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2019-11-28	R19-11	AUTOSAR Release Management	• No content changes • Changed Document Status from Final to published

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2018-10-31	4.4.0	AUTOSAR Release Management	• Updated the range and resolution of requirements SWS_EFX_00220,SWS_EFX_00223,SWS_EFX_00226,SWS_EFX_00229,SWS_EFX_00232,SWS_EFX_00235,SWS_EFX_00240,SWS_EFX_00243,SWS_EFX_00246,SWS_EFX_00250,SWS_EFX_00253,SWS_EFX_00256
2017-12-08	4.3.1	AUTOSAR Release Management	• A note has been added in Section 8.1 of EFX specification to provide clarity in usage of mnemonic for Boolean data types. • The data type for Boolean has been updated in the UML of SWS_Efx_00355 • Inclusion of Pointer to Constant (P2CONST) for SWS_Efx_00355, SWS_Efx_00309, SWS_Efx_00307 & SWS_Efx_00193 and proper categorization of Parameters as InOut for SWS_Efx_00376
2016-11-30	4.3.0	AUTOSAR Release Management	• Updated the correct reference to SRS_BSW_General (SRS_BSW_00437) & (SRS_BSW_00448) for SWS_Efx_00810 & SWS_Efx_00822 requirements • Updated EFX document to support MISRA 2012 standard. (Removed redundant statements in SWS_Efx_00809 which already exist in SWS_BSW document and SWS_SRS document) • Updated SWS_Efx_00275 & SWS_Efx_00276 to provide more clarity on resolution of parameters • Updated SWS_Efx_00278 & SWS_Efx_00279 to provide more clarity on rounding and minimum value of Param_cpcst->SlopeXXX_u32 * dT_s32. Provided the correct IT number • Updated the section 8.5.3.1 for Structure definitions for controller routines • Updated SWS_Efx_00240, SWS_Efx_00243, SWS_Efx_00246, SWS_Efx_00250, SWS_Efx_00253 & SWS_Efx_

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			00256 to correct the case sensitivity for the function name • Section 2 has been revisited to update Default Error Tracer instead of Development Error tracer • Removal of Efx_ISetParam from BSW uml model which is obsolete • Removed the duplicated trace environments for SWS_Efx_00520 & SWS_Efx_00525 • Removed the requirements that are marked as Deprecated. (8.5.1.2 Second computation, SWS_Efx_00009 - SWS_Efx_00011, SWS_Efx_00041 - SWS_Efx_00043, SWS_Efx_00295 - SWS_Efx_00302, SWS_Efx_00347 - SWS_Efx_00354, SWS_Efx_00345, SWS_Efx_00460, SWS_Efx_00461 & 8.5.14 Efx_DeadTime)
2015-07-31	4.2.2	AUTOSAR Release Management	• Updated the requirement ID for SWS_Efx_00033 as per the convention • Updated requirement ID SWS_Efx_00436 (UML) for OutTypeMn as per the standard convention • Updated SWS_Efx_00001 for naming convention under Section 5.1, File Structure • Updated SWS_Efx_00365 to correct the data type of input parameters
2014-10-31	4.2.1	AUTOSAR Release Management	• New Variants for SWS_Efx_00412 (0xE2 - 0xE9) • Note has been added for SWS_Efx_00053, SWS_Efx_00072 & Section 8.5.3.1 • A statement has been added to clarify the formula used for Hypotenuse function just below the section 8.5.9 • A statement has been added to provide more clarity on the formula mentioned in SWS_Efx_00451

			• Updated usage of const in a consistent manner in EFX document. (SWS_Efx_00050, SWS_Efx_00067, SWS_Efx_00085, SWS_Efx_00519, SWS_Efx_00107, SWS_Efx_00122, SWS_Efx_00146, SWS_Efx_00172, SWS_Efx_00205, SWS_Efx_00379 & SWS_Efx_00404) • Formula for TeQ_<size> has been corrected in section 8.5.3.1 and font has been updated for SWS_Efx_00071 • Condition check included for SWS_Efx_00053, SWS_Efx_00072 & Section 8.5.3.1 and corrected for SWS_Efx_00054, SWS_Efx_00073 & SWS_Efx_00504. Formula updated for SWS_Efx_00073 • Updated rounding for SWS_Efx_00071, SWS_Efx_00091, SWS_Efx_00502, SWS_Efx_00151 & SWS_Efx_00156 • Service ID[hex] for SWS_Efx_00405, SWS_Efx_00410 & SWS_Efx_00412 • Input & Output range has been modified for SWS_Efx_00187 • Statement on rounding was updated for SWS_Efx_00441 • Comment for structure element “n“ has been updated for SWS_Efx_00204 & SWS_Efx_00836 • Data type of “n“ has been modified for SWS_Efx_00204
2014-03-31	4.1.3	AUTOSAR Release Management	• Modified: Rounding mechanism was updated for HpFilter, Average, Array_Average & MovingAverage functions • Added: A note below SWS_Efx_00307 for Efx_RampGetSwitchPos function

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2013-10-31	4.1.2	AUTOSAR Release Management	• Deprecated: Efx_DeadTime function • Removed: Requirements for Efx_ SlewRate, Efx_RampCalc and Efx_ RampCalcJump functions • Added: SWS_Efx_00837 for Efx_ RampCalc function • Modified: Descriptions of Efx_RampCalc and Efx_RampSetParam • Modified: Requirements for Efx_ RampCalc and Efx_RampCalcJump functions • Modified: Syntax for variants of Efx_ SlewRate, Efx_Div and Efx_ MovingAverage functions • Modified: Resolution of the in-parameter for Efx_Arcsin and Efx_Arccos functions • Name “underflow“ to “negative overflow“ throughout the document • Editorial changes
2013-03-15	4.1.1	AUTOSAR Administration	• Added 8-bit and 16-bit variants for Hysteresis functions • Formulae modified for Hypotenuse functions • Second computation First-order low-pass filter functions are deprecated • Inequalities are corrected for Efx_ HystLeftRight, Efx_HystDeltaRight, Efx_ HystCenterHalfDelta functions • Description and requirements are modified for Efx_Div, Efx_Debounce, Efx_HystLeftDelta, Efx_SortAscend, Efx_SortDescend, Efx_EdgeBipol, Efx_ Hysteresis, Efx_MovingAverage functions • Description of the in-parameter corrected for Efx_DebounceSetParam, Efx_Debounce functions • Physical range of ’fac’ parameter is modified in LpFilter First computation

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			△ • Renamed RS_FlipFlop function for removing the post-fixes • Added SWS_Efx_00823 for Integral promotion • Modified syntax for Efx_Gt, Efx_ Debounce functions • Corrected for 'DependencyOnArtifact'
2011-12-22	4.0.3	AUTOSAR Administration	• Initialization functionality introduced for 'Counter Routines' • Interface for Efx_CtrlSetLimit corrected • Efx_MovingAverage routine interface corrected • Efx_RampCalcSwitch routine definition and requirements updated for correct behavior' • Interface for Efx_Debounce_u8_u8 routine updated • Updated parameter sequences for DT1 and PI controller routines. • Name revised for Efx_PCalc routine • Description correct for Efx_ DebounceParam_Type and Efx_ DebounceState_Type • Interface table corrected for Efx_Div routine • Interface table corrected for Efx_ MedianSort routine • Error classification support and definition removed as DET call not supported by library • Configuration parameter description / support removed for XXX_ GetVersionInfo routine. • XXX_GetVersionInfo routine name corrected

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2010-09-30	3.1.5	AUTOSAR Administration	• Introduction of additional LIMITED Functions for controllers • Ramp functions optimised for effective usage • Separation of DT1 Type 1 and Type 2 Controller functions • Introduction of additional approximative function for calculation of TeQ
2010-02-02	3.1.4	AUTOSAR Administration	• Initial Release

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Table of Contents

1 Introduction and functional overview 14
2 Acronyms and Abbreviations 16
3 Related documentation 17
3.1 Input documents & related standards and norms . . . 17
3.2 Related specification . . . 17
4 Constraints and assumptions 18
4.1 Limitations . . . 18
4.2 Applicability to car domains . . . 18
5 Dependencies to other modules 19
5.1 File structure . . . 19
6 Requirements Tracing 20
7 Functional specification 21
7.1 Error Classification . . . 21
7.1.1 Development Errors . . . 21
7.1.2 Runtime Errors . . . 21
7.1.3 Production Errors . . . 21
7.2 Initialization and shutdown . . . 21
7.3 Using Library API . . . 21
7.4 library implementation . . . 22
7.5 Comment about rounding . . . 23
7.6 Comment about routines optimized for target . . . 23
8 API specification 24
8.1 Imported types . . . 24
8.2 Type definitions . . . 25
8.3 Function definitions . . . 26
8.3.1 First-order low-pass filter . . . 26
8.3.1.1 First computation . . . 26
8.3.1.2 Third computation . . . 28
8.3.2 First-order High-pass filter . . . 29
8.3.3 Controller routines . . . 35
8.3.3.1 Structure definitions for controller routines . . . 35
8.3.3.2 Proportional Controller . . . 40
8.3.3.3 Proportional controller with first order time constant . . . 42
8.3.3.4 Differential component with time delay : DT1 . . . 48
8.3.3.5 Proportional and Differential controller . . . 54
8.3.3.6 Integral component . . . 59
8.3.3.7 Proportional and Integral controller . . . 63
8.3.3.8 Proportional, Integral and Differential controller . . . 69

8.3.4 Square root . . . 75
8.3.5 Exponential . . . 78
8.3.6 Average . . . 78
8.3.7 Array Average . . . 79
8.3.8 Moving Average . . . 80
8.3.9 Hypotenuse . . . 82
8.3.10 Trigonometric functions . . . 84
8.3.10.1 Sine function . . . 84
8.3.10.2 Cosine function . . . 85
8.3.10.3 Inverse Sine function . . . 87
8.3.10.4 Inverse cosine function . . . 88
8.3.11 Rate limiter . . . 90
8.3.12 Ramp routines . . . 91
8.3.12.1 Ramp routine . . . 93
8.3.12.2 Ramp Initialisation . . . 94
8.3.12.3 Ramp Set Slope . . . 95
8.3.12.4 Ramp out routines . . . 96
8.3.12.5 Ramp Jump routine . . . 96
8.3.12.6 Ramp switch routine . . . 97
8.3.12.7 Get Ramp Switch position . . . 98
8.3.12.8 Check Ramp Activity . . . 99
8.3.13 Hysteresis routines . . . 100
8.3.13.1 Hysteresis . . . 100
8.3.13.2 Hysteresis center half delta . . . 101
8.3.13.3 Hysteresis left right . . . 102
8.3.13.4 Hysteresis delta right . . . 103
8.3.13.5 Hysteresis left delta . . . 104
8.3.14 Debounce routines . . . 105
8.3.14.1 Efx_Debounce . . . 105
8.3.14.2 Efx_DebounceInit . . . 107
8.3.14.3 Efx_DebounceSetparam . . . 108
8.3.15 Ascending Sort Routine . . . 108
8.3.16 Descending Sort Routine . . . 109
8.3.17 Median sort routine . . . 110
8.3.18 Edge detection routines . . . 111
8.3.18.1 Edge bipol detection . . . 111
8.3.18.2 Edge falling detection . . . 112
8.3.18.3 Edge rising detection . . . 113
8.3.19 Interval routines . . . 113
8.3.19.1 Interval Closed . . . 113
8.3.19.2 Interval Open . . . 114
8.3.19.3 Interval Left Open . . . 115
8.3.19.4 Interval Right Open . . . 116

8.3.20 Counter routines . . . 116
8.3.21 Flip-Flop routine . . . 118
8.3.22 Limiter routines . . . 119
8.3.23 64 bits functions . . . 120
8.3.23.1 General requirements . . . 120
8.3.23.2 Absolute value . . . 121
8.3.23.3 Additions . . . 121
8.3.23.4 Subtractions . . . 122
8.3.23.5 Multiplications . . . 123
8.3.23.6 Division . . . 124
8.3.23.7 Modulo . . . 125
8.3.23.8 Signum Function . . . 126
8.4 Scheduled functions . . . 126
8.5 Expected interfaces . . . 126
8.5.1 Mandatory Interfaces . . . 127
8.5.2 Optional Interfaces . . . 127
8.5.3 Configurable interfaces . . . 127
9 Sequence diagrams 128
10 Configuration specification 129
10.1 How to read this chapter . . . 129
10.2 Containers and configuration parameters . . . 129
10.3 Published Information . . . 129
A Not applicable requirements 130
B Change history of AUTOSAR traceable items 131
B.1 Traceable item history of this document according to AUTOSAR Release R23-11 . . . 131
B.1.1 Added Specification Items in R23-11 . . . 131
B.1.2 Changed Specification Items in R23-11 . . . 131
B.1.3 Deleted Specification Items in R23-11 . . . 131
B.2 Traceable item history of this document according to AUTOSAR Release R24-11 . . . 131
B.2.1 Added Specification Items in R24-11 . . . 131
B.2.2 Changed Specification Items in R24-11 . . . 131
B.2.3 Deleted Specification Items in R24-11 . . . 131
B.3 Traceable item history of this document according to AUTOSAR Release R25-11 . . . 132
B.3.1 Added Specification Items in R25-11 . . . 132
B.3.2 Changed Specification Items in R25-11 . . . 132
B.3.3 Deleted Specification Items in R25-11 . . . 132
B.4 Traceable item history of this document according to AUTOSAR Release R26-11 . . . 132
B.4.1 Added Specification Items in R26-11 . . . 132

B.4.2 Changed Specification Items in R26-11 132
B.4.3 Deleted Specification Items in R26-11 132

1 Introduction and functional overview

AUTOSAR Library routines are the part of system services in AUTOSAR architecture and below figure shows position of AUTOSAR library in layered architecture.

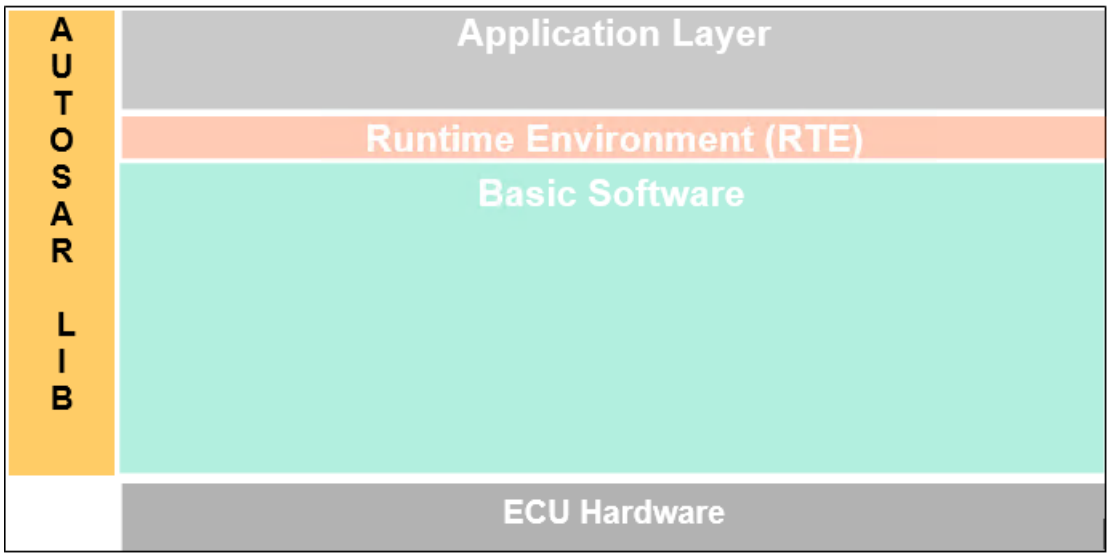


Figure 1.1

This specification specifies the functionality, API and the configuration of the AUTOSAR library dedicated to extended mathematical functions for fixed-point values.

This extended mathematical library (Efx) contains the following routines:

- Moving average
- First order high pass filter
- First order low-pass filter
- Controller routines
- Square root
- Exponential
- Average
- Array Average
- Moving Average
- Hypotenuse
- Trigonometric functions
- Rate limiter functions
- Ramp routines

- Hysteresis function
- Dead Time
- Debounce
- Ascending Sort Routine
- Descending Sort Routine
- Median Sort
- Edge detection routines
- Interval routines
- Counter routines
- Flip-Flop routine
- Limiter routines
- 64 bit functions

All routines are re-entrant and can be used by multiple runnables at the same time.

2 Acronyms and Abbreviations

The glossary below includes acronyms and abbreviations relevant to the EFX Library module that are not included in the [1, AUTOSAR glossary].

Abbreviation / Acronym:	Description:
Arcsin	Inverse Sine
Arccos	Inverse Cosine
Cos	Cosine
EFX	Extended Mathematical library - Fixed point
Hypot	Hypotenuse
HpFilter	High pass filter
LpFilterFac1	Low pass filter with a factor of 1 (included in [0, 1])
LpFilter	Low pass filter
Mn	Mnemonic
Lib	Library
Sqrt	Square root
Sin	Sine
u8	Mnemonic for the uint8, specified in AUTOSAR_SWS_ PlatformTypes
u16	Mnemonic for the uint16, specified in AUTOSAR_SWS_ PlatformTypes
u32	Mnemonic for the uint32, specified in AUTOSAR_SWS_ PlatformTypes
s8	Mnemonic for the sint8, specified in AUTOSAR_SWS_ PlatformTypes
s16	Mnemonic for the sint16, specified in AUTOSAR_SWS_ PlatformTypes
s32	Mnemonic for the sint32, specified in AUTOSAR_SWS_ PlatformTypes
s64	Mnemonic for the sint64, specified in AUTOSAR_SWS_ PlatformTypes
u64	Mnemonic for the uint64, specified in AUTOSAR_SWS_ PlatformTypes

Table 2.1: Acronyms and Abbreviations

3 Related documentation

3.1 Input documents & related standards and norms

[1] Glossary
AUTOSAR_FO_TR_Glossary

[2] ISO/IEC 9899:1990 Programming Language - C
https://www.iso.org

[3] General Specification of Basic Software Modules
AUTOSAR_CP_SWS_BSWGeneral

[4] General Requirements on Basic Software Modules
AUTOSAR_CP_RS_BSWGeneral

3.2 Related specification

AUTOSAR provides a General Specification on Basic Software modules [3, SWS BSW General], which is also valid for EFX Library.

Thus, the specification SWS BSW General shall be considered as additional and required specification for EFX Library.

4 Constraints and assumptions

4.1 Limitations

No limitations.

4.2 Applicability to car domains

No restrictions.

5 Dependencies to other modules

5.1 File structure

Implementation & grouping of routines with respect to C files is recommended as per below options and there is no restriction to follow the same.

Option 1 : <Name> can be function name providing one C file per function,

eg.: Efx_Pt1_s32.c etc.

Option 2 : <Name> can have common name of group of functions:

- 2.1 Group by object family:

  eg.:Efx_Pt1.c, Efx_Dt1.c, Efx_Pid.c

- 2.2 Group by routine family:

  eg.: Efx_Filter.c, Efx_Controller.c, Efx_Average.c etc.

- 2.3 Group by method family:

  eg.: Efx_Sin.c, Efx_Exp.c, Efx_Arcsin.c, etc.

- 2.4 Group by architecture:

  eg.: Efx_Slewrate16.c, Efx_Slewrate32.c

- 2.5 Group by other methods: (individual grouping allowed)

Option 3 : <Name> can be removed so that single C file shall contain all Efx functions, eg.: Efx.c.

Using above options gives certain flexibility of choosing suitable granularity with reduced number of C files. Linking only on-demand is also possible in case of some options.

6 Requirements Tracing

The following tables reference the requirements specified in [4] and links to the fulfillment of these. Please note that if column “Satisfied by” is empty for a specific requirement this means that this requirement is not fulfilled by this document.

Requirement	Description	Satisfied by
[SRS_BSW_00007]	All Basic SW Modules written in C language shall conform to the MISRA C 2025 Standard.	[SWS_Efx_00809]
[SRS_BSW_00304]	All AUTOSAR Basic Software Modules shall use only AUTOSAR data types instead of native C data types	[SWS_Efx_00812]
[SRS_BSW_00306]	AUTOSAR Basic Software Modules shall be compiler and platform independent	[SWS_Efx_00813]
[SRS_BSW_00374]	All Basic Software Modules shall provide a readable module vendor identification	[SWS_Efx_00814]
[SRS_BSW_00378]	AUTOSAR shall provide a boolean type	[SWS_Efx_00812]
[SRS_BSW_00379]	All software modules shall provide a module identifier in the header file and in the module XML description file.	[SWS_Efx_00814]
[SRS_BSW_00402]	Each module shall provide version information	[SWS_Efx_00814]
[SRS_BSW_00437]	Memory mapping shall provide the possibility to define RAM segments which are not to be initialized during startup	[SWS_Efx_00810]
[SRS_BSW_00448]	Module SWS shall not contain requirements from other modules	[SWS_Efx_00822]

Table 6.1: Requirements Tracing

7 Functional specification

7.1 Error Classification

[SWS_Efx_00821] ⌈Chapter [3, General Specification of Basic Software Modules] 7.2 *"Error Handling"* describes the error handling of the Basic Software in detail. Above all, it constitutes a classification scheme consisting of five error types which may occur in BSW modules.⌋

Based on this foundation, the following section specifies particular errors arranged in the respective subsections below.

7.1.1 Development Errors

There are no development errors.

7.1.2 Runtime Errors

There are no runtime errors.

7.1.3 Production Errors

There are no production errors.

7.2 Initialization and shutdown

[SWS_Efx_00800] ⌈Efx library shall not require initialization phase. A Library function may be called at the very first step of ECU initialization, e.g. even by the OS or EcuM, thus the library shall be ready.⌋

[SWS_Efx_00801] ⌈Efx library shall not require a shutdown operation phase.⌋

7.3 Using Library API

Efx API can be directly called from BSW modules or SWC. No port definition is required. It is a pure function call.

The statement 'Efx.h' shall be placed by the developer or an application code generator but not by the RTE generator

Using a library should be documented. if a BSW module or a SWC uses a Library, the developer should add an Implementation-DependencyOnArtifact in the BSW/SWC template.

minVersion and maxVersion parameters correspond to the supplier version. In case of AUTOSAR library, these parameters may be left empty because a SWC or BSW module may rely on a library behaviour, not on a supplier implementation. However, the SWC or BSW modules shall be compatible with the AUTOSAR platform where they are integrated.

7.4 library implementation

[SWS_Efx_00806] ⌈The Efx library shall be implemented in a way that the code can be shared among callers in different memory partitions.⌋

[SWS_Efx_00807] ⌈Usage of macros should be avoided. The function should be declared as function or inline function. Macro #define should not be used.⌋

[SWS_Efx_00808] ⌈A library function shall not call any BSW modules functions, e.g. the DET. A library function can call other library functions. Because a library function shall be re-entrant. But other BSW modules functions may not be re-entrant.⌋

[SWS_Efx_00809]

Upstream requirements: SRS_BSW_00007

⌈The library, written in C programming language, should conform to the MISRA C Standard.

Please refer to SWS_BSW_00115 for more details.⌋

[SWS_Efx_00810]

Upstream requirements: SRS_BSW_00437

⌈Each AUTOSAR library Module implementation <library>*.c and

<library>*.h shall map their code to memory sections using the AUTOSAR memory mapping mechanism.⌋

[SWS_Efx_00812]

Upstream requirements: SRS_BSW_00304, SRS_BSW_00378

⌈All AUTOSAR library Modules should use the AUTOSAR data types (integers, boolean) instead of native C data types, unless this library is clearly identified to be compliant only with a platform.⌋

[SWS_Efx_00813]

Upstream requirements: SRS_BSW_00306

⌈All AUTOSAR library Modules should avoid direct use of compiler and platform specific keyword, unless this library is clearly identified to be compliant only with a platform. eg. #pragma, typeof etc.⌋

[SWS_Efx_00823] ⌈Integral promotion has to be adhered to when implementing Efx services. Thus, to obtain maximal precision, intermediate results shall not be limited.⌋

7.5 Comment about rounding

Two types of rounding can be applied:

Results are 'rounded off', it means:

- -0.5 < X < 0.5 rounded to 0
- 0.5 <= X <= 1 rounded to 1
- -1 <= X <= -0.5 rounded to -1

Results are rounded towards zero.

- -1 < X < 1 rounded to 0

7.6 Comment about routines optimized for target

The routines described in this library may be realized as regular routines or inline functions. For ROM optimization purposes, it is recommended that the c routines be realized as individual source files so they may be linked in on an as-needed basis.

For example, depending on the target, two types of optimization can be done:

- Some routines can be replaced by another routine using integer promotion
- Some routines can be replaced by the combination of a limiting routine and a routine with a different signature.

8 API specification

8.1 Imported types

In this chapter, all types included from the following modules are listed:

[SWS_Efx_91001] Definition of imported datatypes of module Efx ⌈

Module	*Header File*	*Imported Type*
There are no imported types.		

⌋

It is observed that since the sizes of the integer types provided by the C language are implementation-defined, the range of values that may be represented within each of the integer types will vary between implementations.

The following mnemonic are used in the library routine names.

Size	Platform Type	Mnemonic	Range
unsigned 8-Bit	boolean	u8	[TRUE, FALSE]
signed 8-Bit	sint8	s8	[-128, 127]
signed 16-Bit	sint16	s16	[-32768, 32767]
signed 32-Bit	sint32	s32	[-2147483648, 2147483647]
signed 64-Bit	sint64	s64	[-9223372036854775808, 9223372036854775807]
unsigned 8-Bit	uint8	u8	[0, 255]
unsigned 16-Bit	uint16	u16	[0, 65535]
unsigned 32-Bit	uint32	u32	[0, 4294967295]
unsigned 64-Bit	uint64	u64	[0, 18446744073709551615]

Table 8.1: Base Types

As a convention in the rest of the document:

- mnemonics will be used in the name of the routines (using <InTypeMn1> that means Type Mnemonic for Input 1)
- the real type will be used in the description of the prototypes of the routines (using <InTypeMn1> or <OutType>).

Note:

The naming convention for the api's with boolean return type/parameter type is given as _u8 which shall be interpreted as _b. (Boolean)

If there is no boolean data type present in the return type/parameter type then _u8 shall be interpreted as _u8 only.

8.2 Type definitions

None

8.3 Function definitions

This chapter contains all APIs provided by the module.

This table describes the meaning of used symbols in below sections.

Symbols	Description
Yn	Actual output to calculate
Yn-1	Output value, one time step before
Xn	Actual input, given from the input
Xn-1	Input, one time step before
a, b0, b1	Filter dependent constants

Table 8.2: Symbols for mathematical function definitions

8.3.1 First-order low-pass filter

We consider a recursive first-order low-pass filter with a transfer function :

$$H(z) = \frac{b_1}{1 + a * z^{-1}}$$

Figure 8.1

The new return value (Yn) at any point of time can be calculated given the previous value (Yn-1), the current value (Xn) and a known constant (K). The formula to calculate the same is as follows:

Yn = Yn-1 + (Xn - Yn-1) * K

Where b1=K and a = K - 1

The filter is a convergent low-pass filter only if the average value K is included in [0,1]

8.3.1.1 First computation

[SWS_Efx_00005] Definition of API function Efx_LpFilterFac1_<InTypeMn><InTypeMn><InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_LpFilterFac1_<InTypeMn><InTypeMn><InTypeMn>_<OutTypeMn>

Syntax	`<OutType> Efx_LpFilterFac1_<InTypeMn><InTypeMn><InTypeMn>_<OutTypeMn>`
	`(`
	`  <InType> Yn-1,`
	`  <InType> Xn,`
	`  <InType> fac`
	`)`

Service ID [hex]	0x01 to 0x08

▽

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Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Yn-1	Old output value
	Xn	Current measured value
	fac	Factor value that represents the physical range: sint16: [-1, 0.999969482421875] uint8: [0, 0.9960937500000] uint16: [0, 0.9999847412109] uin32: [0, 0.9999999997671] Only physical value [0, 1] shall be used if the filter shall converge.
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result (Yn) of the calculation
Description	This service computes the output of a first order low-pass filter	
Available via	Efx.h	

⌋

[SWS_Efx_00006] ⌈Yn = Yn-1 + (((Xn - Yn-1) * fac) >> n)

Where 'n' is a shift that depends on the types used by the functions for the factor⌋

[SWS_Efx_00007] ⌈In order to converge all the time, the result is corrected for value saturation using the following logic:

If (Yn == Yn-1)

If (((Xn - Yn-1) * fac) > 0)

Yn ++

End If

Endif⌋

[SWS_Efx_00008] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax	Associated shift
0x01	sint16 Efx_LpFilterFac1_s16s16s16_ s16 (sint16, sint16, sint16)	15
0x02	sint16 Efx_LpFilterFac1_s16s16u16_ s16 (sint16, sint16, uint16)	16
0x03	sint32 Efx_LpFilterFac1_s32s32u16_ s32 (sint32, sint32, uint16)	16
0x04	uint16 Efx_LpFilterFac1_u16u16s16_ u16 (uint16, uint16, sint16)	15
0x05	uint16 Efx_LpFilterFac1_u16u16u16_ u16 (uint16, uint16, uint16)	16
0x06	uint8 Efx_LpFilterFac1_u8u8u8_u8 (uint8, uint8, uint8)	8
0x07	uint32 Efx_LpFilterFac1_u32u32u32_ u32 (uint32, uint32, uint32)	32
0x08	uint32 Efx_LpFilterFac1_u32u32u16_ u32 (uint32, uint32, uint16)	16

⌋

8.3.1.2 Third computation

[SWS_Efx_00012] Definition of API function Efx_LpFilter_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_LpFilter_<InTypeMn>_<OutTypeMn>	

Syntax	`<OutType> Efx_LpFilter_<InTypeMn>_<OutTypeMn> (`
	`  <InType> input,`
	`  <InType> old_output,`
	`  uint32 tau_const,`
	`  uint16 recurrence,`
	`  uint8 reset,`
	`  <InType> init_val,`
	`  uint8* started`
	`)`	

Service ID [hex]	0x0D and 0x0E	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	input	Input signal
	old_output	Previous value of the output value (filtered signal)
	tau_const	Parameter Tau of the filter : the time constant (second)
	recurrence	Delta time between two executions of the function
	reset	Flag to reset the filtered signal
	init_val	Initial value of the filter
Parameters (inout)	started	Pointer to the flag to detect the first call of the function
Parameters (out)	None	
Return value	<OutType>	Return value of the filter
Description	This service computes the first one order discrete filter	
Available via	Efx.h	

⌋

[SWS_Efx_00013] ⌈If (tau_const==0), then output = input⌋

[SWS_Efx_00014] ⌈If (*started==0), then output = init_val

This flag is used to indicate the filter state. *Started = 0, indicates that current function call is the first call of the function to trigger initialisation.⌋

[SWS_Efx_00015] ⌈This service computes the first one order discrete filter:⌋

$$output = old_output + (input - old_output) * \left(1 - \exp\left(\frac{-recurrence}{tau_const}\right)\right)$$

$$output = old_output * \exp\left(\frac{-recurrence}{tau_const}\right) + input * \left(1 - \exp\left(\frac{-recurrence}{tau_const}\right)\right)$$

Figure 8.2

Remark : the exponential functions can be computed with interpolations

[SWS_Efx_00016] ⌈if ((reset == 1) or (*started == 0)), then output = init_val⌋

[SWS_Efx_00017] ⌈if (*started == 0), then *started=1⌋

[SWS_Efx_00018] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x0D	uint32 Efx_LpFilter_u32_u32 (uint32, uint32, uint32, uint16, uint8, uint32, uint8*)
0x0E	sint32 Efx_LpFilter_s32_s32 (sint32, sint32, uint32, uint16, uint8, sint32, uint8 *)

⌋

[SWS_Efx_00020] ⌈input, old_output, and init_val must have the same resolution and the same physical unit.⌋

[SWS_Efx_00021] ⌈tau_const and recurrence must have the same resolution and the same physical unit⌋

It is not recommended to call Efx_LpFilter_<InTypeMn>_<OutTypeMn> under any condition. It must be called at each recurrence, even if it is not used, If the conditions are not fulfilled then output shall be frozen to the previous value all the time.

The parameter started has to be declared as private variable by the caller and shall be initialized to 0 (default init), because the function uses the previous values of this output (so the stack mustn't be used).

8.3.2 First-order High-pass filter

We consider a recursive first-order high-pass filter with a transfer function :

$$H(z) = \frac{b_0 * z + b_1}{z + a}$$

Figure 8.3

The new return value (Yn) at any point of time can be calculated given the previous value (Yn-1), the current input (Xn), the previous input (Xn-1) and a known constant (K). The formula to calculate the same is as follows:

Yn = Yn-1 - K * Yn-1 + (Xn - Xn-1)

Where b0 = 1, b1 = -1 and a=K -1

The filter is a convergent high-pass filter only if the factor value m is included in [0,1]

[SWS_Efx_00022] Definition of API function Efx_HpFilter_u8_s16 ⌈

Service Name	Efx_HpFilter_u8_s16	

Syntax	`sint16 Efx_HpFilter_u8_s16 (`
	`  sint16 Yn-1,`
	`  uint8 Xn,`
	`  uint8 Xn-1,`
	`  uint16 K`
	`)`	

Service ID [hex]	0x10	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Yn-1	Previous sint16 output Physical range: [-256 , 255.9921875] Resolution: $1/2^7$
	Xn	Present uint8 input Physical range: [0,255] Resolution: 1
	Xn-1	Previous uint8 input Physical range: [0,255] Resolution: 1
	K	Constant uint16 multiplying factor Physical range: [0,0.99998] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint16	Yn : Result of the calculation Physical range: [-256 , 255.9921875] Resolution: 1/2^7
Description	This service computes the output of a first order high-Pass filter	
Available via	Efx.h	

⌋

[SWS_Efx_00023] ⌈:

Yn = Yn-1 - (K * Yn-1 / 2^16) + (Xn - Xn-1)*2^7

The result is rounded towards zero.⌋

[SWS_Efx_00024] ⌈Return value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00025] ⌈A saturation correction for converging output to zero is applied to the result :

If ((Yn equals Yn-1) and (Yn-1 > 0))

decrement Yn by one

If ((Yn equals Yn-1) and (Yn-1 < 0))

increment Yn by one⌋

[SWS_Efx_00026] Definition of API function Efx_HpFilter_s8_s16 ⌈

Service Name	Efx_HpFilter_s8_s16	
Syntax	`sint16 Efx_HpFilter_s8_s16 ( sint16 Yn-1, sint8 Xn, sint8 Xn-1, uint16 K )`	
Service ID [hex]	0x11	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Yn-1	Previous sint16 output Physical range: [-256 , 255.9921875] Resolution: $1/2^7$
	Xn	Present sint8 input Physical range: [-128 , 127] Resolution: 1
	Xn-1	Previous sint8 input Physical range: [-128 , 127] Resolution: 1
	K	Constant uint16 multiplying factor Physical range: [0,0.99998] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint16	Yn : Result of the calculation Physical range: [-256 , 255.9921875] Resolution: 1/2^7
Description	This service computes the output of a first order high-Pass filter	
Available via	Efx.h	

⌋

[SWS_Efx_00027] ⌈Yn = Yn-1 - (K* Yn-1 /2^16) + (Xn - Xn-1)*2^7

The result is rounded towards zero.⌋

[SWS_Efx_00028] ⌈Return value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00029] ⌈A saturation correction for converging output to zero is applied to the result :

If ((Yn equals Yn-1) and (Yn-1 > 0))

decrement Yn by one

If ((Yn equals Yn-1) and (Yn-1 < 0))

increment Yn by one⌋

[SWS_Efx_00030] Definition of API function Efx_HpFilter_u16_s32 ⌈

Service Name	Efx_HpFilter_u16_s32	

Syntax	`sint32 Efx_HpFilter_u16_s32 (`
	`  sint32 Yn-1,`
	`  uint16 Xn,`
	`  uint16 Xn-1,`
	`  uint16 K`
	`)`	

Service ID [hex]	0x12	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Yn-1	Previous sint32 output Physical range: [-65536 , 65535.99996] Resolution: $1/2^{15}$
	Xn	Present uint16 input Physical range: [0,65535] Resolution: 1
	Xn-1	Previous uint16 input Physical range: [0,65535] Resolution: 1
	K	Constant uint16 multiplying factor Physical range: [0,0.99998] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Yn : Result of the calculation Physical range: [-65536 , 65535.99996] Resolution: 1/2^15
Description	This service computes the output of a first order high-Pass filter	
Available via	Efx.h	

⌋

[SWS_Efx_00031] ⌈Yn = Yn-1 - (K* Yn-1 /2^16) + (Xn - Xn-1)*2^15

The result is rounded towards zero.⌋

[SWS_Efx_00032] ⌈Return value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00033] ⌈A saturation correction for converging output to zero is applied to the result :

If ((Yn equals Yn-1) and (Yn-1 > 0))

decrement Yn by one

If ((Yn equals Yn-1) and (Yn-1 < 0))

increment Yn by one⌋

[SWS_Efx_00035] Definition of API function Efx_HpFilter_s16_s32 ⌈

Service Name	Efx_HpFilter_s16_s32	

Syntax	`sint32 Efx_HpFilter_s16_s32 (`
	`  sint32 Yn-1,`
	`  sint16 Xn,`
	`  sint16 Xn-1,`
	`  uint16 K`
	`)`	

Service ID [hex]	0x13	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Yn-1	Previous sint32 output Physical range: [-65536 , 65535.99996] Resolution: $1/2^{15}$
	Xn	Present sint16 input Physical range: [-32768,32767] Resolution: 1
	Xn-1	Previous sint16 input Physical range: [-32768,32767] Resolution: 1
	K	Constant uint16 multiplying factor Physical range: [0,0.99998] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Yn : Result of the calculation Physical range: [-65536 , 65535.99996] Resolution: 1/2ˆ31
Description	This service computes the output of a first order high-Pass filter	
Available via	Efx.h	

⌋

[SWS_Efx_00036] ⌈Yn = Yn-1- (K* Yn-1/2ˆ16) + (Xn- Xn-1)*2ˆ15

The result is rounded towards zero.⌋

[SWS_Efx_00037] ⌈Return value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00038] ⌈A saturation correction for converging output to zero is applied to the result :

If ((Yn equals Yn-1) and (Yn-1> 0))

decrement Ynby one

If ((Yn equals Yn-1) and (Yn-1< 0))

increment Yn by one⌋

8.3.3 Controller routines

Controller routines includes P, PT1, DT1, PD, I, PI, PID governors used in control system applications. For these controllers, the required parameters are derived using Laplace-Z transformation. The following parameters are required to calculate the new controller output yn and can be represented in the following equation.

Yn = a1 * Yn-1 + b0 * Xn + b1 * Xn-1 + b2 * Xn-2 + ... + bn-1 * X1 + bn * X0

In the equation, the following symbols are used

Symbols	Description
Yn	Actual output to calculate
Yn-1	Output value, one time step before
Xn	Actual input, given from the input
Xn-1	Input, one time step before
Xn-2	Input, two time steps before
X1	Input, n-1 time steps before
X0	Input, n time steps before
a1, b0, b1, b2, bn-1, bn	Controller dependent proportional parameters are used to describe the weight of the states.

Table 8.3: Symbols for controller routines

8.3.3.1 Structure definitions for controller routines

System parameters are separated from time or time equivalent parameters. The system parameters are grouped in controller dependent structures Efx_Param<controller>_Type, whereas the time (equivalent) parameters are assigned directly. Systems states are grouped in a structure Efx_State<controller>_Type except the actual input value Xn which is assigned directly.

The System parameters, used in the equations are given by:

K : Amplification factor, The amplification factor K shall have a resolution of 1/2^16.

T1 : Decay time constant.

T1rec is scaled by the factor 2^32.

T1rec is given by the equation: 2^32 / (10^6 * T1)

Tv : Lead time. Physical unit [sec] describes the Lead time.

Tv is expressed in us (micro seconds) and shall have a resolution of 1/(2^8 * 10^6)

Tv range = [0.003906 us, 8388607 us] dT, with respect to [Tv_min, Tv_max]

Tn : Follow-up time. Physical unit [sec] describes the Follow-up time.

Tn is expressed in us and have a resolution of 1/10^6.

Tn is given by a reciprocal value (Tnrec) to avoid a division in the implementation.

Tnrec is scaled by the factor 2^32.

Tnrec is given by the equation: 2^32 / (10^6 * Tn).

The time and time equivalent parameters in the equation / implementation are given by:

dT : Time step = sampling interval. dT is expressed in us (micro seconds) and shall have a resolution of 1/10^6.

Analogous to the abbreviations above, the following abbreviations are used in the implementation:

K_<size>, K_C : Amplification factor

T1rec_<size> : Reciprocal delay time constant = 1/ T1.

The result shall be Rounded towards Zero.

Tv _<size>, Tv_C : Lead time

Tnrec _<size>, Tnrec_C : Reciprocal follow-up time = 1/ Tn.

The result shall be Rounded towards Zero.

dT_<size> : Time step = sampling interval [10^(-6) seconds per increment of 1 data representation unit]

TeQ_<size> : Time equivalent, TeQ = exp (- dT/ T1).

Herein "<size>" denotes the size of the variable, e.g _s32 stand for a sint32 bit variable.

Note:

1. Tv & Tn cannot be negative

2. Dt should always be greater than zero.

Following C-structures are specially defined for the controller routines.

[SWS_Efx_00040] Definition of datatype Efx_StatePT1_Type ⌈

Name	Efx_StatePT1_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for PT1 controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00824] Definition of datatype Efx_StateDT1Typ1_Type ⌈

Name	Efx_StateDT1Typ1_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	X2	
	Type	sint32
	Comment	Input value, two time steps before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for DT1-Type1 controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00825] Definition of datatype Efx_StateDT1Typ2_Type ⌈

Name	Efx_StateDT1Typ2_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for DT1-Type2 controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00826] Definition of datatype Efx_StatePD_Type ⌈

Name	Efx_StatePD_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for PD controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00827] Definition of datatype Efx_ParamPD_Type ⌈

Name	Efx_ParamPD_Type	
Kind	Structure	
Elements	K_C	
	Type	sint32
	Comment	Amplification factor
	Tv_C	
	Type	sint32
	Comment	Lead time
Description	System and Time equivalent parameter Structure for PD controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00828] Definition of datatype Efx_StateI_Type ⌈

Name	Efx_StateI_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for I controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00829] Definition of datatype Efx_StatePI_Type ⌈

Name	Efx_StatePI_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for PI additive (*Type1 and Type 2*) controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00830] Definition of datatype Efx_ParamPI_Type ⌈

Name	Efx_ParamPI_Type	
Kind	Structure	
Elements	K_C	
	Type	sint32
	Comment	Amplification factor
	Tnrec_C	
	Type	sint32
	Comment	Reciprocal follow up time (1/Tn)
Description	System and Time equivalent parameter Structure for PI additive (*Type1 and Type 2*) controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00831] Definition of datatype Efx_StatePID_Type ⌈

Name	Efx_StatePID_Type	
Kind	Structure	
Elements	X1	
	Type	sint32
	Comment	Input value, one time step before
	X2	
	Type	sint32
	Comment	Input value, two time step before
	Y1	
	Type	sint32
	Comment	Output value, one time step before
Description	System State Structure for PID additive (*Type1 and Type 2*) controller routine	
Available via	Efx.h	

⌋

[SWS_Efx_00832] Definition of datatype Efx_ParamPID_Type ⌈

Name	Efx_ParamPID_Type	
Kind	Structure	
Elements	K_C	
	Type	sint32
	Comment	Amplification factor
	Tv_C	
	Type	sint32
	Comment	Lead time
	Tnrec_C	
	Type	sint32
	Comment	Reciprocal follow up time (1/Tn)
Description	System and Time equivalent parameter Structure for PID additive (*Type1 and Type 2*) controller routine	

▽

△

Available via	Efx.h

⌋

[SWS_Efx_00833] Definition of datatype Efx_Limits_Type ⌈

Name	Efx_Limits_Type	
Kind	Structure	
Elements	Min_C	
	Type	sint32
	Comment	Minimum limit value
	Max_C	
	Type	sint32
	Comment	Maximum limit value
Description	Controller limit value structure	
Available via	Efx.h	

⌋

8.3.3.2 Proportional Controller

Proportional component calculates Y(x) = Kp * X.

1. 'P' Controller

[SWS_Efx_00525] Definition of API function Efx_PCalc ⌈

Service Name	Efx_PCalc	
Syntax	`void Efx_PCalc ( sint32 X_s32, sint32* P_ps32, sint32 K_s32 )`	
Service ID [hex]	0x14	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	input value
	K_s32	Amplification factor (Quantized with $1/2^{16}$ per increment of 1 data representation unit)
Parameters (inout)	P_ps32	Pointer to the calculated state
Parameters (out)	None	
Return value	None	
Description	This routine computes differential equation Differential equation: Y = K * X	
Available via	Efx.h	

⌋

[SWS_Efx_00526] ⌈Calculated value *P_ps32 = (K_s32 * X_s32) >> 16⌋

[SWS_Efx_00527] ⌈Amplification factor is quantized with 1/2^16 per increment of 1 data representation unit⌋

1. Set 'P' State

This routine can be realised using inline function.

[SWS_Efx_00044] Definition of API function Efx_PSetState ⌈

Service Name	Efx_PSetState	
Syntax	`void Efx_PSetState ( sint32* P_s32, sint16 Y_s16 )`	
Service ID [hex]	0x21	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Y_s16	Input value
Parameters (inout)	P_s32	Pointer to the calculated state
Parameters (out)	None	
Return value	void	No return value
Description	The routine sets the internal state variables of a P element.	
Available via	Efx.h	

⌋

[SWS_Efx_00045] ⌈Output value *P_s32 = Y_s16 << 16⌋

[SWS_Efx_00046] ⌈The internal state of the P element is stored as (Y_s16 << 16)⌋

1. Get 'P' output

This routine can be realised using inline function.

[SWS_Efx_00047] Definition of API function Efx_POut_<OutTypeMn> ⌈

Service Name	Efx_POut_<OutTypeMn>	
Syntax	`<OutType> Efx_POut_<OutTypeMn> ( const sint32* P_ps32 )`	
Service ID [hex]	0x22 to 0x23	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	P_ps32	Pointer to the calculated state
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'P' controller output value
Description	This routine returns 'P' controllers output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00048] ⌈Output value = *P_ps32 >> 16⌋

[SWS_Efx_00049] ⌈Return value shall be saturated to boundary values of the return data type in case of negative or positive overflow.⌋

[SWS_Efx_00050] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x22	sint16 Efx_POut_s16(const sint32 *)
0x23	sint8 Efx_POut_s8(const sint32 *)

⌋

8.3.3.3 Proportional controller with first order time constant

This routine calculates proportional element with first order time constant

1. 'PT1' Controller

[SWS_Efx_00051] Definition of API function Efx_PT1Calc ⌈

Service Name	Efx_PT1Calc	
Syntax	`void Efx_PT1Calc ( sint32 X_s32, Efx_StatePT1_Type* State_cpst, sint32 K_s32, sint32 TeQ_s32 )`	
Service ID [hex]	0x2A	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the PT1 element

▽

△

	K_s32	Amplification factor
	TeQ_s32	Time equivalent
Parameters (inout)	State_cpst	Pointer to PT1 state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes PT1 controller output value using below difference equation Yn = exp(-d T/T1) * Yn-1+ K(1 - exp(-dT/T1)) * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00052] ⌈This equation derives implementation :

Output_value = (TeQ_s32 * State_cpst->Y1) + K_s32 * (1 - TeQ_s32) * State_cpst->X1

where TeQ_s32 = exp (-dT/T1)⌋

[SWS_Efx_00053] ⌈Efx_CalcTeQ_s32 shall be used for calculation of time equivalent parameter TeQ_s32 only if T1 > 0.⌋

Note: If T1 = 0, a PT1 controller behaves like a P controller. In this case, usage of Efx_CalcTeq_s32 should be avoided and Teq value should be passed as 0.

[SWS_Efx_00054] ⌈If (Teq = 0) then PT1 controller follows Input value,

State_cpst->Y1 = k_s32 * State_cpst->X1⌋

[SWS_Efx_00055] ⌈calculated Output_value and current input value shall be stored to State_cpst->Y1 and State_cpst->X1 respectively.

State_cpst->Y1 = Output_value

State_cpst->X1 = X_s32⌋

1. ’PT1’ Controller - Type1

[SWS_Efx_00531] Definition of API function Efx_PT1Typ1Calc ⌈

Service Name	Efx_PT1Typ1Calc	

Syntax	`void Efx_PT1Typ1Calc (`
	`  sint32 X_s32,`
	`  Efx_StatePT1_Type* State_cpst,`
	`  sint32 K_s32,`
	`  sint32 TeQ_s32`
	`)`	

Service ID [hex]	0x38	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the PT1 element
	K_s32	Amplification factor

▽

△

	TeQ_s32	Time equivalent
Parameters (inout)	State_cpst	Pointer to PT1 state structure
Parameters (out)	None	
Return value	None	
Description	This routine computes PT1 controller output value using below difference equation Yn = exp(-d T/T1) * Yn-1+ K(1 - exp(-dT/T1)) * Xn	
Available via	Efx.h	

⌋

[SWS_Efx_00532] ⌈This equation derives implementation :

Output_value = (TeQ_s32 * State_cpst->Y1) + K_s32 * (1 - TeQ_s32) * State_cpst->X1

where TeQ_s32 = exp (-dT/T1)⌋

[SWS_Efx_00533] ⌈Efx_CalcTeQ_s32 shall be used for calculation of time equivalent parameter TeQ_s32 only if T1 > 0.⌋

Note: If T1 = 0, a PT1 controller behaves like a P controller. In this case, usage of Efx_ CalcTeq_s32 should be avoided and Teq value should be passed as 0.

[SWS_Efx_00534] ⌈If (Teq = 0) then PT1 controller follows Input value,

State_cpst->Y1 = k_s32 * State_cpst->X1⌋

[SWS_Efx_00535] ⌈calculated Output_value and current input value shall be stored to State_cpst->Y1 and State_cpst->X1 respectively.

State_cpst->Y1 = Output_value

State_cpst->X1 = X_s32⌋

1. ’PT1’ Set State Value

This routine can be realised using inline function.

[SWS_Efx_00056] Definition of API function Efx_PT1SetState ⌈

Service Name	Efx_PT1SetState	
Syntax	`void Efx_PT1SetState ( Efx_StatePT1_Type* State_cpst, sint32 X1_s32, sint16 Y1_s16 )`	
Service ID [hex]	0x2B	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for input state
	Y1_s16	Initial value for output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to PT1 state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a PT1 element.	
Available via	Efx.h	

⌋

[SWS_Efx_00057] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00058] ⌈The internal state of the PT1 element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00059] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32⌋

1. Calculate time equivalent Value

This routine can be realised using inline function.

[SWS_Efx_00060] Definition of API function Efx_CalcTeQ_s32 ⌈

Service Name	Efx_CalcTeQ_s32	
Syntax	`sint32 Efx_CalcTeQ_s32 ( sint32 T1rec_s32, sint32 dT_s32 )`	
Service ID [hex]	0x2C	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	T1rec_s32	Reciprocal delay time
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Time Equivalent TeQ

▽

△

Description	This routine calculates time equivalent factor
Available via	Efx.h

⌋

[SWS_Efx_00061] ⌈TeQ = exp(-T1rec_s32 * dT_s32)⌋

[SWS_Efx_00062] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Calculate an approximate time equivalent Value

This routine calculates approximate time equivalent and can be realised using inline function.

[SWS_Efx_00450] Definition of API function Efx_CalcTeQApp_s32 ⌈

Service Name	Efx_CalcTeQApp_s32	
Syntax	`sint32 Efx_CalcTeQApp_s32 ( sint32 T1rec_s32, sint32 dT_s32 )`	
Service ID [hex]	0x29	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	T1rec_s32	Reciprocal delay time
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Time Equivalent TeQ (Approximate)
Description	This routine calculates time equivalent factor	
Available via	Efx.h	

⌋

[SWS_Efx_00451] ⌈TeQApp = 1 - (T1rec_s32 * dT_s32)

TeQApp is factorised by 2^16

This approximation is valid only when the product of the physical values of T1rec_s32 and dt_s32 is less than 1. i.e, (T1rec_s32 * dT_s32) < 1⌋

[SWS_Efx_00452] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Get 'PT1' output

This routine can be realised using inline function.

[SWS_Efx_00063] Definition of API function Efx_PT1Out_<OutTypeMn> ⌈

Service Name	Efx_PT1Out_<OutTypeMn>	
Syntax	`<OutType> Efx_PT1Out_<OutTypeMn> ( const Efx_StatePT1_Type* State_cpst )`	
Service ID [hex]	0x2D to 0x2E	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to constant state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'PT1' controller output value
Description	This routine returns 'PT1' controllers output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00064] ⌈Output value = State_cpst->Y1_s32 >> 16⌋

[SWS_Efx_00065] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00066] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00067] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x2D	sint16 Efx_PT1Out_s16(const Efx_StatePT1_Type *)
0x2E	sint8 Efx_PT1Out_s8(const Efx_StatePT1_Type *)

⌋

8.3.3.4 Differential component with time delay : DT1

This routine calculates differential element with first order time constant.

Routine Efx_CalcTeQ_s32, given in [SWS_Efx_00060], shall be used for Efx_DT1_s32 function to calculate the time equivalent TeQ.

1. 'DT1' Controller - Type1

[SWS_Efx_00070] Definition of API function Efx_DT1Typ1Calc ⌈

Service Name	Efx_DT1Typ1Calc	

Syntax	`void Efx_DT1Typ1Calc (`
	`  sint32 X_s32,`
	`  Efx_StateDT1Typ1_Type* State_cpst,`
	`  sint32 K_s32,`
	`  sint32 TeQ_s32,`
	`  sint32 dT_s32`
	`)`	

Service ID [hex]	0x30	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the DT1 controller
	K_s32	Amplification factor
	TeQ_s32	Time equivalent
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes DT1 controller output value using differential equation, Yn= exp(-dT/T1) * Yn-1+ K * (1- exp(-dT/T1)) * ((Xn-1 - Xn-2) / dT)	
Available via	Efx.h	

⌋

[SWS_Efx_00071] ⌈This equation derives implementation :

Output_value = (TeQ * State_cpst->Y1) + K_s32 * (1 - TeQ) * ((State_cpst->X1 - State_cpst->X2) / dT)

where TeQ = exp(-dT/T1)

The result shall be Rounded towards Zero.⌋

[SWS_Efx_00072] ⌈Efx_CalcTeQ_s32 shall be used for calculation of time equivalent parameter TeQ_s32 only if T1 > 0.⌋

Note: If T1 = 0, a DT1 controller behaves like a D controller. In this case, usage of Efx_CalcTeq_s32 should be avoided and Teq value should be passed as 0.

[SWS_Efx_00073] ⌈If (Teq = 0), then DT1 controller follows Input value,

Output_value = k_s32 * (State_cpst->X1 - State_cpst->X2) / dT.⌋

[SWS_Efx_00074] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00075] ⌈Old input value State->cpst->X1 shall be stored to State_cpst->X2.

State_cpst->X2 = State_cpst->X1

Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00076] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'DT1' Controller - Type2

[SWS_Efx_00501] Definition of API function Efx_DT1Typ2Calc ⌈

Service Name	Efx_DT1Typ2Calc	
Syntax	`void Efx_DT1Typ2Calc ( sint32 X_s32, Efx_StateDT1Typ2_Type* State_cpst, sint32 K_s32, sint32 TeQ_s32, sint32 dT_s32 )`	
Service ID [hex]	0x2F	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the DT1 controller
	K_s32	Amplification factor
	TeQ_s32	Time equivalent
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes DT1 controller output value using differential equation, Yn= exp(-dT/T1) * Yn-1+ K * (1- exp(-dT/T1)) * ((Xn - Xn-1) / dT)	
Available via	Efx.h	

⌋

[SWS_Efx_00502] ⌈This equation derives implementation :

Output_value = (TeQ * State_cpst->Y1) + K_s32 * (1 - TeQ) * ((X_s32 - State_cpst->X1) / dT)

where TeQ = exp(-dT/T1)

The result shall be Rounded towards Zero.⌋

[SWS_Efx_00503] ⌈Efx_CalcTeQ_s32 shall be used for calculation of time equivalent parameter TeQ_s32.⌋

[SWS_Efx_00504] ⌈If (Teq = 0), then DT1 controller follows Input value,

Output_value = k_s32 * (X_s32 - State_cpst->X1) / dT⌋

[SWS_Efx_00505] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00506] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00507] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Set 'DT1' State Value - Type1

This routine can be realised using inline function.

[SWS_Efx_00077] Definition of API function Efx_DT1Typ1SetState ⌈

Service Name	Efx_DT1Typ1SetState	
Syntax	`void Efx_DT1Typ1SetState ( Efx_StateDT1Typ1_Type* State_cpst, sint32 X1_s32, sint32 X2_s32, sint16 Y1_s16 )`	
Service ID [hex]	0x31	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for the input state X1
	X2_s32	Initial value for the input state X2
	Y1_s16	Initial value for the output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a DT1 element.	
Available via	Efx.h	

⌋

[SWS_Efx_00078] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00079] ⌈The internal state of the DT1 element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00080] ⌈Initialisation of input state variables X1 and X2.

State_cpst->X1 = X1_s32

State_cpst->X2 = X2_s32⌋

1. Set 'DT1' State Value - Type2

This routine can be realised using inline function.

[SWS_Efx_00510] Definition of API function Efx_DT1Typ2SetState ⌈

Service Name	Efx_DT1Typ2SetState	

Syntax	`void Efx_DT1Typ2SetState (`
	`  Efx_StateDT1Typ2_Type* State_cpst,`
	`  sint32 X1_s32,`
	`  sint16 Y1_s16`
	`)`	

Service ID [hex]	0x32	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for the input state
	Y1_s16	Initial value for the output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a DT1 element.	
Available via	Efx.h	

⌋

[SWS_Efx_00511] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00512] ⌈The internal state of the DT1 element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00513] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32⌋

1. Get 'DT1' output - Type1

This routine can be realised using inline function.

[SWS_Efx_00081] Definition of API function Efx_DT1Typ1Out_<OutTypeMn> ⌈

Service Name	Efx_DT1Typ1Out_<OutTypeMn>	

Syntax	`<OutType> Efx_DT1Typ1Out_<OutTypeMn> (`
	`  const Efx_StateDT1Typ1_Type* State_cpst`
	`)`	

Service ID [hex]	0x33 to 0x34	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'DT1' controller output value
Description	This routine returns 'DT1' controller's output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00082] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00083] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00084] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00085] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x33	sint16 Efx_DT1Typ1Out_s16(const Efx_StateDT1Typ1_Type *)
0x34	sint8 Efx_DT1Typ1Out_s8(const Efx_StateDT1Typ1_Type *)

⌋

1. Get 'DT1' output - Type2

This routine can be realised using inline function.

[SWS_Efx_00515] Definition of API function Efx_DT1Typ2Out_<OutTypeMn> ⌈

Service Name	Efx_DT1Typ2Out_<OutTypeMn>	
Syntax	`<OutType> Efx_DT1Typ2Out_<OutTypeMn> ( const Efx_StateDT1Typ2_Type* State_cpst )`	
Service ID [hex]	0x35 to 0x36	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'DT1' controller output value
Description	This routine returns 'DT1' controller's output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00516] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00517] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00518] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00519] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x35	sint16 Efx_DT1Typ2Out_s16(const Efx_StateDT1Typ2_Type *)
0x36	sint8 Efx_DT1Typ2Out_s8(const Efx_StateDT1Typ2_Type *)

⌋

8.3.3.5 Proportional and Differential controller

This routine is a combination of proportional and differential controller.

1. PD Controller

[SWS_Efx_00090] Definition of API function Efx_PDCalc ⌈

Service Name	Efx_PDCalc	

Syntax	`void Efx_PDCalc (`
	`  sint32 X_s32,`
	`  Efx_StatePD_Type* State_cpst,`
	`  const Efx_ParamPD_Type* Param_cpst,`
	`  sint32 dT_s32`
	`)`	

Service ID [hex]	0x3A	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the PD controller
	Param_cpst	Pointer to parameter structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to internal state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes proportional plus derivative controller output value using differential equation: Yn= K(1+Tv/dT) * Xn - K(Tv/dT) * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00091] ⌈This equation derives implementation :

Output_value = (Param_cpst->K_C * (1+ Param_cpst->Tv_C/dT_s32) * X_s32) - (Param_cpst->K_C * (Param_cpst->Tv_C/dT_s32) * State_cpst->X1)

The result shall be Rounded towards Zero.⌋

[SWS_Efx_00092] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00093] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00094] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. PD Set State Value

This routine can be realised using inline function.

[SWS_Efx_00095] Definition of API function Efx_PDSetState ⌈

Service Name	Efx_PDSetState	
Syntax	`void Efx_PDSetState ( Efx_StatePD_Type* State_cpst, sint32 X1_s32, sint16 Y1_s16 )`	
Service ID [hex]	0x3B	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for input state
	Y1_s16	Initial value for output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a PD element.	
Available via	Efx.h	

⌋

[SWS_Efx_00096] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00097] ⌈The internal state of the PD element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00098] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32⌋

1. Set ’PD’ Parameters

This routine can be realised using inline function.

[SWS_Efx_00100] Definition of API function Efx_PDSetParam ⌈

Service Name	Efx_PDSetParam	

Syntax	`void Efx_PDSetParam (`
	`  Efx_ParamPD_Type* Param_cpst,`
	`  sint32 K_s32,`
	`  sint32 Tv_s32`
	`)`	

Service ID [hex]	0x3C	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	K_s32	Amplification factor
	Tv_s32	Lead time
Parameters (inout)	None	
Parameters (out)	Param_cpst	Pointer to internal parameter structure
Return value	void	No return value
Description	The routine sets the parameter structure of a PD element.	
Available via	Efx.h	

⌋

[SWS_Efx_00101] ⌈Initialisation of amplification factor.

Param_cpst->K_C = K_s32⌋

[SWS_Efx_00102] ⌈Initialisation of lead time state variable

Param_cpst->Tv_C = Tv_s32⌋

1. Get 'PD' output

This routine can be realised using inline function.

[SWS_Efx_00103] Definition of API function Efx_PDOut_<OutTypeMn> ⌈

Service Name	Efx_PDOut_<OutTypeMn>	

Syntax	`<OutType> Efx_PDOut_<OutTypeMn> (`
	`  const Efx_StatePD_Type* State_cpcst`
	`)`	

Service ID [hex]	0x3D to 0x3E	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpcst	Pointer to constant state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'PD' controller output value
Description	This routine returns 'PD' controllers output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00104] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00105] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00106] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00107] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x3D	sint16 Efx_PDOut_s16(const Efx_StatePD_Type *)
0x3E	sint8 Efx_PDOut_s8(const Efx_StatePD_Type *)

⌋

8.3.3.6 Integral component

This routine calculates Integration element .

1. 'I' Controller

[SWS_Efx_00110] Definition of API function Efx_ICalc ⌈

Service Name	Efx_ICalc	
Syntax	`void Efx_ICalc ( sint32 X_s32, Efx_StateI_Type* State_cpst, sint32 K_s32, sint32 dT_s32 )`	
Service ID [hex]	0x40	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'I' controller
	K_s32	Amplification factor
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to state variable.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes 'I' controller output value using differential equation, Yn = Yn-1 + K * dT * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00111] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + K_s32 * dT_s32 * State_cpst->X1⌋

[SWS_Efx_00112] ⌈Calculated Output_value and current input value shall be stored to State_cpst->Y1 and State_cpst->X1 respectively.

State_cpst->Y1 = Output_value

State_cpst->X1 = X_s32⌋

[SWS_Efx_00113] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'I' Controller with limitation

[SWS_Efx_00455] Definition of API function Efx_ILimCalc ⌈

Service Name	Efx_ILimCalc	

Syntax	`void Efx_ILimCalc (`
	`  sint32 X_s32,`
	`  Efx_StateI_Type* State_cpst,`
	`  sint32 K_s32,`
	`  const Efx_Limits_Type* Limit_cpst,`
	`  sint32 dT_s32`
	`)`	

Service ID [hex]	0x3F	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'I' controller
	K_s32	Amplification factor
	Limit_cpst	Pointer to limit structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to state variable
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes DT1 controller output value using differential equation, Yn = Yn-1 + K * d T * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00456] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + K_s32 * dT_s32 * State_cpst->X1⌋

[SWS_Efx_00457] ⌈Limit output value with minimum and maximum controller limits.

If (Output value < Limit_cpst->Min_C) Then,

Output_value = Limit_cpst->Min_C

If (Output value > Limit_cpst->Max_C) Then,

Output_value = Limit_cpst->Max_C⌋

[SWS_Efx_00458] ⌈Calculated Output_value and current input value shall be stored to State_cpst->Y1 and State_cpst->X1 respectively.

State_cpst->Y1 = Output_value

State_cpst->X1 = X_s32⌋

[SWS_Efx_00459] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Set limits for controllers

[SWS_Efx_00523] Definition of API function Efx_CtrlSetLimits ⌈

Service Name	Efx_CtrlSetLimits	
Syntax	`void Efx_CtrlSetLimits ( Efx_Limits_Type* Limit_cpst, sint32 Min_s32, sint32 Max_s32 )`	
Service ID [hex]	0x97	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Min_s32	Minimum limit
	Max_s32	Maximum limit
Parameters (inout)	Limit_cpst	Pointer to limit structure
Parameters (out)	None	
Return value	None	
Description	Update limit structure	
Available via	Efx.h	

⌋

[SWS_Efx_00524] ⌈Update limit structure

Limit_cpst->Min_C = Min_s32

Limit_cpst->Max_C = Max_s32⌋

1. Set 'I' State Value

This routine can be realised using inline function.

[SWS_Efx_00114] Definition of API function Efx_ISetState ⌈

Service Name	Efx_ISetState	
Syntax	`void Efx_ISetState ( Efx_StateI_Type* State_cpst, sint32 X1_s32, sint16 Y1_s16 )`	
Service ID [hex]	0x41	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for input state
	Y1_s16	Initial value for output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value

▽

△

Description	The routine initialises internal state variables of an I element.
Available via	Efx.h

⌋

[SWS_Efx_00115] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00116] ⌈The internal state of the DT1 element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00117] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32⌋

1. Get 'I' output

This routine can be realised using inline function.

[SWS_Efx_00118] Definition of API function Efx_IOut_<OutTypeMn> ⌈

Service Name	Efx_IOut_<OutTypeMn>	
Syntax	`<OutType> Efx_IOut_<OutTypeMn> ( const Efx_StateI_Type* State_cpst )`	
Service ID [hex]	0x43 to 0x44	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to constant state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'I' controller output value
Description	This routine returns 'I' controller's output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00119] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00120] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00121] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00122] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x43	sint16 Efx_IOut_s16(const Efx_StateI_Type*)
0x44	sint8 Efx_IOut_s8(const Efx_StateI_Type *)

⌋

8.3.3.7 Proportional and Integral controller

This routine is a combination of proportional and integral controller. Routine Efx_Ctrl SetLimits shall be used to set limits for this controller in case of limited functionality.

1. 'PI' Controller - Type1 (Implicit type)

[SWS_Efx_00125] Definition of API function Efx_PITyp1Calc ⌈

Service Name	Efx_PITyp1Calc	
Syntax	`void Efx_PITyp1Calc ( sint32 X_s32, Efx_StatePI_Type* State_cpst, const Efx_ParamPI_Type* Param_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x45	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PI' controller
	Param_cpst	Pointer to parameter structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral controller (implicit type) output value using differential equation: Yn= Yn-1+ K * Xn - K * (1 - dT/Tn) * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00126] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + (Param_cpst->K_C * X_s32) - (Param_cpst->K_C * (1 - Param_cpst->Tnrec_C * dT_s32) * State_cpst->X1)⌋

[SWS_Efx_00127] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00128] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00129] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'PI' Controller - Type1 with limitation (Implicit type)

[SWS_Efx_00465] Definition of API function Efx_PITyp1LimCalc ⌈

Service Name	Efx_PITyp1LimCalc	

Syntax	`void Efx_PITyp1LimCalc (`
	`  sint32 X_s32,`
	`  Efx_StatePI_Type* State_cpst,`
	`  const Efx_ParamPI_Type* Param_cpst,`
	`  const Efx_Limits_Type* Limit_cpst,`
	`  sint32 dT_s32`
	`)`	

Service ID [hex]	0x42	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PI' controller
	Param_cpst	Pointer to parameter structure
	Limit_cpst	Pointer to limit structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral controller (implicit type) output value using differential equation: Yn = Yn-1+ K * Xn - K * (1 - dT/Tn) * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00466] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + (Param_cpst->K_C * X_s32) - (Param_cpst->K_C * (1 - Param_cpst->Tnrec_C * dT_s32) * State_cpst->X1)⌋

[SWS_Efx_00467] ⌈Limit output value with minimum and maximum controller limits.

If (Output value < Limit_cpst->Min_C) Then,

Output_value = Limit_cpst->Min_C

If (Output value > Limit_cpst->Max_C) Then,

Output_value = Limit_cpst->Max_C⌋

[SWS_Efx_00468] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00469] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00470] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'PI' Controller - Type2 (Explicit type)

[SWS_Efx_00130] Definition of API function Efx_PITyp2Calc ⌈

Service Name	Efx_PITyp2Calc	
Syntax	`void Efx_PITyp2Calc ( sint32 X_s32, Efx_StatePI_Type* State_cpst, const Efx_ParamPI_Type* Param_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x46	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PI' controller
	Param_cpst	Pointer to parameter structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral controller (explicit type) output value using differential equation: Yn= Yn-1 + K * (1 + dT/Tn) * Xn - K * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00131] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + (Param_cpst->K_C * (1 + Param_cpst->Tnrec_C * dT_s32) * X_s32) - (Param_cpst->K_C * State_cpst->X1)⌋

[SWS_Efx_00132] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00133] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00134] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'PI' Controller - Type2 with limitation (Explicit type)

[SWS_Efx_00475] Definition of API function Efx_PITyp2LimCalc ⌈

Service Name	Efx_PITyp2LimCalc	

Syntax	`void Efx_PITyp2LimCalc (`
	`  sint32 X_s32,`
	`  Efx_StatePI_Type* State_cpst,`
	`  const Efx_ParamPI_Type* Param_cpst,`
	`  const Efx_Limits_Type* Limit_cpst,`
	`  sint32 dT_s32`
	`)`	

Service ID [hex]	0x39	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PI' controller
	Param_cpst	Pointer to parameter structure
	Limit_cpst	Pointer to limit structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral controller (explicit type) output value using differential equation: Yn = Yn-1 + K * (1 + dT/Tn) * Xn - K * Xn-1	
Available via	Efx.h	

⌋

[SWS_Efx_00476] ⌈This equation derives implementation :

Output_value = State_cpst->Y1 + (Param_cpst->K_C * (1 + Param_cpst->Tnrec_C * dT_s32) * X_s32) - (Param_cpst->K_C * State_cpst->X1)⌋

[SWS_Efx_00477] ⌈Limit output value with minimum and maximum controller limits.

If (Output value < Limit_cpst->Min_C) Then,

Output_value = Limit_cpst->Min_C

If (Output value > Limit_cpst->Max_C) Then,

Output_value = Limit_cpst->Max_C⌋

[SWS_Efx_00478] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00479] ⌈Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00480] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Set 'PI' State Value

This routine can be realised using inline function.

[SWS_Efx_00135] Definition of API function Efx_PISetState ⌈

Service Name	Efx_PISetState	
Syntax	`void Efx_PISetState ( Efx_StatePI_Type* State_cpst, sint32 X1_s32, sint16 Y1_s16 )`	
Service ID [hex]	0x47	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for input state
	Y1_s16	Initial value for output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a PI element.	
Available via	Efx.h	

⌋

[SWS_Efx_00136] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00137] ⌈The internal state of the PD element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00138] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32⌋

1. Set 'PI' Parameters

This routine can be realised using inline function.

[SWS_Efx_00139] Definition of API function Efx_PISetParam ⌈

Service Name	Efx_PISetParam	
Syntax	`void Efx_PISetParam ( Efx_ParamPI_Type* Param_cpst, sint32 K_s32, sint32 Tnrec )`	
Service ID [hex]	0x48	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	K_s32	Amplification factor
	Tnrec	Reciprocal follow-up time
Parameters (inout)	None	
Parameters (out)	Param_cpst	Pointer to internal parameter structure
Return value	void	No return value
Description	The routine sets the parameter structure of a PI element.	

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Available via	Efx.h

⌋

[SWS_Efx_00140] ⌈Initialisation of amplification factor.

Param_cpst->K_C = K_s32⌋

[SWS_Efx_00141] ⌈Initialisation of reciprocal follow up time state variable

Param_cpst->Tnrec_C = Tnrec_s32⌋

1. Get 'PI' output

This routine can be realised using inline function.

[SWS_Efx_00142] Definition of API function Efx_PIOut_<OutTypeMn> ⌈

Service Name	Efx_PIOut_<OutTypeMn>	
Syntax	`<OutType> Efx_PIOut_<OutTypeMn> ( const Efx_StatePI_Type* State_cpst )`	
Service ID [hex]	0x49 to 0x4A	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to constant state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'PI' controller output value
Description	This routine returns 'PI' controllers output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00143] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00144] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00145] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00146] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x49	sint16 Efx_PIOut_s16(const Efx_StatePI_Type *)
0x4A	sint8 Efx_PIOut_s8(const Efx_StatePI_Type *)

⌋

8.3.3.8 Proportional, Integral and Differential controller

This routine is a combination of Proportional, integral and differential controller. Routine Efx_CtrlSetLimits shall be used to set limits for this controller in case of limited functionality.

1. 'PID' Controller - Type1 (Implicit type)

[SWS_Efx_00150] Definition of API function Efx_PIDTyp1Calc ⌈

Service Name	Efx_PIDTyp1Calc	
Syntax	`void Efx_PIDTyp1Calc ( sint32 X_s32, Efx_StatePID_Type* State_cpst, const Efx_ParamPID_Type* Param_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x4B	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PID' controller
	Param_cpst	Parameter structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral plus derivative controller (implicit type) output value using differential equation: Yn=Yn-1+ K * (1 + Tv/dT) * Xn- K *(1 - dT/Tn + 2Tv/dT) * Xn-1 + K * (Tv/dT) * Xn-2	
Available via	Efx.h	

⌋

[SWS_Efx_00151] ⌈This equation derives implementation :

calc1 = Param_cpst->K_C * (1 + t_val) * X_s32

calc2 = Param_cpst->K_C * (1 - dT_s32 * Param_cpst->Tnrec_C + 2 * t_val) * State_cpst->X1

calc3 = Param_cpst->K_C * t_val * State_cpst->X2

Output_value = State_cpst->Y1 + calc1 - calc2 + calc3

Where t_val = Param_cpst->Tv_C / dT_s32

The result shall be Rounded towards Zero.⌋

[SWS_Efx_00152] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00153] ⌈Old input value State_cpst->X1 shall be stored to State_cpst->X2

State_cpst->X2 = State_cpst->X1

Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00154] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'PID' Controller - Type1 with limitation (Implicit type)

[SWS_Efx_00485] Definition of API function Efx_PIDTyp1LimCalc ⌈

Service Name	Efx_PIDTyp1LimCalc	
Syntax	`void Efx_PIDTyp1LimCalc ( sint32 X_s32, Efx_StatePID_Type* State_cpst, const Efx_ParamPID_Type* Param_cpst, const Efx_Limits_Type* Limit_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x37	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PID' controller
	Param_cpst	Pointer to parameter structure
	Limit_cpst	Pointer to limit structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral plus derivative controller (implicit type) output value using differential equation: Yn=Yn-1+ K * (1 + Tv/dT) * Xn- K *(1 - dT/Tn + 2Tv/dT) * Xn-1 + K * (Tv/dT) * Xn-2	
Available via	Efx.h	

⌋

[SWS_Efx_00486] ⌈This equation derives implementation :

calc1 = Param_cpst->K_C * (1 + t_val) * X_s32

calc2 = Param_cpst->K_C * (1 - dT_s32 * Param_cpst->Tnrec_C + 2 * t_val) * State_cpst->X1

calc3 = Param_cpst->K_C * t_val * State_cpst->X2

Output_value = State_cpst->Y1 + calc1 - calc2 + calc3

Where t_val = Param_cpst->Tv_C / dT_s32⌋

[SWS_Efx_00487] ⌈Limit output value with minimum and maximum controller limits.

If (Output value < Limit_cpst->Min_C) Then,

Output_value = Limit_cpst->Min_C

If (Output value > Limit_cpst->Max_C) Then,

Output_value = Limit_cpst->Max_C⌋

[SWS_Efx_00488] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00489] ⌈Old input value State_cpst->X1 shall be stored to State_cpst->X2

State_cpst->X2 = State_cpst->X1

Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00490] ⌈Resolution of dT_s32 is 10ˆ(-6) seconds per increment of 1 data representation unit⌋

1. 'PID' Controller - Type2

[SWS_Efx_00155] Definition of API function Efx_PIDTyp2Calc ⌈

Service Name	Efx_PIDTyp2Calc	
Syntax	`void Efx_PIDTyp2Calc ( sint32 X_s32, Efx_StatePID_Type* State_cpst, const Efx_ParamPID_Type* Param_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x4C	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PID' controller
	Param_cpst	Parameter structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure.
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral plus derivative controller (explicit type) output value using differential equation: Yn = Yn-1 + K * (1 + dT/Tn+ Tv/dT) * Xn- K *(1 + 2Tv/dT) * Xn-1+ K * (Tv/dT) * Xn-2	
Available via	Efx.h	

⌋

[SWS_Efx_00156] ⌈This equation derives implementation :

calc1 = Param_cpst->K_C * (1 + dT_s32 * Param_cpst->Tnrec_C + t_val) * X_s32

calc2 = Param_cpst->K_C * (1 + 2 * t_val) * State_cpst->X1

calc3 = Param_cpst->K_C * t_val * State_cpst->X2

Output_value = State_cpst->Y1 + calc1 - calc2 + calc3

Where t_val = Param_cpst->Tv_C / dT_s32

The result shall be Rounded towards Zero.⌋

[SWS_Efx_00157] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00158] ⌈Old input value State_cpst->X1 shall be stored to State_cpst->X2

State_cpst->X2 = State_cpst->X1

Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00159] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. 'PID' Controller - Type2 with limitation

[SWS_Efx_00495] Definition of API function Efx_PIDTyp2LimCalc ⌈

Service Name	Efx_PIDTyp2LimCalc	
Syntax	`void Efx_PIDTyp2LimCalc ( sint32 X_s32, Efx_StatePID_Type* State_cpst, const Efx_ParamPID_Type* Param_cpst, const Efx_Limits_Type* Limit_cpst, sint32 dT_s32 )`	
Service ID [hex]	0x4F	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Input value for the 'PID' controller
	Param_cpst	Pointer to parameter structure
	Limit_cpst	Pointer to limit structure
	dT_s32	Sample Time [10^{-6}seconds per increment of 1 data representation unit]
Parameters (inout)	State_cpst	Pointer to the internal state structure
Parameters (out)	None	
Return value	void	No return value
Description	This routine computes Proportional plus integral plus derivative controller (explicit type) output value using differential equation: Yn = Yn-1 + K * (1 + dT/Tn+ Tv/dT) * Xn- K *(1 + 2Tv/dT) * Xn-1+ K * (Tv/dT) * Xn-2	
Available via	Efx.h	

⌋

[SWS_Efx_00496] ⌈This equation derives implementation :

calc1 = Param_cpst->K_C * (1 + dT_s32 * Param_cpst->Tnrec_C + t_val) * X_s32

calc2 = Param_cpst->K_C * (1 + 2 * t_val) * State_cpst->X1

calc3 = Param_cpst->K_C * t_val * State_cpst->X2

Output_value = State_cpst->Y1 + calc1 - calc2 + calc3

Where t_val = Param_cpst->Tv_C / dT_s32⌋

[SWS_Efx_00497] ⌈Limit output value with minimum and maximum controller limits.

If (Output value < Limit_cpst->Min_C) Then,

Output_value = Limit_cpst->Min_C

If (Output value > Limit_cpst->Max_C) Then,

Output_value = Limit_cpst->Max_C⌋

[SWS_Efx_00498] ⌈Calculated Output_value shall be stored to State_cpst->Y1.

State_cpst->Y1 = Output_value⌋

[SWS_Efx_00499] ⌈Old input value State_cpst->X1 shall be stored to State_cpst->X2

State_cpst->X2 = State_cpst->X1

Current input value X_s32 shall be stored to State_cpst->X1.

State_cpst->X1 = X_s32⌋

[SWS_Efx_00500] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

1. Set 'PID' State Value

This routine can be realised using inline function.

[SWS_Efx_00160] Definition of API function Efx_PIDSetState ⌈

Service Name	Efx_PIDSetState	

Syntax	`void Efx_PIDSetState (`
	`  Efx_StatePID_Type* State_cpst,`
	`  sint32 X1_s32,`
	`  sint32 X2_s32,`
	`  sint16 Y1_s16`
	`)`	

Service ID [hex]	0x4D	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X1_s32	Initial value for input state
	X2_s32	Initial value for input state
	Y1_s16	Initial value for output state
Parameters (inout)	None	
Parameters (out)	State_cpst	Pointer to internal state structure
Return value	void	No return value
Description	The routine initialises internal state variables of a PID element.	

▽

△

Available via	Efx.h

⌋

[SWS_Efx_00161] ⌈Initialisation of output state variable Y1.

State_cpst->Y1 = Y1_s16 << 16⌋

[SWS_Efx_00162] ⌈The internal state of the PD element is stored as (Y1_s16 << 16)⌋

[SWS_Efx_00163] ⌈Initialisation of input state variable X1.

State_cpst->X1 = X1_s32

Initialisation of input state variable X2.

State_cpst->X2 = X2_s32⌋

1. Set 'PID' Parameters

This routine can be realised using inline function.

[SWS_Efx_00164] Definition of API function Efx_PIDSetParam ⌈

Service Name	Efx_PIDSetParam	
Syntax	`void Efx_PIDSetParam ( Efx_ParamPID_Type* Param_cpst, sint32 K_s32, sint32 Tv_s32, sint32 Tnrec_s32 )`	
Service ID [hex]	0x4E	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	K_s32	Amplification factor
	Tv_s32	Lead Time
	Tnrec_s32	Reciprocal follow-up timer
Parameters (inout)	None	
Parameters (out)	Param_cpst	Pointer to internal parameter structure
Return value	void	No return value
Description	The routine sets the parameter structure of a PID element.	
Available via	Efx.h	

⌋

[SWS_Efx_00165] ⌈Initialisation of amplification factor.

Param_cpst->K_C = K_s32⌋

[SWS_Efx_00166] ⌈Initialisation of lead time state variable

Param_cpst->Tv_C = Tv_s32⌋

[SWS_Efx_00167] ⌈Initialisation of reciprocal follow up time state variable

Param_cpst->Tnrec_C = Tnrec_s32⌋

1. Get 'PID' output

This routine can be realised using inline function.

[SWS_Efx_00168] Definition of API function Efx_PIDOut_<OutTypeMn> ⌈

Service Name	Efx_PIDOut_<OutTypeMn>	
Syntax	`<OutType> Efx_PIDOut_<OutTypeMn> ( const Efx_StatePID_Type* State_cpst )`	
Service ID [hex]	0x50 to 0x51	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to constant state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return 'PID' controller output value
Description	This routine returns 'PID' controllers output value.	
Available via	Efx.h	

⌋

[SWS_Efx_00169] ⌈Output value = State_cpst->Y1 >> 16⌋

[SWS_Efx_00170] ⌈Output value shall be normalized by 16 bit right shift of internal state variable.⌋

[SWS_Efx_00171] ⌈Return value shall be limited by boundary values of the return data type.⌋

[SWS_Efx_00172] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x50	sint16 Efx_PIDOut_s16(const Efx_StatePID_Type *)
0x51	sint8 Efx_PIDOut_s8(const Efx_StatePID_Type *)

⌋

8.3.4 Square root

[SWS_Efx_00175] Definition of API function Efx_Sqrt_u32_u32 ⌈

Service Name	Efx_Sqrt_u32_u32
Syntax	`uint32 Efx_Sqrt_u32_u32 ( uint32 x_value )`
Service ID [hex]	0x52

▽

△

Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [0, 0.999999999767169] Resolution: $1/2^{32}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint32	Return value of the function Physical range: [0, 0.999999999767169] Resolution: $1/2^{32}$
Description	This service computes the square root of a value	
Available via	Efx.h	

⌋

[SWS_Efx_00176] ⌈Result = square_root (x_value)⌋

[SWS_Efx_00177] ⌈The result is rounded off.⌋

[SWS_Efx_00178] Definition of API function Efx_Sqrt_u16_u16 ⌈

Service Name	Efx_Sqrt_u16_u16	
Syntax	`uint16 Efx_Sqrt_u16_u16 ( uint16 x_value )`	
Service ID [hex]	0x53	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [0, 0.9999847] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint16	Return value of the function Physical range: [0, 0.9999847] Resolution: $1/2^{16}$
Description	This service computes the square root of a value	
Available via	Efx.h	

⌋

[SWS_Efx_00179] ⌈Result = square_root (x_value)⌋

[SWS_Efx_00180] ⌈The result is rounded off.⌋

[SWS_Efx_00181] Definition of API function Efx_Sqrt_u8_u8 ⌈

Service Name	Efx_Sqrt_u8_u8	
Syntax	`uint8 Efx_Sqrt_u8_u8 ( uint8 x_value )`	
Service ID [hex]	0x54	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [0, 0.996] Resolution: $1/2^{8}$

▽

△

Parameters (inout)	None	
Parameters (out)	None	
Return value	uint8	Return value of the function Physical range: [0, 0.996] Resolution: $1/2^8$
Description	This service computes the square root of a value	
Available via	Efx.h	

⌋

[SWS_Efx_00182] ⌈Result = square_root (x_value)⌋

[SWS_Efx_00183] ⌈The result is rounded off.⌋

8.3.5 Exponential

[SWS_Efx_00185] Definition of API function Efx_Exp_s32_s32 ⌈

Service Name	Efx_Exp_s32_s32	
Syntax	`sint32 Efx_Exp_s32_s32 ( sint32 Value1 )`	
Service ID [hex]	0x55	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Value1	Input value
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Return value of the function
Description	The routine returns the exponential value of the negated input value.	
Available via	Efx.h	

⌋

[SWS_Efx_00186] ⌈Output = e^(-x)

where x = Value1⌋

[SWS_Efx_00187] ⌈Output is quantized by 2^16

Output Range = ([0.00004539....22026.4657948] * 2^16) = [2....1443526462]

Input Range = ([-10....10] * 2^16) = [0xFFF60000....0x000A0000]⌋

8.3.6 Average

[SWS_Efx_00190] Definition of API function Efx_Average_s32_s32 ⌈

Service Name	Efx_Average_s32_s32	
Syntax	`sint32 Efx_Average_s32_s32 ( sint32 value1, sint32 value2 )`	
Service ID [hex]	0x5A	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	value1	Input value1
	value2	Input value2
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Return value of the function
Description	The routine returns average value.	
Available via	Efx.h	

⌋

[SWS_Efx_00191] ⌈Output = (Value1 + Value2) / 2⌋

[SWS_Efx_00192] ⌈The result is rounded towards zero.⌋

8.3.7 Array Average

[SWS_Efx_00193] Definition of API function Efx_Array_Average_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Array_Average_<InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_Array_Average_<InTypeMn>_<OutTypeMn> ( const <InType>* Array, uint16 Count )`	
Service ID [hex]	0x60 and 0x61	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Array	Pointer to an array
	Count	Number of array elements
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return value of the function
Description	The routine returns average value of an array.	
Available via	Efx.h	

⌋

[SWS_Efx_00194] ⌈Output = (Array[0] + Array[1] + ... + Array[N-1]) / Count⌋

[SWS_Efx_00195] ⌈The result is rounded towards zero.⌋

[SWS_Efx_00196] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x60	sint32 Efx_Array_Average_s32_s32(sint32*, uint16)
0x61	sint16 Efx_Array_Average_s16_s16(sint16*, uint16)

⌋

8.3.8 Moving Average

[SWS_Efx_00197] Definition of API function Efx_MovingAverage_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_MovingAverage_<InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_MovingAverage_<InTypeMn>_<OutTypeMn> ( Efx_MovingAvrg<InTypeMn>_Type* state, <InType> value )`	
Service ID [hex]	0x6A to 0x6B	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	value	Input value
Parameters (inout)	state	Pointer to sliding average structure
Parameters (out)	None	
Return value	<OutType>	Return value of the function
Description	The routine returns sliding average value of n - 1 last subsequent values of an array plus one new value.	
Available via	Efx.h	

⌋

[SWS_Efx_00198] ⌈state ->p_beg pointer holds start address of an array

state ->p_end pointer holds end address of an array

state ->p_act pointer holds address of an oldest entry of an array⌋

[SWS_Efx_00199] ⌈state ->sum shall store total sum including 'value' & excluding oldest entry

state ->sum = state ->sum - *(state ->p_act) + value⌋

[SWS_Efx_00200] ⌈In every routine call state ->p_act shall be incremented with wrap around.

This increment ensures that oldest entry gets replaced with new entry.⌋

[SWS_Efx_00201] ⌈Output_value = state->sum / state->n⌋

[SWS_Efx_00202] ⌈If state ->n = 0 the result shall be zero by definition.⌋

[SWS_Efx_00203] ⌈The result is rounded towards zero.⌋

Structure definition for function argument

[SWS_Efx_00204] Definition of datatype Efx_MovingAvrgS16_Type ⌈

Name	Efx_MovingAvrgS16_Type	
Kind	Structure	
Elements	sum	
	Type	sint32
	Comment	Sum of array elements
	n	
	Type	sint16
	Comment	Size of an array (only positive values)
	*p_beg	
	Type	sint16
	Comment	Pointer to the first array element
	*p_end	
	Type	sint16
	Comment	Pointer to the last array element
	*p_act	
	Type	sint16
	Comment	Pointer to the oldest entry array element
Description	Structure definition for sliding average routine for sint16 input value	
Available via	Efx.h	

⌋

[SWS_Efx_00836] Definition of datatype Efx_MovingAvrgS32_Type ⌈

Name	Efx_MovingAvrgS32_Type	
Kind	Structure	
Elements	sum	
	Type	sint64
	Comment	Sum of array elements
	n	
	Type	sint32
	Comment	Size of an array (only positive values)
	*p_beg	
	Type	sint32
	Comment	Pointer to the first array element
	*p_end	
	Type	sint32
	Comment	Pointer to the last array element
	*p_act	
	Type	sint32
	Comment	Pointer to the oldest entry array element
Description	Structure definition for sliding average routine for sint32 input value	
Available via	Efx.h	

⌋

[SWS_Efx_00205] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x6A	sint16 Efx_MovingAverage_s16_s16(Efx_MovingAvrgS16_Type*, sint16)
0x6B	sint32 Efx_MovingAverage_s32_s32(Efx_MovingAvrgS32_Type*, sint32)

⌋

8.3.9 Hypotenuse

The formula used for calculation in the below hypotenuse requirements is,

sqrt(x_value * x_value/2 + y_value * y_value/2).

This is to achieve the specified resolution in the result.

Warning: Hypotenuse functions shall not be used directly for distance computation because the result has not the same resolution than the inputs.

[SWS_Efx_00210] Definition of API function Efx_Hypot_u32u32_u32 ⌈

Service Name	Efx_Hypot_u32u32_u32	
Syntax	`uint32 Efx_Hypot_u32u32_u32 ( uint32 x_value, uint32 y_value )`	
Service ID [hex]	0x70	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument Physical range: [0, 0.999999999767169] Resolution: $1/2^{32}$
	y_value	Second argument Physical range: [0, 0.999999999767169] Resolution: $1/2^{32}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint32	Return value of the function Physical range: [0, sqrt(2)] Resolution: $sqrt(2)/2^{32}$
Description	This service computes the length of a vector	
Available via	Efx.h	

⌋

[SWS_Efx_00211] ⌈Result = sqrt(x_value * x_value/2 + y_value * y_value/2)⌋

[SWS_Efx_00212] ⌈The result is rounded off.⌋

[SWS_Efx_00213] Definition of API function Efx_Hypot_u16u16_u16 ⌈

Service Name	Efx_Hypot_u16u16_u16	

Syntax	`uint16 Efx_Hypot_u16u16_u16 (`
	`  uint16 x_value,`
	`  uint16 y_value`
	`)`	

Service ID [hex]	0x71	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument Physical range: [0, 0.9999847] Resolution: $1/2^{16}$
	y_value	Second argument Physical range: [0, 0.9999847] Resolution: $1/2^{16}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint16	Return value of the function Physical range: [0, sqrt(2)] Resolution: $sqrt(2)/2^{16}$
Description	This service computes the length of a vector	
Available via	Efx.h	

⌋

[SWS_Efx_00214] ⌈Result = sqrt(x_value * x_value/2 + y_value * y_value/2)⌋

[SWS_Efx_00215] ⌈The result is rounded off.⌋

[SWS_Efx_00216] Definition of API function Efx_Hypot_u8u8_u8 ⌈

Service Name	Efx_Hypot_u8u8_u8	

Syntax	`uint8 Efx_Hypot_u8u8_u8 (`
	`  uint8 x_value,`
	`  uint8 y_value`
	`)`	

Service ID [hex]	0x72	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument Physical range: [0, 0.996] Resolution: $1/2^{8}$
	y_value	Second argument Physical range: [0, 0.996] Resolution: $1/2^{8}$
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint8	Return value of the function Physical range: [0, sqrt(2)] Resolution: $sqrt(2)/2^{8}$
Description	This service computes the length of a vector	
Available via	Efx.h	

⌋

[SWS_Efx_00217] ⌈Result = sqrt(x_value * x_value/2 + y_value * y_value/2)⌋

[SWS_Efx_00218] ⌈The result is rounded off.⌋

8.3.10 Trigonometric functions

8.3.10.1 Sine function

[SWS_Efx_00220] Definition of API function Efx_Sin_s32_s32 ⌈

Service Name	Efx_Sin_s32_s32	
Syntax	`sint32 Efx_Sin_s32_s32 ( sint32 x_value )`	
Service ID [hex]	0x75	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^32)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^31)
Description	This service computes the sine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00222] ⌈The result is rounded off.⌋

[SWS_Efx_00223] Definition of API function Efx_Sin_s16_s16 ⌈

Service Name	Efx_Sin_s16_s16	
Syntax	`sint16 Efx_Sin_s16_s16 ( sint16 x_value )`	
Service ID [hex]	0x76	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^16)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint16	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^15)
Description	This service computes the sine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00225] ⌈The result is rounded off.⌋

[SWS_Efx_00226] Definition of API function Efx_Sin_s8_s8 ⌈

Service Name	Efx_Sin_s8_s8	
Syntax	`sint8 Efx_Sin_s8_s8 ( sint8 x_value )`	
Service ID [hex]	0x77	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^8)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint8	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^7)
Description	This service computes the sine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00228] ⌈The result is rounded off.⌋

8.3.10.2 Cosine function

[SWS_Efx_00229] Definition of API function Efx_Cos_s32_s32 ⌈

Service Name	Efx_Cos_s32_s32	
Syntax	`sint32 Efx_Cos_s32_s32 ( sint32 x_value )`	
Service ID [hex]	0x7A	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^32)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^31)
Description	This service computes the cosine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00231] ⌈The result is rounded off.⌋

[SWS_Efx_00232] Definition of API function Efx_Cos_s16_s16 ⌈

Service Name	Efx_Cos_s16_s16	

Syntax	`sint16 Efx_Cos_s16_s16 (`
	`  sint16 x_value`
	`)`	

Service ID [hex]	0x7B	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^16)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint16	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^15)
Description	This service computes the cosine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00234] ⌈The result is rounded off.⌋

[SWS_Efx_00235] Definition of API function Efx_Cos_s8_s8 ⌈

Service Name	Efx_Cos_s8_s8	

Syntax	`sint8 Efx_Cos_s8_s8 (`
	`  sint8 x_value`
	`)`	

Service ID [hex]	0x7C	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-PI, PI[Resolution: 2*PI/(2^8
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint8	Return value of the function Physical range: [-1, 1[Resolution: 1/(2^7)
Description	This service computes the cosine of an angle.	
Available via	Efx.h	

⌋

[SWS_Efx_00237] ⌈The result is rounded off.⌋

8.3.10.3 Inverse Sine function

[SWS_Efx_00240] Definition of API function Efx_ArcSin_s32_s32 ⌈

Service Name	Efx_ArcSin_s32_s32	
Syntax	`sint32 Efx_ArcSin_s32_s32 ( sint32 x_value )`	
Service ID [hex]	0x80	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^31)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Return value of the function Physical range: [-PI/2 , PI/2[Resolution: PI/(2^32)
Description	This service computes the inverse sine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00242] ⌈The result is rounded off.⌋

[SWS_Efx_00243] Definition of API function Efx_ArsSin_s16_s16 ⌈

Service Name	Efx_ArsSin_s16_s16	
Syntax	`sint16 Efx_ArsSin_s16_s16 ( sint16 x_value )`	
Service ID [hex]	0x81	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^15)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint16	Return value of the function Physical range: [-PI/2, PI/2[Resolution: PI/(2^16)
Description	This service computes the inverse sine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00245] ⌈The result is rounded off.⌋

[SWS_Efx_00246] Definition of API function Efx_ArcSin_s8_s8 ⌈

Service Name	Efx_ArcSin_s8_s8	
Syntax	`sint8 Efx_ArcSin_s8_s8 ( sint8 x_value )`	
Service ID [hex]	0x82	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^7)
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint8	Return value of the function Physical range: [-PI/2, PI/2[Resolution: PI/(2^8)
Description	This service computes the inverse sine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00248] ⌈The result is rounded off.⌋

8.3.10.4 Inverse cosine function

[SWS_Efx_00250] Definition of API function Efx_ArcCos_s32_u32 ⌈

Service Name	Efx_ArcCos_s32_u32	
Syntax	`uint32 Efx_ArcCos_s32_u32 ( sint32 x_value )`	
Service ID [hex]	0x85	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^31)
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint32	Return value of the function Physical range: [0 , PI[Resolution: PI/(2^32)
Description	This service computes the inverse cosine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00252] ⌈The result is rounded off.⌋

[SWS_Efx_00253] Definition of API function Efx_ArcCos_s16_u16 ⌈

Service Name	Efx_ArcCos_s16_u16	

Syntax	`uint16 Efx_ArcCos_s16_u16 (`
	`  sint16 x_value`
	`)`	

Service ID [hex]	0x86	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^15)
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint16	Return value of the function Physical range: [0 , PI[Resolution: PI/(2^16)
Description	This service computes the inverse cosine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00255] ⌈The result is rounded off.⌋

[SWS_Efx_00256] Definition of API function Efx_ArcCos_s8_u8 ⌈

Service Name	Efx_ArcCos_s8_u8	

Syntax	`uint8 Efx_ArcCos_s8_u8 (`
	`  sint8 x_value`
	`)`	

Service ID [hex]	0x87	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Argument Physical range: [-1, 1[Resolution: 1/(2^7)
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint8	Return value of the function Physical range: [0, PI[Resolution: PI/(2^8)
Description	This service computes the inverse cosine of a value.	
Available via	Efx.h	

⌋

[SWS_Efx_00258] ⌈The result is rounded off.⌋

8.3.11 Rate limiter

[SWS_Efx_00261] Definition of API function Efx_SlewRate_<InTypeMn> ⌈

Service Name	Efx_SlewRate_<InTypeMn>	

Syntax	`void Efx_SlewRate_<InTypeMn> (`
	`  <InType> limit_pos,`
	`  <InType> input,`
	`  <InType> limit_neg,`
	`  <InType>* output,`
	`  uint8* init`
	`)`	

Service ID [hex]	0x8B to 0x8E	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	limit_pos	positive slope
	input	Input signal
	limit_neg	negative slope
Parameters (inout)	output	Output signal
	init	Pointer on a flag used to detect the first call of the API
Parameters (out)	None	
Return value	void	No return value
Description	The routine limits the increase and the decrease of the Input entry by using tunable slopes.	
Available via	Efx.h	

⌋

[SWS_Efx_00262] ⌈If *init==0, *output=input⌋

[SWS_Efx_00264] ⌈Input, limit_pos, limit_neg and output must have the same resolution and the same physical unit.⌋

[SWS_Efx_00265] ⌈If the result of the Efx_SlewRate is only computed when some conditions are fulfilled, do not call the slew rate under the condition, but systematically! The slew rate must be called at each recurrence, even if it is not used, because otherwise, the output will be frozen to the previous value all the time, if conditions are not fulfilled.⌋

[SWS_Efx_00266] ⌈The parameters given for output and init, for which we receive the addresses, must be declared by the caller as private variables and will be initialized at 0, because the function uses the previous values of these outputs (so the stack must not be used).⌋

[SWS_Efx_00267] ⌈Physical values of limit_pos and limit_neg are positive. Internally limit_pos is added to output value and limit_neg is substracted from output value to get upper and lower limit band within which output value is limited.⌋

[SWS_Efx_00268] ⌈At first step, when *init==0, output takes the value of input and *init will be put at 1.⌋

[SWS_Efx_00269] ⌈limit_pos is added to the output and it becomes the maximum value of the new output

limit_neg is deducted from the output and it becomes the minimum value of the new output.

If input is outside this range, output is limited to these values, in the other case, output takes the value of input⌋

[SWS_Efx_00270] ⌈Values of limit_pos and limit_neg shall be adapted to the frequency of the call of the service.⌋

[SWS_Efx_00271] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x8B	void Efx_SlewRate_u16 (uint16, uint16, uint16, uint16 *, uint8 *)
0x8C	void Efx_SlewRate_s16 (uint16, sint16, uint16, sint16 *, uint8 *)
0x8D	void Efx_SlewRate_u32 (uint32, uint32, uint32, uint32 *, uint8 *)
0x8E	void Efx_SlewRate_s32 (uint32, sint32, uint32, sint32 *, uint8 *)

⌋

8.3.12 Ramp routines

In case of a change of the input value, the ramp output value follows the input value with a specified limited slope.

Efx_ParamRamp_Type and Efx_StateRamp_Type are the data types for storing ramp parameters. Usage of Switch-Routine and Jump-Routine is optional based on the functionality requirement. Usage of Switch-Routine, Jump-Routine, Calc-Routine and Out-Method have the following precondition concerning the sequence of the calls.

- Efx_RampCalcSwitch
- Efx_RampCalcJump
- Efx_RampCalc
- Efx_RampOut_s32

Structure definition for function argument

[SWS_Efx_00275] Definition of datatype Efx_ParamRamp_Type ⌈

Name	Efx_ParamRamp_Type	
Kind	Structure	
Elements	SlopePos_u32	
	Type	uint32
	Comment	Positive slope for ramp in absolute value. The resolution of SlopePos_u32 shall be 1/2^16.
	SlopeNeg_u32	
	Type	uint32
	Comment	Negative slope for ramp in absolute value. The resolution of Slope Neg_u32 shall be 1/2^16.
Description	Structure definition for Ramp routine	
Available via	Efx.h	

⌋

[SWS_Efx_00834] Definition of datatype Efx_StateRamp_Type ⌈

Name	Efx_StateRamp_Type	
Kind	Structure	
Elements	State_s32	
	Type	sint32
	Comment	State of the ramp
	Dir_s8	
	Type	sint8
	Comment	Ramp direction
	Switch_s8	
	Type	sint8
	Comment	Position of switch
Description	Structure definition for Ramp routine	
Available via	Efx.h	

⌋

8.3.12.1 Ramp routine

[SWS_Efx_00276] Definition of API function Efx_RampCalc ⌈

Service Name	Efx_RampCalc	
Syntax	`void Efx_RampCalc ( sint32 X_s32, Efx_StateRamp_Type* State_cpst, const Efx_ParamRamp_Type* Param_cpcst, sint32 dT_s32 )`	
Service ID [hex]	0x90	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Target value for the ramp to reach
	Param_cpcst	Pointer to parameter structure
	dT_s32	Sample Time [10^{-6} seconds per increment of 1 data representation unit]. dT_s32 shall be > 0.
Parameters (inout)	State_cpst	Pointer to state structure
Parameters (out)	None	
Return value	None	
Description	The ramp output value increases or decreases a value with slope * dT_s32 depending if (State_cpst->State_s32 < X_s32) or (State_cpst->State_s32 > X_s32).	
Available via	Efx.h	

⌋

[SWS_Efx_00837] ⌈If the ramp state State_cpst->State_s32 has reached or crossed the target value X_s32 while the direction of the ramp had been RISING/FALLING, then set State_cpst->State_s32 = X_s32⌋

[SWS_Efx_00278] ⌈If ramp direction is rising then ramp increases a value with slope * dT_s32

if (State_cpst->Dir_s8 == RISING)

State_cpst->State_s32 = State_cpst->State_s32 + (Param_cpcst->SlopePos_u32 * dT_s32)

The minimum value of Param_cpcst->SlopePos_u32 * dT_s32 shall be 1, when Param->SlopePos > 0.

The intermediate results shall be rounded off.

Ex: minimum increment of Param_cpcst->SlopePos_u32 * dT_s32 = 1/(2^16*10^6)⌋

[SWS_Efx_00279] ⌈If ramp direction is falling then ramp decreases a value with slope * dT_s32

if (State_cpst->Dir_s8 == FALLING)

State_cpst->State_s32 = State_cpst->State_s32 - (Param_cpcst->SlopeNeg_u32 * dT_s32)

The minimum value of Param_cpcst->SlopeNeg_u32 * dT_s32 shall be 1, when Param->SlopeNeg > 0.

The intermediate results shall be rounded off.

Ex: minimum decrement of Param_cpcst->SlopeNeg_u32 * dT_s32 = 1/(2^16*10^6)⌋

[SWS_Efx_00280] ⌈Direction of the ramp is stored so that a change of the target can be recognized and the output will follow immediately to the new target value.

State_cpst->Dir_s8 states are: RISING, FALLING, END.⌋

[SWS_Efx_00281] ⌈Comparison of State and Target decides ramp direction

If(State_cpst->State_s32 > X_s32) then State_cpst->Dir_s8 = FALLING

If(State_cpst->State_s32 < X_s32) then State_cpst->Dir_s8 = RISING

If(State_cpst->State_s32 == X_s32) then State_cpst->Dir_s8 = END⌋

[SWS_Efx_00284] ⌈Resolution of dT_s32 is 10^(-6) seconds per increment of 1 data representation unit⌋

8.3.12.2 Ramp Initialisation

[SWS_Efx_00285] Definition of API function Efx_RampInitState ⌈

Service Name	Efx_RampInitState	
Syntax	`void Efx_RampInitState ( Efx_StateRamp_Type* State_cpst, sint32 Val_s32 )`	
Service ID [hex]	0x91	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Val_s32	Initial value for state variable
Parameters (inout)	State_cpst	Pointer to the state structure
Parameters (out)	None	
Return value	None	
Description	Initializes the state, direction and switch parameters for the ramp.	
Available via	Efx.h	

⌋

[SWS_Efx_00286] ⌈Ramp direction is initialised with END value. User has no possibility to change or modify ramp direction.

State_cpst->Dir_s8 = END

E.g. of ramp direction states: RISING = 1, FALLING = -1, END = 0⌋

[SWS_Efx_00442] ⌈Initialisation of state variable

State_cpst->State_s32 = Val_s32⌋

[SWS_Efx_00443] ⌈Initialisation of switch variable. User has no possibility to change or modify switch initialization value.

State_cpst->Switch_s8 = OFF

E.g. of switch states: TARGET_A = 1, TARGET_B = -1, OFF = 0⌋

8.3.12.3 Ramp Set Slope

[SWS_Efx_00287] Definition of API function Efx_RampSetParam ⌈

Service Name	Efx_RampSetParam	

Syntax	`void Efx_RampSetParam (`
	`  Efx_ParamRamp_Type* Param_cpst,`
	`  uint32 SlopePosVal_u32,`
	`  uint32 SlopeNegVal_u32`
	`)`	

Service ID [hex]	0x92	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	SlopePosVal_u32	Positive slope value
	SlopeNegVal_u32	Negative slope value
Parameters (inout)	None	
Parameters (out)	Param_cpst	Pointer to parameter structure
Return value	None	
Description	Sets the slope parameter for the ramp provided by the structure Efx_ParamRamp_Type.	
Available via	Efx.h	

⌋

[SWS_Efx_00288] ⌈Sets positive and negative ramp slopes.

Param_cpst->SlopePos_u32 = SlopePosVal_u32

Param_cpst ->SlopeNeg_u32 = SlopeNegVal_u32⌋

8.3.12.4 Ramp out routines

[SWS_Efx_00289] Definition of API function Efx_RampOut_s32 ⌈

Service Name	Efx_RampOut_s32	
Syntax	`sint32 Efx_RampOut_s32 ( const Efx_StateRamp_Type* State_cpcst )`	
Service ID [hex]	0x93	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpcst	Pointer to the state value
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint32	Internal state of the ramp element
Description	Returns the internal state of the ramp element.	
Available via	Efx.h	

⌋

[SWS_Efx_00290] ⌈Return Value = State_cpcst->State_s32⌋

8.3.12.5 Ramp Jump routine

[SWS_Efx_00291] Definition of API function Efx_RampCalcJump ⌈

Service Name	Efx_RampCalcJump	
Syntax	`void Efx_RampCalcJump ( sint32 X_s32, Efx_StateRamp_Type* State_cpst )`	
Service ID [hex]	0x94	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X_s32	Target value for ramp to jump
Parameters (inout)	State_cpst	Pointer to the state value
Parameters (out)	None	
Return value	None	
Description	This routine works in addition to main ramp function Efx_RampCalc to provide a faster adaption to target value.	
Available via	Efx.h	

⌋

[SWS_Efx_00292] ⌈If target value changes to a value contrary to current ramp direction and ramp has not reached its old target value then ramp state jumps to new target value immediately.

State_cpst->State_s32 = X_s32

State_cpst->Dir_s8 = END⌋

[SWS_Efx_00293] ⌈If target value is changed to new value and ramp has reached its old target value then normal ramp behavior is maintained.

State_cpst->Dir_s8 = END⌋

[SWS_Efx_00303] ⌈Direction of the ramp is stored so that a change of the target can be recognized and the output will follow immediately to the new target value.

State_cpst->Dir_s8 states are: RISING, FALLING, END.⌋

[SWS_Efx_00304] ⌈Comparison of State and Target decides ramp direction

If(State_cpst->State_s32 > X_s32) then State_cpst->Dir_s8 = FALLING

If(State_cpst->State_s32 < X_s32) then State_cpst->Dir_s8 = RISING

If(State_cpst->State_s32 == X_s32) then State_cpst->Dir_s8 = END⌋

[SWS_Efx_00277] ⌈This routine decided if jump has to be done or not in case of change in target. Efx_RampCalc function shall be called after this function that a jump or the standard ramp behaviour is executed.⌋

8.3.12.6 Ramp switch routine

[SWS_Efx_00520] Definition of API function Efx_RampCalcSwitch ⌈

Service Name	Efx_RampCalcSwitch	
Syntax	`sint32 Efx_RampCalcSwitch ( sint32 Xa_s32, sint32 Xb_s32, boolean Switch, Efx_StateRamp_Type* State_cpst )`	
Service ID [hex]	0x96	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Xa_s32	Target value for the ramp to reach if switch is in position 'A'
	Xb_s32	Target value for the ramp to reach if switch is in position 'B'
	Switch	Switch to decide target value
Parameters (inout)	State_cpst	Pointer to StateRamp structure
Parameters (out)	None	
Return value	sint32	Returns the selected target value
Description	This routine switches between two target values for a ramp service based on a Switch parameter.	
Available via	Efx.h	

⌋

[SWS_Efx_00521] ⌈Parameter Switch decides which target value is selected.

If Switch = TRUE, then Xa_s32 is selected.

State_cpst->Switch_s8 is set to TARGET_A

Return value = Xa_s32

If Switch = FALSE, then Xb_s32 is selected.

State_cpst->Switch_s8 is set to TARGET_B

Return value = Xb_s32⌋

[SWS_Efx_00522] ⌈State_cpst->Dir_s8 hold direction information

State_cpst->Dir_s8 shall be set to END to reset direction information in case of target switch.⌋

[SWS_Efx_00528] ⌈Efx_RampCalcSwitch routine has to be called before Efx_Ramp Calc⌋

8.3.12.7 Get Ramp Switch position

[SWS_Efx_00307] Definition of API function Efx_RampGetSwitchPos ⌈

Service Name	Efx_RampGetSwitchPos	
Syntax	`boolean Efx_RampGetSwitchPos ( const Efx_StateRamp_Type* State_cpst )`	
Service ID [hex]	0x98	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to the state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	return value TRUE or FALSE
Description	Gets the current switch position of ramp switch function.	
Available via	Efx.h	

⌋

[SWS_Efx_00308] ⌈Return value = TRUE if Switch position State_cpst->Switch_s8 = TARGET_A

Return value = FALSE if Switch position State_cpst->Switch_s8 = TARGET_B⌋

Note: The function "Efx_RampGetSwitchPos" should be called only after calling the function "Efx_RampCalcSwitch" or "Efx_RampCalc".

8.3.12.8 Check Ramp Activity

[SWS_Efx_00309] Definition of API function Efx_RampCheckActivity ⌈

Service Name	Efx_RampCheckActivity	
Syntax	`boolean Efx_RampCheckActivity ( const Efx_StateRamp_Type* State_cpst )`	
Service ID [hex]	0x99	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	State_cpst	Pointer to the state structure
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	return value TRUE or FALSE
Description	This routine checks the status of the ramp and returns TRUE if the ramp is active, otherwise it returns FALSE.	
Available via	Efx.h	

⌋

[SWS_Efx_00310] ⌈return value = TRUE, if Ramp is active (State_cpst->Dir_s8 != END)

return value = FALSE, if Ramp is inactive (State_cpst->Dir_s8 == END)⌋

8.3.13 Hysteresis routines

8.3.13.1 Hysteresis

[SWS_Efx_00311] Definition of API function Efx_Hysteresis_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Hysteresis_<InTypeMn>_<OutTypeMn>	

Syntax	`<OutType> Efx_Hysteresis_<InTypeMn>_<OutTypeMn> (`
	`  <InType> input,`
	`  <InType> thresholdLow,`
	`  <InType> thresholdHigh,`
	`  <InType> Out_Val,`
	`  <InType> Out_LowThresholdVal,`
	`  <InType> Out_HighThresholdVal`
	`)`	

Service ID [hex]	0x9A to 0x9F	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	input	Input signal
	thresholdLow	First threshold used to compute the output
	thresholdHigh	Second threshold used to compute the output
	Out_Val	Output value between the threshold
	Out_LowThresholdVal	Output value for Low Threshold trigger
	Out_HighThresholdVal	Output value for High Threshold trigger
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Return value of the function
Description	The routine estimates the output of the hysteresis.	
Available via	Efx.h	

⌋

[SWS_Efx_00312] ⌈If Input < thresholdLow, Then return_value = Out_LowThreshold Val⌋

[SWS_Efx_00313] ⌈If Input > thresholdHigh, Then return_value = Out_HighThreshold Val⌋

[SWS_Efx_00314] ⌈If thresholdLow $\leq$ Input $\leq$ thresholdHigh, then return_value = Out_Val⌋

[SWS_Efx_00315] ⌈Input, thresholdLow and thresholdHigh must have the same resolution and the same physical unit.⌋

[SWS_Efx_00316] ⌈Return_value , Out_Val, Out_LowThresholdVal and Out_High ThresholdVal must have the same resolution and the same physical unit.⌋

[SWS_Efx_00317] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0x9A	uint8 Efx_Hysteresis_u8_u8 (uint8, uint8, uint8, uint8, uint8, uint8)
0x9B	uint16 Efx_Hysteresis_u16_u16(uint16, uint16, uint16, uint16, uint16,uint16)
0x9C	uint32 Efx_Hysteresis_u32_u32 (uint32, uint32,uint32,uint32,uint32,uint32)
0x9D	sint8 Efx_Hysteresis_s8_s8 (sint8,sint8,sint8,sint8,sint8,sint8)
0x9E	sint16 Efx_Hysteresis_s16_s16 (sint16,sint16,sint16,sint16,sint16,sint16)
0x9F	sint32 Efx_Hysteresis_s32_s32 (sint32,sint32,sint32,sint32,sint32,sint32)

⌋

8.3.13.2 Hysteresis center half delta

[SWS_Efx_00320] Definition of API function Efx_HystCenterHalfDelta_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_HystCenterHalfDelta_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_HystCenterHalfDelta_<InTypeMn>_<OutTypeMn> ( <InType> X, <InType> center, <InType> halfDelta, boolean* State )`	
Service ID [hex]	0xA0 to 0xA1, 0x0100 to 0x0103 (see SWS_Efx_00324)	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Input value
	center	Center of hysteresis range
	halfDelta	Half width of hysteresis range
Parameters (inout)	State	Pointer to state value
Parameters (out)	None	
Return value	boolean	Returns TRUE or FALSE depending of input value and state value
Description	Hysteresis with center and left and right side halfDelta switching point.	
Available via	Efx.h	

⌋

[SWS_Efx_00321] ⌈Return value = TRUE, if X > center + halfDelta

Return value = FALSE, if X < center - halfDelta

Return value is former state value if

(center - halfDelta) $\leq$ X $\leq$ (center + halfDelta)⌋

[SWS_Efx_00322] ⌈Parameters X, center and halfDelta should have the same data type.⌋

[SWS_Efx_00323] ⌈State variable shall store the old boolean result.⌋

[SWS_Efx_00324] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xA0	boolean Efx_HystCenterHalfDelta_s32_u8(sint32, sint32, sint32, boolean *)
0xA1	boolean Efx_HystCenterHalfDelta_u32_u8 (uint32, uint32, uint32, boolean *)
0x100	boolean Efx_HystCenterHalfDelta_s8_u8 (sint8, sint8, sint8, boolean *)
0x101	boolean Efx_HystCenterHalfDelta_u8_u8 (uint8, uint8, uint8, boolean *)
0x102	boolean Efx_HystCenterHalfDelta_s16_u8(sint16, sint16, sint16, boolean *)
0x103	boolean Efx_HystCenterHalfDelta_u16_u8(uint16, uint16, uint16, boolean *)

⌋

8.3.13.3 Hysteresis left right

[SWS_Efx_00325] Definition of API function Efx_HystLeftRight_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_HystLeftRight_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_HystLeftRight_<InTypeMn>_<OutTypeMn> ( <InType> X, <InType> Lsp, <InType> Rsp, boolean* State )`	
Service ID [hex]	0xA3 to 0xA4, 0x0104 to 0x0107 (see SWS_Efx_00330)	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Input value
	Lsp	Left switching point
	Rsp	Right switching point
Parameters (inout)	State	Pointer to state value
Parameters (out)	None	
Return value	boolean	Returns TRUE or FALSE depending of input value and state value
Description	Hysteresis with left and right switching point.	
Available via	Efx.h	

⌋

[SWS_Efx_00326] ⌈Return value = TRUE, if X > Rsp (right switching point)

Return value = FALSE, if X < Lsp (left switching point)

Return value is former state value if Lsp $\leq$ X $\leq$ Rsp⌋

[SWS_Efx_00327] ⌈Parameters X, Lsp and Rsp should have the same data type.⌋

[SWS_Efx_00328] ⌈State variable shall store the old boolean result.⌋

[SWS_Efx_00329] ⌈Rsp shall be always greater than Lsp⌋

[SWS_Efx_00330] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xA3	boolean Efx_HystLeftRight_s32_u8 (sint32, sint32, sint32, boolean *)
0xA4	boolean Efx_HystLeftRight_u32_u8 (uint32, uint32, uint32, boolean *)
0x104	boolean Efx_HystLeftRight_s8_u8 (sint8, sint8, sint8, boolean *)
0x105	boolean Efx_HystLeftRight_u8_u8 (uint8, uint8, uint8, boolean *)
0x106	boolean Efx_HystLeftRight_s16_u8(sint16, sint16, sint16, boolean *)
0x107	boolean Efx_HystLeftRight_u16_u8(uint16, uint16, uint16, boolean *)

⌋

8.3.13.4 Hysteresis delta right

[SWS_Efx_00331] Definition of API function Efx_HystDeltaRight_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_HystDeltaRight_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_HystDeltaRight_<InTypeMn>_<OutTypeMn> ( <InType> X, <InType> Delta, <InType> Rsp, boolean* State )`	
Service ID [hex]	0xA5 to 0xA6, 0x0108 to 0x010B (see SWS_Efx_00335)	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Input value
	Delta	Left switching point = rsp - delta
	Rsp	Right switching point
Parameters (inout)	State	Pointer to state value
Parameters (out)	None	
Return value	boolean	Returns TRUE or FALSE depending of input value and state value
Description	Hysteresis with right switching point and delta to left switching point	
Available via	Efx.h	

⌋

[SWS_Efx_00332] ⌈Return value = TRUE if X > Rsp (right switching point)

Return value = FALSE if X < (Rsp - Delta)

Return value is former state value if (Rsp - Delta) $\leq$ X $\leq$ Rsp⌋

[SWS_Efx_00333] ⌈Parameters X, Rsp and Delta should have the same data type.⌋

[SWS_Efx_00334] ⌈State variable shall store the old boolean result.⌋

[SWS_Efx_00335] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xA5	boolean Efx_HystDeltaRight_s32_u8 (sint32, sint32, sint32, boolean *)
0xA6	boolean Efx_HystDeltaRight_u32_u8 (uint32, uint32, uint32, boolean *)
0x108	boolean Efx_HystDeltaRight_s8_u8 (sint8, sint8, sint8, boolean *)
0x109	boolean Efx_HystDeltaRight_u8_u8 (uint8, uint8, uint8, boolean *)
0x10A	boolean Efx_HystDeltaRight_s16_u8(sint16, sint16, sint16, boolean *)
0x10B	boolean Efx_HystDeltaRight_u16_u8(uint16, uint16, uint16, boolean *)

⌋

8.3.13.5 Hysteresis left delta

[SWS_Efx_00336] Definition of API function Efx_HystLeftDelta_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_HystLeftDelta_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_HystLeftDelta_<InTypeMn>_<OutTypeMn> ( <InType> X, <InType> Lsp, <InType> Delta, boolean* State )`	
Service ID [hex]	0xA7 to 0xA8, 0x010C to 0x010E (see SWS_Efx_00340)	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Input value
	Lsp	Left switching point
	Delta	Right switching point = lsp + delta
Parameters (inout)	State	Pointer to state value
Parameters (out)	None	
Return value	boolean	Returns TRUE or FALSE depending of input value and state value
Description	Hysteresis with left switching point and delta to right switching point.	

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Available via	Efx.h

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[SWS_Efx_00337] ⌈Return value is TRUE if X > (Lsp + Delta)

Return value is FALSE if X < Lsp

Return value is former state value if Lsp ≤ X ≤ (Lsp + Delta)⌋

[SWS_Efx_00338] ⌈Parameters X, Lsp and Delta should have the same data type.⌋

[SWS_Efx_00339] ⌈State variable shall store the old boolean result.⌋

[SWS_Efx_00340] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xA7	boolean Efx_HystLeftDelta_s32_u8 (sint32, sint32, sint32, boolean *)
0xA8	boolean Efx_HystLeftDelta_u32_u8 (uint32, uint32, uint32, boolean *)
0x10C	boolean Efx_HystLeftDelta_s8_u8 (sint8, sint8, sint8, boolean *)
0x10D	boolean Efx_HystLeftDelta_u8_u8 (uint8, uint8, uint8, boolean *)
0x10E	boolean Efx_HystLeftDelta_s16_u8(sint16, sint16, sint16, boolean *)
0x10F	boolean Efx_HystLeftDelta_u16_u8(uint16, uint16, uint16, boolean *)

⌋

8.3.14 Debounce routines

8.3.14.1 Efx_Debounce

[SWS_Efx_00355] Definition of API function Efx_Debounce_u8_u8 ⌈

Service Name	Efx_Debounce_u8_u8	
Syntax	`boolean Efx_Debounce_u8_u8 ( boolean X, Efx_DebounceState_Type * State, const Efx_DebounceParam_Type * Param, sint32 dT )`	
Service ID [hex]	0xB0	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Input value
	Param	Pointer to state structure of type Efx_DebounceParam_Type

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	dT	Sample Time
Parameters (inout)	State	Pointer to state structure of type Efx_DebounceState_Type
Parameters (out)	None	
Return value	boolean	Returns the debounced input value
Description	This routine debounces a digital input signal and returns the state of the signal as a boolean value.	
Available via	Efx.h	

⌋

[SWS_Efx_00356] ⌈If(X != State->XOld) then check start debouncing.⌋

[SWS_Efx_00357] ⌈If transition occurs from FALSE to TRUE (i.e State->XOld = FALSE and X = TRUE), then use Param->TimeLowHigh as debouncing time; otherwise use Param->TimeHighLow.⌋

[SWS_Efx_00358] ⌈State->Timer is incremented with sample time for debouncing input signal.

Once reached to the set period, old state is updated with X.

State->Timer += dT;

If (State->Timer $\geq$ (TimePeriod * 10000))

State->XOld = X, and stop the timer, State->Timer = 0

where TimePeriod = Param->TimeLowHigh or Param->TimeHighLow⌋

[SWS_Efx_00359] ⌈Old value shall be returned as a output value. Current input is stored to old state.

Return value = State->XOld

State->XOld = X⌋

[SWS_Efx_00360] ⌈Resolution of dT is 10^(-6) seconds per increment of 1 data representation unit⌋

Structure definition for function argument

[SWS_Efx_00361] Definition of datatype Efx_DebounceParam_Type ⌈

Name	Efx_DebounceParam_Type	
Kind	Structure	
Elements	TimeHighLow	
	Type	sint16
	Comment	Time for a High to Low transition, given in 10ms steps
	TimeLowHigh	

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	Type	sint16
	Comment	Time for a Low to High transition, given in 10ms steps
Description	Structure definition for Debounce routine	
Available via	Efx.h	

⌋

[SWS_Efx_00835] Definition of datatype Efx_DebounceState_Type ⌈

Name	Efx_DebounceState_Type	
Kind	Structure	
Elements	XOld	
	Type	boolean
	Comment	Old input value from last call
	Timer	
	Type	sint32
	Comment	Timer for internal state
Description	Structure definition for Debounce routine	
Available via	Efx.h	

⌋

8.3.14.2 Efx_DebounceInit

[SWS_Efx_00362] Definition of API function Efx_DebounceInit ⌈

Service Name	Efx_DebounceInit	

Syntax	`void Efx_DebounceInit (`
	`  Efx_DebounceState_Type* State,`
	`  boolean X`
	`)`	

Service ID [hex]	0xB1	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	X	Initial value for the input state
Parameters (inout)	None	
Parameters (out)	State	Pointer to state structure of type Efx_DebounceState_Type
Return value	void	No return value
Description	This routine call shall stop the debouncing timer.	
Available via	Efx.h	

⌋

[SWS_Efx_00363] ⌈State->Timer = 0⌋

[SWS_Efx_00364] ⌈Sets the input state to the given init value.

State->XOld = X;⌋

8.3.14.3 Efx_DebounceSetparam

[SWS_Efx_00365] Definition of API function Efx_DebounceSetParam ⌈

Service Name	Efx_DebounceSetParam	

Syntax	`void Efx_DebounceSetParam (`
	`  Efx_DebounceParam_Type * Param,`
	`  sint16 THighLow,`
	`  sint16 TLowHigh`
	`)`	

Service ID [hex]	0xB2	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	THighLow	Value for TimeHighLow of Efx_DebounceParam_Type
	TLowHigh	Value for TimeLowHigh of Efx_DebounceParam_Type
Parameters (inout)	None	
Parameters (out)	Param	Pointer to state structure of type Efx_DebounceParam_Type
Return value	void	No return value
Description	This routine sets timing parameters, time for high to low transition and time for low to high for debouncing.	
Available via	Efx.h	

⌋

[SWS_Efx_00366] ⌈Param-> TimeHighLow = THighLow

Param-> TimeLowHigh = TLowHigh⌋

8.3.15 Ascending Sort Routine

[SWS_Efx_00370] Definition of API function Efx_SortAscend_<InTypeMn> ⌈

Service Name	Efx_SortAscend_<InTypeMn>	

Syntax	`void Efx_SortAscend_<InTypeMn> (`
	`  <OutType> * Array,`
	`  uint16 Num`
	`)`	

Service ID [hex]	0xB4 to 0xB9	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Num	Size of an data array
Parameters (inout)	Array	Pointer to an data array
Parameters (out)	None	
Return value	void	No return value
Description	The sorting algorithm modifies the given input array and rearranges data in ascending order.	
Available via	Efx.h	

⌋

Example for unsigned array :

Input array : uint16 Array [5] = [42, 10, 88, 8, 15]

Result : Array will be sorted to [8, 10, 15, 42, 88]

Example for signed array :

Input array : sint16 Array [5] = [-42, -10, 88, 8, 15]

Result : Array will be sorted to [-42, -10, 8, 15, 88]

[SWS_Efx_00372] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xB4	void Efx_SortAscend_s8 (sint8*, uint16)
0xB5	void Efx_SortAscend_u8 (uint8*, uint16)
0xB6	void Efx_SortAscend_u16 (uint16*, uint16)
0xB7	void Efx_SortAscend_s16 (sint16*, uint16)
0xB8	void Efx_SortAscend_u32 (uint32*, uint16)
0xB9	void Efx_SortAscend_s32 (sint32*, uint16)

⌋

8.3.16 Descending Sort Routine

[SWS_Efx_00373] Definition of API function Efx_SortDescend_<InTypeMn> ⌈

Service Name	Efx_SortDescend_<InTypeMn>	
Syntax	`void Efx_SortDescend_<InTypeMn> ( <OutType> * Array, uint16 Num )`	
Service ID [hex]	0xBA to 0xBF	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Num	Size of an data array
Parameters (inout)	Array	Pointer to an data array
Parameters (out)	None	
Return value	void	No return value
Description	The sorting algorithm modifies the given input array and rearranges data in descending order.	
Available via	Efx.h	

⌋

Example for unsigned array :

Input array : uint16 Array [5] = [42, 10, 88, 8, 15]

Result : Array will be sorted to [88, 42, 15, 10, 8]

Example for signed array :

Input array : sint16 Array [5] = [-42, -10, 88, 8, 15]

Result : Array will be sorted to [88, 15, 8, -10, -42]

[SWS_Efx_00375] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xBF	void Efx_SortDescend_s8 (sint8*, uint16)
0xBA	void Efx_SortDescend_u8 (uint8*, uint16)
0xBB	void Efx_SortDescend_u16 (uint16*, uint16)
0xBC	void Efx_SortDescend_s16 (sint16*, uint16)
0xBD	void Efx_SortDescend_u32 (uint32*, uint16)
0xBE	void Efx_SortDescend_s32 (sint32*, uint16)

⌋

8.3.17 Median sort routine

[SWS_Efx_00376] Definition of API function Efx_MedianSort_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_MedianSort_<InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_MedianSort_<InTypeMn>_<OutTypeMn> ( <InType>* Array, uint8 N )`	
Service ID [hex]	0xC0 to 0xC4, 0xC8	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	N	Size of an array
Parameters (inout)	Array	Pointer to an array
Parameters (out)	None	
Return value	<OutType>	Return value of the function
Description	Sort an array and return its median value	
Available via	Efx.h	

⌋

[SWS_Efx_00377] ⌈This routine sorts values of an array in ascending order. Input array passed by the pointer shall have sorted values after this routine call.⌋

For example:

Input array [5] = [42, 10, 88, 8, 15]

Sorted array[5] = [8, 10, 15, 42, 88]

[SWS_Efx_00378] ⌈Returns the median value of sorted array in case of N is even.

Result = (Sorted_array[N/2] + Sorted_array[(N/2) - 1]) / 2⌋

For example:

Sorted_array[4] = [8, 10, 15, 42]

Result = (15 + 10) / 2 = 12

[SWS_Efx_00440] ⌈Returns the median value of sorted array in case of N is odd.

Return_Value = Sorted_array [N/2] = 15⌋

For example:

Sorted_array[5] = [8, 10, 15, 42, 88]

Result = 15

[SWS_Efx_00441] ⌈In above calculation, N/2 shall be rounded towards zero.⌋

[SWS_Efx_00379] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xC0	uint8 Efx_MedianSort_u8_u8(uint8*, uint8)
0xC1	uint16 Efx_MedianSort_u16_u16(uint16*, uint8)
0xC2	sint16 Efx_MedianSort_s16_s16(sint16*, uint8)
0xC3	sint8 Efx_MedianSort_s8_s8(sint8*, uint8)
0xC4	uint32 Efx_MedianSort_u32_u32(uint32*, uint8)
0xC8	sint32 Efx_MedianSort_s32_s32(sint32*, uint8)

⌋

8.3.18 Edge detection routines

8.3.18.1 Edge bipol detection

[SWS_Efx_00380] Definition of API function Efx_EdgeBipol_u8_u8 ⌈

Service Name	Efx_EdgeBipol_u8_u8	

Syntax	`boolean Efx_EdgeBipol_u8_u8 (`
	`  boolean Inp_Val,`
	`  boolean* Old_Val`
	`)`	

Service ID [hex]	0xC5	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Inp_Val	Actual value of the signal
Parameters (inout)	Old_Val	Pointer to the value of the signal from the last call
Parameters (out)	None	
Return value	boolean	Returns TRUE when the signal has changed since the last call
Description	This routine detects whether a signal has changed since the last call and returns TRUE. If signal has not changed then returns FALSE.	
Available via	Efx.h	

⌋

[SWS_Efx_00381] ⌈if (Inp_Val != *Old_Val)

return value = TRUE

else

return value = FALSE.⌋

8.3.18.2 Edge falling detection

[SWS_Efx_00382] Definition of API function Efx_EdgeFalling_u8_u8 ⌈

Service Name	Efx_EdgeFalling_u8_u8	
Syntax	`boolean Efx_EdgeFalling_u8_u8 ( boolean Inp_Val, boolean* Old_Val )`	
Service ID [hex]	0xC6	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Inp_Val	Actual value of the signal
Parameters (inout)	Old_Val	Pointer to the value of the signal from the last call
Parameters (out)	None	
Return value	boolean	Returns TRUE when the signal has falling edge
Description	Returns TRUE when the signal has a falling edge, i.e. the signal was TRUE at the last call and FALSE at the actual call of this routine	
Available via	Efx.h	

⌋

[SWS_Efx_00383] ⌈Return value = TRUE, If (*Old_Val == TRUE && Inp_Val == FALSE)

Return value = FALSE, otherwise.⌋

8.3.18.3 Edge rising detection

[SWS_Efx_00384] Definition of API function Efx_EdgeRising_u8_u8 ⌈

Service Name	Efx_EdgeRising_u8_u8	

Syntax	`boolean Efx_EdgeRising_u8_u8 (`
	`  boolean Inp_Val,`
	`  boolean* Old_Val`
	`)`	

Service ID [hex]	0xC7	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Inp_Val	Actual value of the signal
Parameters (inout)	Old_Val	Pointer to the value of the signal from the last call
Parameters (out)	None	
Return value	boolean	Returns TRUE when the signal has rising edge
Description	Returns TRUE when the signal has a rising edge, i.e. the signal was FALSE at the last call and TRUE at the actual call of this routine	
Available via	Efx.h	

⌋

[SWS_Efx_00385] ⌈Return value = TRUE, If (*Old_Val == FALSE && Inp_Val == TRUE)

Return value = FALSE, otherwise.⌋

8.3.19 Interval routines

8.3.19.1 Interval Closed

[SWS_Efx_00386] Definition of API function Efx_IntervalClosed_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_IntervalClosed_<InTypeMn>_<OutTypeMn>	

Syntax	`boolean Efx_IntervalClosed_<InTypeMn>_<OutTypeMn> (`
	`  <InType> MinVal,`
	`  <InType> InpVal,`
	`  <InType> MaxVal`
	`)`	

Service ID [hex]	0xCA to 0xCB	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	MinVal	Minimum limit value
	InpVal	Actual value of the signal
	MaxVal	Maximum limit value
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	Returns TRUE when MinVal <= InpVal <= MaxVal

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Description	This routine compares a value 'InpVal' with lower and upper limit 'MinVal' and 'MaxVal' respectively.
Available via	Efx.h

⌋

[SWS_Efx_00387] ⌈Return value = TRUE, if (MinVal ≤ InpVal ≤ MaxVal)

Return value = FALSE, otherwise.⌋

[SWS_Efx_00388] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xCA	boolean Efx_IntervalClosed_s32_u8(sint32, sint32, sint32)
0xCB	boolean Efx_IntervalClosed_u32_u8(uint32, uint32, uint32)

⌋

8.3.19.2 Interval Open

[SWS_Efx_00390] Definition of API function Efx_IntervalOpen_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_IntervalOpen_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_IntervalOpen_<InTypeMn>_<OutTypeMn> ( sint32 MinVal, sint32 InpVal, sint32 MaxVal )`	
Service ID [hex]	0xCC to 0xCD	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	MinVal	Minimum limit value
	InpVal	Actual value of the signal
	MaxVal	Maximum limit value
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	Returns TRUE when MinVal < InpVal < MaxVal
Description	This routine compares a value 'InpVal' with lower and upper limit 'MinVal' and 'MaxVal' respectively.	
Available via	Efx.h	

⌋

[SWS_Efx_00391] ⌈Return value = TRUE, if (MinVal < InpVal < MaxVal)

Return value = FALSE, otherwise.⌋

[SWS_Efx_00392] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xCC	boolean Efx_IntervalOpen_s32_u8(sint32, sint32, sint32)
0xCD	boolean Efx_IntervalOpen_u32_u8(uint32, uint32, uint32)

⌋

8.3.19.3 Interval Left Open

[SWS_Efx_00393] Definition of API function Efx_IntervalLeftOpen_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_IntervalLeftOpen_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_IntervalLeftOpen_<InTypeMn>_<OutTypeMn> ( sint32 MinVal, sint32 InpVal, sint32 MaxVal )`	
Service ID [hex]	0xCE to 0xCF	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	MinVal	Minimum limit value
	InpVal	Actual value of the signal
	MaxVal	Maximum limit value
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	Returns TRUE when MinVal < InpVal <= MaxVal
Description	This routine compares a value 'InpVal' with lower and upper limit 'MinVal' and 'MaxVal' respectively.	
Available via	Efx.h	

⌋

[SWS_Efx_00394] ⌈Return value = TRUE, if (MinVal < InpVal $\leq$ MaxVal)

Return value = FALSE, otherwise.⌋

[SWS_Efx_00395] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xCE	boolean Efx_IntervalLeftOpen_s32_u8(sint32, sint32, sint32)
0xCF	boolean Efx_IntervalLeftOpen_u32_u8(uint32, uint32, uint32)

⌋

8.3.19.4 Interval Right Open

[SWS_Efx_00396] Definition of API function Efx_IntervalRightOpen_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_IntervalRightOpen_<InTypeMn>_<OutTypeMn>	
Syntax	`boolean Efx_IntervalRightOpen_<InTypeMn>_<OutTypeMn> ( sint32 MinVal, sint32 InpVal, sint32 MaxVal )`	
Service ID [hex]	0xD0 to 0xD1	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	MinVal	Minimum limit value
	InpVal	Actual value of the signal
	MaxVal	Maximum limit value
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	Returns TRUE when MinVal <= InpVal < MaxVal
Description	This routine compares a value 'InpVal' with lower and upper limit 'MinVal' and 'MaxVal' respectively.	
Available via	Efx.h	

⌋

[SWS_Efx_00397] ⌈Return value = TRUE, if (MinVal $\leq$ InpVal < MaxVal)

Return value = FALSE, otherwise.⌋

[SWS_Efx_00398] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xD0	boolean Efx_IntervalRightOpen_s32_u8(sint32, sint32, sint32)
0xD1	boolean Efx_IntervalRightOpen_u32_u8(uint32, uint32, uint32)

⌋

8.3.20 Counter routines

[SWS_Efx_00399] Definition of API function Efx_CounterSet_<InTypeMn> ⌈

Service Name	Efx_CounterSet_<InTypeMn>
Syntax	`void Efx_CounterSet_<InTypeMn> ( <InType>* CounterVal, <InType> Val )`
Service ID [hex]	0xD2 to 0xD4

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Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Val	Initial value
Parameters (inout)	CounterVal	Pointer to input value
Parameters (out)	None	
Return value	None	
Description	The CounterSet routines initialise counter value with initial value • CounterVal = Val;	
Available via	Efx.h	

⌋

[SWS_Efx_00404] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xD2	void Efx_CounterSet_u16 (uint16*, uint16)
0xD3	void Efx_CounterSet_u32 (uint32*, uint32)
0xD4	void Efx_CounterSet_u8 (uint8*, uint8)

⌋

[SWS_Efx_00400] Definition of API function Efx_Counter_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Counter_<InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_Counter_<InTypeMn>_<OutTypeMn> ( <InType> * CounterVal )`	
Service ID [hex]	0xD5 to 0xD7	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	CounterVal	Pointer to input value
Parameters (out)	None	
Return value	<OutType>	Returns value is the new value of the parameter CounterVal.
Description	The counter routines increments the value of the parameter CounterVal by 1.	
Available via	Efx.h	

⌋

[SWS_Efx_00401] ⌈The return value is the new value of the parameter CounterVal.

* CounterVal ++;

Return value = *CounterVal;⌋

[SWS_Efx_00402] ⌈In case of saturation, counter value shall not be reset to 0 and shall not be incremented.

Return value = Saturated value of the counter data type⌋

[SWS_Efx_00403] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xD5	uint8 Efx_Counter_u8_u8 (uint8 *)
0xD6	uint16 Efx_Counter_u16_u16 (uint16 *)
0xD7	uint32 Efx_Counter_u32_u32 (uint32 *)

⌋

8.3.21 Flip-Flop routine

[SWS_Efx_00405] Definition of API function Efx_RSFlipFlop ⌈

Service Name	Efx_RSFlipFlop	

Syntax	`boolean Efx_RSFlipFlop (`
	`  boolean R_Val,`
	`  boolean S_Val,`
	`  boolean* State_Val`
	`)`	

Service ID [hex]	0xEF	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	R_Val	Reset switch - changes the flip flop state to FALSE
	S_Val	Set switch - changes the flip flop state to TRUE
Parameters (inout)	State_Val	Pointer to flip-flop state variable
Parameters (out)	None	
Return value	boolean	Returns the new state of the flip flop
Description	RS flip flop can be set and reset via input switches R_Val and S_Val.	
Available via	Efx.h	

⌋

[SWS_Efx_00406] ⌈The reset switch is higher prior than the set switch,

e.g. R_Val = TRUE,

S_Val = TRUE

Then state and return value = FALSE⌋

[SWS_Efx_00407] ⌈Reset condition :

R_Val = TRUE,

S_Val = FALSE

Then state and return value = FALSE⌋

[SWS_Efx_00408] ⌈Set condition :

R_Val = FALSE,

S_Val = TRUE

Then state and return value = TRUE⌋

[SWS_Efx_00409] ⌈Invalid condition :

R_Val = FALSE,

S_Val = FALSE

Then state and return value are unchanged⌋

8.3.22 Limiter routines

[SWS_Efx_00410] Definition of API function Efx_TypeLimiter_<InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_TypeLimiter_<InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_TypeLimiter_<InTypeMn>_<OutTypeMn> ( <InType> Input_Val )`	
Service ID [hex]	0xD8 to 0xE9, 0x0125 to 0x0132	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Input_Val	Input value to be limited
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Returns the limited value for input
Description	limiter routine	
Available via	Efx.h	

⌋

[SWS_Efx_00411] ⌈Input value shall be saturated according to the data type of the return parameter.

e.g. If return type is sint16 and input data range is uint32, then output value will be limited to sint16 data range.⌋

[SWS_Efx_00412] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xD8	uint8 Efx_TypeLimiter_s32_u8 (sint32)
0xD9	uint16 Efx_TypeLimiter_s32_u16 (sint32)
0xDA	uint32 Efx_TypeLimiter_s32_u32 (sint32)
0xDB	sint8 Efx_TypeLimiter_s32_s8 (sint32)
0xDC	sint16 Efx_TypeLimiter_s32_s16 (sint32)
0xDD	uint8 Efx_TypeLimiter_u32_u8 (uint32)
0xDE	uint16 Efx_TypeLimiter_u32_u16 (uint32)
0xDF	sint32 Efx_TypeLimiter_u32_s32 (uint32)

▽

△

Service ID[hex]	Syntax
0xE0	sint8 Efx_TypeLimiter_u32_s8 (uint32)
0xE1	sint16 Efx_TypeLimiter_u32_s16 (uint32)
0xE2	uint8 Efx_TypeLimiter_s16_u8 (sint16)
0xE3	uint16 Efx_TypeLimiter_s16_u16 (sint16)
0xE4	sint8 Efx_TypeLimiter_s16_s8 (sint16)
0xE5	uint8 Efx_TypeLimiter_u16_u8 (uint16)
0xE6	sint8 Efx_TypeLimiter_u16_s8 (uint16)
0xE7	sint16 Efx_TypeLimiter_u16_s16 (uint16)
0xE8	uint8 Efx_TypeLimiter_s8_u8 (sint8)
0xE9	sint8 Efx_TypeLimiter_u8_s8 (uint8)
0x125	sint8 Efx_TypeLimiter_s64_s8(sint64)
0x126	uint8 Efx_TypeLimiter_s64_u8(sint64)
0x127	sint16 Efx_TypeLimiter_s64_s16(sint64)
0x128	uint16 Efx_TypeLimiter_s64_u16(sint64)
0x129	sint32 Efx_TypeLimiter_s64_s32(sint64)
0x12A	uint32 Efx_TypeLimiter_s64_u32(sint64)
0x12B	uint64 Efx_TypeLimiter_s64_u64(sint64)
0x12C	sint8 Efx_TypeLimiter_u64_s8(uint64)
0x12D	uint8 Efx_TypeLimiter_u64_u8(uint64)
0x12E	sint16 Efx_TypeLimiter_u64_s16(uint64)
0x12F	uint16 Efx_TypeLimiter_u64_u16(uint64)
0x130	sint32 Efx_TypeLimiter_u64_s32(uint64)
0x131	uint32 Efx_TypeLimiter_u64_u32(uint64)
0x132	sint64 Efx_TypeLimiter_u64_s64(uint64)

⌋

8.3.23 64 bits functions

8.3.23.1 General requirements

The usage of 64bits data must remain an exception in the code if the requirement cannot be reached by another mean.

8.3.23.2 Absolute value

[SWS_Efx_10001] Definition of API function Efx_Abs_<InTypeMn1>_<OutTypeMn> ⌈

Service Name	Efx_Abs_<InTypeMn1>_<OutTypeMn>	
Syntax	`<OutType> Efx_Abs_<InTypeMn1>_<OutTypeMn> ( <InType1> x_value )`	
Service ID [hex]	0x0110 to 0x0111	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result of the interpolation
Description	This routine computes the absolute value of a signed value	
Available via	Efx.h	

⌋

[SWS_Efx_10002] ⌈

This routine computes the absolute value of a signed value: Return-value = |x_value|⌋

[SWS_Efx_10003] ⌈

Return-value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_10004] Here is the list of implemented functions. ⌈

Service ID[hex]	Service prototype
0x110	sint64 Efx_Abs_s64_s64(sint64)
0x111	uint64 Efx_Abs_s64_u64(sint64)

⌋

8.3.23.3 Additions

[SWS_Efx_00423] Definition of API function Efx_Add_<InTypeMn><InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Add_<InTypeMn><InTypeMn>_<OutTypeMn>
Syntax	`<OutType> Efx_Add_<InTypeMn><InTypeMn>_<OutTypeMn> ( <InType> x_value, <InType> y_value )`
Service ID [hex]	0xF0 to 0xF2

▽

△

Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
	y_value	Second argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result of the calculation
Description	This service makes an addition between the two arguments The addition is protected against the overflow.	
Available via	Efx.h	

⌋

[SWS_Efx_00424] ⌈Return value = x_value + y_value⌋

[SWS_Efx_00843] ⌈Return-value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00425] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xF0	sint64 Efx_Add_s64s32_s64(sint64, sint32)
0xF1	sint64 Efx_Add_s64u32_s64(sint64, uint32)
0xF2	sint64 Efx_Add_s64s64_s64(sint64, sint64)
0x112	uint64 Efx_Add_u64u64_u64(uint64, uint64)

⌋

8.3.23.4 Subtractions

[SWS_Efx_10006] Definition of API function Efx_Sub_<InTypeMn1><InType Mn2>_<OutTypeMn> ⌈

Service Name	Efx_Sub_<InTypeMn1><InTypeMn2>_<OutTypeMn>	

Syntax	`<OutType> Efx_Sub_<InTypeMn1><InTypeMn2>_<OutTypeMn> (`
	`  <InType1> x_value,`
	`  <InType2> y_value`
	`)`	

Service ID [hex]	0x0113 to 0x0116	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
	y_value	Second argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result of the interpolation

▽

△

Description	This routine makes a subtraction between the two arguments.
Available via	Efx.h

⌋

[SWS_Efx_10007] ⌈

This routine makes a subtraction between the two arguments:

Return-value = x_value - y_value.⌋

[SWS_Efx_10008] ⌈

Return-value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_10009] Here is the list of implemented functions. ⌈

Service ID[hex]	Routine prototype
0x113	sint64 Efx_Sub_s64s32_s64(sint64, sint32)
0x114	sint64 Efx_Sub_s64u32_s64(sint64, uint32)
0x115	sint64 Efx_Sub_s64s64_s64(sint64, sint64)
0x116	uint64 Efx_Sub_u64u64_u64(uint64, uint64)

⌋

8.3.23.5 Multiplications

[SWS_Efx_00426] Definition of API function Efx_Mul_<InTypeMn><InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Mul_<InTypeMn><InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_Mul_<InTypeMn><InTypeMn>_<OutTypeMn> ( <InType> x_value, <InType> y_value )`	
Service ID [hex]	0xF3 to 0xF5	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
	y_value	Second argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result of the calculation
Description	This service makes a multiplication between the two arguments The multiplication is protected against the overflow.	
Available via	Efx.h	

⌋

[SWS_Efx_00427] ⌈Return value = x_value * y_value⌋

[SWS_Efx_00844] ⌈Return-value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00428] Here is the list of implemented functions. ⌈

Service ID[hex]	Syntax
0xF3	sint64 Efx_Mul_s64u32_s64(sint64, uint32)
0xF4	sint64 Efx_Mul_s64s32_s64(sint64, sint32)
0xF5	sint64 Efx_Mul_s64s64_s64(sint64, sint64)
0x117	uint64 Efx_Mul_u64u32_u64(uint64, uint32)
0x118	uint64 Efx_Mul_u64u64_u64(uint64, uint64)

⌋

8.3.23.6 Division

[SWS_Efx_00429] Definition of API function Efx_Div_<InTypeMn><InTypeMn>_<OutTypeMn> ⌈

Service Name	Efx_Div_<InTypeMn><InTypeMn>_<OutTypeMn>	
Syntax	`<OutType> Efx_Div_<InTypeMn><InTypeMn>_<OutTypeMn> ( <InType> x_value, <InType> y_value )`	
Service ID [hex]	0x00F6 to 0x00FB, 0x0119 to 0x0121, 0x0133	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
	y_value	Second argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	<OutType>	Result of the calculation
Description	These services make a division between the two arguments	
Available via	Efx.h	

⌋

[SWS_Efx_00430] ⌈Return value = x_value / y_value⌋

[SWS_Efx_00431] ⌈The result after division by zero is defined by:

If x_value $\geq$ 0 then the function returns the maximum value of the output type

If x_value < 0 then the function returns the minimum value of the output type⌋

[SWS_Efx_00433] ⌈The result is rounded towards 0.⌋

[SWS_Efx_00845] ⌈Return-value shall be saturated to boundary values in the event of negative or positive overflow.⌋

[SWS_Efx_00434] ⌈

Service ID[hex]	Syntax
0xF6	sint64 Efx_Div_s64u32_s64(sint64, uint32)
0xF7	sint64 Efx_Div_s64s32_s64(sint64, sint32)
0xF8	sint32 Efx_Div_s64s32_s32 (sint64, sint32)
0xF9	uint32 Efx_Div_s64s32_u32 (sint64, sint32)
0xFA	sint32 Efx_Div_s64u32_s32 (sint64, uint32)
0xFB	uint32 Efx_Div_s64u32_u32 (sint64, uint32)
0x119	uint32 Efx_Div_u64u32_u32 (uint64, uint32)
0x11A	sint32 Efx_Div_s64s32_s32(sint64, sint32)
0x11B	uint64 Efx_Div_u64u32_u64 (uint64, uint32)
0x11C	sint64 Efx_Div_s64u32_s64(sint64, uint32)
0x11D	sint64 Efx_Div_s64s32_s64(sint64, sint32)
0x11E	sint64 Efx_Div_s64u64_s64(sint64, uint64)
0x11F	sint64 Efx_Div_u64s32_s64(uint64, sint32)
0x120	sint64 Efx_Div_s64s64_s64 (sint64, sint64)
0x121	uint64 Efx_Div_u64u64_u64 (uint64, uint64)
0x133	sint64 Efx_Div_u64s64_s64(uint64, sint64)

⌋

8.3.23.7 Modulo

[SWS_Efx_10015] Definition of API function Efx_Mod_<TypeMn> ⌈

Service Name	Efx_Mod_<TypeMn>	
Syntax	`<Type> Efx_Mod_<TypeMn> ( <Type> x_value, <Type> y_value )`	
Service ID [hex]	0x0122 to 0x0123	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	Numerator
	y_value	Denominator
Parameters (inout)	None	
Parameters (out)	None	
Return value	<Type>	Result of the interpolation
Description	This routine returns the remainder of the division x_value / y_value if y_value is not zero.	
Available via	Efx.h	

⌋

[SWS_Efx_10011] ⌈

IF y_value is zero, the result is zero.⌋

[SWS_Efx_10012] ⌈

In other cases, Return-value = x_value mod y_value⌋

[SWS_Efx_10013] ⌈The sign of the remainder is the same than the sign of x_value.⌋

[SWS_Efx_10014] Here is the list of implemented functions. ⌈

Service ID[hex]	Routine prototype
0x122	uint64 Efx_Mod_u64u64_u64 (uint64, uint64)
0x123	sint64 Efx_Mod_s64s64_s64 (sint64, sint64)

⌋

8.3.23.8 Signum Function

[SWS_Efx_91002] Definition of API function Efx_Sgn_s64_s8 ⌈

Service Name	Efx_Sgn_s64_s8	
Syntax	`sint8 Efx_Sgn_s64_s8 ( sint64 x_value )`	
Service ID [hex]	0x0124	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	x_value	First argument
Parameters (inout)	None	
Parameters (out)	None	
Return value	sint8	Sign of the first argument
Description	Signum function. Extract the sign of an integer value.	
Available via	Efx.h	

⌋

[SWS_Efx_00435] ⌈

Extract the sign of an integer value. It is defined as follows:

Return-value = {-1, if x_value < 0; 0, if x_value == 0; 1, if x_value > 0}⌋

8.4 Scheduled functions

The EfX library does not have scheduled functions.

8.5 Expected interfaces

None

8.5.1 Mandatory Interfaces

None

8.5.2 Optional Interfaces

None

8.5.3 Configurable interfaces

None

9 Sequence diagrams

Not applicable.

10 Configuration specification

In general, this chapter defines configuration parameters and their clustering into containers. In order to support the specification Chapter 10.1 describes fundamentals. It also specifies a template (table) you shall use for the parameter specification. We intend to leave Chapter 10.1 in the specification to guarantee comprehension.

Chapter 10.2 specifies the structure (containers) and the parameters of the module EFXLibrary.

Chapter 10.3 specifies published information of the module EFXLibrary.

10.1 How to read this chapter

For details refer to [3] Chapter 10.1 *"Introduction to configuration specification"*.

10.2 Containers and configuration parameters

[SWS_Efx_00818] ⌈The Efx library shall not have any configuration options that may affect the functional behavior of the routines. I.e. for a given set of input parameters, the outputs shall be always the same. For example, the returned value in case of error shall not be configurable.⌋

However, a library vendor is allowed to add specific configuration options concerning library implementation, e.g. for resources consumption optimization.

10.3 Published Information

For details refer to [3] Chapter 10.3 *"Published Information"*.

[SWS_Efx_00814]

Upstream requirements: SRS_BSW_00402, SRS_BSW_00374, SRS_BSW_00379

⌈The standardized common published parameters as required by SRS_BSW_00402 in the General Requirements on Basic Software Modules [4] shall be published within the header file of this module and need to be provided in the BSW Module Description. The according module abbreviation can be found in the List of Basic Software Modules.⌋

A Not applicable requirements

[SWS_Efx_00822]

Upstream requirements: SRS_BSW_00448

⌈These requirements are not applicable to this specification.⌋

B Change history of AUTOSAR traceable items

Please note that the lists in this chapter also include specification items that have been removed from the specification in a later version. These specification items do not appear as hyperlinks in the document.

B.1 Traceable item history of this document according to AUTOSAR Release R23-11

B.1.1 Added Specification Items in R23-11

none

B.1.2 Changed Specification Items in R23-11

none

B.1.3 Deleted Specification Items in R23-11

none

B.2 Traceable item history of this document according to AUTOSAR Release R24-11

B.2.1 Added Specification Items in R24-11

none

B.2.2 Changed Specification Items in R24-11

[SWS_Efx_00007] [SWS_Efx_00023] [SWS_Efx_00027] [SWS_Efx_00031] [SWS_Efx_00036] [SWS_Efx_00410] [SWS_Efx_91002]

B.2.3 Deleted Specification Items in R24-11

none

B.3 Traceable item history of this document according to AUTOSAR Release R25-11

B.3.1 Added Specification Items in R25-11

none

B.3.2 Changed Specification Items in R25-11

[SWS_Efx_00185] [SWS_Efx_00240] [SWS_Efx_00243] [SWS_Efx_00246]

B.3.3 Deleted Specification Items in R25-11

none

B.4 Traceable item history of this document according to AUTOSAR Release R26-11

B.4.1 Added Specification Items in R26-11

none

B.4.2 Changed Specification Items in R26-11

[SWS_Efx_00434] [SWS_Efx_91001]

B.4.3 Deleted Specification Items in R26-11

[SWS_Efx_00815] [SWS_Efx_00816] [SWS_Efx_10005] [SWS_Efx_10010]