```
::::::::::::::
cordic.scfix.cpp
::::::::::::::
//*****************************************************************************
//  Test of SystemC Fixpoint CORDIC
//
//  Licensing:
//    This code is distributed under GNU LGPL license.
//
//  Modified:
//    2012.07.05
//
//  Author:
//    Based on SCLive 3.0 and www.asic-world.com example codes
//
//    Modifications by Young W. Lim
//
//
//*****************************************************************************


#define SC_INCLUDE_FX

#include <systemc.h>
#include <iostream>
#include <iomanip>

#include "cordic.hpp"

using namespace std;

int sc_main(int argc, char * argv[]) {

  double pi = 3.141592653589793;
  double K = 1.646760258121;
  int nIter = 10;

  double x, y, z;

  double theta, eacos, easin;

  //-----------------------------------------------------------------------------
  // printf ("\nGrinding on [K, 0, 0]\n");
  // Circular (X0C, 0L, 0L);
  //-----------------------------------------------------------------------------
  theta = 0.0;
  x = 1 / K;
  y = 0.0;
  z = theta;
  cout << "-----------------------------------------------\n";
  cout << z * 180. / pi << " deg (" << z << " rad ) \n";
  cout << "xi =" << x << " yi =" << y << " zi=" << z << "\n";

  cordic(&x, &y, &z, nIter);

  cout  << "xo =" << x << " yo =" << y << " zo=" << z << "\n";

  eacos = (cos(theta) - x) / cos(theta);
  easin = (sin(theta) - y) / sin(theta);
  cout  << "cos=" << setw(16) << setprecision(8) << cos(theta) ;
  cout  << " xo=" << setw(16) << setprecision(8) << x ;
  cout  << " ea=" << setw(16) << setprecision(8) << eacos << endl;
  cout  << "sin=" << setw(16) << setprecision(8) << sin(theta) ;
  cout  << " yo=" << setw(16) << setprecision(8) << y ;
  cout  << " ea=" << setw(16) << setprecision(8) << easin << endl;



  //-----------------------------------------------------------------------------
  // printf ("\nGrinding on [K, 0, pi/6] -> [0.86602540, 0.50000000, 0]\n");
```

```
// Circular (X0C, 0L, HalfPi / 3L);
//------------------------------------------------------------------------
theta = pi / 6.0;
x = 1 / K;
y = 0.0;
z = theta;
cout << "-----------------------------------------------\n";
cout << theta * 180. / pi << " deg (" << theta << " rad ) \n";
cout << "xi =" << x << " yi =" << y << " zi=" << z << "\n";

cordic(&x, &y, &z, nIter);

cout  << "xo =" << x << " yo =" << y << " zo=" << z << "\n";

eacos = (cos(theta) - x) / cos(theta);
easin = (sin(theta) - y) / sin(theta);
cout  << "cos=" << setw(16) << setprecision(8) << cos(theta) ;
cout  << " xo=" << setw(16) << setprecision(8) << x ;
cout  << " ea=" << setw(16) << setprecision(8) << eacos << endl;
cout  << "sin=" << setw(16) << setprecision(8) << sin(theta) ;
cout  << " yo=" << setw(16) << setprecision(8) << y ;
cout  << " ea=" << setw(16) << setprecision(8) << easin << endl;



//------------------------------------------------------------------------
// printf ("\nGrinding on [K, 0, pi/4] -> [0.70710678, 0.70710678, 0]\n");
// Circular (X0C, 0L, HalfPi / 2L);
//------------------------------------------------------------------------
theta = pi / 4.0;
x = 1 / K;
y = 0.0;
z = theta;
cout << "-----------------------------------------------\n";
cout << z * 180. / pi << " deg (" << z << " rad ) \n";
cout << "xi =" << x << " yi =" << y << " zi=" << z << "\n";

cordic(&x, &y, &z, nIter);

cout  << "xo =" << x << " yo =" << y << " zo=" << z << "\n";

eacos = (cos(theta) - x) / cos(theta);
easin = (sin(theta) - y) / sin(theta);
cout  << "cos=" << setw(16) << setprecision(8) << cos(theta) ;
cout  << " xo=" << setw(16) << setprecision(8) << x ;
cout  << " ea=" << setw(16) << setprecision(8) << eacos << endl;
cout  << "sin=" << setw(16) << setprecision(8) << sin(theta) ;
cout  << " yo=" << setw(16) << setprecision(8) << y ;
cout  << " ea=" << setw(16) << setprecision(8) << easin << endl;



//------------------------------------------------------------------------
// printf ("\nGrinding on [K, 0, pi/3] -> [0.50000000, 0.86602540, 0]\n");
// Circular (X0C, 0L, 2L * (HalfPi / 3L));
//------------------------------------------------------------------------
theta = pi / 3.0;
x = 1 / K;
y = 0.0;
z = theta;
cout << "-----------------------------------------------\n";
cout << z * 180. / pi << " deg (" << z << " rad ) \n";
cout << "xi =" << x << " yi =" << y << " zi=" << z << "\n";

cordic(&x, &y, &z, nIter);

cout  << "xo =" << x << " yo =" << y << " zo=" << z << "\n";

eacos = (cos(theta) - x) / cos(theta);
easin = (sin(theta) - y) / sin(theta);
```

```
  cout  << "cos=" << setw(16) << setprecision(8) << cos(theta) ;
  cout  << " xo=" << setw(16) << setprecision(8) << x ;
  cout  << " ea=" << setw(16) << setprecision(8) << eacos << endl;
  cout  << "sin=" << setw(16) << setprecision(8) << sin(theta) ;
  cout  << " yo=" << setw(16) << setprecision(8) << y ;
  cout  << " ea=" << setw(16) << setprecision(8) << easin << endl;

  cout << endl << endl << endl;


  double msecos = 0.;
  double msesin = 0.;
  int    no = 0;

  for (theta = -pi / 2; theta < +pi / 2; theta += pi / (1 << nIter) ) {
    x = 1 / K;
    y = 0.0;
    z = theta;

    cordic(&x, &y, &z, nIter);
    no++;

    eacos = (cos(theta) - x) / cos(theta);
    easin = (sin(theta) - y) / sin(theta);

    cout << "------------------------------------------------\n";
    cout  << "rad=" << setw(16) << setprecision(8) << theta << endl;
    cout  << "cos=" << setw(16) << setprecision(8) << cos(theta) ;
    cout  << " xo=" << setw(16) << setprecision(8) << x ;
    cout  << " ea=" << setw(16) << setprecision(8) << eacos << endl;
    cout  << "sin=" << setw(16) << setprecision(8) << sin(theta) ;
    cout  << " yo=" << setw(16) << setprecision(8) << y ;
    cout  << " ea=" << setw(16) << setprecision(8) << easin << endl;

    msecos += (cos(theta) - x) * (cos(theta) - x);
    msesin += (sin(theta) - y) * (sin(theta) - y);


  }

  msecos /= no;
  msesin /= no;

  cout << endl << endl << endl;

  cout  << "msecos=" << setw(16) << setprecision(8) << msecos << endl;
  cout  << "msesin=" << setw(16) << setprecision(8) << msesin << endl;
  cout  << "rmscos=" << setw(16) << setprecision(8) << sqrt(msecos) << endl;
  cout  << "rmssin=" << setw(16) << setprecision(8) << sqrt(msesin) << endl;



  return (0);




}
::::::::::::::
cordic.cpp
::::::::::::::
# include <cstdlib>
# include <iostream>
# include <iomanip>
# include <cmath>
# include <ctime>

using namespace std;

# include "cordic.hpp"
```

```
#define SC_INCLUDE_FX

#include <systemc.h>


#define FIXPT
#define WL 32
#define IWL 15

sc_fxtype_params param1(32, 15);
sc_fxtype_context c1(param1);

//****************************************************************************80

void cordic ( double *x, double *y, double *z, int n )

//****************************************************************************80
//  CORDIC returns the sine and cosine using the CORDIC method.
//
//  Licensing:
//
//    This code is distributed under the GNU LGPL license.
//
//  Modified:
//
//    2012.04.17
//
//  Author:
//
//    Based on MATLAB code in a Wikipedia article.
//
//    Modifications by John Burkardt
//
//    Further modified by Young W. Lim
//
//  Parameters:
//
//    Input:
//      *x: x coord of an init vector
//      *y: y coord of an init vector
//      *z: angle (-90 <= angle <= +90)
//       n: number of iteration
//         A value of 10 is low.  Good accuracy is achieved
//         with 20 or more iterations.
//
//    Output:
//      *xo: x coord of a final vector
//      *yo: y coord of a final vector
//      *zo: angle residue
//
//  Local Parameters:
//
//    Local, real ANGLES(60) = arctan ( (1/2)^(0:59) );
//
//    Local, real KPROD(33), KPROD(j) = product ( 0 <= i <= j ) K(i),
//    K(i) = 1 / sqrt ( 1 + (1/2)^(2i) ).
//
//
{
# define ANGLES_LENGTH 60
# define KPROD_LENGTH 33

#ifdef FIXPT
  // sc_fixed<WL, IWL> angle;
  // sc_fixed<WL, IWL> angles[ANGLES_LENGTH] = {


  sc_fix angle;
  sc_fix angles[ANGLES_LENGTH] = {
```

```
#else
  double angle;
  double angles[ANGLES_LENGTH] = {
#endif
    7.8539816339744830962E-01,
    4.6364760900080611621E-01,
    2.4497866312686415417E-01,
    1.2435499454676143503E-01,
    6.2418809995957348474E-02,
    3.1239833430268276254E-02,
    1.5623728620476830803E-02,
    7.8123410601011112965E-03,
    3.9062301319669718276E-03,
    1.9531225164788186851E-03,
    9.7656218955931943040E-04,
    4.8828121119489827547E-04,
    2.4414062014936176402E-04,
    1.2207031189367020424E-04,
    6.1035156174208775022E-05,
    3.0517578115526096862E-05,
    1.5258789061315762107E-05,
    7.6293945311019702634E-06,
    3.8146972656064962829E-06,
    1.9073486328101870354E-06,
    9.5367431640596087942E-07,
    4.7683715820308885993E-07,
    2.3841857910155798249E-07,
    1.1920928955078068531E-07,
    5.9604644775390554414E-08,
    2.9802322387695303677E-08,
    1.4901161193847655147E-08,
    7.4505805969238279871E-09,
    3.7252902984619140453E-09,
    1.8626451492309570291E-09,
    9.3132257461547851536E-10,
    4.6566128730773925778E-10,
    2.3283064365386962890E-10,
    1.1641532182693481445E-10,
    5.8207660913467407226E-11,
    2.9103830456733703613E-11,
    1.4551915228366851807E-11,
    7.2759576141834259033E-12,
    3.6379788070917129517E-12,
    1.8189894035458564758E-12,
    9.0949470177292823792E-13,
    4.5474735088646411896E-13,
    2.2737367544323205948E-13,
    1.1368683772161602974E-13,
    5.6843418860808014870E-14,
    2.8421709430404007435E-14,
    1.4210854715202003717E-14,
    7.1054273576010018587E-15,
    3.5527136788005009294E-15,
    1.7763568394002504647E-15,
    8.8817841970012523234E-16,
    4.4408920985006261617E-16,
    2.2204460492503130808E-16,
    1.1102230246251565404E-16,
    5.5511151231257827021E-17,
    2.7755575615628913511E-17,
    1.3877787807814456755E-17,
    6.9388939039072283776E-18,
    3.4694469519536141888E-18,
    1.7347234759768070944E-18 };

  int j;

#ifdef FIXPT
  // sc_fixed <WL, IWL> factor;
  // sc_fixed <WL, IWL> kprod[KPROD_LENGTH] = {
```

```
  sc_fix factor;
  sc_fix kprod[KPROD_LENGTH] = {
#else
  double factor;
  double kprod[KPROD_LENGTH] = {
#endif
    0.70710678118654752440,
    0.63245553203367586640,
    0.61357199107789634961,
    0.60883391251775242102,
    0.60764825625616820093,
    0.60735177014129595905,
    0.60727764409352599905,
    0.60725911229889273006,
    0.60725447933256232972,
    0.60725332108987516334,
    0.60725303152913433540,
    0.60725295913894481363,
    0.60725294104139716351,
    0.60725293651701023413,
    0.60725293538591350073,
    0.60725293510313931731,
    0.60725293503244577146,
    0.60725293501477238499,
    0.60725293501035403837,
    0.60725293500924945172,
    0.60725293500897330506,
    0.60725293500890426839,
    0.60725293500888700922,
    0.60725293500888269443,
    0.60725293500888161574,
    0.60725293500888134606,
    0.60725293500888127864,
    0.60725293500888126179,
    0.60725293500888125757,
    0.60725293500888125652,
    0.60725293500888125626,
    0.60725293500888125619,
    0.60725293500888125617 };

#ifdef FIXPT
  // sc_fixed<WL, IWL> pi = 3.141592653589793;
  // sc_fixed<WL, IWL> poweroftwo;
  // sc_fixed<WL, IWL> sigma;
  // sc_fixed<WL, IWL> sign_factor;
  // sc_fixed<WL, IWL> theta;
  //
  // sc_fixed<WL, IWL> xn, yn;


  sc_fix pi = 3.141592653589793;
  sc_fix poweroftwo;
  sc_fix sigma;
  sc_fix sign_factor;
  sc_fix theta;

  sc_fix xn, yn;
#else
  double pi = 3.141592653589793;
  double poweroftwo;
  double sigma;
  double sign_factor;
  double theta;

  double xn, yn;
#endif

//
//  Initialize loop variables:
```

```
//
  theta = *z;

  xn = *x;
  yn = *y;

  poweroftwo = 1.0;
  angle = angles[0];

//
//  Iterations
//
  for ( j = 1; j <= n; j++ )
  {
    if ( theta < 0.0 )
    {
      sigma = -1.0;
    }
    else
    {
      sigma = 1.0;
    }

    factor = sigma * poweroftwo;

    *x =          xn - factor * yn;
    *y = factor * xn +          yn;

    xn = *x;
    yn = *y;


//
//  Update the remaining angle.
//
    theta = theta - sigma * angle;

    poweroftwo = poweroftwo / 2.0;
//
//  Update the angle from table, or eventually by just dividing by two.
//
    if ( ANGLES_LENGTH < j + 1 )
    {
      angle = angle / 2.0;
    }
    else
    {
      angle = angles[j];
    }

    *z = theta;
  }
//
//  Adjust length of output vector to be [cos(beta), sin(beta)]
//
//  KPROD is essentially constant after a certain point, so if N is
//  large, just take the last available value.
//
//   if ( 0 < n )
//   {
//     *c = *c * kprod [ i4_min ( n, KPROD_LENGTH ) - 1 ];
//     *s = *s * kprod [ i4_min ( n, KPROD_LENGTH ) - 1 ];
//   }
//
//  Adjust for possible sign change because angle was originally
//  not in quadrant 1 or 4.
//
//   *c = sign_factor * *c;
//   *s = sign_factor * *s;
```

```
  return;
# undef ANGLES_LENGTH
# undef KPROD_LENGTH
}
```