, a branch signal (its potential or flow) can be monitored (probed); for source branches, contributions can be made to the output signal.

## 7.6 Scope rules

The following elements define a new scope in Verilog-AMS HDL:

- modules
- tasks
- named blocks
- functions
- analog functions

An identifier can be used to declare only one item within a scope. This means it is illegal to declare two or more variables which have the same name or to give an instance the same name as the name of the net connected to its output.

If an identifier is referenced directly (without a hierarchical path) within a named block, it shall be declared either locally within the named block, within a module, or within a named block which is higher in the same branch of the name tree containing the named block. If it is declared locally, the local item shall be used; if not, the search shall continue upward until an item by that name is found or until a module boundary is encountered. The search can cross named block boundaries, but not module boundaries.

**Note:** Because of the upward searching process, path names which are not strictly on a downward path can be used.

# Section 8

## Mixed signal

### 8.1 Introduction

With the mixed use of digital and analog simulators, a common terminology is needed. This section provides the core terminology used in this LRM and highlights the behavior of the mixed-signal capabilities of Verilog-AMS HDL.

Verilog-AMS HDL provides the ability to accurately model analog, digital, and mixed-signal blocks. Mixed-signal blocks provide the ability to access data and be controlled by events from the other domain. In addition to providing mixed-signal interaction directly through behavioral descriptions, Verilog-AMS HDL also provides a mechanism for the mixed-signal interaction between modules.

Verilog-AMS HDL is a hierarchical language which enables top-down design of mixed-signal systems. Connect modules are used in the language to resolve the mixed-signal interaction between modules. These modules can be manually inserted (by the user) or automatically inserted (by the simulator) based on rules provided by the user.

Connect rules and the discipline of the mixed signals can be used to control auto-insertion throughout the hierarchy. Prior to insertion, all net segments of a mixed signal shall first be assigned a discipline. This is commonly needed for interconnect, which often does not have a discipline declared for it. Once a discipline has been assigned (usually through use of a discipline resolution algorithm), connect modules shall be inserted based on the specified connect rules. *Connect rules* control which connect modules are used and where are they inserted.

*Connect modules* are a special form of a mixed-signal module which provide significant power in accurately modeling the interfaces between analog and digital blocks. They help ensure the drivers and receivers of a connect module are correctly handled so the simulation results are not impacted.

This section also details a feature which allows analog to accurately model the effects the digital receivers for mixed signals containing both drivers and receivers. In addition, special functions provide access to driver values so a more accurate connect module can be created.

The following subsections define these capabilities in more detail.

## 8.2 Fundamentals

The most important feature of Verilog-AMS HDL is it puts capabilities of both analog and digital modeling into a single language. This section describes how the continuous (analog) and discrete (digital) domains interact together, as well as the mixed-signal-specific features of the language.

### 8.2.1 Domains

The domain of a value refers to characteristics of the computational method used to calculate it. In Verilog-AMS HDL, a variable is calculated either in the *continuous* (analog) *domain* or the *discrete* (digital) *domain* every time. The potentials and flows described in nature are calculated in the continuous domain, while register contents and the states of gate primitives are calculated in the discrete domain. The values of real and integer variables can be calculated in either the continuous or discrete domain depending on how their values are assigned.

Values calculated in the discrete domain change value instantaneously and only at integer multiples of a minimum resolvable time. For this reason, the derivative with respect to time of a digital value is always zero (0). Values calculated in the continuous domain, on the other hand, are continuously varying.

### 8.2.2 Contexts

Statements in a Verilog-AMS HDL module description can appear in the body of an analog block, in the body of an **initial** or **always** block, or outside of any block (in the body of the module itself). Those statements which appear in the body of an analog block are said to be in the *continuous* (analog) *context*; all others are said to be in the *discrete* (digital) *context*. A given variable can be assigned values only in one context or the other, but not in both. The domain of a variable is that of the context from which its value is assigned.

### 8.2.3 Nets, nodes, ports, and signals

In Verilog-AMS HDL, hierarchical structures are created when higher-level modules create instances of lower level modules and communicate with them through input, output, and bidirectional ports. A *port* represents the physical connection between an expression in the instantiating or parent module and an expression in the instantiated or child module. The expressions involved are referred to as *nets*, although they can include registers, variables, and nets of both continuous and discrete disciplines. A port of an instantiated module has two nets, the upper connection (`vpiHiConn`) which is a net in the instantiating module and the lower connection (`vpiLoConn`) which is a net in the instantiated module, as shown in Figure 8-1. The `vpiLoConn` and `vpiHiConn`

connections to a port are frequently referred to as the *formal* and *actual connections* respectively.

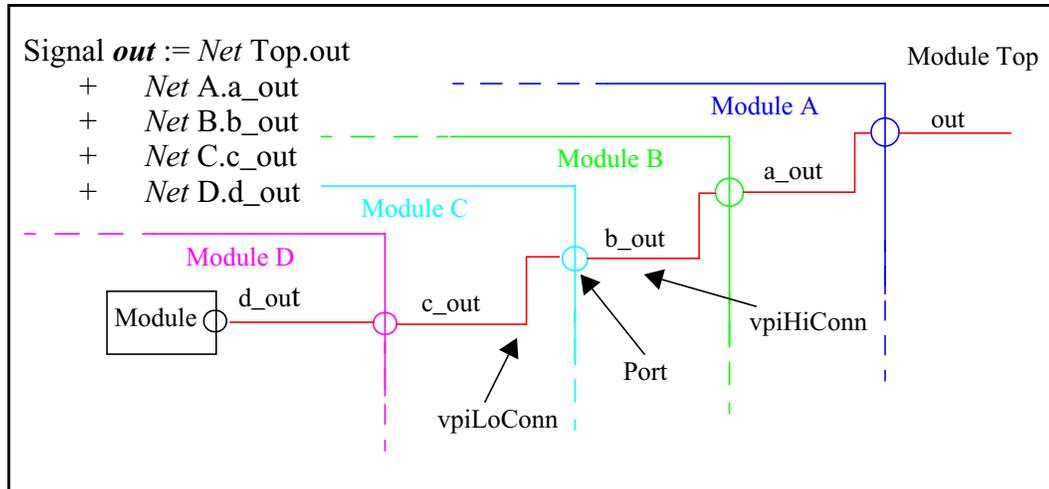


Figure 8-1 Signal “out” hierarchy of net segments

A net can be declared with either a discrete or analog *discipline* or no *discipline* (neutral interconnect). Within the Verilog-AMS language, only digital blocks and primitives can drive a discrete net (*drivers*), and only analog blocks can contribute to an analog net (*contributions*). A *signal* is a hierarchical collection of nets which, because of port connections, are contiguous. If all the nets that make up a signal are in the discrete domain, the signal is a *digital signal*. If all the nets that make up a signal are in the continuous domain, the signal is an *analog signal*. A signal that consists of nets from both domains is called a *mixed signal*.

Similarly, a port whose connections are both analog is an *analog port*, a port whose connections are both digital is a *digital port*, and a port whose connections are analog and digital is a *mixed port*.

Since it is physically one wire in the design, Kirchoff’s current law applies to the whole signal, and it forms one node in analog simulation (see Section 3.4). Drivers in the digital domain are converted to contributions in analog domain using auto-inserted digital-to-analog connection modules (D2As), and the signal value is calculated in the analog domain. Instead of determining the final digital receiver value of the signal by resolving all the digital drivers, the resolved analog signal is converted back to a digital value. A digital behavioral block that reads the value of a signal is a *receiver*, but since Verilog-AMS has no syntax that identifies multiple receivers within a module as distinct, the associated net can be viewed as a single receiver for the purposes of analog to digital conversion. Drivers are created by declaring a reg, instantiating a digital primitive or using a continuous assign statement. Since it is only possible to insert connect modules at port boundaries, when multiple continuous assign statements exist in a module, they are handled by a single connect module.

The drivers and receivers of a mixed signal are associated with their locally-declared net; the discipline of that net is used to determine which connection modules to use. The discipline of the whole signal is found by discipline resolution, as described in Section 8.4, and is used to determine the attributes of the node in simulation.

#### 8.2.4 Mixed-signal and net disciplines

One job of the discipline of a continuous net is to specify the tolerance (*abstol*) for the potential of the associated node. A mixed signal can have a number of compatible continuous nets, with different continuous disciplines and different *abstols*. In this case, the *abstol* of the associated node shall be the smallest of the *abstols* specified in the disciplines associated with all the continuous nets of the signal.

If an undeclared net segment has multiple compatible disciplines connected to it, a `connect` statement shall specify which discipline to use during discipline resolution.

### 8.3 Behavioral interaction

Verilog-AMS HDL supports several types of block statements for describing behavior, such as `analog` blocks, `initial` blocks, and `always` blocks. Typically, non-analog behavior is described in `initial` and `always` blocks, assignment statements, or assign declarations. There can be any number of `initial` and `always` blocks in a particular Verilog-AMS HDL module. However there can only be one `analog` block in that module.

Nets and variables in the continuous domain are termed *continuous nets* and *continuous variables* respectively. Likewise nets, regs and variables in the discrete domain are termed *discrete nets*, *discrete regs*, and *discrete variables*. In Verilog-AMS HDL, the nets and variables of one domain can be referenced in the other's context. This is the means for passing information between two different domains (continuous and discrete). Read operations of nets and variables in both domains are allowed from both contexts. Write operations of nets and variables are only allowed from the context of their domain.

Verilog-AMS HDL provides ways to:

- access discrete primaries (e.g., nets, regs, or variables) from a continuous context
- access continuous primaries (e.g., flows, potentials, or variables) from a discrete context
- detect discrete events in a continuous context
- detect continuous events in a discrete context

The specific time when an event from one domain is detected in the other domain is subject to the synchronization algorithm described in Section 8.3.6 and Section 9. This

algorithm also determines when changes in nets and variables of one domain are accessible in the other domain.

### 8.3.1 Accessing discrete nets and variables from a continuous context

Discrete nets and variables can be accessed from a continuous context. However, because the data types which are supported in continuous contexts are more restricted than those supported in discrete contexts, certain discrete types can not be accessed in a continuous context.

Table 8-1 lists how the various discrete net/variable types can be accessed from a continuous context.

**Table 8-1—Discrete net/reg/variable access from a continuous context**

Discrete net/reg/variable type	Examples	Equivalent continuous variable type	Access to this discrete net/reg/variable type from a continuous context
real	<b>real</b> r; <b>real</b> rm[0:8];	real	Discrete reals are accessed in the continuous context as real numbers.
integer	<b>integer</b> i; <b>integer</b> im[0:4];	integer	Discrete integers are accessed in continuous context as integer numbers.
bit	<b>reg</b> r1; <b>wire</b> w1; <b>reg</b> [0:9] r[0:7]; <b>reg</b> r[0:66]; <b>reg</b> [0:34] rb;	integer	Discrete bit and bit groupings (buses and part selects) are accessed in the continuous context as integer numbers. The sign bit (bit 31) of the integer is always set to zero (0). The lowest bit of the bit grouping is mapped to the 0th bit of the integer. The next bit of the bus is mapped to the 1st bit of the integer and so on. If the bus width is less than 31 bits, the higher bits of the integer are set to zero (0). Access of discrete bit groupings with greater than 31 bits is illegal.

The syntax for a Verilog-AMS HDL primary is defined in Syntax 8-1.

```

primary ::=
    number
  | identifier
  | identifier [ expression ]
  | identifier [ msb_constant_expression : lsb_constant_expression ]
  | concatenation
  | analog_function_call
  | string
  | access_function

```

Syntax 8-1—Syntax for primary

*Examples:*

The following example accesses the discrete primary `in` from a continuous context.

```

module onebit_dac (in, out);
input in;
inout out;
wire in;
electrical out;
real x;

analog begin
    if (in == 0)
        x = 0.0;
    else
        x = 3.0;
        V(out) <+ x;
end

endmodule

```

### 8.3.2 Accessing X and Z bits of a discrete net in a continuous context

Discrete nets can contain bits which are set to `x` (*unknown*) or `z` (*high impedance*). Verilog-AMS HDL supports accessing of 4-state logic values within the analog context. The `x` and `z` states must be translated to equivalent analog real or integer values before being used within the analog context. The language supports the following specific features, which provide a mechanism to perform this conversion.

- the case equality operator (`===`)
- the case inequality operator (`!==`)
- the `case`, `casex`, and `casez` statements

- binary, octal and hexadecimal numeric constants which can contain x and z as digits.

The case equality and case inequality operators have the same precedence as the equality operator.

*Example:*

```

module a2d(dnet, anet);
input dnet;
wire dnet;
logic dnet;
output anet;
electrical out;

analog begin
  case (dnet)
    1'b1:var = 5;
    1'bx:var = var;// hold value
    1'b0:var = 0;
    1'bz:var = 2.5; // high impedance - float value
  endcase
  V(anet) <+ var;
end
endmodule

```

**Note:** A case statement may be replaced with an *if-else-if* statement using the case equality operators to perform the 4-state logic value comparisons.

Accessing digital net and digital binary constant operands are supported within analog context expressions. It is an error if these operands return 'x' or 'z' bit values when solved. It will be an error if the value of the digital variable being accessed in the analog context goes either to 'x' or 'z'.

*Example:*

```

module converter(dnet, anet);
reg dnet;
electrical anet;
integer var1;
real var2;

initial begin
  dnet = 1'b1;
  #50 dnet = 1'bz;
  $finish;
end

analog begin
  var1 = 1'bx;// error
  var2 = 1'bz;// error
  var1 = 1 + dnet;// error after #50
end

```

```

    if (dnet == 1'bx)// error
        $display("Error to access x bit in continuous context");
    V(anet) <+ 1'bz;// error
    V(anet) <+ 1'bz;// error after #50
end
endmodule

```

The syntax for the features that support x and z comparisons in a continuous context is defined in Section 2.5 and Section 6.5. Support for x and z is limited in the analog blocks as defined above.

**Note:** Consult *IEEE 1364-1995 Verilog HDL* for a description of the semantics of these operators.

### 8.3.2.1 Special floating point values

Floating point arithmetic can produce special values representing plus and minus infinity and Not-a-Number (NaN) to represent a bad value. While use of these special numbers in digital expressions is not an error, it is illegal to assign these values to a branch through contribution in the analog context.

### 8.3.3 Accessing continuous nets and variables from a discrete context

All continuous nets can be probed from a discrete context using access functions. All probes which are legal in a continuous context of a module are also legal in the discrete context of a module. Therefore for Verilog-AMS HDL, the definition of *IEEE 1364-1995 Verilog HDL's primary* is shown in Syntax 8-2.

```

digital_primary ::=
    digital_number
    | identifier
    | identifier [ digital_expression ]
    | identifier [ digital_msb_constant_expression : digital_lsb_constant_expression ]
    | digital_concatenation
    | digital_multiple_concatenation
    | digital_function_call
    | ( digital_mintypmax_expression )
    | access_function_reference

```

Syntax 8-2—Syntax for *digital\_primary*

*Examples:*

The following example accesses the continuous net `v(in)` from the discrete context is.

```

module sampler (in, clk, out);
inout in;
input clk;
output out;
electrical in;
wire clk;
reg out;

always @(posedge clk)
    out = V(in);

endmodule

```

Continuous variables can be accessed for reading from any discrete context in the same module where these variables are declared. Because the discrete domain can fully represent all continuous types, a continuous variable is fully visible when it is read in a discrete context.

### 8.3.4 Detecting discrete events in a continuous context

Discrete events can be detected in a Verilog-AMS HDL continuous context. The arguments to discrete events in continuous contexts are in the discrete context. A discrete event in a continuous context is non-blocking like the other event types allowed in continuous contexts. The syntax for events in a continuous context is shown in Syntax 8-3.

```

event_control_statement ::=
    event_control statement_or_null

event_control ::=
    @ event_identifier
    | @ ( event_expression )

event_expression ::=
    global_event
    | event_function
    | digital_expression
    | event_identifier
    | posedge digital_expression
    | negedge digital_expression
    | event_expression or event_expression

```

Syntax 8-3—Syntax for event control statement

#### Examples:

The following example shows a discrete event being detected in an analog block.

```

module sampler3 (in, clk1, clk2, out);
input in, clk1, clk2;
output out;
wire clk1;
electrical in, clk2, out;

analog begin
    @(posedge clk1 or cross(V(clk2), 1))
        vout = V(in);
    V(out) <+ vout;
end

endmodule

```

### 8.3.5 Detecting continuous events in a discrete context

In Verilog-AMS HDL, monitored continuous events can be detected in a discrete context. The arguments to these events are in the continuous context. A continuous event in a discrete context is blocking like other discrete events. For Verilog-AMS HDL, the definition of *IEEE 1364-1995 Verilog HDL's event\_expression* is shown in Syntax 8-4.

```

digital_event_expression ::=
    digital_expression
    | event_identifier
    | posedge digital_expression
    | negedge digital_expression
    | event_function
    | digital_event_expression or digital_event_expression

```

Syntax 8-4—Syntax for digital event expression

*Examples:*

The following example detects a continuous event in an always block.

```

module sampler2 (in, clk, out);
input in, clk;
output out;
wire in;
reg out;
electrical clk;

always @(cross(V(clk) - 2.5, 1))
    out = in;

endmodule

```

### 8.3.6 Concurrency

Verilog-AMS HDL provides synchronization between the continuous and discrete domains. Simulation in the discrete domain proceeds in integer multiples of the digital tick. This is the smallest value of the second argument of the ``timescale` directive (see Section 16.7 in *IEEE 1364-1995 Verilog HDL*). Thus, values calculated in the digital domain shall be constant between digital ticks and can only change at digital ticks.

Simulation in the continuous domain appears to proceed continuously. Thus, there is no time granularity below which continuous values can be guaranteed to be constant.

The rest of this section describes synchronization semantics for each of the four types of mixed-signal behavioral interaction. Any synchronization method can be employed, provided the semantics preserved. A typical synchronization algorithm is described in Section 9.2.

#### 8.3.6.1 Analog event appearing in a digital event control

In this case, an analog event, such as `cross` or `timer`, appears in an `@( )` statement in the digital context.

*Examples:*

```
always begin
    @(cross(v(x) - 5.5, 1))
    n = 1;
end
```

When it is determined the event has occurred in the analog domain, the statements under the event control shall be scheduled in the digital domain at the largest digital time tick smaller than or equal to the time of the analog event. This event shall not be schedule in the digital domain earlier than the current digital event (see Section 9.2.3).

#### 8.3.6.2 Digital event appearing in an analog event control

*Examples:*

```
analog begin
    @(posedge n)
    r = 3.14;
end
```

In this case, a digital event, such as `posedge` or `negedge`, appears in an `@( )` statement in the analog context.

When it is determined the event has occurred in the digital domain, the statements under the event control shall be executed in the analog domain at the time corresponding to a real promotion of the digital time (e.g., `27 ns` to `27.0e-9`).

### 8.3.6.3 Analog primary appearing in a digital expression

In this case, an analog primary (variable, potential, or flow) whose value is calculated in the continuous domain appears in an expression which is in the digital context; thus the analog primary is evaluated in the digital domain.

The expression shall be evaluated using the analog value calculated for the time corresponding to a real promotion of the digital time at which the expression is evaluated.

### 8.3.6.4 Digital primary appearing in an analog expression

In this case, a digital primary (reg, wire, integer, etc.) whose value is calculated in the discrete domain appears in an expression which is in the analog context; thus the analog primary is evaluated in the continuous domain.

The expression shall be evaluated using the digital value calculated for the greatest digital time tick which is less than or equal to the analog time when the expression is evaluated.

### 8.3.7 Function calls

Analog functions can only be called from a continuous context. Digital functions can only be called from a digital context.

## 8.4 Discipline resolution

In general a mixed signal is a collection of nets, some with discrete discipline(s) and some with continuous discipline(s). Additionally, some of the nets can have undeclared discipline(s). Discipline resolution assigns disciplines to those nets whose discipline is undeclared. This is done to control auto-insertion of connect modules, according to the rules embodied in *connect statements*.

The assignments are based on: discipline declarations, ``default_discipline` directives (see Section 3.6), and the hierarchical connectivity of the design. Once all net segments of every mixed signal has been resolved, insertion of connect modules shall be performed.

### 8.4.1 Compatible discipline resolution

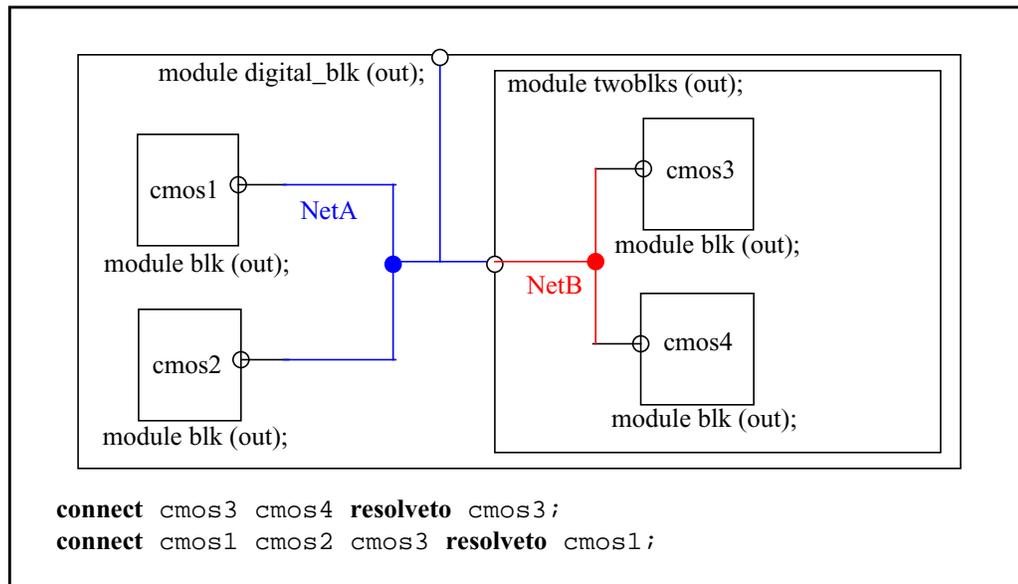
One factor which influences the resolved discipline of a net whose discipline is undeclared is the disciplines of nets to which it is connected via ports; i.e., if multiple compatible disciplines are connected to the same net via multiple ports only one discipline can be assigned to that net. This is controlled by the `resolveto` form of the connect statement; the syntax of this form is described in Section 8.7.2.

If disciplines at the lower connections of ports (where the undeclared net is an upper connection) are among the disciplines in `discipline_list`, the `result_discipline` is the discipline

which is assigned to the undeclared net. If all the nets are of the same discipline, no rule is needed; that discipline becomes the resolved discipline of the net.

*Example:*

In the example shown in Figure 8-2, `NetA` and `NetB` are undeclared interconnects. `NetB` has `cmos3` and `cmos4` at the lower connection ports, while it is an upper connection.



**Figure 8-2 Compatible discipline resolution**

The first connect statement resolves `NetB` to be assigned the discipline `cmos3`.

`NetA` has `cmos1`, `cmos2` and the resulting `cmos3` from module `twoblks` at the lower connection ports; based on the second connect statement, it resolves to be assigned the discipline `cmos1`.

## 8.4.2 Connection of discrete-time disciplines

Ports of discrete-time disciplines (ports where digital signals appear at both upper (`vpiHiConn`) and lower (`vpiLoConn`) connections) shall obey the rules imposed by *IEEE 1364-1995 Verilog HDL* on such connections.

In addition, the real-value nets shall obey the rules imposed by Section 3.5.

## 8.4.3 Connection of continuous-time disciplines

Ports of continuous-time disciplines (ports where analog signals appear at both upper (`vpiHiConn`) and lower (`vpiLoConn`) connections) shall obey the rules imposed in Section 3.8. It shall be an error to connect incompatible continuous disciplines together.

## 8.4.4 Resolution of mixed signals

Once discipline declarations and the ``default_discipline` compiler directive have been applied, if any mixed-signal nets are still undeclared additional resolution is needed. This section provides an additional method for discipline resolution of remaining undeclared nets (to control the auto-insertion of connect modules).

There are two modes for this method of resolution, *basic* (the default) and *detail*, which determine how known disciplines are used to resolve these undeclared nets. For the entire design, undeclared nets shall be resolved at each level of the hierarchy where continuous (analog) has precedence over discrete (digital). The selection of these discipline resolution modes shall be vendor-specific.

More than one conflicting discipline declaration from the same context (in or out of context) for the same hierarchical segment of a signal is an error. In this case, *conflicting* simply means an attempt to declare more than one discipline regardless of whether the disciplines are compatible or not.

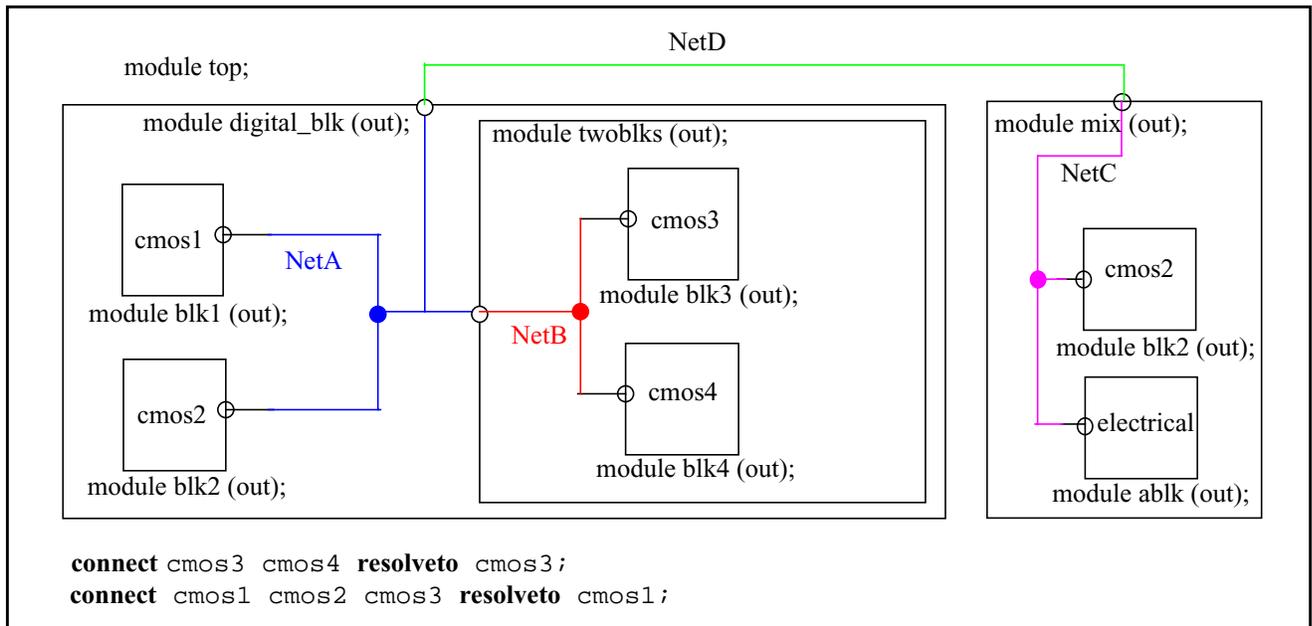
Sample algorithms for the complete discipline resolution process are listed in Annex F.

### 8.4.4.1 Basic discipline resolution algorithm

In this mode (the default), both continuous and discrete disciplines propagate up the hierarchy to meet one another. At each level of the hierarchy where continuous and discrete meet for an undeclared net that net segment is declared continuous. This typically results in connect modules being inserted higher up the design hierarchy.

*Examples:*

In the example shown in Figure 8-3, `NetA`, `NetB`, `NetC`, and `NetD` are undeclared interconnects.



**Figure 8-3 Discipline resolution mode: basic**

Using the basic mode of discipline resolution and the specified **resolveto** connect statements for this example results in the following:

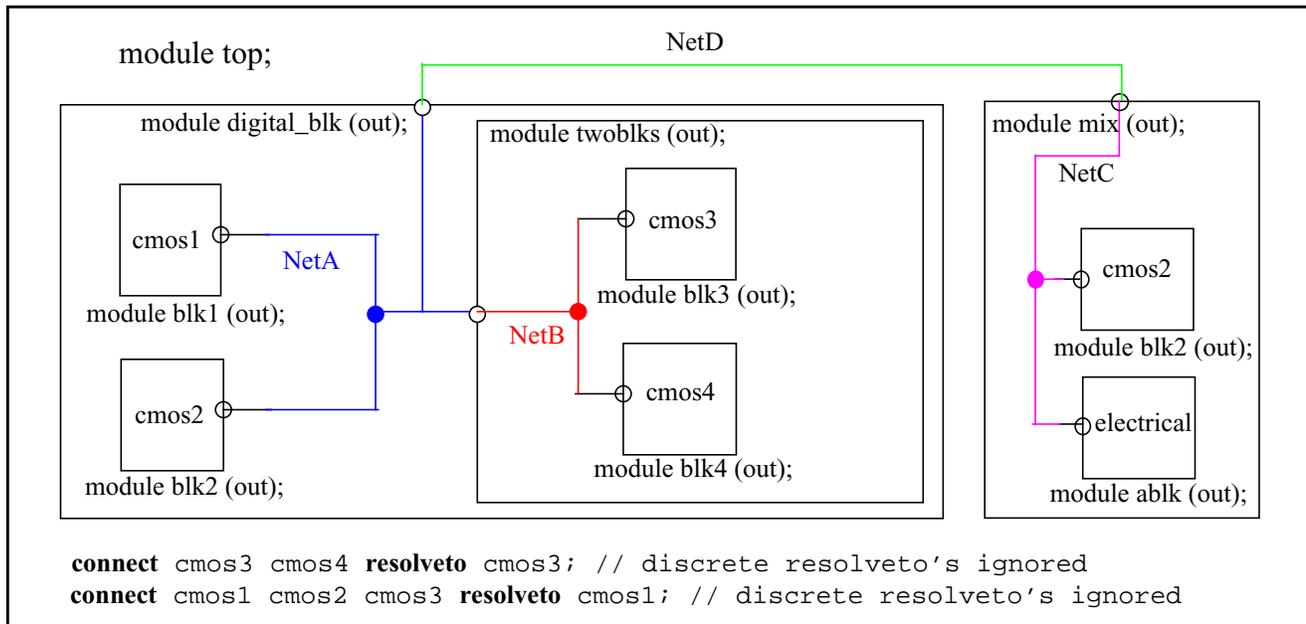
- NetB resolves to `cmos3` based on the first **resolveto** connect statement.
- NetA resolves to `cmos1` based on the second **resolveto** connect statement.
- NetC resolves to `electrical` based on continuous (`electrical`) winning over discrete (`cmos2`).
- NetD resolves to `electrical` based on continuous (`electrical`) winning over discrete (`cmos1`).

#### 8.4.4.2 Detail discipline resolution algorithm

In this mode continuous disciplines propagate up and then back down to meet discrete disciplines. Discrete disciplines do not propagate up the hierarchy. This can result in more connect modules being inserted lower down into discrete sections of the design hierarchy for added accuracy.

*Examples:*

In the example shown in Figure 8-4, `NetA`, `NetB`, `NetC`, and `NetD` are undeclared interconnects.



**Figure 8-4 Discipline resolution mode: detail**

Using the detail mode of discipline resolution for this example results in the following:

- *Continuous up*: NetC resolves to electrical based on continuous (electrical) winning over discrete (cmos2).
- *Continuous up*: NetD resolves to electrical based on continuous (electrical) winning over undeclared.
- *Continuous down*: NetA resolves to electrical based on continuous (electrical) winning over undeclared.
- *Continuous down*: NetB resolves to electrical based on continuous (electrical) winning over undeclared.

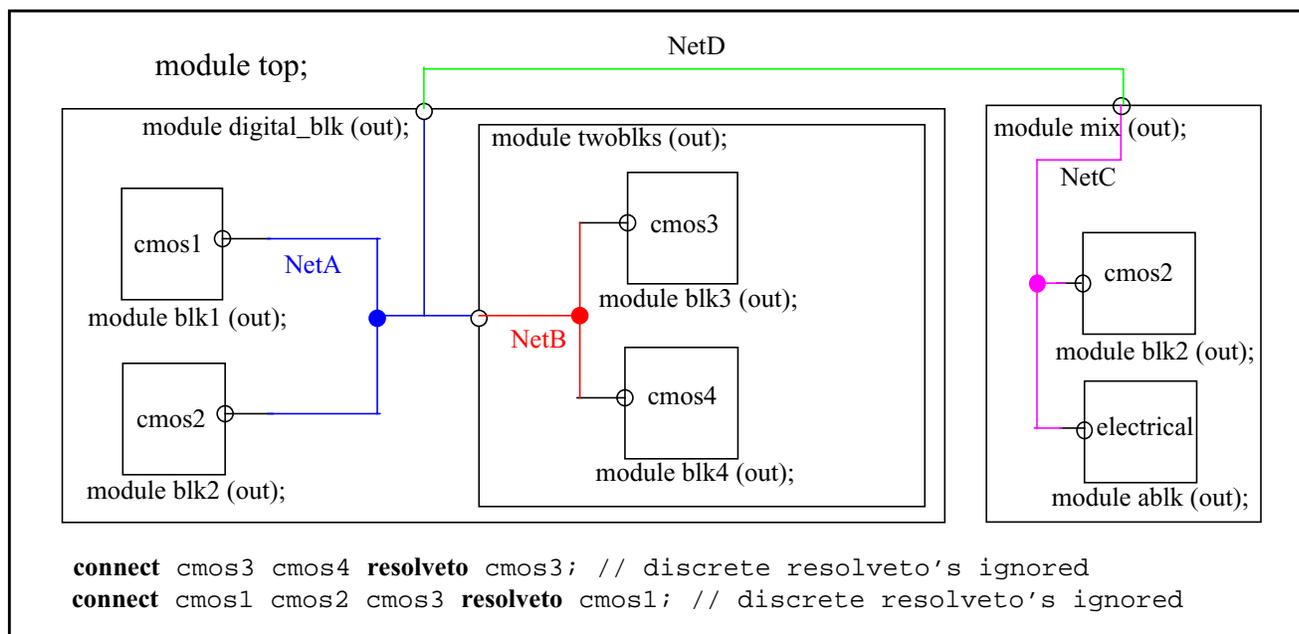
**Note:** The specified **resolveto** connect statements are ignored in this mode unless coercion (see Section 8.8.1) is used.

#### 8.4.4.3 Coercing discipline resolution

Connect module insertion can be affected by *coercion* i.e., declaring disciplines for the interconnect in the hierarchy. If an interconnect is assigned a discipline, that discipline shall be used unless the **resolveto** connect statement overrides the discipline.

*Examples:*

The example in Figure 8-5 shows several effects of coercion on auto-insertion.



**Figure 8-5 Coercion effects on auto- insertion**

**Case1:** NetB is declared as cmos3 (the others are undeclared)

```
cmos3 top.digital_blk.twoblks.NetB
```

*discipline resolution basic:* Same as without coercion.

*discipline resolution detail:* NetB stays cmos3; NetA, NetC, and NetD become electrical.

**Case2:** NetA is declared as cmos1 (the others are undeclared)

*discipline resolution basic:* NetA stays cmos1, NetB is assigned cmos3, and NetC and NetD become electrical.

*discipline resolution detail:* Same as basic mode.

**Case3:** NetC is declared as cmos2 (the others are undeclared)

*discipline resolution basic:* NetC stays cmos2, NetB is assigned cmos3, NetA is assigned cmos1, and NetD is assigned cmos1.

*discipline resolution detail:* Same as basic mode.

## 8.5 Connect modules

Connect modules are automatically inserted to connect the continuous and discrete disciplines (mixed nets) of the design hierarchy together. The continuous and discrete

disciplines of the ports of the connect modules and their directions are used to determine the circumstances in which the module can be automatically inserted.

The connect module is a special form of a module; its definition is shown in Syntax 8-5.

```
connectmodule_declaration ::=
    connectmodule module_identifier ( connectmod_port , connectmod_port ) ;
    [ module_items ]
    endmodule

connectmod_port ::=
    connectmod_port_identifier
```

Syntax 8-5—Syntax for connect modules

## 8.6 Connect module descriptions

The disciplines of mixed nets are determined prior to the connect module insertion phase of elaboration. Connect module declarations with matching port discipline declarations and directions are instantiated to connect the continuous and discrete domains of the mixed net.

The port disciplines define the default type of disciplines which shall be bridged by the connect module. The directional qualifiers of the discrete port determine the default scenarios where the module can be instantiated. The following combinations of directional qualifiers are supported for the continuous and discrete disciplines of a connect module:

continuous	discrete
<b>input</b>	<b>output</b>
<b>output</b>	<b>input</b>
<b>inout</b>	<b>inout</b>

*Examples:*

*Example 1*

```
connectmodule d2a(in, out);
    input in;
    output out;
    logic in;
    electrical out;
    // insert connect module behavioral here
endmodule
```

can bridge a mixed `input` port whose upper connection is compatible with discipline `logic` and whose lower connection is compatible with `electrical`, or a mixed `output` port whose upper connection is compatible with discipline `electrical` and whose lower connection is compatible with `logic`.

*Example 2*

```
connectmodule a2d(out, in);
    output out;
    input in;
    logic out;
    electrical in;
    // insert connect module behavioral here
endmodule
```

can bridge a mixed `output` port whose upper connection is compatible with discipline `logic` and whose lower connection is compatible with `electrical`, or a mixed `input` port whose upper connection is compatible with discipline `electrical` and whose lower connection is compatible with `logic`.

*Example 3*

```
connectmodule bidir(out, in);
    inout out;
    inout in;
    logic out;
    electrical in;
    // insert connect module behavioral here
endmodule
```

can bridge any mixed port whose one connection is compatible with discipline `logic` and whose connection is compatible with `electrical`.

## 8.7 Connect specification statements

Any number of connect modules can be defined. The designer can choose and specialize those in the design via the connect specification statements. The connect specification statements allow the designer to define:

- specification of which connect module is used, including parameterization, for bridging given discrete and continuous disciplines
- overrides for the connect module default disciplines and port directions
- resolution of incompatible disciplines

The syntax for connect specifications is shown in Syntax 8-6.

```

connect_specification ::=
    connectrules connectrule_identifier;
    {connect_spec_item }
    endconnectrules
connect_spec_item ::=
    connect_insertion
    | connect_resolution

```

Syntax 8-6—Syntax for connect specification statements

The two forms of the connect specification statements and their syntaxes are detailed in the following subsections.

### 8.7.1 Connect module auto-insertion statement

The connect module insertion statement declares which connect modules are automatically inserted when mixed nets of the appropriate types are encountered, as shown in Syntax 8-7.

This specifies the connect module *connect\_module\_identifier* is used to determine the mixed nets of the type used in the declaration of the connect module.

There can be multiple connect module declarations of a given (**discrete - continuous**) discipline pair and the connect module specification statement specifies which is to be used in the auto-insertion process. In addition, parameters of the connect module declaration can be specified via the *connect\_attributes*.

```

connect_insertion ::=
    connect connect_module_identifier connect_attributes
    [ [ direction ] discipline_identifier , [ direction ] discipline_identifier ] ;

connect_attributes ::=
    [ connect_mode ] [ #( attribute_list ) ]

connect_mode ::=
    merged
    | split

attribute_list ::=
    attribute
    | attribute_list , attribute

attribute ::=
    .parameter_identifier ( expression )

direction ::=
    input
    | output
    | inout

discipline_list ::=
    discipline_identifier
    | discipline_list , discipline_identifier

```

Syntax 8-7—Syntax for connect configuration statements

Connect modules can be reused for different, but compatible disciplines by specifying different discipline combinations in which the connect module can be used. The form is

```
connect connect_module_identifier connect_attributes discipline_identifier , discipline_identifier ;
```

where the specified disciplines shall be compatible for both the continuous and discrete disciplines of the given connect module.

It is also possible to override the port directions of the connect module, which allows a module to be used both as a unidirectional and bidirectional connect module. This override also aids library based designs by allowing the user to specify the connect rules, rather than having to search the entire library. The form is

```
connect connect_module_identifier connect_attributes direction discipline_identifier ,
    direction discipline_identifier ;
```

where the specified disciplines shall be compatible for both the continuous and discrete disciplines of the given connect module and the specified directions are used to define the type of connect module.

## 8.7.2 Discipline resolution connect statement

The discipline resolution connect statement specifies a single discipline to use during the discipline resolution process when multiple nets with compatible discipline are part of the same mixed net, as shown in Syntax 8-8.

```
connect_resolution ::=
  connect discipline_list resolveto discipline_identifier ;
discipline_list ::=
  discipline_identifier
  | discipline_list , discipline_identifier
```

Syntax 8-8—Syntax for connect configuration resolveto statements

where *discipline\_list* is the list of compatible disciplines and *discipline\_identifier* is the discipline to be used.

### 8.7.2.1 Connect Rule Resolution Mechanism

When there is an exact match for the set of disciplines specified as part of the *discipline\_list*, the resolved discipline would be as per the rule specified in the exact match. When more than one specified rule applies to a given scenario a "Warning" message shall be issued by the simulator and the first match would be used.

When there is no exact fit, then the resolved discipline would be based on the subset of the rules specified. If there is more than one subset matching a set of disciplines, the simulator shall give a "Warning" message and apply the first subset rule that satisfies the current scenario.

The resolved discipline need not be one of the disciplines specified in the discipline list.

The *connect-resolveto* shall not be used as a mechanism to set the disciplines of simulator primitives but used only for discipline resolution.

*Example 1:*

```
connect x,y,a resolveto a;
connect x,y resolveto x;
```

For the above set of connect rule specifications,

disciplines *x,y* would resolve to discipline *x*.

disciplines *x,y,a* would resolve to discipline *a*.

disciplines *y,a* would resolve to discipline *a*.

*Example 2:*

```
connect x,y,a resolveto y;
connect x,y,a resolveto a;
connect x,y,b resolveto b;
```

For the above set of connect rule specifications,

disciplines *x,y* would resolve to discipline *y* with a warning.

disciplines *x,y,a* would resolve to discipline *y* with a warning.

disciplines *y,b* would resolve to *b*.

### 8.7.3 Parameter passing attribute

An attribute method can be used with the connect statement to specify parameter values to pass into the Verilog-AMS HDL connect module and override the default values. Any parameters declared in the connect module can be specified.

*Examples:*

```
connect a2d_035u #(.tt(3.5n), .vcc(3.3));
```

Here each parameter is listed with the new value to be used for that parameter.

### 8.7.4 connect\_mode

This can be used to specify additional segregation of connect modules at each level of the hierarchy. Setting *connect\_mode* to **split** or **merged** defines whether all ports of a common discrete discipline and port direction share an connect module or have individual connect modules.

*Examples:*

```
connect a2d_035u split #(.tt(3.5n), .vcc(3.3));
```

Here each digital port has a separate connect module.

## 8.8 Automatic insertion of connect modules

Automatic insertion of connect modules is performed when signals and ports with continuous time domain and discrete time domain disciplines are connected together. The connect module defines the conversion between these different disciplines.

An instance of the connect module shall be inserted across any mixed port that matches the rule specified by a **connect** statement. Rules for matching connect statements with ports take into account the port direction (see Section 8.8.1) and the disciplines of the signals connected to the port.

Each `connect` statement designates a module to be a connect module. When two disciplines are specified in a connect statement, one shall be discrete and the other continuous.

*Examples:*

```

module dig_inv(in, out);
  input in;
  output out;
  reg out;
  logic in, out;

  always begin
    out = #10 ~in;
  end
endmodule

module analog_inv(in, out);
  input in;
  output out;
  electrical in, out;
  parameter real vth = 2.5;
  real outval;

  analog begin
    if (V(in) > vth)
      outval = 0;
    else
      outval = 5 ;
    V(out) <+ transition(outval);
  end
endmodule

module ring;

  dig_inv d1 (n1, n2);
  dig_inv d2 (n2, n3);
  analog_inv a3 (n3, n1);
endmodule

connectmodule elect_to_logic(el,cm);
  input el;
  output cm;
  reg cm;
  electrical el;
  logic cm;

  always
    @(cross(V(el) - 2.5, 1))
      cm = 1;

  always
    @(cross(V(el) - 2.5, -1))
      cm = 0;

```

```

endmodule

connectmodule logic_to_elect(cm,el);
    input cm;
    output el;
    logic cm;
    electrical el;

    analog
        V(el) <+ transition((cm == 1) ? 5.0 : 0.0);

endmodule

connectrules mixedsignal;
    connect elect_to_logic;
    connect logic_to_elect;
endconnectrules

```

Here two modules, `elect_to_logic` and `logic_to_elect`, are specified as the connect modules to be automatically inserted whenever a signal and a module port of disciplines `electrical` and `logic` are connected.

Module `elect_to_logic` converts signals on port `out` of instance `a3` to port `in` of instance `d1`. Module `logic_to_elect` converts the signal on port `out` of instance `d2` to port `in` of instance `a3`.

### 8.8.1 Connect module selection

The selection of a connect module for automatic insertion depends upon the disciplines of nets connected together at ports. It is, therefore, a post elaboration operation since the signal connected to a port is only known when the module in which the port is declared has been instantiated.

Auto-insertion of connect modules is done hierarchically. The connect modules are inserted based on the net disciplines and ports at each level of the hierarchy. The *connect\_mode* **split** and **merged** are applied at each level of the hierarchy. This insertion supports the ability to coerce the placement of connect modules by declaring the disciplines of interconnect.

*Example:*

Figure 8-6 shows an example of auto-insertion with coercion.

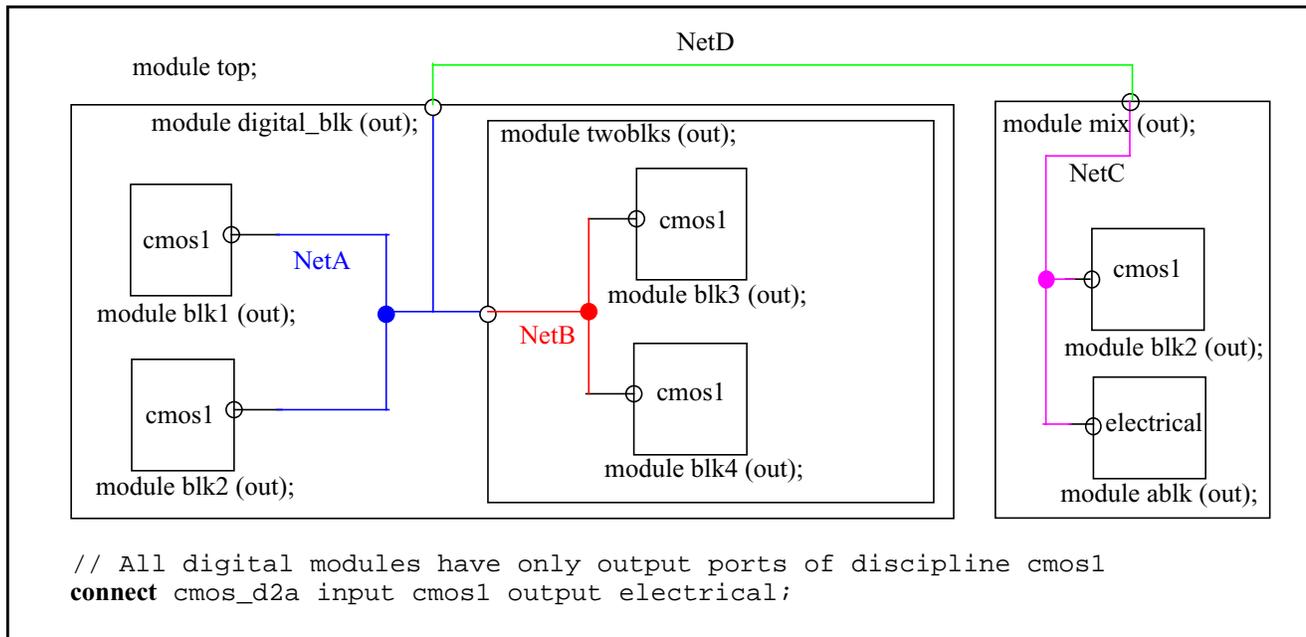


Figure 8-6 Auto-insertion with coercion

**Case1:** All interconnects are undeclared

*discipline resolution basic:*

*merged:* d2a at top.mix.blk2 and d2a at top.digital\_blk (two connect modules).

*split:* Same as merged.

*discipline resolution detail:*

*merged:* d2a at top.mix.blk2, d2a at top.digital\_blk.(blk1-blk2), and d2a at top.digital\_blk.twoblks (three connect modules).

*split:* d2a at each of the five cmos1 blocks.

**Case2:** If NetB is declared as cmos1 and the remaining interconnect is undeclared

*discipline resolution basic:*

*merged:* d2a at top.mix.blk2 and d2a at top.digital\_blk (two connect modules).

*split:* Same as merged.

*discipline resolution detail:*

*merged:* d2a at top.mix.blk2, d2a at top.digital\_blk.(blk1-blk2), and d2a at top.digital\_blk.twoblks (three connect modules).

*split:* d2a at top.mix.blk2, d2a at top.digital\_blk.blk1, d2a at top.digital\_blk.blk2, and d2a at top.digital\_blk.twoblks (four connect modules).

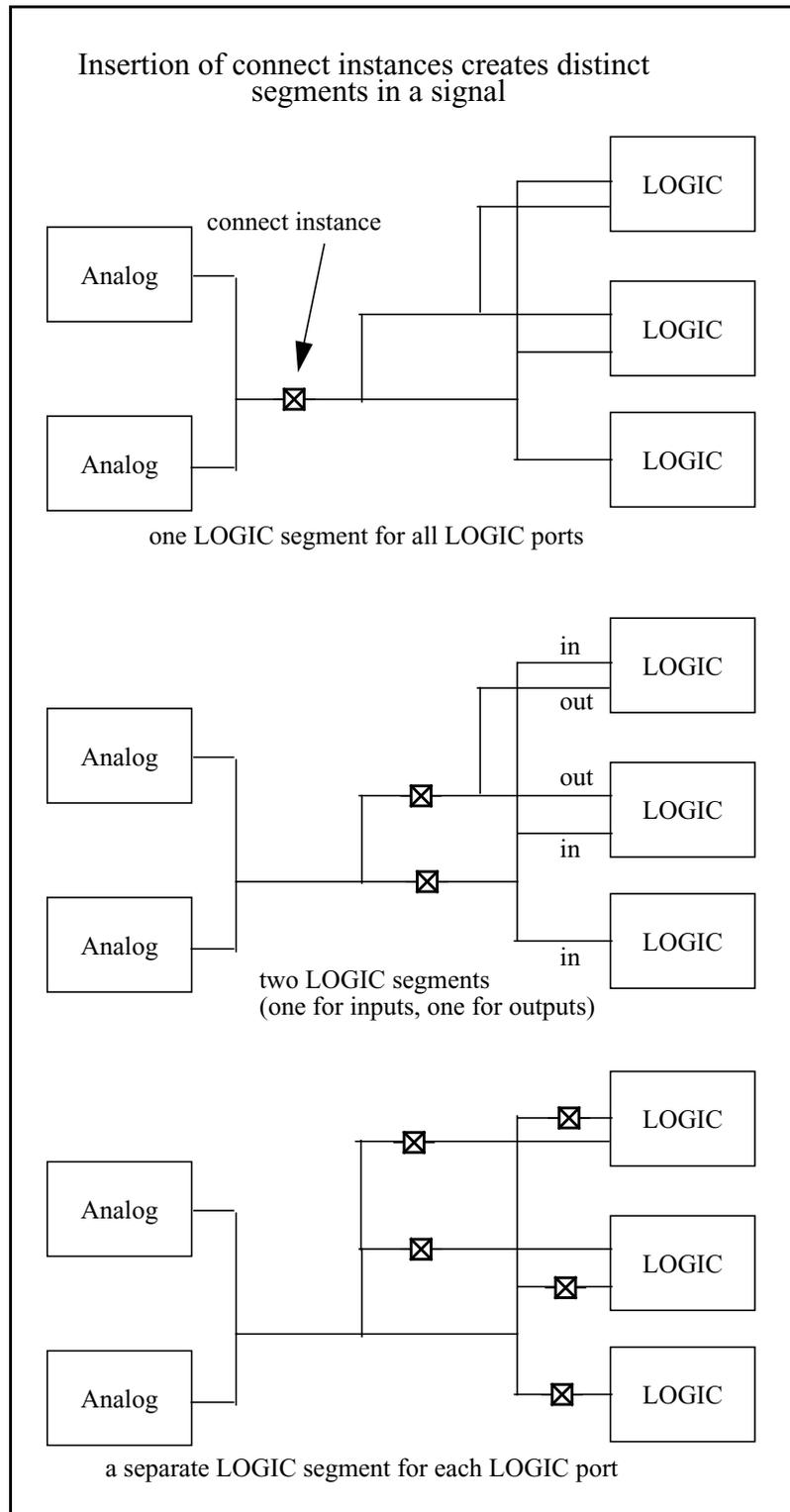
## 8.8.2 Signal segmentation

Once a connect module has been selected it can not be inserted until it can be determined whether there should be one connect module per port or one connect module for all the ports on the net of a signal which match a given `connect` statement. Inserting multiple copies of the same connect module on one signal (i.e., between the signal and the multiple ports) has the effect of creating distinct segments of the signal with the same discipline at that level of the hierarchy.

This segmentation of the signal which connects ports is only performed in the case of digital ports (i.e., ports with discrete-time domain or digital discipline). For analog (or continuous-time domain) disciplines, it is not desirable to segment the signal between the ports; i.e, there shall never be more than one analog node representing a signal. However, it can be desirable for the simulator's internal representation of the signal to consist of various separate digital segments, each with its own connect module.

*Examples:*

Figure 8-7 shows how to model the loading effect of each individual digital port on the analog node.



**Figure 8-7 Signal segmentation by connect modules**

### 8.8.3 connect\_mode parameter

This parameter can be used in the `connect` statement to direct the segmentation of the signal at each level of the hierarchy, which can occur while inserting a connect module. It can be one of two predefined values, **split** or **merged**. The default is **merged**.

The `connect_mode` indicates how input, output, or inout ports of the given discipline shall be combined for the purpose of inserting connect modules. It is applied when there is more than one port of discrete discipline on a net of a signal where the `connect` statement applies.

#### 8.8.3.1 merged

This instructs the simulator to try to group all ports (whether they are input, output, or inout) and to use just one connector module, provided the module is the same.

*Example:*

Figure 8-8 illustrates the effect of the **merged** attribute.

Connection of the `electrical` signal to the `t1` inout ports and `t1` input ports results in a single connector module, `bidir`, being inserted between the ports and the `electrical` signal. The `t1` output ports are merged, but with a different connect module; i.e., there is one connector module inserted between the `electrical` signal and all of the `t1` output ports.

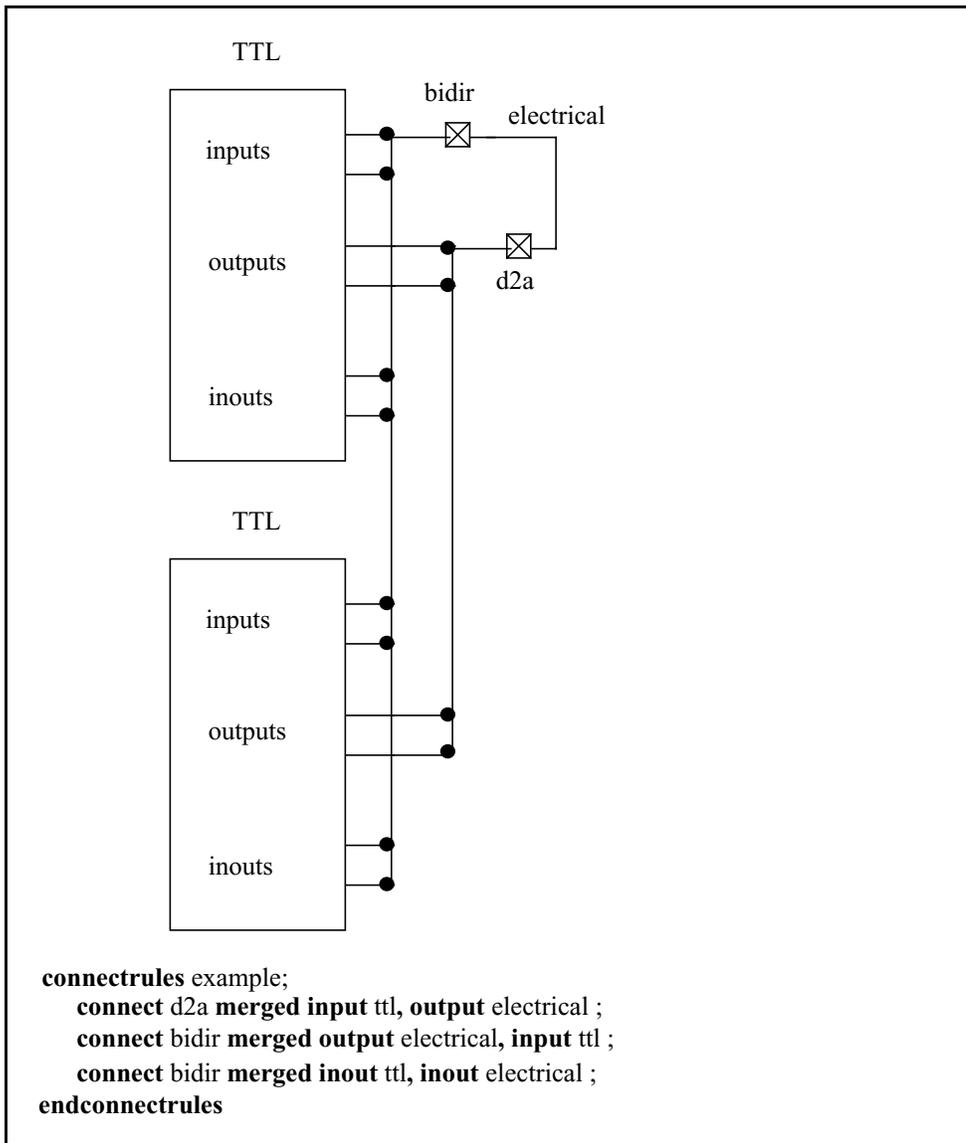


Figure 8-8 Connector insertion using merged

### 8.8.3.2 split

If more than one input port is connected at a net of a signal, using `split` forces there to be one connect module for each port which converts between the net discipline and the port discipline. In this way, the net connecting to the ports is segmented by the insertion of one connect module for each port.

*Examples:*

*Example 1*

```
connect elect_to_logic split;
```

This `connect` statement specifies the module `elect_to_logic` shall be split across the discrete module ports:

- if an input port has `logic` discipline and the signal connecting to the port has `electrical` discipline, or
- if an output port has `electrical` discipline and the signal connecting to the port has `logic` discipline.

### *Example 2*

In Figure 8-9, the connections of an `electrical` signal to `t1` output ports results in a distinct instance of the `d2a` connect module being inserted for each output port. This is mandated by the `split` parameter.

Connection of the `electrical` signal to `t1` input ports results in a single instance of the `a2d` connect module being inserted between the `electrical` signal and all the `t1` input ports. This is mandated by `merged` parameter. This behavior is also seen for the `t1` inout ports where the `merged` parameter is used.

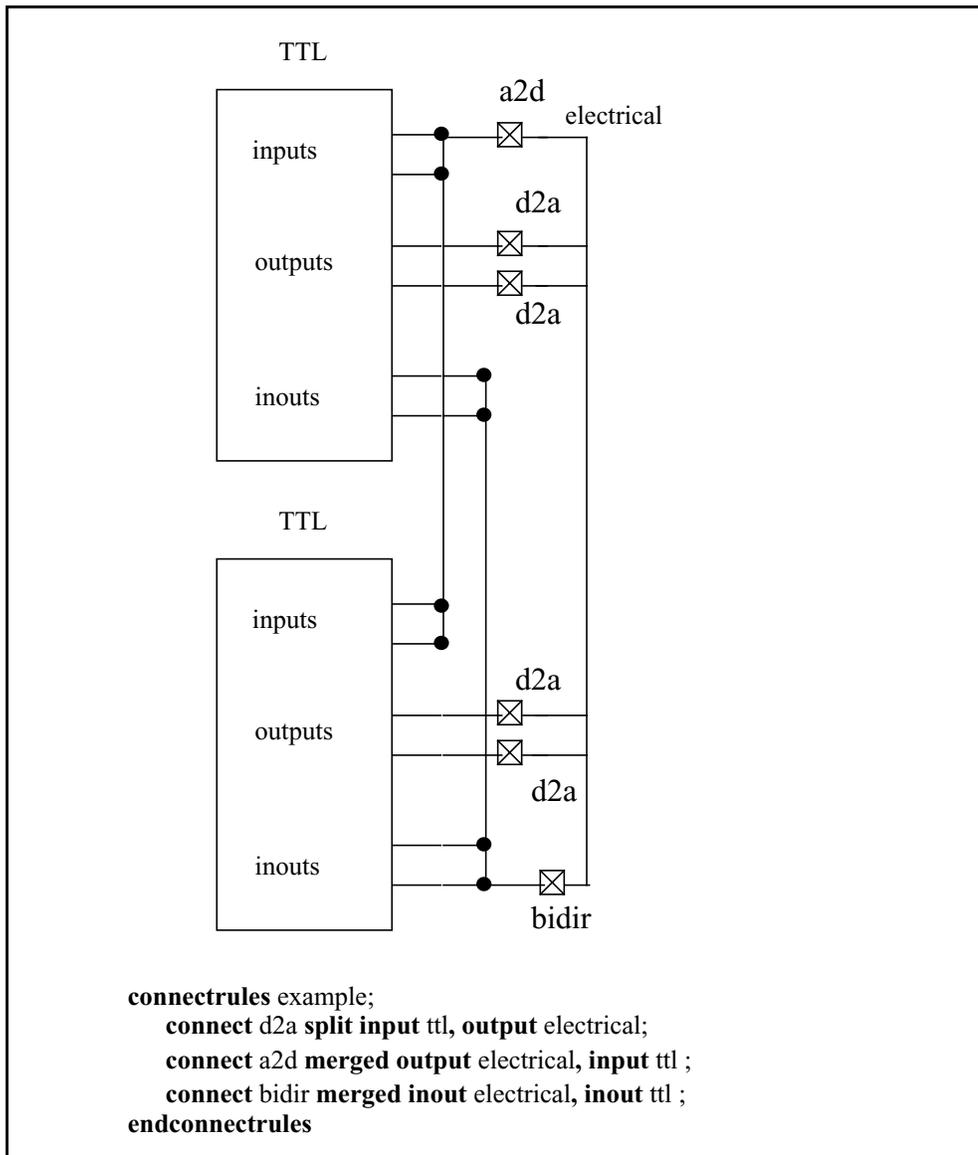


Figure 8-9 Connect module insertion with signal segmentation

### Example 3

This example:

```
connect cmosA2d split #(.r(30k) input electrical, output cmos02u;
```

performs three functions:

1. connects an instance of `cmosA2d` module between a signal with `electrical` discipline and the input port with `cmos02u` discipline, or an output port with `electrical` discipline and the signal with `cmos02u` discipline;

2. sets the value of the parameter `r` to 30k; and
3. uses one module instance for each input port.

If there are many output ports where this rule applies, by definition there is no segmentation of the signal between these ports, since the ports have discipline `electrical` (an analog discipline).

#### Example 4

This last example:

```
connect cmosA2d merged #(.r(15k) input electrical, output cmos04u;
does three things:
```

1. connects an instance of `cmosA2d` module between a signal with electrical discipline and an input port with `cmos04u` discipline, or an output port with `electrical` discipline and a signal with `cmos4u` discipline;
2. sets the value of the parameter `r` to 15k; and
3. uses one module instance regardless of the number of ports.

### 8.8.4 Rules for driver-receiver segregation and connect module selection and insertion

Driver-receiver segregation and connect module insertion is a post elaboration operation. It depends on a complete hierarchical examination of each signal in the design, i.e., an examination of the signal in all the contexts through which it passes. If the complete hierarchy of a signal is digital, i.e., the signal has a digital discipline in all contexts through which it passes, it is a *digital signal* rather than a mixed signal. Similarly, if the complete hierarchy of a signal is analog, it is an *analog signal* rather than a mixed signal. Rules for driver-receiver segregation and connect module insertion apply only to *mixed signals*, i.e., signals which have an analog discipline in one or more of the contexts through which they pass and a digital discipline in one or more of the contexts. In this case, *context* refers to the appearance of a signal in a particular module instance.

For a particular signal, a module instance has a digital context if the signal has a digital discipline in that module or an analog context if the signal has an analog discipline. The appearance of a signal in a particular context is referred to as a *segment* of the signal. In general, a *signal* in a fully elaborated design consists of various segments, some of which can be analog and some of which can be digital.

A *port* represents a connection between two net segments of a signal. The context of one of the net segments is an instantiated module and the context of the other is the module which instantiates it. The segment in the instantiated module is called the *lower* or *formal connection* and the segment in the instantiating module is the *upper* or *actual connection*. A connection element is selected for each port where one connection is analog and the other digital.

The following rules govern driver-receiver segregation and connect module selection. These rules apply only to mixed signals.

1. A mixed signal is represented in the analog domain by a single node, regardless of how its analog contexts are distributed hierarchically.
2. Digital drivers of mixed signals are segregated from receivers so the digital drivers contribute to the analog state of the signal and the analog state determines the value seen by the receivers.
3. A connection shall be selected for a port only if one of the connections to the port is digital and the other is analog. In this case, the port shall match one (and only one) connect statement. The module named in the connect statement is the one which shall be selected for the port.

Once connect modules have been selected, they are inserted according to the `connect_mode` parameter in the pertinent connect statements. These rules apply to connect module insertion:

1. The connect mode of a port for which a connect module has been selected shall be determined by the value of the `connect_mode` parameter of the `connect` statement which was used to select the connect module.
2. The connect module for a port shall be instantiated in the context of the ports upper connection.
3. All ports connecting to the same signal (upper connection), sharing the same connect module, and having `merged` parameter shall share a single instance of the selected connect module.
4. All other ports shall have an instance of the selected connect module, i.e., one connect module instance per port.

### 8.8.5 Instance names for auto-inserted instances

Parameters of auto-inserted connect instances can be set on an instance-by-instance basis with the use of the `defparam` statement. This requires predictable instance names for the auto-inserted modules.

The following naming scheme is employed to unambiguously distinguish the connector modules for the case of auto-inserted instances.

1. **merged**  
In the merged case, one or more ports have a given discipline at their bottom connection, call it `BottomDiscipline`, and a common signal, call it `SigName`, of another discipline at their top connection. A single connect module, call it `ModuleName`, is placed between the top signal and the bottom signals. In this case,

the instance name of the connect module is derived from the signal name, module name, and the bottom discipline:

```
SigName__ModuleName__BottomDiscipline
```

## 2. **split**

In the split case, one or more ports have a given discipline at their bottom connection and a common signal of another discipline, call it `TopDiscipline`, at their top connection. One module instance is instantiated for each such port. In this case, the instance name of the connect module is

```
SigName__InstName__PortName
```

where `InstName` and `PortName` are the local instance name of the port and its instance respectively.

**Note:** The `__` between the elements of these generated instance names is a double underscore.

### 8.8.5.1 Port names for Verilog built-in primitives

In the cases of instances of modules and instances of UDPs, port names are well defined. In these cases the port name is the name of the signal at the lower connection of the port. In the case of built-in digital primitives, however, IEEE 1364-2001 does not define port names. In order to support the unique naming of auto inserted connect modules and the ability to override the parameters of those connect modules, built-in digital primitives ports will be provided with predictable names. These names are only for the purpose of naming the connect modules and do not define actual port names. These port names may not be used to instantiate or to do access of these primitives.

The following naming conventions shall be used when generating connect module instance names that are connected to built-in digital primitives.

1. For N-input gates (`and`, `nand`, `nor`, `or`, `xnor`, `xor`) the output will be named `out`, and the inputs reading from left to right will be `in1`, `in2`, `in3`, and so forth.
2. For N-output gates (`buf`, `not`) The input will be named `in`, and the outputs reading from left to right will be named `out1`, `out2`, `out3`, and so forth.
3. For 3 port MOS switches (`nmos`, `pmos`, `rnmos`, `rpmos`) the ports reading from left to right will be named `source`, `drain`, `gate`.
4. For 4 port MOS switches (`cmos`, `rcmos`) the ports reading from left to right will be named `source`, `drain`, `ngate`, `pgate`.
5. For bidirectional pass switches (`tran`, `tranif1`, `tranif0`, `rtran`, `rtranif1`, `rtranif0`) the ports reading from left to right will be named `source`, `drain`, `gate`.
6. For single port primitives (`pullup`, `pulldown`) the port will be named `out`.

## 8.9 Driver-receiver segregation

If the hierarchical segments of a signal are all digital or all analog, the signal is not a mixed signal and the internal representation of the signal does not differ from that of a purely digital or an analog signal.

If the signal has both analog and digital segments in its hierarchy, it is a mixed signal. In this case, the appropriate conversion elements are inserted, either manually or automatically, based on the following rules.

- All the analog segments of a mixed signal are representations of a single analog node.
- Each of the non-contiguous digital segments of a signal shall be represented internally as a separate digital signal, with its own state.
- Each non-contiguous digital segment shall be segregated into the collection of drivers of the segment and the collection of receivers of the segment.

In the digital domain, signals can have drivers and receivers. A driver makes a contribution to the state of the signal. A receiver accesses, or reads, the state of the signal. In a pure digital net, i.e., one without an analog segment, the simulation kernel resolves the values of the drivers of a signal and it propagates the new value to the receivers by means of an event when there is a change in state.

In the case of a mixed net, i.e., one with digital segments and an analog segment, it can be useful to propagate the change to the analog simulation kernel, which can then detect a threshold crossing, and then propagate the change in state back to the digital kernel. This, among other things, allows the simulation to account for rise and fall times caused by analog parasitics.

Within digital segments of a mixed-signal net, drivers and receivers of ordinary modules shall be segregated, so transitions are not propagated directly from drivers to receivers, but propagate through the analog domain instead. In this case, the drivers and receivers of connect modules shall be oppositely segregated; i.e., the connect module drivers shall be grouped with the ordinary module receivers and the ordinary module drivers shall be grouped with the connect module receivers.

Thus, digital transitions are propagated from drivers to receivers by way of analog (through using connect module instances). Figure 8-10 and Figure 8-11 show driver-receiver segregation in modules having bidirectional and unidirectional ports, respectively.

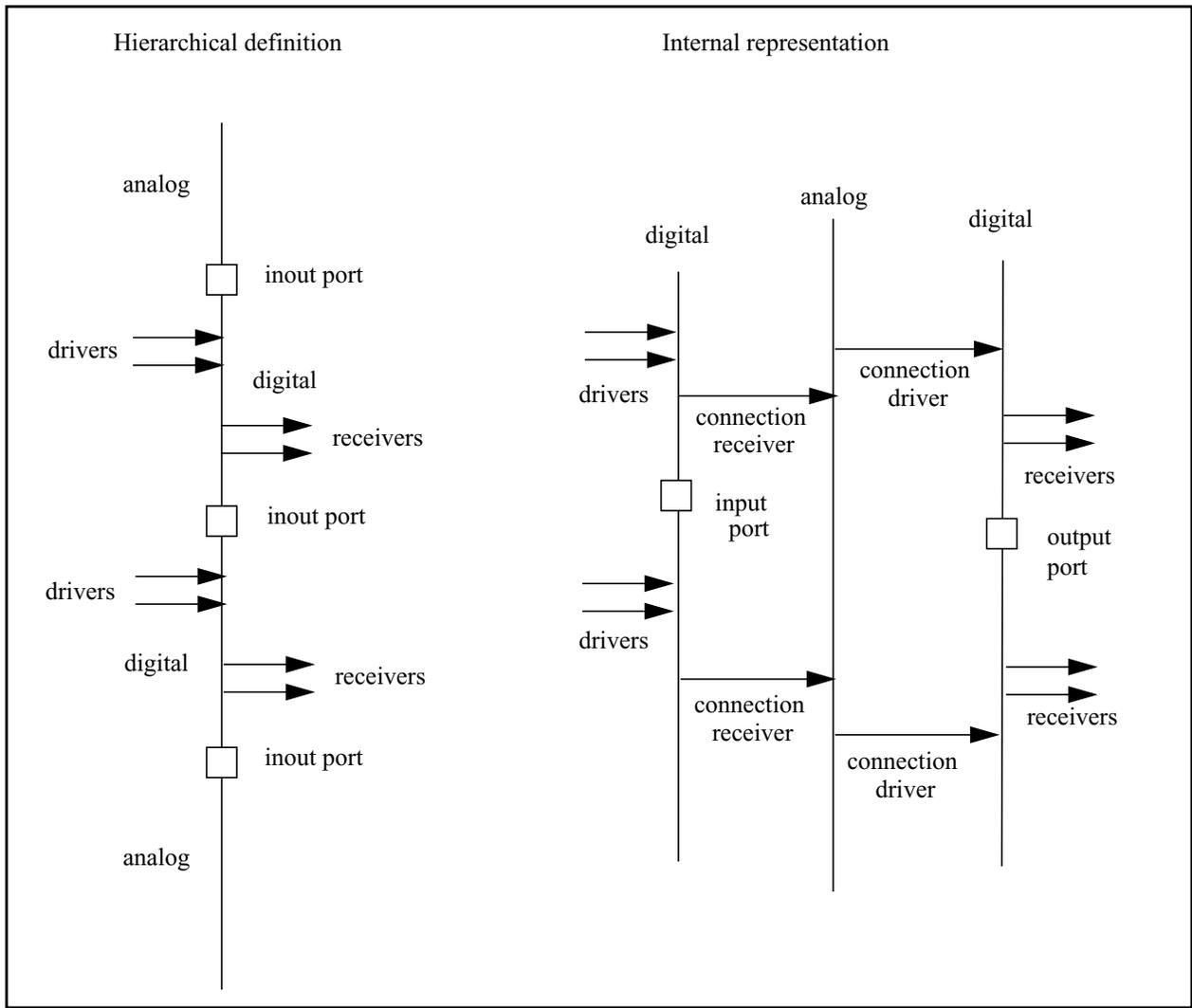


Figure 8-10 Driver-receiver segregation in modules with bidirectional ports

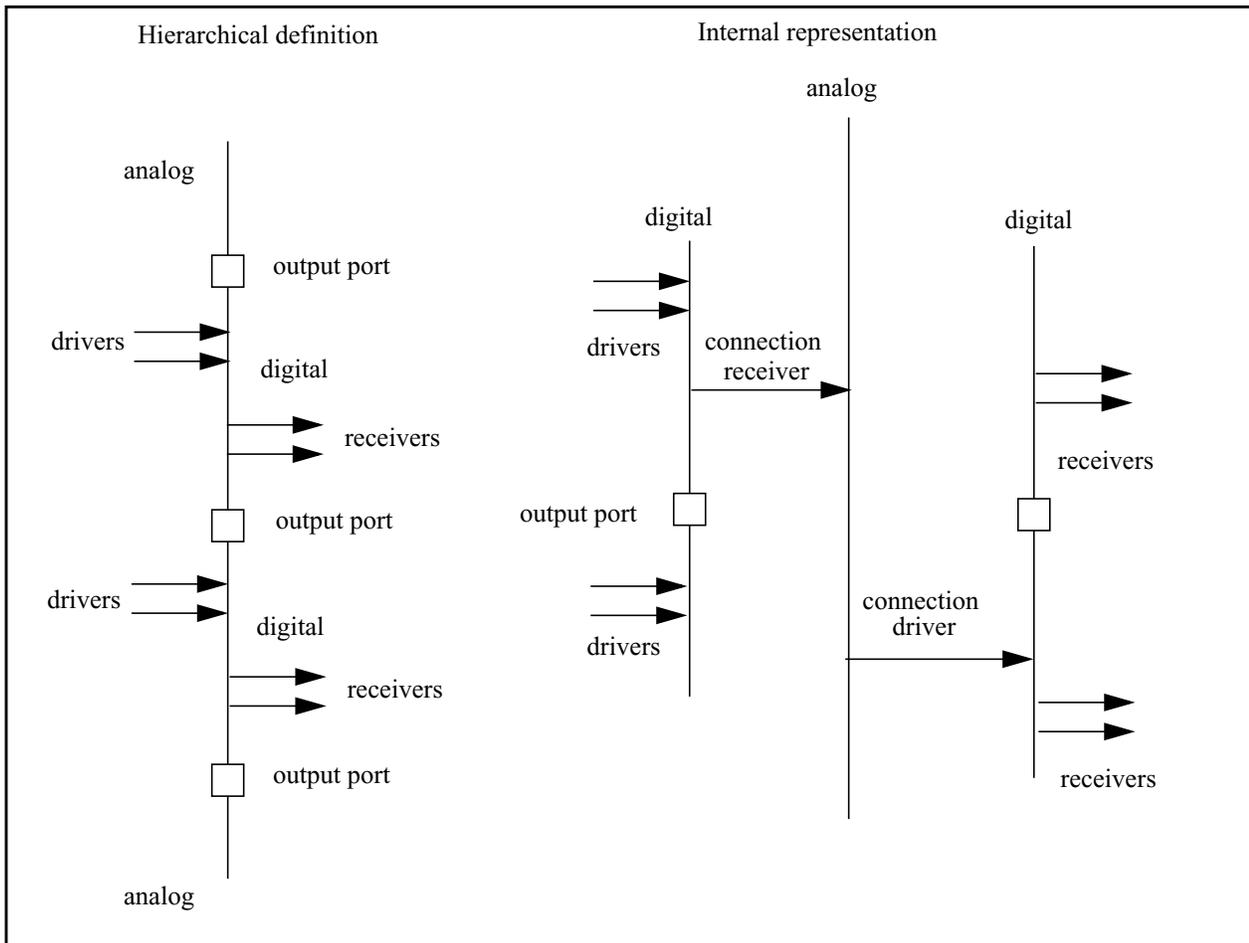


Figure 8-11 Driver-receiver segregation in modules with unidirectional ports

## 8.10 Driver access and net resolution

Access to individual drivers and net resolution is necessary for accurate implementation of connect modules (see Section 8.5). A *driver* of a signal is a process which assigns a value to the signal, or a connection of the signal to an output port of a module instance or simulation primitive. The driver access functions described here only access drivers found in ordinary modules and not to those found in connect modules. Driver access functions can only be called from connect modules.

A signal can have any number of drivers; for each driver the current status, value, and strength can be accessed.

### 8.10.1 **\$driver\_count**

**\$driver\_count** returns an integer representing the number of drivers associated with the signal in question. The syntax is shown in Syntax 8-9.

```
driver_count_function ::=
    $driver_count ( signal_name )
```

*Syntax 8-9—Syntax for \$driver\_count*

The drivers are arbitrarily numbered from 0 to  $N-1$ , where  $N$  is the total number of ordinary drivers contributing to the signal value. For example, if this function returns a value 5 then the signal has five drivers numbered from 0 to 4.

### 8.10.2 **\$driver\_state**

**driver\_state** returns the current value contribution of a specific driver to the state of the signal. The syntax is shown in Syntax 8-10.

```
driver_state_function ::=
    $driver_state ( signal_name , driver_index )
```

*Syntax 8-10—Syntax for \$driver\_state*

*driver\_index* is an integer value between 0 and  $N-1$ , where  $N$  is the total number of drivers contributing to the signal value. The state value is returned as 0, 1, x, or z.

### 8.10.3 **\$driver\_strength**

**driver\_strength** returns the current strength contribution of a specific driver to the strength of the signal. The syntax is shown in Syntax 8-11.

```
driver_strength_function ::=
    $driver_strength ( signal_name , driver_index )
```

*Syntax 8-11—Syntax for \$driver\_strength*

*driver\_index* is an integer value between 0 and  $N-1$ , where  $N$  is the total number of drivers contributing to the signal value. The strength value is returned as two strengths, Bits 5-3 for *strength0* and Bits 2-0 for *strength1* (see *IEEE 1364-1995 Verilog HDL*, sections 7.10 and 7.11).

If the value returned is 0 or 1, `strength0` returns the high-end of the strength range and `strength1` returns the low-end of the strength range. Otherwise, the strengths of both `strength0` and `strength1` is defined as shown in Figure 8-12 below.

strength0									strength1								
Bits	7 Su0	6 St0	5 Pu0	4 La0	3 We0	2 Me0	1 Sm0	0 HiZ0	0 HiZ1	1 Sm1	2 Me1	3 We1	4 La1	5 Pu1	6 St1	7 Su1	Bits
B5	1	1	1	1	0	0	0	0	0	0	0	0	1	1	1	1	B2
B4	1	1	0	0	1	1	0	0	0	0	1	1	0	0	1	1	B1
B3	1	0	1	0	1	0	1	0	0	1	0	1	0	1	0	1	B0

Figure 8-12 Strength value mapping

#### 8.10.4 driver\_update

The status of drivers for a given signal can be monitored with the event detection keyword `driver_update`. It can be used in conjunction with the event detection operator `@` to detect updates to any of the drivers of the signal.

*Examples:*

```
always @(driver_update clock)
    statement;
```

causes the `statement` to execute any time a driver of the signal `clock` is updated. Here, an update is defined as the addition of a new pending value to the driver. This is true whether or not there is a change in the resolved value of the signal.

#### 8.10.5 Receiver net resolution

As a result of driver receiver segregation, the drivers and receivers are separated so that any analog connected to a mixed net has the opportunity to influence the value driving the digital receivers. Since a single digital port is used in the connect module, the user must specify the value that the receivers will see. By not specifying the receiver value directly in the connect module driver, receiver segregation will be ignored, which is the default case. This assignment of the receiver value is done via the `assign` statement in which the digital port will be used to read the driver values as well as to set the receiver value.

1. The default is equivalent of `assign d_receivers = d_drivers ;`

Where the value passed to the receivers through driver receiver segregation is the value being driven without delay or any impact from analog connections to the net. This is essentially bypassing driver receiver segregation.

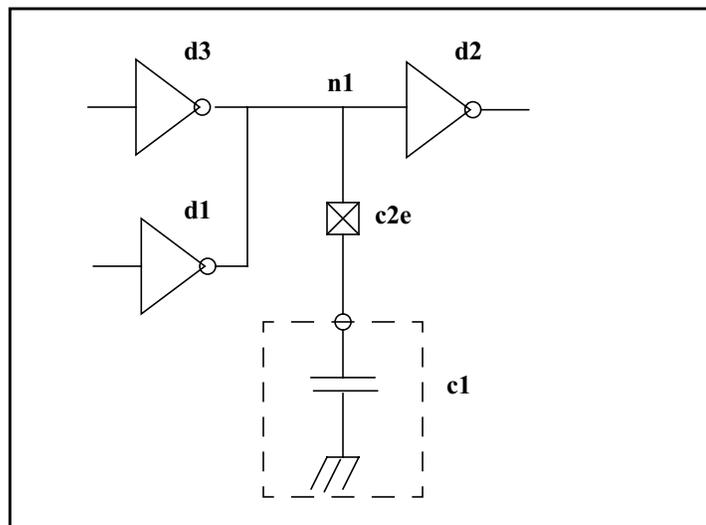
2. Anything else is done explicitly, such as:

```
reg out; // value of out determined in CM, see example
// Section 8.10.6
assign d = out;
```

In this case, the digital port of the connect module will drive the receivers with a value determined in the connect module. This value may potentially be different from the value of the drivers of the connect module digital port.

### 8.10.6 Connect module example using driver access functions

Using the example shown in Figure 8-13, a connect module can be created using driver access functions to accurately model the effects of multiple drivers on an interface.



**Figure 8-13 Driver-receiver segregation connect module example**

The connect module below takes advantage of much of the mixed-signal language including driver access functions. This module effectively adds another parallel resistor from output to ground whenever a digital output connected to the net goes high, and another parallel resistor from output to rail (*supply*) whenever a digital output connected to the net goes low. If this is used as the connect module in Figure 8-13, not only is the delay from digital outputs to the digital input a function of the value of the capacitor, for a given capacitance it takes approximately half the time (since two gates are driving the signal rather than one).

```
connectmodule c2e(d,a);
input d;
output a;

logic d;
electrical a, rail, gnd;
```

```

reg out;
ground gnd;
branch (rail,a)pull_up;
branch (a,gnd)pull_down;
branch (rail,gnd)power;
parameter real impedance0 = 120.0;
parameter real impedance1 = 100.0;
parameter real impedanceOff = 1e6;
parameter real vt_hi = 3.5;
parameter real vt_lo = 1.5;
parameter real supply = 5.0;
integer i, num_ones, num_zeros;

assign d=out;
initial begin
    num_ones = 0;
    num_zeros = 0;
end

always @(driver_update(d)) begin
    num_ones = 0;
    num_zeros = 0;
    for ( i = 0; i < $driver_count(d); i=i+1)
        if ( $driver_state(d,i) == 1 )
            num_ones = num_ones + 1;
        else
            num_zeros = num_zeros + 1;
    end

    always @(cross(V(a) - vt_hi, -1) or cross(V(a) - vt_lo, +1))
        out = 1`bx;
    always @(cross(V(a) - vt_hi, +1))
        out = 1`b1;
    always @(cross(V(a) - vt_lo, -1))
        out = 1`b0;

    analog begin
        // Approximately one impedance1 resistor to rail per high output
        // connected to the digital net
        V(pull_up) <+ 1/((1/impedance1)*num_ones+(1/impedanceOff)) *
            I(pull_up);
        // Approximately one impedance0 resistor to ground per low output
        // connected to the digital net
        V(pull_down) <+ 1/((1/impedance0)*num_zeros+(1/impedanceOff)) *
            I(pull_down);
        V(power) <+ supply;
    end
endmodule

```

## 8.11 Supplementary driver access functions

The following driver access functions are provided for access to digital events which have been scheduled onto a driver but might not have matured by the current simulation time.

These functions can be used to create analog waveforms which cross a specified threshold at the same time the digital event matures, thus providing accurate registration of analog and digital representations of a signal. This assumes there is at least as long a delay in the maturation of the digital signal as the required rise/fall times of the analog waveform.

**Note:** Because the scheduled digital events can be scheduled with an insufficient delay or cancelled before they mature, be careful when using these functions.

### 8.11.1 \$driver\_delay

**\$driver\_delay** returns the delay, from current simulation time, after which the pending state or strength becomes active. If there is no pending value on a signal, it returns the value minus one (-1.0). The syntax is shown in Syntax 8-12.

```
driver_delay_function ::=
    $driver_delay ( signal_name , driver_index )
```

*Syntax 8-12—Syntax for \$driver\_delay*

*driver\_index* is an integer value between 0 and  $N-1$ , where  $N$  is the total number of drivers contributing to the signal value. The returned delay value is a real number, which is defined by the ``timescale` for that module where the call has been made. The fractional part arises from the possibility of a driver being updated by an A2D event off the digital timeticks.

### 8.11.2 \$driver\_next\_state

**\$driver\_next\_state** returns the pending state of the driver, if there is one. If there is no pending state, it returns the current state. The syntax is shown in Syntax 8-13.

```
driver_next_state_function ::=
    $driver_next_state ( signal_name , driver_index )
```

*Syntax 8-13—Syntax for \$driver\_next\_state*

*driver\_index* is an integer value between 0 and  $N-1$ , where  $N$  is the total number of drivers contributing to the signal value. The pending state value is returned as 1'b0, 1'b1, 1'bx, or 1'bz.

### 8.11.3 \$driver\_next\_strength

**\$driver\_next\_strength** returns the strength associated with the pending state of the driver, if there is one. If there is no pending state, it returns the current strength. The syntax is shown in Syntax 8-14.

```
driver_next_strength_function ::=
    $driver_next_strength ( signal_name , driver_index )
```

Syntax 8-14—Syntax for \$ driver\_next\_strength

*driver\_index* is an integer value between 0 and  $N-1$ , where  $N$  is the total number of drivers contributing to the signal value. The pending strength value is returned as an integer between 0 and 7.

### 8.11.4 \$driver\_type

**\$driver\_type** returns an integer value with its bits set according to the system header file “driver\_access.vams” (refer to Annex D for the header file) for the driver specified by the *signal\_name* and the *driver\_index*. Connect modules for digital to analog conversion can use the returned information to help minimize the difference between the digital event time and the analog crossover when the user swaps between coding styles and performs backannotation<sup>1</sup>. A simulator that cannot provide proper information for a given driver type should return 0 (‘DRIVER\_UNKNOWN’). All drivers on *wor* and *wand* nets will have a bit set indicating such, and any extra drivers added by the kernel for pull-up or pull-down will be marked as belonging to the kernel. The syntax is shown in Syntax 8-15.

```
driver_type_function ::=
    $driver_type( signal_name , driver_index )
```

Syntax 8-15—Syntax for \$ driver\_type

Digital primitives (like nand and nor gates) should always provide data about their scheduled output changes; i.e., a gate with a 5ns delay should provide 5ns of look-ahead.

1. SDF backannotation will not change which D2A is inserted.

Behavioral code with blocking assigns cannot provide look-ahead, but non-blocking assigns with delays can. However, since the capability is implementation- and configuration-dependent, this function is provided so that the connect module can adapt for a particular instance.



# Section 9

## Scheduling semantics

This section details the simulation cycles for analog simulation and mixed A/D simulations.

### 9.1 Introduction

A mixed-signal simulator shall contain an analog solver that complies with the analog simulation cycle described in Section 9.2. This component of the mixed-signal simulator is termed the analog engine. A mixed signal simulator shall also contain a discrete event simulator that complies with the scheduling semantics described in Section 9.4. This component is termed the digital engine.

In a mixed-signal circuit, an “analog macro-process” is a set of continuous nodes that must be solved together because they are joined by analog blocks or analog primitives. A mixed-signal circuit can comprise one or more analog macro-process separated by digital processes.

### 9.2 Analog simulation cycle

Simulation of a network, or system, starts with an analysis of each node to develop equations which define the complete set of values and flows in a network. Through transient analysis, the value and flow equations are solved incrementally with respect to time. At each time increment, equations for each signal are iteratively solved until they converge on a final solution.

#### 9.2.1 Nodal analysis

To describe a network, simulators combine constitutive relationships with Kirchhoff’s Laws in *nodal analysis* to form a system of differential-algebraic equations of the form

$$f(v, t) = \frac{dq(v, t)}{dt} + i(v, t) = 0$$

$$v(0) = v_0$$

These equations are a restatement of Kirchhoff’s Flow Law (KFL).

$v$  is a vector containing all node values

$t$  is time

$q$  and  $i$  are the dynamic and static portions of the flow

$f()$  is a vector containing the total flow out of each node

$v_0$  is the vector of initial conditions

This equation was formulated by treating all nodes as being conservative (even signal flow nodes). In this way, signal-flow and conservative terminals can be connected naturally. However, this results in unnecessary KFL equations for those nodes with only signal-flow terminals attached. This situation is easily recognized and those unnecessary equations are eliminated along with the associated flow unknowns, which shall be zero (0) by definition.

### 9.2.2 Transient analysis

The equation describing the network is differential and non-linear, which makes it impossible to solve directly. There are a number of different approaches to solving this problem numerically. However, all approaches discretize time and solve the nonlinear equations iteratively, as shown in Figure 9-1.

The simulator replaces the time derivative operator ( $dq/dt$ ) with a discrete-time finite difference approximation. The simulation time interval is discretized and solved at individual time points along the interval. The simulator controls the interval between the time points to ensure the accuracy of the finite difference approximation. At each time point, a system of nonlinear algebraic equations is solved iteratively. Most circuit simulators use the Newton-Raphson (NR) method to solve this system.

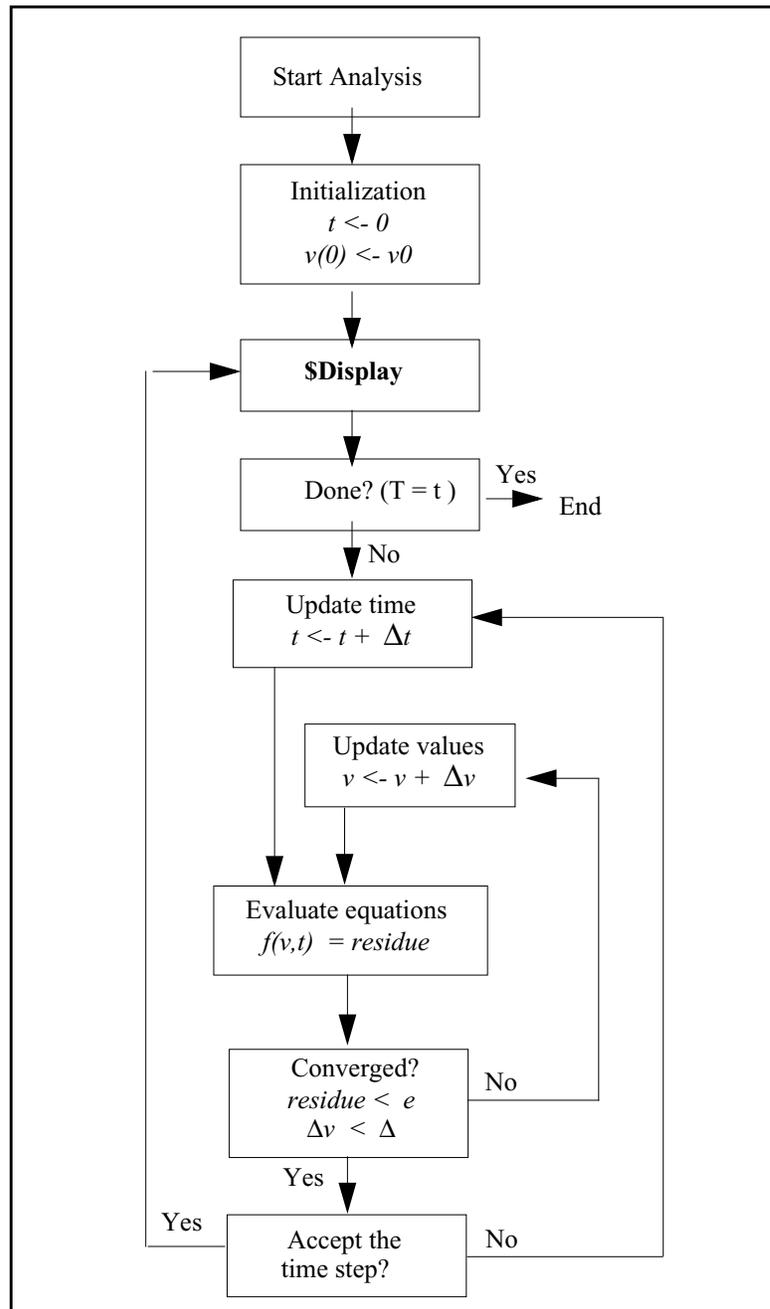


Figure 9-1 Simulation flowchart (transient analysis)

### 9.2.3 Convergence

In the analog kernel, the behavioral description is evaluated iteratively until the NR method converges. On the first iteration, the signal values used in expressions are approximate and do not satisfy Kirchhoff's Laws.

In fact, the initial values might not be reasonable, so models need to be written so they do something reasonable even when given unreasonable signal values.

For example, the log or square root of a signal value is being computed, some signal values cause the arguments to these functions to become negative, even though a real-world system never exhibits negative values.

As the iteration progresses, the signal values approach the solution. Iteration continues until two convergence criteria are satisfied. The first criterion is the proposed solution on this iteration,  $v_n^{(j)}(t)$ , shall be close to the proposed solution on the previous iteration,  $v_n^{(j-1)}(t)$ , and

$$|v_n^{(j)} - v_n^{(j-1)}| < reltol (\max(|v_n^{(j)}|, |v_n^{(j-1)}|)) + abstol$$

where *reltol* is the relative tolerance and *abstol* is the absolute tolerance.

*reltol* is set as a simulator option and typically has a value of 0.001. There can be many absolute tolerances, which one is used depends on the quantity the signal represents (volts, amps, etc.). The absolute tolerance is important when  $v_n$  is converging to zero (0). Without *abstol*, the iteration never converges.

The second criterion ensures Kirchoff's Flow Law is satisfied:

$$\left| \sum_n f_n^i(v^{(j)}) \right| < reltol (\max(|f_n^i(v^{(j)})|)) + abstol$$

where  $f_n^i(v^{(j)})$  is the flow exiting node  $n$  from branch  $i$ .

Both of these criteria specify the absolute tolerance to ensure convergence is not precluded when  $v_n$  or  $f_n(v)$  go to zero (0). The relative tolerance can be set once in an options statement to work effectively on any node in the circuit, but the absolute tolerance shall be scaled appropriately for its associated signal. The absolute tolerance shall be the largest signal value which is considered negligible on all the signals where it is associated.

The simulator uses absolute tolerance to get an idea of the scale of signals. Absolute tolerances are typically 1,000 to 1,000,000 times smaller than the largest typical value for signals of a particular quantity. For example, in a typical integrated circuit, the largest potential is about 5 volts, so the default absolute tolerance for voltage is 1 $\mu$ V. The largest current is about 1mA, so the default absolute tolerance for current is 1pA.

### 9.3 Mixed-signal simulation cycle

This section describes the semantics of the initialization and time-sweep phases of a transient analysis in a mixed-signal simulation cycle.

### 9.3.1 Circuit initialization

The initialization phase of a transient analysis is the process of initializing the circuit state before advancing time.

### 9.3.2 Synchronization of analog and digital in transient analysis

A Verilog-AMS simulation consists of a number of analog and digital processes communicating via events, shared memory and conservative nodes. Analog processes that share conservative nodes are “solved” jointly and can be viewed as a “macro” process, there may be any number “macro” processes, and it is left up to the implementation whether it solves them in a single matrix, multiple matrices or uses other techniques but it should abide by the accuracy stipulated in the disciplines and analog functions.

#### 9.3.2.1 Concurrency

Most (current) simulators are single-threaded in execution, meaning that although the semantics of Verilog-AMS imply processes are active concurrently, the reality is that they are not. If an implementation is genuinely multi-threaded, it should not evaluate processes that directly share memory concurrently, as there are no data locking semantics in Verilog-AMS.

#### 9.3.2.2 Analog macro process scheduling semantics

The internal evaluation of an analog macro process is described in Section 9.2.2. Once the analog engine has determined its behavior for a given time, it must communicate the results to other processes in the mixed signal simulation through events and shared variables. When an analog macro process is evaluated, the analog engine finds a potential “solution” at a future time (the “acceptance time”), and it stores (but does not communicate) values<sup>1</sup> for all the process’s nodes up to that time. A “wake up” event is scheduled for the acceptance time of the process, and the process is then inactive until it is either woken up or receives an event from another process. If it is woken up by its own “wake up” event, it calculates a new solution point, acceptance time (and so forth) and deactivates. If it is woken up prior to acceptance time by an event that disturbs its current solution, it will cancel its own “wake up” event, accept at the wake-up time, recalculate its solution and schedule a new “wake up” event for the new acceptance time. The process may also wake itself up early for reevaluation by use of a timer (which can be viewed as just another process).

If the analog process identifies future analog events such as “crossings” or timer events (see Section 6.7.5) then it will schedule its wake-up event for the time of the first such event rather than the acceptance time. If the analog process is woken by such an analog event it will communicate any related events at that time and de-activate, rescheduling

---

1. Or derivatives w.r.t. time used to calculate the values.

it's wake-up for the next analog event or acceptance. Events to external processes generated from analog events are not communicated until the global simulation time reaches the time of the analog event.

If the time to acceptance is infinite then no wake-up event needs to be scheduled<sup>1</sup>.

Analog processes are sensitive to changes in all variables and digital signals read by the process unless that access is only in statements 'guarded' by event expressions. For example the following code implements a simple digital to analog convertor:

```
module d2a(val,vo); // 16 bit D->A
    parameter Vgain = 1.0/65536;
    input      val;
    wire [15:0] val;
    electrical vo;
    analog begin
        V(vo) <+ Vgain * val;
    end
endmodule
```

The output voltage  $V(vo)$  is reevaluated when any bit in *val* changes, which is not a problem if all the bits change simultaneously and no 'X' values occur. A practical design would require that the digital value is latched to avoid bad bit sequences, as in the following version:

```
module d2aC(clk,val,vo); // Clocked 16 bit D2A
    parameter Vgain = 1.0/65536;
    input      clk;
    input      val;
    wire [15:0] val;
    electrical vo;
    real      v_clkd;
    analog begin
        @(posedge clk) v_clkd = Vgain * val;
        V(vo) <+ v_clkd;
    end
endmodule
```

Since *val* is now guarded by the *@(posedge clock)* expression the analog block is not sensitive to changes in *val* and only reevaluates when *clk* changes.

---

1. The case when all derivatives are zero - the circuit is stable.

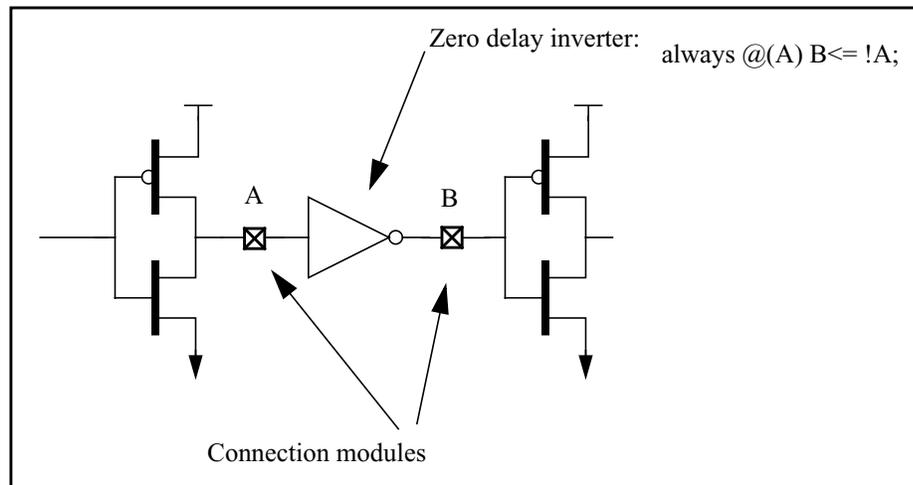
Macro processes can be evaluated separately but may be evaluated together<sup>1</sup>, in which case, the wake up event for one process will cause the re-evaluation of all or some of the processes. Users should bear this in mind when writing mixed-signal code, as it will mean that the code should be able to handle re-evaluation at any time (not just at its own event times).

### 9.3.2.3 A/D boundary timing

In the analog kernel, time is a floating point value. In the digital kernel time is an integer value. Hence, A2D events generally do not occur exactly at digital integer clock ticks.

For the purpose of reporting results and scheduling delayed future events, the digital kernel converts analog event times to digital times such that the error is limited to half the precision base for the module where the conversion occurs. For the examples below the timescale is 1ns/1ns, so the maximum scheduling error when swapping a digital module for its analog counterpart will be 0.5ns.

Consequently an A2D event that results in a D2A event being scheduled with zero (0) delay, shall have its effect propagated back to the analog kernel with zero (0) delay.



**Figure 9-2 A zero delay inverter**

If the circuit shown in Figure 9-2 is being simulated with a digital time resolution of  $1e-9$  (one (1) nanosecond) then all digital events shall be reported by the digital kernel as having occurred at an integer multiple of  $1e-9$ . The A2D and D2A modules inserted are a simple level detector and a voltage ramp generator:

```
connectmodule a2d(i,o);
    parameter vdd = 1.0;
    logic      o;
    input      i;
```

1. This is implementation-dependent.

```

output      o;
reg         o;
electrical  i;
always begin @(cross(V(i) - vdd/2,+1)o = 1; end
always begin @(cross(V(i) - vdd/2,-1)o = 0; end
endmodule

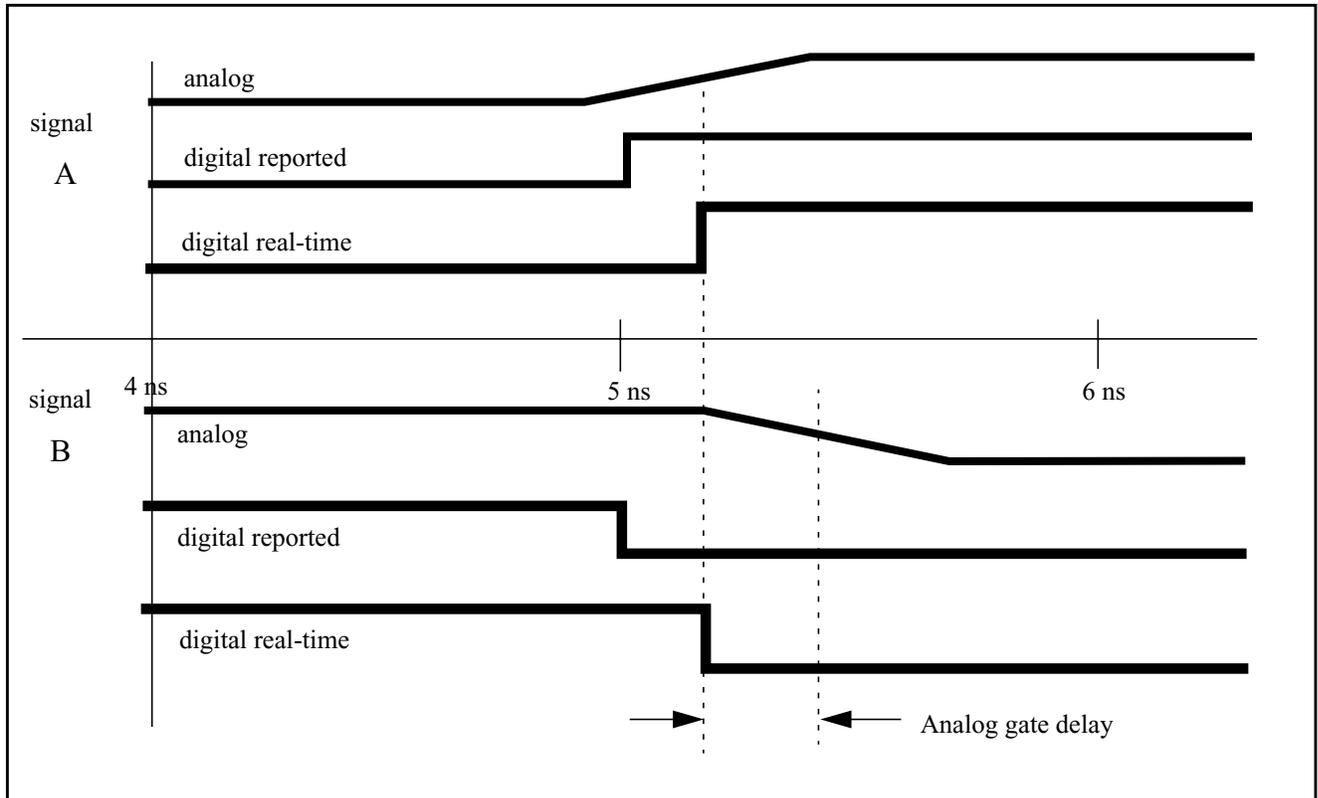
connectmodule d2a(i, o);
parameter   vdd    = 1.0;
parameter   slewrate = 2.0/1e9; // V/s
input       i;
output      o;
electrical  o;
reg         qd_val, // queued value
           nw_val;
real        et;     // delay to event
real start_delay; // .. to ramp start
always @(driver_update i) begin
    nw_val = $driver_next_state(i,0); // assume one driver
    if (nw_val == qd_val) begin
        // no change (assume delay constant)
    end else begin
        et      = $driver_delay(i,0) * 1e-9; // real delay
        qd_val  = nw_val;
    end
end
analog begin
    @(qd_val) start_delay = et - (vdd/2)/slewrate;
    V(o) <+ vdd * transition(qd_val,start_delay,vdd/slewrate);
end
endmodule

```

If connector A detects a positive threshold crossing, the resulting falling edge at connector B generated by the propagation of the signal through verilog inverter model shall be reported to the analog kernel with no further advance of analog time. The digital kernel will treat these events as if they occurred at the nearest nanosecond.

*Example:*

If  $A$  detects a positive crossing as a result of a transient solution at time  $5.2e-9$ , the digital kernel shall report a rising edge at  $A$  at time  $5.0e-9$  and falling edge at  $B$  at time  $5.0e-9$ , but the analog kernel shall see the transition at  $B$  begin at time  $5.2e-9$ , as shown in Figure 9-3. D2As fed with zero delay events cannot be preemptive, so the crossover on the return is delayed from the digital event; zero-delay inverters are not physically realizable devices.



**Figure 9-3 Zero delay transient solution times**

If the inverter equation is changed to use a one unit delay (*always @(A) B <= #1 !A*), then the timing is as in Figure 9-4.

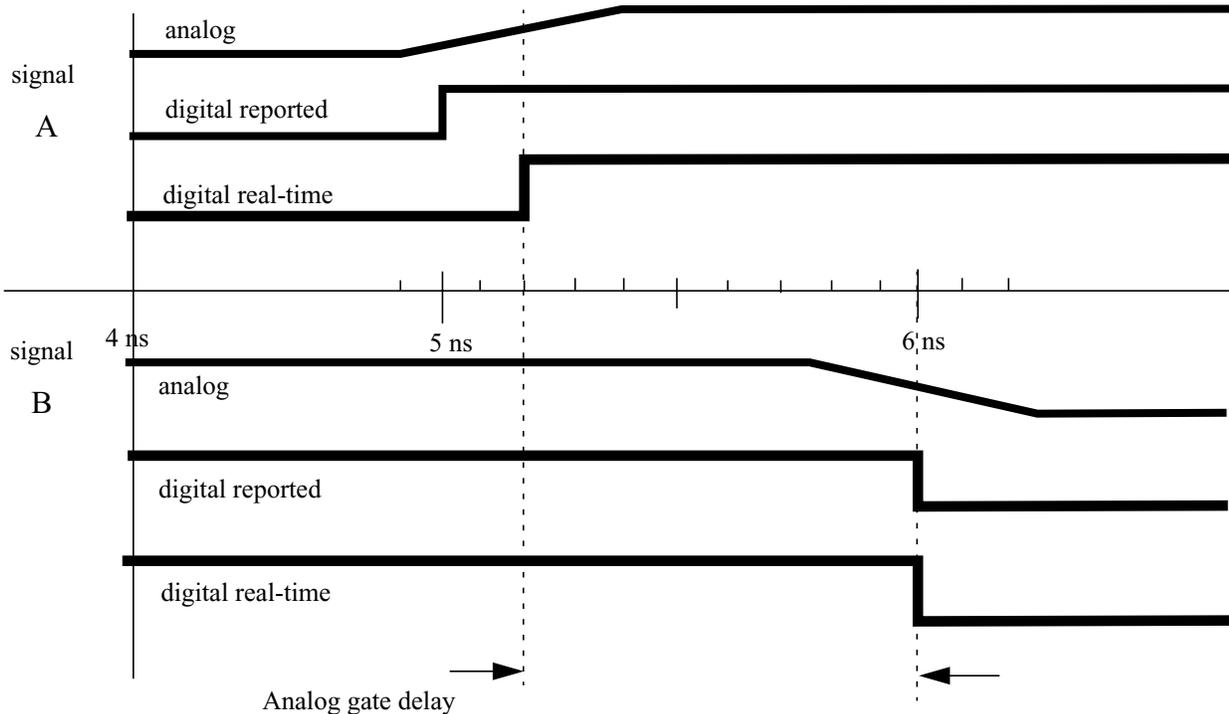


Figure 9-4 Unit delay transient solution times

### 9.3.3 The synchronization loop

Verilog-AMS uses a “conservative” simulation algorithm, the analog and digital processes that are managed by the simulation kernel are synchronized such that neither computes results that will invalidate signal values that have already been assigned; time never goes backwards. While the implementation of the simulator may have separate event queues for analog and digital events (see Section 9.3.4), it can be viewed as a single event queue logically with a common global time. Analog processes are similar to Verilog *initial* statements in that they start automatically at time zero. The event sequence for the transient simulation shown in Figure 9-4 would be as follows:

Time	Event Queue
4.9ns	Evaluate the first analog inverter
	Evaluate acceptance at 5.4ns, but schedule wake-up for 5.2 for crossing.
5.2ns	Evaluate crossing event
	The A2D logic sets the digital signal A, which triggers the evaluation of the non-blocking assign to B, which

	schedules the actual assignment for 6ns (rounded 1ns delay).
	D2A notices queued event and schedules wake-up for 5.75 via rampgen module.
	Schedule wake-up at 5.4ns (as previously calculated).
5.4ns	Evaluate acceptance Circuit evaluates stable, nothing scheduled.
5.75ns	D2A/rampgen process wake-up Start ramp in analog domain.
6.0ns	Non blocking assign performed (digital event). D2A may be sensitive, but doesn't need to do anything.
6.25ns	D2A/rampgen process wake-up Drive 0V to complete ramp. Nothing more to schedule.

Any events queued ahead of the current global event time may be cancelled. For instance, if the sequence above is interrupted by a change on the primary input before digital assignment takes place as shown in Figure 9-5.

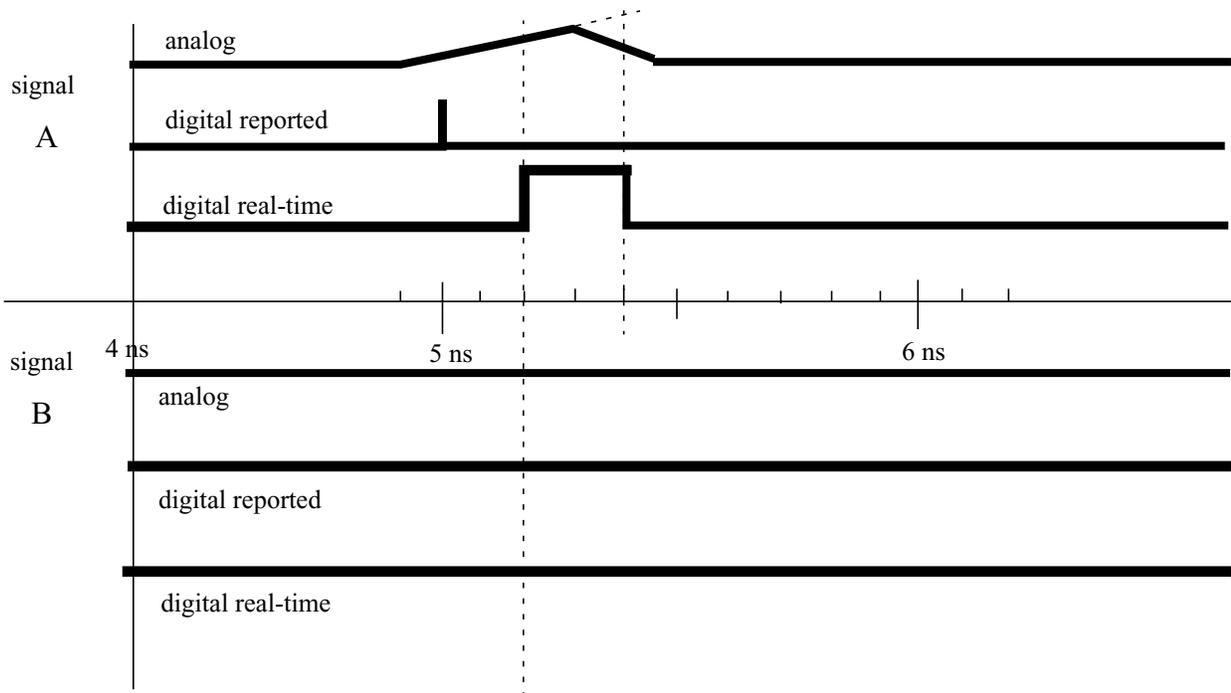
<b>Time</b>	<b>Event Queue</b>
4.9ns	Evaluating the first analog inverter Evaluate acceptance at 5.4ns, but schedule wake-up for 5.2 for crossing.
5.2ns	Evaluate crossing event The A2D logic sets the digital signal A, which triggers the evaluation of the non-blocking assign to B, which schedules the actual assignment for 6ns (rounded 1ns delay). D2A notices queued event and changes value using transition filter. Schedule wake-up at 5.4ns (as previously calculated).
5.3ns	Analog event disturbs the solution Accept at 5.3ns. Cancel 5.4ns wake-up. New acceptance is 5.45ns, but schedule wake-up for crossing at 5.4ns.
5.4ns	Evaluate crossing event

The A2D logic sets the digital signal A, which triggers the evaluation of the non-blocking assign to B, which schedules the actual assignment for 6ns (rounded 1ns delay), cancelling previous event.

D2A detects the driver change and *qd\_val* toggles back to 1 before the 0 propagates through the transition filter, so no analog change occurs at B.

Schedule wake-up at 5.45ns (as previously calculated).

- 5.45ns Evaluate acceptance  
Circuit evaluates stable, nothing scheduled.
- 6.00ns Non blocking assign performed (digital event).  
Value of B doesn't change.



**Figure 9-5 Transient solution times with glitch**

If the cancelling event arrived after the ramp on B had started but before the assignment to the digital B, it is possible to see the glitch propagate back into the analog domain without an event appearing on B.

### 9.3.4 Synchronization and communication algorithm

Figure 9-6 is an abstract representation of how the analog engine simulating an analog macro process communicates and synchronizes with the digital engine and vice-versa.

The synchronization algorithm can exploit characteristics of the analog and digital kernels described in the next section. The arrows represent an engine moving from one synchronization point to another, which in the case of an analog macro-process involves one or more time-steps and in the case of a digital engine, involves once or more discrete times at which events are processed.

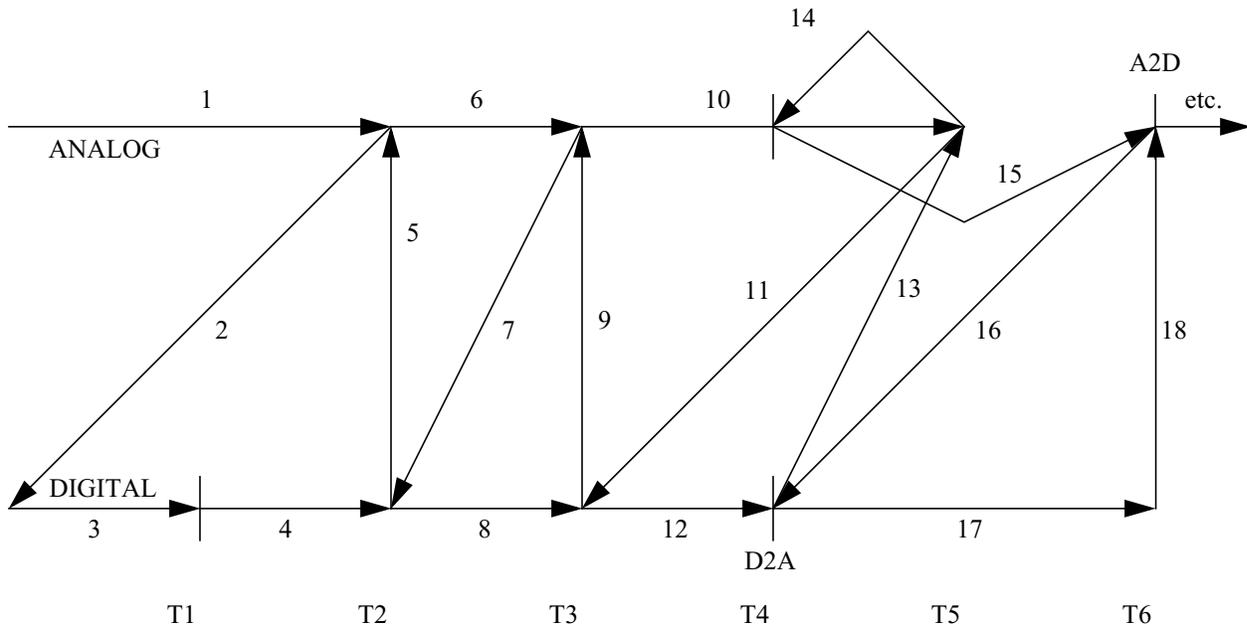


Figure 9-6 Sample run

1. The Analog engine begins transient analysis and sends state information (that it is good up to T2) to the Digital engine (1, 2).
2. The Digital engine begins to run using its own time steps (3); however, if there is no D2A event, the Analog engine is not notified and the digital engine continues to simulate until it can not advance its time without surpassing the time of the analog solution (4). Control of the simulation is then returned to the analog engine (5), which accepts at T2. This process is repeated (7, 8, 9, 10, and 11).
3. If the Digital engine produces a D2A event (12), control of the simulation is returned to the Analog engine (13). The analog engine accepts at the time of the D2A event (14, which may involve recalculating from T3). The Analog engine then calculates the next time step (15).

4. If the Analog engine produces an A2D event, it returns control to the Digital engine (16), which simulates up to the time of the A2D event, and then surrenders control (17 and 18).
5. This process continues until transient analysis is complete.

### 9.3.5 Assumptions about the analog and digital algorithms

1. Advance of time in a digital algorithm
  - A. The digital simulation has some minimum time granularity and all digital events occur at a time which is some integer multiple of that granularity.
  - B. The digital simulator can always accept events for a given simulation time provided it has not yet executed events for a later time. Once it executes events for a given time, it can not accept events for an earlier time.
  - C. The digital simulator can always report the time of the most recently executed event and the time of the next pending event.
2. Advance of time in an analog algorithm
  - A. The analog simulator advances time by calculating a sequence of solutions. Each solution has an associated time which, unlike the digital time, is not constrained to a particular minimum granularity.
  - B. The analog simulator can not tell for certain the time when the next solution converges. Thus, it can tell the time of the most recently calculated solution, but not the time of the next solution.
  - C. In general, the analog solution is a function of one or more previous solutions. Having calculated the solution for a given time, the analog simulator can either accept or reject that solution; it cannot calculate a solution for a future time until it has accepted the solution for the current time.
3. Analog to digital events
  - A. Analog to digital events are generated by conversion elements (which are analog/digital behavioral models) when evaluated by the analog simulator.
  - B. Analog events (e.g., `cross`, `initial_step`, and `final_step`) cause an analog solution of the time where they occur.
  - C. Thus, any analog to digital event is generated as the result of a particular transient solution. This means events can stay associated with the solution that produced them until they are passed to the digital simulator. Until then, they can be rejected along with the solution, if it is rejected.
4. Digital to analog events shall cause an analog solution of the time where they occur.

## 9.4 Scheduling semantics for the digital engine

The scheduling semantics for Verilog-HDL simulation are outlined in Section 5 of IEEE 1364-2001.

The digital engine of a Verilog-AMS mixed-signal simulator shall comply with that section except for the changes outlined in this section.

For mixed-signal simulation, the major change from Section 5 of IEEE 1364-2001 is that two new types of event must be supported by the event queue called the *explicit D2A* (digital-to-analog) *event*, and the *analog macro-process event*.

Explicit D2A events are created when a digital event occurs to which an analog block is *explicitly sensitive*. An analog block is explicitly sensitive to event expressions mentioned in an event control statement in that analog block.

Similarly, there is also the concept of the *implicit D2A event* that is created when a digital variable to which an analog block is *implicitly sensitive* changes value. An analog block is implicitly sensitive to all digital variable references that are not guarded by event control statements in that analog block.

An analog macro-process event is also created when either type of D2A event occurs. The analog macro-process event is associated with the analog macro-process that is sensitive to the D2A event. An analog macro-process event is evaluated by calling the analog engine to solve it. Note that implicit D2A events are not added to the stratified event queue, but as they directly cause an analog macro-process event, they effectively force a digital-analog synchronization when they occur.

### 9.4.1 The stratified event queue

The Verilog event queue is logically segmented into *seven* different regions. Events are added to any of the seven regions but are only removed from the *active* region. Regions 1b and 3b have been added for mixed-signal simulation.

1. Events that occur at the current simulation time and can be processed in any order. These are the *active* events.
- 1b. Explicit D2A events that occur at the current simulation time shall be processed after all the active events are processed.
2. Events that occur at the current simulation time, but that shall be processed after all the active and explicit D2A events are processed. These are the *inactive* events.
3. Events that have been evaluated during some previous simulation time, but that shall be assigned at this simulation time after all the active, explicit D2A and inactive events are processed. These are the non blocking assign update events.

- 3b. Analog macro-process events shall be processed after all active, explicit D2A events, inactive events and non blocking assign update events are processed.
4. Events that shall be processed after all the active, explicit D2A, inactive, non blocking assign update events and analog macro-process events are processed. These are the *monitor* events.
5. Events that occur at some future simulation time. These are the *future* events. Future events are divided into *future inactive events* and *future non blocking assignment update events*.

The processing of all the active events is called a *simulation cycle*.

The freedom to choose any active event for immediate processing is an essential source of nondeterminism in the Verilog HDL.

An *explicit zero delay* (#0) requires that the process be suspended and added as an inactive event for the current time so that the process is resumed in the next simulation cycle in the current time.

A non blocking assignment (see Section 9.2.2 of IEEE 1364-2001) creates a non blocking assign update event, scheduled for current or a later simulation time.

The **\$monitor** and **\$strobe** system tasks (see Section 17.1 of IEEE 1364-2001) create monitor events for their arguments. These events are continuously re-enabled in every successive time step. The monitor events are unique in that they cannot create any other events.

The call back procedures scheduled with PLI routines such as `tf_synchronize()` (see Section 25.58 of IEEE 1364-2001) or `vpi_register_cb(cb_readwrite)` (see Section 27.33 of IEEE 1364-1995) shall be treated as inactive events.

Note that A2D events must be analog event controlled statements ( e.g., `@cross`, `@timer`). These are scheduled just like other event controlled statements in Verilog-HDL (e.g., `@posedge`).

## 9.4.2 The Verilog-AMS digital engine reference model

In all the examples that follow, T refers to the current simulation time of the digital engine, and all events are held in the event queue, ordered by simulation time.

```
while (there are events){
  if (no active events){
    if (there are inactive events){
      activate all inactive events;
    } else if (there are explicit D2A events) {
      activate all explicit D2A events;
    } else if (there are non blocking assign update events){
```

```

        activate all non blocking assign update events;
    }else if (there are analog macro-process events) {
        activate all analog macro-process events;
    }else if (there are monitor events){
        activate all monitor events;
    }else {
        advance T to the next event time;
        activate all inactive events for time T;
    }
}
E =any active event;
if (E is an update event){
    update the modified object;
    add evaluation events for sensitive processes to event queue;
}else if (E is a D2A event) {
    evaluate the D2A
    modify the analog values
    add A2D events to event queue, if any
}else if (E is an analog macro-process event) {
    evaluate the analog macro-process
    modify the analog values
    add A2D events to event queue, if any
}else { /*shall be an evaluation event */
    evaluate the process;
    add update events to the event queue;
}
}
}

```

### 9.4.3 Scheduling implication of assignments

Assignments are translated into processes and events as follows.

#### 9.4.3.1 Continuous assignment

A continuous assignment statement (Section 6 of IEEE 1364-2001) corresponds to a process, sensitive to the source elements in the expression. When the value of the

expression changes, it causes an active update event to be added to the event queue, using current values to determine the target.

#### 9.4.3.2 Procedural continuous assignment

A procedural continuous assignment (which is the **assign** or **force** statement; see Section 9.3 of IEEE 1364-2001) corresponds to a process that is sensitive to the source elements in the expression. When the value of the expression changes, it causes an active update event to be added to the event queue, using current values to determine the target.

A **deassign** or a **release** statement deactivates any corresponding **assign** or **force** statement(s).

#### 9.4.3.3 Blocking assignment

A blocking assignment statement (see Section 9.2.1 of IEEE 1364-2001) with a delay computes the right-hand side value using the current values, then causes the executing process to be suspended and scheduled as a future event. If the delay is 0, the process is scheduled as an inactive event for the current time.

When the process is returned (or if it returns immediately if no delay is specified), the process performs the assignment to the left-hand side and enables any events based upon the update of the left-hand side. The values at the time the process resumes are used to determine the target(s). Execution may then continue with the next sequential statement or with other active events.

#### 9.4.3.4 Non blocking assignment

A non blocking assignment statement (see Section 9.2.2 of IEEE 1364-2001) always computes the updated value and schedules the update as a non blocking assign update event, either in this time step if the delay is zero or as a future event if the delay is nonzero. The values in effect when the update is placed on the event queue are used to compute both the right-hand value and the left-hand target.

#### 9.4.3.5 Switch (transistor) processing

The event-driven simulation algorithm described in Section 5.4 of IEEE 1364-2001 depends on unidirectional signal flow and can process each event independently. The inputs are read, the result is computed, and the update is scheduled. The Verilog HDL provides switch-level modeling in addition to behavioral and gate-level modeling. Switches provide bi-directional signal flow and require coordinated processing of nodes connected by switches.

The Verilog HDL source elements that model switches are various forms of transistors, called **tran**, **tranif0**, **tranif1**, **rtran**, **rtranif0**, and **rtranif1**.

Switch processing shall consider all the devices in a bidirectional switch-connected net before it can determine the appropriate value for any node on the net, because the inputs and outputs interact. A simulator can do this using a relaxation technique. The simulator

can process tran at any time. It can process a subset of tran-connected events at a particular time, intermingled with the execution of other active events. Further refinement is required when some transistors have gate value x. A conceptually simple technique is to solve the network repeatedly with these transistors set to all possible combinations of fully conducting and nonconducting transistors. Any node that has a unique logic level in all cases has steady-state response equal to this level. All other nodes have steady-state response.

#### **9.4.3.6 Processing explicit D2A events (region 1b)**

An explicit D2A event is processed by evaluating the analog block that is sensitive to this event. This is so that the values used for the digital variables referenced inside the explicitly sensitive event control statement in the analog block are the values of those variables after region 1 has been processed, not the values of those variables just before region 3b is processed.

#### **9.4.3.7 Processing analog macro-process events (region 3b)**

An analog macro-process event is evaluated by calling the analog engine to solve the associated analog macro-process. Note that if multiple events for a particular analog macro-process are active, then a single evaluation of the analog macro-process shall consume all of these events from the queue.

The reason for processing analog macro-processes after regions 1-3 have been processed is to minimize the number of times analog macro-processes are evaluated, because such evaluations tend to be expensive.



## Section 10

# System tasks and functions

This section describes system tasks and functions available in Verilog-AMS HDL.

### 10.1 Environment parameter functions

The syntax for these functions are shown in Syntax 10-1.

```
environment_parameter_functions ::=
    $temperature
    | $abstime
    | $realtime [ ( real_number ) ]
    | $vt [ ( temperature_expression ) ]
    | $simparam (string [, expression] )
```

Syntax 10-1—Syntax for the environment parameter functions

These functions return information about the current environment parameters as a real value.

**\$temperature** does not take any input arguments and returns the circuit's ambient temperature in Kelvin units.

**\$abstime** returns the absolute time, that is a real value number representing time in seconds.

**\$realtime** can have an optional argument which scales the time. If no argument is given, **\$realtime**'s return value is scaled to the ``time_unit` of the module which invoked it. If an argument is given, **\$realtime** shall divide the absolute time by the value of the argument (i.e., scale to the value specified in the argument). The argument for **\$realtime** follows the semantics of the ``time_unit`, that is it shall consist of an integer followed by a scale factor. Valid integers are: 1, 10, and 100; valid scale factors are: `s` (seconds), `ms` (milliseconds), `us` (microseconds), `ns` (nanoseconds), `ps` (picoseconds), and `fs` (femtoseconds).

**Note:** Previous Verilog-A modules using **\$realtime** may not produce the same results as in the past as `$realtime` used to return time scaled to one (1) second. If the `time_unit` of the ``timescale` directive is set to `1s`, the behavior shall be the same. For analog blocks, the **\$abstime** function should typically be used, as it returns time in seconds.

`$vt` can optionally have temperature (in Kelvin units) as an input argument and returns the thermal voltage ( $kT/q$ ) at the given temperature. `$vt` without the optional input temperature argument returns the thermal voltage using `$temperature`.

`$simparam()` queries the simulator for a simulation parameter named *string*. If *string* is known, its value is returned. If *string* is not known, and the optional *expression* is not supplied, then an error is generated. If the optional *expression* is supplied, its value is returned if *string* is not known and no error is generated. `$simparam()` shall always return a real value; simulation parameters that have integer values shall be coerced to real. There is no fixed list of simulation parameters. However, simulators shall accept the strings in Table 10-1 to access commonly-known simulation parameters, if they support the parameter. Simulators can also accept other strings to access the same parameters.

**Table 10-1—Simulation parameter names**

String	Units	Description
<code>gdev</code>	1/Ohms	Additional conductance to be added to nonlinear branches for conductance homotopy convergence algorithm.
<code>gmin</code>	1/Ohms	Minimum conductance placed in parallel with nonlinear branches.
<code>imax</code>	Amps	Branch current threshold above which the constitutive relation of a nonlinear branch should be linearized.
<code>imelt</code>	Amps	Branch current threshold indicating device failure.
<code>iteration</code>		Iteration number of the analog solver.
<code>scale</code>		Scale factor for device instance geometry parameters.
<code>shrink</code>		Optical linear shrink factor.
<code>simulatorSubversion</code>		The simulator sub-version.
<code>simulatorVersion</code>		The simulator version.
<code>sourceScaleFactor</code>		Multiplicative factor for independent sources for source stepping homotopy convergence algorithm.
<code>tnom</code>	degrees Celsius	Default value of temperature at which model parameters were extracted.

The values returned by `simulatorVersion` and `simulatorSubversion` are at the vendor's discretion, but the values shall be monotonically increasing for new versions or releases of the simulator, to facilitate checking that the simulator supports features that were added in a certain version or sub-version.

*Examples:*

In this first example, the variable `gmin` is set to the simulator's parameter named `gmin`, if it exists, otherwise, an error is generated.

```
gmin = $simparam("gmin");
```

In this second example, the variable `sourcescale` is set to the simulator's parameter named `gmin`, if it exists, otherwise, the value 1.0 is returned.

```
sourcescale = $simparam("sourceScaleFactor", 1.0);
```

## 10.2 \$random function

The syntax for this function is shown in Syntax 10-2.

```
random_function ::=
    $random [ ( seed [, type_string] ) ];

seed ::=
    integer_variable_identifier
    | reg_variable_identifier
    | time_variable_identifier
    | integer_parameter_identifier
    | decimal_number

type_string ::=
    "global"
    | "instance"
```

Syntax 10-2—Syntax for the `random_function`

The system function `$random` provides a mechanism for generating random numbers. The random number returned is a 32-bit signed integer; it can be positive or negative.

The `seed` argument may take one of several forms. It may be omitted, in which case the simulator picks a seed. It may be a `reg`, `integer`, or `time` variable, in which case it is an `inout` argument; that is, a value is passed to the function and a different value is returned. The variable should be initialized by the user prior to calling `$random` and only updated by the system function. If the seed is a variable or is omitted, the function returns a new 32-bit random number each time it is called.

The system function `$random` shall always return the same stream of values given the same initial `seed`. This facilitates debugging by making the operation of the system repeatable.

The `seed` argument may also be a parameter or a constant, in which case the system function does not update the value. This makes the system function useable for parameter initialization. In order to get different random values when the `seed` argument is a parameter, the user can override the parameter using a method in Section 7.2.

The `type_string` provides support for Monte-Carlo analysis. If the `type_string` is “global,” then one value is generated for each Monte-Carlo trial. If the `type_string` is “instance,” then one value is generated for each instance that references this value, and a new set of values for these instances is generated for each Monte-Carlo trial.

*Examples:*

Where  $b > 0$ , the expression `($random % b)` gives a number in the following range: `[(-b+1) : (b-1)]`.

The following code fragment shows an example of random number generation between -59 and 59:

```
integer rand;
rand = $random % 60;
```

## 10.3 \$dist\_functions

The syntax for these functions are shown in Syntax 10-3.

```
distribution_functions ::=
    $digital_dist_functions ( args ) ;
    | $rdist_uniform ( seed, start_expression, end_expression [, type_string] ) ;
    | $rdist_normal ( seed, mean_expression, standard_deviation_expression [, type_string] ) ;
    | $rdist_exponential ( seed, mean_expression [, type_string] ) ;
    | $rdist_poisson ( seed, mean_expression [, type_string] ) ;
    | $rdist_chi_square ( seed, degree_of_freedom_expression [, type_string] ) ;
    | $rdist_t ( seed, degree_of_freedom_expression [, type_string] ) ;
    | $rdist_erlang ( seed, k_stage_expression, mean_expression [, type_string] ) ;

seed ::=
    integer_variable_identifier
    | integer_parameter_identifier
    | decimal_number

type_string ::=
    "global"
    | "instance"
```

Syntax 10-3—Syntax for the probabilistic distribution functions

The following rules apply to these functions.

- All arguments to the system functions are real values, except for *seed* (which is defined by `$random`). For the `$rdist_exponential`, `$rdist_poisson`, `$rdist_chi_square`, `$rdist_t`, and `$rdist_erlang` functions, the arguments *mean*, *degree\_of\_freedom*, and *k\_stage* shall be greater than zero (0).
- Each of these functions returns a pseudo-random number whose characteristics are described by the function name, e.g., `$rdist_uniform` returns random numbers uniformly distributed in the interval specified by its arguments.
- For each system function, the *seed* argument shall be an integer. If it is an integer variable, then it is an `inout` argument; that is, a value is passed to the function

and a different value is returned. The variable is initialized by the user and only updated by the system function. This ensures the desired distribution is achieved upon successive calls to the system function. If the *seed* argument is a parameter or constant, then the system function does not update the value. This makes the system function useable for parameter initialization.

- The system functions shall always return the same value given the same *seed*. This facilitates debugging by making the operation of the system repeatable. In order to get different random values when the *seed* argument is a parameter, the user can override the parameter.
- All functions return a real value.
- In `$rdist_uniform`, the *start* and *end* arguments are real inputs which bound the values returned. The *start* value shall be smaller than the *end* value.
- The *mean* argument used by `$rdist_normal`, `$rdist_exponential`, `$rdist_poisson`, and `$rdist_erlang` is an real input which causes the average value returned by the function to approach the value specified.
- The *standard\_deviation* argument used by `$rdist_normal` is a real input, which helps determine the shape of the density function. Using larger numbers for *standard\_deviation* spreads the returned values over a wider range. Using a *mean* of zero (0) and a *standard\_deviation* of one (1), `$rdist_normal` generates Gaussian distribution.
- The *degree\_of\_freedom* argument used by `$rdist_chi_square` and `$rdist_t` is a real input, which helps determine the shape of the density function. Using larger numbers for *degree\_of\_freedom* spreads the returned values over a wider range.
- The *type\_string* provides support for Monte-Carlo analysis. If the *type\_string* is “global,” then one value is generated for each Monte-Carlo trial. If the *type\_string* is “instance,” then one value is generated for each instance that references this value, and a new set of values for these instances is generated for each Monte-Carlo trial. See Section 7.3.1 for an example.

## 10.4 Simulation control system tasks

There are two simulation control system tasks, `$finish` and `$stop`.

### 10.4.1 `$finish`

The syntax for this task is shown in Syntax 10-4.

```
finish_task ::=
    $finish [ ( n ) ] ;
```

Syntax 10-4—Syntax for the `finish_task`

**\$finish** simply makes the simulator exit. If an expression is supplied to this task, its value determines which diagnostic messages are printed before the prompt is issued, as shown in Table 10-2. One (1) is the default if no argument is supplied.

Table 10-2—Diagnostic messages

Parameter	Message
0	Prints nothing
1	Prints simulation time and location
2	Prints simulation time, location, and statistics about the memory and CPU time used in simulation

## 10.4.2 \$stop

The syntax for this task is shown in Syntax 10-5.

```
stop_task ::=
    $stop [ ( n ) ] ;
```

Syntax 10-5—Syntax for the `stop_task`

**\$stop** causes simulation to be suspended at a converged timepoint. This task takes an optional expression argument (0, 1, or 2), which determines what type of diagnostic message is printed. The amount of diagnostic messages output increases with the value of *n*, as shown in Table 10-2.

## 10.5 File operation tasks

This section details the file operation tasks.

### 10.5.1 \$fopen

The syntax for this task is shown in Syntax 10-6.

```
file_open_task ::=
    integer multi_channel_descriptor = $fopen ( " file_name " ) ;
```

Syntax 10-6—Syntax for the `file_open_task`

**\$fopen** opens the file specified as an argument and returns a 32-bit multichannel descriptor which is uniquely associated with the file. It returns 0 if the file could not be opened for writing.

The multichannel descriptor can be thought of as a set of 32 flags, where each flag represents a single output channel. The least significant bit (`bit 0`) of a multichannel descriptor always refers to the standard output. The standard output is also called `channel 0`. The other bits refer to channels which have been opened by **\$fopen**.

The first call to **\$fopen** opens `channel 1` and returns a multichannel descriptor value of 2—that is, `bit 1` of the descriptor is set. A second call to **\$fopen** opens `channel 2` and returns a value of 4—that is, only `bit 2` of the descriptor is set. Subsequent calls to **\$fopen** open channels 3, 4, 5, and so on and return values of 8, 16, 32, and so on, up to a maximum of 32 open channels. Thus, a channel number corresponds to an individual bit in a multichannel descriptor.

### 10.5.2 \$fclose

The syntax for this task is shown in Syntax 10-7.

```
file_close_task ::=
    $fclose ( multi_channel_descriptor_identifier );
```

Syntax 10-7—Syntax for the `file_close_task`

**\$fclose** closes the channels specified in the multichannel descriptor and does not allow any further output to the closed channels. **\$fopen** reuses channels which have been closed.

## 10.6 Display tasks

The syntax for these functions are shown in Syntax 10-8.

```
display_tasks ::=
    $strobe ( list_of_arguments );
    | $display ( list_of_arguments );
    | $monitor ( list_of_arguments );
    | $write ( list_of_arguments );
    | $debug ( list_of_arguments );
```

Syntax 10-8—Syntax for the `display_tasks`

The following rules apply to these functions.

- **\$strobe** provides the ability to display simulation data when the simulator has converged on a solution for all nodes.

- **\$strobe** displays its arguments in the same order they appear in the argument list. Each argument can be a quoted string, an expression which returns a value, or a null argument.
- The contents of string arguments are output literally, except when certain escape sequences are inserted to display special characters or specify the display format for a subsequent expression.
- Escape sequences are inserted into a string in three ways:
  - The special character `\` indicates the character to follow is a literal or non-printable character (see Table 10-3).
  - The special character `%` indicates the next character shall be interpreted as a format specification which establishes the display format for a subsequent expression argument (see Table 10-4). For each `%` character which appears in a string, a corresponding expression argument shall be supplied after the string.
  - The special character string `%%` indicates the display of the percent sign character (`%`) (see Table 10-3).
- Any null argument produces a single space character in the display. (A *null argument* is characterized by two adjacent commas (`, ,`) in the argument list.)
- When **\$strobe** is invoked without arguments, it simply prints a newline character.

The **\$display** task provides the same capabilities as **\$strobe**. The **\$write** task provides the same capabilities as **\$strobe**, but with no newline. The **\$monitor** task provides the same capabilities as **\$strobe**, but outputs only when an argument changes. The **\$debug** task provides the capability to display simulation data while the analog simulator is solving the equations; it displays its arguments for each iteration of the analog solver.

### 10.6.1 Escape sequences for special characters

The escape sequences shown in Table 10-3, when included in a string argument, print special characters.

**Table 10-3— Escape sequences for printing special characters**

<code>\n</code>	The newline character
<code>\t</code>	The tab character
<code>\\</code>	The <code>\</code> character
<code>\"</code>	The <code>"</code> character
<code>\ddd</code>	A character specified by 1 to 3 octal digits
<code>%%</code>	The <code>%</code> character

### 10.6.2 Format specifications

Table 10-4 shows the escape sequences used for format specifications. Each escape sequence, when included in a string argument, specifies the display format for a subsequent expression. For each % character (except %m and %%) which appears in a string, a corresponding expression shall follow the string in the argument list, except a null argument. The value of the expression replaces the format specification when the string is displayed.

**Table 10-4— Escape sequences for format specifications**

%h or %H	Display in hexadecimal format
%d or %D	Display in decimal format
%o or %O	Display in octal format
%b or %B	Display in binary format
%c or %C	Display in ASCII character format
%m or %M	Display hierarchical name
%s or %S	Display as a string

Any expression argument which has no corresponding format specification is displayed using the default decimal format in **\$stroke**.

The format specifications in Table 10-5 are used for real numbers and have the full formatting capabilities available in the C language. For example, the format specification %10.3g sets a minimum field width of 10 with three (3) fractional digits.

**Table 10-5— Format specifications for real numbers**

%e or %E	Display 'real' in an exponential format
%f or %F	Display 'real' in a decimal format
%g or %G	Display 'real' in exponential or decimal format, whichever format results in the shorter printed output
%r or %R	Display 'real' in engineering notation, using the scale factors defined in Section 2.5.3

### 10.6.3 Hierarchical name format

The %m format specifier does not accept an argument. Instead, it causes the display task to print the hierarchical name of the module, task, function, or named block which invokes the system task containing the format specifier. This is useful when there are many instances of the module which call the system task. One obvious application is timing check messages in a flip-flop or latch module; the %m format specifier pinpoints the module instance responsible for generating the timing check message.

### 10.6.4 String format

The `%s` format specifier is used to print ASCII codes as characters. For each `%s` specification which appears in a string, a corresponding argument shall follow the string in the argument list. The associated argument is interpreted as a sequence of 8-bit hexadecimal ASCII codes, with each 8 bits representing a single character. If the argument is a variable, its value shall be right-justified so the right-most bit of the value is the least-significant bit of the last character in the string. No termination character or value is required at the end of a string and leading zeros (0) are never printed.

## 10.7 Announcing discontinuity

The `$discontinuity` function is used to give hints to the simulator about the behavior of the module so the simulator can control its simulation algorithms to get accurate results in exceptional situations. This function does not directly specify the behavior of the module. `$discontinuity` shall be executed whenever the analog behavior changes discontinuously.

The general form is

```
$discontinuity[ ( constant_expression ) ];
```

where *constant\_expression* indicates the degree of the discontinuity.

`$discontinuity(i)` implies a discontinuity in the *i*'th derivative of the constitutive equation with respect to either a signal value or time where *i* must be non-negative.

Hence, `$discontinuity(0)` indicates a discontinuity in the equation,

`$discontinuity(1)` indicates a discontinuity in its slope, etc.

**Note:** Because discontinuous behavior can cause convergence problems, discontinuity shall be avoided whenever possible.

The filter functions (`transition()`, `slew()`, `laplace()`, etc.) can be used to smooth discontinuous behavior. However, in some cases it is not possible to implement the desired functionality using these filters. In those cases, the `$discontinuity` function shall be executed when the signal behavior changes abruptly.

**Note:** Discontinuity created by switch branches and built-in system functions, such as `transition()` and `slew()`, does not need to be announced.

A special form of the `$discontinuity` function, `$discontinuity(-1)`, is used with the `$limit()` function. See Section 10.9 for an explanation.

*Examples:*

*Example 1*

The following example uses the discontinuity function to model a relay.

```

module relay (c1, c2, pin, nin) ;
  inout c1, c2 ;
  input pin, nin ;
  electrical c1, c2, pin, nin ;
  parameter real r=1 ;

  analog begin
    @(cross(V(pin,nin))) $discontinuity ;
    if (V(pin,nin) >= 0)
      I(c1,c2) <+ V(c1,c2)/r;
    else
      I(c1,c2) <+ 0 ;
    end
  endmodule

```

In this example, `cross()` controls the time step so the time when the relay changes position is accurately resolved. It also triggers the `$discontinuity` function, which causes the simulator to react properly to the discontinuity. This would have been handled automatically if the type of the branch `(c1,c2)` had been switched between voltage and current.

### Example 2

Another example is a source which generates a triangular wave. In this case, neither the model nor the waveforms generated by the model are discontinuous. Rather, the waveform generated is piecewise linear with discontinuous slope. If the simulator is aware of the abrupt change in slope, it can adapt to eliminate problems resulting from the discontinuous slope (typically changing to a first order integration method).

```

module triangle(out);
  output out;
  voltage out;
  parameter real period = 10.0, amplitude = 1.0;
  integer slope;
  real offset;

  analog begin
    @(timer(0, period)) begin
      slope = +1;
      offset = $abstime ;
      $discontinuity;
    end

    @(timer(period/2, period)) begin
      slope = -1 ;
      offset = $abstime;
      $discontinuity ;
    end

    V(out) <+ amplitude*slope*
      (4*($abstime - offset)/period - 1);
  end
endmodule

```

## 10.8 Time related functions

The `$bound_step()` function puts a bound on the next time step. It does not specify exactly what the next time step is, but it bounds how far the next time point can be from the present time point. The function takes the maximum time step as an argument. It does not return a value.

The general form is

```
$bound_step ( expression );
```

where *expression* is a required argument and represents the maximum timestep the simulator can advance.

*Examples:*

The example below implements a sinusoidal voltage source and uses the `$bound_step()` function to assure the simulator faithfully follows the output signal (it is forcing 20 points per cycle).

```
module vsine(out);
  output out;
  voltage out;
  parameter real freq=1.0, ampl=1.0, offset=0.0;

  analog begin
    V(out) <+ ampl*sin(2.0*`M_PI*freq*$abstime) + offset;
    $bound_step(0.05/freq);
  end
endmodule
```

For details on the `last_crossing()` function, see Section 4.4.11.

## 10.9 Limiting functions

Other nonlinearities besides the exponential are present in semiconductor device compact models. The `$limit()` function provides a method to indicate these nonlinearities to the simulator and, if necessary, recommend a function to use to limit the change of its output from iteration to iteration. Syntax 10-9 shows the methods of using the `$limit()` function.

```
limit_call ::=
  $limit ( access_function_reference )
  | $limit ( access_function_reference, string, arg_list )
  | $limit ( access_function_reference, analog_function_identifier, arg_list )
```

Syntax 10-9—Syntax for `$limit()`

When the simulator has converged, the return value of the `$limit()` function is the value of the access function reference, within appropriate tolerances. For some analysis types or solution methods, such as damped Newton-Raphson, the return value of the `$limit()` function may depend on the value of the access function and internal state of the function. In all cases, the simulator is responsible for determining if limiting should be applied and what the return value is on a given iteration.

When more than one argument is supplied to the `$limit()` function, the second argument recommends a function to use to compute the return value. When the second argument is a string, it refers to a built-in function of the simulator. The two most common such functions are `pnjlim` and `fetlim`, which are found in SPICE and many SPICE-like simulators. Simulators may support other built-in functions and need not support `pnjlim` or `fetlim`. If the string refers to an unknown or unsupported function, the simulator is responsible for determining the appropriate limiting algorithm, just as if no string had been supplied.

`pnjlim` is intended for limiting arguments to exponentials, and the `limexp()` function of Section 4.4.14 may be implemented through a function derived from `pnjlim`. Two additional arguments to the `$limit()` function are required when the second argument to the limit function is the string “pnjlim”: the third argument to `$limit()` indicates a step size `vte` and the fourth argument is a critical voltage `vcrit`. The step size `vte` is usually the product of the thermal voltage `$vt` and the emission coefficient of the junction. The critical voltage is generally obtained from the formula  $V_{crit} = vte \cdot \ln(vte / (\sqrt{2} \cdot I_s))$ , where  $I_s$  is the saturation current of the junction.

`fetlim` is intended for limiting the potential across the oxide of a MOS transistor. One additional argument to the `$limit()` function is required when the second argument to the limit function is the string “fetlim”: the third argument to `$limit()` is generally the threshold voltage of the MOS transistor.

In the case that none of the built-in functions of the simulator is appropriate for limiting the potential (or flow) used in a nonlinear equation, the second argument of the `$limit()` function may be an identifier referring to a user-defined analog function. User-defined functions are described in Section 4.6. In this case, if the simulator determines that limiting is needed to improve convergence, it will pass the following quantities as arguments to the user-defined function:

- The first argument of the user-defined function shall be the value of the access function reference for the current iteration.
- The second argument shall be the appropriate internal state; generally, this is the value that was returned by the `$limit()` function on the previous iteration.
- If more than two arguments are given to the `$limit()` function, then the third and subsequent arguments are passed as the third and subsequent arguments of the user-defined function.

The arguments of the user-defined function shall all be declared **input**.

In order to prevent convergence when the output of the `$limit()` function is not sufficiently close to the value of the access function reference, the user-defined function shall call `$discontinuity(-1)` (see Section 10.7) when its return value is not sufficiently close to the value of its first argument.

*Example:*

The module below defines a diode and includes an analog function that mimics the behavior of `pnjlim` in SPICE. Though `limexp()` could have been used for the exponential in the current, using `$limit()` allows the same voltage to be used in the charge calculation.

```

module diode(a,c);
  electrical a, c;
  inout a, c;
  parameter real IS = 1.0e-14;
  parameter real CJO = 0.0;
  analog function real spicepnjlim;
  input vnew, vold, vt, vcrit;
  real vnew, vold, vt, vcrit, arg;
  begin
    if ((vnew > vcrit) && (abs(vnew-vold) > (vt+vt))) begin
      if (vold > 0) begin
        arg = 1 + (vnew-vold) / vt;
        if (arg > 0)
          vnew = vold + vt * ln(arg);
        else
          vnew = vcrit;
        end else
        vnew = vt * ln(vnew/vt);
      end
      $discontinuity(-1);
    end
    spicepnjlim = vnew;
  end
endfunction
real vdio, idio, qdio;
analog begin
  vdio = $limit(V(a,c), spicepnjlim, $vt, vcrit);
  idio = IS * (exp(vdio/$vt) - 1);
  I(a,c) <+ idio;
  if (vdio < 0.5) begin
    qdio = 0.5 * CJO * (1-sqrt(1-Vd));
  end else begin
    qdio = cjo * (2.0*(1.0-sqrt(0.5))
      + sqrt(2.0)/2.0*(vdio*vdio+vdio-3.0/4.0));
  end
  I(a,c) <+ ddt(qdio);
end
endmodule

```

## 10.10 Hierarchical system parameter functions

The syntax for these functions are shown in Syntax 10-10.

```

hierarchical_system_parameter_functions ::=
    $mfactor
    | $xposition
    | $yposition
    | $angle
    | $hflip
    | $vflip

```

Syntax 10-10—Syntax for the hierarchical system parameter functions

These functions return hierarchical information about the instance of a module or paramset.

**\$mfactor** is the shunt multiplicity factor of the instance, that is, the number of identical devices that should be combined in parallel and modeled.

**\$xposition** and **\$yposition** are the offsets, in meters, of the location of the center of the instance.

**\$hflip** and **\$vflip** are used to indicate that the instance has been mirrored about its center, and **\$angle** indicates that the instance has been rotated some number of degrees in the counter-clockwise directions.

The value returned for each of these functions is computed by combining values from the top of the hierarchy down to the instance making the function call. The rules for combining the values are given in Table 10-6. The top-level value is the starting value at the top of the hierarchy. If a module is instantiated without specifying a value of one of these system parameters (using any of the methods in Section 7.2), then the value of that system parameter will be unchanged from the instantiating module. If a value is specified, then it is combined with the value from the instantiating module according to the appropriate rule from Table 10-6: the subscript “specified” indicates the value specified for the instance, and the subscript “hier” indicates the value obtained by traversing the hierarchy from the top to the instantiating module.

Table 10-6— Hierarchical parameter values

System parameter	Top-level value	Resolved value for instance	Allowed values
<b>\$angle</b>	0 degrees	$\mathbf{\$angle}_{\text{specified}} + \mathbf{\$angle}_{\text{hier}}$ , modulo 360 degrees	$0 \leq \mathbf{\$angle} < 360$
<b>\$hflip</b>	+1	$\mathbf{\$hflip}_{\text{specified}} * \mathbf{\$hflip}_{\text{hier}}$	$\mathbf{\$hflip} = +1 \text{ or } -1$
<b>\$mfactor</b>	1.0	$\mathbf{\$mfactor}_{\text{specified}} * \mathbf{\$mfactor}_{\text{hier}}$	$\mathbf{\$mfactor} > 0$

**Table 10-6— Hierarchical parameter values**

<b>\$vflip</b>	+1	<b>\$vflip</b> <sub>specified</sub> * <b>\$vflip</b> <sub>hier</sub>	<b>\$vflip</b> = +1 or -1
<b>\$xposition</b>	0.0 m	<b>\$xposition</b> <sub>specified</sub> + <b>\$xposition</b> <sub>hier</sub>	Any
<b>\$yposition</b>	0.0 m	<b>\$yposition</b> <sub>specified</sub> + <b>\$yposition</b> <sub>hier</sub>	Any

For example, when a module makes a call to **\$mfactor**, the simulator computes the product of the multiplicity factor specified for the instance (or 1.0, if no override was specified) times the value for the parent module that instantiated the module, times the parent's parent's value, and so on, until the top level is reached.

Note that **\$angle** is specified and returned in degrees, but the trigonometric functions of Section 4.2.2 operate in radians.

## 10.11 Hierarchy detection functions

The behavioral code of a module can depend on the way in which it was instantiated. The hierarchy detection functions shown in Syntax 10-11 may be used to determine information about the instantiation.

```

genvar_system_function ::=
    $param_given ( module_parameter_identifier )
    | $port_connected ( port_scalar_expression )

```

*Syntax 10-11—Syntax for the hierarchy detection functions*

Note that the return values of these functions shall be constant during a simulation; the value is fixed during elaboration. As such, these functions can be used in genvar expressions controlling conditional or looping behavior of the analog operators of Section 4.4.

The **\$param\_given()** function can be used to determine whether a parameter value was obtained from the default value in its declaration statement or if that value was overridden. The **\$param\_given()** function takes a single argument, which must be a parameter identifier. The return value shall be one (1) if the parameter was overridden, either by a **defparam** statement or by a module instance parameter value assignment, and zero (0) otherwise.

*Example:*

The following example sets the variable `temp` to represent the device temperature. Note that **\$temperature** is not a constant\_expression, so it cannot be used as the default value of the parameter `tdevice`. It is important to be able to distinguish the case where `tdevice` has its default value (say, 27) from the declaration statement from the case

where the value 27 was in fact specified as an override, if the simulation is performed at a different temperature.

```

if ($param_given(tdevice))
    temp = tdevice + `P_CELSIUS0;
else
    temp = $temperature;

```

Module ports need not be connected when the module is instantiated. The `$port_connected()` function can be used to determine whether a connection was specified for a port. The `$port_connected()` function takes one argument, which must be a port identifier. The return value shall be one (1) if the port was connected to a net (by order or by name) when the module was instantiated, and zero (0) otherwise. Note that the port may be connected to a net that has no other connections, but `$port_connected()` shall still return one.

*Example:*

In the following example, `$port_connected()` is used to skip the **transition** filter for unconnected nodes. In module `twoclk`, the instances of `myclk` only have connections for their `vout_q` ports, and thus the filter for `vout_qbar` is not implemented for either instance. In module `top`, the `vout_q2` port is not connected, so that the `vout_q` port of `topclk1.clk2` is not ultimately used in the circuit; however, the filter for `vout_q` of `clk2` is implemented, because it `vout_q` is connected on `clk2`'s instantiation line.

```

module myclk(vout_q, vout_qbar);
    output vout_q, vout_qbar;
    electrical vout_q, vout_qbar;
    parameter real tdel = 3u from [0:inf);
    parameter real trise = 1u from (0:inf);
    parameter real tfall = 1u from (0:inf);
    parameter real period = 20u from (0:inf);
    integer q;
    analog begin
        @ (timer(0, period))
            q = 0;
        @ (timer(period/2, period))
            q = 1;
        if ($port_connected(vout_q))
            V(vout_q) <+ transition( q, tdel, trise, tfall);
        else
            V(vout_q) <+ 0.0;
        if ($port_connected(vout_qbar))
            V(vout_qbar) <+ transition( !q, tdel, trise, tfall);
        else
            V(vout_qbar) <+ 0.0;
    end
endmodule

```

```

module twoclk(vout_q1, vout_q2);
  output vout_q1, vout_q2;
  electrical vout_q1, vout_q1b;
  myclk clk1(.vout_q(vout_q1));
  myclk clk2(.vout_q(vout_q2));
endmodule

module top(clk_out);
  output clk_out;
  electrical clk_out;
  twoclk topclk1(.vout_q1(clk_out));
endmodule

```

## 10.12 Interpolation function

The `$table_model` function models the behavior of a system by interpolating between data points that are samples of that system's behavior. To build such a model, the user provides a set of sample behavior points  $(x_{i1}, x_{i2}, \dots, x_{iN}, y_i)$  so that  $f(x_{i1}, x_{i2}, \dots, x_{iN}) = y_i$ , where  $f$  is the model function and  $N$  is the number of independent variables of the model. Using interpolation techniques, one can get the model value at any point in the domain of the sample points approximately. In the case when the evaluated point is outside the domain of the sample points, extrapolation techniques can be used to calculate the model value at that point. However, extrapolation is usually unreliable when the evaluated point is far from the domain of the sample points.

The syntax for the `$table_model` function is shown in Syntax 10-12.

```

table_model_function ::=
  $table_model ( table_inputs, table_data_source, table_control_string )

table_inputs ::=
  expression [, 2nd_dim_expression [, 3rd_dim_expression]]

table_data_source ::=
  filename_string | table_model_array

table_model_array ::=
  1st_dim_array_identifier [, 2nd_dim_array_identifier [, 3rd_dim_array_identifier]],
  output_array_identifier

table_control_string ::=
  "[1st_dim_table_ctrl_substr] [, 2nd_dim_table_ctrl_substr [, 3rd_dim_table_ctrl_substr]]"

table_ctrl_substr ::=
  [table_extrap_char [higher_table_extrap_char]]

table_extrap_char ::=
  L | E

```

Syntax 10-12—Syntax for table model function

The Verilog-AMS HDL provides only piecewise-linear interpolation for the **\$table\_model** function. Higher-order interpolation may be provided in a future revision.

The **\$table\_model** system function has the same restrictions as analog operators in terms of where it may be used - i.e. it shall not be used inside if, case or for statements unless these statements are controlled by genvar-constant expressions. See Section 4.4 for more details on the restrictions on analog operators.

### 10.12.1 Table model inputs

`table_inputs` are numerical expressions that are used as the independent model variables. They may be any legal expressions that can be assigned to an analog signal.

### 10.12.2 Table data source

`table_data_source` specifies the source of sample points for the table model. There are two kinds of data sources: files and arrays. The file source requires that the sample points be stored in a file, while the array source requires that the data points be stored in a set of array variables. The user may select the data source by either providing the file name of a file source or a set of array variables.

The table is constructed when the **\$table\_model** system function is called for the first time. If there are changes to the `table_data_source` argument(s) of the **\$table\_model** after the first call, these are ignored i.e. the table model is not reconstructed.

For a file source, each sample point is represented as a sequence of numbers in the order of  $X_{i1} X_{i2} \dots X_{iN} Y_i$ , where  $X_{ik}$  is the coordinate of the sample point in  $k$ 'th dimension and  $Y_i$  is the model value at this sample point. Each sample point shall be separated by a newline. The numbers in the sequence shall be separated by one or more spaces or tabs. To increase readability of the data file, comments may be inserted before or after any sample point. Comments begin with '#' and end with a newline.

The data file shall be in text format only. The numbers shall be real or integer (`real_number` or `decimal_number` as defined in Annex A.9).

The sample points may be stored in the file in any order. The following shows a sample data file:

```
# example.tbl
# 2-D table model sample example
#
#      x      y      f(x,y)
#      -10     -10     0
#      -10     -8      -0.4
#      -10     -6      -0.8
#      -9      -10     0.2
#      -9      -8      -0.2
#      -9      -6      -0.6
#      -9      -4      -1
#      -8      -10     0.4
#      -8      -9      0.2
#      -8      -7      -0.2
#      -8      -5      -0.6
#      -8      -3      -1
#      -7      -10     0.6
#      -7      -9      0.4
#      -7      -8      0.2
#      -7      -7      0
#      -7      -6      -0.2
#      -7      -5      -0.4
```

If the user chooses the array source, a set of one-dimensional arrays that contain the data points shall be passed to the `$table_model` function. The size of these arrays is the number of sample points in the table,  $M$ . The data will be stored in the arrays such that for the  $k^{\text{th}}$  dimension of the  $i^{\text{th}}$  sample point,  $k^{\text{th}}_{dim\_array\_identifier}[i] = X_{ik}$  and such that for the  $i^{\text{th}}$  sample point  $output\_array\_identifier[i] = Y_i$ .

An example using the array source is given in Section 10.12.4.

### 10.12.3 Extrapolation control string

The extrapolation control string is used to control the extrapolation process. It may contain one or two extrapolation method characters for each dimension of the model. The extrapolation method characters determine the behavior of the table model when the point to be evaluated is beyond the region of the user provided sample points. The Linear extrapolation method, specified with the character “L,” extends the nearest piecewise linear interpolation region to the requested point. The user may also disable extrapolation by choosing the Error extrapolation method using the character “E.” With this method, an extrapolation error is reported if the `$table_model` function is requested to evaluate a point beyond the interpolation region.

For each dimension of the table, users may use up to 2 extrapolation method characters to specify the extrapolation method used for each end. When no extrapolation method character is given, the Linear extrapolation method will be used for both ends as default.

When one extrapolation method character is given, the specified extrapolation method will be used for both ends. When two extrapolation method characters are given, the first character specifies the extrapolation method used for the end with the lower coordinate value, and the second character is used for the end with the higher coordinate value.

### 10.12.3.1 Control String Examples

Table 10-7 contains some examples of the control strings and interpretation.

**Table 10-7—Example control strings and their interpretation**

control string	1st dimen. lower coordinate extrap. method	1st dimen. higher coordinate extrap. method	2nd dimen. lower coordinate extrap. method	2nd dimen. higher coordinate extrap. method
"LE,EL"	Linear	Error	Error	Linear
"E,E"	Error	Error	Error	Error
",EL"	Linear	Linear	Error	Linear
""	Linear	Linear	Linear	Linear

### 10.12.4 Examples

The following examples are for the same 2-D table model but using the different types of data source.

*Example 1: \$table\_model with file data source*

Note the contents of `example.tbl` are those given earlier in this section.

```

module measured_resistance (a, b);
  electrical a, b;
  inout a, b;
  analog begin
    I(a, b) <+ $table_model (V(a), V(b), "example.tbl", "L,L");
  end
endmodule

```

*Example 2: \$table\_model with data source in one-dimensional arrays*

```

module measured_resistance (a, b);
electrical a, b;
inout a, b;
real x[0:17], y[0:17], f_xy[0:17];
analog begin
  @(initial_step) begin
    x[0]= -10; y[0]=-10; f_xy[0]=0; // 0th sample point
    x[1]= -10; y[1]=-8; f_xy[1]=-0.4; // 1st sample point
    x[2]= -10; y[2]=-6; f_xy[2]=-0.8; // 2nd sample point
    x[3]= -9; y[3]=-10; f_xy[3]=0.2;
    x[4]= -9; y[4]=-8; f_xy[4]=-0.2;
    x[5]= -9; y[5]=-6; f_xy[5]=-0.6;
    x[6]= -9; y[6]=-4; f_xy[6]=-1;
    x[7]= -8; y[7]=-10; f_xy[7]=0.4;
    x[8]= -8; y[8]=-9; f_xy[8]=0.2;
    x[9]= -8; y[9]=-7; f_xy[9]=-0.2;
    x[10]= -8; y[10]=-5; f_xy[10]=-0.6;
    x[11]= -8; y[11]=-3; f_xy[11]=-1;
    x[12]= -7; y[12]=-10; f_xy[12]=0.6;
    x[13]= -7; y[13]=-9; f_xy[13]=0.4;
    x[14]= -7; y[14]=-8; f_xy[14]=0.2;
    x[15]= -7; y[15]=-7; f_xy[15]=0;
    x[16]= -7; y[16]=-6; f_xy[16]=-0.2;
    x[17]= -7; y[17]=-5; f_xy[17]=-0.4;
  end
  I(a, b) <+ $stable_model (V(a), V(b), x, y, f_xy, "L,L");
end
endmodule

```

# Section 11

## Compiler directives

All Verilog-AMS HDL compiler directives are preceded by the ``` character. This character is called accent grave. It is different from the `'` character, which is the single quote character. The scope of compiler directives extends from the point where it is processed, across all files processed, to the point where another compiler directive supersedes it or the processing completes.

This section describes the following compiler directives:

```
`default_discipline
`default_transition
`define
`else
`endif
`ifdef
`include
`resetall
`undef
```

Those compiler directives defined in *IEEE 1364-1995 Verilog HDL* are also supported.

### 11.1 ``default_discipline`

The scope of this directive is similar to the scope of the ``define` compiler directive, although it can be used only outside of module definitions. The default discipline is applied to all discrete signals without a discipline declaration that appear in the text stream following the use of the ``default_discipline` directive, until either the end of the text stream or another ``default_discipline` directive with the qualifier (if applicable) is found in the subsequent text, even across source file boundaries. Therefore, more than one ``default_discipline` directive can be in force simultaneously, provided each differs in qualifier.

In addition to ``reset_all`, if this directive is used without a discipline name, it turns off all currently active default disciplines without setting a new default discipline. Subsequent discrete signals without a discipline shall be associated with the empty discipline. Syntax 11-1 shows the syntax for this directive.

```

default_discipline_directive ::=
  `default_discipline [discipline_identifier [ qualifier ] ]

qualifier ::=
  integer | real | reg | wreal
  wire | tri | wand | triand | wor | trior | triereg |
  tri0 | tri1 | supply0 | supply1

```

Syntax 11-1—Syntax for the default discipline compiler directive

*Example:*

```

`default_discipline logic
module behavnand(in1, in2, out);
  input in1, in2;
  output out;
  reg out;

  always begin
    out = ~(in1 && in2);
  end
endmodule

```

This example illustrates the usage of the ``default_discipline` directive. The nets `in1`, `in2`, and `out` all have discipline `logic` by default.

There is a precedence of compiler directives; the more specific directives have higher precedence over general directives.

## 11.2 ``default_transition`

The scope of this directive is similar to the scope of the ``define` compiler directive although it can be used only outside of module definitions. This directive specifies the default value for rise and fall time for the transition filter (see Section 4.4.9). There are no scope restrictions for this directive. The syntax for this directive is shown in Syntax 11-2.

```

default_transition_compiler_directive ::=
  `default_transition transition_time

transition_time ::=
  constant_expression

```

Syntax 11-2—Syntax for default transition compiler directive

*transition\_time* is a real value.

For all transition filters which follow this directive and do not have rise time and fall time arguments specified, *transition\_time* is used as the default rise and fall time values. If another ``default_transition` directive is encountered in the subsequent source description, the transition filters following the newly encountered directive derive their default rise and fall times from the transition time value of the newly encountered directive. In other words, the default rise and fall times for a transition filter are derived from the *transition\_time* value of the directive which immediately precedes the transition filter.

If a ``default_transition` directive is not used in the description, *transition\_time* is controlled by the simulator.

## 11.3 `define and `undef

A text macro substitution facility allows meaningful names to be used to represent commonly used pieces of text. For example, in the situation where a constant number is repetitively used throughout a description, a text macro would be useful, as only one place in the source description needs to be altered if the value of the constant changed.

### 11.3.1 `define

``define` creates a macro for text substitution. This directive can be used both inside and outside module definitions. After a text macro is defined, it can be used in the source description by using the ``` character, followed by the macro name. The compiler substitutes the text of the macro for the string *text\_macro\_name*. All compiler directives are considered pre-defined macro names; it is illegal to re-define a compiler directive as a macro name.

A text macro can be defined with arguments. This allows the macro to be customized for each use individually.

The syntax for text macro definitions is shown in Syntax 11-3.

```

text_macro_definition ::=
    `define text_macro_name macro_text

text_macro_name ::=
    text_macro_identifier [ ( list_of_formal_arguments ) ]

list_of_formal_arguments ::=
    formal_argument_identifier { , formal_argument_identifier }

```

Syntax 11-3—Syntax for text macro definition

The macro text can be any arbitrary text specified on the same line as the text macro name, but shall not begin with `__VAMS_` to avoid conflicts with predefined macros in Section 11.7. If more than one line is necessary to specify the text, the newline shall be

preceded by a backslash (`\`). The first newline not preceded by a backslash shall end the macro text. The newline preceded by a backslash is replaced in the expanded macro with a newline (but without the preceding backslash character).

When formal arguments are used to define a text macro, the scope of the formal arguments extend up to the end of the macro text. A formal argument can be used in the macro text in the same manner as an identifier.

If a one-line comment (i.e., a comment specified with the characters `//`) is included in the text, the comment does not become part of the text substituted. The macro text can be blank, in which case the text macro is defined to be empty and no text is substituted when the macro is used.

The syntax for using a text macro shown in Syntax 11-4.

```

text_macro_usage ::=
    `text_macro_identifier [ ( list_of_actual_arguments ) ]

list_of_actual_arguments ::=
    actual_argument { , actual_argument }

actual_argument ::=
    expression

```

*Syntax 11-4—Syntax for text macro usage*

For a macro without an argument, the text is substituted “as is” for every occurrence of ``text_macro`. However, a text macro with one or more arguments shall be expanded by substituting each formal argument with the expression used as the actual argument in the macro usage.

Once a text macro name has been defined, it can be used anywhere in a source description; i.e., there are no scope restrictions.

The text specified for macro text can not be split across the following lexical tokens:

- comments
- numbers
- strings
- identifiers
- keywords
- operators

*Examples:*

```
`define M_PI 3.14159265358979323846
```

```

`define size 8
electrical [1:` size] vout;

//define an adc with variable delay
`define var_adc(dly) adc #(dly)
// Given the above macro the following uses
`var_adc(2) g121 (q21, n10, n11);
`var_adc(5) g122 (q22, n10, n11);

// shall result in:
adc #(2) g121 (q21, n10, n11);
adc #(5) g122 (q22, n10, n11);

```

The following is illegal syntax because it is split across a string.

```

`define first_half "start of string
$display(`first_half end of string");

```

**Note 1:** Text macro names can not be the same as compiler directive keywords.

**Note 2:** Text macro names can re-use names being used as ordinary identifiers. For example, `signal_name` and ``signal_name` are different.

**Note 3:** Redefinition of text macros is allowed; the latest definition of a particular text macro read by the compiler prevails when the macro name is encountered in the source text.

### 11.3.2 ``undef`

``undef` undefines a previously defined text macro. An attempt to undefine a text macro which was not previously defined by a ``define` compiler directive can result in a warning. The syntax for ``undef` is shown in Syntax 11-5.

<pre> undefine_compiler_directive ::= `undef text_macro_identifier </pre>
---

Syntax 11-5—Syntax for `undef` compiler directive

An undefined text macro has no value.

## 11.4 ``ifdef, `else, `endif`

These conditional compilation compiler directives are used to optionally include lines of a Verilog-AMS HDL source description during compilation. ``ifdef` checks for the definition of a variable name. If the variable name is defined, the lines following the ``ifdef` directive are included. If the variable name is not defined and an ``else` directive exists, then this source is compiled.

These directives can appear anywhere in the source description.

``ifdef`, ``else`, and ``endif` can be useful when:

- selecting different representations of a module such as behavioral, structural, or mixed level;
- choosing different timing or structural information; or
- selecting different stimulus for a given simulation run.

Syntax 11-6 shows the syntax for ``ifdef`, ``else`, and ``endif`.

```
conditional_compilation_directive ::=
  `ifdef text_macro_name
    first_group_of_lines
  [ `else
    second_group_of_lines
  `endif ]
```

Syntax 11-6—Syntax for conditional compilation directives

*text\_macro\_name* is a Verilog-AMS HDL identifier. The *first\_group\_of\_lines* and the *second\_group\_of\_lines* are parts of a Verilog-AMS HDL source description. The ``else` compiler directive and the *second\_group\_of\_lines* are optional.

``ifdef`, ``else`, and ``endif` work in the following manner:

- When an ``ifdef` is encountered, *text\_macro\_name* is tested to see if it is defined as a *text\_macro\_name* by ``define` within the Verilog-AMS HDL source description.
- If *text\_macro\_name* is defined, the *first\_group\_of\_lines* is compiled as part of the description. If there is an ``else` compiler directive, the *second\_group\_of\_lines* is ignored.
- If *text\_macro\_name* has not been defined, the *first\_group\_of\_lines* is ignored. If there is an ``else` compiler directive the *second\_group\_of\_lines* is compiled.

**Note 1:** Any group of lines the compiler ignores still needs to follow the Verilog-AMS HDL lexical conventions for white space, comments, numbers, strings, identifiers, keywords, and operators.

**Note 2:** These compiler directives can be nested.

## 11.5 ``include`

This directive is used to insert the entire contents of a source file in another file during compilation. The result is as though the contents of the included source file appear in place of the ``include` compiler directive. ``include` can be used to include global or

commonly used definitions and tasks without encapsulating repeated code within module boundaries.

This directive can be useful in the following situations:

- providing an integral part of configuration management;
- improving the organization of Verilog-AMS HDL source descriptions; or
- facilitating the maintenance of Verilog-AMS HDL source descriptions.

The syntax for ``include` is shown in Syntax 11-7.

```
include_compiler_directive ::=
    `include "filename"
```

Syntax 11-7—Syntax for include compiler directive

The compiler directive ``include` can be specified anywhere within the Verilog-AMS HDL description. The *filename* is the name of the file to be included in the source file. The *filename* can be a full or relative path name.

Only white space or a comment can appear on the same line as the ``include` compiler directive.

A file included in the source using ``include` can contain other ``include` compiler directives. The number of nesting levels for included files are finite.

*Examples:*

```
`include "parts/count.v"
`include "fileA"
`include "fileB" // including fileB
```

**Note:** Implementations can limit the maximum number of levels to which include files can be nested, but this limit shall be a minimum of 15 levels.

## 11.6 `resetall

When the ``resetall` compiler directive is encountered during compilation, all compiler directives are set to their default values. This is useful for ensuring only those directives which are desired in compiling a particular source file are active.

To do so, place ``resetall` at the beginning of each source text file, followed immediately by the directives desired in the file.

## 11.7 Predefined macros

Verilog-AMS HDL supports a predefined macro to allow modules to be written that work with both *IEEE 1364-1995 Verilog HDL* and Verilog-AMS HDL. The predefined macro is called `__VAMS_ENABLE__`.

This macro shall always be defined during the parsing of Verilog-AMS source text. Its purpose is to support the creation of modules which are both legal Verilog and Verilog-AMS. The Verilog-AMS features of such modules are made visible only when the `__VAMS_ENABLE__` macro has previously been defined.

*Example:*

```

module not_gate(in, out);
  input in;
  output out;
  reg out;
  `ifdef __VAMS_ENABLE__
  parameter integer del = 1 from [1:100];
  `else
  parameter del = 1;
  `endif
  always @ in
    out = #del !in;
endmodule

```

Verilog-AMS HDL version 2.2 introduced a number of extensions to support compact modeling. A predefined macro allows modules to add functionality if these extensions are supported, or to generate warnings or errors if they are not. This predefined macro is called `__VAMS_COMPACT_MODELING__` and shall be defined during the parsing of Verilog-AMS source text if and only if all the compact modeling extensions are supported by the simulator.

The following example computes noise of a nonlinear resistor only if the extensions, specifically `ddx`, are supported.

*Example:*

```

module nonlin_res(a, b);
  input a, b;
  electrical a, b;
  parameter real rnom = 1;
  parameter real vc1 = 0;
  real reff, iab;
  analog begin
    iab = V(a,b) / (rnom * (1.0 + vc1 * V(a,b)));
    I(a,b) <+ iab;
  `ifdef __VAMS_COMPACT_MODELING__
    reff = ddx(iab, V(a));
  end
endmodule

```

```
        I(a,b) <+ white_noise(4.0*`P_K*$temperature*reff, "thermal");  
    `else  
        if (analysis("noise"))  
            $strobe("Noise not computed.");  
    `endif  
end  
endmodule
```

Verilog-AMS simulators shall also provide a predefined macro so that the module can conditionally include (or exclude) portions of the source text specific to a particular simulator. This macro shall be documented in the Verilog-AMS section of the simulator manual.



# Section 12

## Using VPI routines

Sections 12 and 13 specify the Verilog Procedural Interface (VPI) for the Verilog-AMS HDL. This section describes how the VPI routines are used and Section 13 defines each of the routines in alphabetical order.

### 12.1 The VPI interface

The VPI interface provides routines which allow Verilog-AMS product users to access information contained in a Verilog-AMS design and allow facilities to interact dynamically with a software product. Applications of the VPI interface can include delay calculators and annotators, connecting a Verilog-AMS simulator with other simulation and CAE systems, and customized debugging tasks.

The functions of the VPI interface can be grouped into two main areas:

- Dynamic software product interaction using VPI callbacks
- Access to Verilog-AMS HDL objects and simulation specific objects

#### 12.1.1 VPI callbacks

Dynamic software product interaction shall be accomplished with a registered callback mechanism. VPI callbacks shall allow a user to request a Verilog-AMS HDL software product, such as a logic simulator, call a user-defined application when a specific activity occurs. For example, the user can request the user application `my_monitor()` be called when a particular net changes value or `my_cleanup()` be called when the software product execution has completed.

The VPI callback facility shall provide the user with the means to interact dynamically with a software product, detecting the occurrence of value changes, advancement of time, end of simulation, etc. This feature allows applications such as integration with other simulation systems, specialized timing checks, complex debugging features, etc. to be used.

The reasons for providing callbacks can be separated into four categories:

- *Simulation event* (e.g., a value change on a net or a behavioral statement execution)
- *Simulation time* (e.g., the end of a time queue or after certain amount of time)

- *Simulator action/feature* (e.g., the end of compile, end of simulation, restart, or enter interactive mode)
- *User-defined system task or function execution*

VPI callbacks shall be registered by the user with the functions `vpi_register_cb()`, `vpi_register_systf()` and `vpi_register_analog_systf()`. These routines indicate the specific reason for the callback, the application to be called, and what system and user data shall be passed to the callback application when the callback occurs. A facility is also provided to call the callback functions when a Verilog-AMS HDL product is first invoked. A primary use of this facility shall be for the registration of user-defined system tasks and functions.

### 12.1.2 VPI access to Verilog-AMS HDL objects and simulation objects

Accessible Verilog-AMS HDL objects and simulation objects and their relationships and properties are described using data model diagrams. These diagrams are presented in Section 12.5. The data diagrams indicate the routines and constants which are required to access and manipulate objects within an application environment. An associated set of routines to access these objects is defined in Section 13.

The VPI interface also includes a set of utility routines for functions such as handle comparison, file handling, and redirected printing, which are described in Section 13.12.

VPI routines provide access to objects in an *instantiated* Verilog-AMS design. An instantiated design is one where each instance of an object is uniquely accessible. For instance, if a module `m` contains wire `w` and is instantiated twice as `m1` and `m2`, then `m1.w` and `m2.w` are two distinct objects, each with its own set of related objects and properties.

The VPI interface is designed as a *simulation* interface, with access to both Verilog-AMS HDL objects and specific simulation objects. This simulation interface is different from a hierarchical language interface, which would provide access to HDL information but would not provide information about simulation objects.

### 12.1.3 Error handling

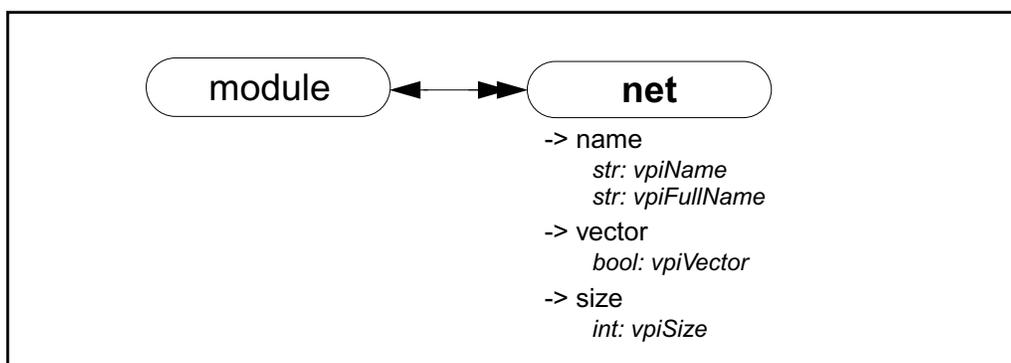
To determine if an error occurred, the routine `vpi_chk_error()` shall be provided. The `vpi_chk_error()` routine shall return a nonzero value if an error occurred in the previously called VPI routine. Callbacks can be set up for when an error occurs as well. The `vpi_chk_error()` routine can provide detailed information about the error.

## 12.2 VPI object classifications

VPI objects are classified with data model diagrams. These diagrams provide a graphical representation of those objects within a Verilog-AMS design to which the VPI routines

shall provide access. The diagrams shall show the relationships between objects and the properties of each object. Objects with sufficient commonality are placed in groups. Group relationships and properties apply to all the objects in the group.

As an example, the simplified diagram in Figure 12-1 shows there is a *one-to-many relationships* from objects of type `module` to objects of type `net` and a *one-to-one relationship* from objects of type `net` to objects of type `module`. Objects of type `net` have properties `vpiName`, `vpiVector`, and `vpiSize`, with the C data types `string`, `Boolean`, and `integer` respectively.



**Figure 12-1 Object relationships**

The VPI object data diagrams are presented in Section 12.5.

### 12.2.1 Accessing object relationships and properties

The VPI interface defines the C data type of `vpiHandle`. All objects are manipulated via a `vpiHandle` variable. Object handles can be accessed from a relationship with another object, or from a hierarchical name, as the following example demonstrates.

*Examples:*

```
vpiHandle net;
net = vpi_handle_by_name("top.m1.w1", NULL);
```

This example call retrieves a handle to wire `top.m1.w1` and assigns it to the `vpiHandle` variable `net`. The `NULL` second argument directs the routine to search for the name from the top level of the design.

The VPI interface provides generic functions for tasks, such as traversing relationships and determining property values. One-to-one relationships are traversed with routine `vpi_handle()`.

*Examples:*

In the following example, the module containing `net` is derived from a handle to that net:

```
vpiHandle net, mod;
net = vpi_handle_by_name("top.m1.w1", NULL);
mod = vpi_handle(vpiModule, net);
```

The call to `vpi_handle()` in the above example shall return a handle to module `top.m1`. Properties of objects shall be derived with routines in the `vpi_get` family. The routine `vpi_get()` returns integer and Boolean properties. The routine `vpi_get_str()` accesses string properties.

*Example:*

To retrieve a pointer to the full hierarchical name of the object referenced by handle `mod`, the following call would be made:

```
char *name = vpi_get_str(vpiFullName, mod);
```

In the above example, character pointer `name` shall now point to the string `top.m1`.

One-to-many relationships are traversed with an iteration mechanism. The routine `vpi_iterate()` creates an object of type `vpi_iterator`, which is then passed to the routine `vpi_scan()` to traverse the desired objects.

*Examples:*

In the following example, each net in module `top.m1` is displayed:

```
vpiHandle itr;
itr = vpi_iterate(vpiNet, mod);
while (net = vpi_scan(itr) )
    vpi_printf( "\t%s\n", vpi_get_str(vpiFullName, net) );
```

As the above examples illustrate, the routine naming convention is a *vpi* prefix with ‘\_’ word delimiters (with the exception of callback-related defined values, which use the *cb* prefix). Macro-defined types and properties have the *vpi* prefix and they use capitalization for word delimiters.

The routines for traversing Verilog-AMS HDL structures and accessing objects are described in *IEEE 1364-1995 Verilog HDL*, section 22.

## 12.2.2 Delays and values

Properties are of type integer, boolean, real or string. Delay and logic value properties, however, are more complex and require specialized routines and associated structures. The routines `vpi_get_delays()` and `vpi_put_delays()` use structure pointers, where the structure contains the pertinent information about delays. Similarly, simulation values are also handled with the routines `vpi_get_value()` and `vpi_put_value()`, along with an associated set of structures. For analog tasks and functions, `vpi_handle_multi()` and `vpi_put_value()` support declaration and assignment of derivatives for the task arguments and function return values.

The routines and C structures for handling delays, derivatives, and logic values are presented in *IEEE 1364-1995 Verilog HDL*, section 22.

## 12.3 List of VPI routines by functional category

The VPI routines can be divided into groups based on primary functionality.

- VPI routines for simulation-related callbacks
- VPI routines for system task/function callbacks
- VPI routines for traversing Verilog-AMS HDL hierarchy
- VPI routines for accessing properties of objects
- VPI routines for accessing objects from properties
- VPI routines for delay processing
- VPI routines for logic and strength value processing
- VPI routines for task parameters derivatives processing
- VPI routines for analysis and simulation time processing
- VPI routines for miscellaneous utilities

Table 12-1 through Table 12-9 list the VPI routines by major category. *IEEE 1364-1995 Verilog HDL*, Section 22 defines each of the VPI routines, listed in alphabetical order.

**Table 12-1—VPI routines for simulation related callbacks**

To	Use
Register a simulation-related callback	<code>vpi_register_cb()</code>
Remove a simulation-related callback	<code>vpi_remove_cb()</code>
Get information about a simulation-related callback	<code>vpi_get_cb_info()</code>

**Table 12-2—VPI routines for system task/function callbacks**

To	Use
Register a system task/function callback	<code>vpi_register_systf()</code>
Get information about a system task/function callback	<code>vpi_get_systf_info()</code>

**Table 12-3—VPI routines for analog system task/function callbacks**

To	Use
Register a analog system task/function callback	<code>vpi_register_analog_systf()</code>
Get information about a analog system task/function callback	<code>vpi_get_analog_systf_info()</code>

**Table 12-4—VPI routines for traversing Verilog-AMS HDL hierarchy**

To	Use
Obtain a handle for an object with a one-to-one relationship	<code>vpi_handle()</code>
Obtain handles for objects in a one-to-many relationship	<code>vpi_iterate()</code> <code>vpi_scan()</code>
Obtain a handles for an object in a many-to-one relationship	<code>vpi_handle_multi()</code>

**Table 12-5—VPI routines for accessing properties of objects**

To	Use
Get the value of objects with types of int or bool	<code>vpi_get()</code>
Get the value of objects with types of string	<code>vpi_get_str()</code>
Get the value of objects with types of real	<code>vpi_get_real()</code>

**Table 12-6—VPI routines for accessing objects from properties**

To	Use
Obtain a handle for a named object	<code>vpi_handle_by_name()</code>
Obtain a handle for an indexed object	<code>vpi_handle_by_index()</code>

**Table 12-7—VPI routines for delay processing**

To	Use
Retrieve delays or timing limits of an object	<code>vpi_get_delays()</code>
Write delays or timing limits to an object	<code>vpi_put_delays()</code>

**Table 12-8—VPI routines for logic, real, strength and analog value processing**

To	Use
Retrieve logic value or strength value of an object	<code>vpi_get_value()</code>
Write logic value or strength value to an object	<code>vpi_put_value()</code>
Retrieve values of an analog object	<code>vpi_get_analog_value()</code>

**Table 12-9—VPI routines for analysis and simulation time processing**

To	Use
Find the current simulation time or the scheduled time of future events	<code>vpi_get_time()</code>
Find the current simulation time value in the continuous domain.	<code>vpi_get_analog_time()</code>
Find the current simulation time delta value in continuous domain.	<code>vpi_get_analog_delta()</code>
Find the current simulation frequency in the small-signal domain.	<code>vpi_get_analog_freq()</code>

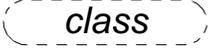
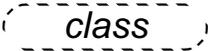
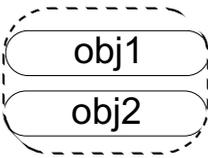
**Table 12-10—VPI routines for miscellaneous utilities**

To	Use
Write to stdout and the current log file	<code>vpi_printf()</code>
Open a file for writing	<code>vpi_mcd_open()</code>
Close one or more files	<code>vpi_mcd_close()</code>
Write to one or more files	<code>vpi_mcd_printf()</code>
Retrieve the name of an open file	<code>vpi_mcd_name()</code>
Retrieve data about product invocation options	<code>vpi_get_vlog_info()</code>
See if two handles refer to the same object	<code>vpi_compare_objects()</code>
Obtain error status and error information about the previous call to a VPI routine	<code>vpi_chk_error()</code>
Free memory allocated by VPI routines	<code>vpi_free_object()</code>

## 12.4 Key to object model diagrams

This clause contains the keys to the symbols used in the object model diagrams. Keys are provided for objects and classes, traversing relationships, and accessing properties.

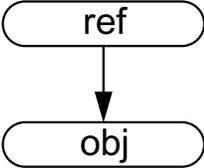
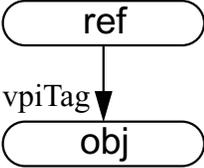
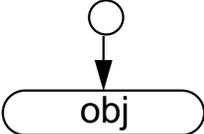
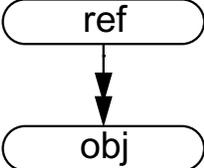
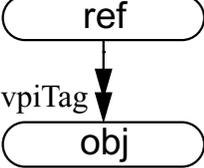
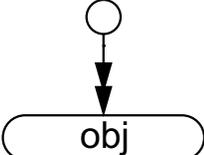
### 12.4.1 Diagram key for objects and classes

	<p>Object Definition:</p> <p><b>Bold</b> letters in a solid enclosure indicate an object definition. The properties of the object are defined in this location.</p>
	<p>Object Reference:</p> <p>Normal letters in a solid enclosure indicate an object reference.</p>
<p><b><i>class defn</i></b></p>   	<p>Class Definition:</p> <p><b><i>Bold italic</i></b> letters in a dotted enclosure indicate a class definition, where the class groups other objects and classes. Properties of the class are defined in this location. The class definition can contain an object definition.</p>
	<p>Class Reference:</p> <p><i>Italic</i> letters in a dotted enclosure indicate a class reference.</p>
	<p>Unnamed Class:</p> <p>A dotted enclosure with no name is an unnamed class. It is sometimes convenient to group objects although they shall not be referenced as a group elsewhere, so a name is not indicated.</p>

## 12.4.2 Diagram key for accessing properties

<p><b>obj</b></p> <p>-&gt; vector  <i>bool: vpiVector</i></p> <p>-&gt; size  <i>int: vpiSize</i></p>	<p>Integer and Boolean properties are accessed with the routine <b>vpi_get()</b>.</p> <p>Example: Given a <b>vpiHandle</b> obj_h to an object of type <b>vpiObj</b>, get the size of the object.</p> <pre>bool vect_flag = vpi_get(vpivector, obj_h); int size = vpi_get_size(vpiSize, obj_h);</pre>
<p><b>obj</b></p> <p>-&gt; name  <i>str: vpiName</i>  <i>str: vpiFullName</i></p>	<p>String properties are accessed with routine <b>vpi_get_str()</b>.</p> <p>Example:</p> <pre>char name[nameSize]; vpi_get_str(vpiName, obj_h);</pre>
<p><b>object</b></p> <p>-&gt; complex  <i>func1()</i>  <i>func2()</i></p>	<p>Complex properties for time and logic value are accessed with the indicated routines. See the descriptions of the routines for usage.</p>

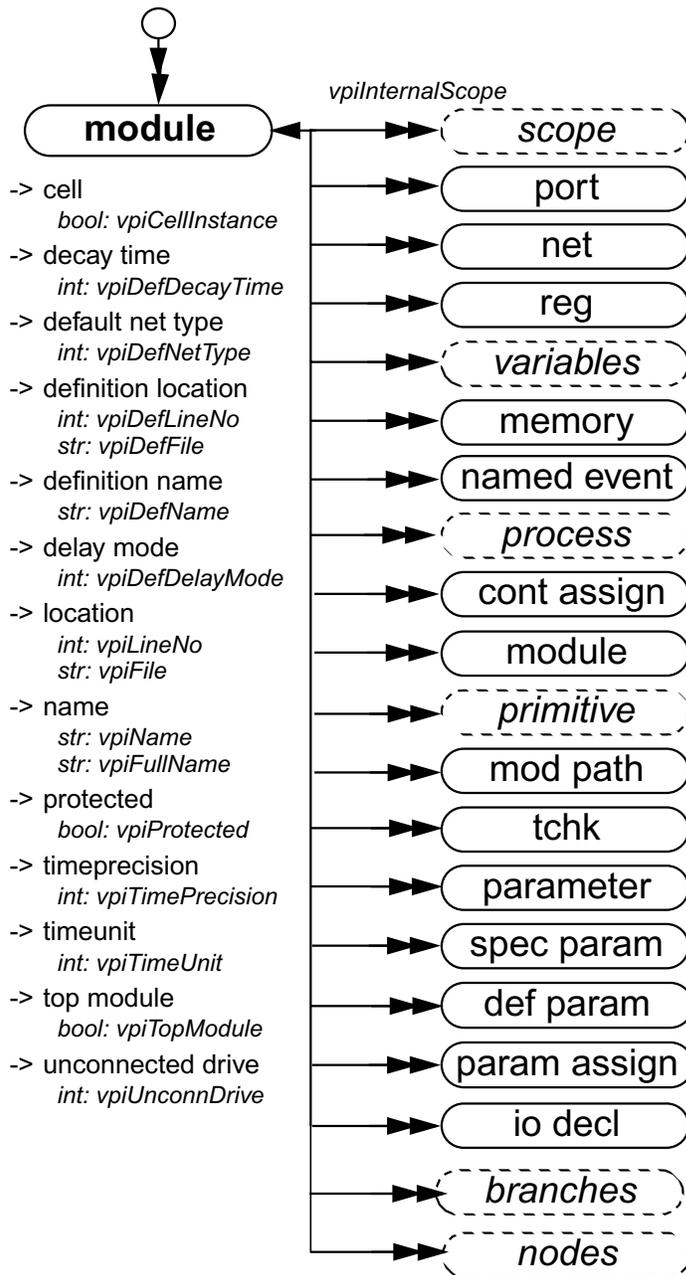
### 12.4.3 Diagram key for traversing relationships

	<p>A single arrow indicates a <i>one-to-one</i> relationship accessed with the routine <b>vpi_handle()</b>.</p> <p>Example: Given <b>vpiHandle</b> variable ref_h of type ref, access obj_h of type <b>vpiObj</b>:</p> <pre>obj_h = vpi_handle(vpiObj, ref_h);</pre>
	<p>A tagged <i>one-to-one</i> relationship is traversed similarly, using <b>vpiTag</b> instead of <b>vpiObj</b>:</p> <p>Example:</p> <pre>obj_h = vpi_handle(vpiTag, ref_h);</pre>
	<p>A top-level <i>one-to-one</i> relationship is traversed similarly, using NULL instead of ref_h:</p> <p>Example:</p> <pre>obj_h = vpi_handle(vpiObj, NULL);</pre>
	<p>A double arrow indicates a <i>one-to-many</i> relationship accessed with the routine <b>vpi_scan()</b>.</p> <p>Example: Given <b>vpiHandle</b> variable ref_h of type ref, scan objects of type <b>vpiObj</b>:</p> <pre>itr = vpi_iterate(vpiObj, ref_h); while (obj_h = vpi_scan(itr) ) /* process 'obj_h' */</pre>
	<p>A tagged <i>one-to-many</i> relationship is traversed similarly, using <b>vpiTag</b> instead of <b>vpiObj</b>:</p> <p>Example:</p> <pre>itr = vpi_iterate(vpiTag, ref_h); while (obj_h = vpi_scan(itr) ) /* process 'obj_h' */</pre>
	<p>A top-level <i>one-to-many</i> relationship is traversed similarly, using NULL instead of ref_h:</p> <p>Example:</p> <pre>itr = vpi_iterate(vpiObj, NULL); while (obj_h = vpi_scan(itr) ) /* process 'obj_h' */</pre>

## **12.5 Object data model diagrams**

Subclauses in Sections 12.5.1 through 12.5.26 contain the data model diagrams that define the accessible objects and groups of objects, along with their relationships and properties.

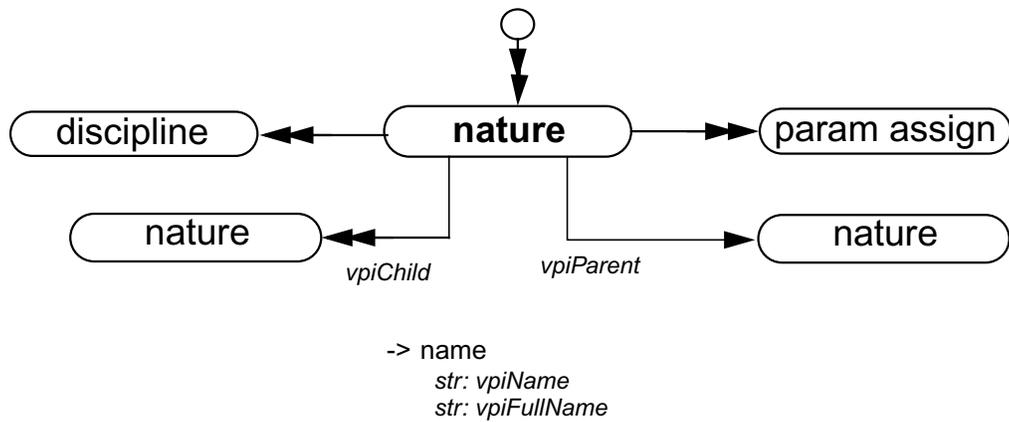
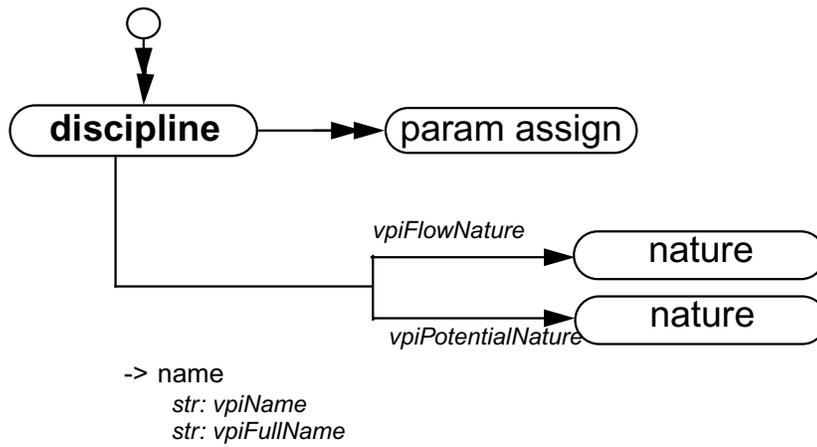
### 12.5.1 Module



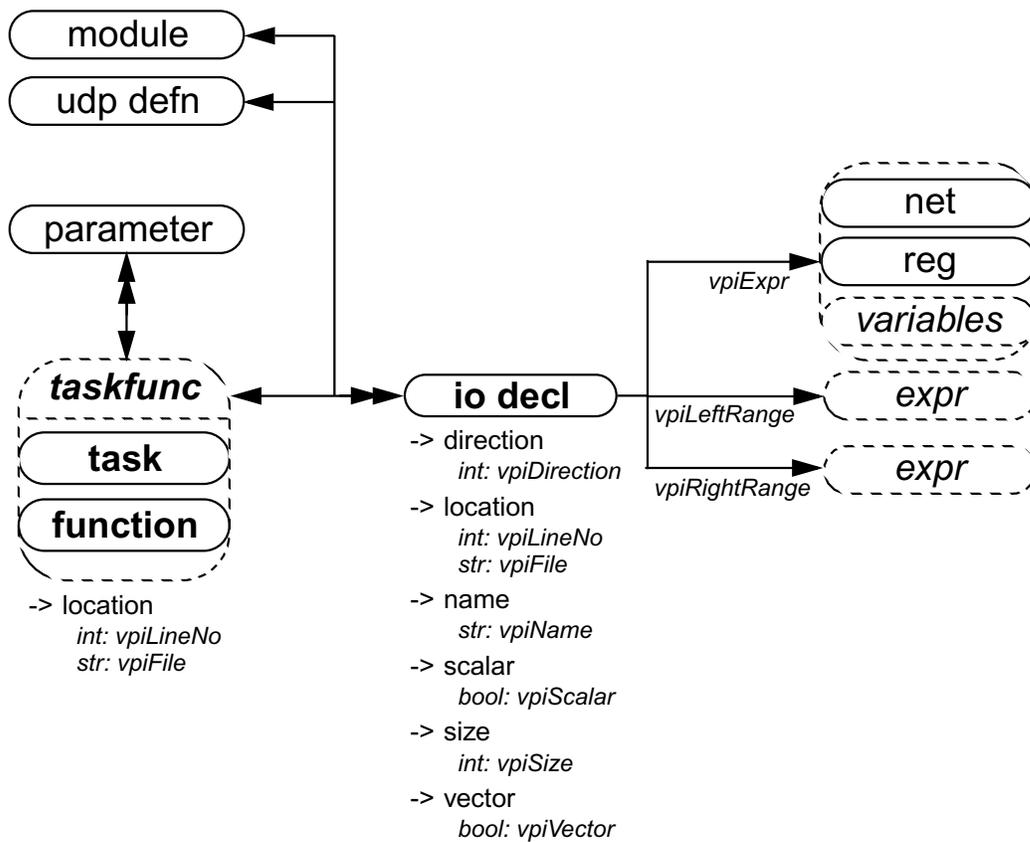
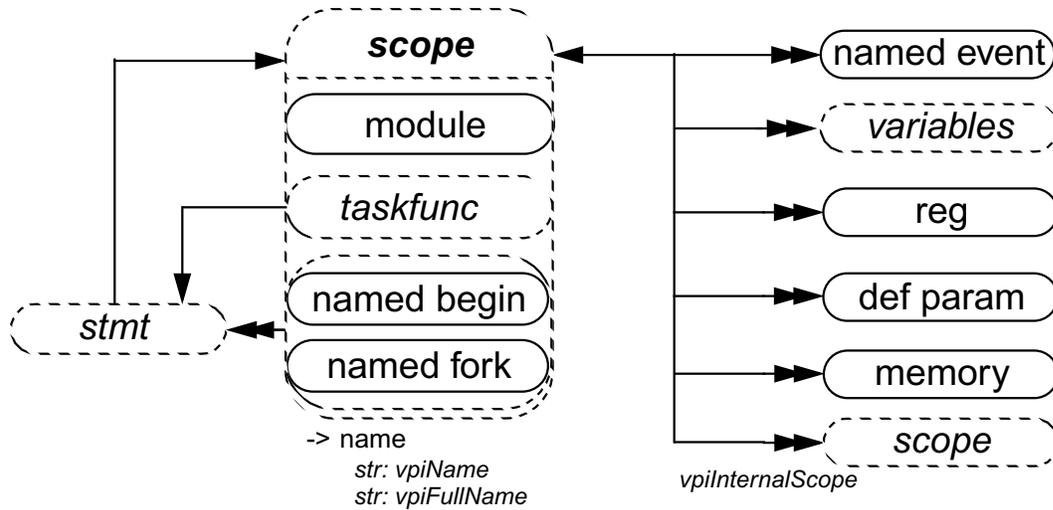
#### NOTES

- 1—Top-level modules shall be accessed using **vpi\_iterate()** with a NULL reference object.
- 2—Passing a NULL handle to **vpi\_get()** with types **vpiTimePrecision** or **vpiTimeUnit** shall return the smallest time precision of all modules in the instantiated design.

12.5.2 Nature, discipline

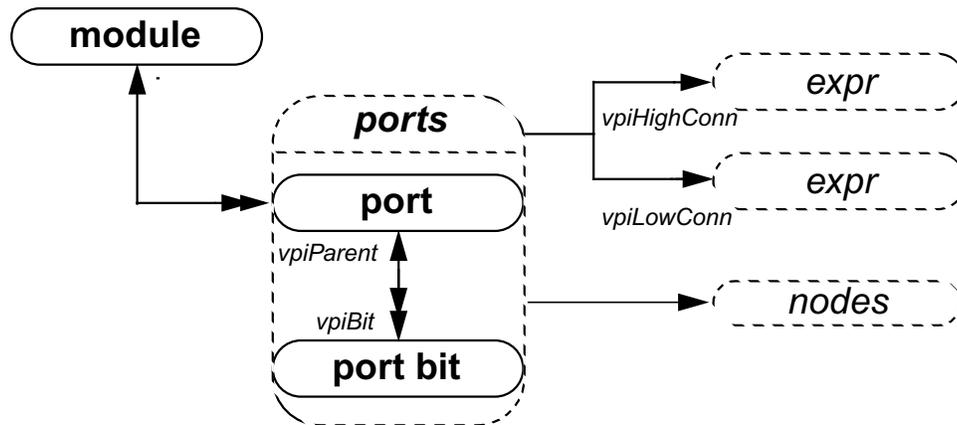


### 12.5.3 Scope, task, function, IO declaration



NOTE—A Verilog-AMS HDL function shall contain an object with the same name, size, and type as the function.

### 12.5.4 Ports

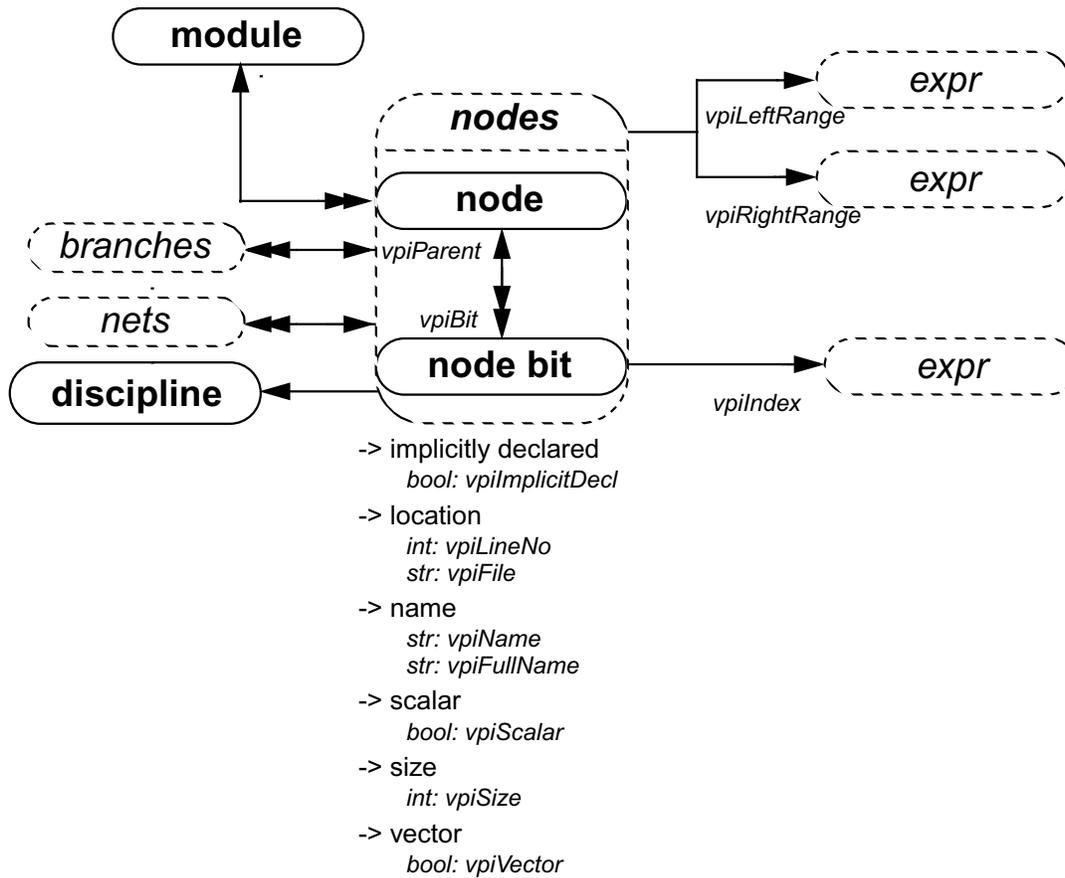


- > connected by name  
*bool: vpiConnByName*
- > delay (mipd)  
*vpi\_get\_delays()*  
*vpi\_put\_delays()*
- > direction  
*int: vpiDirection*
- > explicitly named  
*bool: vpiExplicitName*
- > index  
*int: vpiPortIndex*
- > location  
*int: vpiLineNo*  
*str: vpiFile*
- > name  
*str: vpiName*  
*str: vpiFullName*
- > scalar  
*bool: vpiScalar*
- > size  
*int: vpiSize*
- > vector  
*bool: vpiVector*

#### NOTES

- 1— **vpiHighConn** shall indicate the hierarchically higher (closer to the top module) port connection.
- 2— **vpiLowConn** shall indicate the lower (further from the top module) port connection.
- 3— Properties *scalar* and *vector* shall indicate if the port is 1 bit or more than 1 bit. They shall not indicate anything about what is connected to the port.
- 4— Properties *index* and *name* shall not apply for port bits.
- 5— If a port is explicitly named, then the explicit name shall be returned. If not, and a name exists, that name shall be returned. Otherwise, NULL shall be returned.
- 6— **vpiPortIndex** can be used to determine the port order.

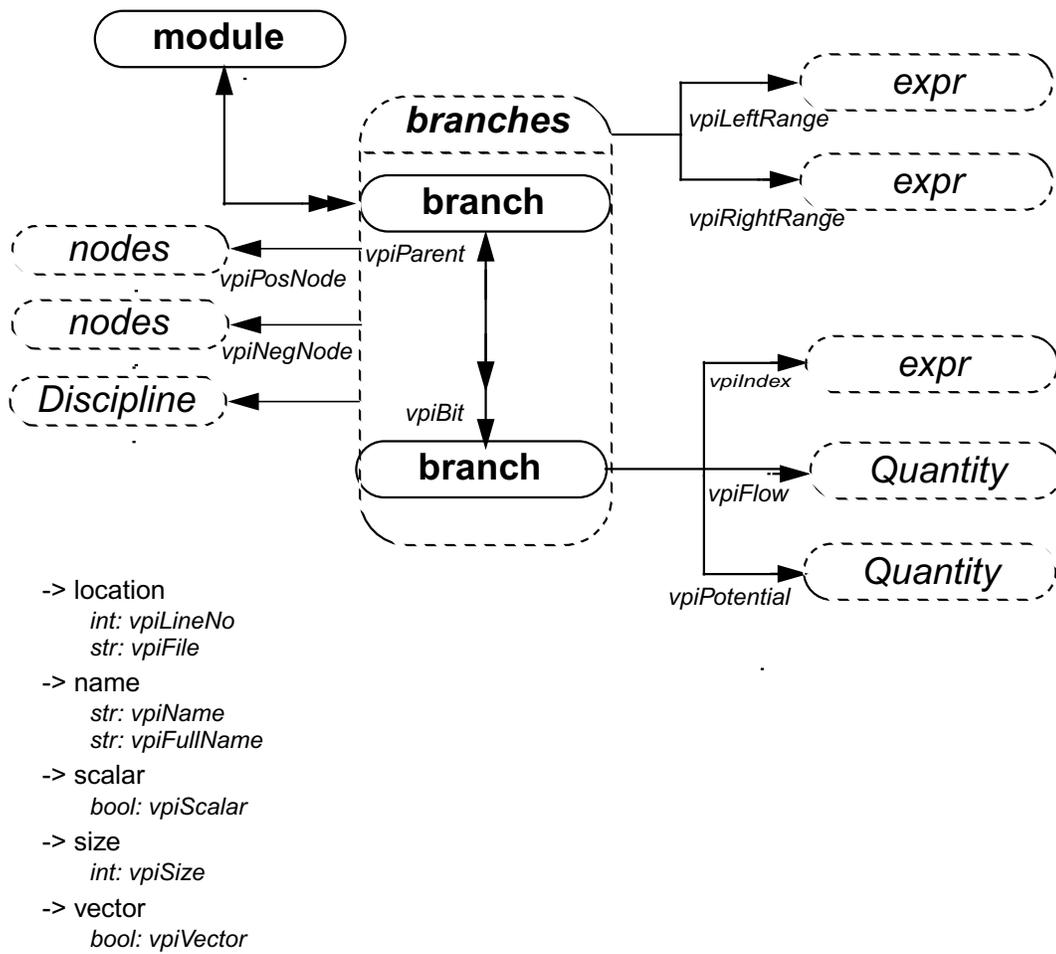
## 12.5.5 Nodes



## NOTES

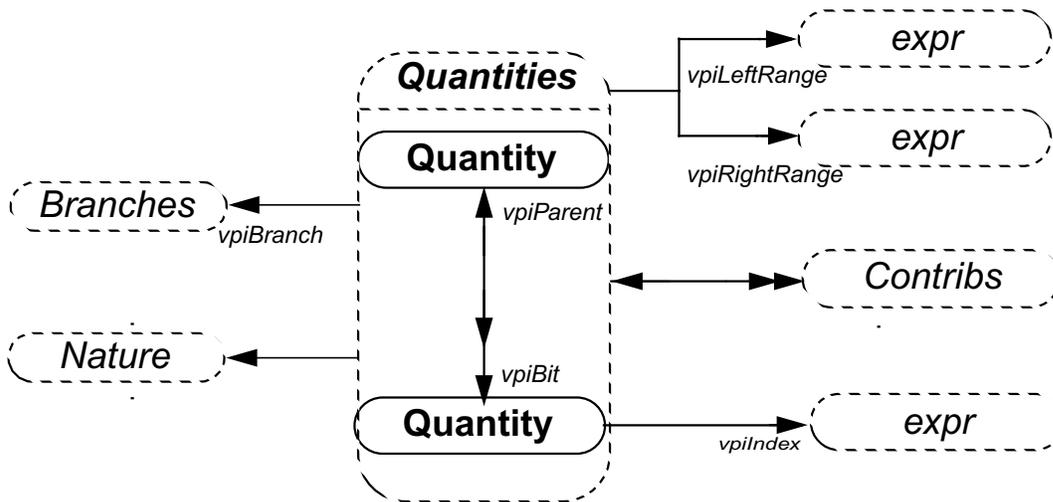
1—Properties *scalar* and *vector* shall indicate if the node is 1 bit or more than 1 bit.

## 12.5.6 Branches



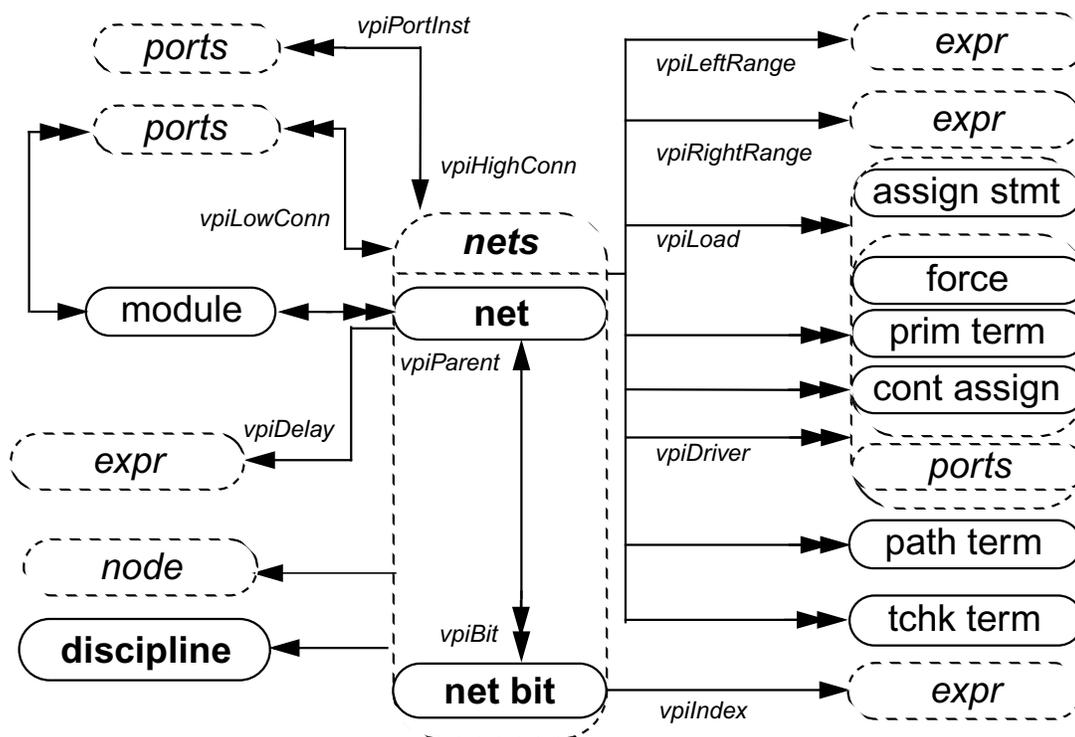
NOTE—Properties *scalar* and *vector* shall indicate if the branch is 1 bit or more than 1 bit.

## 12.5.7 Quantities



- > implicitly declared  
    *bool: vpiImplicitDecl*
- > real value  
    *vpi\_get\_analog\_value()*
- > imaginary value  
    *vpi\_get\_analog\_value()*
- > scalar  
    *bool: vpiScalar*
- > size  
    *int: vpiSize*
- > vector  
    *bool: vpiVector*
- > source  
    *bool: vpiSource*
- > equation target  
    *bool: vpiEquationTarget*

## 12.5.8 Nets

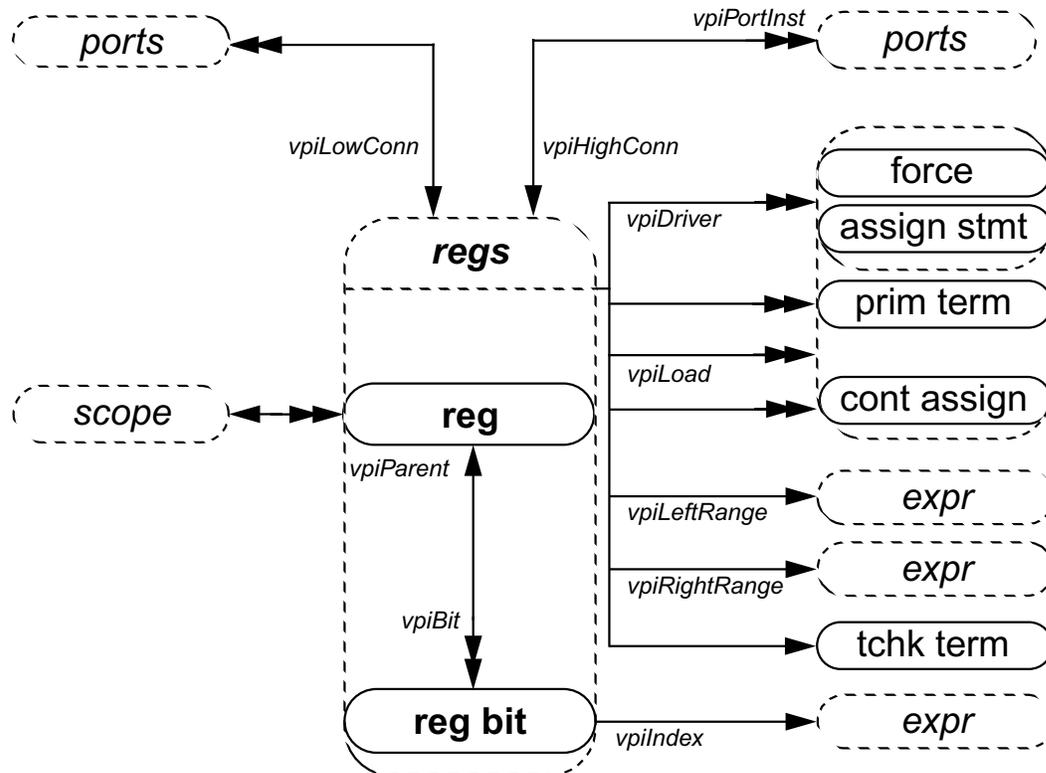


-> delay <i>vpi_get_delays()</i>	-> net decl assign <i>bool: vpiNetDeclAssign</i>	-> strength <i>int: vpiStrength0</i> <i>int: vpiStrength1</i> <i>int: vpiChargeStrength</i>
-> expanded <i>bool: vpiExpanded</i>	-> net type <i>int: vpiNetType</i>	-> value <i>vpi_get_value()</i> <i>vpi_put_value()</i>
-> implicitly declared <i>bool: vpiImplicitDecl</i>	-> scalar <i>bool: vpiScalar</i>	-> vector <i>bool: vpiVector</i>
-> location <i>int: vpiLineNo</i> <i>str: vpiFile</i>	-> scalared declaration <i>bool: vpiExplicitScalared</i>	-> vectored declaration <i>bool: vpiExplicitVectored</i>
-> name <i>str: vpiName</i> <i>str: vpiFullName</i>	-> size <i>int: vpiSize</i>	
	-> domain <i>int vpiDomain</i>	

## NOTES

- 1—For vectors, net bits shall be available regardless of vector expansion.
- 2—Continuous assignments and primitive terminals shall be accessed regardless of hierarchical boundaries.
- 3—Continuous assignments and primitive terminals shall only be accessed from scalar nets or bit selects.
- 4—For **vpiPortInst** and **vpiPort**, if the reference handle is a bit or the entire vector, the relationships shall return a handle to either a port bit or the entire port, respectively.
- 5—For implicit nets, **vpiLineNo** shall return **0**, and **vpiFile** shall return the filename where the implicit net is first referenced.
- 6—Only active forces and assign statements shall be returned for **vpiLoad**.
- 7—Only active forces shall be returned for **vpiDriver**.
- 8—**vpiDriver** shall also return ports which are driven by objects other than nets and net bits.

## 12.5.9 Regs



-> location

int: *vpiLineNo*  
str: *vpiFile*

-> name

str: *vpiName*  
str: *vpiFullName*

-> scalar

bool: *vpiScalar*

-> size

int: *vpiSize*

-> value

*vpi\_get\_value()*  
*vpi\_put\_value()*

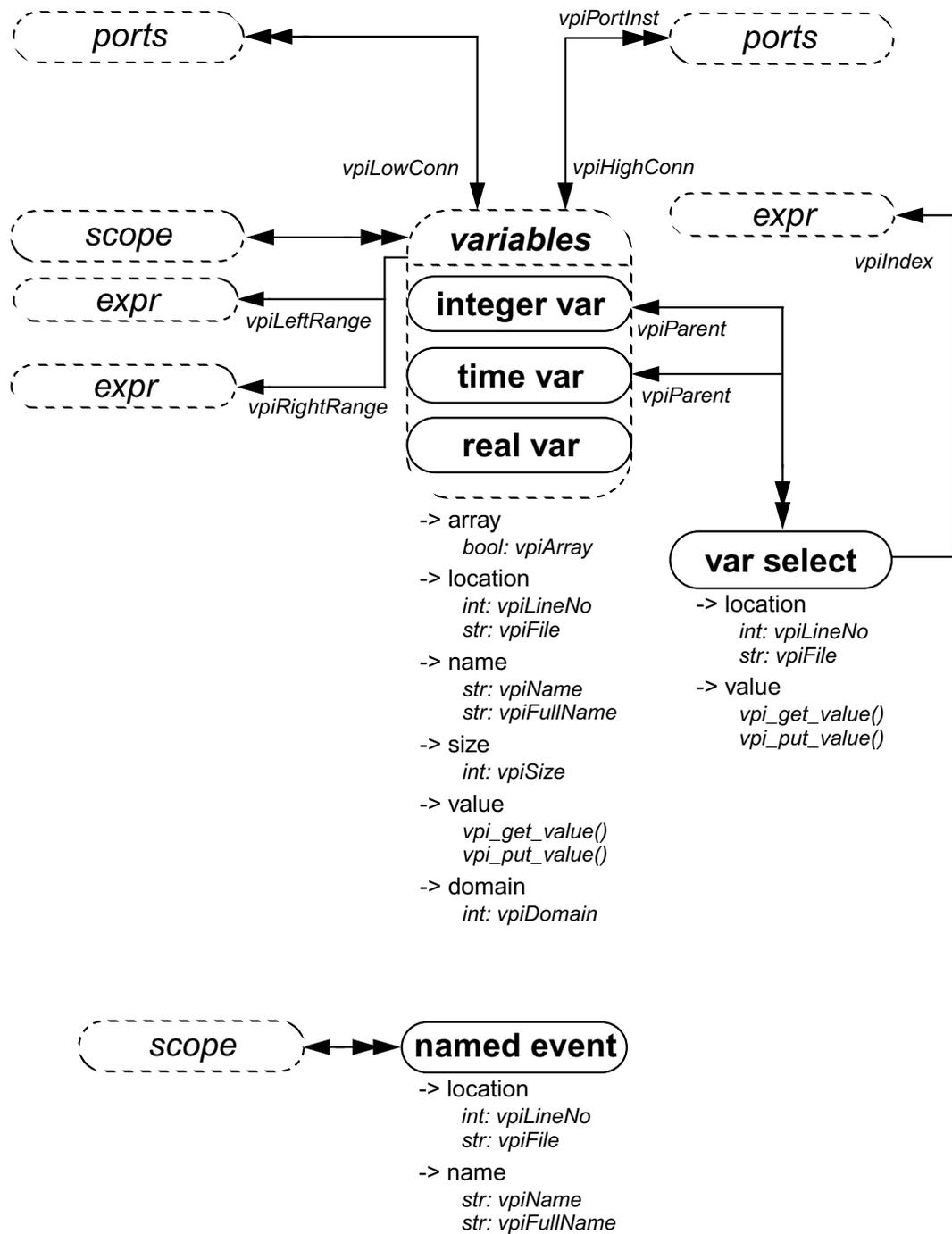
-> vector

bool: *vpiVector*

## NOTES

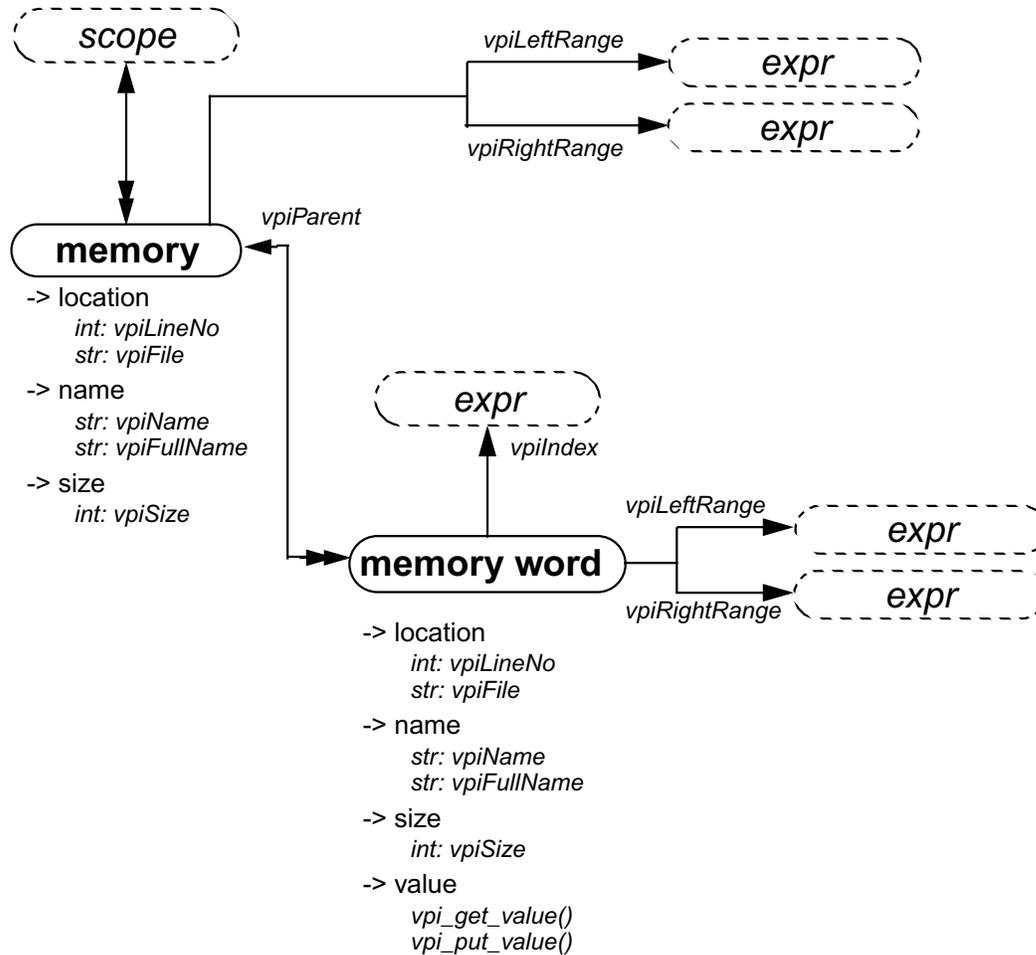
- 1—Continuous assignments and primitive terminals shall be accessed regardless of hierarchical boundaries.
- 2—Continuous assignments and primitive terminals shall only be accessed from scalar regs and bit selects.
- 3—Only active forces and assign statements shall be returned for **vpiLoad** and **vpiDriver**.

### 12.5.10 Variables, named event



NOTE—**vpiLeftRange** and **vpiRightRange** shall be invalid for reals, since there can not be arrays of reals.

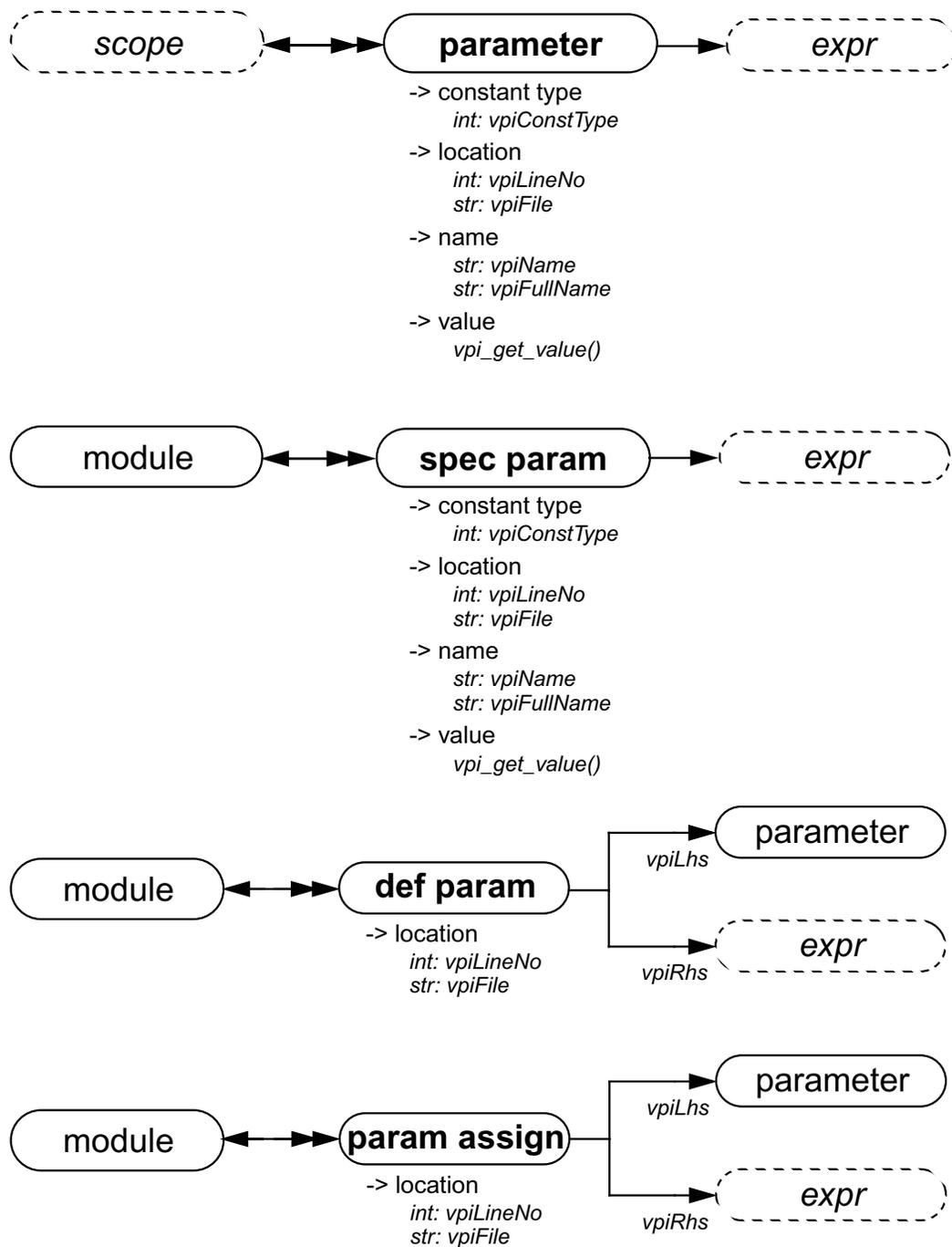
## 12.5.11 Memory



## NOTES

- 1—**vpiSize** for a memory shall return the number of words in the memory.
- 2—**vpiSize** for a memory word shall return the number of bits in the word.

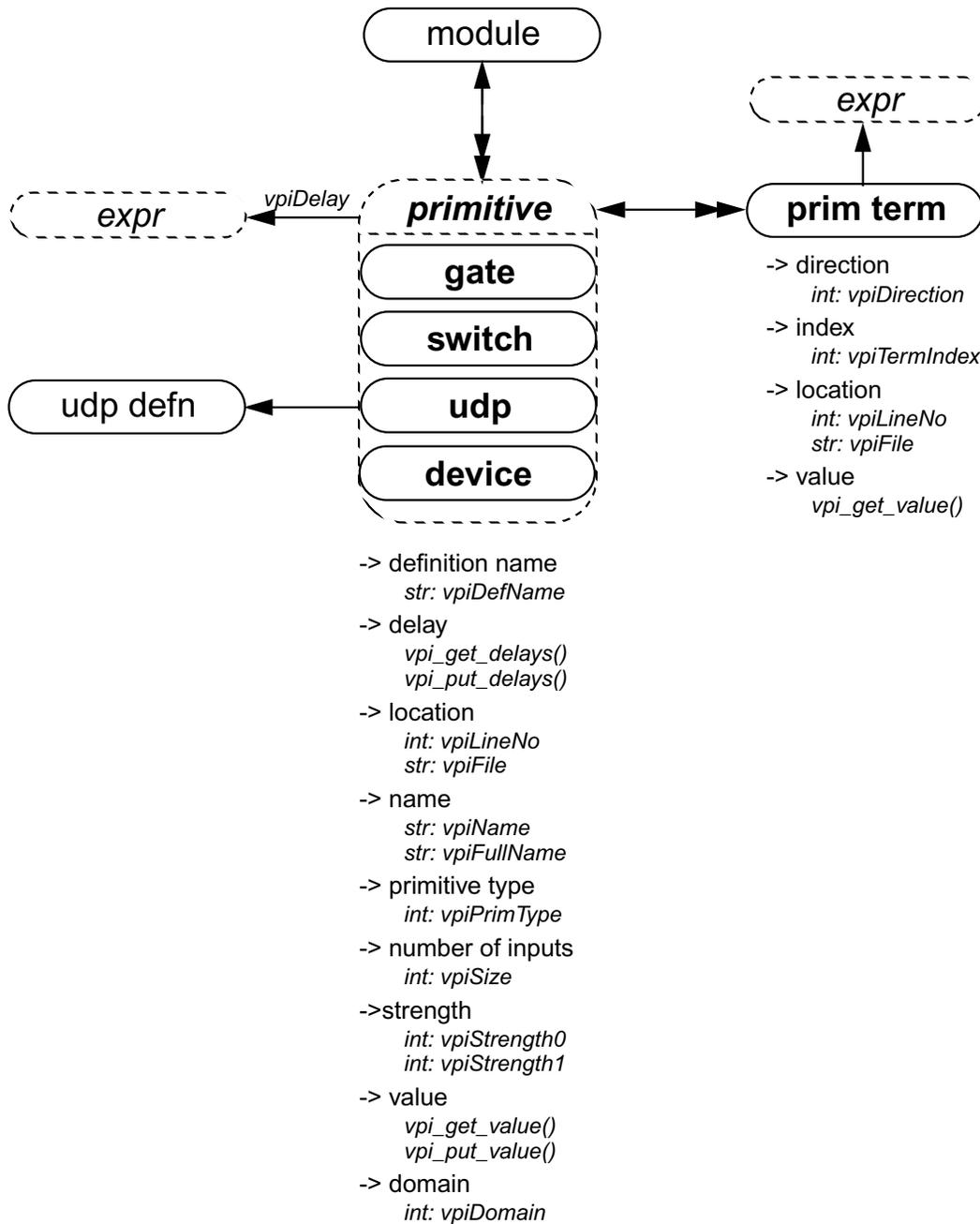
## 12.5.12 Parameter, specparam



## NOTES

- 1—Obtaining the value from the object **parameter** shall return the final value of the parameter after all module instantiation overrides and defparams have been resolved.
- 2—**vpiLhs** from a param assign object shall return a handle to the overridden parameter.

## 12.5.13 Primitive, prim term

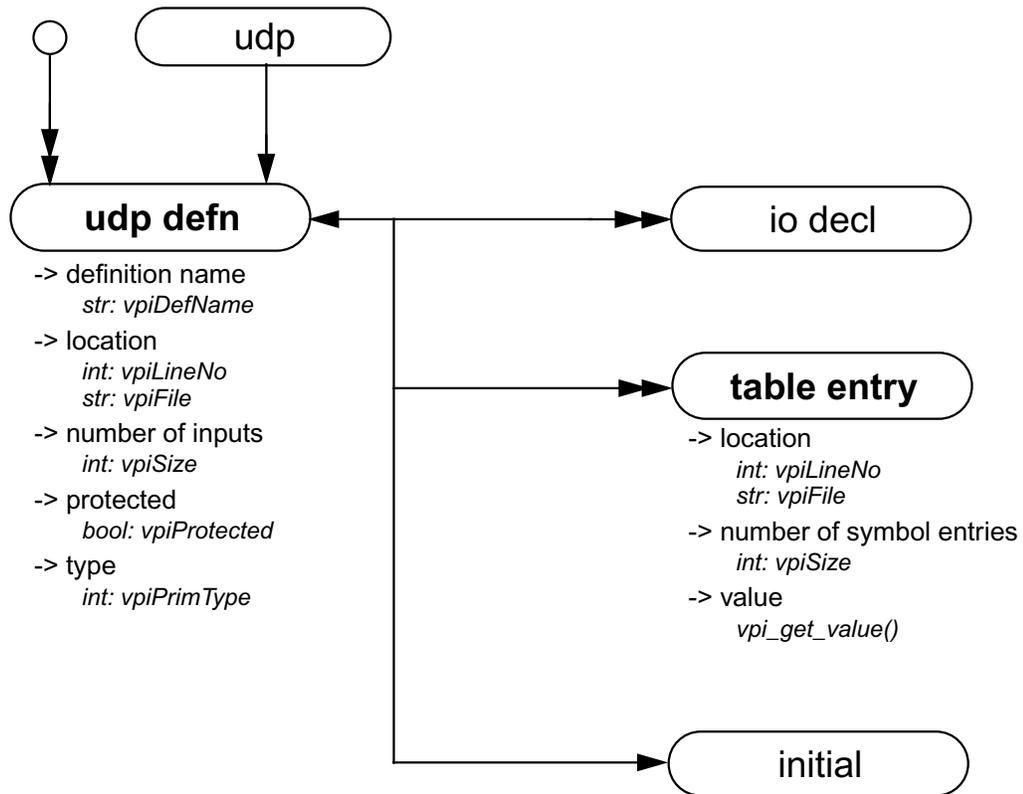


## NOTES

1— **vpiSize** shall return the number of inputs.

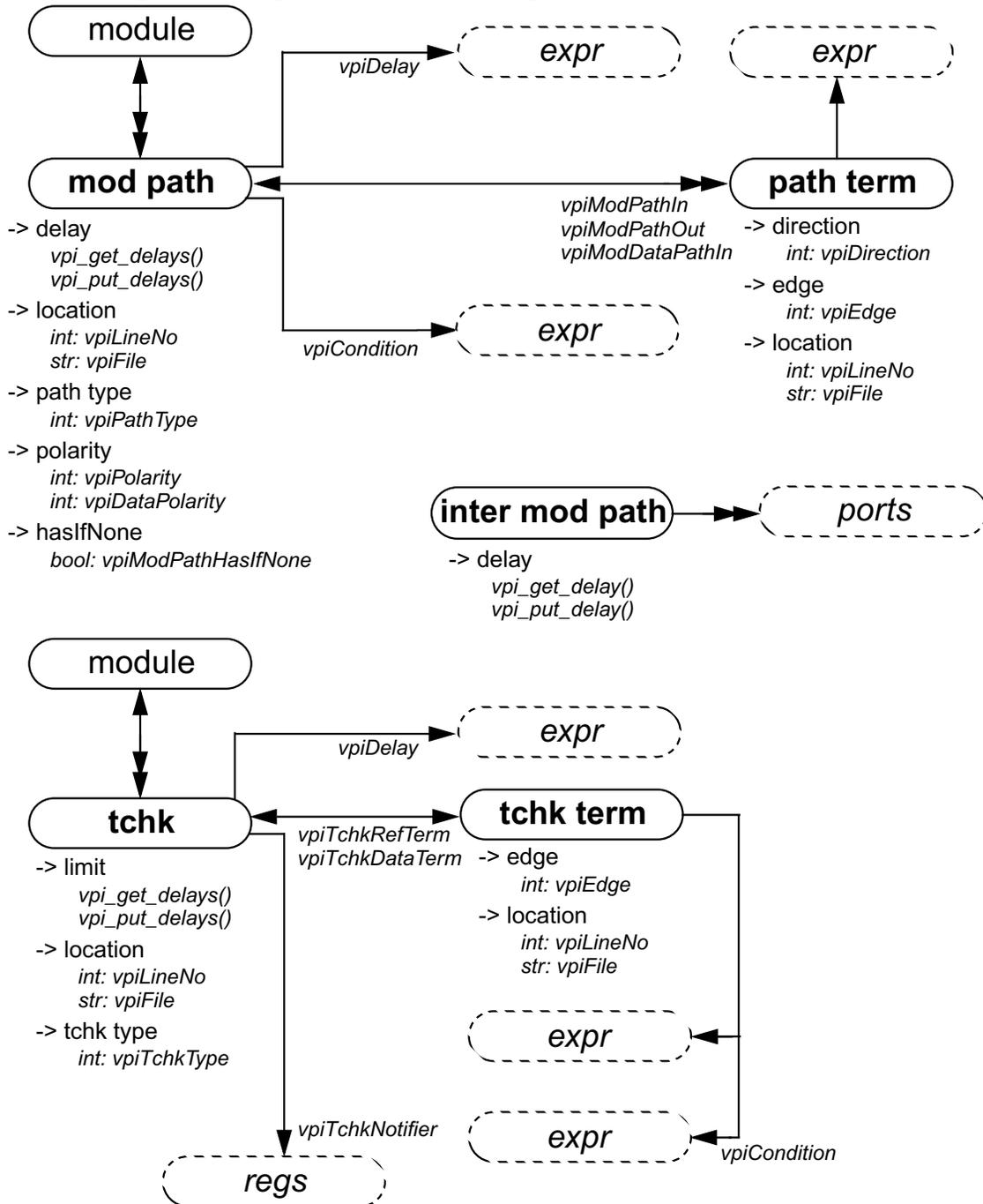
2— For primitives, **vpi\_put\_value()** shall only be used with sequential UDP primitives.

## 12.5.14 UDP



NOTE—Only string (decompilation) and vector (ASCII values) shall be obtained for table entry objects using **vpi\_get\_value()**. Refer to the definition of **vpi\_get\_value()** for additional details.

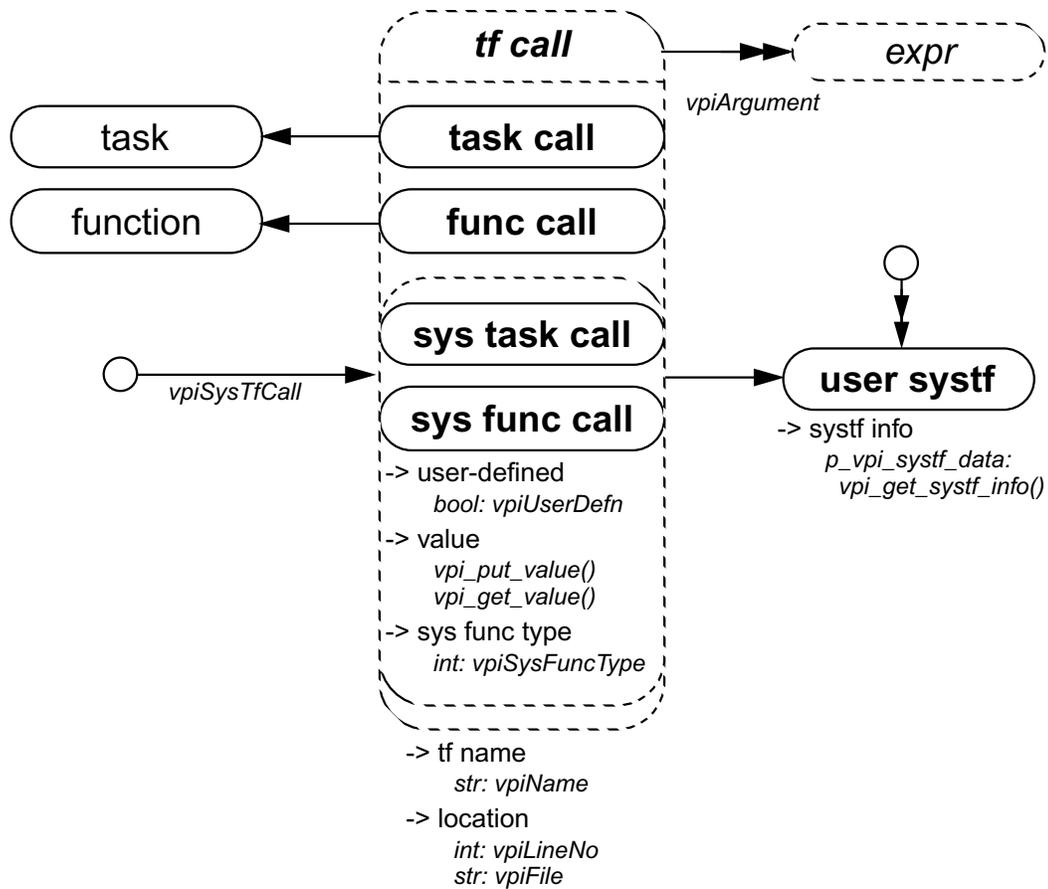
### 12.5.15 Module path, timing check, intermodule path



NOTES

- 1—The `vpiTchkRefTerm` is the first terminal for all tchks except `$setup`, where `vpiTchkDataTerm` is the first terminal and `vpiTchkRefTerm` is the second terminal.
- 2—To get to an intermodule path, `vpi_handle_multi(vpiInterModPath, port1, port2)` can be used.

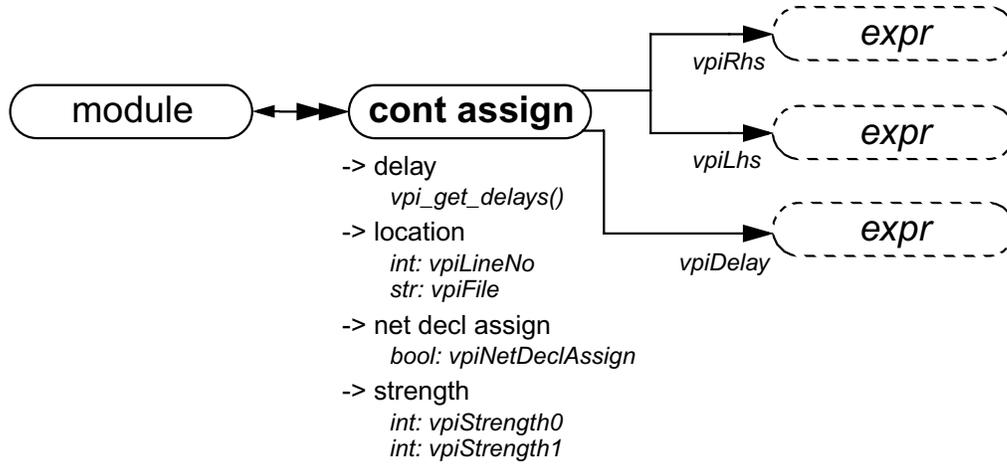
## 12.5.16 Task and function call



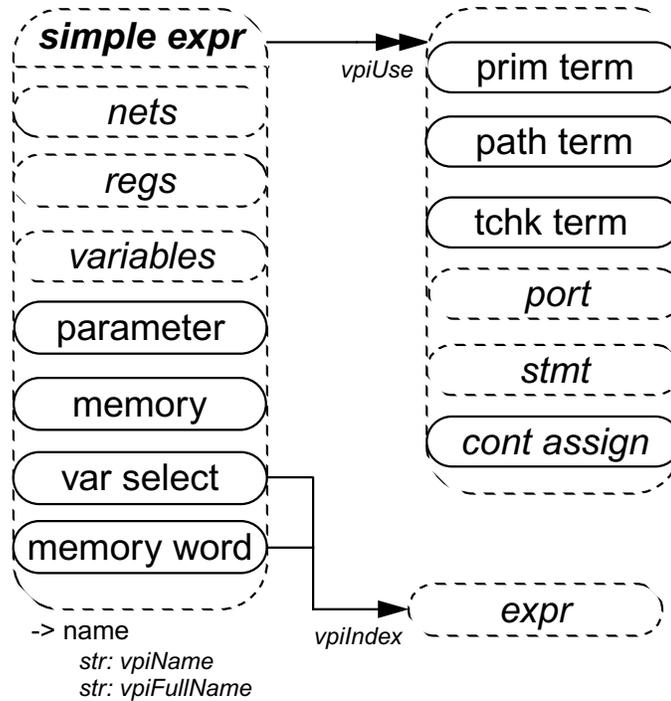
## NOTES

- 1—The system task or function which invoked an application shall be accessed with **vpi\_handle(vpiSysTfCall, NULL)**
- 2—**vpi\_get\_value()** shall return the current value of the system function.
- 3—If the **vpiUserDefn** property of a system task or function call is true, then the properties of the corresponding systf object shall be obtained via **vpi\_get\_systf\_info()**.
- 4—All user-defined system tasks or functions shall be retrieved using **vpi\_iterate()**, with **vpiUserSystf** as the type argument, and a NULL reference argument.

### 12.5.17 Continuous assignment



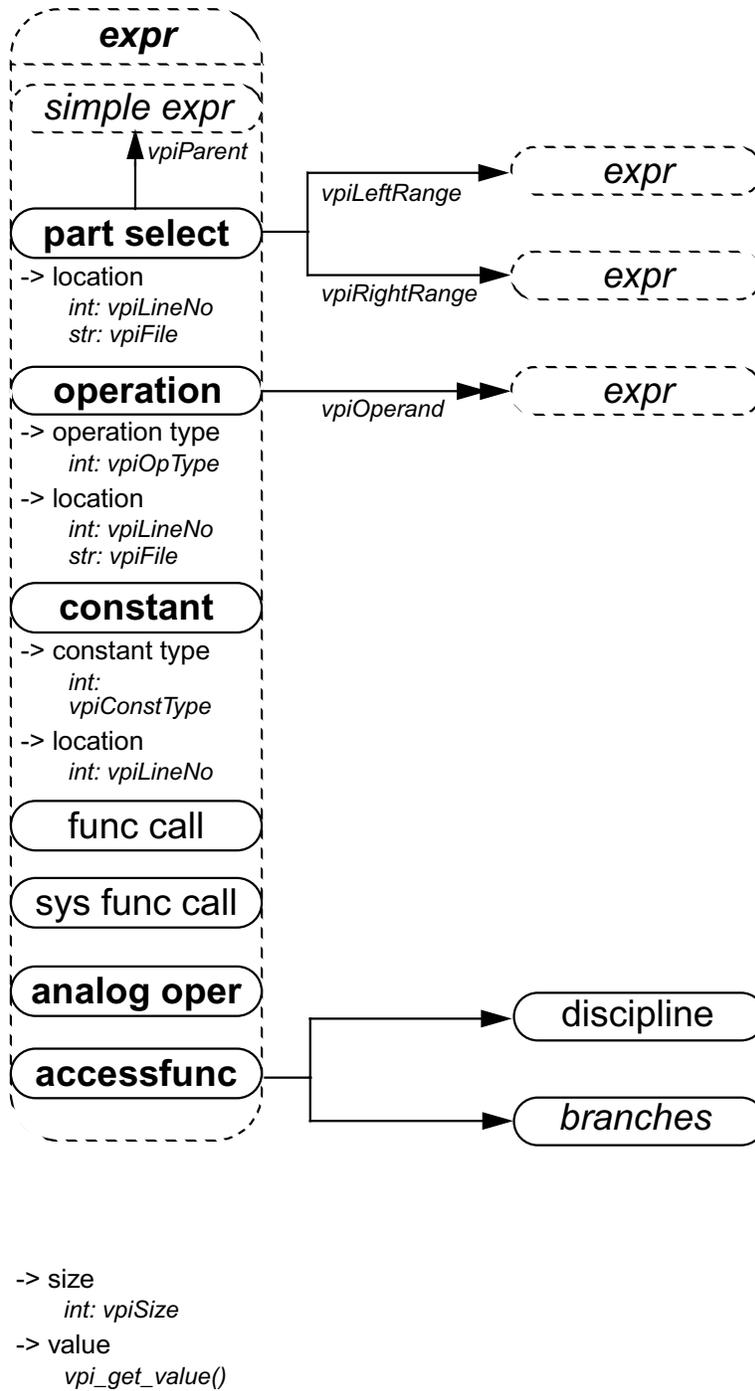
### 12.5.18 Simple expressions



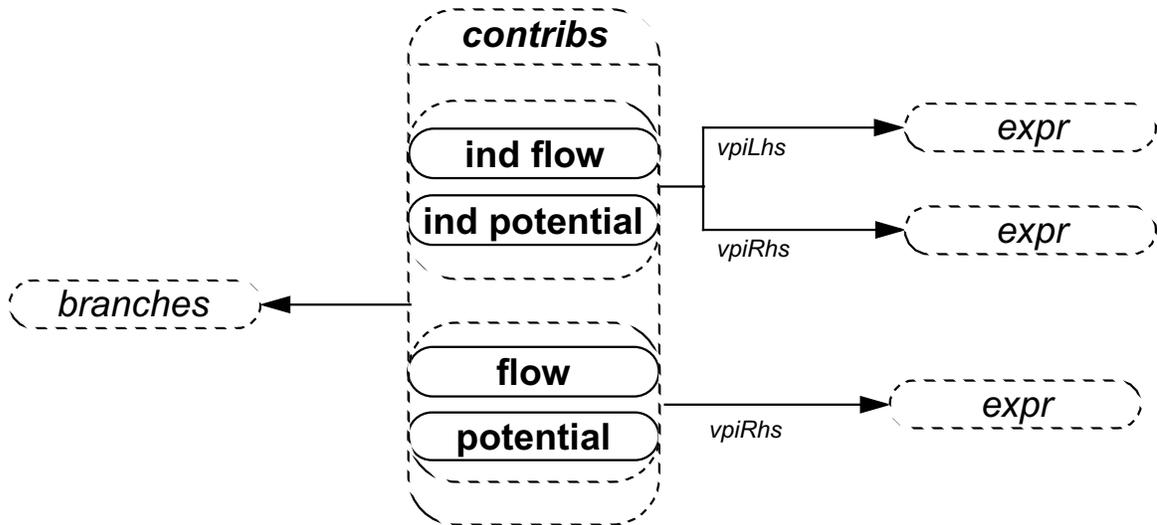
#### NOTES

- 1—For vectors, the **vpiUse** relationship shall access any use of the vector or part-selects or bit-selects thereof.
- 2—For bit-selects, the **vpiUse** relationship shall access any specific use of that bit, any use of the parent vector, and any part-select which contains that bit.

### 12.5.19 Expressions

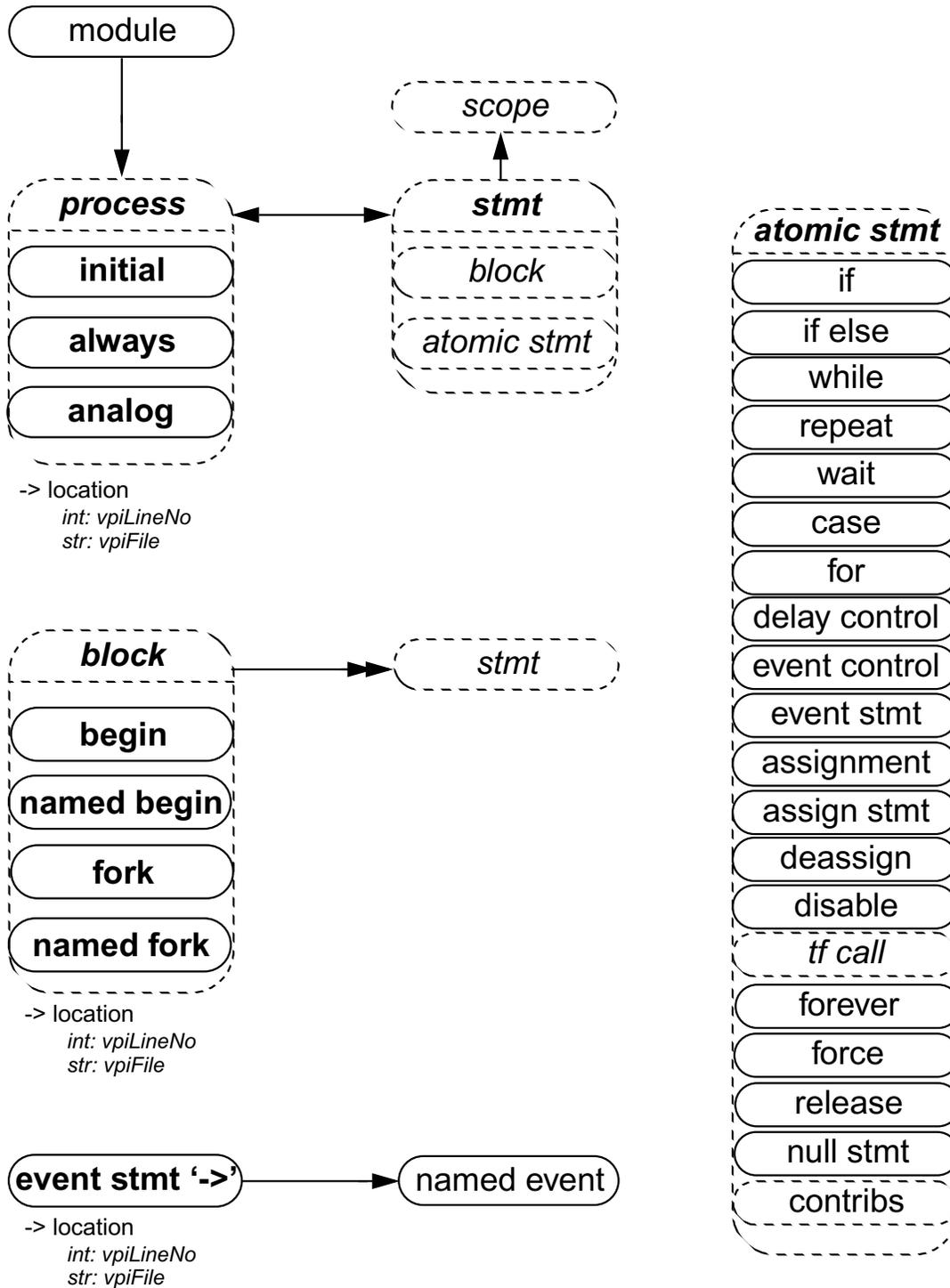


NOTE—For an operator whose type is **vpiMultiConcat**, the first operand shall be the multiplier expression.

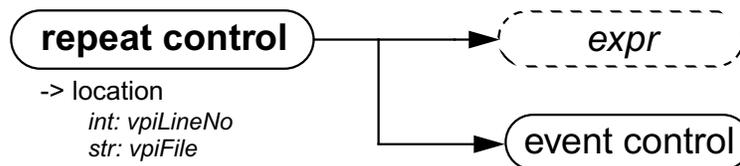
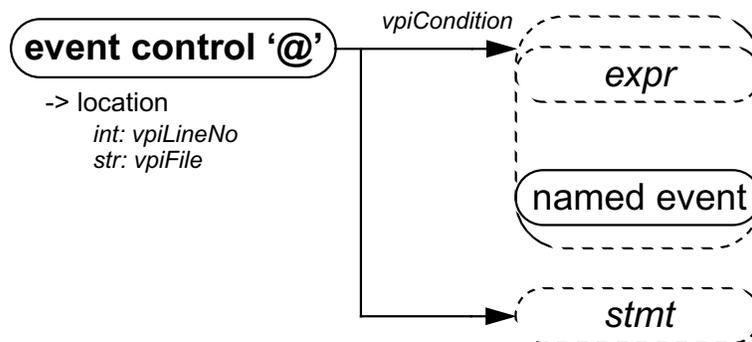
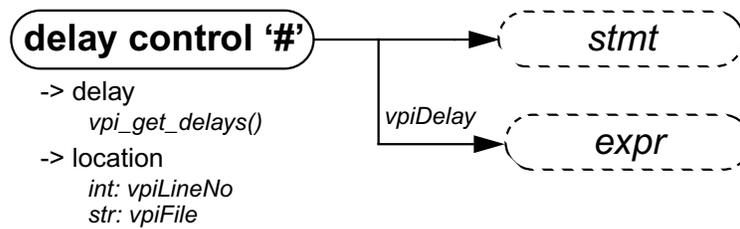
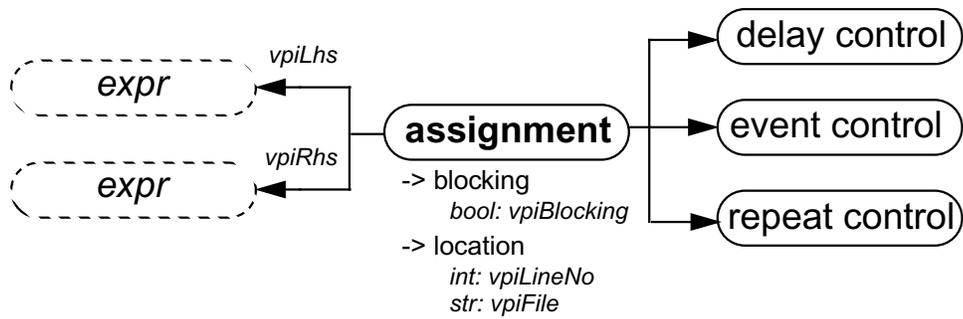
12.5.20 **Contribs**

-> value  
*vpi\_get\_value()*  
 -> direct  
*bool: vpiDirect*  
 -> flow  
*bool: vpiFlow*

12.5.21 Process, block, statement, event statement

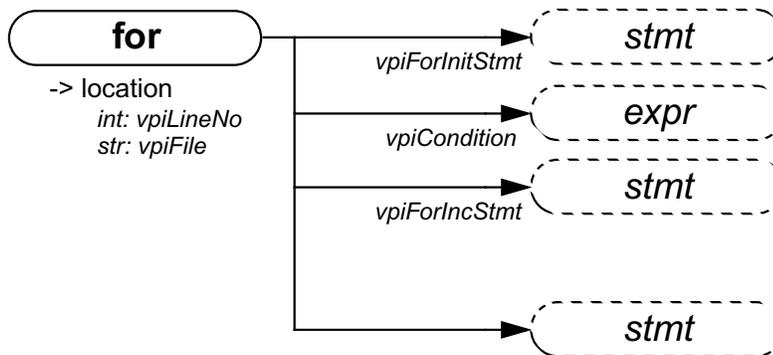
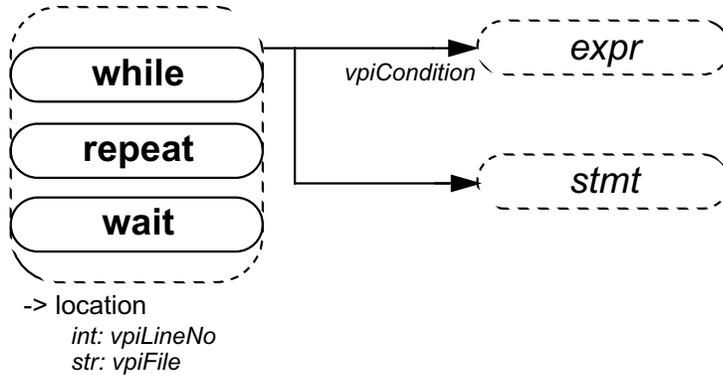


### 12.5.22 Assignment, delay control, event control, repeat control

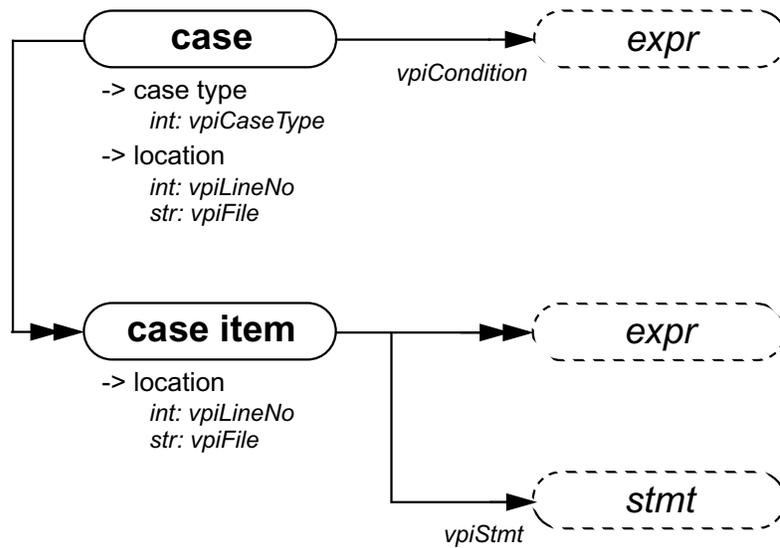
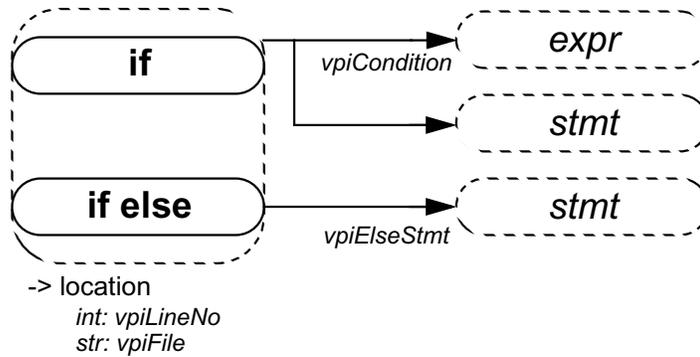


NOTE—For delay control and event control associated with assignment, the statement shall always be NULL.

### 12.5.23 While, repeat, wait, for, forever



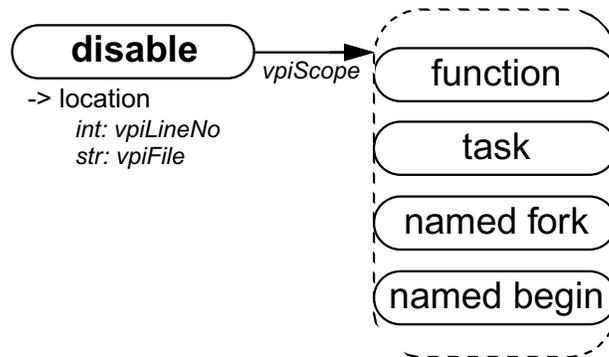
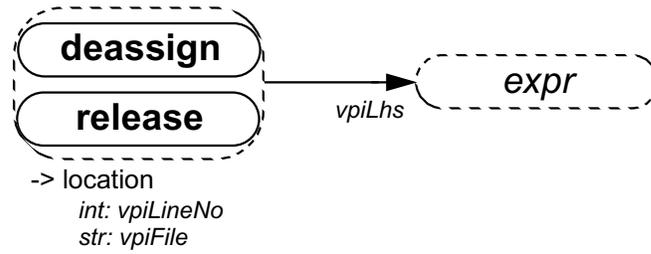
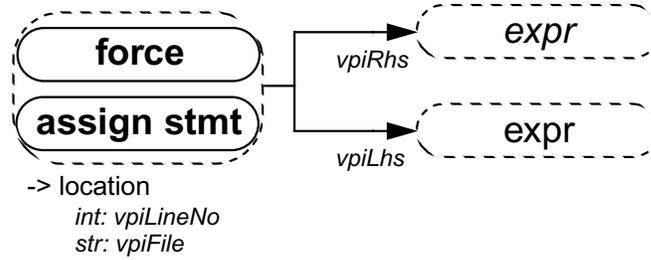
## 12.5.24 If, if-else, case



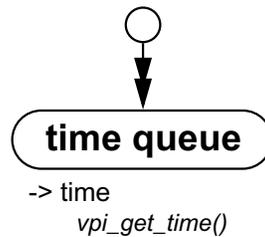
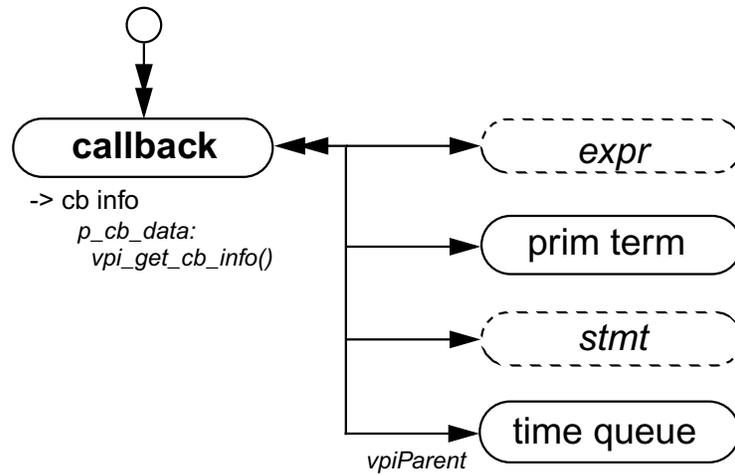
## NOTES

- 1—The *case item* shall group all case conditions which branch to the same statement.
- 2—**vpi\_iterate()** shall return NULL for the default case item since there is no expression with the default case.

### 12.5.25 Assign statement, deassign, force, release, disable



### 12.5.26 Callback, time queue



#### NOTES

- 1—To get information about the callback object, the routine **vpi\_get\_cb\_info()** can be used.
- 2—To get callback objects not related to the above objects, the second argument to **vpi\_iterate()** shall be NULL.
- 3—The time queue objects shall be returned in increasing order of simulation time.
- 4—**vpi\_iterate()** shall return NULL if there is nothing left in the simulation queue.
- 5—If any events after read only sync remain in the current queue, then it shall not be returned as part of the iteration.



## Section 13

# VPI routine definitions

This section describes the Verilog Procedural Interface (VPI) routines, explaining their function, syntax, and usage. The routines are listed in alphabetical order. The following conventions are used in the definitions of the VPI routines.

**Synopsis:** A brief description of the PLI routine functionality, intended to be used as a quick reference when searching for PLI routines to perform specific tasks.

**Syntax:** The exact name of the PLI routine and the order of the arguments passed to the routine.

**Returns:** The definition of the value returned when the PLI routine is called, along with a brief description of what the value represents. The return definition contains the fields

- **Type:** The data type of the C value which is returned. The data type is either a standard ANSI C type or a special type defined within the PLI.
- **Description:** A brief description of what the value represents.

**Arguments:** The definition of the arguments passed with a call to the PLI routine. The argument definition contains the fields

- **Type:** The data type of the C values which are passed as arguments. The data type is either a standard ANSI C type or a special type defined within the PLI.
- **Name:** The name of the argument used in the *Syntax* definition.
- **Description:** A brief description of what the value represents.

All arguments shall be considered mandatory unless specifically noted in the definition of the PLI routine. Two tags are used to indicate arguments that might not be required:

- **Conditional:** Arguments tagged as conditional shall be required only if a previous argument is set to a specific value or if a call to another PLI routine has configured the PLI to require the arguments. The PLI routine definition explains when conditional arguments are required.
- **Optional:** Arguments tagged as optional can have default values within the PLI, but they can be required if a previous argument is set to a specific value, or if a call to another PLI routine has configured the PLI to require the arguments. The PLI routine definition explains the default values and when optional arguments are required.

**Related routines:** A list of PLI routines which are typically used with, or provide similar functionality to, the PLI routine being defined. This list is provided as a convenience to facilitate finding information in this standard. It is not intended to be all-inclusive and it does not imply the related routines have to be used.

## 13.1 vpi\_chk\_error()

vpi_chk_error()			
<b>Synopsis:</b>	Retrieve information about VPI routine errors.		
<b>Syntax:</b>	vpi_chk_error(error_info_p)		
<b>Returns:</b>	<b>Type</b>	<b>Description</b>	
	int	returns the error severity level if the previous VPI routine call resulted in an error and FALSE if no error occurred	
<b>Arguments:</b>	<b>Type</b>	<b>Name</b>	<b>Description</b>
	p_vpi_error_info	error_info_p	Pointer to a structure containing error information

The VPI routine `vpi_chk_error()` shall return an integer constant representing an error severity level if the previous call to a VPI routine resulted in an error. The error constants are shown in Table 13-1. If the previous call to a VPI routine did not result in an error, then `vpi_chk_error()` shall return `FALSE`. The error status shall be reset by any VPI routine call except `vpi_chk_error()`. Calling `vpi_chk_error()` shall have no effect on the error status.

**Table 13-1—Return error constants for vpi\_chk\_error()**

Error constant	Severity level
<code>vpiNotice</code>	lowest severity
<code>vpiWarning</code>	
<code>vpiError</code>	
<code>vpiSystem</code>	
<code>vpiInternal</code>	
	highest severity

If an error occurred, the `s_vpi_error_info` structure shall contain information about the error. If the error information is not needed, a `NULL` can be passed to the routine. The `s_vpi_error_info` structure used by `vpi_chk_error()` is defined in `vpi_user.h` and is listed in Figure 13-1.

```
typedef struct t_vpi_error_info {
    int state; /* vpi[Compile,PLI,Run] */
    int level; /* vpi[Notice, Warning, Error, System, Internal] */
    char *message;
    char *product;
    char *code;
    char *file;
    int line;
} s_vpi_error_info, *p_vpi_error_info;
```

**Figure 13-1 The s\_vpi\_error\_info structure definition**

## 13.2 vpi\_compare\_objects()

<b>vpi_compare_objects()</b>			
<b>Synopsis:</b>	Compare two handles to determine if they reference the same object.		
<b>Syntax:</b>	vpi_compare_objects(obj1, obj2)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	bool	true if the two handles refer to the same object. Otherwise, false	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj1	Handle to an object
	vpiHandle	obj2	Handle to an object

The VPI routine `vpi_compare_objects()` shall return `TRUE` if the two handles refer to the same object. Otherwise, `FALSE` shall be returned. Handle equivalence can not be determined with a C `'=='` comparison.

### 13.3 vpi\_free\_object()

<b>vpi_free_object()</b>			
<b>Synopsis:</b>	Free memory allocated by VPI routines.		
<b>Syntax:</b>	vpi_free_object(obj)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	bool	true on success and false on failure	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle of an object

The VPI routine `vpi_free_object()` shall free memory allocated for objects. It shall generally be used to free memory created for iterator objects. The iterator object shall automatically be freed when `vpi_scan()` returns `NULL` either because it has completed an object traversal or encountered an error condition. If neither of these conditions occur (which can happen if the code breaks out of an iteration loop before it has scanned every object), `vpi_free_object()` needs to be called to free any memory allocated for the iterator. This routine can also optionally be used for implementations which have to allocate memory for objects. The routine shall return `TRUE` on success and `FALSE` on failure.

## 13.4 vpi\_get()

<b>vpi_get()</b>			
<b>Synopsis:</b>	Get the value of an integer or Boolean property of an object.		
<b>Syntax:</b>	vpi_get(prop, obj)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	int	Value of an integer or Boolean property	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	prop	An integer constant representing the property of an object for which to obtain a value
	vpiHandle	obj	Handle to an object
<b>Related routines:</b>	Use vpi_get_str() to get string properties		

The VPI routine `vpi_get()` shall return the value of object properties, for properties of type *int* and *bool* (*bool* shall be defined to *int*). Object properties of type *bool* shall return 1 for TRUE and 0 for FALSE. For object properties of type *int* such as `vpiSize`, any integer shall be returned. For object properties of type *int* which return a defined value, refer to *Annex C* of the *IEEE 1364-2001 Verilog HDL* specification for the value that shall be returned. Note for object property `vpiTimeUnit` or `vpiTimePrecision`, if the object is NULL, then the simulation time unit shall be returned. Should an error occur, `vpi_get()` shall return `vpiUndefined`.

## 13.5 vpi\_get\_cb\_info()

vpi_get_cb_info()			
<b>Synopsis:</b>	Retrieve information about a simulation-related callback.		
<b>Syntax:</b>	vpi_get_cb_info(obj, cb_data_p)		
<b>Returns:</b>	<b>Type</b>	<b>Description</b>	
	void		
<b>Arguments:</b>	<b>Type</b>	<b>Name</b>	<b>Description</b>
	vpiHandle	obj	Handle to a simulation-related callback
	p_cb_data	cb_data_p	Pointer to a structure containing callback information
<b>Related routines:</b>	Use vpi_get_systf_info() to retrieve information about a system task/function callback		

The VPI routine `vpi_get_cb_info()` shall return information about a simulation-related callback in an `s_cb_data` structure. The memory for this structure shall be allocated by the user.

The `s_cb_data` structure used by `vpi_get_cb_info()` is defined in `vpi_user.h` and is listed in Figure 13-2.

```
typedef struct t_cb_data {
    int reason;
    int (*cb_rtn)();
    vpiHandle obj;
    p_vpi_time time; /* structure with simulation time info */
    p_vpi_value value; /* structure with simulation value info */
    char *user_data; /* user data to be passed to callback function */
} s_cb_data, *p_cb_data;
```

**Figure 13-2 The s\_cb\_data structure definition**

## 13.6 vpi\_get\_analog\_delta()

<b>vpi_get_analog_delta()</b>		
<b>Synopsis:</b>	Get the time elapsed since the previous solution.	
<b>Syntax:</b>	vpi_get_analog_delta()	
	<b>Type</b>	<b>true on success and false on failureDescription</b>
<b>Returns:</b>	double	time elapsed between the solution being calculated and the last converged solution
	<b>Type</b>	<b>Name</b>
<b>Arguments:</b>	NONE	this function accepts no arguments

The VPI routine `vpi_get_analog_delta()` shall be used determine the size of the analog time step being attempted. It returns the elapsed time between the latest converged and accepted solution and the solution being calculated. The function shall return zero (0) during DC or the time zero transient solution.

## 13.7 vpi\_get\_analog\_freq()

<b>vpi_get_analog_freq()</b>		
<b>Synopsis:</b>	Get the frequency for the current small-signal analysis.	
<b>Syntax:</b>	vpi_get_analog_freq()	
	<b>Type</b>	<b>true on success and false on failure</b>
<b>Returns:</b>	double	time elapsed between the solution being calculated and the last converged solution
	<b>Type</b>	<b>Name</b>
<b>Arguments:</b>	NONE	this function accepts no arguments

The VPI routine `vpi_get_analog_freq()` shall be used determine the current frequency used in the small-signal analysis. The function shall return zero (0) during DC or transient analysis.

## 13.8 vpi\_get\_analog\_time()

vpi_get_analog_time()		
<b>Synopsis:</b>	Get the time of the current solution.	
<b>Syntax:</b>	vpi_get_analog_time()	
	<b>Type</b>	<b>true on success and false on failure</b>
<b>Returns:</b>	double	time associated with the current solution
	<b>Type</b>	<b>Name</b>
<b>Arguments:</b>	NONE	this function accepts no arguments

The VPI routine `vpi_get_analog_time()` shall be used determine the time of the solution attempted or of the latest converged and accepted solution otherwise. The function shall return zero (0) during DC or the time zero transient solution.

## 13.9 vpi\_get\_analog\_value()

vpi_get_analog_value()			
<b>Synopsis:</b>	Retrieve the simulation value of an analog quantity object.		
<b>Syntax:</b>	vpi_get_analog_value(obj, value_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	void		
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to an analog quantity object
	p_vpi_value	value_p	Pointer to a structure containing value information
<b>Related routines:</b>	Use vpi_get_value() to get simulation values of digital objects. Use vpi_put_value() to set the value of an object		

The VPI routine `vpi_get_analog_value()` shall retrieve the simulation value of VPI analog `vpiFlow` or `vpiPotential` (node or branch) quantity objects. The value shall be placed in an `s_vpi_analog_value` structure, which has been allocated by the user. The format of the value shall be set by the `format` field of the structure.

The buffer this routine uses for string values shall be different from the buffer which `vpi_get_str()` shall use. The string buffer used by `vpi_get_analog_value()` is overwritten with each call. If the value is needed, it needs to be saved by the application.

The `s_vpi_analog_value` structure used by `vpi_get_analog_value()` is defined in `vpi_user.h` and listed in Figure 13-3.

```
typedef struct t_vpi_analog_value {
    int format; /* vpiRealVal, vpiExpStrVal, vpiDecStrVal, vpiStringVal
*/
    union {
        char *str;
        double real;
        char *misc;
    } real;
    union {
        char *str;
        double real;
        char *misc;
    } imaginary;
} s_vpi_analog_value, *p_vpi_analog_value;
```

**Figure 13-3 The `s_vpi_analog_value` structure definition**

The memory for the union members `str` and `misc` of the value for real and imaginary unions in the `s_vpi_analog_value` structure shall be provided by the routine

`vpi_get_analog_value()`. This memory shall only be valid until the next call to `vpi_get_analog_value()`.

**Table 13-2—Return value field of the `s_vpi_analog_value` structure union**

Format	Union members	Return description
<b>vpiDecStrVal</b>	str	Real and imaginary values of object are returned as strings of decimal char(s) [0–9]
<b>vpExpStrVal</b>	str	Real and imaginary values of object are returned as strings formatted like <code>printf %e</code> .
<b>vpiRealVal</b>	real	Real and imaginary values of the object are returned as doubles.
<b>vpiStringVal</b>	str	Real and imaginary parts are returned as strings formatted like <code>printf %g</code> . The call shall reset the format field to <b>vpiExpStrVal</b> or <b>vpiDecStrVal</b> to the selected format.

**Note:** The user shall provide the memory for these members when calling `vpi_put_value()`.

## 13.10 vpi\_get\_delays()

vpi_get_delays()			
<b>Synopsis:</b>	Retrieve the delays or pulse limits of an object.		
<b>Syntax:</b>	vpi_get_delays(obj, delay_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	void		
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to an object
	p_vpi_delay	delay_p	Pointer to a structure containing delay information
<b>Related routines:</b>	Use vpi_put_delays() to set the delays or timing limits of an object		

The VPI routine `vpi_get_delays()` shall retrieve the delays or pulse limits of an object and place them in an `s_vpi_delay` structure which has been allocated by the user. The format of the delay information shall be controlled by the `time_type` flag in the `s_vpi_delay` structure. This routine shall ignore the value of the `type` flag in the `s_vpi_time` structure.

The `s_vpi_delay` and `s_vpi_time` structures used by both `vpi_get_delays()` and `vpi_put_delays()` are defined in `vpi_user.h` and are listed in Figures 13-4 and 13-5.

```
typedef struct t_vpi_delay {
    struct t_vpi_time *da; /* ptr to user allocated array of delay
                           values */
    int no_of_delays; /* number of delays */
    int time_type; /* [vpiScaledRealTime, vpiSimTime] */
    bool mtm_flag; /* true for mtm */
    bool append_flag; /* true for append, false for replace */
    bool pulserere_flag; /* true for pulserere values */
} s_vpi_delay, *p_vpi_delay;
```

Figure 13-4 The `s_vpi_delay` structure definition

```
typedef struct t_vpi_time
{
    int type; /* [vpiScaledRealTime, vpiSimTime] */
    unsigned int high, low; /* for vpiSimTime */
    double real; /* for vpiScaledRealTime */
} s_vpi_time, *p_vpi_time;
```

Figure 13-5 The `s_vpi_time` structure definition

The *da* field of the `s_vpi_delay` structure shall be a user-allocated array of `s_vpi_time` structures. This array shall store delay values returned by `vpi_get_delays()`. The number of elements in this array shall be determined by

- The number of delays to be retrieved
- The `mtm_flag` setting
- The `pulsere_flag` setting

The number of delays to be retrieved shall be set in the `no_of_delays` field of the `s_vpi_delay` structure. Legal values for the number of delays shall be determined by the type of object.

- For primitive objects, the `no_of_delays` value shall be 2 or 3.
- For path delay objects, the `no_of_delays` value shall be 1, 2, 3, 6, or 12.
- For timing check objects, the `no_of_delays` value shall match the number of limits existing in the timing check.
- For inter-module path objects, the `no_of_delays` value shall be 2 or 3.

The user-allocated `s_vpi_delay` array shall contain delays in the same order in which they occur in the Verilog-AMS HDL description. The number of elements for each delay shall be determined by the flags `mtm_flag` and `pulsere_flag`, as shown in Table 13-3.

**Table 13-3—Size of the `s_vpi_delay->da` array**

Flag values	Number of <code>s_vpi_time</code> array elements required for <code>s_vpi_delay-&gt;da</code>	Order in which delay elements shall be filled
<code>mtm_flag = false</code> <code>pulsere_flag = false</code>	<i>no_of_delays</i>	1st delay: <code>da[0]</code> -> 1st delay 2nd delay: <code>da[1]</code> -> 2nd delay ...
<code>mtm_flag = true</code> <code>pulsere_flag = false</code>	$3 * no\_of\_delays$	1st delay: <code>da[0]</code> -> min delay <code>da[1]</code> -> typ delay <code>da[2]</code> -> max delay 2nd delay: ...
<code>mtm_flag = false</code> <code>pulsere_flag = true</code>	$3 * no\_of\_delays$	1st delay: <code>da[0]</code> -> delay <code>da[1]</code> -> reject limit <code>da[2]</code> -> error limit 2nd delay element: ...
<code>mtm_flag = true</code> <code>pulsere_flag = true</code>	$9 * no\_of\_delays$	1st delay: <code>da[0]</code> -> min delay <code>da[1]</code> -> typ delay <code>da[2]</code> -> max delay <code>da[3]</code> -> min reject <code>da[4]</code> -> typ reject <code>da[5]</code> -> max reject <code>da[6]</code> -> min error <code>da[7]</code> -> typ error <code>da[8]</code> -> max error 2nd delay: ...

The delay structure has to be allocated before passing a pointer to `vpi_get_delays()`.

*Examples:*

In the following example, a static structure, `prim_da`, is allocated for use by each call to the `vpi_get_delays()` function.

```
display_prim_delays(prim)
vpiHandle prim;t2
{
    static s_vpi_time prim_da[3];
    static s_vpi_delay delay_s = {NULL, 3, vpiScaledRealTime};
    static p_vpi_delay delay_p = &delay_s;

    delay_s.da = &prim_da;
    vpi_get_delays(prim, delay_p);
    vpi_printf("Delays for primitive %s: %6.2f %6.2f %6.2f\n",
        vpi_get_str(vpiFullName, prim)
        delay_p->da[0].real, delay_p->da[1].real,
        delay_p->da[2].real);
}
```

## 13.11 vpi\_get\_str()

<b>vpi_get_str()</b>			
<b>Synopsis:</b>	Get the value of a string property of an object.		
<b>Syntax:</b>	vpi_get_str(prop, obj)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	char *	Pointer to a character string containing the property value	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	prop	An integer constant representing the property of an object for which to obtain a value
	vpiHandle	obj	Handle to an object
<b>Related routines:</b>	Use vpi_get() to get integer and Boolean properties		

The VPI routine `vpi_get_str()` shall return string property values. The string shall be placed in a temporary buffer which shall be used by every call to this routine. If the string is to be used after a subsequent call, the string needs to be copied to another location. A different string buffer shall be used for string values returned through the `s_vpi_value` structure.

*Examples:*

The following example illustrates the usage of `vpi_get_str()`.

```
char *str;
vpiHandle mod = vpi_handle_by_name("top.mod1", NULL);
vpi_printf ("Module top.mod1 is an instance of %s\n",
           vpi_get_str(vpiDefName, mod));
```

## 13.12 vpi\_get\_analog\_systf\_info()

vpi_get_analog_systf_info()			
<b>Synopsis:</b>	Retrieve information about a user-defined analog system task/function-related callback.		
<b>Syntax:</b>	vpi_get_analog_systf_info(obj, systf_data_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	void		
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to a system task/function-related callback
	p_vpi_analog_systf_data	systf_data_p	Pointer to a structure containing callback information
<b>Related routines:</b>	Use vpi_get_cb_info() to retrieve information about a simulation-related callback		

The VPI routine `vpi_get_analog_systf_info()` shall return information about a user-defined analog system task or function callback in an `s_vpi_analog_systf_data` structure. The memory for this structure shall be allocated by the user.

The `s_vpi_systf_data` structure used by `vpi_get_analog_systf_info()` is defined in `vpi_user.h` and is listed in Figure 13-6.

```
typedef struct t_vpi_analog_systf_data {
    int type;          /* vpiSys[Task,Function] */
    int sysfunctype;  /* vpi[IntFunc,RealFunc,TimeFunc,SizedFunc] */
    char *tfname;     /* first character shall be "$" */
    int (*calltf)();
    int (*completf)();
    int (*sizedtf)(); /* for vpiSizedFunc system functions only */
    p_vpi_stf_partials (*derivtf)(); /* for partial derivatives */
    char *user_data;
} s_vpi_analog_systf_data, *p_vpi_analog_systf_data;
```

**Figure 13-6** The `s_vpi_systf_data` structure definition

## 13.13 vpi\_get\_systf\_info()

vpi_get_systf_info()			
<b>Synopsis:</b>	Retrieve information about a user-defined system task/function-related callback.		
<b>Syntax:</b>	vpi_get_systf_info(obj, systf_data_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	void		
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to a system task/function-related callback
	p_vpi_systf_data	systf_data_p	Pointer to a structure containing callback information
<b>Related routines:</b>	Use vpi_get_cb_info() to retrieve information about a simulation-related callback		

The VPI routine `vpi_get_systf_info()` shall return information about a user-defined system task or function callback in an `s_vpi_systf_data` structure. The memory for this structure shall be allocated by the user.

The `s_vpi_systf_data` structure used by `vpi_get_systf_info()` is defined in `vpi_user.h` and is listed in Figure 13-7.

```
typedef struct t_vpi_systf_data {
    int type;          /* vpiSys[Task,Function] */
    int sysfunctype;  /* vpi[IntFunc,RealFunc,TimeFunc,SizedFunc] */
    char *tfname;     /* first character shall be "$" */
    int (*calltf)();
    int (*completf)();
    int (*sizedtf)(); /* for vpiSizedFunc system functions only */
    char *user_data;
} s_vpi_systf_data, *p_vpi_systf_data;
```

**Figure 13-7 The `s_vpi_systf_data` structure definition**

## 13.14 vpi\_get\_time()

vpi_get_time()			
<b>Synopsis:</b>	Retrieve the current simulation.		
<b>Syntax:</b>	vpi_get_time(obj, time_p)		
<b>Returns:</b>	<b>Type</b>	<b>Description</b>	
	void		
<b>Arguments:</b>	<b>Type</b>	<b>Name</b>	<b>Description</b>
	vpiHandle	obj	Handle to an object
	p_vpi_time	time_p	Pointer to a structure containing time information
<b>Related routines:</b>			

The VPI routine `vpi_get_time()` shall retrieve the current simulation time, using the time scale of the object. If `obj` is `NULL`, the simulation time is retrieved using the simulation time unit. The `time_p->type` field shall be set to indicate if scaled real, analog, or simulation time is desired. The memory for the `time_p` structure shall be allocated by the user.

The `s_vpi_time` structure used by `vpi_get_time()` is defined in `vpi_user.h` and is listed in Figure 13-8 (this is the same time structure as used by `vpi_put_value()`).

```
typedef struct t_vpi_time {
    int type;          /* for vpiScaledRealTime, vpiSimTime,
vpiAnalogTime */
    unsigned int high, low; /* for vpiSimTime */
    double real;      /* for vpiScaledRealTime */
} s_vpi_time, *p_vpi_time;
```

**Figure 13-8 The s\_vpi\_time structure definition**

## 13.15 vpi\_get\_value()

<b>vpi_get_value()</b>			
<b>Synopsis:</b>	Retrieve the simulation value of an object.		
<b>Syntax:</b>	vpi_get_value(obj, value_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	void		
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to an expression
	p_vpi_value	value_p	Pointer to a structure containing value information
<b>Related routines:</b>	Use vpi_get_analog_value() for simulation value of quantity objects. Use vpi_put_value() to set the value of an object		

The VPI routine **vpi\_get\_value()** shall retrieve the simulation value of VPI objects (use **vpi\_get\_analog\_value()** for the simulation value of VPI analog quantity objects). The value shall be placed in an `s_vpi_value` structure, which has been allocated by the user. The format of the value shall be set by the *format* field of the structure.

When the *format* field is **vpiObjTypeVal**, the routine shall fill in the value and change the *format* field based on the object type, as follows:

- For an integer, **vpiIntVal**
- For a real, **vpiRealVal**
- For a scalar, either **vpiScalar** or **vpiStrength**
- For a time variable, **vpiTimeVal** with **vpiSimTime**
- For a vector, **vpiVectorVal**

The buffer this routine uses for string values shall be different from the buffer which **vpi\_get\_str()** shall use. The string buffer used by `vpi_get_value()` is overwritten with each call. If the value is needed, it needs to be saved by the application.

The `s_vpi_value`, `s_vpi_vecval` and `s_vpi_strengthval` structures used by `vpi_get_value()` are defined in `vpi_user.h` and are listed in Figures 13-9, 13-10, and 13-11.

```
typedef struct t_vpi_value {
    int format; /* vpi[[Bin,Oct,Dec,Hex]Str,Scalar,Int,Real,String,
                Time,Vector,Strength,ObjType]Val*/
    union {
        char *str;
        int scalar; /* vpi[0,1,X,Z] */
        int integer;
        double real;
        struct t_vpi_time *time;
        struct t_vpi_vecval *vector;
        struct t_vpi_strengthval *strength;
        char *misc;
    } value;
} s_vpi_value, *p_vpi_value;
```

**Figure 13-9 The `s_vpi_value` structure definition**

```
typedef struct t_vpi_vecval {
    int aval, bval; /* bit encoding: ab: 00=0, 10=1, 11=X, 01=Z */
} s_vpi_vecval, *p_vpi_vecval;
```

**Figure 13-10 The `s_vpi_vecval` structure definition**

```
typedef struct t_vpi_strengthval {
    int logic; /* vpi[0,1,X,Z] */
    int s0, s1; /* refer to strength coding in the LRM */
} s_vpi_strengthval, *p_vpi_strengthval;
```

**Figure 13-11 The `s_vpi_strengthval` structure definition**

For vectors, the `p_vpi_vecval` field shall point to an array of `s_vpi_vecval` structures. The size of this array shall be determined by the size of the vector, where  $array\_size = ((vector\_size-1)/32 + 1)$ . The lsb of the vector shall be represented by the lsb of the 0-indexed element of `s_vpi_vecval` array. The 33<sup>rd</sup> bit of the vector shall be represented by the lsb of the 1-indexed element of the array, and so on. The memory for the union members `str`, `time`, `vector`, `strength`, and `misc` of the value union in the `s_vpi_value` structure shall be provided by the routine `vpi_get_value()`. This memory shall only be valid until the next call to `vpi_get_value()`. (The user shall provide the memory for these members when calling `vpi_put_value()`). When a value change callback occurs for a value

type of **vpiVectorVal**, the system shall create the associated memory (an array of `s_vpi_vecval` structures) and free the memory upon the return of the callback.

**Table 13-4—Return value field of the `s_vpi_value` structure union**

Format	Union member	Return description
<b>vpiBinStrVal</b>	str	String of binary char(s) [1, 0, x, z]
<b>vpiOctStrVal</b>	str	String of octal char(s) [0–7, x, X, z, Z] <b>x</b> When all the bits are <b>x</b> <b>X</b> When some of the bits are <b>x</b> <b>z</b> When all the bits are <b>z</b> <b>Z</b> When some of the bits are <b>z</b>
<b>vpiDecStrVal</b>	str	String of decimal char(s) [0–9]
<b>vpiHexStrVal</b>	str	String of hex char(s) [0–f, x, X, z, Z] <b>x</b> When all the bits are <b>x</b> <b>X</b> When some of the bits are <b>x</b> <b>z</b> When all the bits are <b>z</b> <b>Z</b> When some of the bits are <b>z</b>
<b>vpiScalarVal</b>	scalar	vpi1, vpi0, vpiX, vpiZ, vpiH, vpiL
<b>vpiIntVal</b>	integer	Integer value of the handle. Any bits x or z in the value of the object are mapped to a 0
<b>vpiRealVal</b>	real	Value of the handle as a double
<b>vpiStringVal</b>	str	A string where each 8-bit group of the value of the object is assumed to represent an ASCII character
<b>vpiTimeVal</b>	time	Integer value of the handle using two integers
<b>vpiVectorVal</b>	vector	<i>aval/bval</i> representation of the value of the object
<b>vpiStrengthVal</b>	strength	Value plus strength information of a scalar object only
<b>vpiObjectVal</b>	—	Return a value in the closest format of the object

NOTE—If the object has a real value, it shall be converted to an integer using the rounding defined by the Verilog-AMS HDL before being returned in a format other than **vpiRealVal**.

To get the ASCII values of UDP table entries (as explained in *Section 8.1.6, Table 8-1* of the *IEEE 1364-2001 Verilog HDL* specification), the `p_vpi_vecval` field shall point to an array of `s_vpi_vecval` structures. The size of this array shall be determined by the size of the table entry (no. of symbols per table entry), where  $array\_size = ((table\_entry\_size - 1) / 4 + 1)$ . Each symbol shall require a byte; the ordering of the symbols within `s_vpi_vecval` shall be the most significant byte of *abit* first, then the least significant byte of *abit*, then the most significant byte of *bbit*, and then the least significant byte of *bbit*. Each symbol can be either one or two characters; when it is a single character, the second half of the byte shall be an ASCII “\0”.

The *misc* field in the `s_vpi_value` structure shall provide for alternative value types, which can be implementation specific. If this field is utilized, one or more corresponding format types shall also be provided.

*Examples:*

In the following example, the binary value of each net which is contained in a particular module and whose name begins with a particular string is displayed. (This function makes use of the `strcmp()` facility normally declared in a `string.h` C library.)

```
void display_certain_net_values(mod, target)
vpiHandle mod;
char *target;
{
    static s_vpi_value value_s = {vpiBinStrVal};
    static p_vpi_value value_p = &value_s;
    vpiHandle net, itr;

    itr = vpi_iterate(vpiNet, mod);
    while (net = vpi_scan(itr))
    {
        char *net_name = vpi_get_str(vpiName, net);
        if (strcmp(target, net_name) == 0)
        {
            vpi_get_value(net, value_p);
            vpi_printf("Value of net %s: %s\n",
                vpi_get_str(vpiFullName, net), value_p->value.str);
        }
    }
}
```

The following example illustrates the use of `vpi_get_value()` to access UDP table entries. Two sample outputs from this example are provided after the example.

```
/*
 * hUDP shall be a handle to a UDP definition
 */
static void dumpUDPTableEntries(vpiHandle hUDP)
{
    vpiHandle hEntry, hEntryIter;
    s_vpi_value value;
    int numb;
    int udpType;
    int item;
    int entryVal;
    int *abItem;
    int cnt, cnt2;
    numb = vpi_get(vpiSize, hUDP);
    udpType = vpi_get(vpiPrimType, hUDP);
    if (udpType == vpiSeqPrim)
        numb++; /* There is one more table entry for state */
    numb++; /* There is a table entry for the output */
    hEntryIter = vpi_iterate(vpiTableEntry, hUDP);
```

```

if (!hEntryIter)
    return;
value.format = vpiVectorVal;
while(hEntry = vpi_scan(hEntryIter))
{
    vpi_printf("\n");
    /* Show the entry as a string */
    value.format = vpiStringVal;
    vpi_get_value(hEntry, &value);
    vpi_printf("%s\n", value.value.str);
    /* Decode the vector value format */
    value.format = vpiVectorVal;
    vpi_get_value(hEntry, &value);
    abItem = (int *)value.value.vector;
    for(cnt=((numb-1)/2+1);cnt>0;cnt--)
    {
        entryVal = *abItem;
        abItem++;
        /* Rip out 4 characters */
        for (cnt2=0;cnt2<4;cnt2++)
        {
            item = entryVal&0xff;
            if (item)
                vpi_printf("%c", item);
            else
                vpi_printf("_");
            entryVal = entryVal>>8;
        }
    }
    vpi_printf("\n");
}

```

For a UDP table of

```

1    0    :?:1;
0    (01) :?:-;
(10) 0    :0:1;

```

The output from the preceding example is

```

10:1
_0_1__1
01:0
_1_0__0
00:1
_0_0__1

```

For a UDP table entry of

```

1    0    :?:1;
0    (01) :?:-;
(10) 0    :0:1;

```

The output from the preceding example is

```

10:?:1
_0_1_1_?
0(01):?:-
10_0_-_?
(10)0:0:1
_001_1_0

```

## 13.16 vpi\_get\_vlog\_info()

vpi_get_vlog_info()			
<b>Synopsis:</b>	Retrieve information about Verilog-AMS simulation execution.		
<b>Syntax:</b>	vpi_get_vlog_info(vlog_info_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	bool	true on success and false on failure	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	p_vpi_vlog_info	vlog_info_p	Pointer to a structure containing simulation information

The VPI routine `vpi_get_vlog_info()` shall obtain the following information about Verilog-AMS product execution:

- The number of invocation options (*argc*)
- Invocation option values (*argv*)
- Product and version strings

The information shall be contained in an `s_vpi_vlog_info` structure. The routine shall return `TRUE` on success and `FALSE` on failure.

The `s_vpi_vlog_info` structure used by `vpi_get_vlog_info()` is defined in `vpi_user.h` and is listed in Figure 13-12.

```
typedef struct t_vpi_vlog_info {
    int argc;
    char **argv;
    char *product;
    char *version;
} s_vpi_vlog_info, *p_vpi_vlog_info;
```

**Figure 13-12** The `s_vpi_vlog_info` structure definition

## 13.17 vpi\_get\_real()

<b>vpi_get_real()</b>			
<b>Synopsis:</b>	Fetch a real property value associated with an object.		
<b>Syntax:</b>	vpi_get_real(prop,obj)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	double	value of a real property	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	prop	An integer constant representing the property of an object for which to obtain a value
	vpiHandle	obj	Handle to an object

The VPI routine `vpi_get_real()` shall return the value of object properties, for properties of type *real*. Note for object properties shown below, if the object is `NULL`, then the corresponding value shall be returned.

- `vpiStartTime` for beginning of transient analysis time
- `vpiEndTime` for end of transient analysis time
- `vpiTransientMaxStep` for maximum analog time step
- `vpiStartFrequency` for the start frequency of AC analysis
- `vpiEndFrequency` for the end frequency of AC analysis

This function is available to analog tasks and functions only. Should an error occur, `vpi_get_real()` shall return `vpiUndefined`.

## 13.18 vpi\_handle()

vpi_handle()			
<b>Synopsis:</b>	Obtain a handle to an object with a one-to-one relationship.		
<b>Syntax:</b>	vpi_handle(type, ref)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	type	An integer constant representing the type of object for which to obtain a handle
	vpiHandle	ref	Handle to a reference object
<b>Related routines:</b>	Use vpi_iterate() and vpi_scan() to obtain handles to objects with a one-to-many relationship Use vpi_handle_multi() to obtain a handle to an object with a many-to-one relationship		

The VPI routine **vpi\_handle()** shall return the object of type *type* associated with object *ref*. The one-to-one relationships which are traversed with this routine are indicated as single arrows in the data model diagrams.

*Examples:*

The following example application displays each primitive that an input net drives.

```
void display_driven_primitives(net)
vpiHandle net;
{
    vpiHandle load, prim, itr;
    vpi_printf("Net %s drives terminals of the primitives: \n",
        vpi_get_str(vpiFullName, net));
    itr = vpi_iterate(vpiLoad, net);
    if (!itr)
        return;
    while (load = vpi_scan(itr))
    {
        switch(vpi_get(vpiType, load))
        {
            case vpiGate:
            case vpiSwitch:
            case vpiUdp:
                prim = vpi_handle(vpiPrimitive, load);
                vpi_printf("\t%s\n", vpi_get_str(vpiFullName, prim));
            }
        }
    }
}
```

## 13.19 vpi\_handle\_by\_index()

<b>vpi_handle_by_index()</b>			
<b>Synopsis:</b>	Get a handle to an object using its index number within a parent object.		
<b>Syntax:</b>	vpi_handle_by_index(obj, index)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to an object
	int	index	Index number of the object for which to obtain a handle

The VPI routine `vpi_handle_by_index()` shall return a handle to an object based on the index number of the object within a parent object. This function can be used to access all objects which can access an expression using `vpiIndex`. Argument *obj* shall represent the parent of the indexed object. For example, to access a net-bit, *obj* is the associated net, while for a memory word, *obj* is the associated memory.

## 13.20 vpi\_handle\_by\_name()

<b>vpi_handle_by_name()</b>			
<b>Synopsis:</b>	Get a handle to an object with a specific name.		
<b>Syntax:</b>	vpi_handle_by_name(name, scope)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	char *	name	A character string or pointer to a string containing the name of an object
	vpiHandle	scope	Handle to a Verilog-AMS HDL scope

The VPI routine `vpi_handle_by_name()` shall return a handle to an object with a specific name. This function can be applied to all objects with a *fullname* property. The *name* can be hierarchical or simple. If *scope* is `NULL`, then *name* shall be searched for from the top level of hierarchy. Otherwise, *name* shall be searched for from *scope* using the scope search rules defined by the Verilog-AMS HDL.

## 13.21 vpi\_handle\_multi()

vpi_handle_multi()			
<b>Synopsis:</b>	Obtain a handle to inter-module paths with a many-to-one relationship.		
<b>Syntax:</b>	vpi_handle_multi(type, ref1, ref2, ...)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	type	An integer constant representing the type of object for which to obtain a handle
	vpiHandle	ref1, ref2, ...	Handles to two or more reference objects
<b>Related routines:</b>	Use vpi_iterate() and vpi_scan() to obtain handles to objects with a one-to-many relationship Use vpi_handle() to obtain handles to objects with a one-to-one relationship		

The VPI routine **vpi\_handle\_multi()** shall return a handle to objects of type **vpiInterModPath** associated with a list of *output port* and *input port* reference objects. The ports shall be of the same size and can be at different levels of the hierarchy. This routine performs a *many-to-one* operation instead of the usual one-to-one or one-to-many.

### 13.21.1 Derivatives for analog system task/functions

The VPI routine **vpi\_handle\_multi()** is used to access the derivative handles associated with analog system task/functions (see also: **vpi\_register\_analog\_systf()**). The first argument is the type **vpiDerivative**. The second is the handle for the task/function argument for which a partial derivative is to be declared. The third argument indicates the value with respect to which the derivative being declared shall be calculated. For example, assuming `argHandle2` and `argHandle3` are handles to the second and third arguments of an analog system task, then `vpi_handle_multi(vpiDerivative, argHandle2, argHandle3)` indicates the partial derivative of the returned value with respect to the third argument. For **vpiDerivative**, the **vpi\_handle\_multi()** function can only be called for those derivatives allocated during the *derivtf* phase of execution.

### 13.21.2 Examples

The following example illustrates the declaration and use of derivative handles in an analog task `$resistor()`, which implements a conductance relationship. The task can be used as follows:

```

module resistor(p, n);
  electrical p, n;
  parameter real r = 1k;
  real curr;
  analog begin
    $resistor(curr, V(p, n), r);
    I(p, n) <+ curr;
  end
endmodule

```

The implementation of the analog task can be performed by the `resistor_compile_tf()` and `resistor_call_tf()` routines shown below:

```

#include "vpiutils.h"

/* compiletf() */
static int resistor_compiletf(p_cb_data cb_data) {
  vpiHandle funcHandle, i_handle, v_handle, r_handle, didv_handle;
  int type;
  s_vpi_value value;
  double g;
  p_resistor_data res;

  /* Retrieve handle to current function */
  funcHandle = vpi_handle(vpiSysTfCall, NULL);

  /* Get the handle on the first function argument*/
  i_handle = vpi_handle_by_index(funcHandle, 1);

  /* Check that argument exists */
  if (!i_handle) {
    vpi_error("Not enough arguments for $resistor function.");
  }

  /* Check that argument #1 is a real variable */
  type = vpi_get(vpiType, v_handle);
  if (type != vpiRealVar) {
    vpi_error("Arg #1 of $resistor should be a real variable");
    return 1;
  }

  /* Get the handle on the second function argument*/
  v_handle = vpi_handle_by_index(funcHandle, 2);

  /* Check that argument exists */
  if (!v_handle) {
    vpi_error("Not enough arguments for $resistor function.");
    return 1;
  }

  /* Check that argument #1 is a real valued */
  type = vpi_get(vpiType, v_handle);

```

```

if (type != vpiRealVar && type != vpiRealVal) {
    vpi_error("Arg #2 of $resistor should be a real variable");
    return 1;
}
/* Get the handle on the third function argument*/
r_handle = vpi_handle_by_index(funcHandle, 3);

/* Check that argument exists */
if (!v_handle) {
    vpi_error("Not enough arguments for $resistor function.");
    return 1;
}

/* Check that argument #3 is real valued */
type = vpi_get(vpiType, r_handle);
if (type != vpiRealVar && type != vpiRealVal) {
    vpi_error("Arg #3 of $resistor should be a real variable");
    return 1;
}

return 0;
}

/* derivtf() */
static p_vpi_stf_partials resistor_derivtf(p_cb_data cb_data) {
    static t_vpi_stf_partials derivs;
    static int deriv_of[] = { 1 };
    static int deriv_to[] = { 2 };

    derivs.count = 1;
    derivs.derivative_of = deriv_of;
    derivs.derivative_to = deriv_to;

    return &derivs;
}

/* load() */
static int resistor_calltf(int data, int reason) {
    vpiHandle funcHandle, i_handle, v_handle, didv_handle;
    double g;
    s_vpi_value value;

    /* Retrieve handle to current function */
    funcHandle = vpi_handle(vpiSysTfCall, NULL);
    i_handle = vpi_handle_by_index(funcHandle, 1);
    v_handle = vpi_handle_by_index(funcHandle, 2);
    didv_handle = vpi_handle_multi(vpiDerivative, i_handle,
        v_handle);

    /* Get resistance value, compute conductance and store it as*/
    /* derivative*/

```

```

value.format = vpiRealVal;
    vpi_get_value(r_handle, &value);
g = 1.0 / value.value.real;

value.value.real = g;
vpi_put_value(didv_handle, &value, NULL, vpiNoDelay);

/* Get voltage value, compute current and store it into "I"*/
vpi_get_value(v_handle, &value);
value.value.real *= g;
vpi_put_value(i_handle, &value, NULL, vpiNoDelay);

return 0;
}

/*
 * Public structure declaring the task
 */
static s_vpi_analog_systf_data resistor_systf = {
    vpiSysAnalogTask,          /* type: function / task */
    0,                        /* returned type */
    "$resistor",              /* name */
    resistor_calltf,          /* calltf callback */
    resistor_compiletf,       /* compiletf callback */
    0,                        /* unused: sizetf callback */
    resistor_derivtf,         /* derivtf callback */
    0                          /* user_data: nothing */
};

```

## 13.22 vpi\_iterate()

<b>vpi_iterate()</b>			
<b>Synopsis:</b>	Obtain an iterator handle to objects with a one-to-many relationship.		
<b>Syntax:</b>	vpi_iterate(type, ref)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an iterator for an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	type	An integer constant representing the type of object for which to obtain iterator handles
	vpiHandle	ref	Handle to a reference object
<b>Related routines:</b>	Use vpi_scan() to traverse the HDL hierarchy using the iterator handle returned from vpi_iterate() Use vpi_handle() to obtain handles to object with a one-to-one relationship Use vpi_handle_multi() to obtain a handle to an object with a many-to-one relationship		

The VPI routine **vpi\_iterate()** shall be used to traverse one-to-many relationships, which are indicated as double arrows in the data model diagrams. The **vpi\_iterate()** routine shall return a handle to an iterator, whose type shall be **vpiIterator**, which can be used by **vpi\_scan()** to traverse all objects of type *type* associated with object *ref*. To get the reference object from the iterator object use `vpi_handle(vpiUse, iterator_handle)`. If there are no objects of type *type* associated with the reference handle *ref*, then the **vpi\_iterate()** routine shall return `NULL`.

*Examples:*

The following example application uses **vpi\_iterate()** and **vpi\_scan()** to display each net (including the size for vectors) declared in the module. The example assumes it shall be passed a valid module handle.

```
void display_nets(mod)
vpiHandle mod;
{
    vpiHandle net;
    vpiHandle itr;

    vpi_printf("Nets declared in module %s\n",
vpi_get_str(vpiFullName, mod));

    itr = vpi_iterate(vpiNet, mod);
    while (net = vpi_scan(itr))
    {
        vpi_printf("\t%s", vpi_get_str(vpiName, net));
    }
}
```

```
    if (vpi_get(vpiVector, net))
    {
        vpi_printf(" of size %d\n", vpi_get(vpiSize, net));
    }
    else vpi_printf("\n");
}
}
```

## 13.23 vpi\_mcd\_close()

<b>vpi_mcd_close()</b>			
<b>Synopsis:</b>	Close one or more files opened by vpi_mcd_open().		
<b>Syntax:</b>	vpi_mcd_close(mcd)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	unsigned int	0 if successful, the mcd of unclosed channels if unsuccessful	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	unsigned int	mcd	A multichannel descriptor representing the files to close
<b>Related routines:</b>	Use vpi_mcd_open() to open a file Use vpi_mcd_printf() to write to an opened file Use vpi_mcd_name() to get the name of a file represented by a channel descriptor		

The VPI routine **vpi\_mcd\_close()** shall close the file(s) specified by a multichannel descriptor, *mcd*. Several channels can be closed simultaneously, since channels are represented by discrete bits in the integer *mcd*. On success this routine returns a zero (0); on error it returns the *mcd* value of the unclosed channels.

The following descriptors are predefined and can not be closed using **vpi\_mcd\_close()**:

- descriptor 1 is *stdout*
- descriptor 2 is *stderr*
- descriptor 3 is the current log file

## 13.24 vpi\_mcd\_name()

<b>vpi_mcd_name()</b>			
<b>Synopsis:</b>	Get the name of a file represented by a channel descriptor.		
<b>Syntax:</b>	vpi_mcd_name(cd)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	char *	Pointer to a character string containing the name of a file	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	unsigned int	cd	A single-channel descriptor representing a file
<b>Related routines:</b>	Use vpi_mcd_open() to open a file Use vpi_mcd_close() to close files Use vpi_mcd_printf() to write to an opened file		

The VPI routine **vpi\_mcd\_name()** shall return the name of a file represented by a single-channel descriptor, *cd*. On error, the routine shall return `NULL`. This routine shall overwrite the returned value on subsequent calls. If the application needs to retain the string, it shall copy it.

## 13.25 vpi\_mcd\_open()

<b>vpi_mcd_open()</b>			
<b>Synopsis:</b>	Open a file for writing.		
<b>Syntax:</b>	vpi_mcd_open(file)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	unsigned int	A multichannel descriptor representing the file which was opened	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	char *	file	A character string or pointer to a string containing the file name to be opened
<b>Related routines:</b>	Use vpi_mcd_close() to close a file Use vpi_mcd_printf() to write to an opened file Use vpi_mcd_name() to get the name of a file represented by a channel descriptor		

The VPI routine **vpi\_mcd\_open()** shall open a file for writing and return a corresponding multichannel descriptor number (*mcd*). The following channel descriptors are predefined and shall be automatically opened by the system:

- Descriptor 1 is *stdout*
- Descriptor 2 is *stderr*
- Descriptor 3 is the current log file

The **vpi\_mcd\_open()** routine shall return a zero (0) on error. If the file is already opened, **vpi\_mcd\_open()** shall return the descriptor number.

## 13.26 vpi\_mcd\_printf()

<b>vpi_mcd_printf()</b>			
<b>Synopsis:</b>	Write to one or more files opened with vpi_mcd_open().		
<b>Syntax:</b>	vpi_mcd_printf(mcd, format, ...)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	int	The number of characters written	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	unsigned int	mcd	A multichannel descriptor representing the files to which to write
	char *	format	A format string using the C fprintf() format
<b>Related routines:</b>	Use vpi_mcd_open() to open a file Use vpi_mcd_close() to close a file Use vpi_mcd_name() to get the name of a file represented by a channel descriptor		

The VPI routine **vpi\_mcd\_printf()** shall write to one or more channels (up to 32) determined by the *mcd*. An *mcd* of 1 (bit 0 set) corresponds to Channel 1, a *mcd* of 2 (bit 1 set) corresponds to Channel 2, a *mcd* of 4 (bit 2 set) corresponds to Channel 3, and so on. Channel 1 is *stdout*, channel 2 is *stderr*, and channel 3 is the current log file. Several channels can be written to simultaneously, since channels are represented by discrete bits in the integer *mcd*. The format strings shall use the same format as the C **fprintf()** routine. The routine shall return the number of characters printed or EOF if an error occurred.

## 13.27 vpi\_printf()

<b>vpi_printf()</b>			
<b>Synopsis:</b>	Write to stdout and the current product log file.		
<b>Syntax:</b>	vpi_printf(format, ...)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	int	The number of characters written	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	char *	format	A format string using the C printf() format
<b>Related routines:</b>	Use vpi_mcd_printf() to write to an opened file		

The VPI routine **vpi\_printf()** shall write to both *stdout* and the current product log file. The format string shall use the same format as the C **printf()** routine. The routine shall return the number of characters printed or `EOF` if an error occurred.

## 13.28 vpi\_put\_delays()

vpi_put_delays()			
<b>Synopsis:</b>	Set the delays or timing limits of an object.		
<b>Syntax:</b>	vpi_put_delays(obj, delay_p)		
<b>Returns:</b>	<b>Type</b>	<b>Description</b>	
	void		
<b>Arguments:</b>	<b>Type</b>	<b>Name</b>	<b>Description</b>
	vpiHandle	obj	Handle to an object
	p_vpi_delay	delay_p	Pointer to a structure containing delay information
<b>Related routines:</b>	Use vpi_get_delays() to retrieve delays or timing limits of an object		

The VPI routine `vpi_put_delays()` shall set the delays or timing limits of an object as indicated in the `delay_p` structure. The same ordering of delays shall be used as described in the `vpi_get_delays()` function. If only the delay changes, and not the pulse limits, the pulse limits shall retain the values they had before the delays were altered.

The `s_vpi_delay` and `s_vpi_time` structures used by both `vpi_get_delays()` and `vpi_put_delays()` are defined in `vpi_user.h` and are listed in Figures 13-13 and 13-14.

```
typedef struct t_vpi_delay {
    struct t_vpi_time *da; /* ptr to user allocated array of delay
                           values */
    int no_of_delays;      /* number of delays */
    int time_type;         /* [vpiScaledRealTime, vpiSimTime] */
    bool mtm_flag;         /* true for mtm */
    bool append_flag;     /* true for append, false for replace */
    bool pulserere_flag;  /* true for pulserere values */
} s_vpi_delay, *p_vpi_delay;
```

**Figure 13-13 The s\_vpi\_delay structure definition**

```
typedef struct t_vpi_time
{
    int type;              /* [vpiScaledRealTime, vpiSimTime] */
    unsigned int high, low; /* for vpiSimTime */
    double real;           /* for vpiScaledRealTime */
} s_vpi_time, *p_vpi_time;
```

**Figure 13-14 The s\_vpi\_time structure definition**

The *da* field of the `s_vpi_delay` structure shall be a user-allocated array of `s_vpi_time` structures. This array shall store the delay values to be written by `vpi_put_delays()`. The number of elements in this array shall be determined by:

- The number of delays to be retrieved
- The `mtm_flag` setting
- The `pulsere_flag` setting

The number of delays to be retrieved shall be set in the `no_of_delays` field of the `s_vpi_delay` structure. Legal values for the number of delays shall be determined by the type of object.

- For primitive objects, the `no_of_delays` value shall be 2 or 3.
- For path delay objects, the `no_of_delays` value shall be 1, 2, 3, 6, or 12.
- For timing check objects, the `no_of_delays` value shall match the number of limits existing in the timing check.
- For inter-module path objects, the `no_of_delays` value shall be 2 or 3.

The user-allocated `s_vpi_delay` array shall contain delays in the same order in which they occur in the Verilog-AMS HDL description. The number of elements for each delay shall be determined by the flags `mtm_flag` and `pulsere_flag`, as shown in Table 13-5.

**Table 13-5—Size of the `s_vpi_delay->da` array**

Flag values	Number of <code>s_vpi_time</code> array elements required for <code>s_vpi_delay-&gt;da</code>	Order in which delay elements shall be filled
<code>mtm_flag = false</code> <code>pulsere_flag = false</code>	<i>no_of_delays</i>	1st delay: <code>da[0]</code> -> 1st delay 2nd delay: <code>da[1]</code> -> 2nd delay ...
<code>mtm_flag = true</code> <code>pulsere_flag = false</code>	$3 * no\_of\_delays$	1st delay: <code>da[0]</code> -> min delay <code>da[1]</code> -> typ delay <code>da[2]</code> -> max delay 2nd delay: ...
<code>mtm_flag = false</code> <code>pulsere_flag = true</code>	$3 * no\_of\_delays$	1st delay: <code>da[0]</code> -> delay <code>da[1]</code> -> reject limit <code>da[2]</code> -> error limit 2nd delay element: ...
<code>mtm_flag = true</code> <code>pulsere_flag = true</code>	$9 * no\_of\_delays$	1st delay: <code>da[0]</code> -> min delay <code>da[1]</code> -> typ delay <code>da[2]</code> -> max delay <code>da[3]</code> -> min reject <code>da[4]</code> -> typ reject <code>da[5]</code> -> max reject <code>da[6]</code> -> min error <code>da[7]</code> -> typ error <code>da[8]</code> -> max error 2nd delay: ...

*Examples:*

The following example application accepts a module path handle, rise and fall delays, and replaces the delays of the indicated path.

```
void set_path_rise_fall_delays(path, rise, fall)
vpiHandle path;
double rise, fall;
{
    static s_vpi_time path_da[2];
    static s_vpi_delay delay_s = {NULL, 2, vpiScaledRealTime};
    static p_vpi_delay delay_p = &delay_s;

    delay_s.da = &path_da;
    path_da[0].real = rise;
    path_da[1].real = fall;

    vpi_put_delays(path, delay_p);
}
```

## 13.29 vpi\_put\_value()

vpi_put_value()			
<b>Synopsis:</b>	Set a value on an object.		
<b>Syntax:</b>	vpi_put_value(obj, value_p, time_p, flags)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to the scheduled event caused by vpi_put_value()	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	obj	Handle to an object
	p_vpi_value	value_p	Pointer to a structure with value information
	p_vpi_time	time_p	Pointer to a structure with delay information
	int	flags	Integer constants which set the delay mode
<b>Related routines:</b>	Use vpi_get_value() to retrieve the value of an expression		

The VPI routine **vpi\_put\_value()** shall set simulation logic values on an object. The value to be set shall be stored in an `s_vpi_value` structure which has been allocated. The delay time before the value is set shall be stored in an `s_vpi_time` structure which has been allocated. The routine can be applied to nets, regs, variables, memory words, system function calls, sequential UDPs, and schedule events. The *flags* argument shall be used to direct the routine to use one of the following delay modes:

- vpiInertialDelay** All scheduled events on the object shall be removed before this event is scheduled.
- vpiTransportDelay** All events on the object scheduled for times later than this event shall be removed (modified transport delay).
- vpiPureTransportDelay** No events on the object shall be removed (transport delay).
- vpiNoDelay** The object shall be set to the passed value with no delay. Argument *time\_p* shall be ignored and can be set to NULL.
- vpiForceFlag** The object shall be forced to the passed value with no delay (same as the Verilog-AMS HDL procedural **force**). Argument *time\_p* shall be ignored and can be set to NULL.
- vpiReleaseFlag** The object shall be released from a forced value (same as the Verilog-AMS HDL procedural **release**). Argument *time\_p* shall be ignored and can be set to NULL. The *value\_p* shall contain the current value of the object.
- vpiCancelEvent** A previously scheduled event shall be cancelled. The object passed to **vpi\_put\_value()** shall be a handle to an object of type **vpiSchedEvent**.

If the *flags* argument also has the bit mask **vpiReturnEvent**, **vpi\_put\_value()** shall return a handle of type **vpiSchedEvent** to the newly scheduled event, provided there is some form

of a delay and an event is scheduled. If the bit mask is not used, or if no delay is used, or if an event is not scheduled, the return value shall be `NULL`.

The handle to the event can be cancelled by calling `vpi_put_value()` with the flag set to `vpiCancelEvent`. It shall not be an error to cancel an event which has already occurred. The scheduled event can be tested by calling `vpi_get()` with the flag `vpiScheduled`. If an event is cancelled, it shall simply be removed from the event queue. Any effects which were caused by scheduling the event shall remain in effect (e.g., events which were cancelled due to inertial delay).

Calling `vpi_free_object()` on the handle shall free the handle but shall not effect the event.

Sequential UDPs shall be set to the indicated value with no delay regardless of any delay on the primitive instance.

**Note:** `vpi_put_value()` shall only return a function value in a `calltf` application, when the call to the function is active. The action of `vpi_put_value()` to a function shall be ignored when the function is not active.

The `s_vpi_value` and `s_vpi_time` structures used by `vpi_put_value()` are defined in `vpi_user.h` and are listed in Figures 13-15 and 13-16.

```
typedef struct t_vpi_value {
    int format; /* vpi[[Bin,Oct,Dec,Hex]Str,Scalar,Int,Real,String,
                Time,Vector,Strength,ObjType]Val*/
    union {
        char *str;
        int scalar; /* vpi[0,1,X,Z] */
        int integer;
        double real;
        struct t_vpi_time *time;
        struct t_vpi_vecval *vector;
        struct t_vpi_strengthval *strength;
        char *misc;
    } value;
} s_vpi_value, *p_vpi_value;
```

**Figure 13-15 The `s_vpi_value` structure definition**

```
typedef struct t_vpi_time {
    int type; /* for vpiScaledRealTime, vpiSimTime */
    unsigned int high, low; /* for vpiSimTime */
    double real; /* for vpiScaledRealTime */
} s_vpi_time, *p_vpi_time;
```

**Figure 13-16 The `s_vpi_time` structure definition**

For `vpiScaledRealTime`, the indicated time shall be in the timescale associated with the object.

## 13.30 vpi\_register\_cb()

vpi_register_cb()			
<b>Synopsis:</b>	Register simulation-related callbacks.		
<b>Syntax:</b>	vpi_register_cb(cb_data_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to the callback object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	p_cb_data	cb_data_p	Pointer to a structure with data about when callbacks should occur and the data to be passed
<b>Related routines:</b>	Use vpi_register_systf() to register callbacks for user-defined system tasks and functions Use vpi_remove_cb() to remove callbacks registered with vpi_register_cb()		

The VPI routine **vpi\_register\_cb()** is used for registration of simulation-related callbacks to a user-provided application for a variety of reasons during a simulation. The reasons for which a callback can occur are divided into three categories:

- Simulation event
- Simulation time
- Simulation action or feature

How callbacks are registered for each of these categories is explained in the following paragraphs.

The *cb\_data\_p* argument shall point to a `s_cb_data` structure, which is defined in `vpi_user.h` and given in Figure 13-17.

```
typedef struct t_cb_data {
    int reason;
    int (*cb_rtn)();
    vpiHandle obj;
    p_vpi_time time; /* structure defined in vpi_user.h */
    p_vpi_value value; /* structure defined in vpi_user.h */
    int index; /* index of memory word or var select which changed */
    char *user_data; /* user data to be passed to callback function */
} s_cb_data, *p_cb_data;
```

**Figure 13-17 The s\_cb\_data structure definition**

For all callbacks, the *reason* field of the `s_cb_data` structure shall be set to a predefined constant, such as `cbValueChange`, `cbAtStartOfSimTime`, `cbEndOfCompile`, etc. The reason constant shall determine when the user application shall be called back. Refer to the

`vpi_user.h` file listing in *Annex C* of the *IEEE 1364-2001 Verilog HDL* specification for a list of all callback reason constants.

The `cb_rtn` field of the `s_cb_data` structure shall be set to the application routine name, which shall be invoked when the simulator executes the callback. The use of the remaining fields are detailed in the following sub clauses.

### 13.30.1 Simulation-event-related callbacks

The `vpi_register_cb()` callback mechanism can be registered for callbacks to occur for simulation events, such as value changes on an expression or terminal, or the execution of a behavioral statement. When the `cb_data_p->reason` field is set to one of the following, the callback shall occur as described below:

<b>cbValueChange</b>	After value change on an expression or terminal
<b>cbStmt</b>	Before execution of a behavioral statement
<b>cbForce/cbRelease</b>	After a force or release has occurred
<b>cbAssign/cbDeassign</b>	After a procedural assign or deassign statement has been executed
<b>cbDisable</b>	After a named block or task containing a system task or function has been disabled

The following fields shall need to be initialized before passing the `s_cb_data` structure to `vpi_register_cb()`:

<code>cb_data_p-&gt;obj</code>	This field shall be assigned a handle to an expression, terminal, or statement for which the callback shall occur. For force and release callbacks, if this is set to <code>NULL</code> , every force and release shall generate a callback.
<code>cb_data_p-&gt;time-&gt;type</code>	This field shall be set to either <b>vpiScaledRealTime</b> or <b>vpiSimTime</b> , depending on what time information the user application requires during the callback. If simulation time information is not needed during the callback, this field can be set to <b>vpiSuppressTime</b> .
<code>cb_data_p-&gt;value-&gt;format</code>	This field shall be set to one of the value formats indicated in Table 13-6. If value information is not needed during the callback, this field can be set to <b>vpiSuppressVal</b> . For <b>cbStmt</b> callbacks, value information is not passed to the callback routine, so this field shall be ignored.

**Table 13-6—Value format field of `cb_data_p->value->format`**

Format	Registers a callback to return
<b>vpiBinStrVal</b>	String of binary char(s) [1, 0, x, z]
<b>vpiOctStrVal</b>	String of octal char(s) [0–7, x, X, z, Z]
<b>vpiDecStrVal</b>	String of decimal char(s) [0–9]
<b>vpiHexStrVal</b>	String of hex char(s) [0–f, x, X, z, Z]
<b>vpiScalarVal</b>	<b>vpi1, vpi0, vpiX, vpiZ, vpiH, vpiL</b>

**Table 13-6—Value format field of `cb_data_p->value->format`, *continued***

Format	Registers a callback to return
<code>vpiIntVal</code>	Integer value of the handle
<code>vpiRealVal</code>	Value of the handle as a double
<code>vpiStringVal</code>	An ASCII string
<code>vpiTimeVal</code>	Integer value of the handle using two integers
<code>vpiVectorVal</code>	<i>aval/bval</i> representation of the value of the object
<code>vpiStrengthVal</code>	Value plus strength information of a scalar object only
<code>vpiObjectVal</code>	Return a value in the closest format of the object

When a simulation event callback occurs, the user application shall be passed a single argument, which is a pointer to an `s_cb_data` structure (this is not a pointer to the same structure which was passed to `vpi_register_cb()`). The *time* and *value* information shall be set as directed by the *time type* and *value* format fields in the call to `vpi_register_cb()`. The *user\_data* field shall be equivalent to the *user\_data* field passed to `vpi_register_cb()`. The user application can use the information in the passed structure and information retrieved from other VPI interface routines to perform the desired callback processing.

For a `cbValueChange` callback, if the *obj* is a memory word or a variable array, the *value* in the `s_cb_data` structure shall be the value of the memory word or variable select which changed value. The *index* field shall contain the index of the memory word or variable select which changed value.

For `cbForce`, `cbRelease`, `cbAssign`, and `cbDeassign` callbacks, the object returned in the *obj* field shall be a handle to the force, release, assign or deassign statement. The *value* field shall contain the resultant value of the LHS expression. In the case of a release, the *value* field shall contain the value after the release has occurred.

*Examples:*

The following example shows an implementation of a simple monitor functionality for scalar nets, using a simulation-event-related callback.

```

setup_monitor(net)
vpiHandle net;
{
    static s_vpi_time time_s = {vpiScaledRealTime};
    static s_vpi_value value_s = {vpiBinStrVal};
    static s_cb_data cb_data_s =
        {cbValueChange, my_monitor, NULL, &time_s, &value_s};
    char *net_name = vpi_get_str(vpiFullName, net);
    cb_data_s.obj = net;
    cb_data_s.user_data = malloc(strlen(net_name)+1);
    strcpy(cb_data_s.user_data, net_name);
    vpi_register_cb(&cb_data_s);
}

```

```

my_monitor(cb_data_p)
p_cb_data cb_data_p; {
    vpi_printf("%d %d: %s = %s\n",
        cb_data_p->time->high, cb_data_p->time->low,
        cb_data_p->user_data,
        cb_data_p->value->value.str);
}

```

### 13.30.2 Simulation-time-related callbacks

The `vpi_register_cb()` can register callbacks to occur for simulation time reasons, include callbacks at the beginning or end of the execution of a particular time queue. The following time-related callback reasons are defined:

<b>cbAtStartOfSimTime</b>	Callback shall occur before execution of events in a specified time queue. A callback can be set for any time, even if no event is present.
<b>cbReadWriteSynch</b>	Callback shall occur after execution of events for a specified time.
<b>cbReadOnlySynch</b>	Same as <b>cbReadWriteSynch</b> , except writing values or scheduling events before the next scheduled event is not allowed.
<b>cbNextSimTime</b>	Callback shall occur before execution of events in the next event queue.
<b>cbAfterDelay</b>	Callback shall occur after a specified amount of time, before execution of events in a specified time queue. A callback can be set for anytime, even if no event is present.

The following fields shall need to be set before passing the `s_cb_data` structure to `vpi_register_cb()`:

<code>cb_data_p-&gt;time-&gt;type</code>	This field shall be set to either <b>vpiScaledRealTime</b> or <b>vpiSimTime</b> , depending on what time information the user application requires during the callback.
<code>cb_data_p-&gt;[time-&gt;low,time-&gt;high,time-&gt;real]</code>	These fields shall contain the requested time of the callback or the delay before the callback.

The *value* fields are ignored for all reasons with simulation-time-related callbacks.

When the `cb_data_p->time->type` is set to **vpiScaledRealTime**, the `cb_data_p->obj` field shall be used as the object for determining the time scaling.

For reason **cbNextSimTime**, the time structure is ignored.

When a simulation-time-related callback occurs, the user callback application shall be passed a single argument, which is a pointer to an `s_cb_data` structure (this is not a pointer to the same structure which was passed to `vpi_register_cb()`). The *time* structure shall contain the current simulation time. The *user\_data* field shall be equivalent to the *user\_data* field passed to `vpi_register_cb()`.

The callback application can use the information in the passed structure and information retrieved from other interface routines to perform the desired callback processing.

### 13.30.3 Simulator analog and related callbacks

The `vpi_register_cb()` callback mechanism can be registered for callbacks to occur for analog simulation events, such as acceptance of the initial or final analog solution. When the `cb_data_p->reason` field is set to one of the following, the callback shall occur as described below:

<b>acbInitialStep</b>	Upon acceptance of the first analog solution
<b>acbFinalStep</b>	Upon acceptance of the last analog solution
<b>acbAbsTime</b>	Upon acceptance of the analog solution for the given time (this callback shall force a solution at that time)
<b>acbElapsedTime</b>	Upon acceptance of the solution advanced from the current solution by the given interval (this callback shall force a solution at that time)
<b>acbConvergenceTest</b>	Prior acceptance of the analog solution for the given time (this callback allows rejection of the analog solution at that time and backup to an earlier time)
<b>acbAcceptedPoint</b>	Upon acceptance of the solution at the given time

### 13.30.4 Simulator action and feature related callbacks

The `vpi_register_cb()` can register callbacks to occur for simulator action reasons or simulator feature reasons. *Simulator action reasons* are callbacks such as the end of compilation or end of simulation. *Simulator feature reasons* are software-product-specific features, such as restarting from a saved simulation state or entering an interactive mode. Actions are differentiated from features in that actions shall occur in all VPI-compliant products, whereas features might not exist in all VPI-compliant products.

The following action-related callbacks shall be defined:

<b>cbEndOfCompile</b>	End of simulation data structure compilation or build
<b>cbStartOfSimulation</b>	Start of simulation (beginning of time 0 simulation cycle)
<b>cbEndOfSimulation</b>	End of simulation (e.g., <code>\$finish</code> system task executed)
<b>cbError</b>	Simulation run-time error occurred
<b>cbPLIError</b>	Simulation run-time error occurred in a PLI function call
<b>cbTchkViolation</b>	Timing check error occurred

Examples of possible feature related callbacks are

<b>cbStartOfSave</b>	Simulation save state command invoked
<b>cbEndOfSave</b>	Simulation save state command completed
<b>cbStartOfRestart</b>	Simulation restart from saved state command invoked
<b>cbEndOfRestart</b>	Simulation restart command completed
<b>cbEnterInteractive</b>	Simulation entering interactive debug mode (e.g., <code>\$stop</code> system task executed)

<b>cbExitInteractive</b>	Simulation exiting interactive mode
<b>cbInteractiveScopeChange</b>	Simulation command to change interactive scope executed
<b>cbUnresolvedSysf</b>	Unknown user-defined system task or function encountered

The only fields in the `s_cb_data` structure which need to be setup for simulation action/feature callbacks are the `reason`, `cb_rtn`, and `user_data` (if desired) fields.

When a simulation action/feature callback occurs, the user routine shall be passed a pointer to an `s_cb_data` structure. The `reason` field shall contain the reason for the callback. For **cbTchkViolation** callbacks, the `obj` field shall be a handle to the timing check. For **cbInteractiveScopeChange**, `obj` shall be a handle to the new scope. For **cbUnresolvedSysf**, `user_data` shall point to the name of the unresolved task or function. On a **cbError** callback, the routine `vpi_chk_error()` can be called to retrieve error information.

*Examples:*

The following example shows a callback application which reports cpu usage at the end of a simulation. If the user routine `setup_report_cpu()` is placed in the `vlog_startup_routines` list, it shall be called just after the simulator is invoked.

```
static int initial_cputime_g;

void report_cpu()
{
    int total = get_current_cputime() - initial_cputime_g;
    vpi_printf("Simulation complete. CPU time used: %d\n", total);
}

void setup_report_cpu()
{
    static s_cb_data cb_data_s = {cbEndOfSimulation, report_cpu};
    initial_cputime_g = get_current_cputime();
    vpi_register_cb(&cb_data_s);
}
```

## 13.31 vpi\_register\_analog\_systf()

vpi_register_analog_systf()			
<b>Synopsis:</b>	Register user-defined system task/function-related callbacks.		
<b>Syntax:</b>	vpi_register_analog_systf(systf_data_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to the callback object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	p_vpi_analog_systf_data	systf_analog_data_p	Pointer to a structure with data about when callbacks should occur and the data to be passed
<b>Related routines:</b>	Use vpi_register_systf() to register digital domain system tasks/functions. Use vpi_register_cb() to register callbacks for simulation-related events		

The VPI routine `vpi_register_analog_systf()` shall register callbacks for user-defined analog system tasks or functions. Callbacks can be registered to occur when a user-defined system task or function is encountered during compilation or execution of analog Verilog-AMS HDL source code. Tasks or functions can be registered with either the analog or digital domain. The registration function (`vpi_register_analog_systf()` or `vpi_register_systf()`) with which the task or function is registered shall determine the context or contexts from which the task or function can be invoked and how and when the call backs associated with the function shall be called. The task or function name shall be unique in the domain in which it is registered. That is, the same name can be shared by two sets of callbacks, provided that one set is registered in the digital domain and the other is registered in the analog.

The `systf_analog_data_p` argument shall point to a `s_vpi_systf_analog_data` structure, which is defined in `vpi_user.h` and listed in Figure 13-18.

```
typedef struct t_vpi_systf_analog_data {
    int type;          /* vpiAnalogSysTask,vpiAnalogSysFunc */
    int sysfunc_type; /* vpi[IntFunc,RealFunc] */
    char *tfname;     /* first character shall be "$" */
    int (*calltf)();
    int (*compiletf)();
    int (*sizetf)(); /* for vpiSizedFunc system functions only */
    p_vpi_stf_partials (*derivtf)(); /* for partial derivatives */
    char *user_data;
} s_vpi_analog_systf_data, *p_vpi_analog_systf_data;
```

**Figure 13-18** The `s_vpi_analog_systf_data` structure definition

### 13.31.1 System task and function callbacks

User-defined Verilog-AMS system tasks and functions which use VPI routines can be registered with `vpi_register_systf()` or `vpi_register_analog_systf()`. The *calltf*, *completf*, and *sizetf* system task/function-related callbacks are defined in `vpi_register_systf()`.

The *type* field of the `s_vpi_systf_data` structure shall register the user application to be a system task or a system function. The *type* field value shall be an integer constant of `vpiAnalogSysTask` or `vpiAnalogSysFunction`.

The *sysfunctype* field of the `s_vpi_analog_systf_data` structure shall define the type of value which a system function shall return. The *sysfunctype* field shall be an integer constant of `vpiIntFunc` or `vpiRealFunc`. This field shall only be used when the *type* field is set to `vpiAnalogSysFunction`.

The *completf*, *calltf*, *sizetf*, and *derivtf* fields of the `s_vpi_analog_systf_data` structure shall be pointers to the user-provided applications which are to be invoked by the system task/function callback mechanism. One or more of the *completf*, *calltf*, *sizetf*, and *derivtf* fields can be set to `NULL` if they are not needed. Callbacks to the applications pointed to by the *completf* and *sizetf* fields shall occur when the simulation data structure is compiled or built (or for the first invocation if the system task or function is invoked from an interactive mode). Callbacks to the applications pointed to by the *derivtf* fields shall occur when registering partial derivatives for the analog system task/function arguments or return value. Callbacks to the application pointed to by the *calltf* routine shall occur each time the system task or function is invoked during simulation execution.

The *user\_data* field of the `s_vpi_analog_systf_data` structure shall specify a user-defined value, which shall be passed back to the *completf*, *sizetf*, *derivtf*, and *calltf* applications when a callback occurs.

The usage of the *completf*, *sizetf*, and *calltf* routines for the analog system task/function are identical to those of digital system task/functions registered with `vpi_register_systf()`. Refer to the description of `vpi_register_systf()` for more information.

### 13.31.2 Declaring derivatives for analog system task/functions

Analog system tasks and functions require partial derivatives of the outputs (arguments for system tasks and the return value for system functions). Thus it is possible (though not necessary) to have a partial derivative of the returned value with respect to any or all of the arguments and a partial derivative of any particular argument with respect to any or all of the other arguments.

The *derivtf* field of the `t_vpi_analog_systf_data` structure can be called during the build process (similar to *sizetf*) and returns a pointer to a `t_vpi_stf_partials` data structure containing the required information. The purpose of this function is declarative only, it does not assign any value to the derivative being declared. Having declared a partial derivative using this function in the *derivtf* callback, values can then be contributed to the derivative using the `vpi_put_value` function in the *calltf* call back.

The `t_vpi_stf_partials` data structure is defined:

```
typedef struct t_vpi_stf_partials {
    int count;
    int *derivative_of; /* 0 = returned value, 1 = 1st arg, etc. */
    int *derivative_wrt; /* 1 = 1st arg, 2 = 2nd arg, etc. */
} s_vpi_stf_partials, *p_vpi_stf_partials;
```

This data structure declares the derivative objects for the associated analog task/function. During the *call\_tf* phase, their handles can be retrieved via calls to `vpi_handl_multi()`.

### 13.31.3 Examples

The following example illustrates the declaration and use of callbacks in an analog function `$sampler()` which implements a sample and hold. The task is used as follows:

```
module sampnhold(out, in);
    electrical out, in;
    parameter real period = 1e-3;
    analog begin
        V(out) <+ $sampler(V(in), period);
    end
endmodule
```

The VPI implementation of the sampler is as follows:

```
typedef struct {
    vpiHandle returnHandle; /* Arg #0 (returned value) */
    vpiHandle exprHandle; /* Arg #1 (sampled expression) */
    double period; /* Arg #2 (static period expression) */
    s_cb_data cb_data; /* callback structure */
    s_vpi_value value;
    /* value structure (holds the expression value) */
} s_sampler_data, *p_sampler_data;

/* Forward declarations */
static int sampler_callback(p_cb_data data);
static void schedule_callback(p_sampler_data sampler,
    double currTime);

/* compiletf() */
static int sampler_compiletf(p_cb_data task_cb_data) {
    vpiHandle functionHandle, returnHandle, exprHandle, periodHandle;
    s_cb_data cb_data;
    int type;
    p_sampler_data sampler;
    s_vpi_value value;

    /* Retrieve handle to current function */
    functionHandle = vpi_handle(vpiSysTfCall, NULL);

    /* Get the handle on the expression argument*/
    exprHandle = vpi_handle_by_index(functionHandle, 1);
```

```

/* Check that expression argument exists */
if (!exprHandle) {
    vpi_error("Not enough arguments for $sampler function.");
}

/* Check that expression argument is of real value */
type = vpi_get(vpiType, exprHandle);
if (type != vpiRealVal && type != vpiRealVar) {
    vpi_error("Arg #1 of $sampler should be real valued.");
    return 1;
}

/* Get the handle on the period argument */
periodHandle = vpi_handle_by_index(functionHandle, 2);

/* Check that period argument exists */
if (!periodHandle) {
    vpi_error("Not enough arguments for $sampler function.");
}

/* Check that period argument has a real value */
type = vpi_get(vpiType, periodHandle);
if (type != vpiRealVal && type != vpiRealVar) {
    vpi_error("Arg #2 of $sampler should be real valued");
    return 1;
}

/* Schedule callback for time = 0 */
sampler->cb_data.reason = cbEndOfCompile;
sampler->cb_data.cb_rtn = sampler_postcompile_cb;
sampler->cb_data.time.type = 0;
sampler->cb_data.user_data = (char *) functionHandle;
sampler->cb_data.time.real = 0.0;
schedule_callback(sampler, 0.0);

vpi_register_cb(&sampler->cb_data);

return 0;
}

/* calltf */
static int sampler_calltf(int data, int reason) {
    vpiHandle funcHandle;
    p_sampler_data sampler = (p_sampler_data) data;
    s_vpi_value value;

    /* Retrieve handle to current function */
    funcHandle = vpi_handle(vpiSysTfCall, NULL);

```

```

    /* Set returned value to held value */
    vpi_set_value(sampler->returnHandle, &sampler->value, NULL,
        vpiNoDelay);
    return 0;
}

/* initialization callback after compile */
static int sampler_postcompile_cb(p_cb_data data) {
    vpiHandle functionHandle = (vpiHandle) data;
    p_sampler_data sampler;
    s_vpi_value value;

    /* Allocate the instance data and initialize it*/
    sampler = (p_sampler_data)malloc(sizeof(s_sampler_data));

    /*Get the handle to the returned value, no need to check that one*/
    sampler->returnHandle = vpi_handle_by_index(functionHandle, 0);
    sampler->exprHandle = vpi_handle_by_index(functionHandle, 1);
    sampler->periodHandle = vpi_handle_by_index(functionHandle, 2);

    /* Get the period value, it is assumed to be constant */
    /* (but not necessary) */
    sampler->value.format = vpiRealVal;
    vpi_get_value(periodHandle, &value);
    sampler->period = value.value.real;

    /* Schedule callback for time = period */
    sampler->cb_data.reason = acbElapsedTime;
    sampler->cb_data.cb_rtn = sampler_update_cb;
    sampler->cb_data.time.type = vpiScaledTme;
    sampler->cb_data.user_data = (char *) sampler;
    sampler->cb_data.time.real = sampler->period;
    schedule_callback(sampler, 0.0);

    vpi_register_cb(&sampler->cb_data);

    return 0;
}

/* timer callback */
static int sampler_update_cb(p_cb_data data) {
    p_sampler_data sampler = (p_sampler_data)data->user_data;
    s_vpi_value value;

    /* Hold expression value */
    vpi_get_value(sampler->exprHandle, &value);

    /* Schedule next callback */
    sampler->cb_data.reason = acbAbsTime;
    sampler->cb_data.cb_rtn = sampler_update_cb;
    sampler->cb_data.time.type = vpiScaledTime;
    sampler->cb_data.user_data = (char *) sampler;

```

```

    sampler->cb_data.time.real =
        vpi_get_analog_time() + sampler->period;
    register_callback(&sampler->cb_data);
    return 0;
}

/*
 * Public structure declaring the function
 */
static s_vpi_systf_data sampler_systf = {
    vpiSysFunc,          /* type: function / function */
    vpiRealFunc,        /* returned type          */
    "$sampler",         /* name                   */
    sampler_calltf,     /* calltf callback       */
    sampler_compiletf, /* compiletf callback    */
    0,                  /* unused: sizetf callback */
    0,                  /* unused: derivtf callback */
    0                   /* user_data: nothing    */
};

```

## 13.32 vpi\_register\_systf()

vpi_register_systf()			
<b>Synopsis:</b>	Register user-defined system task/function-related callbacks.		
<b>Syntax:</b>	vpi_register_systf(systf_data_p)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to the callback object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	p_vpi_systf_data	systf_data_p	Pointer to a structure with data about when callbacks should occur and the data to be passed
<b>Related routines:</b>	Use vpi_register_analog_systf() to register analog system task/functions. Use vpi_register_cb() to register callbacks for simulation-related events		

The VPI routine **vpi\_register\_systf()** shall register callbacks for user-defined system tasks or functions. Callbacks can be registered to occur when a user-defined system task or function is encountered during compilation or execution of Verilog-AMS HDL source code.

The *systf\_data\_p* argument shall point to a `s_vpi_systf_data` structure, which is defined in `vpi_user.h` and listed in Figure 13-19.

```
typedef struct t_vpi_systf_data {
    int type; /* vpiSys[Task,TaskA,Function,FunctionA] */
    int sysfunctype; /* vpi[IntFunc,RealFunc,TimeFunc,SizedFunc] */
    char *tfname; /* first character shall be "$" */
    int (*calltf)();
    int (*compiletf)();
    int (*sizedtf)(); /* for vpiSizedFunc system functions only */
    char *user_data;
} s_vpi_systf_data, *p_vpi_systf_data;
```

**Figure 13-19 The s\_vpi\_systf\_data structure definition**

### 13.32.1 System task and function callbacks

User-defined Verilog-AMS system tasks and functions which use VPI routines can be registered with **vpi\_register\_systf()**. The following system task/function-related callbacks are defined.

The *type* field of the `s_vpi_systf_data` structure shall register the user application to be a system task or a system function. The *type* field value shall be an integer constant of `vpiSysTask` or `vpiSysFunction`. `vpiSysTask` shall register a task with the digital domain. `vpiSysFunction` shall register a function with the digital domain.

The *sysfunctype* field of the `s_vpi_systf_data` structure shall define the type of value the system function returns. The *sysfunctype* field shall be an integer constant of `vpiIntFunc`, `vpiRealFunc`, `vpiTimeFunc`, or `vpiSizedFunc`. This field shall only be used when the *type* field is set to `vpiSysFunction`.

The *compiletf*, *calltf*, and *sizetf* fields of the `s_vpi_systf_data` structure shall be pointers to the user-provided applications which are to be invoked by the system task/function callback mechanism. One or more of the *compiletf*, *calltf*, and *sizetf* fields can be set to `NULL` if they are not needed. Callbacks to the applications pointed to by the *compiletf* and *sizetf* fields shall occur when the simulation data structure is compiled or built (or for the first invocation if the system task or function is invoked from an interactive mode). Callbacks to the application pointed to by the *calltf* routine shall occur each time the system task or function is invoked during simulation execution.

The *sizetf* application shall only be called if the PLI application type is `vpiSysFunction` and the *sysfunctype* is `vpiSizedFunc`. If no *sizetf* is provided, a user-defined system function of `vpiSizedFunc` shall return 32-bits.

The *user\_data* field of the `s_vpi_systf_data` structure shall specify a user-defined value, which shall be passed back to the *compiletf*, *sizetf*, and *calltf* applications when a callback occurs.

#### Examples:

The following example application demonstrates dynamic linking of a VPI system task. The example uses an imaginary routine, `dlink()`, which accepts a file name and a function name and then links that function dynamically. This routine derives the target file and function names from the target *systf* name.

```
link_systf(target)
char *target;
{
    char task_name[strSize];
    char file_name[strSize];
    char compiletf_name[strSize];
    char calltf_name[strSize];
    static s_vpi_systf_data task_data_s = {vpiSysTask};
    static p_vpi_systf_data task_data_p = &task_data_s;

    sprintf(task_name, "$%s", target);
    sprintf(file_name, "%s.o", target);
    sprintf(compiletf_name, "%s_compiletf", target);
    sprintf(calltf_name, "%s_calltf", target);

    task_data_p->tfname = task_name;
    task_data_p->compiletf = (int (*)()) dlink(file_name,
        compiletf_name);
    task_data_p->calltf = (int (*)()) dlink(file_name, calltf_name);
    vpi_register_systf(task_data_p);
}
```

### 13.32.2 Initializing VPI system task/function callbacks

A means of initializing system task/function callbacks and performing any other desired task just after the simulator is invoked shall be provided by placing routines in a NULL-terminated static array, `vlog_startup_routines`. A C function using the array definition shall be provided as follows:

```
void (*vlog_startup_routines[]) ();
```

This C function shall be provided with a VPI-compliant product. Entries in the array shall be added by the user. The location of `vlog_startup_routines` and the procedure for linking `vlog_startup_routines` with a software product shall be defined by the product vendor. (Callbacks can also be registered or removed at any time during an application routine, not just at startup time).

This array of C functions shall be for registering system tasks and functions. User tasks and functions which appear in a compiled description shall generally be registered by a routine in this array.

*Examples:*

The following example uses `vlog_startup_routines` to register system tasks and functions and to run a user initialization routine.

```
/*In a vendor product file which contains vlog_startup_routines ...*/
extern void register_my_systfs();
extern void my_init();
void (*vlog_startup_routines[]) () =
{
    setup_report_cpu, /* user routine example in 23.24.3 */
    register_my_systfs, /* user routine listed below */
    0 /* shall be last entry in list */
}

/* In a user provided file... */
void register_my_systfs()
{
    static s_vpi_systf_data systf_data_list[] = {
        {vpiSysTask, 0 "$my_task", my_task_calltf, my_task_compiletf},
        {vpiSysFunc, vpiIntFunc, "$my_func", my_func_calltf,
         my_func_compiletf},
        {vpiSysFunc, vpiRealFunc, "$my_real_func", my_rfunc_calltf,
         my_rfunc_compiletf},
        {0}
    };

    p_vpi_systf_data systf_data_p = &(systf_data_list[0]);
    while (systf_data_p->type)
        vpi_register_systf(systf_data_p++);
}
```

### 13.33 vpi\_remove\_cb()

<b>vpi_remove_cb()</b>			
<b>Synopsis:</b>	Remove a simulation callback registered with vpi_register_cb().		
<b>Syntax:</b>	vpi_remove_cb(cb_obj)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	bool	1 (true) if successful; 0 (false) on a failure	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	cb_obj	Handle to the callback object
<b>Related routines:</b>	Use vpi_register_cb() to register callbacks for simulation-related events		

The VPI routine `vpi_remove_cb()` shall remove callbacks which were registered with `vpi_register_cb()`. The argument to this routine shall be a handle to the callback object. The routine shall return a 1 (`TRUE`) if successful, and a 0 (`FALSE`) on a failure. After `vpi_remove_cb()` is called with a handle to the callback, the handle is no longer valid.

## 13.34 vpi\_scan()

<b>vpi_scan()</b>			
<b>Synopsis:</b>	Scan the Verilog-AMS HDL hierarchy for objects with a one-to-many relationship.		
<b>Syntax:</b>	vpi_scan(itr)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	vpiHandle	Handle to an object	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	vpiHandle	itr	Handle to an iterator object returned from vpi_iterate()
<b>Related routines:</b>	Use vpi_iterate() to obtain an iterator handle Use vpi_handle() to obtain handles to an object with a one-to-one relationship Use vpi_handle_multi() to obtain a handle to an object with a many-to-one relationship		

The VPI routine **vpi\_scan()** shall traverse the instantiated Verilog-AMS HDL hierarchy and return handles to objects as directed by the iterator *itr*. The iterator handle shall be obtained by calling **vpi\_iterate()** for a specific object type. Once **vpi\_scan()** returns `NULL`, the iterator handle is no longer valid and can not be used again.

*Examples:*

The following example application uses **vpi\_iterate()** and **vpi\_scan()** to display each net (including the size for vectors) declared in the module. The example assumes it shall be passed a valid module handle.

```

void display_nets(mod)
vpiHandle mod;
{
    vpiHandle net;
    vpiHandle itr;

    vpi_printf("Nets declared in module %s\n",
vpi_get_str(vpiFullName, mod));

    itr = vpi_iterate(vpiNet, mod);
    while (net = vpi_scan(itr))
    {
        vpi_printf("\t%s", vpi_get_str(vpiName, net));
        if (vpi_get(vpiVector, net))
        {
            vpi_printf(" of size %d\n", vpi_get(vpiSize, net));
        }
        else vpi_printf("\n");
    }
}

```

## 13.35 vpi\_sim\_control()

vpi_sim_control()			
<b>Synopsis:</b>	Provide software-specific simulation control.		
<b>Syntax:</b>	vpi_sim_control(flag, ...)		
	<b>Type</b>	<b>Description</b>	
<b>Returns:</b>	bool	1 (true) if successful; 0 (false) on a failure	
	<b>Type</b>	<b>Name</b>	<b>Description</b>
<b>Arguments:</b>	int	flag	Descriptor of the simulation control request
	var args	...	Variable number and type of arguments depending on flag
<b>Related routines:</b>	NONE		

The VPI routine *vpi\_sim\_control* shall be used to pass information from user code to Verilog simulator. All standard compliant simulators must support the following three operations:

*vpiStop* - cause **\$stop** built-in Verilog system task to be executed upon return of user function. This operation shall be passed one additional diagnostic message level integer argument that is the same as the argument passed to **\$stop** (see Section 10.4.2).

*vpiFinish* - cause **\$finish** built-in Verilog system task to be executed upon return of user function. This operation shall be passed one additional diagnostic message level integer argument that is the same as the argument passed to **\$finish** (see Section 10.4.1).

*vpiReset* - cause **\$reset** informative built-in Verilog system task to be executed upon return of user VPI function. This operation shall be passed three integer value arguments: *stop\_value*, *reset\_value*, *diagnostic\_level* that are the same values passed to the **\$reset** system task (see Section F.7 of *IEEE 1364-1995 Verilog HDL*).

*vpiSetInteractiveScope* - cause interactive scope to be immediately changed to new scope. This operation shall be passed one argument that is a *vpiHandle* object with type *vpiScope*.

*vpiRejectTransientStep* - cause the current analog simulation timepoint to be rejected. This operation shall pass one argument which is the current timestep (delta).

*vpiTransientFailConverge* - cause the current analog simulation to continue iterating for a (valid) solution.

Because there may be a need for user VPI applications to pass simulator specific information from back from a user application to control simulation, additional operators and operation specific arguments may be defined.

# Annex A

## Syntax

This annex contains the formal syntax definition of Verilog-AMS HDL. The conventions used are described in Section 1. Any category whose name begins with the italicized word *digital\_* should be interpreted by its definition in the grammar given in *IEEE 1364-1995 Verilog HDL Annex A*, and not by the local definition given herein. When such a category is defined herein (e.g., *digital\_primary ::=*), that definition should be taken to supersede the definition in *IEEE 1364-1995 Verilog HDL* when used for Verilog-AMS HDL. If any category is defined here and also in *IEEE 1364-1995 Verilog HDL*, it is a repetition of *IEEE 1364-1995 Verilog HDL*. This is done for the convenience of readers of this LRM.

### A.1 Source text

```

source_text ::=
    {description}
description ::=
    module_declaration
    | paramset_declaration
    | discipline_definition
    | nature_definition
    | connect_specification
    | digital_udp_declaration
module_declaration ::=
    {attribute_instance} module_keyword module_identifier [ digital_list_of_ports ] ;
    [ module_items ]
    endmodule
module_keyword ::=
    module
    | macromodule
module_items ::=
    { module_item }
    | analog_block
module_item ::=
    module_item_declaration
    | parameter_override
    | module_instantiation
    | digital_continuous_assignment
    | digital_gate_instantiation
    | digital_udp_instantiation
    | digital_specify_block

```

```

| digital_initial_construct
| digital_always_construct
module_item_declaration ::=
    {attribute_instance} parameter_declaration
| {attribute_instance} local_parameter_declaration
| {attribute_instance} string_parameter_declaration
| {attribute_instance} local_string_parameter_declaration
aliasparam_declaration
| {attribute_instance} digital_input_declaration
| {attribute_instance} digital_output_declaration
| {attribute_instance} digital_inout_declaration
ground_declaration
| {attribute_instance} integer_declaration
| {attribute_instance} real_declaration
| {attribute_instance} net_discipline_declaration
genvar_declaration
branch_declaration
analog_function_declaration
digital_function_declaration
digital_net_declaration
digital_reg_declaration
digital_time_declaration
digital_realtime_declaration
digital_event_declaration
digital_task_declaration
parameter_override ::=
    defparam list_of_param_assignments ;
paramset_declaration ::=
    {attribute_instance} paramset paramset_identifier module_or_paramset_identifier ;
    paramset_item_declaration {paramset_item_declaration}
    paramset_statement { paramset_statement }
    endparamset
paramset_item_declaration ::=
    {attribute_instance} parameter_declaration
| {attribute_instance} local_parameter_declaration
| {attribute_instance} string_parameter_declaration
| {attribute_instance} local_string_parameter_declaration
aliasparam_declaration
| {attribute_instance} integer_declaration
| {attribute_instance} real_declaration
paramset_statement ::=
    .module_parameter_identifier = constant_expression ;
    .$system_parameter_identifier = constant_expression ;
| statement

```

## A.2 Natures

```

nature_declaration ::=
    nature nature_name
    [ nature_descriptions ]
    endnature
nature_name ::=
    nature_identifier
    | nature_identifier : parent_identifier
parent_identifier ::=
    nature_identifier
    | discipline_identifier.flow
    | discipline_identifier.potential
nature_descriptions ::=
    nature_description { nature_description }
nature_description ::=
    attribute = constant_expression ;
attribute ::=
    abstol
    | access
    | ddt_nature
    | idt_nature
    | units
    | attribute_identifier

```

## A.3 Disciplines

```

discipline_declaration ::=
    discipline discipline_identifier
    [ discipline_descriptions ]
    enddiscipline
discipline_descriptions ::=
    discipline_description { discipline_description }
discipline_description ::=
    nature_binding
    | attr_override
    | domain_binding
nature_binding ::=
    pot_or_flow nature_identifier ;
attr_override ::=
    pot_or_flow . attribute_identifier = constant_expression ;
pot_or_flow ::=
    potential
    | flow
domain_binding ::=
    domain discrete
    | domain continuous

```

## A.4 Declarations

```

digital_net_declaration ::=
    digital_net_declaration
    | wreal [ list_of_identifiers ] ;
parameter_declaration ::=
    parameter [opt_type] list_of_param_assignments ;
local_parameter_declaration ::=
    localparam [opt_type] list_of_param_assignments ;
opt_type ::=
    real
    | integer
list_of_param_assignments ::=
    declarator_init { , declarator_init }
declarator_init ::=
    parameter_identifier = constant_expression {opt_value_range}
    | parameter_array_identifier range = constant_param_arrayinit {opt_value_range}
opt_value_range ::=
    from value_range_specifier
    | exclude value_range_specifier
    | exclude value_constant_expression
value_range_specifier ::=
    start_range_spec expression1 : expression2 end_range_spec
value_range_specifier ::=
    start_paren expression1 : expression2 end_paren
start_paren ::=
    [ (
end_paren ::=
    ] )
expression1 ::=
    constant_expression | -inf
expression2 ::=
    constant_expression | inf
constant_param_arrayinit ::=
    { param_arrayinit_element_list }
param_arrayinit_element_list
    param_arrayinit_element { , param_arrayinit_element }
param_arrayinit_element ::=
    constant_expression
    | { replicator_constant_expression {constant_expression} }
string_parameter_declaration ::=
    parameter string parameter_identifier = string_constant_expression [ string_list ] ;
local_string_parameter_declaration ::=
    localparam string parameter_identifier = string_constant_expression [ string_list ] ;
string_list ::=
    [ from { string { , string } } ] [ exclude { string { , string } } ]
aliasparam_declaration ::=
    aliasparam alias_identifier = parameter_identifier ;
integer_declaration ::=
    integer list_of_identifiers ;
real_declaration ::=
    real list_of_identifiers ;

```

```

list_of_identifiers ::=
    var_name { , var_name }
var_name ::=
    variable_identifier
    | array_identifier array_range
array_range ::=
    [ upper_limit_constant_expression : lower_limit_constant_expression ]
ground_declaration ::=
    ground [ range ] list_of_nets ;
net_discipline_declaration ::=
    discipline_identifier [range] list_of_nets ;
list_of_nets ::=
    net_type { , net_type }
net_type ::=
    net_identifier [range] [= constant_expression | constant_array_expression]
range ::=
    [ constant_expression : constant_expression ]
branch_declaration ::=
    branch list_of_branches ;
list_of_branches ::=
    terminals list_of_branch_identifiers
terminals ::=
    ( net_or_port_scalar_expression )
    | ( net_or_port_scalar_expression , net_or_port_scalar_expression )
list_of_branch_identifiers ::=
    branch_identifier [ range ]
    | branch_identifier [ range ] , list_of_branch_identifiers
genvar_declaration ::=
    genvar list_of_genvar_identifiers ;
list_of_genvar_identifiers ::=
    genvar_identifier { , genvar_identifier }
analog_function_declaration ::=
    analog function [ type ] function_identifier ;
    function_item_declaration { function_item_declaration }
    statement
    endfunction
type ::=
    integer
    | real
function_item_declaration ::=
    input_declaration
    | inout_declaration
    | output_declaration
    | block_item_declaration
block_item_declaration ::=
    parameter_declaration
    | integer_declaration
    | real_declaration

```

## A.5 Module instantiation

```

module_instantiation ::=
    module_or_paramset_identifier [ parameter_value_assignment ] instance_list
instance_list ::=
    module_instance { , module_instance } ;
module_instance ::=
    name_of_instance ( [ list_of_module_connections ] )
name_of_instance ::=
    module_instance_identifier [ range ]
list_of_module_connections ::=
    ordered_port_connection { , ordered_port_connection }
    | named_port_connection { , named_port_connection }
ordered_port_connection ::=
    net_expression
named_port_connection ::=
    . port_identifier ( net_expression )
parameter_value_assignment ::=
    # ( ordered_param_override_list )
    | # ( named_param_override_list )
ordered_param_override_list ::=
    constant_or_constant_array_expression { , constant_or_constant_array_expression }
named_param_override_list ::=
    named_param_override { , named_param_override }
named_param_override ::=
    . parameter_identifier ( constant_or_constant_array_expression )
constant_or_constant_array_expression ::=
    constant_expression
    | constant_array_expression
net_expression ::=
    net_identifier
    | net_identifier [ expression ]
    | net_identifier [ msb_constant_expression : lsb_constant_expression ]
    | net_concatenation
net_concatenation ::=
    { net_expression_list }
net_expression_list ::=
    net_expression { , net_expression }

```

## A.6 Mixed signal

```

connectmodule_declaration ::=
    connectmodule module_identifier ( connectmod_port , connectmod_port ) ;
    [ module_items ]
    endmodule
connectmod_port ::=
    connectmod_port_identifier

```

```

connect_specification ::=
    connectrules connectrule_identifier ;
    { connect_spec_item }
    endconnectrules
connect_spec_item ::=
    connect_insertion
    | connect_resolution
connect_insertion ::=
    connect connect_module_identifier connect_attributes
    [ [ direction ] discipline_identifier , [ direction ] discipline_identifier ] ;
connect_attributes ::=
    [ connect_mode ] [ #( attribute_list ) ]
connect_mode ::=
    merged
    | split
attribute_list ::=
    attribute
    | attribute_list , attribute
attribute ::=
    .parameter_identifier ( expression )
direction ::=
    input
    | output
    | inout
discipline_list ::=
    discipline_identifier
    | discipline_list , discipline_identifier
connect_resolution ::=
    connect discipline_list resolveto discipline_identifier ;
discipline_list ::=
    discipline_identifier
    | discipline_list , discipline_identifier

```

## A.7 Behavioral statements

```

analog_block ::=
    analog analog_statement
analog_statement ::=
    analog_seq_block
    | analog_branch_contribution
    | analog_indirect_branch_assignment
    | analog_procedural_assignment
    | analog_conditional_statement
    | analog_for_statement
    | analog_case_statement
    | analog_event_controlled_statement
    | system_task_enable
    | statement

```

```

statement ::=
    seq_block
    | procedural_assignment
    | conditional_statement
    | loop_statement
    | case_statement
analog_seq_block ::=
    begin [ : block_identifier { block_item_declaration } ]
    { analog_statement }
    end
analog_statement_or_null ::=
    analog_statement | ;
analog_branch_contribution ::=
    bvalue <+ analog_expression ;
analog_indirect_branch_assignment ::=
    bvalue : nexpr == analog_expression ;
nexpr ::=
    bvalue
    | pvalue
    | ddt ( bvalue | pvalue )
    | idt ( bvalue | pvalue )
analog_procedural_assignment ::=
    lexpr = analog_expression ;
lexpr ::=
    integer_identifier
    | real_identifier
    | array_element
array_element ::=
    integer_identifier [ expression ]
    | real_identifier [ expression ]
analog_conditional_statement ::=
    if ( genvar_expression ) analog_statement_or_null
    [ else analog_statement_or_null ]
analog_case_statement ::=
    case ( genvar_expression ) analog_case_item { analog_case_item } endcase
    | casex ( genvar_expression ) analog_case_item { analog_case_item } endcase
    | casez ( genvar_expression ) analog_case_item { analog_case_item } endcase
analog_case_item ::=
    genvar_expression { , genvar_expression } : analog_statement_or_null
    | default [ : ] analog_statement_or_null
analog_for_statement ::=
    for ( genvar_assignment ; genvar_expression ;
    genvar_assignment ) analog_statement
event_control_statement ::=
    event_control statement_or_null
event_control ::=
    @ event_identifier
    | @ ( event_expression )
analog_event_expression ::=
    global_event
    | event_function
    | digital_expression

```

```

| event_identifier
| posedge digital_expression
| negedge digital_expression
| event_expression or event_expression
digital_event_expression ::=
    digital_expression
| event_identifier
| posedge digital_expression
| negedge digital_expression
| event_function
| digital_event_expression or digital_event_expression
global_event ::=
    initial_step [ ( analysis_list ) ]
| final_step [ ( analysis_list ) ]
analysis_list ::=
    analysis_name { , analysis_name }
analysis_name ::=
    "analysis_identifier "
event_function ::=
    cross_function
| above_function
| timer_function
cross_function ::=
    cross ( arg_list )
above_function ::=
    above ( arg_list )
timer_function ::=
    timer ( arg_list )
statement_or_null ::=
    statement | ;
system_task_enable ::=
    system_task_name [ ( expression { , expression } ) ];
system_task_name ::=
    $identifier
Note: The $ may not be followed by a space.
seq_block ::=
    begin [ : block_identifier { block_item_declaration } ]
    { statement }
    end
procedural_assignment ::=
    lexpr = expression ;
conditional_statement ::=
    if ( expression ) statement_or_null
    [ else statement_or_null ]
case_statement ::=
    case ( expression ) case_item { case_item } endcase
| casex ( expression ) case_item { case_item } endcase
| casez ( expression ) case_item { case_item } endcase
case_item ::=
    expression { , expression } : statement_or_null
| default [ : ] statement_or_null

```

```

loop_statement ::=
    repeat ( expression ) statement
  | while ( expression ) statement
  | for ( procedural_assignment ; expression ;
    procedural_assignment ) statement

```

## A.8 Analog expressions

```

analog_expression ::=
    expression
  | analog_operator ( analog_operator_arg_list )
  | analog_system_function ( analog_operator_arg_list )
analog_operator_arg_list ::=
    analog_operator_argument { , analog_operator_argument }
analog_operator_argument ::=
    expression
  | constant_array_expression
  | analog_operator ( analog_operator_arg_list )
analog_operator ::=
    ddt | ddx | idt | idtmod | absdelay | transition | slew |
    laplace_zd | laplace_zp | laplace_np | laplace_nd
  | zi_zp | zi_zd | zi_np | zi_nd | last_crossing | ac_stim
  | limexp | white_noise | flicker_noise | noise_table
analog_system_function ::=
    $limit | $stable_model
genvar_expression ::=
    genvar_primary
  | unary_operator genvar_primary
  | genvar_expression binary_operator genvar_primary
  | genvar_expression ? genvar_expression : genvar_expression
  | string
genvar_primary ::=
    constant_primary
  | genvar_identifier
  | genvar_identifier [ genvar_expression ]
  | analysis ( arg_list )
  | genvar_system_function
genvar_system_function ::=
    $param_given ( module_parameter_identifier )
  | $port_connected ( port_scalar_expression )
genvar_assignment ::=
    genvar_identifier = genvar_expression

```

## A.9 Expressions

```

range ::=
    [ constant_expression : constant_expression ]

```

```

constant_expression ::=
    constant_primary
    | string
    | unary_operator constant_primary
    | constant_expression binary_operator constant_expression
    | constant_expression ? constant_expression : constant_expression
    | constant_array_expression
    | attribute_reference
    | built_in_function ( const_arg_list )
    | random_function ( const_arg_list )
const_arg_list ::=
    constant_expression { , constant_expression }
attribute_reference ::=
    net_identifier . pot_or_flow . attribute_identifier
constant_primary ::=
    number
    | parameter_identifier
    | localparam_identifier
    | $system_parameter_identifier
    | constant_concatenation
constant_array_expression ::=
    { constant_arrayinit_element { , constant_arrayinit_element } }
constant_arrayinit_element ::=
    constant_expression
    | integer_constant_expression { constant_expression }
expression ::=
    primary
    | unary_operator primary
    | expression binary_operator expression
    | expression ? expression : expression
    | function_call
    | access_function_reference
    | built_in_function ( arg_list )
    | system_function ( arg_list )
    | random_function [ ( arg_list ) ]
function_call ::=
    function_identifier ( expression { , expression } )
arg_list ::=
    argument { , argument }
argument ::=
    expression
    | constant_array_expression
constant_array_expression ::=
    { constant_array_init_element { , constant_array_init_element } }
constant_array_init_element ::=
    constant_expression
    | integer_constant_expression { , constant_expression }
access_function_reference ::=
    bvalue
    | pvalue
bvalue ::=
    access_identifier ( analog_signal_list )

```

```

analog_signal_list ::=
    branch_identifier
    | array_branch_identifier [ genvar_expression ]
    | net_or_port_scalar_expression
    | net_or_port_scalar_expression , net_or_port_scalar_expression
net_or_port_scalar_expression ::=
    net_or_port_identifier
    | array_net_or_port_identifier [ genvar_expression ]
    | vector_net_or_port_identifier [ genvar_expression ]
pvalue ::=
    flow_access_identifier ( < port_scalar_expression > )
port_scalar_expression ::=
    port_identifier
    | array_port_identifier [ genvar_expression ]
    | vector_port_identifier [ genvar_expression ]
unary_operator ::=
    + | - | ! | ~
binary_operator ::=
    + | - | * | / | % | == | === | != | !== | && | ||
    | < | <= | > | >= | & | ~& | | | ~ | ^ | ^~ | ~^ | >> | <<
digital_primary ::=
    primary
primary ::=
    number
    | identifier
    | identifier [ expression ]
    | identifier [ digital_msb_constant_expression : digital_lsb_constant_expression ]
    | digital_concatenation
    | digital_multiple_concatenation
    | digital_function_call
    | (digital_mintypmax_expression )
    | string
    | nexpr
    | ( expression )
number ::=
    decimal_number
    | digital_octal_number
    | digital_binary_number
    | digital_hex_number
    | real_number
decimal_number ::=
    [ sign ] unsigned_num
real_number ::=
    [ sign ] unsigned_num . unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] e [ sign ] unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] E [ sign ] unsigned_num
    | [ sign ] unsigned_num [ . unsigned_num ] scale_factor
concatenation ::=
    { expression { , expression } }
sign ::=
    +
    | -

```

```

unsigned_num ::=
    decimal_digit { _ | decimal_digit }
digital_number ::=
    number
decimal_digit ::=
    0 | 1 | 2 | 3 | 4 | 5 | 6 | 7 | 8 | 9
scale_factor ::=
    T | G | M | K | k | m | u | n | p | f | a
built_in_function ::=
    ln | log | exp | sqrt | min | max | abs | pow | ceil | floor
    | sin | cos | tan | asin | acos | atan | atan2
    | sinh | cosh | tanh | asinh | acosh | atanh | hypot
driver_access_function ::=
    driver_update | net_resolution
system_function ::=
    $abstime | $realttime | $temperature | $vt | $simparam | $bound_step | $discontinuity
    | $driver_count | $driver_state | $driver_strength
random_function ::=
    $random | $rdist_uniform | $rdist_normal | $rdist_exponential | $rdist_poisson
    | $rdist_chi_square | $rdist_t | $rdist_erlang

```

## A.10 General

```

attribute_instance ::=
    (* attr_spec {, attr_spec } *)
attr_spec ::=
    attr_name = constant_expression
    | attr_name
attr_name ::=
    identifier
comment ::=
    short_comment
    | long_comment
short_comment ::=
    // comment_text \n
long_comment ::=
    /* comment_text */
comment_text ::=
    { Any_ASCII_character }
string ::=
    " { Any_ASCII_character_except_newline } "
identifier ::=
    IDENTIFIER [ { . IDENTIFIER } ]

```

NOTE: The period in identifier may not be preceded or followed by a space.

```

IDENTIFIER ::=
    simple_identifier
    | escaped_identifier
simple_identifier ::=
    [ a-zA-Z_ ] { a-zA-Z_$0-9 }

```

```
escaped_identifier ::=  
  \ { Any_ASCII_character_except_white_space } white_space  
white_space ::=  
  space  
  | tab  
  | newline  
  | formfeeds
```

# **Annex B**

## **Keywords**

This annex contains the list of all keywords used in Verilog-AMS HDL.

### **B.1 All keywords**

Keywords are predefined nonescaped identifiers which define Verilog-AMS HDL language constructs. An escaped identifier shall not be treated as a keyword.

above	endconnectrules	last_crossing	scalared
abs	endmodule	limexp	sin
absdelay	endfunction	ln	sinh
acos	endnature	localparam	slew
acosh	endparamset	log	small
ac_stim	endprimitive	macromodule	specify
aliasparam	endspecify	max	specparam
always	endtable	medium	sqrt
analog	endtask	min	string
analysis	event	module	strong0
and	exclude	nand	strong1
asin	exp	nature	supply0
asinh	final_step	negedge	supply1
assign	flicker_noise	net_resolution	table
atan	floor	nmos	tan
atan2	flow	noise_table	tanh
atanh	for	nor	task
begin	force	not	time
branch	forever	notif0	timer
buf	fork	notif1	tran
bufif0	from	or	tranif0
bufif1	function	output	tranif1
case	generate	parameter	transition
casex	genvar	paramset	tri
casez	ground	pmos	tri0
ceil	highz0	posedge	tri1
cmos	highz1	potential	triand
connectrules	hypot	pow	trior
cos	idt	primitive	trireg
cosh	idtmod	pull0	vectored
cross	if	pull1	wait
ddt	ifnone	pullup	wand
ddx	inf	pulldown	weak0
deassign	initial	rcmos	weak1
default	initial_step	real	while
defparam	inout	realtime	white_noise
disable	input	reg	wire
discipline	integer	release	wor
driver_update	join	repeat	wreal
edge	laplace_nd	rnmos	xnor
else	laplace_np	rpmos	xor
end	laplace_zd	rtran	zi_nd
enddiscipline	laplace_zp	rtranif0	zi_np
endcase	large	rtranif1	zi_zd

## B.2 Discipline/nature

Discipline and nature keywords are predefined nonescaped identifiers which define and are only applicable to Verilog-AMS HDL discipline and nature constructs. All discipline and nature keywords are used between the Verilog-AMS HDL keywords **discipline** and **enddiscipline** and between the keywords **nature** and **endnature**. An escaped identifier shall not be treated as a `discipline` or `nature` keyword.

**abstol**  
**access**  
**continuous**  
**ddt\_nature**  
**discrete**  
**domain**  
**idt\_nature**  
**units**

## B.3 Connect rules

Connect rules keywords are predefined nonescaped identifiers which define and are only applicable to Verilog-AMS HDL connect constructs. All connect rules keywords are used between the Verilog-AMS HDL keywords **connectrules** and **endconnectrules**. An escaped identifier shall not be treated as a `connect_rules` keyword.

**connect**  
**merged**  
**resolveto**  
**split**



# Annex C

## Analog language subset

Prior to the release of Verilog-AMS HDL, the OVI board approved an analog-only specification called *Verilog-A v1.0*. With the release of Verilog-AMS HDL, the “official” *Verilog-A LRM* is no longer supported as it is included as part of the Verilog-AMS HDL specification. This annex defines a working subset of Verilog-AMS HDL for analog-only products.

### C.1 Verilog-AMS introduction

This section previews Verilog-A and its language features.

#### C.1.1 Verilog-A overview

This Verilog-A subset defines a behavioral language for analog only systems. Verilog-A is derived from the *IEEE 1364-1995 Verilog HDL* specification using a minimum number of constructs for analog and mixed-signal behavioral descriptions. This Annex is intended to cover the definition and semantics of Verilog-A as proposed by OVI.

The intent of Verilog-A is to let designers of analog systems and integrated circuits create and use modules which encapsulate high-level behavioral descriptions of systems and components. The behavior of each module can be described mathematically in terms of its terminals and external parameters applied to the module. These behavioral descriptions can be used in many disciplines such as electrical, mechanical, fluid dynamics, and thermodynamics.

Verilog-A has been defined to be applicable to both electrical and non-electrical systems description. It supports conservative and signal-flow descriptions by using the terminology for these descriptions using the concepts of nodes, branches, and terminals. The solution of analog behaviors which obey the laws of conservation fall within the generalized form of Kirchhoff’s Potential and Flow Laws (KPL and KFL). Both of these are defined in terms of the quantities associated with the analog behaviors.

#### C.1.2 Verilog-A language features

The Verilog-A subset provides access to a salient set of features of the full modeling language that allow analog designers the ability to model analog systems:

- Verilog-A modules are compatible with Verilog-AMS HDL.
- Analog behavioral modeling descriptions are contained in a separate analog block.
- Branches can be named for easy selection and access.
- Parameters can be specified with valid range limits.
- Systems can be modeled by using expressions consisting of operators, variables, and signals:
  - 1.a full set of operators including trigonometric functions, integrals, and derivatives;
  - 2.a set of waveform filters to modify the waveform results for faster and more accurate simulation like transition, slew, Laplace, and Z-domain;
  - 3.a set of events to control when certain code is simulated;
  - 4.selection of the simulation time step for simulation control;
  - 5.support for accessing SPICE primitives from within the language.

## C.2 Lexical conventions

With the exception of certain keywords required for Verilog-AMS HDL, Section 2 is applicable to both Verilog-A and Verilog-AMS HDL. All Verilog-AMS HDL keywords shall be supported by Verilog-A as reserved words, but *IEEE 1364-2001 Verilog HDL* and Verilog-AMS HDL specific keywords are not used in Verilog-A. The following Verilog-AMS HDL keywords are not required to be supported for a fully compliant Verilog-A subset:

- From Section 2.5, Numbers: support for x and z values is limited in the analog block only to mixed signal, as defined in Section 8.3.2.
- From Section 2.6, Strings: support for regs is limited to the digital context only.
- From Section 2.7.2, Keywords: certain keywords are not applicable in Verilog-A, as defined in Annex C.15.

## C.3 Data types

The data types of Section 3 are applicable to both Verilog-AMS HDL and Verilog-A with the following exceptions:

- From Section 3.4.2.2, Domain binding: the domain binding type `discrete` shall be an error in Verilog-A.
- From Section 3.5, Real net declarations: the `wreal` data type is not supported in Verilog-A.
- From Section 3.6, Default discipline: the ``default_discipline` compiler directive is not supported in Verilog-A. All Verilog-A modules shall have a discipline defined for each module.

**Note:** This feature allows the use of digital modules in Verilog-AMS HDL without editing them to add a discipline.

## C.4 Expressions

The expressions defined in Section 4 are applicable to both Verilog-AMS HDL and Verilog-A with the following exception:

The case equality operators (`===`, `!===`) are not supported in Verilog-A.

## C.5 Signals

The signals defined in Section 5 are applicable to both Verilog-AMS HDL and Verilog-A.

## C.6 Analog behavior

The analog behavior defined in Section 6 are applicable to both Verilog-AMS HDL and Verilog-A with the following exceptions:

- No digital behavior or events are supported in Verilog-A.
- `casex` and `casez` are not supported in Verilog-A.

## C.7 Hierarchical structures

The hierarchical structure defined in Section 7 is applicable to both Verilog-AMS HDL and Verilog-A, except support for *real value ports* is only applicable to Verilog-AMS HDL and *IEEE 1364-1995 Verilog HDL* (see Section 7.4.3).

## C.8 Mixed signal

This section only applies to Verilog-AMS HDL.

## C.9 Scheduling semantics

The analog simulation cycle is applicable to both Verilog-AMS HDL and Verilog-A. The mixed-signal simulation cycle from Section 9.2 is only applicable to Verilog-AMS HDL.

## C.10 System tasks and functions

The system tasks and functions in Section 10 are applicable to both Verilog-AMS HDL and Verilog-A.

## C.11 Compiler directives

The compiler directives of Section 11 are applicable to both Verilog-AMS HDL and Verilog-A.

Verilog-A also supports the ``default_function_type_analog` directive, which allows user-defined functions to be treated as analog functions in Verilog-A if they do not have the key word `analog` as part of the definition. This is provided for backwards compatibility.

## C.12 Using VPI routines

The analog behavior defined in Section 12 are applicable to both Verilog-AMS HDL and Verilog-A.

## C.13 VPI routine definitions

The analog behavior defined in Section 13 are applicable to both Verilog-AMS HDL and Verilog-A.

## C.14 Syntax

This annex (Annex A) defines the differences between Verilog-AMS HDL and Verilog-A. Annex A defines the BNF for Verilog-AMS HDL.

## C.15 Keywords

The keywords in this annex (Annex B) are the complete set of Verilog-AMS HDL keywords, including those from *IEEE 1364-2001 Verilog HDL*. The following keywords as defined in this LRM are not used by Verilog-A:

- From Annex B.1, All keywords:

```
connectmodule
connectrules
driver_update
endconnectrules
net_resolution
wreal
```

- From Annex B.2, Discipline/nature:

All keywords in this section are supported in Verilog-A.

- From Annex B.3, Connect rules:

```
connect
merged
split
resolvedto
```

**Note:** All keywords of Verilog-AMS HDL are reserved words for Verilog-A.

## C.16 Standard definitions

The definitions of Annex D are applicable to both Verilog-AMS HDL and Verilog-A, with the exception of those disciplines with a domain of **discrete**.

## C.17 SPICE compatibility

Annex E defines the SPICE compatibility for both Verilog-A and Verilog-AMS HDL.

## C.18 Changes from previous Verilog-A LRM versions

As part of the Verilog-AMS HDL development, some changes and clarifications have occurred to the current Verilog-A subset. Most of the changes resulted in clarifications or additional capability; but some new compatibility issues now exist. This subsection highlights some of the key differences. The syntax and semantics of this document supersede any syntax, semantics, or interpretations of the original document. Table C.1 lists the changes from Verilog-A LRM v1.0 to v2.0. Table C.2 lists the changes from Verilog-A LRM v2.0 to v2.1.

**Table C.1—Changes from v1.0 to v2.0 syntax**

Feature	OVI Verilog-A v1.0	OVI Verilog-AMS v2.0	Change type
Analog time	\$realtime	\$abstime	new
Ceiling operator	N/A	<b>ceil</b> (expr)	new
Floor operator	N/A	<b>floor</b> (expr)	new
Circular integrator	N/A	<b>idtmod</b> (expr)	new
Expression looping	N/A	<b>genvar</b>	new
Distribution functions	\$dist_functions() Integer based functions	\$dist_functions() Real value equivalents to \$dist_functions()	new
Empty discipline	predefined as type wire	type not defined	default definition
Implicit nodes	'default_nodetype discipline_identifier default: <b>wire</b>	default type: empty discipline, no domain type	default definition
<b>initial_step</b>	default = TRAN	default = ALL	default definition
<b>final_step</b>	default = TRAN	default = ALL	default definition
Analog <b>ground</b>	no definition	now a declaration statement	definition
\$realtime	\$realtime :timescale =1 sec	\$realtime :timescale= 'timescale def=1n, see \$abstime	definition
Array setting	aa[0:1] = {2.1 = (1), 4.5 = (2)}	aa[0:1] = {2.1,4.5}	syntax
Discontinuity function	<b>discontinuity</b> (x)	<b>\$discontinuity</b> (x)	syntax
Limiting exponential function	\$limexp( <i>expression</i> )	<b>limexp</b> ( <i>expression</i> )	syntax
Port branch access	I(a,a)	I(<a>)	syntax
Timestep control (maximum stepsize)	<b>bound_step</b> ( <i>const_expression</i> <i>n</i> )	\$bound_step( <i>expr</i> )	syntax
Continuous waveform delay	<b>delay</b> ()	<b>absdelay</b> ()	syntax

Feature	OVI Verilog-A v1.0	OVI Verilog-AMS v2.0	Change type
User-defined analog functions	<b>function</b>	<b>analog function</b> See Section C.11	syntax
Discipline domain	N/A, assumed continuous	now continuous(default) and discrete	Extension
k scalar ( $10^3$ )	N/A, only “K” supported	now supported	Extension
Module keyword	<b>module</b>	<b>module</b> or <b>macromodule</b>	Extension
Modulus operator	integers only	now supports integer and reals	Extension
Time tolerance on timer functions	N/A	supports additional time tolerance argument for <b>timer()</b>	Extension
Time tolerance on transition filter	N/A	supports additional time tolerance argument for <b>transition()</b>	Extension
<code>'default_nodetype</code>	<b>'default_nodetype</b>	<b>'default_discipline</b>	Obsolete
Forever statement	<b>forever</b>	N/A	Obsolete
Generate statement	<b>generate</b>	N/A	Obsolete
Null statement	;	Limited to case, conditional, and event statements (see syntax)	Obsolete

Table C.2— Changes from v2.0 to v2.1

Item	Description/Issue	Section
1	Clarification on when range checking for parameters is done. Range check will be done only on the final value of the parameter for that instance.	Section 3.2.2
2	Not to use “max” and use “maxval” instead since <b>max</b> is a keyword	Section 3.4.1.1, Section 3.4.2.6
3	Support of user-defined attributes to disciplines similar to natures has been added. This would be a useful way to pass information to other tools reading the Verilog-AMS netlist	Section 3.4.2, Section 3.4.2.7
4	LRM specifies TRI and WIRE as aliases. The existing AMS LRM forces nets with wiretypes other than wire or tri to become digital, but in many cases these are really interconnect also. If they are tied to behavioral code they will become digital but if they are interconnected, we should not force them until after discipline resolution. This is needed if you have configs where the blocks connected to the net can change between analog and digital. If we force these nets to be digital we force unneeded CMs when blocks are switched to analog.	Section 3.4.2.4, Section 3.5
5	Setting an initial value on net as part of the net declaration.	Section 3.4.3 Syntax 3-6, Section 3.4.3.2
6	Initial value of <b>wreal</b> to be set to 0.0 if the value has not been determined at $t = 0$ .	Section 3.5

Item	Description/Issue	Section
7	Clarification on the usage of <b>`default_discipline</b> and default discipline for analog and digital primitives. Analog primitives will have default discipline as electrical, whereas digital primitives shall use the <b>`default_discipline</b> declaration. <b>`default_discipline</b> explanation moved to the section along with other compiler directives and clarification of impact on <b>'reset_all</b> on this. The usage of word 'scope' is clarified to be used as the scope of the application of the compiler directive, and not as a scope argument.	Section 3.6, Section 3.6.1, Section 3.7  Section 11.1, Section 11.2
8	Reference to derived disciplines to be removed as current BNF does not support the syntax	Section 3.8
9	Reworked discipline and nature compatibility rules for better clarity.	Section 3.8
10	Removed the reference to neutral discipline since wire can be used in the same context.	Section 3.8
11	<b>absdelay</b> instead of <b>delay</b>	Section 4.4.15
12	Array declaration wrongly specified before the variable identifier. For variables, array specification is written after the name of the variable.	Section 6.5.2 (Example)
13	<b>@(final_step)</b> without arguments should not have parenthesis	Section 6.7.4, Table 6-1
15	<b>@(final_step)</b> for DCOP should be 1	Section 6.7.4, Table 6-1
16	Examples to be fixed to use assign for <b>wreal</b> and use <b>wreal</b> in instantiation, and also add a top level block for example in 7.3.3, and the testbench use <b>wreal</b> .	Section 7.4.3, Section 3.5
17	Clarification on the port bound semantics in explaining the hierarchical structure for a port with respect to vpiLoConn and vpiHiConn and clarification on driver and receiver segregation	Section 8.2.3
18	Figure should have NetC.c_out instead of NetC.b_out	Section 8.2.3
19	Mixed-signal module examples to use case syntax with X & Z instead of "==" for value comparison	Section 8.2.3
20	Clarification on accessing discrete nets and variables and X & Z bits in the analog context.	Section 8.2.3
21	Adding Support for 'NaN & X' into Verilog-AMS. Contribution of these values to a branch would be an error; however, analog variables should be able to propagate this value. Added a section regarding NaN	Section 8.2.3, Section 8.3.2.1
22	The diagram corresponding to the bidir model has been reworked, and the example module shown for bidir will match the corresponding figure.	Section 8.6
23	Rework on <i>connect-resolveto</i> syntax section to clarify the rules	Section 8.7.2.1
24	Use <b>merged</b> instead of <b>merge</b>	Section 8.8.1
25	Support for digital primitive instantiation in an analog block. Port names are created for the ports of the digital primitives, and these digital port names cannot be used in child instantiations.	Section 8.8.5.1

Item	Description/Issue	Section
26	Net resolution function has been removed and replaced with ‘Receiver Net Resolution’. Reintroduced the <b>assign</b> statement syntax.	Section 8.10.5
27	Corrections to the connect module example using the driver access function. The errors in the example have been corrected to make it syntactically and semantically correct	Section 8.10.6
28	The constraints for supplementary drivers and delays ar clearly stated.	Section 8.11
29	Driver Type function: There should be a driver access function for finding type of driver. driver_type_function ::= \$driver_type(signal_name, signal_index)	Section 8.11.4, Annex D
30	Clarification on the MS synchronization algorithm: Includes a more detailed explanation on the analog-digital synchronization mechanism.	Section 9
31	Truncation versus Rounding mechanism for converting from analog to digital times.	Section 9.3.2.3
32	Spelling mistake on “boltzmann” and “planck” in constants file	Annex D
33	Units for charge, angle and other definitions in disciplines.vams have been changed to adhere to SI standards.	Annex D
34	Values specified in constants file for charge, light, Boltzmann constant, and so forth have been changed to adhere to the standard definitions.	Annex D

## C.19 Obsolete functionality

The following statements are not supported in the current version of Verilog-AMS HDL; they are only noted for backward compatibility.

### C.19.1 Forever

This statement is no longer supported.

### C.19.2 NULL

This statement is no longer supported. Certain functions such as case, conditionals and the event statement do allow null statements as defined by the syntax.

### C.19.3 Generate

The *generate statement* is a looping construct which is unrolled at elaboration time. It is the only looping statement that can contain analog operators. The syntax of generate statement is shown in Figure C.1.

```

generate_statement ::=
    generate indexr_identifier ( start_expr , end_expr [ , incr_expr ] )
        statement

start_expr ::=
    constant_expression

end_expr ::=
    constant_expression

incr_expr ::=
    constant_expression

```

**Figure C.1—Syntax for generate statement**

The index shall not be assigned or modified in any way inside the loop. In addition, it is local to the loop and is expanded when the loop is unrolled. Even if there is a local variable with the same name as the index and the variable is modified as a side effect of a function called from within the loop, the loop index is unaffected.

The start and end bounds and the increment are constant expressions. They are only evaluated at elaboration time. If the expressions used for the increment and bounds change during the simulation, it does not affect the behavior of the generate statement.

If the lower bound is less than the upper bound and the increment is negative, or if the lower bound is greater than the upper bound and the increment is positive, then the generate statement does not execute.

If the lower bound equals the upper bound, the increment is ignored and the statement execute once. If the increment is not given, it is taken to be +1 if the lower bound is less than the upper bound, and -1 if the lower bound is greater than the upper bound.

The statement, which can be a sequential block, is replicated with all occurrences of *index* in the statement replaced by a constant. In the first instance of the statement, the index is replaced with the lower bound. In the second, it is replaced by the lower bound plus the increment. In the third, it is replaced by the lower bound plus two times (2x) the increment. This pattern is repeated until the lower bound plus a multiple of the increment is greater than the upper bound.

*Examples:*

This module implements a continuously running (unlocked) analog-to-digital converter.

```

module adc(in,out) ;
    parameter bits=8, fullscale=1.0, dly=0.0, ttime=10n;
    input in;
    output [0:bits-1] out;
    electrical in;
    electrical [0:bits-1] out;
    real sample, thresh;

```

```
analog begin
  thresh = fullscale/2.0;
  generate i (bits-1,0) begin
    V(out[i]) <+ transition(sample > thresh, dly, ttime);
    if (sample > thresh) sample = sample - thresh;
    sample = 2.0*sample;
  end
end
endmodule
```



# **Annex D**

## **Standard definitions**

This annex contains the standard definition packages (`disciplines.vams` and `constants.vams`) for Verilog-AMS HDL.

## D.1 The disciplines.vams file

```

`ifdef DISCIPLINES_VAMS
`else
`define DISCIPLINES_VAMS 1

//
// Natures and Disciplines
//

discipline logic
  domain discrete;
enddiscipline

/*
 * Default absolute tolerances may be overridden by setting the
 * appropriate _ABSTOL prior to including this file
 */

// Electrical

// Current in amperes
nature Current
  units      = "A";
  access     = I;
  idt_nature = Charge;
`ifdef CURRENT_ABSTOL
  abstol     = `CURRENT_ABSTOL;
`else
  abstol     = 1e-12;
`endif
endnature

// Charge in coulombs
nature Charge
  units      = "coul";
  access     = Q;
  ddt_nature = Current;
`ifdef CHARGE_ABSTOL
  abstol     = `CHARGE_ABSTOL;
`else
  abstol     = 1e-14;
`endif
endnature

```

```

// Potential in volts
nature Voltage
  units      = "V";
  access    = V;
  idt_nature = Flux;
`ifdef VOLTAGE_ABSTOL
  abstol    = `VOLTAGE_ABSTOL;
`else
  abstol    = 1e-6;
`endif
endnature

// Flux in Webers
nature Flux
  units      = "Wb";
  access    = Phi;
  ddt_nature = Voltage;
`ifdef FLUX_ABSTOL
  abstol    = `FLUX_ABSTOL;
`else
  abstol    = 1e-9;
`endif
endnature

// Conservative discipline
discipline electrical
  potential Voltage;
  flow      Current;
enddiscipline

// Signal flow disciplines
discipline voltage
  potential Voltage;
enddiscipline

discipline current
  potential Current;
enddiscipline

// Magnetic
// Magnetomotive force in Ampere-Turns.
nature Magneto_Motive_Force
  units      = "A*turn";
  access    = MMF;
`ifdef MAGNETO_MOTIVE_FORCE_ABSTOL
  abstol    = `MAGNETO_MOTIVE_FORCE_ABSTOL;
`else
  abstol    = 1e-12;
`endif
endnature

```

```

// Conservative discipline
discipline magnetic
  potential    Magneto_Motive_Force;
  flow         Flux;
enddiscipline

// Thermal
// Temperature in Kelvin
nature Temperature
  units       = "K";
  access     = Temp;
`ifdef TEMPERATURE_ABSTOL
  abstol     = `TEMPERATURE_ABSTOL;
`else
  abstol     = 1e-4;
`endif
endnature

// Power in Watts
nature Power
  units       = "W";
  access     = Pwr;
`ifdef POWER_ABSTOL
  abstol     = `POWER_ABSTOL;
`else
  abstol     = 1e-9;
`endif
endnature

// Conservative discipline
discipline thermal
  potential    Temperature;
  flow         Power;
enddiscipline

// Kinematic
// Position in meters
nature Position
  units       = "m";
  access     = Pos;
  ddt_nature = Velocity;
`ifdef POSITION_ABSTOL
  abstol     = `POSITION_ABSTOL;
`else
  abstol     = 1e-6;
`endif
endnature

```

```

// Velocity in meters per second
nature Velocity
  units      = "m/s";
  access    = Vel;
  ddt_nature = Acceleration;
  idt_nature = Position;
`ifdef VELOCITY_ABSTOL
  abstol    = `VELOCITY_ABSTOL;
`else
  abstol    = 1e-6;
`endif
endnature

// Acceleration in meters per second squared
nature Acceleration
  units      = "m/s^2";
  access    = Acc;
  ddt_nature = Impulse;
  idt_nature = Velocity;
`ifdef ACCELERATION_ABSTOL
  abstol    = `ACCELERATION_ABSTOL;
`else
  abstol    = 1e-6;
`endif
endnature

// Impulse in meters per second cubed
nature Impulse
  units      = "m/s^3";
  access    = Imp;
  idt_nature = Acceleration;
`ifdef IMPULSE_ABSTOL
  abstol    = `IMPULSE_ABSTOL;
`else
  abstol    = 1e-6;
`endif
endnature

// Force in Newtons
nature Force
  units      = "N";
  access    = F;
`ifdef FORCE_ABSTOL
  abstol    = `FORCE_ABSTOL;
`else
  abstol    = 1e-6;
`endif
endnature

// Conservative disciplines
discipline kinematic
  potential  Position;
  flow      Force;
enddiscipline

```

```

discipline kinematic_v
  potential    Velocity;
  flow         Force;
enddiscipline

// Rotational

// Angle in radians
nature Angle
  units       = "rads";
  access      = Theta;
  ddt_nature  = Angular_Velocity;
`ifdef ANGLE_ABSTOL
  abstol     = `ANGLE_ABSTOL;
`else
  abstol     = 1e-6;
`endif
endnature

// Angular Velocity in radians per second
nature Angular_Velocity
  units       = "rads/s";
  access      = Omega;
  ddt_nature  = Angular_Acceleration;
  idt_nature  = Angle;
`ifdef ANGULAR_VELOCITY_ABSTOL
  abstol     = `ANGULAR_VELOCITY_ABSTOL;
`else
  abstol     = 1e-6;
`endif
endnature

// Angular acceleration in radians per second squared
nature Angular_Acceleration
  units       = "rads/s^2";
  access      = Alpha;
  idt_nature  = Angular_Velocity;
`ifdef ANGULAR_ACCELERATION_ABSTOL
  abstol     = `ANGULAR_ACCELERATION_ABSTOL;
`else
  abstol     = 1e-6;
`endif
endnature

// Torque in Newtons
nature Angular_Force
  units       = "N*m";
  access      = Tau;
`ifdef ANGULAR_FORCE_ABSTOL
  abstol     = `ANGULAR_FORCE_ABSTOL;
`else
  abstol     = 1e-6;
`endif
endnature

```

```
// Conservative disciplines
discipline rotational
  potential    Angle;
  flow         Angular_Force;
enddiscipline

discipline rotational_omega
  potential    Angular_Velocity;
  flow         Angular_Force;
enddiscipline

`endif
```

## D.2 The constants.vams file

```
// Mathematical and physical constants
`ifdef CONSTANTS_VAMS
`else
`define CONSTANTS_VAMS 1
// M_ is a mathematical constant
`define M_E 2.7182818284590452354
`define M_LOG2E 1.4426950408889634074
`define M_LOG10E 0.43429448190325182765
`define M_LN2 0.69314718055994530942
`define M_LN10 2.30258509299404568402
`define M_PI 3.14159265358979323846
`define M_TWO_PI 6.28318530717958647693
`define M_PI_2 1.57079632679489661923
`define M_PI_4 0.78539816339744830962
`define M_1_PI 0.31830988618379067154
`define M_2_PI 0.63661977236758134308
`define M_2_SQRTPI 1.12837916709551257390
`define M_SQRT2 1.41421356237309504880
`define M_SQRT1_2 0.70710678118654752440

// The following constants have been taken from http://physics.nist.gov
// P_ is a physical constant
// charge of electron in coulombs
`define P_Q 1.602176462e-19
// speed of light in vacuum in meters/sec
`define P_C 2.99792458e8
// Boltzmann's constant in joules/kelvin
`define P_K 1.3806503e-23
// Planck's constant in joules*sec
`define P_H 6.62606876e-34
// permittivity of vacuum in farads/meter
`define P_EPS0 8.854187817e-12
// permeability of vacuum in henrys/meter
`define P_U0 (4.0e-7 * `M_PI)
// zero celsius in kelvin
`define P_CELSIUS0 273.15
`endif
```

### D.3 The driver\_access.vams file

```
`define DRIVER_UNKNOWN      32'b000000000000// No information
`define DRIVER_DELAYED      32'b000000000001// driver has fixed delay
`define DRIVER_GATE          32'b000000000010// driver is a primitive
`define DRIVER_UDP           32'b000000000100// driver is a user defined primitive
`define DRIVER_ASSIGN        32'b000000001000// driver is a continuous assignment
`define DRIVER_BEHAVIORAL    32'b000000010000// driver is a reg
`define DRIVER_SDF           32'b000000100000// driver is from backannotated code
`define DRIVER_NODELETE      32'b000001000000// events won't be deleted1
`define DRIVER_NOPREEMPT     32'b000010000000// events won't be preempted
`define DRIVER_KERNEL        32'b001000000000 // added by kernel (wor/wand)
`define DRIVER_WOR           32'b010000000000// driver is on a wor net
`define DRIVER_WAND          32'b100000000000// driver is on a wand net
```

---

1. For optimization



# Annex E

## SPICE compatibility

### E.1 Introduction

Analog simulation has long been performed with SPICE and SPICE-like simulators. As such, there is a huge legacy of SPICE netlists. In addition, SPICE provides a rich set of predefined models and it is considered neither practical nor desirable to convert these models into a Verilog-AMS HDL behavioral description. In order for Verilog-AMS HDL to be embraced by the analog design community, it is important Verilog-AMS HDL provide an appropriate degree of SPICE compatibility. This annex describes the degree of compatibility which Verilog-AMS HDL provides and the approach taken to provide that compatibility.

#### E.1.1 Scope of compatibility

SPICE is not a single language, but rather is a family of related languages. The first widely used version of SPICE was SPICE2g6 from the University of California at Berkeley. However, SPICE has been enhanced and distributed by many different companies, each of which has added their own extensions to the language and models. As a result, there is a great deal of incompatibility even among the SPICE languages themselves.

Verilog-AMS HDL makes no judgement as to which of the various SPICE languages should be supported. Instead, it states if a simulator which supports Verilog-AMS HDL is also able to read SPICE netlists of a particular flavor, then certain objects defined in that flavor of SPICE netlist can be referenced from within a Verilog-AMS HDL structural description. In particular, SPICE models and subcircuits can be instantiated within a Verilog-AMS HDL module. This is also true for any SPICE primitives which are built into the simulator.

#### E.1.2 Degree of incompatibility

There are four primary areas of incompatibility between versions of SPICE simulators.

1. The version of the SPICE language accepted by various simulators is different and to some degree proprietary. This issue is not addressed by Verilog-AMS HDL. So whether a particular Verilog-AMS simulator is SPICE compatible, and with which particular variant of SPICE it is compatible, is solely determined by the authors of the simulator.

2. Not all SPICE simulators support the same set of component primitives. Thus, a particular SPICE netlist can reference a primitive which is unsupported. Verilog-AMS HDL offers no alternative in this case other than the possibility that if the model equations are known, the primitive can be rewritten as a module.
3. The names of the built-in SPICE primitives, their parameters, or their ports can differ from simulator to simulator. This is particularly true because many primitives, parameters, and ports are unnamed in SPICE. When instantiating SPICE primitives in Verilog-AMS HDL, the primitives shall, and parameters and ports can, be named. Since there are no established standard names, there is a high likelihood of incompatibility cropping up in these names.

To reduce this, a list of what names shall be used for the more common components is shown in Annex E.3. However, it is not possible to anticipate all SPICE primitives and parameters which could be supported; so different implementations can end up using different names. This level of incompatibility can be overcome by using wrapper modules to map names.

4. The mathematical description of the built-in primitives can differ. As with the netlist syntax, incompatible enhancements of the models have crept in through the years. Again, Verilog-AMS HDL offers no solution in this case other than the possibility that if the model equations are known, the primitive can be rewritten as a module.

## E.2 Accessing SPICE objects from Verilog-AMS HDL

If an implementation of a Verilog-AMS tool supports SPICE compatibility, it is expected to provide the basic set of SPICE primitives (see Annex E.3) and be able to read SPICE netlists which contain models and subcircuit statements.

SPICE primitives built into the simulator are treated in the same manner in Verilog-AMS HDL as built-in primitives. However, while the Verilog-AMS HDL built-in primitives are standardized, the SPICE primitives are not. All aspects of SPICE primitives are implementation dependent.

In addition to SPICE primitives, it is also possible to access subcircuits and models defined within SPICE netlists. The subcircuits and models contained within the SPICE netlist are treated as module definitions.

### E.2.1 Case sensitivity

Some SPICE netlists are case insensitive, whereas Verilog-AMS HDL descriptions are case-sensitive. From within Verilog-AMS HDL, a mixed-case name matches the same name with an identical case (if one is defined in a Verilog-AMS HDL description).

However, if no exact match is found, the mixed-case name shall match the same name defined within SPICE regardless of the case.

## E.2.2 Examples

This subsection shows some examples.

### E.2.2.1 Accessing SPICE models

Consider the following SPICE model file being read by a Verilog-AMS HDL simulator.

```
.MODEL VERTNPN NPN BF=80 IS=1E-18 RB=100 VAF=50
+ CJE=3PF CJC=2PF CJS=2PF TF=0.3NS TR=6NS
```

This model can be instantiated in a Verilog-AMS HDL module as shown in Figure E.1.

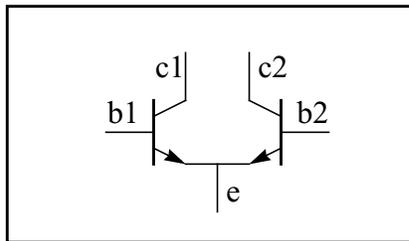


Figure E.1—Instantiated module

```
module diffPair (c1, b1, e, b2, c2);
    electrical c1, b1, e, b2, c2;

    vertNPN Q1 (c1, b1, e, );
    vertNPN Q2 (.c(c2), .b(b2), .e(e));

endmodule
```

Unlike with SPICE, the first letter of the instance name, in this case Q1 and Q2, is not constrained by the primitive type. For example, they can just as easily be T1 and T2.

The ports and parameters of the BJT are determined by the BJT primitive itself and not by the model statement for the BJT. See Annex E.3 for more details. The BJT has 3 mandatory ports (collector, base, and emitter) and one optional port (the substrate). In the instantiation of Q1, the ports are passed by order. With Q2, the ports are passed by name. In both cases, the optional substrate port is defaulted by simply not giving it.

### E.2.2.2 Accessing SPICE subcircuits

As an example of how a SPICE subcircuit is referenced from Verilog-AMS HDL, consider the following SPICE subcircuit definition of an oscillator.

```

.SUBCKT ECPOSC (OUT GND)
  VA VCC GND 5
  IEE E GND 1MA
  Q1 VCC B1 E VCC VERTNPN
  Q2 OUT B2 E OUT VERTNPN
  L1 VCC OUT 1UH
  C1 VCC OUT 1P IC=1
  C2 OUT B1 272.7PF
  C3 B1 GND 3NF
  R1 B1 GND 10K
  C4 B2 GND 3NF
  R2 B2 GND 10K
.ENDS ECPOSC

```

This oscillator can be referenced from Verilog-AMS HDL as:

```

module osc (out, gnd);
  electrical out, gnd;
  ecpOsc Osc1 (out, gnd);
endmodule

```

**Note:** In Verilog-AMS HDL the name of the subcircuit instance is not constrained to start with x as it is in SPICE.

### E.2.2.3 Accessing SPICE primitives

To show how various SPICE primitives can be accessed from Verilog-AMS HDL, the subcircuit in Figure E.1 is translated to native Verilog-AMS HDL.

```

module ecpOsc (out, gnd);
  electrical out, gnd;

  vsine #(.dc(5)) Vcc (vcc, gnd);
  isine #(.dc(1m)) Iee (e, gnd);
  vertnpn Q1 (vcc, b1, e, vcc);
  vertnpn Q2 (out, b2, e, out);
  inductor #(.l(1u)) L1 (vcc, out);
  capacitor #(.c(1p), .ic(1)) C1 (vcc, out);
  capacitor #(.c(272.7p)) C2 (out, b1);
  capacitor #(.c(3n)) C3 (b1, gnd);
  resistor #(.r(10k)) R1 (b1, gnd);
  capacitor #(.c(3n)) C4 (b2, gnd);
  resistor #(.r(10k)) R2 (b2, gnd);
endmodule

```

## E.3 Preferred primitive, parameter, and port names

Table E.1 shows the required names for primitives, parameters, and ports which are otherwise unnamed in SPICE. For connection by order instead of by name, the ports and

parameters shall be given in the order listed. The default discipline of the ports for these primitives shall be `electrical` and their descriptions shall be `inout`.

**Table E.1—Required names**

Primitive name	Port name	Parameter name
resistor	p, n	r, tc1, tc2
capacitor	p, n	c, ic
inductor	p, n	l, ic
vexp	p, n	dc, mag, phase, val0, val1, td0, tau0, td1, tau1
vpulse	p, n	dc, mag, phase, val0, val1, td, rise, fall, width, period
vpwl	p, n	dc, mag, phase, wave
vsine	p, n	dc, mag, phase, offset, ampl, freq, td, damp, sinephase, ammodindex, ammodfreq, ammodphase, fmmodindex, fmmodfreq
iexp	p, n	dc, mag, phase, val0, val1, td0, tau0, td1, tau1
ipulse	p, n	dc, mag, phase, val0, val1, td, rise, fall, width, period
ipwl	p, n	dc, mag, phase, wave
isine	p, n	dc, mag, phase, offset, ampl, freq, td, damp, sinephase, ammodindex, ammodfreq, ammodphase, fmmodindex, fmmodfreq
diode <sup>a</sup>	a, c	area
bjt <sup>a</sup>	c, b, e, s	area
mosfet <sup>a</sup>	d, g, s, b	w, l, ad, as, pd, ps, nrd, nrs
jfet <sup>a</sup>	d, g, s	area
mesfet <sup>a</sup>	d, g, s	area
vcvs	p, n, ps, ns	gain
vccs	sink, src, ps, ns	gm
tline	t1, b1, t2, b2	z0, td, f, nl

a. The names `diode`, `bjt`, `jfet`, `mesfet`, and `mosfet` are never used from within Verilog-AMS HDL because these components require a model. Thus, the model name is used in Verilog-AMS HDL instead of the primitive name.

### E.3.1 Independent sources

The parameters associated with each type of independent source are given in Table E.2. “ac” and “dc” parameters are common to each source type and need to be specified to list parameters by order before any waveshape parameters are specified.

**Table E.2—Independent source parameters**

Source Type	Parameter	Description
“ac” ALL	mag, phase	AC small signal level and phase
“dc” ALL	dc	DC value
“pulse”	val0, val1	Pulse levels
	td	Start time of first pulse
	rise, fall	Pulse rise and fall time
	width	Pulse width
	period	Pulse period

Table E.2—Independent source parameters, *continued*

Source Type	Parameter	Description	
"pwl"	wave	Vector of time/value pairs defining the waveform	
"sine"	offset	DC level of sinusoid	
	ampl	Amplitude of sinusoid	
	freq	Frequency of sinusoid	
	td	Start time of first pulse	
	damp	Damping factor of sinusoid	
	sinephase	Phase of sinusoid	
	ammodindex	AM index of modulation	
	ammodfreq	AM modulation frequency	
	ammodphase	AM modulation phase	
	fmmodindex	FM index of modulation	
	fmmodfreq	FM modulation frequency	
	"exp"	val0, val1	Equilibrium levels
		td0, td1	Start time for transitions to val0, val1
		tau0, tau1	Time constant for transition to val0, val1

### E.3.2 Unsupported components

Verilog-AMS HDL does not support the concept of passing an instance name as a parameter. As such, the following components are not supported: `ccvs`, `cccs`, and mutual inductors; however, these primitives can be instantiated inside a subcircuit.

### E.3.3 Discipline of primitives

To afford the ability to use analog primitive in any design, including mixed disciplines, the default discipline override is provided. The discipline of analog primitives will be resolved based on instance specific attributes, the disciplines of other instances on the same net, or default to electrical if it cannot be determined.

The precedence for the discipline of analog primitives is as follows:

1. A `port_discipline` attribute on the analog primitive
2. The resolution of the discipline
3. The default analog primitive of electrical

#### E.3.3.1 Setting the discipline of analog primitives

A new optional attribute shall be provided called "`port_discipline`", which shall have as a value the desired discipline for the analog primitive. It shall only apply to the instance to which it is attached. The value shall be of type string and the value must be a valid discipline of domain continuous. This attribute shall only apply to analog primitives and for all other modules shall be ignored. The following provides an example of this attribute.

```

resistor #(.r(1k)) (* integer port_discipline="electrical" ; *) r1
(node1, node2); // not needed as default

resistor #(.r(1k)) (* integer port_discipline="rotational" ; *) r2
(node1, node2);

```

Attributes are defined in the IEEE 1364-2001 LRM and will not be described in this document.

### E.3.3.2 Resolving the disciplines of analog primitives

If no attribute exists on the instance of an analog primitive, then the discipline may be determined by the disciplines of other instances connected to the same net segment. The disciplines of the vpiLoConn of all other instances on the net segment shall be evaluated to determine if they are of domain continuous and compatible with each other. If they are, then the discipline of the analog primitive shall be set to the same discipline. If they are not compatible, then an error will occur as defined in Section 3.8 of this LRM. If there are no continuous disciplines defined on the net segment, then the discipline shall default to electrical.

## E.4 Limiting algorithms

Many SPICE simulators use limiting algorithms to improve convergence in Newton-Raphson iterations. Table E.3 lists the preferred names for three functions that may be available in a simulator, their arguments, and their intended uses. The function name, enclosed in quotation marks, can be used in the `$limit()` function of Section 10.9. This allows a Verilog-AMS module to use the same limiting algorithms available to built-in SPICE primitives. The arguments are described in Section 10.9.

**Table E.3—SPICE limiting functions**

Function name	Arguments	Meant for limiting:
fetlim	vth	gate-to-source voltage of field-effect transistors
pnjlim	vte, vcrit	voltage across diodes and pn junctions in other devices
vdslim	(none)	drain-to-source voltage of field-effect transistors

## E.5 Other issues

This section highlights some other issues

### E.5.1 Multiplicity factor on subcircuits

Some SPICE simulators support a multiplicity factor ( $M$ ) parameter on subcircuits without the parameter being explicitly being declared. This factor is typically used to indicate the subcircuit should be modeled as if there are a specified number of copies in parallel. In previous versions of Verilog-AMS HDL, subcircuits defined as modules could not support automatic  $M$  factors.

Starting with LRM Version 2.2, the multiplicity factor is supported for modules in Verilog-AMS using the hierarchical system parameter `$mfactor`, as described in Section 7.2.6.

### E.5.2 Binning and libraries

Some SPICE netlists provide mechanisms for mapping an instance to a group of models, with the final determination of which model to use being based on rules encapsulated in the SPICE netlist. Examples include model binning or corners support. From within an instance statement, it appears as if the instance is referencing a simple SPICE model; supporting these additional capabilities in Verilog-AMS HDL is supported via the instance line by default. Support of SPICE model cards is implementation specific (including those using these mechanisms).

Similar functionality for Verilog-AMS is supported through use of the paramset, as described in Section 7.3. Instead of referencing a specific module, an instance may refer to a paramset identifier, and there may be several paramsets with the same identifier (name). The final determination of which paramset to use is made according to rules specified in Section 7.3.2.

# Annex F

## Discipline resolution methods

### F.1 Discipline resolution

Discipline resolution is described in Section 8.4; it provides the semantics for two methods of resolving the discipline of undeclared interconnect. This annex provides a possible algorithm for achieving the semantics of each method. It is also possible to develop and use other algorithms to match the semantics.

### F.2 Resolution of mixed signals

The following algorithms for discipline resolution of undeclared nets provide users with the ability to control the auto-insertion of connection modules. The undeclared nets are resolved at each level of the hierarchy in which *continuous* (analog) has precedence over *discrete* (digital). In both algorithms, the *continuous* domain is passed up the hierarchy from lower levels to the top level.

#### F.2.1 Default discipline resolution algorithm

This default algorithm propagates both continuous and discrete disciplines up the hierarchy to meet one another. Insertion of interface elements shall occur at each level of the hierarchy where both continuous and discrete disciplines meet. This results in connection modules being inserted higher up the design hierarchy. The algorithm is described as follows.

1. Elaborate the design

After this step, every port in the design has both its upper (actual) connection and its lower (formal) connection defined.

2. Apply all in-context node and signal declarations

For example, `electrical sig;` makes all instances of `sig` electrical, unless they have been overridden by an out-of-context declaration.

3. Apply all out-of-context node and signal declarations.

For example, `electrical top.middle.bottom.sig;` overrides any discipline which may be declared for `sig` in the module where `sig` was declared.

More than one conflicting in-context discipline declaration or more than one conflicting out-of-context discipline declaration for the same hierarchical segment of a signal is an error. In this case, *conflicting* simply means an attempt to declare more than one discipline regardless of whether the disciplines are compatible or not.

4. Traverse each signal hierarchically (depth-first) when a net is encountered which still has not been assigned a discipline:
  - A. It shall be determined whether the net is analog or digital. Any net whose port connections (i.e., connections to the upper part of a port) are all digital shall be considered digital (discrete domain), any others shall be considered analog (continuous domain).
  - B. Apply any ``default_discipline` directives to any net segments which do not yet have a discipline, provided their domain is the same as the domain of the default discipline. This is done according to the rules of precedence for ``default_discipline` (see Section 3.7).
  - C. If the segment has not yet been assigned a discipline, examine all ports to which the segment forms the upper connection and construct a list of all disciplines at the lower connections of these ports whose domains match the domain of the segment:
    - If there is only a single discipline in the list, the signal is of that discipline
    - If there is more than one discipline in the list and the contents of the list match the discipline list of a resolution connect statement, the net is of the resolved discipline given by the statement.
    - Otherwise the discipline is unknown. This is legal provided the net segment has no mixed-port connections (i.e., it does not connect through a port to a segment of a different domain). Otherwise this is an error.

At this point, connection module selection and insertion can be performed. Insert converters applying the rules and semantics of the connect statement (Section 8.7) and auto-insertion sections (Section 8.8).

### F.2.2 Alternate expanded analog discipline resolution algorithm

This algorithm propagates continuous disciplines up and then back down to meet discrete disciplines. This may result in more connection modules being inserted lower down into discrete sections of the design hierarchy for added accuracy. The selection of this algorithm instead of the default shall be controlled by a simulator option. The algorithm is described as follows.

1. Elaborate the design

After this step, every port in the design has both its upper (actual) connection and its lower (formal) connection defined.

2. Apply all in-context node and signal declarations

For example, `electrical sig;` makes all instances of `sig` electrical, unless they have been overridden by an out-of-context declaration.

3. Apply all out-of-context node and signal declarations.

For example, `electrical top.middle.bottom.sig;` overrides any discipline which may be declared for `sig` in the module where `sig` was declared.

More than one conflicting in-context discipline declaration or more than one conflicting out-of-context discipline declaration for the same hierarchical segment of a signal is an error. In this case, *conflicting* simply means an attempt to declare more than one discipline regardless of whether the disciplines are compatible or not.

4. Traverse each signal hierarchically (depth-first) when a net is encountered which has still not been assigned a discipline:

- A. It shall be determined whether the net is analog or digital. Any net whose port connections (i.e., connections to the upper part of a port) are all digital shall be considered digital. If any of the connections are analog, the net shall be considered analog. Any others shall still be considered unknown.
- B. Apply any ``default_discipline` directives to any net segments which do not yet have a discipline, provided their domain is the same as the domain of the default discipline. This is done according to the rules of precedence for ``default_discipline` (see Section 3.7).
- C. If the segment has not yet been assigned a discipline, examine all ports to which the segment forms the upper or lower connection. and construct a list of all disciplines at the other connections of these ports whose domains match the domain of the segment:
  - If there is only a single discipline in the list, the signal is of that discipline
  - If there is more than one discipline in the list and the contents of the list match the discipline list of a resolution connect statement, the net is of the resolved discipline given by the statement.
  - Otherwise the discipline is unknown.

5. Traverse each net hierarchically (top-down) when a net is encountered which still has not been assigned a discipline:

- A. It shall be determined whether the net is analog or digital. Any net whose port (i.e., connection to the lower part of a port) is digital shall be considered digital. Any others shall be considered analog.
- B. Apply any ``default_discipline` directives which to any net segments which do not yet have a discipline, provided their domain is the same as the domain of the default discipline. This is done according to the rules of precedence for ``default_discipline` (see Section 3.7).
- C. If the segment has not yet been assigned a discipline, examine all ports to which the segment forms the lower connection and construct a list of all disciplines at the upper connections of these ports whose domains match the domain of the segment:
  - If there is only a single discipline in the list, the signal is of that discipline
  - If there is more than one discipline in the list and the contents of the list match the discipline list of a resolution connect statement, the net is of the resolved discipline given by the statement.
  - Otherwise the discipline is unknown. This is legal provided the net segment has no mixed-port connections (i.e., it does not connect through a port to a segment of a different domain). Otherwise this is an error.

At this point, connection module selection and insertion can be performed. Insert converters applying the rules and semantics of the connect statement (Section 8.7) and auto-insertion sections (Section 8.8).

# Annex G

## Open issues

Annex G identifies issues in this LRM version that require additional investigation, and which will be addressed in the next revision. The following table describes the issues and categorizes them as follows:

- **Ambiguity**  
Indicates something that is unclear in the current version of the LRM
- **BNF**  
Indicates that the Verilog-AMS syntax grammar requires modification
- **Enhancement**  
Indicates something that is not addressed in the current language but will be addressed in future revisions

**Table G.1—Open issues in LRM 2.1**

Item	Description/Issue	Category
1	<p><b>wreal</b> declaration and usage should be synchronized with System Verilog language. The BNF allows a <b>wreal</b> declaration without any identifier, for example, <b>wreal;</b></p> <p>Change syntax from</p> <pre>wreal_declaration := wreal [list_of_identifiers];</pre> <p>to</p> <pre>wreal_declaration := wreal list_of_identifiers;</pre>	BNF
2	Verilog-AMS has no language extensions to support back annotation.	Enhancement
3	<p>Discipline Resolution Issues: Algorithm is based on net types rather than driver that appears on mixed net.</p> <p>Related Issues:</p> <ul style="list-style-type: none"> <li>• Driver-Receiver segregation</li> <li>• placement of A/D converter</li> <li>• empty disciplines, undeclared nets</li> <li>• how to deal with leaf level wires</li> <li>• no clear definition on OOMR</li> <li>• What is the discipline of an expression when an expression is specified as an actual in a port connection? A driver might have to be created as an unnamed implicit function.</li> </ul>	Ambiguity

Item	Description/Issue	Category
4	<p>LRM does not clearly illustrate the MS simulation cycle and the initialization is not clearly defined. Illustration of IC analysis in AMS is non-existent.</p> <ul style="list-style-type: none"> <li>• Which solver starts first</li> <li>• Initialization mechanism</li> <li>• Rules for synchronization are not clear enough and could impact portability</li> </ul> <p>Initialization with digital engine:</p> <ul style="list-style-type: none"> <li>• Mixed-signal initialization: Verilog-D simulators are transient in operation and hence there is no mechanism defined for static/steady state simulation.</li> </ul>	Ambiguity
5	System tasks and function. Issue with <b>\$random</b> . The syntax is defined in both digital (1364-2001) as well as analog (LRM 2.1) BNF. The syntax should be in sync.	BNF
6	Issue with genvar. Currently genvar is defined both in Verilog-D 1364-2001 std as well as LRM 2.1, and they are used in different contexts. Digital genvar is used more in structural context and analog genvar is used in a behavioural ( <i>analog_for</i> ) context.	BNF
7	<ul style="list-style-type: none"> <li>• External module definition to support direct import of SPICE netlists in Annex E. Currently this is not clearly stated in the LRM.</li> <li>• Augment “external module” and “macromodule” definitions within a “simulator class”. Extend the “external module” syntax with parameters indicating the language used. Also, case sensitivity of SPICE simulators should be accounted for in the language. Should there be filters for support of foreign language? Implement something similar to “shell” which is used in digital simulators.</li> </ul>	Enhancement
8	Support for global variables using dynamic parameters	Enhancement
9	Ambiguities with <i>if-else-if</i> BNF syntax, when nested <i>if</i> statements are used, when the <i>if-condition</i> is statically evaluatable.	BNF
10	<p>Contribution statements:</p> <ul style="list-style-type: none"> <li>• It is not clear whether contribution statements should be allowed as part of initial conditions like <b>initial_step</b>. The current BNF restricts the use of contribution statements in this context.</li> <li>• Contribution statement inside loops. Should this be allowed? Current LRM disallows using contribution statements in loops.</li> </ul>	Enhancement
11	LRM does not specify DC Sweep behavior for mixed-signal simulations.	Ambiguity
13	SPICE versus Verilog name conflict. There is an issue while instantiating two modules with the same name defined in different abstractions (SPICE versus Verilog). Currently, the LRM does not have any name scoping mechanisms. Look at the possibility of issuing an error when a name conflict occurs, or use the standard library methodology to pick the first match from the library.	Enhancement
14	Switch branch syntax not defined in BNF, though it is explained in an example. Also, should indirect branch assignment be made illegal in conditional? This is not clearly defined in the LRM (direct contribution statements are allowed in <i>if</i> statements to model switch behavior).	BNF
15	<p>Discipline Compatibility:</p> <p>How do you resolve disciplines with different abstol. Should there be a resolution function? Should the tighter tolerance apply?</p>	Ambiguity
16	<p>Discipline Compatibility:</p> <p>Current LRM makes it illegal to have incompatible continuous disciplines on the same net. Should this be allowed?</p>	Enhancement
18	‘include does not support both <code>&lt;&gt;</code> and <code>""</code> to include header files. This syntax could be used to differentiate system-defined header files and user-defined header files.	Enhancement

Item	Description/Issue	Category
19	The specification of roots for the Zi filter has changed from $Z^{-1}$ to $Z$ . Poles and zeros are roots of $Z^{-1}$ , but this changed in post 1.4 versions.	Ambiguity
20	Should flow and potential etc. be part of global keyword list? Should there be a single global keyword list?	Enhancement
21	Coercion of string to <b>real</b> does not make sense and is not defined, but it is currently allowed. The LRM should not allow coercing of a string to <b>real</b> . This should be treated as an error in the analog context.	BNF
22	The concept of associating variables based on which context they are assigned is apparently felt to be ambiguous. Can there be a better approach to identifying the domain of a variable in a mixed-signal context?	Enhancement
23	Can “,” (comma-comma) syntax be used for null arguments instead of “{}”? This can be useful for defining NULL numerator/denominator arguments in Laplace/Zi. Can this be explicitly allowed for these operators?	Enhancement
24	How will we handle parameter override values specified in <b>defparam</b> versus instantiation precedence? If the module is pre-compiled, the compiler would not know about the last override value. (Apparently there was a discussion on Verilog-D not to support <b>defparam</b> .)	Enhancement
25	Light Weight Conversions: connectmodule only addresses automatic conversion of signals passed through ports (structural). What about OOMRs where behavioral code asks for values not passed through ports? These are just probes, which do not need resolution. There should be a mechanism in the LRM for treating these light weight conversions.	Enhancement
26	VPI issue: Nature and disciplines should not use param_assign, instead there should be a new object called attr_assign	Ambiguity
27	Support break/continue statement in behavioral syntax to break out of loops.	Enhancement
28	Indexing of Named vector branches: What should be the index of a vector branch declared between two vector nodes:  <pre>electrical [1:2] a; electrical [0:1] b; branch (a,b) br1 [1:2]; branch (a,b) br2; //??</pre> Should br2 default to [0:1]?	BNF
30	Currently, the digital syntax does not allow register declaration in named blocks mentioned in an @(initial) or @(always) block. Register and net declarations should be allowed as part of these named blocks	Enhancement
32	Events inside loop statements: Events are used inside loops in references through examples (Section 5.2, dac), though this is disallowed as per the grammar.	Ambiguity
33	Accessing discipline attributes (both digital and analog) to be supported in the language.	Enhancement
34	Discipline name “logic” in disciplines.vams conflicts with keyword in SystemVerilog for a variable type <b>logic</b> .	BNF
35	The LRM should conform to IEEE Standard Style Guide for usage of "may," "shall," and "can."	BNF

Item	Description/Issue	Category
36	Issues with system tasks and system functions: <b>\$bound_step</b> and <b>\$discontinuity</b> are listed in Annex A BNF as functions and called functions in Section 10, but they have no return value; Some system functions missing from BNF ( <b>\$fopen</b> , <b>\$fclose</b> ); System tasks are not listed explicitly in Annex A BNF.	BNF
37	<b>\$stable_model</b> should support higher-order interpolation methods	Enhancement

# Annex H

## Glossary

### Glossary of Terms

#### A

##### AMS

See also, *Verilog-AMS*.

#### B

##### behavioral description

A mathematical mapping of inputs to outputs for a module, including intermediate variables and control flow.

##### behavioral model

A version of a module with a unique set of parameters designed to model a specific component.

##### block

A level within the behavioral description of a module, delimited by **begin** and **end**.

##### branch

A relationship between two nodes and their attached quantities within the behavioral description of a module. Each branch has two quantities, a value and a flow, with a reference direction for each.

#### C

##### compact model

A behavioral model or description of a semiconductor device.

**component**

A fundamental unit within a system which encapsulates behavior and/or structure. Modules and models can represent a single component or a subcircuit with many components.

**constitutive relationships**

The essential relationships (*expressions* and *statements*) between the outputs of a module and its inputs and parameters, which define the nature of the module. These relationships constitute a behavioral description.

**control flow**

The conditional and iterative statements controlling the behavior of a module. These statements evaluate arbitrary variables (counters, flags, and tokens) to control the operation of different sections of a behavioral description.

**child module**

A module instantiated inside another, “parent” module. A complete definition of the child module needs to be defined somewhere. A child module is also known as *submodule* or *instantiated module*.

**F**

**flow**

One of the two fundamental quantities used to simulate the behavior of a system. In electrical systems, the flow is the current.

**I**

**instance**

Any named occurrence of an component created from a module definition. One module can occur in multiple instances.

**instantiation**

The process of creating an instance from a module definition or simulator primitive and defining the connectivity and parameters of that instance. (Placing the instance in the circuit or system.)

**K****Kirchhoff's Laws**

The physical laws defining the interconnection relationships of nodes, branches, values, and flows. They specify a conservation of flow in and out of a node and a conservation of value around a loop of branches.

**L****level**

One block within a behavioral description, delimited by a pair of matching keywords such as **begin-end** or **discipline-endsdiscipline**.

**M****model**

A named instance with a unique group of parameters specifying the behavior of one particular version of a module. Models can be used to instantiate elements with parametric specifications different from those in the original module definition.

**module**

A definition of the interfaces and behavior of a component.

**N****nesting level**

One block within a behavioral description, delimited by a pair of matching keywords such as **begin-end** or **discipline-endsdiscipline**.

**node**

A connection point in the system, with access functions for potential and/or flow through an underlying discipline.

**node declaration**

The statement in a module definition identifying the names of the nets associated with the module ports or local to the module. A net declaration also identifies the discipline of the net, which in turn identifies the access functions.

## NR method

Newton-Raphson method. A generalized method for solving systems of nonlinear algebraic equations by breaking them into a series of many small linear operations ideally suited for computer processing.

## P

### parameter

A constant for characterizing the behavior of an instance of a module. Parameters are defined in the first section of a module, the *module interface declarations*, and can be specified each time a module is called in a netlist instance statement.

### parameter declaration

The statement in a module definition which defines the parameters of that module.

### port

An external connection point for a module (also known as a *terminal*).

### potential

One of the two fundamental quantities used to simulate the behavior of a system. In electrical systems, the potential is the voltage.

### primitive

A basic component defined entirely in terms of behavior, without reference to any other primitives. A primitive is the smallest and simplest portion of a simulated circuit or system.

### probe

A branch in a circuit (or system), which does not alter its behavior, but lets the simulator read out the potential or flow at that point.

## R

### reference direction

A convention for determining whether the value of a node, the flow through a branch, the value across a branch, or the flow in or out of a terminal, is positive or negative.

**reference node**

The global node (which equals zero (0)) against whose potentials all node values are measured. Nets declared as `ground` shall be bound to the reference node.

**run time binding**

The conditional introduction and removal of value and flow sources during a simulation. A value source can replace a flow source and vice-versa. Binding a source to a specific node or branch prevents it from going into an unknown state.

**S****scope**

The current nesting level of a block statement, which includes all lines of code within one set of braces in a module definition.

**structural definitions**

Instantiating modules inside other modules through the use of module definitions and declarations to create a hierarchical structure in the module's behavioral description.

**T****terminal**

See also, *port*.

**V****Verilog-A**

A subset of Verilog-AMS detailing the analog version of Verilog HDL (see Annex C). This is a language for the behavioral description of continuous-time systems, which uses a syntax similar to the *IEEE 1364-2001 Verilog HDL* specification.

**Verilog-AMS**

Mixed-signal version of Verilog HDL. A language for the behavioral description of continuous-time and discrete-time systems based on the *IEEE 1364-2001 Verilog HDL* specification.

