



nVIDIA®

Holoscan SDK User Guide

Release 1.0.3

NVIDIA Corporation

Feb 12, 2024

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OVERVIEW

NVIDIA Holoscan is the AI sensor processing platform that combines hardware systems for low-latency sensor and network connectivity, optimized libraries for data processing and AI, and core microservices to run streaming, imaging, and other applications, from embedded to edge to cloud. It can be used to build streaming AI pipelines for a variety of domains, including Medical Devices, High Performance Computing at the Edge, Industrial Inspection and more.

Note: In previous releases, the prefix **Clara** was used to define Holoscan as a platform designed initially for **medical devices**. As Holoscan has grown, its potential to serve other areas has become apparent. With version 0.4.0, we're proud to announce that the Holoscan SDK is now officially built to be domain-agnostic and can be used to build sensor AI applications in multiple domains. Note that some of the content of the SDK (sample applications) or the documentation might still appear to be healthcare-specific pending additional updates. Going forward, domain specific content will be hosted on the **HoloHub** repository.

The Holoscan SDK assists developers by providing:

1. Various installation strategies

From containers, to python wheels, to source, from development to deployment environments, the Holoscan SDK comes in many packaging flavors to adapt to different needs. Find more information in the [sdk installation](#) section.

2. C++ and Python APIs

These APIs are now the recommended interface for the creation of application pipelines in the Holoscan SDK. See the Using the SDK section to learn how to leverage those APIs, or the Doxygen pages (C++/Python) for specific API documentation.

3. Built-in Operators

The units of work of Holoscan applications are implemented within Operators, as described in the [core concepts](#) of the SDK. The operators included in the SDK provide domain-agnostic functionalities such as IO, machine learning inference, processing, and visualization, optimized for AI streaming pipelines, relying on a set of [Core Technologies](#). This guide provides more information on the operators provided within the SDK [here](#).

4. Minimal Examples

The Holoscan SDK provides a list of examples to illustrate specific capabilities of the SDK. Their source code can be found in the [GitHub repository](#). The [Holoscan by Example](#) section provides step-by-step analysis of some of these examples to illustrate the innerworkings of the Holoscan SDK.

5. Repository of Operators and Applications

HoloHub is a central repository for users and developers to share reusable operators and sample applications with the Holoscan community. Being open-source, these operators and applications can also be used as reference implementations to complete the built-in operators and examples available in the SDK.

6. Tooling to Package and Deploy Applications

Packaging and deploying applications is a complex problem that can require large amount of efforts. The *Holoscan CLI* is a command-line interface included in the Holoscan SDK that provides commands to *package and run applications* in OCI-compliant containers that could be used for production.

7. Performance tools

As highlighted in the relevant technologies section, the soul of the Holoscan project is to achieve peak performance by leveraging hardware and software developed at NVIDIA or provided by third-parties. To validate this, Holoscan provides performance tools to help users and developers track their application performance. They currently include:

- a *Video Pipeline Latency Measurement Tool* to measure and estimate the total end-to-end latency of a video streaming application including the video capture, processing, and output using various hardware and software components that are supported by the Holoscan Developer Kits.
- the *Data Flow Tracking* feature to profile your application and analyze the data flow between operators in its graph.

8. Documentation

The Holoscan SDK documentation is composed of:

- This user guide, in a [webpage](#) or [PDF](#) format
- Build and run instructions specific to each *installation strategy*
- [Release notes](#) on Github

RELEVANT TECHNOLOGIES

Holoscan accelerates streaming AI applications by leveraging both hardware and software. The Holoscan SDK relies on multiple core technologies to achieve low latency and high throughput:

- *Rivermax and GPUDirect RDMA*
- *Graph Execution Framework*
- *TensorRT Optimized Inference*
- *Interoperability between CUDA and rendering frameworks*
- *Accelerated Image Transformations*
- *Unified Communications X*

2.1 Rivermax and GPUDirect RDMA

The Holoscan Developer Kits can be used along with the [NVIDIA Rivermax SDK](#) to provide an extremely efficient network connection using the onboard [ConnectX](#) network adapter that is further optimized for GPU workloads by using [GPUDirect](#) for RDMA. This technology avoids unnecessary memory copies and CPU overhead by copying data directly to or from pinned GPU memory, and supports both the integrated GPU or the discrete GPU.

Note: NVIDIA is also committed to supporting hardware vendors enable RDMA within their own drivers, an example of which is provided by the [AJA Video Systems](#) as part of a partnership with NVIDIA for the Holoscan SDK. The [AJASource](#) operator is an example of how the SDK can leverage RDMA.

For more information about GPUDirect RDMA, see the following:

- [GPUDirect RDMA Documentation](#)
- [Minimal GPUDirect RDMA Demonstration](#) source code, which provides a real hardware example of using RDMA and includes both kernel drivers and userspace applications for the RHS Research PicoEVB and HiTech Global HTG-K800 FPGA boards.

2.2 Graph Execution Framework

The Graph Execution Framework (GXF) is a core component of the Holoscan SDK that provides features to execute pipelines of various independent tasks with high performance by minimizing or removing the need to copy data across each block of work, and providing ways to optimize memory allocation.

GXF will be mentioned in many places across this user guide, including a dedicated section which provides more details.

2.3 TensorRT Optimized Inference

[NVIDIA TensorRT](#) is a deep learning inference framework based on CUDA that provided the highest optimizations to run on NVIDIA GPUs, including the Holoscan Developer Kits.

The *[inference module](#)* leverages TensorRT among other backends, and provides the ability to execute multiple inferences in parallel.

2.4 Interoperability between CUDA and rendering frameworks

Vulkan is commonly used for realtime visualization and, like CUDA, is executed on the GPU. This provides an opportunity for efficient sharing of resources between CUDA and this rendering framework.

The *[Holoviz](#)* module uses the [external resource interoperability](#) functions of the low-level CUDA driver application programming interface, the Vulkan [external memory](#) and [external semaphore](#) extensions.

2.5 Accelerated Image Transformations

Streaming image processing often requires common 2D operations like resizing, converting bit widths, and changing color formats. NVIDIA has built the CUDA accelerated NVIDIA Performance Primitive Library ([NPP](#)) that can help with many of these common transformations. NPP is extensively showcased in the Format Converter operator of the Holoscan SDK.

2.6 Unified Communications X

The [Unified Communications X](#) (UCX) framework is an open-source communication framework developed as a collaboration between industry and academia. It provides high performance point-to-point communication for data-centric applications. Holoscan SDK uses UCX to send data between fragments in distributed applications. UCX's high level protocols attempt to automatically select an optimal transport layer depending on the hardware available. For example technologies such as [TCP](#), [CUDA memory copy](#), [CUDA IPC](#) and [GPUDirect RDMA](#) are supported.

GETTING STARTED WITH HOLOSCAN

As described in the [Overview](#), the SDK provides many components and capabilities. The goal of this section is to provide a recommended path to getting started with the SDK.

3.1 1. Choose your platform

The Holoscan SDK is optimized and compatible with multiple hardware platforms, including NVIDIA Developer Kits (aarch64) and x86_64 workstations. Learn more on the [developer page](#) to help you decide what hardware you should target.

3.2 2. Setup the SDK and your platform

Start with *installing the SDK*. If you have a need for it, you can go through additional *recommended setups* to achieve peak performance, or *setup additional sensors* from NVIDIA's partners.

3.3 3. Learn the framework

1. Start with the *Core Concepts* to understand the technical terms used in this guide, and the overall behavior of the framework.
2. Learn how to use the SDK in one of two ways (or both) based on your preference:
 1. Going through the *Holoscan by Example* tutorial which will build your knowledge step-by-step by going over concrete minimal examples in the SDK. You can refer to each example source code and run instructions to inspect them and run them as you go.
 2. Going through the condensed documentations that should cover all capabilities of the SDK using minimal mock code snippets, including *creating an application*, *creating a distributed application*, and *creating operators*.

3.4 4. Understand the reusable capabilities of the SDK

The Holoscan SDK does not only provide a framework to build and run applications, but also a set of reusable operators to facilitate implementing applications for streaming, AI, and other general domains.

The list of existing operators is available [here](#), which points to the C++ or Python API documentation for more details. Specific documentation is available for the [visualization](#) (codename: HoloViz) and [inference](#) (codename: HoloInfer) operators.

Additionally, [HoloHub](#) is a central repository for users and developers to share reusable operators and sample applications with the Holoscan community, extending the capabilities of the SDK:

- Just like the SDK operators, the HoloHub operators can be used in your own Holoscan applications.
- The HoloHub sample applications can be used as reference implementations to complete the examples available in the SDK.

Take a glance at HoloHub to find components you might want to leverage in your application, improve upon existing work, or contribute your own additions to the Holoscan platform.

3.5 5. Write and Run your own application

The steps above cover what is required to write your own application and run it. For facilitating packaging and distributing, the Holoscan SDK includes utilities to [package and run your Holoscan application](#) in a OCI-compliant container image.

3.6 6. Master the details

- Expand your understanding of the framework with details on the [logging utility](#) or the [data flow tracking](#) benchmarking tool.
- Learn more details on the configurable components that control the execution of your application, like [Schedulers], [Conditions], and [Resources]. (Advanced) These components are part on the GXF execution backend, hence the **Graph Execution Framework** section at the bottom of this guide if deep understanding of the application execution is needed.

SDK INSTALLATION

The section below refers to the installation of the Holoscan SDK referred to as the **development stack**, designed for NVIDIA Developer Kits (arm64), and for x86_64 Linux compute platforms, ideal for development and testing of the SDK.

Note: An alternative for the [IGX Orin Developer Kit](#) is the *deployment stack*, based on [OpenEmbedded](#) (Yocto build system) instead of Ubuntu. This is recommended to limit your stack to the software components strictly required to run your Holoscan application. The runtime Board Support Package (BSP) can be optimized with respect to memory usage, speed, security and power requirements.

4.1 Prerequisites

Holoscan Developer Kits (aarch64)

Set up your developer kit:

Developer Kit	User Guide	OS	GPU Mode
NVIDIA IGX Orin	Guide	IGX Software 1.0 DP	iGPU or* dGPU
NVIDIA Jetson AGX Orin and Orin Nano	Guide	JetPack 6.0	iGPU
NVIDIA Clara AGX <i>Only supporting the NGC container</i>	Guide	HoloPack 1.2	iGPU or* dGPU

* iGPU and dGPU can be used concurrently on a single developer kit in dGPU mode. See [details here](#).

x86_64

You'll need the following to use the Holoscan SDK on x86_64:

- OS: Ubuntu 22.04 (GLIBC >= 2.35)
- NVIDIA discrete GPU (dGPU)
 - Ampere or above recommended for best performance
 - [Quadro/NVIDIA RTX](#) necessary for RDMA support
 - Tested with [NVIDIA Quadro RTX 6000](#) and [NVIDIA RTX A6000](#)

- **NVIDIA dGPU drivers:** 535 or above
- For RDMA Support, follow the instructions in the *Enabling RDMA* section.
- Additional software dependencies might be needed based on how you choose to install the SDK (see section below).
- Refer to the *Additional Setup* and *Third-Party Hardware Setup* sections for additional prerequisites.

4.2 Install the SDK

We provide multiple ways to install and run the Holoscan SDK:

4.2.1 Instructions

NGC Container

- **dGPU** (x86_64, IGX Orin dGPU, Clara AGX dGPU)

```
docker pull nvcr.io/nvidia/clara-holoscan/holoscan:v1.0.3-dgpu
```

- **iGPU** (Jetson, IGX Orin iGPU, Clara AGX iGPU)

```
docker pull nvcr.io/nvidia/clara-holoscan/holoscan:v1.0.3-igpu
```

See details and usage instructions on [NGC](#).

Debian package

1. Install the latest [CUDA keyring package](#):

- **x86_64:** ubuntu2204/x86_64
- **Jetson:** ubuntu2204/arm64
- **IGX Orin:** ubuntu2204/arm64 for iGPU, ubuntu2204/sbsa for dGPU
 - Note: not necessary, already available from <https://repo.download.nvidia.com/jetson> with IGX OS

2. Install the SDK

```
sudo apt update
sudo apt install holoscan
```

Python wheel

```
pip install holoscan
```

See details and troubleshooting on [PyPI](#).

4.2.2 Not sure what to choose?

- The **Holoscan container image on NGC** is the safest way to ensure all the dependencies are present with the expected versions (including Torch and ONNX Runtime). It is the simplest way to run the embedded examples, while still allowing you to create your own C++ and Python Holoscan application on top of it. These benefits come at a cost:
 - large image size from the numerous (some of them optional) dependencies. If you need a lean runtime image, see [section below](#).
 - standard inconvenience that exist when using Docker, such as more complex run instructions for proper configuration.
 - supporting the CLI require more work than the other solutions at this time.
- If you are confident in your ability to manage dependencies on your own in your host environment, the **Holoscan Debian package** should provide all the capabilities needed to use the Holoscan SDK.
- If you are not interested in the C++ API but just need to work in Python, or want to use a different version than Python 3.10, you can use the **Holoscan python wheels** on PyPI. While they are the easiest solution to install the SDK, it might require the most work to setup your environment with extra dependencies based on your needs.

	NGC dev Container	Debian Package	Python Wheels
Runtime libraries	Included	Included	Included
Python module	3.10	3.10	3.8 to 3.11
C++ headers and C-Make config	Included	Included	N/A
Examples (+ source)	Included	Included	retrieve from GitHub
Sample datasets	Included	retrieve from NGC	retrieve from NGC
CUDA runtime ¹	Included	automatically ² installed	require manual installation
NPP support ³	Included	automatically ² installed	require manual installation
TensorRT support ⁴	Included	automatically ² installed	require manual installation
Vulkan support ⁵	Included	automatically ² installed	require manual installation
V4L2 support ⁶	Included	automatically ² installed	require manual installation
Torch support ⁷	Included	require manual ⁸ installation	require manual ^{Page 10, 8} installation
ONNX Runtime support ⁹	Included	require manual ¹⁰ installation	require manual ^{Page 10, 10} installation
MOFED support ¹¹	User space included Install kernel drivers on the host	require manual installation	require manual installation
CLI support	needs docker dind with buildx plugin on top of the image	needs docker w/buildx plugin	needs docker w/buildx plugin

¹ CUDA 12 is required. Already installed on NVIDIA developer kits with IGX Software and JetPack.

² Debian installation on x86_64 requires the latest [cuda-keyring](#) package to automatically install all dependencies.

³ NPP 12 needed for the FormatConverter and BayerDemosaic operators. Already installed on NVIDIA developer kits with IGX Software and

4.2.3 Need more control over the SDK?

The [Holoscan SDK source repository](#) is **open-source** and provides reference implementations as well as infrastructure for building the SDK yourself.

Attention: We only recommend building the SDK from source if you need to build it with debug symbols or other options not used as part of the published packages. If you want to write your own operator or application, you can use the SDK as a dependency (and contribute to [HoloHub](#)). If you need to make other modifications to the SDK, [file a feature or bug request](#).

4.2.4 Looking for a light runtime container image?

The current Holoscan container on NGC has a large size due to including all the dependencies for each of the built-in operators, but also because of the development tools and libraries that are included. Follow the [instructions on GitHub](#) to build a runtime container without these development packages. This page also includes detailed documentation to assist you in only including runtime dependencies your Holoscan application might need.

JetPack.

⁴ TensorRT 8.6.1+ and cuDNN needed for the Inference operator. Already installed on NVIDIA developer kits with IGX Software and JetPack.

⁵ Vulkan 1.3.204+ loader needed for the HoloViz operator (+ libegl1 for headless rendering). Already installed on NVIDIA developer kits with IGX Software and JetPack.

⁶ V4L2 1.22+ needed for the V4L2 operator. Already installed on NVIDIA developer kits with IGX Software and JetPack.

⁷ Torch support requires LibTorch 2.1+, TorchVision 0.16+, OpenBLAS 0.3.20+, OpenMPI (aarch64 only), MKL 2021.1.1 (x86_64 only), libpng and libjpeg.

⁸ To install LibTorch and TorchVision, either build them from source, download our [pre-built packages](#), or copy them from the holoscan container (in `/opt`).

⁹ ONNXRuntime 1.15.1+ needed for the Inference operator. Note that ONNX models are also supported through the TensorRT backend of the Inference Operator.

¹⁰ To install ONNXRuntime, either build it from source, download our [pre-built package](#) with CUDA 12 and TensorRT execution provider support, or copy it from the holoscan container (in `/opt/onnxruntime`).

¹¹ Tested with MOFED 23.07

ADDITIONAL SETUP

In addition to the required steps to *install the Holoscan SDK*, the steps below will help you achieve peak performance:

5.1 Enabling RDMA

Note: Learn more about RDMA in the *technology overview* section.

There are two parts to enabling RDMA for Holoscan:

- *Enabling RDMA on the ConnectX SmartNIC*
- *Enabling GPUDirect RDMA*

5.1.1 Enabling RDMA on the ConnectX SmartNIC

Skip to the next section if you do not plan to leverage a ConnectX SmartNIC.

The NVIDIA IGX Orin developer kit comes with an embedded [ConnectX Ethernet adapter](#) to offer advanced hardware offloads and accelerations. You can also purchase an individual ConnectX adapter and install it on other systems such as x86_64 workstations.

The following steps are required to ensure your ConnectX can be used for RDMA over Converged Ethernet ([RoCE](#)):

1. Install MOFED drivers

Ensure the Mellanox OFED drivers version 23.07 or above are installed:

```
cat /sys/module/mlx5_core/version
```

If not installed, or an older version, install the appropriate version from the [MLNX_OFED download page](#), or use the script below:

```
# You can choose different versions/OS or download directly from the
# Download Center in the webpage linked above
MOFED_VERSION="23.07-0.5.1.2"
OS="ubuntu22.04"
MOFED_PACKAGE="MLNX_OFED_LINUX-${MOFED_VERSION}-${OS}-${uname -m}"
wget --progress=dot:giga https://www.mellanox.com/downloads/ofed/MLNX_OFED-${MOFED_
↪VERSION}/${MOFED_PACKAGE}.tgz
```

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```
tar xf ${MOFED_PACKAGE}.tgz
sudo ./${MOFED_PACKAGE}/mlnxofedinstall
# add the --force flag to force uninstallation if necessary:
# sudo ./${MOFED_PACKAGE}/mlnxofedinstall --force
rm -r ${MOFED_PACKAGE}*
```

2. Load MOFED drivers

Ensure the drivers are loaded:

```
sudo lsmod | grep ib_core
```

If nothing appears, run the following command:

```
sudo /etc/init.d/openibd restart
```

3. Switch the board Link Layer to Ethernet

The ConnectX SmartNIC can function in two separate modes (called link layer):

- Ethernet (ETH)
- Infiniband (IB)

Holoscan does not support IB at this time (not tested), so the ConnectX will need to use the ETH link layer.

To identify the current mode, run `ibstat` or `ibv_devinfo` and look for the Link Layer value. In the example below, the `mlx5_0` interface is in Ethernet mode, while the `mlx5_1` interface is in Infiniband mode. Do not pay attention to the transport value which is always InfiniBand.

```
$ ibstat
CA 'mlx5_0'
  CA type: MT4129
  Number of ports: 1
  Firmware version: 28.37.0190
  Hardware version: 0
  Node GUID: 0x48b02d0300ee7a04
  System image GUID: 0x48b02d0300ee7a04
  Port 1:
    State: Down
    Physical state: Disabled
    Rate: 40
    Base lid: 0
    LMC: 0
    SM lid: 0
    Capability mask: 0x00010000
    Port GUID: 0x4ab02dffffee7a04
    Link layer: Ethernet
CA 'mlx5_1'
  CA type: MT4129
  Number of ports: 1
  Firmware version: 28.37.0190
```

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```

Hardware version: 0
Node GUID: 0x48b02d0300ee7a05
System image GUID: 0x48b02d0300ee7a04
Port 1:
    State: Active
    Physical state: LinkUp
    Rate: 100
    Base lid: 0
    LMC: 0
    SM lid: 0
    Capability mask: 0x00010000
    Port GUID: 0x4ab02dffffee7a05
    Link layer: InfiniBand

```

If no results appear after `ibstat` and `sudo lsmod | grep ib_core` returns a result like this:

```
ib_core          425984  1 ib_uverbs
```

Consider running the following command or rebooting:

```
sudo /etc/init.d/openibd restart
```

To switch the link layer mode, there are two possible options:

1. On IGX Orin developer kits, you can switch that setting through the BIOS: [see IGX Orin documentation](#).
2. On any system with a ConnectX (including IGX Orin devkits), you can run the command below from a terminal (requires a reboot). `sudo ibdev2netdev -v` is used to identify the PCI address of the ConnectX (any of the two interfaces is fine to use), and `mlxconfig` is used to apply the changes.

```

mlx_pci=$(sudo ibdev2netdev -v | awk '{print $1}' | head -n1)
sudo mlxconfig -d $mlx_pci set LINK_TYPE_P1=ETH LINK_TYPE_P2=ETH

```

Note: `LINK_TYPE_P1` and `LINK_TYPE_P2` are for `mlx5_0` and `mlx5_1` respectively. You can choose to only set one of them. You can pass `ETH` or `2` for Ethernet mode, and `IB` or `1` for InfiniBand.

This is the output of the command above:

```

Device #1:
-----

Device type:    ConnectX7
Name:           P3740-B0-QSFP_Ax
Description:    NVIDIA Prometheus P3740 ConnectX-7 VPI PCIe Switch Motherboard;
↪400Gb/s; dual-port QSFP; PCIe switch5.0 X8 SLOT0 ;X16 SLOT2; secure boot;
Device:         0005:03:00.0

Configurations:
                Next Boot      New
LINK_TYPE_P1   ETH(2)         ETH(2)
LINK_TYPE_P2   IB(1)          ETH(2)

Apply new Configuration? (y/n) [n] :

```

`Next Boot` is actually the current value that was expected to be used at the next reboot, while `New` is the value you're about to set to override `Next Boot`.

Apply with `y` and reboot afterwards:

```
Applying... Done!
-I- Please reboot machine to load new configurations.
```

4. Configure the IP addresses of the ethernet interfaces

First, identify the logical names of your ConnectX interfaces. Connecting a cable in just one of the interfaces on the ConnectX will help you identify which port is which (in the example below, only `mlx5_1` i.e. `eth3` is connected):

```
$ sudo ibdev2netdev
mlx5_0 port 1 ==> eth2 (Down)
mlx5_1 port 1 ==> eth3 (Up)
```

Tip: For IGX Orin Developer Kits with no live source to connect to the ConnectX QSFP ports, adding `-v` can show you which logical name is mapped to each specific port:

- `0005:03:00.0` is the QSFP port closer to the PCI slots
- `0005:03:00.1` is the QSFP closer to the RJ45 ethernet ports

```
$ sudo ibdev2netdev -v
0005:03:00.0 mlx5_0 (MT4129 - P3740-0002 ) NVIDIA IGX, P3740-0002, 2-port QSFP up to 400G, InfiniBand and Ethernet, PCIe5
fw 28.37.0190 port 1 (DOWN ) ==>
eth2 (Down)
0005:03:00.1 mlx5_1 (MT4129 - P3740-0002 ) NVIDIA IGX, P3740-0002, 2-port QSFP up to 400G, InfiniBand and Ethernet, PCIe5
fw 28.37.0190 port 1 (DOWN ) ==>
eth2 (Down)
```

If you have a cable connected but it does not show Up/Down in the output of `ibdev2netdev`, you can try to parse the output of `dmesg` instead. The example below shows that `0005:03:00.1` is plugged, and that it is associated with `eth3`:

```
$ sudo dmesg | grep -w mlx5_core
...
[ 11.512808] mlx5_core 0005:03:00.0 eth2: Link down
[ 11.640670] mlx5_core 0005:03:00.1 eth3: Link down
...
[ 3712.267103] mlx5_core 0005:03:00.1: Port module event: module 1, Cable plugged
```

The next step is to set a static IP on the interface you'd like to use so you can refer to it in your Holoscan applications (ex: *Emergent cameras, distributed applications...*).

First, check if you already have an address setup. We'll use the `eth3` interface in this example for `mlx5_1`:

```
ip -f inet addr show eth3
```

If nothing appears or you'd like to change the address, you can set an IP and MTU (Maximum Transmission Unit) through the Network Manager user interface, CLI (`nmcli`), or other IP configuration tools. In the example below, we

use `ip` (`ifconfig` is legacy) to configure the `eth3` interface with an address of `192.168.1.1/24` and a MTU of `9000` (i.e. “jumbo frame”) to send Ethernet frames with a payload greater than the standard size of 1500 bytes:

```
sudo ip link set dev eth3 down
sudo ip addr add 192.168.1.1/24 dev eth3
sudo ip link set dev eth3 mtu 9000
sudo ip link set dev eth3 up
```

Note: If you are connecting the ConnectX to another ConnectX with a [LinkX interconnect](#), do the same on the other system with an IP address on the same network segment.

For example, to communicate with `192.168.1.1/24` above (`/24 -> 255.255.255.0` submask), setup your other system with an IP between `192.168.1.2` and `192.168.1.254`, and the same `/24` submask.

5.1.2 Enabling GPUDirect RDMA

Note: Only supported on NVIDIA’s Quadro/workstation GPUs (not GeForce).

Follow the instructions below to enable [GPUDirect RDMA](#):

dGPU

On dGPU, the GPUDirect RDMA drivers are named `nvidia-peermem`, and are installed with the rest of the NVIDIA dGPU drivers.

Attention: To enable the use of GPUDirect RDMA with a ConnectX SmartNIC (section above), the following steps are required if the MOFED drivers were installed after the `peermem` drivers:

```
nv_driver_version=$(modinfo nvidia | awk '/^version:/ {print $2}' | cut -d. -f1)
sudo dpkg-reconfigure nvidia-dkms-$nv_driver_version # or nvidia-dkms-${nv_driver_
↪version}-server
```

Load the `peermem` kernel module manually:

```
sudo modprobe nvidia-peermem
```

Run the following to load it automatically during boot:

```
echo nvidia-peermem | sudo tee -a /etc/modules
```

iGPU

Warning: At this time the IGX SW 1.0 DP and JetPack 6.0 DP are missing the `nvidia-p2p` kernel for support for GPU Direct RDMA support. They're planned in the respective GA releases. The instructions below are to load the kernel module once it is packaged in the GA releases.

On iGPU, the GPUDirect RDMA drivers are named `nvidia-p2p`. Run the following to load the kernel module manually:

```
sudo modprobe nvidia-p2p
```

Run the following to load it automatically during boot:

```
echo nvidia-p2p | sudo tee -a /etc/modules
```

5.1.3 Testing with Rivermax

The instructions below describe the steps to test GPUDirect using the [Rivermax](#) SDK. The test applications used by these instructions, `generic_sender` and `generic_receiver`, can then be used as samples in order to develop custom applications that use the Rivermax SDK to optimize data transfers.

Note: The Linux default path where Rivermax expects to find the license file is `/opt/mellanox/rivermax/rivermax.lic`, or you can specify the full path and file name for the environment variable `RIVERMAX_LICENSE_PATH`.

Note: If manually installing the Rivermax SDK from the link above, please note there is no need to follow the steps for installing `MLNX_OFED/MLNX_EN` in the Rivermax documentation.

Running the Rivermax sample applications requires two systems, a sender and a receiver, connected via ConnectX network adapters. If two Developer Kits are used then the onboard ConnectX can be used on each system, but if only one Developer Kit is available then it is expected that another system with an add-in ConnectX network adapter will need to be used. Rivermax supports a wide array of platforms, including both Linux and Windows, but these instructions assume that another Linux based platform will be used as the sender device while the Developer Kit is used as the receiver.

Note: The `$rivermax_sdk` variable referenced below corresponds to the path where the Rivermax SDK package was installed. If the Rivermax SDK was installed via SDK Manager, this path will be:

```
rivermax_sdk=$HOME/Documents/Rivermax/1.31.10
```

If the Rivermax SDK was installed via a manual download, make sure to export your path to the SDK:

```
rivermax_sdk=$DOWNLOAD_PATH/1.31.10
```

Install path might differ in future versions of Rivermax.

1. Determine the logical name for the ConnectX devices that are used by each system. This can be done by using the `lshw -class network` command, finding the `product:` entry for the ConnectX device, and making note of the `logical name:` that corresponds to that device. For example, this output on a Developer Kit shows

the onboard ConnectX device using the `enp9s0f01` logical name (lshw output shortened for demonstration purposes).

```
$ sudo lshw -class network
*-network:0
    description: Ethernet interface
    product: MT28908 Family [ConnectX-6]
    vendor: Mellanox Technologies
    physical id: 0
    bus info: pci@0000:09:00.0
    <b>logical name: enp9s0f0</b>
    version: 00
    serial: 48:b0:2d:13:9b:6b
    capacity: 10Gbit/s
    width: 64 bits
    clock: 33MHz
    capabilities: pciexpress vpd msix pm bus_master cap_list ethernet physical_
    ↳10000bt-fd 100000bt-fd autonegotiation
    configuration: autonegotiation=on broadcast=yes driver=mlx5_core_
    ↳driverversion=5.4-1.0.3 duplex=full firmware=20.27.4006 (NVD0000000001) ip=10.0.0.
    ↳2 latency=0 link=yes multicast=yes
    resources: iomemory:180-17f irq:33 memory:1818000000-1819ffffff
```

The instructions that follow will use the `enp9s0f0` logical name for `ifconfig` commands, but these names should be replaced with the corresponding logical names as determined by this step.

2. Run the `generic_sender` application on the sending system.

a. Bring up the network:

```
$ sudo ifconfig enp9s0f0 up 10.0.0.1
```

b. Build the sample apps:

```
$ cd ${rivermax_sdk}/apps
$ make
```

e. Launch the `generic_sender` application:

```
$ sudo ./generic_sender -l 10.0.0.1 -d 10.0.0.2 -p 5001 -y 1462 -k 8192 -z 500 -v
...
#####
| Sender index: 0
| Thread ID: 0x7fa1ffb1c0
| CPU core affinity: -1
| Number of streams in this thread: 1
| Memory address: 0x7f986e3010
| Memory length: 59883520[B]
| Memory key: 40308
#####
| Stream index: 0
| Source IP: 10.0.0.1
| Destination IP: 10.0.0.2
| Destination port: 5001
| Number of flows: 1
```

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```

| Rate limit bps: 0
| Rate limit max burst in packets: 0
| Memory address: 0x7f986e3010
| Memory length: 59883520[B]
| Memory key: 40308
| Number of user requested chunks: 1
| Number of application chunks: 5
| Number of packets in chunk: 8192
| Packet's payload size: 1462
+*****

```

3. Run the `generic_receiver` application on the receiving system.

a. Bring up the network:

```
$ sudo ifconfig enp9s0f0 up 10.0.0.2
```

b. Build the `generic_receiver` app with GPUDirect support from the [Rivermax GitHub Repo](#). Before following the instructions to [build with CUDA-Toolkit support](#), apply the changes to file `generic_receiver/generic_receiver.cpp` in [this PR](#), this was tested on the IGX Orin Developer Kit with Rivermax 1.31.10.

c. Launch the `generic_receiver` application from the build directory:

```

$ sudo ./generic_receiver -i 10.0.0.2 -m 10.0.0.2 -s 10.0.0.1 -p 5001 -g 0
...
Attached flow 1 to stream.
Running main receive loop...
Got 5877704 GPU packets | 68.75 Gbps during 1.00 sec
Got 5878240 GPU packets | 68.75 Gbps during 1.00 sec
Got 5878240 GPU packets | 68.75 Gbps during 1.00 sec
Got 5877704 GPU packets | 68.75 Gbps during 1.00 sec
Got 5878240 GPU packets | 68.75 Gbps during 1.00 sec
...

```

With both the `generic_sender` and `generic_receiver` processes active, the receiver will continue to print out received packet statistics every second. Both processes can then be terminated with `<ctrl-c>`.

5.2 Enabling G-SYNC

For better performance and to keep up with the high refresh rate of Holoscan applications, we recommend the use of a [G-SYNC display](#).

Tip: Holoscan has been tested with these two G-SYNC displays:

- [Asus ROG Swift PG279QM](#)
- [Asus ROG Swift 360 Hz PG259QNR](#)

Follow these steps to ensure G-SYNC is enabled on your display:

1. Open the “NVIDIA Settings” Graphical application (`nvidia-settings` in Terminal).
2. Click on **X Server Display Configuration** then the **Advanced** button. This will show the **Allow G-SYNC on monitor not validated as G-SYNC compatible** option. Enable the option and click **Apply**:

3. To show the refresh rate and G-SYNC label on the display window, click on `OpenGL Settings` for the selected display. Now click `Allow G-SYNC/G-SYNC Compatible` and `Enable G-SYNC/G-SYNC Compatible Visual Indicator` options and click `Quit`. This step is shown in below image. The Gsync indicator will be at the top right screen once the application is running.

5.3 Disabling Variable Backlight

Various monitors have a Variable Backlight feature. That setting can add up to a frame of latency when enabled. Refer to your monitor's manufacturer instructions to disable it.

Tip: To disable variable backlight on the Asus ROG Swift monitors mentioned above, use the joystick button at the back of the display, go to the `image` tag, select `variable backlight`, then switch that setting to `OFF`.

5.4 Enabling Exclusive Display Mode

By default, applications use a borderless fullscreen window managed by the window manager. Because the window manager also manages other applications, applications may suffer a performance hit. To improve performance, exclusive display mode can be used with Holoscan's new visualization module (Holoviz), allowing the application to bypass the window manager and render directly to the display. Refer to the [Holoviz documentation](#) for details.

5.5 Use both Integrated and Discrete GPUs on Holoscan developer kits

Holoscan developer kits like the [NVIDIA IGX Orin](#) or the [NVIDIA Clara AGX](#) have both a discrete GPU (dGPU - optional on IGX Orin) and an integrated GPU (iGPU - Tegra SoC).

As of this release, when these developer kits are flashed to leverage the dGPU, there are two limiting factors preventing the use of the iGPU:

1. Conflict between the dGPU kernel mode driver and the iGPU display kernel driver (both named `nvidia.ko`). This conflict is not addressable at this time, meaning that **the iGPU cannot be used for display while the dGPU is enabled**.
2. Conflicts between the user mode driver libraries (ex: `libcuda.so`) and the compute stack (ex: `libcuda_rt.so`) for dGPU and iGPU.

We provide utilities to work around the second conflict:

IGX SW 1.0 DP

An improved solution will be introduced alongside the IGX SW 1.0 GA release.

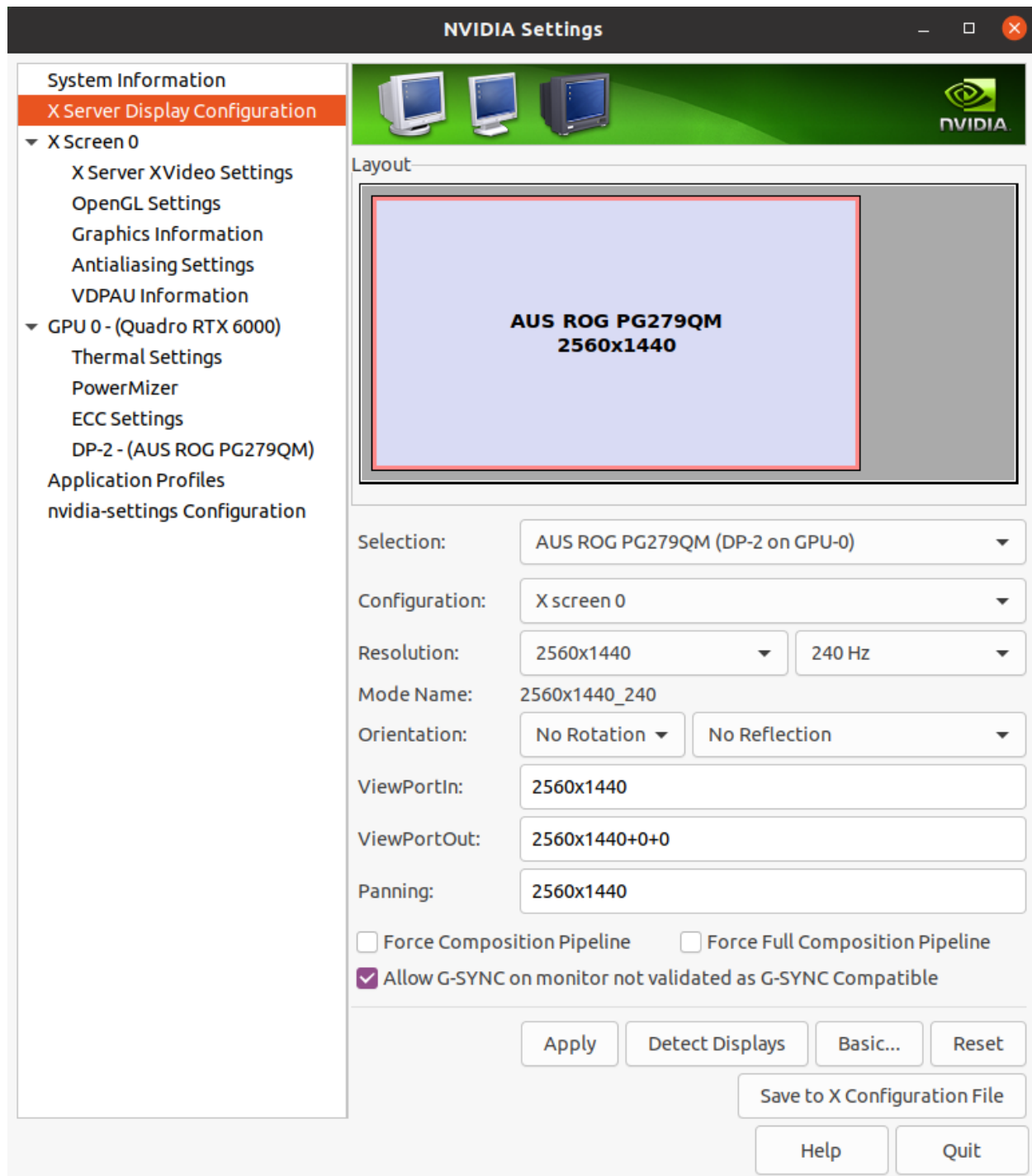


Fig. 5.1: Enable G-SYNC for the current display

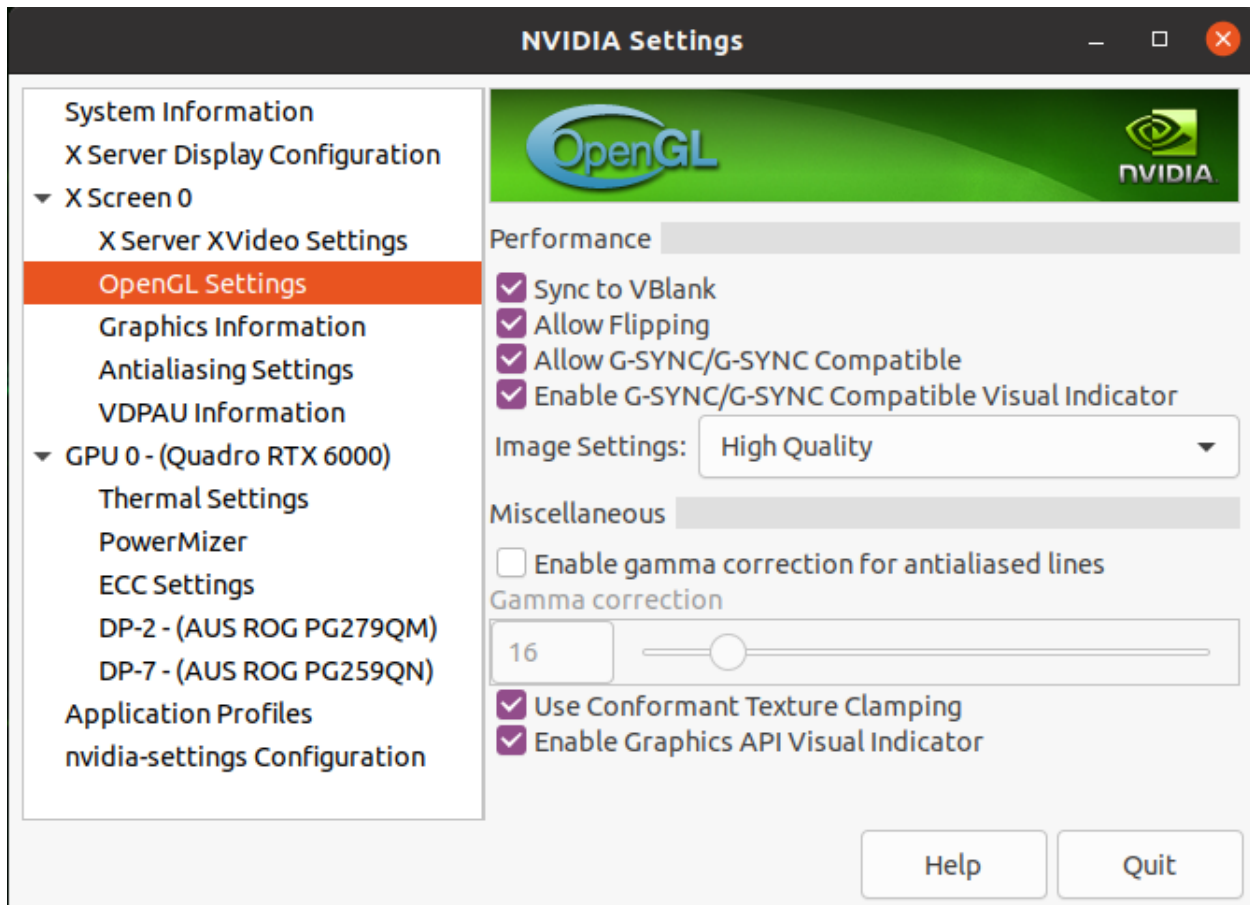


Fig. 5.2: Enable Visual Indicator for the current display

HoloPack 1.2+

The [L4T Compute Assist](#) is a container on NGC which isolates the iGPU stack in order to enable iGPU compute on the developer kits configured for dGPU. Other applications can run concurrently on the dGPU, natively or in another container.

Attention: These utilities enable using the iGPU for capabilities other than **display** only, since they do not address the first conflict listed above.

5.6 Deployment Software Stack

NVIDIA Holoscan accelerates deployment of production-quality applications by providing a set of **OpenEmbedded** build recipes and reference configurations that can be leveraged to customize and build Holoscan-compatible Linux4Tegra (L4T) embedded board support packages (BSP) on Holoscan Developer Kits.

[Holoscan OpenEmbedded/Yocto recipes](#) add OpenEmbedded recipes and sample build configurations to build BSPs for NVIDIA Holoscan Developer Kits that feature support for discrete GPUs (dGPU), AJA Video Systems I/O boards, and the Holoscan SDK. These BSPs are built on a developer's host machine and are then flashed onto a Holoscan Developer Kit using provided scripts.

There are two options available to set up a build environment and start building Holoscan BSP images using OpenEmbedded.

- The first sets up a local build environment in which all dependencies are fetched and installed manually by the developer directly on their host machine. Please refer to the [Holoscan OpenEmbedded/Yocto recipes README](#) for more information on how to use the local build environment.
- The second uses a [Holoscan OpenEmbedded/Yocto Build Container](#) that is provided by NVIDIA on NGC which contains all of the dependencies and configuration scripts such that the entire process of building and flashing a BSP can be done with just a few simple commands.

THIRD PARTY HARDWARE SETUP

GPU compute performance is a key component of the Holoscan hardware platforms, and to optimize GPU based video processing applications and provide lowest possible latency the Holoscan SDK now supports AJA Video Systems capture cards and Emergent Vision Technologies high-speed cameras. The following sections will provide more information on how to setup the system with these technologies.

6.1 AJA Video Systems

AJA provides a wide range of proven, professional video I/O devices, and thanks to a partnership between NVIDIA and AJA, Holoscan supports the AJA NTV2 SDK and device drivers as of the NTV2 SDK 16.1 release.

The AJA drivers and SDK now offer RDMA support for NVIDIA GPUs. This feature allows video data to be captured directly from the AJA card to GPU memory, which significantly reduces latency and system PCI bandwidth for GPU video processing applications as system to GPU copies are eliminated from the processing pipeline.

The following instructions describe the steps required to setup and use an AJA device with RDMA support on Holoscan Developer Kits. Note that the AJA NTV2 SDK support for Holoscan includes all of the [AJA Developer Products](#), though the following instructions have only been verified for the [Corvid 44 12G BNC](#) and [KONA HDMI](#) products, specifically.

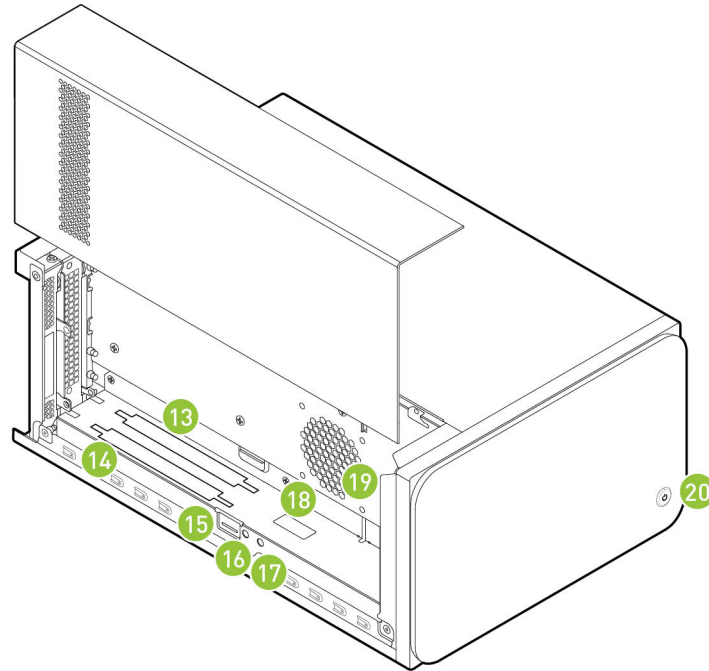
Note: The addition of an AJA device to a Holoscan Developer Kit is optional. The Holoscan SDK has elements that can be run with an AJA device with the additional features mentioned above, but those elements can also run without AJA. For example, there are Holoscan sample applications that have an AJA live input component, however they can also take in video replay as input. Similarly, the latency measurement tool can measure the latency of the video I/O subsystem with or without an AJA device available.

6.1.1 Installing the AJA Hardware

This section describes how to install the AJA hardware on the Clara AGX Developer Kit. Note that the AJA Hardware is also compatible with the NVIDIA IGX Orin Developer Kit.

To install an AJA Video Systems device into the Clara AGX Developer Kit, remove the side access panel by removing two screws on the back of the Clara AGX. This provides access to the two available PCIe slots, labelled 13 and 14 in the [Clara AGX Developer Kit User Guide](#):

While these slots are physically identical PCIe x16 slots, they are connected to the Clara AGX via different PCIe bridges. Only slot 14 shares the same PCIe bridge as the RTX6000 dGPU, and so the AJA device must be installed into slot 14 for RDMA support to be available. The following image shows a [Corvid 44 12G BNC](#) card installed into slot 14 as needed to enable RDMA support.



6.1.2 Installing the AJA Software

The AJA NTV2 SDK includes both the drivers (kernel module) that are required in order to enable an AJA device, as well as the SDK (headers and libraries) that are used to access an AJA device from an application.

The drivers must be loaded every time the system is rebooted, and they must be loaded natively on the host system (i.e. not inside a container). The drivers must be loaded regardless of whether applications will be run natively or inside a container (see *Using AJA Devices in Containers*).

The SDK only needs to be installed on the native host and/or container that will be used to compile applications with AJA support. The Holoscan SDK containers already have the NTV2 SDK installed, and so no additional steps are required to build AJA-enabled applications (such as the reference Holoscan applications) within these containers. However, installing the NTV2 SDK and utilities natively on the host is useful for the initial setup and testing of the AJA device, so the following instructions cover this native installation.

Note: To summarize, the steps in this section must be performed on the native host, outside of a container, with the following steps **required once**:

- *Downloading the AJA NTV2 SDK Source*
- *Building the AJA NTV2 Drivers*

The following steps **required after every reboot**:

- *Loading the AJA NTV2 Drivers*

And the following steps are **optional** (but recommended during the initial setup):

- *Building and Installing the AJA NTV2 SDK*
 - *Testing the AJA Device*
-

Downloading the AJA NTV2 SDK Source

Navigate to a directory where you would like the source code to be downloaded, then perform the following to clone the NTV2 SDK source code.

```
$ git clone https://github.com/nvidia-holoscan/ntv2.git
$ export NTV2=$(pwd)/ntv2
```

Note: These instructions use a fork of the official [AJA NTV2 Repository](#) that is maintained by NVIDIA and may contain additional changes that are required for Holoscan SDK support. These changes will be pushed to the official AJA NTV2 repository whenever possible with the goal to minimize or eliminate divergence between the two repositories.

Building the AJA NTV2 Drivers

The following will build the AJA NTV2 drivers with RDMA support enabled. Once built, the kernel module (`ajantv2.ko`) and load/unload scripts (`load_ajantv2` and `unload_ajantv2`) will be output to the `${NTV2}/bin` directory.

```
$ export AJA_RDMA=1 # Or unset AJA_RDMA to disable RDMA support
$ unset AJA_IGPU # Or export AJA_IGPU=1 to run on the integrated GPU of the
↳ IGX Orin Devkit (L4T >= 35.4)
$ make -j --directory ${NTV2}/ajadriver/linux
```

Loading the AJA NTV2 Drivers

Running any application that uses an AJA device requires the AJA kernel drivers to be loaded, even if the application is being run from within a container.

Note: To enable RDMA with AJA, ensure the *NVIDIA GPUDirect RDMA kernel module is loaded* before the AJA NTV2 drivers.

The AJA drivers must be manually loaded every time the machine is rebooted using the **load_ajantv2** script:

```
$ sudo sh ${NTV2}/bin/load_ajantv2
loaded ajantv2 driver module
created node /dev/ajantv20
```

Note: The NTV2 environment variable must point to the NTV2 SDK path where the drivers were previously built as described in *Building the AJA NTV2 Drivers*.

Secure boot must be disabled in order to load unsigned module. If any errors occur while loading the module refer to the *Troubleshooting* section, below.

Building and Installing the AJA NTV2 SDK

Since the AJA NTV2 SDK is already loaded into the Holoscan containers, this step is not strictly required in order to build or run any Holoscan applications. However, this builds and installs various tools that can be useful for testing the operation of the AJA hardware outside of Holoscan containers, and is required for the steps provided in *Testing the AJA Device*.

```
$ sudo apt-get install -y cmake
$ mkdir ${NTV2}/cmake-build
$ cd ${NTV2}/cmake-build
$ export PATH=/usr/local/cuda/bin:${PATH}
$ cmake ..
$ make -j
$ sudo make install
```

Testing the AJA Device

The following steps depend on tools that were built and installed by the previous step, *Building and Installing the AJA NTV2 SDK*. If any errors occur, see the *Troubleshooting* section, below.

1. To ensure that an AJA device has been installed correctly, the `ntv2enumerateboards` utility can be used:

```
$ ntv2enumerateboards
AJA NTV2 SDK version 16.2.0 build 3 built on Wed Feb 02 21:58:01 UTC 2022
1 AJA device(s) found:
AJA device 0 is called 'KonaHDMI - 0'

This device has a deviceID of 0x10767400
This device has 0 SDI Input(s)
This device has 0 SDI Output(s)
```

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```

This device has 4 HDMI Input(s)
This device has 0 HDMI Output(s)
This device has 0 Analog Input(s)
This device has 0 Analog Output(s)

47 video format(s):
  1080i50, 1080i59.94, 1080i60, 720p59.94, 720p60, 1080p29.97, 1080p30,
  1080p25, 1080p23.98, 1080p24, 2Kp23.98, 2Kp24, 720p50, 1080p50b,
  1080p59.94b, 1080p60b, 1080p50a, 1080p59.94a, 1080p60a, 2Kp25, 525i59.94,
  625i50, UHDp23.98, UHDp24, UHDp25, 4Kp23.98, 4Kp24, 4Kp25, UHDp29.97,
  UHDp30, 4Kp29.97, 4Kp30, UHDp50, UHDp59.94, UHDp60, 4Kp50, 4Kp59.94,
  4Kp60, 4Kp47.95, 4Kp48, 2Kp60a, 2Kp59.94a, 2Kp29.97, 2Kp30, 2Kp50a,
  2Kp47.95a, 2Kp48a

```

2. To ensure that RDMA support has been compiled into the AJA driver and is functioning correctly, the `testrdma` utility can be used:

```

$ testrdma -t500

test device 0 start 0 end 7 size 8388608 count 500

frames/errors 500/0

```

6.1.3 Using AJA Devices in Containers

Accessing an AJA device from a container requires the drivers to be loaded natively on the host (see [Loading the AJA NTV2 Drivers](#)), then the device that is created by the `load_ajantv2` script must be shared with the container using the `--device` docker argument, such as `--device /dev/ajantv20:/dev/ajantv20`.

6.1.4 Troubleshooting

1. **Problem:** The `sudo sh ${NTV2}/bin/load_ajantv2` command returns an error.

Solutions:

- a. Make sure the AJA card is properly installed and powered (see 2.a below)
- b. Check if SecureBoot validation is disabled:

```

$ sudo mokutil --sb-state
SecureBoot enabled
SecureBoot validation is disabled in shim

```

If SecureBoot validation is enabled, disable it with the following procedure:

```

$ sudo mokutil --disable-validation

```

- Enter a temporary password and reboot the system.
- Upon reboot press any key when you see the blue screen MOK Management
- Select Change Secure Boot state
- Enter the password your selected

- Select Yes to disable Secure Book in shim-signed
- After reboot you can verify again that SecureBoot validation is disabled in shim.

2. **Problem:** The `ntv2enumerateboards` command does not find any devices.

Solutions:

- a. Make sure that the AJA device is installed properly and detected by the system (see [Installing the AJA Hardware](#)):

```
$ lspci
0000:00:00.0 PCI bridge: NVIDIA Corporation Device 1ad0 (rev a1)
0000:05:00.0 Multimedia video controller: AJA Video Device eb25 (rev 01)
0000:06:00.0 PCI bridge: Mellanox Technologies Device 1976
0000:07:00.0 PCI bridge: Mellanox Technologies Device 1976
0000:08:00.0 VGA compatible controller: NVIDIA Corporation Device 1e30 (rev a1)
```

- b. Make sure that the AJA drivers are loaded properly (see [Loading the AJA NTV2 Drivers](#)):

```
$ lsmod
Module              Size  Used by
ajantv2             610066  0
nvidia_drm          54950   4
mlx5_ib             170091   0
nvidia_modeset     1250361  8 nvidia_drm
ib_core             211721   1 mlx5_ib
nvidia              34655210 315 nvidia_modeset
```

3. **Problem:** The `testrdma` command outputs the following error:

```
error - GPU buffer lock failed
```

Solution: The AJA drivers need to be compiled with RDMA support enabled. Follow the instructions in [Building the AJA NTV2 Drivers](#), making sure not to skip the `export AJA_RDMA=1` when building the drivers.

6.2 Emergent Vision Technologies (EVT)

Thanks to a collaboration with [Emergent Vision Technologies](#), the Holoscan SDK now supports EVT high-speed cameras.

Note: The addition of an EVT camera to the Holoscan Developer Kits is optional. The Holoscan SDK has an application that can be run with the EVT camera, but there are other applications that can be run without EVT camera.

6.2.1 Installing EVT Hardware

The EVT cameras can be connected to Holoscan Developer Kits through [Mellanox ConnectX SmartNIC](#), with the most simple connection method being a single cable between a camera and the devkit. For 25 GigE cameras that use the SFP28 interface, this can be achieved by using [SFP28](#) cable with [QSFP28 to SFP28 adaptor](#).

Note: The Holoscan SDK application has been tested using a SFP28 copper cable of 2M or less. Longer copper cables or optical cables and optical modules can be used but these have not been tested as a part of this development.

Refer to the [NVIDIA IGX Orin Developer Kit User Guide](#) for the location of the QSFP28 connector on the device.

For EVT camera setup, refer to Hardware Installation in [EVT Camera User's Manual](#). Users need to log in to find be able to download Camera User's Manual.

Tip: The EVT cameras require the user to buy the lens. Based on the application of camera, the lens can be bought from any [online](#) store.

6.2.2 Installing EVT Software

The Emergent SDK needs to be installed in order to compile and run the Clara Holoscan applications with EVT camera. The latest tested version of the Emergent SDK is `eSDK 2.37.05 Linux Ubuntu 20.04.04 Kernel 5.10.65 JP 5.0 HP` and can be downloaded from [here](#). The Emergent SDK comes with headers, libraries and examples. To install the SDK refer to the Software Installation section of [EVT Camera User's Manual](#). Users need to log in to find be able to download Camera User's Manual.

Note: The Emergent SDK depends on Rivermax SDK and the Mellanox OFED Network Drivers. If they're already installed on your system, use the following command when installing the Emergent SDK to avoid duplicate installation:

```
sudo ./install_eSdk.sh no_mellanox
```

Ensure the ConnectX is properly configured to use it with the Emergent SDK.

6.2.3 Testing the EVT Camera

To test if the EVT camera and SDK was installed correctly, run the `eCapture` application with `sudo` privileges. First, ensure that a valid Rivermax license file is under `/opt/mellanox/rivermax/rivermax.lic`, then follow the instructions under the `eCapture` section of [EVT Camera User's Manual](#).

6.2.4 Troubleshooting

1. **Problem:** The application fails to find the EVT camera.

Solution:

- Make sure that the MLNX ConnectX SmartNIC is configured with the correct IP address. Follow section `Configure the ConnectX SmartNIC`

2. **Problem:** The application fails to open the EVT camera.

Solutions:

- Make sure that the application was run with `sudo` privileges.
- Make sure a valid Rivermax license file is located at `/opt/mellanox/rivermax/rivermax.lic`.

3. **Problem:** Fail to find eCapture application in the home window.

Solution:

- Open the terminal and find it under `/opt/EVT/eCapture`. The applications needs to be run with `sudo` privileges.

4. **Problem:** The eCapture application fails to connect to the EVT camera with error message “GVCP ack error”.

Solutions: It could be an issue with the HR12 power connection to the camera. Disconnect the HR12 power connector from the camera and try reconnecting it.

5. **Problem:** The IP address of the Emergent camera is reset even after setting up with the above steps.

Solutions: Check whether the NIC settings in Ubuntu is set to “Connect automatically”. Go to **Settings->Network->NIC for the Camera** and then unselect “Connect automatically” and in the IPv6 tab, select **Disable**.

HOLOSCAN CORE CONCEPTS

Note: In its early days, the Holoscan SDK was tightly linked to the *GXF core concepts*. While the Holoscan SDK still relies on GXF as a backend to execute applications, it now offers its own interface, including a C++ API (0.3), a Python API (0.4), and the ability to write native operators (0.4) without requiring to wrap a GXF extension. Read the *Holoscan and GXF* section for additional details.

An **Application** is composed of **Fragments**, each of which runs a graph of **Operators**. The implementation of that graph is sometimes referred to as a pipeline, or workflow, which can be visualized below:

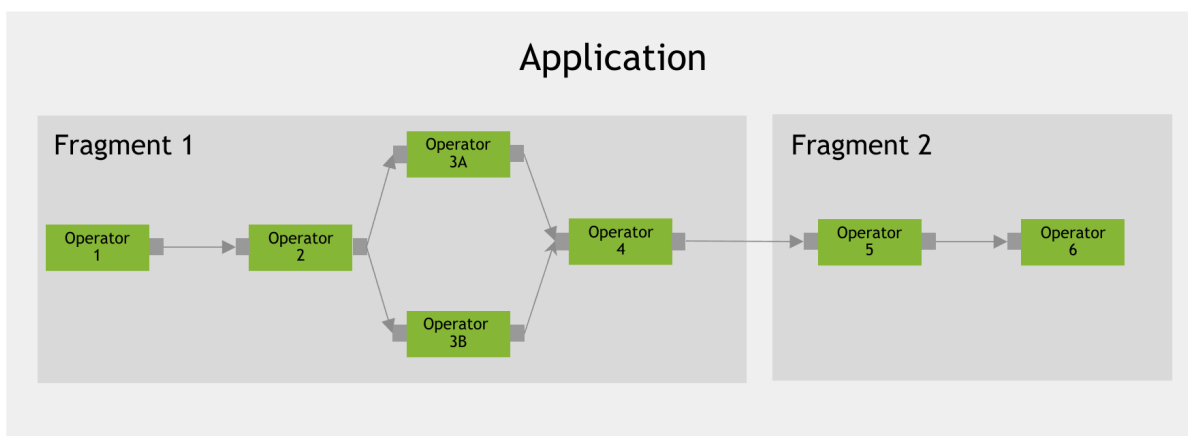


Fig. 7.1: Core concepts: Application

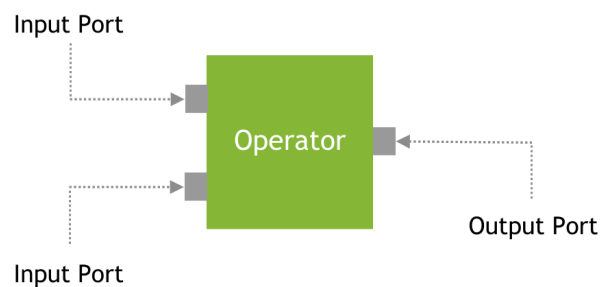


Fig. 7.2: Core concepts: Port

The core concepts of the Holoscan API are:

- **Application:** An application acquires and processes streaming data. An application is a collection of fragments where each fragment can be allocated to execute on a physical node of a Holoscan cluster.
- **Fragment:** A fragment is a building block of the Application. It is a directed graph of operators. A fragment can be assigned to a physical node of a Holoscan cluster during execution. The run-time execution manages communication across fragments. In a Fragment, Operators (Graph Nodes) are connected to each other by flows (Graph Edges).
- **Operator:** An operator is the most basic unit of work in this framework. An Operator receives streaming data at an input port, processes it, and publishes it to one of its output ports. A *Codelet* in GXF would be replaced by an Operator in the Holoscan SDK. An Operator encapsulates Receivers and Transmitters of a GXF *Entity* as Input/Output Ports of the Operator.
- **(Operator) Resource:** Resources such as system memory or a GPU memory pool that an Operator needs to perform its job. Resources are allocated during the initialization phase of the application. This matches the semantics of GXF's *Memory Allocator* or any other components derived from the *Component* class in GXF.
- **Condition:** A condition is a predicate that can be evaluated at runtime to determine if an operator should execute. This matches the semantics of GXF's *Scheduling Term*.
- **Port:** An interaction point between two operators. Operators ingest data at Input ports and publish data at Output ports. *Receiver*, *Transmitter*, and *MessageRouter* in GXF would be replaced with the concept of Input/Output Port of the Operator and the Flow (Edge) of the Application Workflow (DAG) in the Framework.
- **Message:** A generic data object used by operators to communicate information.
- **Executor:** An Executor that manages the execution of a Fragment on a physical node. The framework provides a default Executor that uses a GXF *Scheduler* to execute an Application.

HOLOSCAN BY EXAMPLE

In this section, we demonstrate how to use the Holoscan SDK to build applications through a series of examples. The concepts needed to build your own Holoscan applications will be covered as we go through each example.

Note: Examples source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.1 Hello World

For our first example, we look at how to create a Hello World example using the Holoscan SDK.

In this example we'll cover:

- how to define your application class
- how to define a one-operator workflow
- how to use a `CountCondition` to limit the number of times an operator is executed

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.1.1 Defining the HelloWorldApp class

For more details, see the [Defining an Application Class](#) section.

We define the `HelloWorldApp` class that inherits from holoscan's `Application` base class. An instance of the application is created in `main`. The `run()` method will then start the application.

C++

```
26 class HelloWorldApp : public holoscan::Application {
27     public:
28         void compose() override {
29             using namespace holoscan;
30
31             // Define the operators, allowing the hello operator to execute once
32             auto hello = make_operator<ops::HelloWorldOp>("hello", make_condition<CountCondition>
33                 ↪(1));
34
35             // Define the workflow by adding operator into the graph
36             add_operator(hello);
37         }
38     };
39
40     int main(int argc, char** argv) {
41         auto app = holoscan::make_application<HelloWorldApp>();
42         app->run();
43
44         return 0;
45     }
46 }
```

Python

```
21 class HelloWorldApp(Application):
22     def compose(self):
23         # Define the operators
24         hello = HelloWorldOp(self, CountCondition(self, 1), name="hello")
25
26         # Define the one-operator workflow
27         self.add_operator(hello)
28
29     def main():
30         app = HelloWorldApp()
31         app.run()
32
33     if __name__ == "__main__":
34         main()
```

8.1.2 Defining the HelloWorldApp workflow

For more details, see the [Application Workflows](#) section.

When defining your application class, the primary task is to define the operators used in your application and the interconnectivity between them to define the application workflow. The `HelloWorldApp` uses the simplest form of a workflow which consists of a single operator: `HelloWorldOp`.

For the sake of this first example, we will ignore the details of defining a custom operator to focus on the highlighted information below: when this operator runs (`compute`), it will print out `Hello World!` to the standard output:

C++

```

6 class HelloWorldOp : public Operator {
7 public:
8     HOLOSCAN_OPERATOR_FORWARD_ARGS(HelloWorldOp)
9
10    HelloWorldOp() = default;
11
12    void setup(OperatorSpec& spec) override {
13    }
14
15    void compute(InputContext& op_input, OutputContext& op_output,
16                 ExecutionContext& context) override {
17        std::cout << std::endl;
18        std::cout << "Hello World!" << std::endl;
19        std::cout << std::endl;
20    }
21 };

```

Python

```

4 class HelloWorldOp(Operator):
5     """Simple hello world operator.
6
7     This operator has no ports.
8
9     On each tick, this operator prints out hello world.
10    """
11
12    def setup(self, spec: OperatorSpec):
13        pass
14
15    def compute(self, op_input, op_output, context):
16        print("")
17        print("Hello World!")
18        print("")

```

Defining the application workflow occurs within the application's `compose()` method. In there, we first create an instance of the `HelloWorldOp` operator defined above, then add it to our simple workflow using `add_operator()`.

C++

```

26 class HelloWorldApp : public holoscan::Application {
27 public:
28     void compose() override {
29         using namespace holoscan;
30
31         // Define the operators, allowing the hello operator to execute once
32         auto hello = make_operator<ops::HelloWorldOp>("hello", make_condition<CountCondition>
33             ↳(1));

```

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```

33 // Define the workflow by adding operator into the graph
34 add_operator(hello);
35 }
36 };
37

```

Python

```

21 class HelloWorldApp(Application):
22     def compose(self):
23         # Define the operators
24         hello = HelloWorldOp(self, CountCondition(self, 1), name="hello")
25
26         # Define the one-operator workflow
27         self.add_operator(hello)

```

Holoscan applications deal with streaming data, so an operator's `compute()` method will be called continuously until some situation arises that causes the operator to stop. For our Hello World example, we want to execute the operator only once. We can impose such a condition by passing a `CountCondition` object as an argument to the operator's constructor.

For more details, see the [Configuring operator conditions](#) section.

8.1.3 Running the Application

Running the application should give you the following output in your terminal:

```
Hello World!
```

Congratulations! You have successfully run your first Holoscan SDK application!

8.2 Ping Simple

Most applications will require more than one operator. In this example, we will create two operators where one operator will produce and send data while the other operator will receive and print the data. The code in this example makes use of the built-in **PingTxOp** and **PingRxOp** operators that are defined in the `holoscan::ops` namespace.

In this example we'll cover:

- how to use built-in operators
- how to use `add_flow()` to connect operators together

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.2.1 Operators and Workflow

Here is an example workflow involving two operators that are connected linearly.

Fig. 8.1: A linear workflow

In this example, the source operator **PingTxOp** produces integers from 1 to 10 and passes it to the sink operator **PingRxOp** which prints the integers to standard output.

8.2.2 Connecting Operators

We can connect two operators by calling `add_flow()` (C++/Python) in the application's `compose()` method.

The `add_flow()` method (C++/Python) takes the source operator, the destination operator, and the optional port name pairs. The port name pair is used to connect the output port of the source operator to the input port of the destination operator. The first element of the pair is the output port name of the upstream operator and the second element is the input port name of the downstream operator. An empty port name ("") can be used for specifying a port name if the operator has only one input/output port. If there is only one output port in the upstream operator and only one input port in the downstream operator, the port pairs can be omitted.

The following code shows how to define a linear workflow in the `compose()` method for our example. Note that when an operator appears in an `add_flow()` statement, it doesn't need to be added into the workflow separately using `add_operator()`.

C++

```

1  #include <holoscan/holoscan.hpp>
2  #include <holoscan/operators/ping_tx/ping_tx.hpp>
3  #include <holoscan/operators/ping_rx/ping_rx.hpp>
4
5  class MyPingApp : public holoscan::Application {
6  public:
7      void compose() override {
8          using namespace holoscan;
9          // Create the tx and rx operators
10         auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
11         auto rx = make_operator<ops::PingRxOp>("rx");
12
13         // Connect the operators into the workflow: tx -> rx
14         add_flow(tx, rx);
15     }
16 };
17
18 int main(int argc, char** argv) {
19     auto app = holoscan::make_application<MyPingApp>();
20     app->run();
21
22     return 0;
23 }

```

- The header files that define **PingTxOp** and **PingRxOp** are included on lines 2 and 3 respectively.

- We create an instance of the **PingTxOp** using the `make_operator()` function (line 10) with the name “tx” and constrain it’s `compute()` method to execute 10 times.
- We create an instance of the **PingRxOp** using the `make_operator()` function (line 11) with the name “rx”.
- The tx and rx operators are connected using `add_flow()` (line 14)

Python

```
1 from holoscan.conditions import CountCondition
2 from holoscan.core import Application
3 from holoscan.operators import PingRxOp, PingTxOp
4
5 class MyPingApp(Application):
6     def compose(self):
7         # Create the tx and rx operators
8         tx = PingTxOp(self, CountCondition(self, 10), name="tx")
9         rx = PingRxOp(self, name="rx")
10
11         # Connect the operators into the workflow: tx -> rx
12         self.add_flow(tx, rx)
13
14
15 def main():
16     app = MyPingApp()
17     app.run()
18
19
20 if __name__ == "__main__":
21     main()
```

- The built-in holoscan operators, **PingRxOp** and **PingTxOp**, are imported on line 3.
- We create an instance of the **PingTxOp** operator with the name “tx” and constrain it’s `compute()` method to execute 10 times (line 8).
- We create an instance of the **PingRxOp** operator with the name “rx” (line 9).
- The tx and rx operators are connected using `add_flow()` which defines this application’s workflow (line 12).

8.2.3 Running the Application

Running the application should give you the following output in your terminal:

```
Rx message value: 1
Rx message value: 2
Rx message value: 3
Rx message value: 4
Rx message value: 5
Rx message value: 6
Rx message value: 7
Rx message value: 8
Rx message value: 9
Rx message value: 10
```

8.3 Ping Custom Op

In this section, we will modify the previous `ping_simple` example to add a custom operator into the workflow. We've already seen a custom operator defined in the `hello_world` example but skipped over some of the details.

In this example we will cover:

- the details of creating your own custom operator class
- how to add input and output ports to your operator
- how to add parameters to your operator
- the data type of the messages being passed between operators

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.3.1 Operators and Workflow

Here is the diagram of the operators and workflow used in this example.

Fig. 8.2: A linear workflow with new custom operator

Compared to the previous example, we are adding a new **PingMxOp** operator between the **PingTxOp** and **PingRxOp** operators. This new operator takes as input an integer, multiplies it by a constant factor, and then sends the new value to **PingRxOp**. You can think of this custom operator as doing some data processing on an input stream before sending the result to downstream operators.

8.3.2 Configuring Operator Input and Output Ports

Our custom operator needs 1 input and 1 output port and can be added by calling `spec.input()` and `spec.output()` methods within the operator's `setup()` method. This requires providing the data type and name of the port as arguments (for C++ API), or just the port name (for Python API). We will see an example of this in the code snippet below. For more details, see [Specifying operator inputs and outputs \(C++\)](#) or [Specifying operator inputs and outputs \(Python\)](#).

8.3.3 Configuring Operator Parameters

Operators can be made more reusable by customizing their parameters during initialization. The custom parameters can be provided either directly as arguments or accessed from the application's YAML configuration file. We will show how to use the former in this example to customize the “multiplier” factor of our **PingMxOp** custom operator. Configuring operators using a YAML configuration file will be shown in a subsequent [example](#). For more details, see [Configuring operator parameters](#).

The code snippet below shows how to define the **PingMxOp** class.

C++

```

1  #include <holoscan/holoscan.hpp>
2  #include <holoscan/operators/ping_tx/ping_tx.hpp>
3  #include <holoscan/operators/ping_rx/ping_rx.hpp>
4
5  namespace holoscan::ops {
6
7  class PingMxOp : public Operator {
8  public:
9      HOLOSCAN_OPERATOR_FORWARD_ARGS(PingMxOp)
10
11      PingMxOp() = default;
12
13      void setup(OperatorSpec& spec) override {
14          spec.input<int>("in");
15          spec.output<int>("out");
16          spec.param(multiplier_, "multiplier", "Multiplier", "Multiply the input by this value
17      ↪", 2);
18      }
19
20      void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext&)
21      ↪override {
22          auto value = op_input.receive<int>("in");
23
24          std::cout << "Middle message value: " << value << std::endl;
25
26          // Multiply the value by the multiplier parameter
27          value *= multiplier_;
28
29          op_output.emit(value);
30      };
31
32  private:
33      Parameter<int> multiplier_;
34  };
35 } // namespace holoscan::ops

```

- The PingMxOp class inherits from the Operator base class (line 7).
- The HOLOSCAN_OPERATOR_FORWARD_ARGS macro (line 9) is syntactic sugar to help forward an operator’s constructor arguments to the Operator base class, and is a convenient shorthand to avoid having to manually define constructors for your operator with the necessary parameters.
- Input/output ports with the names “in”/“out” are added to the operator spec on lines 14 and 15 respectively. The port type of both ports are int as indicated by the template argument <int>.
- We add a “multiplier” parameter to the operator spec (line 16) with a default value of 2. This parameter is tied to the private “multiplier_” data member.
- In the compute() method, we receive the integer data from the operator’s “in” port (line 20), print it’s value, multiply it’s value by the multiplicative factor, and send the new value downstream (line 27).
- On line 20, note that the data being passed between the operators has the type int.

- The call to `op_output.emit(value)` on line 27 is equivalent to `op_output.emit(value, "out")` since this operator has only 1 output port. If the operator has more than 1 output port, then the port name is required.

Python

```

1 from holoscan.conditions import CountCondition
2 from holoscan.core import Application, Operator, OperatorSpec
3 from holoscan.operators import PingRxOp, PingTxOp
4
5 class PingMxOp(Operator):
6     """Example of an operator modifying data.
7
8     This operator has 1 input and 1 output port:
9         input: "in"
10        output: "out"
11
12    The data from the input is multiplied by the "multiplier" parameter
13
14    """
15
16    def setup(self, spec: OperatorSpec):
17        spec.input("in")
18        spec.output("out")
19        spec.param("multiplier", 2)
20
21    def compute(self, op_input, op_output, context):
22        value = op_input.receive("in")
23        print(f"Middle message value: {value}")
24
25        # Multiply the values by the multiplier parameter
26        value *= self.multiplier
27
28        op_output.emit(value, "out")

```

- The `PingMxOp` class inherits from the `Operator` base class (line 5).
- Input/output ports with the names “in”/”out” are added to the operator spec on lines 17 and 18 respectively.
- We add a “multiplier” parameter to the operator spec with a default value of 2 (line 19).
- In the `compute()` method, we receive the integer data from the operator’s “in” port (line 22), print it’s value, multiply it’s value by the multiplicative factor, and send the new value downstream (line 28).

Now that the custom operator has been defined, we create the application, operators, and define the workflow.

C++

```

35 class MyPingApp : public holoscan::Application {
36 public:
37     void compose() override {
38         using namespace holoscan;
39         // Define the tx, mx, rx operators, allowing tx operator to execute 10 times
40         auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
41         auto mx = make_operator<ops::PingMxOp>("mx", Arg("multiplier", 3));
42         auto rx = make_operator<ops::PingRxOp>("rx");
43
44         // Define the workflow: tx -> mx -> rx
45         add_flow(tx, mx);
46         add_flow(mx, rx);
47     }
48 };
49
50 int main(int argc, char** argv) {
51     auto app = holoscan::make_application<MyPingApp>();
52     app->run();
53
54     return 0;
55 }

```

- The tx, mx, and rx operators are created in the `compose()` method on lines 40–42.
- The custom mx operator is created in exactly the same way with `make_operator()` (line 41) as the built-in operators, and configured with a “multiplier” parameter initialized to 3 which overrides the parameter’s default value of 2 (line 16).
- The workflow is defined by connecting tx to mx, and mx to rx using `add_flow()` on lines 45–46.

Python

```

29 class MyPingApp(Application):
30     def compose(self):
31         # Define the tx, mx, rx operators, allowing the tx operator to execute 10 times
32         tx = PingTxOp(self, CountCondition(self, 10), name="tx")
33         mx = PingMxOp(self, name="mx", multiplier=3)
34         rx = PingRxOp(self, name="rx")
35
36         # Define the workflow: tx -> mx -> rx
37         self.add_flow(tx, mx)
38         self.add_flow(mx, rx)
39
40
41 def main():
42     app = MyPingApp()
43     app.run()
44
45
46 if __name__ == "__main__":
47     main()

```

- The tx, mx, and rx operators are created in the `compose()` method on lines 32–34.
- The custom mx operator is created in exactly the same way as the built-in operators (line 33), and configured with a “multiplier” parameter initialized to 3 which overrides the parameter’s default value of 2 (line 19).
- The workflow is defined by connecting tx to mx, and mx to rx using `add_flow()` on lines 37–38.

8.3.4 Message Data Types

For the C++ API, the messages that are passed between the operators are the objects of the data type at the inputs and outputs, so the `value` variable from lines 20 and 25 of the example above has the type `int`. For the Python API, the messages passed between operators can be arbitrary Python objects so no special consideration is needed since it is not restricted to the stricter parameter typing used for C++ API operators.

Let’s look at the code snippet for the built-in **PingTxOp** class and see if this helps to make it clearer.

C++

```

1  #include "holoscan/operators/ping_tx/ping_tx.hpp"
2
3  namespace holoscan::ops {
4
5  void PingTxOp::setup(OperatorSpec& spec) {
6      spec.output<int>("out");
7  }
8
9  void PingTxOp::compute(InputContext&, OutputContext& op_output, ExecutionContext&) {
10     auto value = index_++;
11     op_output.emit(value, "out");
12 }
13
14 } // namespace holoscan::ops

```

- The “out” port of the **PingTxOp** has the type `int` (line 6).
- An integer is published to the “out” port when calling `emit()` (line 11).
- The message received by the downstream **PingMxOp** operator when it calls `op_input.receive<int>()` has the type `int`.

Python

```

1  class PingTxOp(Operator):
2      """Simple transmitter operator.
3
4      This operator has a single output port:
5          output: "out"
6
7      On each tick, it transmits an integer to the "out" port.
8      """
9
10     def setup(self, spec: OperatorSpec):
11         spec.output("out")

```

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```

12
13     def compute(self, op_input, op_output, context):
14         op_output.emit(self.index, "out")
15         self.index += 1

```

- No special consideration is necessary for the Python version, we simply call `emit()` and pass the integer object (line 14).

Attention: For advance use cases, e.g., when writing C++ applications where you need interoperability between C++ native and GXF operators you will need to use the `holoscan::TensorMap` type instead. See [Interoperability between GXF and native C++ operators](#) for more details. If you are writing a Python application which needs a mixture of Python wrapped C++ operators and native Python operators, see [Interoperability between wrapped and native Python operators](#)

8.3.5 Running the Application

Running the application should give you the following output in your terminal:

```

Middle message value: 1
Rx message value: 3
Middle message value: 2
Rx message value: 6
Middle message value: 3
Rx message value: 9
Middle message value: 4
Rx message value: 12
Middle message value: 5
Rx message value: 15
Middle message value: 6
Rx message value: 18
Middle message value: 7
Rx message value: 21
Middle message value: 8
Rx message value: 24
Middle message value: 9
Rx message value: 27
Middle message value: 10
Rx message value: 30

```

8.4 Ping Multi Port

In this section, we look at how to create an application with a more complex workflow where operators may have multiple input/output ports that send/receive a user-defined data type.

In this example we will cover:

- how to send/receive messages with a custom data type
- how to add a port that can receive any number of inputs

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.4.1 Operators and Workflow

Here is the diagram of the operators and workflow used in this example.

Fig. 8.3: A workflow with multiple inputs and outputs

In this example, `PingTxOp` sends a stream of odd integers to the `out1` port, and even integers to the `out2` port. `PingMxOp` receives these values using `in1` and `in2` ports, multiplies them by a constant factor, then forwards them to a single port - `receivers` - on `PingRxOp`.

8.4.2 User Defined Data Types

In the previous ping examples, the port types for our operators were integers, but the Holoscan SDK can send any arbitrary data type. In this example, we'll see how to configure operators for our user-defined `ValueData` class.

C++

```

1  #include "holoscan/holoscan.hpp"
2
3  class ValueData {
4  public:
5      ValueData() = default;
6      explicit ValueData(int value) : data_(value) {
7          HOLOSCAN_LOG_TRACE("ValueData::ValueData(): {}", data_);
8      }
9      ~ValueData() { HOLOSCAN_LOG_TRACE("ValueData::~~ValueData(): {}", data_); }
10
11     void data(int value) { data_ = value; }
12
13     int data() const { return data_; }
14
15 private:
16     int data_;
17 };

```

The `ValueData` class wraps a simple integer (line 6, 16), but could have been arbitrarily complex.

Note: The `HOLOSCAN_LOG_<LEVEL>()` macros can be used for logging with `fmtlib` syntax (lines 7, 9 above) as demonstrated across this example. See the [Logging](#) section for more details.

Python

```

1 from holoscan.conditions import CountCondition
2 from holoscan.core import Application, Operator, OperatorSpec
3
4 class ValueData:
5     """Example of a custom Python class"""
6
7     def __init__(self, value):
8         self.data = value
9
10    def __repr__(self):
11        return f"ValueData({self.data})"
12
13    def __eq__(self, other):
14        return self.data == other.data
15
16    def __hash__(self):
17        return hash(self.data)

```

The ValueData class is a simple wrapper, but could have been arbitrarily complex.

8.4.3 Defining an Explicit Number of Inputs and Outputs

After defining our custom ValueData class, we configure our operators' ports to send/receive messages of this type, similarly to the *previous example*.

This is the first operator - PingTxOp - sending ValueData objects on two ports, out1 and out2:

C++

```

18 namespace holoscan::ops {
19
20 class PingTxOp : public Operator {
21 public:
22     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingTxOp)
23
24     PingTxOp() = default;
25
26     void setup(OperatorSpec& spec) override {
27         spec.output<std::shared_ptr<ValueData>>("out1");
28         spec.output<std::shared_ptr<ValueData>>("out2");
29     }
30
31     void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
32         auto value1 = std::make_shared<ValueData>(index_++);
33         op_output.emit(value1, "out1");
34
35         auto value2 = std::make_shared<ValueData>(index_++);
36         op_output.emit(value2, "out2");
37     };

```

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```

38     int index_ = 1;
39 };

```

- We configure the output ports with the `ValueData` type on lines 27 and 28 using `spec.output<std::shared_ptr<ValueData>>()`. Therefore, the data type for the output ports is an object to a shared pointer to a `ValueData` object.
- The values are then sent out using `op_output.emit()` on lines 33 and 36. The port name is required since there is more than one port on this operator.

Note: Data types of the output ports are shared pointers (`std::shared_ptr`), hence the call to `std::make_shared<ValueData>(...)` on lines 32 and 35.

Python

```

19 class PingTxOp(Operator):
20     """Simple transmitter operator.
21
22     This operator has:
23         outputs: "out1", "out2"
24
25     On each tick, it transmits a `ValueData` object at each port. The
26     transmitted values are even on port1 and odd on port2 and increment with
27     each call to compute.
28     """
29
30     def __init__(self, fragment, *args, **kwargs):
31         self.index = 1
32         super().__init__(fragment, *args, **kwargs)
33
34     def setup(self, spec: OperatorSpec):
35         spec.output("out1")
36         spec.output("out2")
37
38     def compute(self, op_input, op_output, context):
39         value1 = ValueData(self.index)
40         self.index += 1
41         op_output.emit(value1, "out1")
42
43         value2 = ValueData(self.index)
44         self.index += 1
45         op_output.emit(value2, "out2")

```

- We configure the output ports on lines 35 and 36 using `spec.output()`. There is no need to reference the type (`ValueData`) in Python.
- The values are then sent out using `op_output.emit()` on lines 41 and 45.

We then configure the middle operator - `PingMxOp` - to receive that data on ports `in1` and `in2`:

C++

```

40 class PingMxOp : public Operator {
41 public:
42     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingMxOp)
43
44     PingMxOp() = default;
45
46     void setup(OperatorSpec& spec) override {
47         spec.input<std::shared_ptr<ValueData>>("in1");
48         spec.input<std::shared_ptr<ValueData>>("in2");
49         spec.output<std::shared_ptr<ValueData>>("out1");
50         spec.output<std::shared_ptr<ValueData>>("out2");
51         spec.param(multiplier_, "multiplier", "Multiplier", "Multiply the input by this value
↪", 2);
52     }
53
54     void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext&)
↪override {
55         auto value1 = op_input.receive<std::shared_ptr<ValueData>>("in1").value();
56         auto value2 = op_input.receive<std::shared_ptr<ValueData>>("in2").value();
57
58         HOLOSCAN_LOG_INFO("Middle message received (count: {})", count_++);
59
60         HOLOSCAN_LOG_INFO("Middle message value1: {}", value1->data());
61         HOLOSCAN_LOG_INFO("Middle message value2: {}", value2->data());
62
63         // Multiply the values by the multiplier parameter
64         value1->data(value1->data() * multiplier_);
65         value2->data(value2->data() * multiplier_);
66
67         op_output.emit(value1, "out1");
68         op_output.emit(value2, "out2");
69     };
70
71 private:
72     int count_ = 1;
73     Parameter<int> multiplier_;
74 };

```

- We configure the input ports with the `std::shared_ptr<ValueData>` type on lines 47 and 48 using `spec.input<std::shared_ptr<ValueData>>()`.
- The values are received using `op_input.receive()` on lines 55 and 56 using the port names. The received values are of type `std::shared_ptr<ValueData>` as mentioned in the templated `receive()` method.

Python

```

46 class PingMxOp(Operator):
47     """Example of an operator modifying data.
48
49     This operator has:
50         inputs: "in1", "in2"
51         outputs: "out1", "out2"
52
53     The data from each input is multiplied by a user-defined value.
54     """
55
56     def __init__(self, fragment, *args, **kwargs):
57         self.count = 1
58         super().__init__(fragment, *args, **kwargs)
59
60     def setup(self, spec: OperatorSpec):
61         spec.input("in1")
62         spec.input("in2")
63         spec.output("out1")
64         spec.output("out2")
65         spec.param("multiplier", 2)
66
67     def compute(self, op_input, op_output, context):
68         value1 = op_input.receive("in1")
69         value2 = op_input.receive("in2")
70         print(f"Middle message received (count: {self.count})")
71         self.count += 1
72
73         print(f"Middle message value1: {value1.data}")
74         print(f"Middle message value2: {value2.data}")
75
76         # Multiply the values by the multiplier parameter
77         value1.data *= self.multiplier
78         value2.data *= self.multiplier
79
80         op_output.emit(value1, "out1")
81         op_output.emit(value2, "out2")

```

Sending messages of arbitrary data types is pretty straightforward in Python. The code to define the operator input ports (lines 61–62), and to receive them (lines 68, 69) did not change when we went from passing `int` to `ValueData` objects.

`PingMxOp` processes the data, then sends it out on two ports, similarly to what is done by `PingTxOp` above.

8.4.4 Receiving Any Number of Inputs

In this workflow, `PingRxOp` has a single input port - `receivers` - that is connected to two upstream ports from `PingMxOp`. When an input port needs to connect to multiple upstream ports, we define it with `spec.param()` instead of `spec.input()`. The inputs are then stored in a vector, following the order they were added with `add_flow()`.

C++

```

75 class PingRxOp : public Operator {
76     public:
77         HOLOSCAN_OPERATOR_FORWARD_ARGS(PingRxOp)
78
79         PingRxOp() = default;
80
81         void setup(OperatorSpec& spec) override {
82             spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {}
83         ↪);
84         }
85
86         void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
87             auto value_vector =
88                 op_input.receive<std::vector<std::shared_ptr<ValueData>>>("receivers").value();
89
90             HOLOSCAN_LOG_INFO("Rx message received (count: {}, size: {})", count_++, value_
91 ↪vector.size());
92
93             HOLOSCAN_LOG_INFO("Rx message value1: {}", value_vector[0]->data());
94             HOLOSCAN_LOG_INFO("Rx message value2: {}", value_vector[1]->data());
95         };
96
97     private:
98         Parameter<std::vector<IOSpec*>> receivers_;
99         int count_ = 1;
100 }; // namespace holoscan::ops

```

- In the operator's `setup()` method, we define a parameter `receivers` (line 82) that is tied to the private data member `receivers_` (line 96) of type `Parameter<std::vector<IOSpec*>>`.
- The values are retrieved using `op_input.receive<std::vector<std::shared_ptr<ValueData>>>(...)`.
- `value_vector`'s type is `std::vector<std::shared_ptr<ValueData>>` (lines 86-87).

Python

```

82 class PingRxOp(Operator):
83     """Simple receiver operator.
84
85     This operator has:
86         input: "receivers"
87
88     This is an example of a native operator that can dynamically have any
89     number of inputs connected to is "receivers" port.
90     """
91
92     def __init__(self, fragment, *args, **kwargs):
93         self.count = 1
94         super().__init__(fragment, *args, **kwargs)
95
96     def setup(self, spec: OperatorSpec):
97         spec.param("receivers", kind="receivers")
98
99     def compute(self, op_input, op_output, context):
100         values = op_input.receive("receivers")
101         print(f"Rx message received (count: {self.count}, size: {len(values)})")
102         self.count += 1
103         print(f"Rx message value1: {values[0].data}")
104         print(f"Rx message value2: {values[1].data}")

```

- In Python, a port that can be connected to multiple upstream ports is created by defining a parameter and setting the argument kind="receivers" (line 97).
- The call to receive() returns a tuple of ValueData objects (line 100).

The rest of the code creates the application, operators, and defines the workflow:

C++

```

100 class MyPingApp : public holoscan::Application {
101     public:
102     void compose() override {
103         using namespace holoscan;
104
105         // Define the tx, mx, rx operators, allowing the tx operator to execute 10 times
106         auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
107         auto mx = make_operator<ops::PingMxOp>("mx", Arg("multiplier", 3));
108         auto rx = make_operator<ops::PingRxOp>("rx");
109
110         // Define the workflow
111         add_flow(tx, mx, {{ "out1", "in1"}, {"out2", "in2"}});
112         add_flow(mx, rx, {{ "out1", "receivers"}, {"out2", "receivers"}});
113     }
114 };
115
116 int main(int argc, char** argv) {
117     auto app = holoscan::make_application<MyPingApp>();

```

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```

118     app->run();
119
120     return 0;
121 }

```

Python

```

105 class MyPingApp(Application):
106     def compose(self):
107         # Define the tx, mx, rx operators, allowing the tx operator to execute 10 times
108         tx = PingTxOp(self, CountCondition(self, 10), name="tx")
109         mx = PingMxOp(self, name="mx", multiplier=3)
110         rx = PingRxOp(self, name="rx")
111
112         # Define the workflow
113         self.add_flow(tx, mx, {"out1", "in1"}, {"out2", "in2"})
114         self.add_flow(mx, rx, {"out1", "receivers"}, {"out2", "receivers"})
115
116     def main():
117         app = MyPingApp()
118         app.run()
119
120
121
122 if __name__ == "__main__":
123     main()

```

- The operators `tx`, `mx`, and `rx` are created in the application's `compose()` similarly to previous examples.
- Since the operators in this example have multiple input/output ports, we need to specify the third, port name pair argument when calling `add_flow()`:
 - `tx/out1` is connected to `mx/in1`, and `tx/out2` is connected to `mx/in2`.
 - `mx/out1` and `mx/out2` are both connected to `rx/receivers`.

8.4.5 Running the Application

Running the application should give you output similar to the following in your terminal.

```

[info] [gxf_executor.cpp:222] Creating context
[info] [gxf_executor.cpp:1531] Loading extensions from configs...
[info] [gxf_executor.cpp:1673] Activating Graph...
[info] [gxf_executor.cpp:1703] Running Graph...
[info] [gxf_executor.cpp:1705] Waiting for completion...
[info] [gxf_executor.cpp:1706] Graph execution waiting. Fragment:
[info] [greedy_scheduler.cpp:195] Scheduling 3 entities
[info] [ping_multi_port.cpp:80] Middle message received (count: 1)
[info] [ping_multi_port.cpp:82] Middle message value1: 1
[info] [ping_multi_port.cpp:83] Middle message value2: 2
[info] [ping_multi_port.cpp:112] Rx message received (count: 1, size: 2)

```

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```
[info] [ping_multi_port.cpp:114] Rx message value1: 3
[info] [ping_multi_port.cpp:115] Rx message value2: 6
[info] [ping_multi_port.cpp:80] Middle message received (count: 2)
[info] [ping_multi_port.cpp:82] Middle message value1: 3
[info] [ping_multi_port.cpp:83] Middle message value2: 4
[info] [ping_multi_port.cpp:112] Rx message received (count: 2, size: 2)
[info] [ping_multi_port.cpp:114] Rx message value1: 9
[info] [ping_multi_port.cpp:115] Rx message value2: 12
...
[info] [ping_multi_port.cpp:114] Rx message value1: 51
[info] [ping_multi_port.cpp:115] Rx message value2: 54
[info] [ping_multi_port.cpp:80] Middle message received (count: 10)
[info] [ping_multi_port.cpp:82] Middle message value1: 19
[info] [ping_multi_port.cpp:83] Middle message value2: 20
[info] [ping_multi_port.cpp:112] Rx message received (count: 10, size: 2)
[info] [ping_multi_port.cpp:114] Rx message value1: 57
[info] [ping_multi_port.cpp:115] Rx message value2: 60
[info] [greedy_scheduler.cpp:374] Scheduler stopped: Some entities are waiting for
↳ execution, but there are no periodic or async entities to get out of the deadlock.
[info] [greedy_scheduler.cpp:403] Scheduler finished.
[info] [gxf_executor.cpp:1714] Graph execution deactivating. Fragment:
[info] [gxf_executor.cpp:1715] Deactivating Graph...
[info] [gxf_executor.cpp:1718] Graph execution finished. Fragment:
[info] [gxf_executor.cpp:241] Destroying context
```

Note: Depending on your log level you may see more or fewer messages. The output above was generated using the default value of INFO.

Refer to the [Logging](#) section for more details on how to set the log level.

8.5 Video Replayer

So far we have been working with simple operators to demonstrate Holoscan SDK concepts. In this example, we look at two built-in Holoscan operators that have many practical applications.

In this example we'll cover:

- how to load a video file from disk using **VideoStreamReplayerOp** operator
- how to display video using **HolovizOp** operator
- how to configure your operator's parameters using a YAML configuration file

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.5.1 Operators and Workflow

Here is the diagram of the operators and workflow used in this example.

Fig. 8.4: Workflow to load and display video from a file

We connect the “output” port of the replayer operator to the “receivers” port of the Holoviz operator.

8.5.2 Video Stream Replayer Operator

The built-in video stream replayer operator can be used to replay a video stream that has been encoded as gxf entities. You can use the `convert_video_to_gxf_entities.py` script to encode a video file as gxf entities for use by this operator.

This operator processes the encoded file sequentially and supports realtime, faster than realtime, or slower than realtime playback of prerecorded data. The input data can optionally be repeated to loop forever or only for a specified count. For more details, see `operators-video-stream-replayer`.

We will use the replayer to read gxf entities from disk and send the frames downstream to the Holoviz operator.

8.5.3 Holoviz Operator

The built-in Holoviz operator provides the functionality to composite real time streams of frames with multiple different other layers like segmentation mask layers, geometry layers and GUI layers.

We will use Holoviz to display frames that have been sent by the replayer operator to its “receivers” port which can receive any number of inputs. In more intricate workflows, this port can receive multiple streams of input data where, for example, one stream is the original video data while other streams detect objects in the video to create bounding boxes and/or text overlays.

8.5.4 Application Configuration File (YAML)

The SDK supports reading an optional YAML configuration file and can be used to customize the application’s workflow and operators. For more complex workflows, it may be helpful to use the application configuration file to help separate operator parameter settings from your code. See *Configuring an Application* for additional details.

Tip: For C++ applications, the configuration file can be a nice way to set the behavior of the application at runtime without having to recompile the code.

This example uses the following configuration file to configure the parameters for the replayer and Holoviz operators. The full list of parameters can be found at `operators-video-stream-replayer` and `operators-holoviz`.

```
%YAML 1.2
replayer:
  directory: "../data/racerox"    # Path to gxf entity video data
  basename: "racerox"            # Look for <basename>.gxf_{entities|index}
  frame_rate: 0                  # Frame rate to replay. (default: 0 follow frame rate in
  timestamps)
  repeat: true                   # Loop video? (default: false)
  realtime: true                 # Play in realtime, based on frame_rate/timestamps (default:
  true)
  count: 0                       # Number of frames to read (default: 0 for no frame count
  restriction)
```

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```

holoviz:
  width: 854          # width of window size
  height: 480         # height of window size
  tensors:
    - name: ""        # name of tensor containing input data to display
      type: color      # input type e.g., color, triangles, text, depth_map
      opacity: 1.0     # layer opacity
      priority: 0      # determines render order, higher priority layers are rendered on_
↪top

```

The code below shows our `video_replayer` example. Operator parameters are configured from a configuration file using `from_config()` (C++) and `self.**kwargs()` (Python).

C++

```

1  #include <holoscan/holoscan.hpp>
2  #include <holoscan/operators/video_stream_replayer/video_stream_replayer.hpp>
3  #include <holoscan/operators/holoviz/holoviz.hpp>
4
5  class VideoReplayerApp : public holoscan::Application {
6  public:
7      void compose() override {
8          using namespace holoscan;
9
10         // Define the replayer and holoviz operators and configure using yaml configuration
11         auto replayer = make_operator<ops::VideoStreamReplayerOp>("replayer", from_config(
↪"replayer"));
12         auto visualizer = make_operator<ops::HolovizOp>("holoviz", from_config("holoviz"));
13
14         // Define the workflow: replayer -> holoviz
15         add_flow(replayer, visualizer, {"output", "receivers"});
16     }
17 };
18
19 int main(int argc, char** argv) {
20     // Get the yaml configuration file
21     auto config_path = std::filesystem::canonical(argv[0]).parent_path();
22     config_path /= std::filesystem::path("video_replayer.yaml");
23     if ( argc >= 2 ) {
24         config_path = argv[1];
25     }
26
27     auto app = holoscan::make_application<VideoReplayerApp>();
28     app->config(config_path);
29     app->run();
30
31     return 0;
32 }

```

- The built-in **VideoStreamReplayerOp** and **HolovizOp** operators are included from lines 1 and 2 respectively.

- We create an instance of **VideoStreamReplayerOp** named “replayer” with parameters initialized from the YAML configuration file using the call to `from_config()` (line 11).
- We create an instance of **HolovizOp** named “holoviz” with parameters initialized from the YAML configuration file using the call to `from_config()` (line 12).
- The “output” port of “replayer” operator is connected to the “receivers” port of the “holoviz” operator and defines the application workflow (line 34).
- The application’s YAML configuration file contains the parameters for our operators, and is loaded on line 28. If no argument is passed to the executable, the application looks for a file with the name “video_replayer.yaml” in the same directory as the executable (lines 21-22), otherwise it treats the argument as the path to the app’s YAML configuration file (lines 23-25).

Python

```

1 import os
2 import sys
3
4 from holoscan.core import Application
5 from holoscan.operators import HolovizOp, VideoStreamReplayerOp
6
7 sample_data_path = os.environ.get("HOLOSCAN_INPUT_PATH", "../data")
8
9
10 class VideoReplayerApp(Application):
11     """Example of an application that uses the operators defined above.
12
13     This application has the following operators:
14
15     - VideoStreamReplayerOp
16     - HolovizOp
17
18     The VideoStreamReplayerOp reads a video file and sends the frames to the HolovizOp.
19     The HolovizOp displays the frames.
20     """
21
22     def compose(self):
23         video_dir = os.path.join(sample_data_path, "racerx")
24         if not os.path.exists(video_dir):
25             raise ValueError(f"Could not find video data: {video_dir}")
26
27         # Define the replayer and holoviz operators
28         replayer = VideoStreamReplayerOp(
29             self, name="replayer", directory=video_dir, **self.kwargs("replayer")
30         )
31         visualizer = HolovizOp(self, name="holoviz", **self.kwargs("holoviz"))
32
33         # Define the workflow
34         self.add_flow(replayer, visualizer, {("output", "receivers")})
35
36
37 def main(config_file):
38     app = VideoReplayerApp()

```

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```

39     # if the --config command line argument was provided, it will override this config_
↪ file
40     app.config(config_file)
41     app.run()
42
43
44 if __name__ == "__main__":
45     config_file = os.path.join(os.path.dirname(__file__), "video_replayer.yaml")
46     main(config_file=config_file)

```

- The built-in **VideoStreamReplayerOp** and **HolovizOp** operators are imported on line 5.
- We create an instance of **VideoStreamReplayerOp** named “replayer” with parameters initialized from the YAML configuration file using `**self.kwargs()` (lines 28-30).
- For the python script, the path to the gxf entity video data is not set in the application configuration file but determined by the code on lines 7 and 23 and is passed directly as the “directory” argument (line 29). This allows more flexibility for the user to run the script from any directory by setting the `HOLOSCAN_INPUT_PATH` directory (line 7).
- We create an instance of **HolovizOp** named “holoviz” with parameters initialized from the YAML configuration file using `**self.kwargs()` (line 31).
- The “output” port of “replayer” operator is connected to the “receivers” port of the “holoviz” operator and defines the application workflow (line 34).
- The application’s YAML configuration file contains the parameters for our operators, and is loaded on line 45. If no argument is passed to the python script, the application looks for a file with the name “video_replayer.yaml” in the same directory as the script (line 39), otherwise it treats the argument as the path to the app’s YAML configuration file (lines 41-42).

8.5.5 Running the Application

Running the application should bring up video playback of the video referenced in the YAML file.



8.6 Video Replayer (Distributed)

In this example, we extend the previous *video replayer application* into a multi-node *distributed application*. A distributed application is made up of multiple Fragments (C++/Python), each of which may run on its own node.

In the distributed case we will:

- create one fragment that loads a video file from disk using **VideoStreamReplayerOp** operator
- create a second fragment that will display the video using the **HolovizOp** operator

These two fragments will be combined into a distributed application such that the display of the video frames could occur on a separate node from the node where the data is read.

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples` in the NGC container and the debian package, alongside their executables.

8.6.1 Operators and Workflow

Here is the diagram of the operators and workflow used in this example.

Fig. 8.5: Workflow to load and display video from a file

This is the same workflow as the *single fragment video replayer*, each operator is assigned to a separate fragment and there is now a network connection between the fragments.

8.6.2 Defining and Connecting Fragments

Distributed applications define Fragments explicitly to isolate the different units of work that could be distributed to different nodes. In this example:

- We define two classes that inherit from `Fragment`:
 - **Fragment1** contains an instance of **VideoStreamReplayerOp** named “replayer”.
 - **Fragment2** contains an instance of **HolovizOp** name “holoviz”.
- We create an application, **DistributedVideoReplayerApp**. In its compose method:
 - we call **make_fragment** to initialize both fragments.
 - we then connect the “output” port of “replayer” operator in fragment1 to the “receivers” port of the “holoviz” operator in fragment2 to define the application workflow.
- The operators instantiated in the fragments can still be configured with parameters initialized from the YAML configuration ingested by the application using `from_config()` (C++) or `kwargs()` (Python).

C++

```

1  #include <holoscan/holoscan.hpp>
2  #include <holoscan/operators/holoviz/holoviz.hpp>
3  #include <holoscan/operators/video_stream_replayer/video_stream_replayer.hpp>
4
5  class Fragment1 : public holoscan::Fragment {
6  public:
7      void compose() override {
8          using namespace holoscan;
9
10         auto replayer = make_operator<ops::VideoStreamReplayerOp>("replayer", from_config(
11             ↪ "replayer"));
12         add_operator(replayer);
13     }
14 };
15
16 class Fragment2 : public holoscan::Fragment {
17 public:
18     void compose() override {
19         using namespace holoscan;
20
21         auto visualizer = make_operator<ops::HolovizOp>("holoviz", from_config("holoviz"));
22         add_operator(visualizer);
23     }
24 };
25
26 class DistributedVideoReplayerApp : public holoscan::Application {
27 public:
28     void compose() override {
29         using namespace holoscan;
30
31         auto fragment1 = make_fragment<Fragment1>("fragment1");
32         auto fragment2 = make_fragment<Fragment2>("fragment2");

```

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```

33 // Define the workflow: replayer -> holoviz
34 add_flow(fragment1, fragment2, {"replayer.output", "holoviz.receivers"});
35 }
36 };
37
38 int main(int argc, char** argv) {
39 // Get the yaml configuration file
40 auto config_path = std::filesystem::canonical(argv[0]).parent_path();
41 config_path /= std::filesystem::path("video_replayer_distributed.yaml");
42
43 auto app = holoscan::make_application<DistributedVideoReplayerApp>();
44 app->config(config_path);
45 app->run();
46
47 return 0;
48 }

```

Python

```

1 import os
2
3 from holoscan.core import Application, Fragment
4 from holoscan.operators import HolovizOp, VideoStreamReplayerOp
5
6 sample_data_path = os.environ.get("HOLOSCAN_INPUT_PATH", "../data")
7
8
9 class Fragment1(Fragment):
10     def __init__(self, app, name):
11         super().__init__(app, name)
12
13     def compose(self):
14         # Set the video source
15         video_path = self._get_input_path()
16         logging.info(
17             f"Using video from {video_path}"
18         )
19
20         # Define the replayer and holoviz operators
21         replayer = VideoStreamReplayerOp(
22             self, name="replayer", directory=video_path, **self.kwargs("replayer")
23         )
24
25         self.add_operator(replayer)
26
27     def _get_input_path(self):
28         path = os.environ.get(
29             "HOLOSCAN_INPUT_PATH", os.path.join(os.path.dirname(__file__), "data")
30         )
31         return os.path.join(path, "racerx")

```

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```

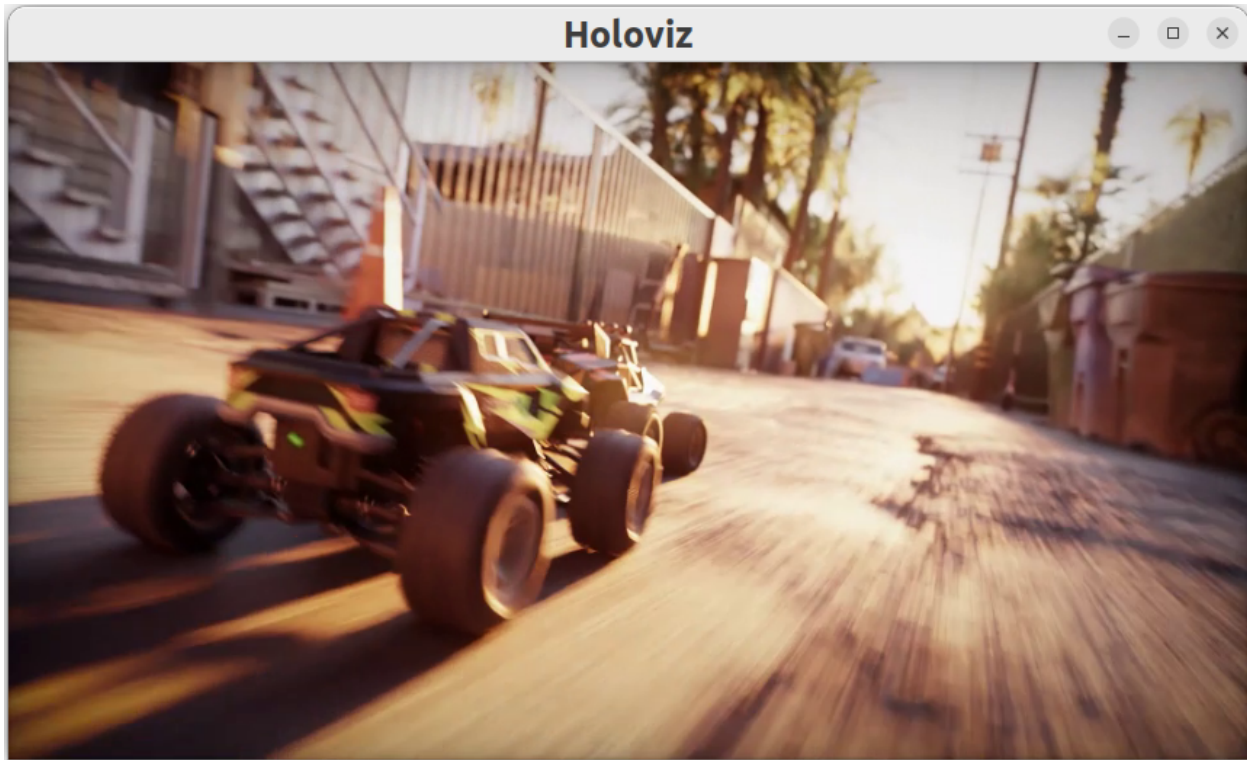
32
33
34 class Fragment2(Fragment):
35     def compose(self):
36         visualizer = HolovizOp(self, name="holoviz", **self.kwargs("holoviz"))
37
38         self.add_operator(visualizer)
39
40
41 class DistributedVideoReplayerApp(Application):
42     """Example of a distributed application that uses the fragments and operators_
43     ↪ defined above.
44
45     This application has the following fragments:
46     - Fragment1
47       - holding VideoStreamReplayerOp
48     - Fragment2
49       - holding HolovizOp
50
51     The VideoStreamReplayerOp reads a video file and sends the frames to the HolovizOp.
52     The HolovizOp displays the frames.
53     """
54     def compose(self):
55         # Define the fragments
56         fragment1 = Fragment1(self, name="fragment1")
57         fragment2 = Fragment2(self, name="fragment2")
58
59         # Define the workflow
60         self.add_flow(fragment1, fragment2, {"replayer.output", "holoviz.receivers"})
61
62
63 def main():
64     config_file_path = os.path.join(os.path.dirname(__file__), "video_replayer_
65     ↪ distributed.yaml")
66
67     logging.info(f"Reading application configuration from {config_file_path}")
68
69     app = DistributedVideoReplayerApp()
70     app.config(config_file_path)
71     app.run()
72
73 if __name__ == "__main__":
74     main()

```

This particular distributed application only has one operator per fragment, so the operators was added via **add_operator (C++/Python)**. In general, each fragment may have multiple operators and connections between operators within a fragment would be made using **add_flow()** (C++/Python) method within the fragment's **compute()** (C++/Python) method.

8.6.3 Running the Application

Running the application should bring up video playback of the video referenced in the YAML file.



Note: Instructions for running the distributed application involve calling the application from the “driver” node as well as from any worker nodes. For details, see the application run instructions in the [examples](#) directory on GitHub, or under `/opt/nvidia/holoscan/examples/video_replayer_distributed` in the NGC container and the debian package.

Tip: Refer to *UCX Network Interface Selection* when running a distributed application across multiple nodes.

8.7 Bring Your Own Model (BYOM)

The Holoscan platform is optimized for performing AI inferencing workflows. This section shows how the user can easily modify the `bring_your_own_model` example to create their own AI applications.

In this example we’ll cover:

- the usage of `FormatConverterOp`, `InferenceOp`, `SegmentationPostprocessorOp` operators to add AI inference into the workflow
- how to modify the existing code in this example to create an ultrasound segmentation application to visualize the results from a spinal scoliosis segmentation model

Note: The example source code and run instructions can be found in the [examples](#) directory on GitHub, or under

/opt/nvidia/holoscan/examples in the NGC container and the debian package, alongside their executables.

8.7.1 Operators and Workflow

Here is the diagram of the operators and workflow used in the `byom.py` example.



Fig. 8.6: The BYOM inference workflow

The example code already contains the plumbing required to create the pipeline above where the video is loaded by `VideoStreamReplayer` and passed to two branches. The first branch goes directly to `Holoviz` to display the original video. The second branch in this workflow goes through AI inferencing and can be used to generate overlays such as bounding boxes, segmentation masks, or text to add additional information.

This second branch has three operators we haven't yet encountered.

- **Format Converter:** The input video stream goes through a preprocessing stage to convert the tensors to the appropriate shape/format before being fed into the AI model. It is used here to convert the datatype of the image from `uint8` to `float32` and resized to match the model's expectations.
- **Inference:** This operator performs AI inferencing on the input video stream with the provided model. It supports inferencing of multiple input video streams and models.
- **Segmentation Postprocessor:** this postprocessing stage takes the output of inference, either with the final softmax layer (multiclass) or sigmoid (2-class), and emits a tensor with `uint8` values that contain the highest probability class index. The output of the segmentation postprocessor is then fed into the `Holoviz` visualizer to create the overlay.

8.7.2 Prerequisites

To follow along this example, you can download the ultrasound dataset with the following commands:

```

$ wget --content-disposition \
  https://api.ngc.nvidia.com/v2/resources/nvidia/clara-holoscan/holoscan_ultrasound_
  sample_data/versions/20220608/zip \
  -O holoscan_ultrasound_sample_data_20220608.zip
$ unzip holoscan_ultrasound_sample_data_20220608.zip -d <SDK_ROOT>/data/ultrasound_
  segmentation

```

You can also follow along using your own dataset by adjusting the operator parameters based on your input video and model, and converting your video and model to a format that is understood by `Holoscan`.

Input video

The video stream replayer supports reading video files that are encoded as gxf entities. These files are provided with the ultrasound dataset as the `ultrasound_256x256.gxf_entities` and `ultrasound_256x256.gxf_index` files.

Note: To use your own video data, you can use the `convert_video_to_gxf_entities.py` script from [here](#) to encode your video.

Input model

Currently, the inference operators in Holoscan are able to load [ONNX models](#), or [TensorRT](#) engine files built for the GPU architecture on which you will be running the model. TensorRT engines are automatically generated from ONNX by the operators when the applications run.

If you are converting your model from PyTorch to ONNX, chances are your input is NCHW and will need to be converted to NHWC. We provide an example [transformation script on Github](#) named `graph_surgeon.py`. You may need to modify the dimensions as needed before modifying your model.

Tip: To get a better understanding of your model, and if this step is necessary, websites such as [netron.app](#) can be used.

8.7.3 Understanding the Application Code

Before modifying the application, let's look at the existing code to get a better understanding of how it works.

Python

```
1 import os
2 from argparse import ArgumentParser
3
4 from holoscan.core import Application
5
6 from holoscan.operators import (
7     FormatConverterOp,
8     HolovizOp,
9     InferenceOp,
10    SegmentationPostprocessorOp,
11    VideoStreamReplayerOp,
12 )
13 from holoscan.resources import UnboundedAllocator
14
15
16 class BYOMApp(Application):
17     def __init__(self, data):
18         """Initialize the application
19
20         Parameters
21         -----
```

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```

22     data : Location to the data
23     """
24
25     super().__init__()
26
27     # set name
28     self.name = "BYOM App"
29
30     if data == "none":
31         data = os.environ.get("HOLOSCAN_INPUT_PATH", "../data")
32
33     self.sample_data_path = data
34
35     self.model_path = os.path.join(os.path.dirname(__file__), "../model")
36     self.model_path_map = {
37         "byom_model": os.path.join(self.model_path, "identity_model.onnx"),
38     }
39
40     self.video_dir = os.path.join(self.sample_data_path, "racerx")
41     if not os.path.exists(self.video_dir):
42         raise ValueError(f"Could not find video data: {self.video_dir}")

```

- The built-in `FormatConvertOp`, `InferenceOp`, and `SegmentationPostprocessorOp` operators are imported on lines 7, 9, and 10. These 3 operators make up the preprocessing, inference, and postprocessing stages of our AI pipeline respectively.
- The `UnboundedAllocator` resource is imported on line 13. This is used by our application's operators for memory allocation.
- The paths to the identity model are defined on lines 35–38. This model passes its input tensor to its output, and acts as a placeholder for this example.
- The directory of the video files are defined on line 40.

Next, we look at the operators and their parameters defined in the application yaml file.

Python

```

43     def compose(self):
44         host_allocator = UnboundedAllocator(self, name="host_allocator")
45
46         source = VideoStreamReplayerOp(
47             self, name="replayer", directory=self.video_dir, **self.kwargs("replayer")
48         )
49
50         preprocessor = FormatConverterOp(
51             self, name="preprocessor", pool=host_allocator, **self.kwargs("preprocessor")
52         )
53
54         inference = InferenceOp(
55             self,
56             name="inference",
57             allocator=host_allocator,

```

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```

58         model_path_map=self.model_path_map,
59         **self.kwargs("inference"),
60     )
61
62     postprocessor = SegmentationPostprocessorOp(
63         self, name="postprocessor", allocator=host_allocator, **self.kwargs(
64             ↪ "postprocessor")
65     )
66
67     viz = HolovizOp(self, name="viz", **self.kwargs("viz"))

```

- An instance of the `UnboundedAllocator` resource class is created (line 44) and used by subsequent operators for memory allocation. This allocator allocates memory dynamically on the host as needed. For applications where latency becomes an issue, there is the `BlockMemoryPool` allocator.
- The preprocessor operator (line 50) takes care of converting the input video from the source video to a format that can be used by the AI model.
- The inference operator (line 54) feeds the output from the preprocessor to the AI model to perform inference.
- The postprocessor operator (line 62) postprocesses the output from the inference operator before passing it downstream to the visualizer. Here, the segmentation postprocessor checks the probabilities output from the model to determine which class is most likely and emits this class index. This is then used by the `Holoviz` operator to create a segmentation mask overlay.

YAML

```

1  %YAML 1.2
2  replayer: # VideoStreamReplayer
3      basename: "racerx"
4      frame_rate: 0 # as specified in timestamps
5      repeat: true # default: false
6      realtime: true # default: true
7      count: 0 # default: 0 (no frame count restriction)
8
9  preprocessor: # FormatConverter
10     out_tensor_name: source_video
11     out_dtype: "float32"
12     resize_width: 512
13     resize_height: 512
14
15  inference: # Inference
16     backend: "trt"
17     pre_processor_map:
18         "byom_model": ["source_video"]
19     inference_map:
20         "byom_model": ["output"]
21
22  postprocessor: # SegmentationPostprocessor
23     in_tensor_name: output
24     # network_output_type: None
25     data_format: nchw

```

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```

26
27 viz: # Holoviz
28     width: 854
29     height: 480
30     color_lut: [
31         [0.65, 0.81, 0.89, 0.1],
32     ]

```

- The preprocessor converts the tensors to float32 values (line 11) and ensures that the image is resized to 512x512 (line 12-13).
- The `pre_processor_map` parameter (lines 17-18) maps the model name(s) to input tensor name(s). Here, “source_video” matches the output tensor name of the preprocessor (line 10). The `inference_map` parameter maps the model name(s) to the output tensor name(s). Here, “output”, matches the input tensor name of the postprocessor (line 23). For more details on InferenceOp parameters, see [Customizing the Inference Operator](#) or refer to [Inference](#).
- The `network_output_type` parameter is commented out on line 24 to remind ourselves that this second branch is currently not generating anything interesting. If not specified, this parameter defaults to “softmax” for SegmentationPostprocessorOp.
- The color lookup table defined on lines 30-32 is used here to create a segmentation mask overlay. The values of each entry in the table are RGBA values between 0.0 and 1.0. For the alpha value, 0.0 is fully transparent and 1.0 is fully opaque.

Finally, we define the application and workflow.

Python

```

67     # Define the workflow
68     self.add_flow(source, viz, {"output", "receivers"})
69     self.add_flow(source, preprocessor, {"output", "source_video"})
70     self.add_flow(preprocessor, inference, {"tensor", "receivers"})
71     self.add_flow(inference, postprocessor, {"transmitter", "in_tensor"})
72     self.add_flow(postprocessor, viz, {"out_tensor", "receivers"})
73
74
75 def main(config_file, data):
76     app = BYOMApp(data=data)
77     # if the --config command line argument was provided, it will override this config_
78     ↪ file
79     app.config(config_file)
80     app.run()
81
82 if __name__ == "__main__":
83     # Parse args
84     parser = ArgumentParser(description="BYOM demo application.")
85     parser.add_argument(
86         "-d",
87         "--data",
88         default="none",
89         help=("Set the data path"),

```

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```

90     )
91
92     args = parser.parse_args()
93     config_file = os.path.join(os.path.dirname(__file__), "byom.yaml")
94     main(config_file=config_file, data=args.data)

```

- The `add_flow()` on line 66 defines the first branch to display the original video.
- The `add_flow()` commands from line 67–70 defines the second branch to display the segmentation mask overlay.

8.7.4 Modifying the Application for Ultrasound Segmentation

To create the ultrasound segmentation application, we need to swap out the input video and model to use the ultrasound files, and adjust the parameters to ensure the input video is resized correctly to the model's expectations.

We will need to modify the python and yaml files to change our application to the ultrasound segmentation application.

Python

```

1  class BYOMApp(Application):
2      def __init__(self, data):
3          """Initialize the application
4
5          Parameters
6          -----
7          data : Location to the data
8          """
9
10         super().__init__()
11
12         # set name
13         self.name = "BYOM App"
14
15         if data == "none":
16             data = os.environ.get("HOLOSCAN_INPUT_PATH", "../data")
17
18         self.sample_data_path = data
19
20         self.model_path = os.path.join(self.sample_data_path, "ultrasound_segmentation",
21 ↪ "model")
22         self.model_path_map = {
23             "byom_model": os.path.join(self.model_path, "us_unet_256x256_nhwc.onnx"),
24         }
25
26         self.video_dir = os.path.join(self.sample_data_path, "ultrasound_segmentation",
27 ↪ "video")
28         if not os.path.exists(self.video_dir):
29             raise ValueError(f"Could not find video data: {self.video_dir}")

```

- Update `self.model_path_map` to the ultrasound segmentation model (lines 20–23).

- Update `self.video_dir` to point to the directory of the ultrasound video files (line 25).

YAML

```

1 replayer: # VideoStreamReplayer
2   basename: "ultrasound_256x256"
3   frame_rate: 0 # as specified in timestamps
4   repeat: true # default: false
5   realtime: true # default: true
6   count: 0 # default: 0 (no frame count restriction)
7
8 preprocessor: # FormatConverter
9   out_tensor_name: source_video
10  out_dtype: "float32"
11  resize_width: 256
12  resize_height: 256
13
14 inference: # Inference
15  backend: "trt"
16  pre_processor_map:
17    "byom_model": ["source_video"]
18  inference_map:
19    "byom_model": ["output"]
20
21 postprocessor: # SegmentationPostprocessor
22  in_tensor_name: output
23  network_output_type: softmax
24  data_format: nchw
25
26 viz: # Holoviz
27  width: 854
28  height: 480
29  color_lut: [
30    [0.65, 0.81, 0.89, 0.1],
31    [0.2, 0.63, 0.17, 0.7]
32  ]

```

- Update `basename` to the `basename` of the ultrasound video files (line 2).
- The AI model expects the width and height of the images to be 256x256, update the preprocessor's parameters to resize the input to 256x256 (line 11–12).
- The AI model's final output layer is a softmax, so we indicate this to the postprocessor (line 23).
- Since this model predicts between two classes, we need another entry in Holoviz's color lookup table (line 31). Note that the alpha value of the first color entry is 0.1 (line 30) so the mask for the background class may not be visible. The second entry we just added is a green color and has an alpha value of 0.7 so it will be easily visible.

The above changes are enough to update the byom example to the ultrasound segmentation application.

In general, when deploying your own AI models, you will need to consider the operators in the second branch. This example uses a pretty typical AI workflow:

- Input: This could be a video on disk, an input stream from a capture device, or other data stream.
- Preprocessing: You may need to preprocess the input stream to convert tensors into the shape and format that is expected by your AI model (e.g., converting datatype and resizing).

- Inference: Your model will need to be in onnx or trt format.
- Postprocessing: An operator that postprocesses the output of the model to a format that can be readily used by downstream operators.
- Output: The postprocessed stream can be displayed or used by other downstream operators.

The Holoscan SDK comes with a number of [built-in operators](#) that you can use to configure your own workflow. If needed, you can write your own custom operators or visit [Holohub](#) for additional implementations and ideas for operators.

8.7.5 Running the Application

After modifying the application as instructed above, running the application should bring up the ultrasound video with a segmentation mask overlay similar to the image below.

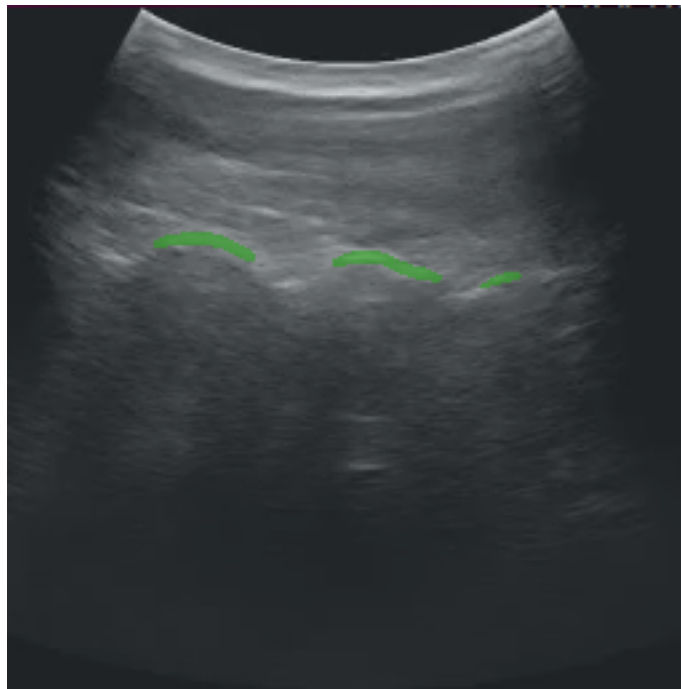


Fig. 8.7: Ultrasound Segmentation

Note: If you run the `byom.py` application without modification and are using the debian installation, you may run into the following error message:

```
[error] Error in Inference Manager ... TRT Inference: failed to build TRT engine file.
```

In this case, modifying the write permissions for the model directory should help (use with caution):

```
sudo chmod a+w /opt/nvidia/holoscan/examples/bring_your_own_model/model
```

8.7.6 Customizing the Inference Operator

The builtin `InferenceOp` operator provides the functionality of the *Inference*. This operator has a `receivers` port that can connect to any number of upstream ports to allow for multi-ai inferencing, and one `transmitter` port to send results downstream. Below is a description of some of the operator's parameters and a general guidance on how to use them.

- `backend`: if the input models are in `tensorrt engine file` format, select `trt` as the backend. If the input models are in `onnx` format select either `trt` or `onnx` as the backend.
- `allocator`: Can be passed to this operator to specify how the output tensors are allocated.
- `model_path_map`: contains dictionary keys with unique strings that refer to each model. The values are set to the path to the model files on disk. All models must be either in `onnx` or in `tensorrt engine file` format. The Holoscan Inference Module will do the `onnx` to `tensorrt` model conversion if the TensorRT engine files do not exist.
- `pre_processor_map`: this dictionary should contain the same keys as `model_path_map`, mapping to the output tensor name for each model.
- `inference_map`: this dictionary should contain the same keys as `model_path_map`, mapping to the output tensor name for each model.
- `enable_fp16`: Boolean variable indicating if half-precision should be used to speed up inferencing. The default value is `False`, and uses single-precision (32-bit fp) values.
- `input_on_cuda`: indicates whether input tensors are on device or host
- `output_on_cuda`: indicates whether output tensors are on device or host
- `transmit_on_cuda`: if `True`, it means the data transmission from the inference will be on **Device**, otherwise it means the data transmission from the inference will be on **Host**

8.7.7 Common Pitfalls Deploying New Models

Color Channel Order

It is important to know what channel order your model expects. This may be indicated by the training data, pre-training transformations performed at training, or the expected inference format used in your application.

For example, if your inference data is RGB, but your model expects BGR, you will need to add the following to your `segmentation_preprocessor` in the yaml file: `out_channel_order: [2,1,0]`.

Normalizing Your Data

Similarly, default scaling for streaming data is `[0,1]`, but dependent on how your model was trained, you may be expecting `[0,255]`.

For the above case you would add the following to your `segmentation_preprocessor` in the yaml file:

```
scale_min: 0.0 scale_max: 255.0
```

Network Output Type

Models often have different output types such as `Sigmoid`, `Softmax`, or perhaps something else, and you may need to examine the last few layers of your model to determine which applies to your case.

As in the case of our ultrasound segmentation example above, we added the following in our yaml file:

```
network_output_type: softmax
```

CREATING AN APPLICATION

In this section, we'll address:

- how to *define an Application class*
- how to *configure an Application*
- how to *define different types of workflows*
- how to *build and run your application*

Note: This section covers basics of applications running as a single fragment. For multi-fragment applications, refer to the *distributed application documentation*.

9.1 Defining an Application Class

The following code snippet shows an example Application code skeleton:

C++

- We define the `App` class that inherits from the `Application` base class.
- We create an instance of the `App` class in `main()` using the `make_application()` function.
- The `run()` method starts the application which will execute its `compose()` method where the custom workflow will be defined.

```
#include <holoscan/holoscan.hpp>

class App : public holoscan::Application {
public:
    void compose() override {
        // Define Operators and workflow
        // ...
    }
};

int main() {
    auto app = holoscan::make_application<App>();
    app->run();
}
```

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```
    return 0;
}
```

Python

- We define the `App` class that inherits from the `Application` base class.
- We create an instance of the `App` class in a `main()` function that is called from `__main__`.
- The `run()` method starts the application which will execute its `compose()` method where the custom workflow will be defined.

```
from holoscan.core import Application

class App(Application):

    def compose(self):
        # Define Operators and workflow
        # ...

def main():
    app = App()
    app.run()

if __name__ == "__main__":
    main()
```

Note: It is recommended to call `run()` from within a separate `main()` function rather than calling it directly from `__main__`. This will ensure that the `Application`'s destructor is called before the Python process exits.

Tip: This is also illustrated in the *hello_world* example.

It is also possible to instead launch the application asynchronously (i.e. non-blocking for the thread launching the application), as shown below:

C++

This can be done simply by replacing the call to `run()` with `run_async()` which returns a `std::future`. Calling `future.wait()` will block until the application has finished running.

```
int main() {
    auto app = holoscan::make_application<App>();
    future = app->run_async();
    future.wait();
    return 0;
}
```

Python

This can be done simply by replacing the call to `run()` with `run_async()` which returns a `Python concurrent.futures.Future`. Calling `future.result()` will block until the application has finished running.

```
def main():
    app = App()
    future = app.run_async()
    future.result()

if __name__ == "__main__":
    main()
```

Tip: This is also illustrated in the `ping_simple_run_async` example.

9.2 Configuring an Application

An application can be configured at different levels:

1. *providing the GXF extensions that need to be loaded* (when using *GXF operators*)
2. configuring parameters for your application, including for:
 1. *the operators* in the workflow
 2. *the scheduler* of your application
3. *configuring some runtime properties* when deploying for production

The sections below will describe how to configure each of them, starting with a native support for YAML-based configuration for convenience.

9.2.1 YAML Configuration support

Holoscan supports loading arbitrary parameters from a YAML configuration file at runtime, making it convenient to configure each item listed above, or other custom parameters you wish to add on top of the existing API. For C++ applications, it also provides the ability to change the behavior of your application without needing to recompile it.

Note: Usage of the YAML utility is optional. Configurations can be hardcoded in your program, or done using any parser of your choosing.

Here is an example YAML configuration:

```
string_param: "test"
float_param: 0.50
bool_param: true
dict_param:
  key_1: value_1
  key_2: value_2
```

Ingesting these parameters can be done using the two methods below:

C++

- The `config()` method takes the path to the YAML configuration file. If the input path is relative, it will be relative to the current working directory.
- The `from_config()` method returns an `ArgList` object for a given key in the YAML file. It holds a list of `Arg` objects, each of which holds a name (key) and a value.
 - If the `ArgList` object has only one `Arg` (when the key is pointing to a scalar item), it can be converted to the desired type using the `as()` method by passing the type as an argument.
 - The key can be a dot-separated string to access nested fields.
- The `config_keys()` method returns an unordered set of the key names accessible via `from_config()`.

```
// Pass configuration file
auto app = holoscan::make_application<App>();
app->config("path/to/app_config.yaml");

// Scalars
auto string_param = app->from_config("string_param").as<std::string>();
auto float_param = app->from_config("float_param").as<float>();
auto bool_param = app->from_config("bool_param").as<bool>();

// Dict
auto dict_param = app->from_config("dict_param");
auto dict_nested_param = app->from_config("dict_param.key_1").as<std::string>();

// Print
std::cout << "string_param: " << string_param << std::endl;
std::cout << "float_param: " << float_param << std::endl;
std::cout << "bool_param: " << bool_param << std::endl;
std::cout << "dict_param:\n" << dict_param.description() << std::endl;
std::cout << "dict_param['key1']: " << dict_nested_param << std::endl;

// // Output
// string_param: test
// float_param: 0.5
// bool_param: 1
// dict_param:
// name: arglist
// args:
//   - name: key_1
//     type: YAML::Node
//     value: value_1
//   - name: key_2
//     type: YAML::Node
//     value: value_2
// dict_param['key1']: value_1
```

Python

- The `config()` method takes the path to the YAML configuration file. If the input path is relative, it will be relative to the current working directory.
- The `kwargs()` method return a regular python dict for a given key in the YAML file.
 - *Advanced:* this method wraps the `from_config()` method similar to the C++ equivalent, which returns an `ArgList` object if the key is pointing to a map item, or an `Arg` object if the key is pointing to a scalar item. An `Arg` object can be cast to the desired type (e.g., `str(app.from_config("string_param"))`).
- The `config_keys()` method returns a set of the key names accessible via `from_config()`.

```
# Pass configuration file
app = App()
app.config("path/to/app_config.yaml")

# Scalars
string_param = app.kwargs("string_param")["string_param"]
float_param = app.kwargs("float_param")["float_param"]
bool_param = app.kwargs("bool_param")["bool_param"]

# Dict
dict_param = app.kwargs("dict_param")
dict_nested_param = dict_param["key_1"]

# Print
print(f"string_param: {string_param}")
print(f"float_param: {float_param}")
print(f"bool_param: {bool_param}")
print(f"dict_param: {dict_param}")
print(f"dict_param['key_1']: {dict_nested_param}")

# # Output:
# string_param: test
# float_param: 0.5
# bool_param: True
# dict_param: {'key_1': 'value_1', 'key_2': 'value_2'}
# dict_param['key_1']: 'value_1'
```

Warning: `from_config()` cannot be used as inputs to the built-in operators at this time, it's therefore recommended to use `kwargs()` in Python.

Tip: This is also illustrated in the [video_replayer](#) example.

Attention: With both `from_config` and `kwargs`, the returned `ArgList`/dictionary will include both the key and its associated item if that item value is a scalar. If the item is a map/dictionary itself, the input key is dropped, and the output will only hold the key/values from that item.

9.2.2 Loading GXF extensions

If you use operators that depend on GXF extensions for their implementations (known as *GXF operators*), the shared libraries (.so) of these extensions need to be dynamically loaded as plugins at runtime.

The SDK already automatically handles loading the required extensions for the *built-in operators* in both C++ and Python, as well as common extensions (listed here). To load additional extensions for your own operators, you can use one of the following approach:

YAML

```
extensions:
- libgxf_myextension1.so
- /path/to/libgxf_myextension2.so
```

C++

```
auto app = holoscan::make_application<App>();
auto exts = {"libgxf_myextension1.so", "/path/to/libgxf_myextension2.so"};
for (auto& ext : exts) {
    app->executor().extension_manager()->load_extension(ext);
}
```

PYTHON

```
from holoscan.gxf import load_extensions
from holoscan.core import Application
app = Application()
context = app.executor.context_uint64
exts = ["libgxf_myextension1.so", "/path/to/libgxf_myextension2.so"]
load_extensions(context, exts)
```

Note: To be discoverable, paths to these shared libraries need to either be absolute, relative to your working directory, installed in the lib/gxf_extensions folder of the holoscan package, or listed under the HOLOSCAN_LIB_PATH or LD_LIBRARY_PATH environment variables.

9.2.3 Configuring operators

Operators are defined in the `compose()` method of your application. They are not instantiated (with the `initialize` method) until an application's `run()` method is called.

Operators have three type of fields which can be configured: parameters, conditions, and resources.

Configuring operator parameters

Operators could have parameters defined in their `setup` method to better control their behavior (see details when *creating your own operators*). The snippet below would be the implementation of this method for a minimal operator named `MyOp`, that takes a string and a boolean as parameters; we'll ignore any extra details for the sake of this example:

C++

```
void setup(OperatorSpec& spec) override {
    spec.param(string_param_, "string_param");
    spec.param(bool_param_, "bool_param");
}
```

PYTHON

```
def setup(self, spec: OperatorSpec):
    spec.param("string_param")
    spec.param("bool_param")
    # Optional in python. Could define `self.<param_name>` instead in `def __init__`
```

Tip: Given an instance of an operator class, you can print a human-readable description of its specification to inspect the parameter fields that can be configured on that operator class:

C++

```
std::cout << operator_object->spec()->description() << std::endl;
```

PYTHON

```
print(operator_object.spec)
```

Given this YAML configuration:

```
myop_param:
  string_param: "test"
  bool_param: true

bool_param: false # we'll use this later
```

We can configure an instance of the `MyOp` operator in the application's `compose` method like this:

C++

```
void compose() override {
    // Using YAML
    auto my_op1 = make_operator<MyOp>("my_op1", from_config("myop_param"));

    // Same as above
    auto my_op2 = make_operator<MyOp>("my_op2",
        Arg("string_param", std::string("test")), // can use Arg(key, value)...
        Arg("bool_param") = true                  // ... or Arg(key) = value
    );
}
```

PYTHON

```
def compose(self):
    # Using YAML
    my_op1 = MyOp(self, name="my_op1", **self.kwargs("myop_param"))

    # Same as above
    my_op2 = MyOp(self,
        name="my_op2",
        string_param="test",
        bool_param=True,
    )
```

Tip: This is also illustrated in the [ping_custom_op](#) example.

If multiple ArgList are provided with duplicate keys, the latest one overrides them:

C++

```
void compose() override {
    // Using YAML
    auto my_op1 = make_operator<MyOp>("my_op1",
        from_config("myop_param"),
        from_config("bool_param")
    );

    // Same as above
    auto my_op2 = make_operator<MyOp>("my_op2",
        Arg("string_param", "test"),
        Arg("bool_param") = true,
        Arg("bool_param") = false
    );

    // -> my_op `bool_param` will be set to `false`
}
```

PYTHON

```
def compose(self):
    # Using YAML
    my_op1 = MyOp(self, name="my_op1",
                  from_config("myop_param"),
                  from_config("bool_param"),
                  )

    # Note: We're using from_config above since we can't merge automatically with kwargs
    # as this would create duplicated keys. However, we recommend using kwargs in python
    # to avoid limitations with wrapped operators, so the code below is preferred.

    # Same as above
    params = self.kwargs("myop_param").update(self.kwargs("bool_param"))
    my_op2 = MyOp(self, name="my_op2", params)

    # -> my_op `bool_param` will be set to `False`
```

Configuring operator conditions

By default, operators with no input ports will continuously run, while operators with input ports will run as long as they receive inputs (as they're configured with the [MessageAvailableCondition](#)).

To change that behavior, one or more other [conditions](#) classes can be passed to the constructor of an operator to define when it should execute.

For example, we set three conditions on this operator `my_op`:

C++

```
void compose() override {
    // Limit to 10 iterations
    auto c1 = make_condition<CountCondition>("my_count_condition", 10);

    // Wait at least 200 milliseconds between each execution
    auto c2 = make_condition<PeriodicCondition>("my_periodic_condition", "200ms");

    // Stop when the condition calls `disable_tick()`
    auto c3 = make_condition<BooleanCondition>("my_bool_condition");

    // Pass directly to the operator constructor
    auto my_op = make_operator<MyOp>("my_op", c1, c2, c3);
}
```

PYTHON

```
def compose(self):
    # Limit to 10 iterations
    c1 = CountCondition(self, 10, name="my_count_condition")

    # Wait at least 200 milliseconds between each execution
    c2 = PeriodicCondition(self, timedelta(milliseconds=200), name="my_periodic_condition")

    # Stop when the condition calls `disable_tick()`
    c3 = BooleanCondition(self, name="my_bool_condition")

    # Pass directly to the operator constructor
    my_op = MyOp(self, c1, c2, c3, name="my_op")

    # Built-in operators that wrap an underlying C++ operator class currently do not accept
    # Condition classes as positional arguments from the Python API. Instead, one should
    ↪ add the
    # condition via the add_arg method of the class
    postproc_op = SegmentationPostprocessorOp(self, allocator=UnboundedAllocator(self),
    ↪ name="post")
    postproc_op.add_arg(CountCondition(self, count=10))
```

Tip: This is also illustrated in the `conditions` examples.

Note: You'll need to specify a unique name for the conditions if there are multiple conditions applied to an operator.

Note: Python operators that wrap an underlying C++ operator currently do not accept conditions as positional arguments. Instead one needs to call the `add_arg()` method after the object has been constructed to add the condition.

Configuring operator resources

Some *resources* can be passed to the operator's constructor, typically an *allocator* passed as a regular parameter.

For example:

C++

```
void compose() override {
    // Allocating memory pool of specific size on the GPU
    // ex: width * height * channels * channel size in bytes
    auto block_size = 640 * 480 * 4 * 2;
    auto p1 = make_resource<BlockMemoryPool>("my_pool1", 1, size, 1);

    // Provide unbounded memory pool
    auto p2 = make_condition<UnboundedAllocator>("my_pool2");
```

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```
// Pass to operator as parameters (name defined in operator setup)
auto my_op = make_operator<MyOp>("my_op",
                                Arg("pool1", p1),
                                Arg("pool2", p2));
}
```

PYTHON

```
def compose(self):
    # Allocating memory pool of specific size on the GPU
    # ex: width * height * channels * channel size in bytes
    block_size = 640 * 480 * 4 * 2;
    p1 = BlockMemoryPool(self, name="my_pool1", storage_type=1, block_size=block_size, num_
    ↪ blocks=1)

    # Provide unbounded memory pool
    p2 = UnboundedAllocator(self, name="my_pool2")

    # Pass to operator as parameters (name defined in operator setup)
    auto my_op = MyOp(self, name="my_op", pool1=p1, pool2=p2)
```

Note: Python operators that wrap an underlying C++ operator currently do not accept resources as positional arguments. Instead one needs to call the `add_arg()` method after the object has been constructed to add the resource.

9.2.4 Configuring the scheduler

The *scheduler* controls how the application schedules the execution of the operators that make up its *workflow*.

The default scheduler is a single-threaded *GreedyScheduler*. An application can be configured to use a different scheduler `Scheduler` (C++/Python) or change the parameters from the default scheduler, using the `scheduler()` function (C++/Python).

For example, if an application needs to run multiple operators in parallel, a *MultiThreadScheduler* can instead be used.

The code snippet belows shows how to set and configure a non-default scheduler:

C++

- We create an instance of a `holoscan::Scheduler` derived class by using the `make_scheduler()` function. Like operators, parameters can come from explicit `Args` or `ArgList`, or from a YAML configuration.
- The `scheduler()` method assigns the scheduler to be used by the application.

```
auto app = holoscan::make_application<App>();
auto scheduler = app->make_scheduler<holoscan::MultiThreadScheduler>(
    "myscheduler",
    Arg("worker_thread_number", 4),
    Arg("stop_on_deadlock", true)
```

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```
);  
app->scheduler(scheduler);  
app->run();
```

Python

- We create an instance of a Scheduler class in the `schedulers` module. Like operators, parameters can come from an explicit Arg or ArgList, or from a YAML configuration.
- The `scheduler()` method assigns the scheduler to be used by the application.

```
app = App()  
scheduler = holoscan.schedulers.MultiThreadScheduler(  
    app,  
    name="myscheduler",  
    worker_thread_number=4,  
    stop_on_deadlock=True,  
)  
app.scheduler(scheduler)  
app.run()
```

Tip: This is also illustrated in the [multithread](#) example.

9.2.5 Configuring runtime properties

As described *below*, applications can run simply by executing the C++ or Python application manually on a given node, or by *packaging it* in a *HAP container*. With the latter, runtime properties need to be configured: refer to the *App Runner Configuration* for details.

9.3 Application Workflows

Note: Operators are initialized according to the [topological order](#) of its fragment-graph. When an application runs, the operators are executed in the same topological order. Topological ordering of the graph ensures that all the data dependencies of an operator are satisfied before its instantiation and execution. Currently, we do not support specifying a different and explicit instantiation and execution order of the operators.

9.3.1 One-operator Workflow

The simplest form of a workflow would be a single operator.

Fig. 9.1: A one-operator workflow

The graph above shows an **Operator** (C++/Python) (named `MyOp`) that has neither inputs nor output ports.

- Such an operator may accept input data from the outside (e.g., from a file) and produce output data (e.g., to a file) so that it acts as both the source and the sink operator.
- Arguments to the operator (e.g., input/output file paths) can be passed as parameters as described in the [section above](#).

We can add an operator to the workflow by calling `add_operator` (C++/Python) method in the `compose()` method.

The following code shows how to define a one-operator workflow in `compose()` method of the `App` class (assuming that the operator class `MyOp` is declared/defined in the same file).

C++

```

1 class App : public holoscan::Application {
2 public:
3     void compose() override {
4         // Define Operators
5         auto my_op = make_operator<MyOp>("my_op");
6
7         // Define the workflow
8         add_operator(my_op);
9     }
10 };

```

PYTHON

```

1 class App(Application):
2
3     def compose(self):
4         # Define Operators
5         my_op = MyOp(self, name="my_op")
6
7         # Define the workflow
8         self.add_operator(my_op)

```

9.3.2 Linear Workflow

Here is an example workflow where the operators are connected linearly:

Fig. 9.2: A linear workflow

In this example, **SourceOp** produces a message and passes it to **ProcessOp**. **ProcessOp** produces another message and passes it to **SinkOp**.

We can connect two operators by calling the `add_flow()` method (C++/Python) in the `compose()` method.

The `add_flow()` method (C++/Python) takes the source operator, the destination operator, and the optional port name pairs. The port name pair is used to connect the output port of the source operator to the input port of the destination operator. The first element of the pair is the output port name of the upstream operator and the second element is the input port name of the downstream operator. An empty port name ("") can be used for specifying a port name if the operator has only one input/output port. If there is only one output port in the upstream operator and only one input port in the downstream operator, the port pairs can be omitted.

The following code shows how to define a linear workflow in the `compose()` method of the `App` class (assuming that the operator classes `SourceOp`, `ProcessOp`, and `SinkOp` are declared/defined in the same file).

CPP

```

1 class App : public holoscan::Application {
2     public:
3         void compose() override {
4             // Define Operators
5             auto source = make_operator<SourceOp>("source");
6             auto process = make_operator<ProcessOp>("process");
7             auto sink = make_operator<SinkOp>("sink");
8
9             // Define the workflow
10            add_flow(source, process); // same as `add_flow(source, process, {"output", "input"})`
11            add_flow(process, sink);   // same as `add_flow(process, sink, {"", ""})`
12        }
13    };

```

PYTHON

```

1 class App(Application):
2
3     def compose(self):
4         # Define Operators
5         source = SourceOp(self, name="source")
6         process = ProcessOp(self, name="process")
7         sink = SinkOp(self, name="sink")
8
9         # Define the workflow
10        self.add_flow(source, process) # same as `self.add_flow(source, process, {(
11        self.add_flow(process, sink)   # same as `self.add_flow(process, sink, {(

```

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9.3.3 Complex Workflow (Multiple Inputs and Outputs)

You can design a complex workflow like below where some operators have multi-inputs and/or multi-outputs:

Fig. 9.3: A complex workflow (multiple inputs and outputs)

CPP

```

1  class App : public holoscan::Application {
2  public:
3      void compose() override {
4          // Define Operators
5          auto reader1 = make_operator<Reader1>("reader1");
6          auto reader2 = make_operator<Reader2>("reader2");
7          auto processor1 = make_operator<Processor1>("processor1");
8          auto processor2 = make_operator<Processor2>("processor2");
9          auto processor3 = make_operator<Processor3>("processor3");
10         auto writer = make_operator<Writer>("writer");
11         auto notifier = make_operator<Notifier>("notifier");
12
13         // Define the workflow
14         add_flow(reader1, processor1, {"image", "image1"}, {"image", "image2"}, {"metadata",
15         ↪ "metadata"}));
16         add_flow(reader1, processor1, {"image", "image2"}));
17         add_flow(reader2, processor2, {"roi", "roi"}));
18         add_flow(processor1, processor2, {"image", "image"}));
19         add_flow(processor1, writer, {"image", "image"}));
20         add_flow(processor2, notifier);
21         add_flow(processor2, processor3);
22         add_flow(processor3, writer, {"seg_image", "seg_image"}));
23     }
24 };

```

PYTHON

```

1  class App(Application):
2
3      def compose(self):
4          # Define Operators
5          reader1 = Reader1Op(self, name="reader1")
6          reader2 = Reader2Op(self, name="reader2")
7          processor1 = Processor1Op(self, name="processor1")
8          processor2 = Processor2Op(self, name="processor2")
9          processor3 = Processor3Op(self, name="processor3")
10         notifier = NotifierOp(self, name="notifier")
11         writer = WriterOp(self, name="writer")

```

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```

12
13     # Define the workflow
14     self.add_flow(reader1, processor1, {"image", "image1"}, ("image", "image2"), (
15 ↪ "metadata", "metadata"))
16     self.add_flow(reader2, processor2, {"roi", "roi"})
17     self.add_flow(processor1, processor2, {"image", "image"})
18     self.add_flow(processor1, writer, {"image", "image"})
19     self.add_flow(processor2, notifier)
20     self.add_flow(processor2, processor3)
    self.add_flow(processor3, writer, {"seg_image", "seg_image"})

```

If there is a cycle in the graph with no implicit root operator, the root operator is either the first operator in the first call to `add_flow` method (C++/Python), or the operator in the first call to `add_operator` method (C++/Python).

C++

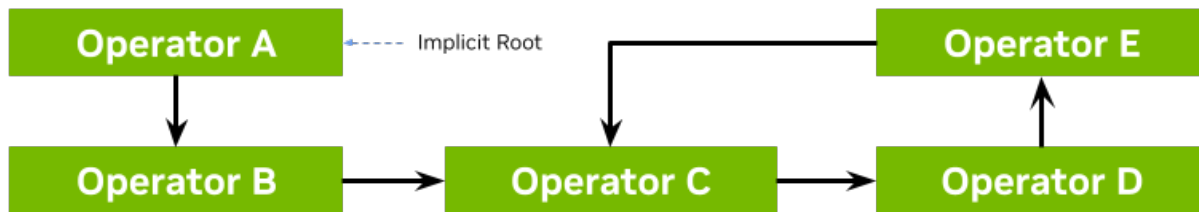
```

auto op1 = make_operator<...>("op1");
auto op2 = make_operator<...>("op2");
auto op3 = make_operator<...>("op3");

add_flow(op1, op2);
add_flow(op2, op3);
add_flow(op3, op1);
// There is no implicit root operator
// op1 is the root operator because op1 is the first operator in the first call to add_
↪ flow

```

If there is a cycle in the graph with an implicit root operator which has no input port, then the initialization and execution orders of the operators are still topologically sorted as far as possible until the cycle needs to be explicitly broken. An example is given below:



Order of operators: Operator A, Operator B, {a combination of Operator C, D and E}

9.4 Building and running your Application

C++

You can build your C++ application using CMake, by calling `find_package(holoscan)` in your `CMakeLists.txt` to load the SDK libraries. Your executable will need to link against:

- `holoscan::core`
- any operator defined outside your `main.cpp` which you wish to use in your app workflow, such as:

- SDK *built-in operators* under the `holoscan::ops` namespace
- operators created separately in your project with `add_library`
- operators imported externally using with `find_library` or `find_package`

Listing 9.1: <src_dir>/CMakeLists.txt

```
# Your CMake project
cmake_minimum_required(VERSION 3.20)
project(my_project CXX)

# Finds the holoscan SDK
find_package(holoscan REQUIRED CONFIG PATHS "/opt/nvidia/holoscan")

# Create an executable for your application
add_executable(my_app main.cpp)

# Link your application against holoscan::core and any existing operators you'd like to use
target_link_libraries(my_app
    PRIVATE
        holoscan::core
        holoscan::ops::<some_built_in_operator_target>
        <some_other_operator_target>
        <...>
)
```

Tip: This is also illustrated in all the examples:

- in `CMakeLists.txt` for the SDK installation directory - `/opt/nvidia/holoscan/examples`
- in `CMakeLists.min.txt` for the SDK `source` directory

Once your `CMakeLists.txt` is ready in <src_dir>, you can build in <build_dir> with the command line below. You can optionally pass `Holoscan_ROOT` if the SDK installation you'd like to use differs from the `PATHS` given to `find_package(holoscan)` above.

```
# Configure
cmake -S <src_dir> -B <build_dir> -D Holoscan_ROOT="/opt/nvidia/holoscan"
# Build
cmake --build <build_dir> -j
```

You can then run your application by running `<build_dir>/my_app`.

Python

Python applications do not require building. Simply ensure that:

- The holoscan python module is installed in your `dist-packages` or is listed under the `PYTHONPATH` env variable so you can import `holoscan.core` and any built-in operator you might need in `holoscan.operators`.
- Any external operators are available in modules in your `dist-packages` or contained in `PYTHONPATH`.

Note: While python applications do not need to be built, they might depend on operators that wrap C++ operators. All python operators built-in in the SDK already ship with the python bindings pre-built. Follow [this section](#) if you are wrapping C++ operators yourself to use in your python application.

You can then run your application by running `python3 my_app.py`.

Note: Given a CMake project, a pre-built executable, or a python application, you can also use the [Holoscan CLI](#) to *package and run your Holoscan application* in a OCI-compliant container image.

CREATING A DISTRIBUTED APPLICATION

Distributed applications refer to those where the workflow is divided into multiple fragments that may be run on separate nodes. For example, data might be collected via a sensor at the edge, sent to a separate workstation for processing, and then the processed data could be sent back to the edge node for visualization. Each node would run a single fragment consisting of a computation graph built up of operators. Thus one fragment is the equivalent of a non-distributed application. In the distributed context, the Application initializes the different fragments and then defines the connections between them to build up the full distributed application workflow.

In this section we'll describe:

- how to *define a distributed Application*
- how to *build and run a distributed application*

10.1 Defining a Distributed Application Class

Tip: Defining distributed applications is also illustrated in the [video_replayer_distributed](#) and [ping_distributed](#) examples. The [ping_distributed](#) examples also illustrate how to update C++ or Python applications to parse user-defined arguments in a way that works without disrupting support for distributed application command line arguments (e.g. `--driver`, `--worker`).

Defining a single Fragment (C++/Python) involves adding operators using `make_operator()` (C++) or the operator constructor (Python), and defining the connections between them using the `add_flow()` method (C++/Python) in the `compose()` method. Thus, defining a Fragment is just like defining a non-distributed Application except that the class should inherit from `Fragment` instead of `Application`.

The application will then be defined by initializing fragments within the application's `compose()` method. The `add_flow()` method (C++/Python) can be used to define the connections across fragments.

C++

- We define the `Fragment1` and `Fragment2` classes that inherit from the `Fragment` base class.
- We define the `App` class that inherits from the `Application` base class.
- The `App` class initializes any fragments used and defines the connections between them. Here we have used dummy port and operator names in the example `add_flow` call connecting the fragments since no specific operators are shown in this example.
- We create an instance of the `App` class in `main()` using the `make_application()` function.

- The `run()` method starts the application which will execute its `compose()` method where the custom workflow will be defined.

```
#include <holoscan/holoscan.hpp>

class Fragment1 : public holoscan::Fragment {
public:
    void compose() override {
        // Define Operators and workflow for Fragment1
        // ...
    }
};

class Fragment2 : public holoscan::Fragment {
public:
    void compose() override {
        // Define Operators and workflow for Fragment2
        // ...
    }
};

class App : public holoscan::Application {
public:
    void compose() override {
        using namespace holoscan;

        auto fragment1 = make_fragment<Fragment1>("fragment1");
        auto fragment2 = make_fragment<Fragment2>("fragment2");

        // Define the workflow: replayer -> holoviz
        add_flow(fragment1, fragment2, {{"fragment1_operator_name.output_port_name",
                                         "fragment2_operator_name.input_port_name"}});
    }
};

int main() {
    auto app = holoscan::make_application<App>();
    app->run();
    return 0;
}
```

Python

- We define the `Fragment1` and `Fragment2` classes that inherit from the `Fragment` base class.
- We define the `App` class that inherits from the `Application` base class.
- The `App` class initializes any fragments used and defines the connections between them. Here we have used dummy port and operator names in the example `add_flow` call connecting the fragments since no specific operators are shown in this example.
- We create an instance of the `App` class in `__main__`.

- The `run()` method starts the application which will execute its `compose()` method where the custom workflow will be defined.

```

from holoscan.core import Application, Fragment

class Fragment1(Fragment):

    def compose(self):
        # Define Operators and workflow
        # ...

class Fragment2(Fragment):

    def compose(self):
        # Define Operators and workflow
        # ...

class App(Application):

    def compose(self):
        fragment1 = Fragment1(self, name="fragment1")
        fragment2 = Fragment2(self, name="fragment2")

        self.add_flow(fragment1, fragment2, {("fragment1_operator_name.output_port_name",
                                              "fragment2_operator_name.input_port_name")})
    ↪)

def main():
    app = App()
    app.run()

if __name__ == "__main__":
    main()

```

10.1.1 Serialization of Custom Data Types for Distributed Applications

Transmission of data between fragments of a multi-fragment application is done via the [Unified Communications X \(UCX\)](#) library. In order to transmit data, it must be serialized into a binary form suitable for transmission over a network. For Tensors ([C++/Python](#)), strings and various scalar and vector numeric types, serialization is already built in. For more details on concrete examples of how to extend the data serialization support to additional user-defined classes, see the separate page on [serialization](#).

10.2 Building and running a Distributed Application

C++

Building a distributed application works in the same way as for a non-distributed one. See *Building and running your Application*

Python

Python applications do not require building. See *Building and running your Application*.

Running an application in a distributed setting requires launching the application binary on all nodes involved in the distributed application. A single node must be selected to act as the application driver. This is achieved by using the `--driver` command-line option. Worker nodes are initiated by launching the application with the `--worker` command-line option. It's possible for the driver node to also serve as a worker if both options are specified.

The address of the driver node must be specified for each process (both the driver and worker(s)) to identify the appropriate network interface for communication. This can be done via the `--address` command-line option, which takes a value in the form of [`<IPv4/IPv6 address or hostname>`][:`<port>`] (e.g., `--address 192.168.50.68:10000`):

- The driver's IP (or hostname) **MUST** be set for each process (driver and worker(s)) when running distributed applications on multiple nodes (default: `0.0.0.0`). It can be set without the port (e.g., `--address 192.168.50.68`).
- In a single-node application, the driver's IP (or hostname) can be omitted, allowing any network interface (`0.0.0.0`) to be selected by the `UCX` library.
- The port is always optional (default: `8765`). It can be set without the IP (e.g., `--address :10000`).

The worker node's address can be defined using the `--worker-address` command-line option ([`<IPv4/IPv6 address or hostname>`][:`<port>`])). If it's not specified, the application worker will default to the host address (`0.0.0.0`) with a randomly chosen port number between `10000` and `32767` that is not currently in use. This argument automatically sets the `HOLOSCAN_UCX_SOURCE_ADDRESS` environment variable if the worker address is a local IP address. Refer to *Environment Variables for Distributed Applications* for details.

The `--fragments` command-line option is used in combination with `--worker` to specify a comma-separated list of fragment names to be run by a worker. If not specified, the application driver will assign a single fragment to the worker. To indicate that a worker should run all fragments, you can specify `--fragments all`.

The `--config` command-line option can be used to designate a path to a configuration file to be used by the application.

Below is an example launching a three fragment application named `my_app` on two separate nodes:

- The application driver is launched at `192.168.50.68:10000` on the first node (A), with a worker running two fragments, "fragment1" and "fragment3".
- On a separate node (B), the application launches a worker for "fragment2", which will connect to the driver at the address above.

C++

```
# Node A
my_app --driver --worker --address 192.168.50.68:10000 --fragments fragment1,fragment3
# Node B
my_app --worker --address 192.168.50.68:10000 --fragments fragment2
```

Python

```
# Node A
python3 my_app.py --driver --worker --address 192.168.50.68:10000 --fragments fragment1,
↪ fragment3
# Node B
python3 my_app.py --worker --address 192.168.50.68:10000 --fragments fragment2
```

Note:

UCX Network Interface Selection

UCX is used in the Holoscan SDK for communication across fragments in distributed applications. It is designed to select the best network device based on performance characteristics (bandwidth, latency, NUMA locality, etc). In some scenarios (under investigation) UCX cannot find the correct network interface to use, and the application fails to run. In this case, you can manually specify the network interface to use by setting the UCX_NET_DEVICES environment variable.

For example, if the user wants to use the network interface `eth0`, you can set the environment variable as follows, before running the application:

```
export UCX_NET_DEVICES=eth0
```

Or, if you are running a packaged distributed application with the *Holoscan CLI*, use the `--nic eth0` option to manually specify the network interface to use.

The available network interface names can be found by running the following command:

```
ucx_info -d | grep Device: | awk '{print $3}' | sort | uniq
# or
ip -o -4 addr show | awk '{print $2, $4}' # to show interface name and IP
```

Warning:

Known limitations

The following are known limitations of the distributed application support in the SDK, which will be addressed in future updates:

1. A connection error message is displayed even when the distributed application is running correctly.

The message `Connection dropped with status -25 (Connection reset by remote peer)` appears in the console even when the application is functioning properly. This is a known issue and will be addressed in future updates, ensuring that this message will only be displayed in the event of an actual connection error.

2. GPU tensors can only currently be sent/received by UCX from a single device on a given node.

By default, device ID 0 is used by the UCX extensions to send/receive data between fragments. To override this default, the user can set environment variable `HOLOSCAN_UCX_DEVICE_ID`.

3. “Address already in use” errors in distributed applications due to the health check service.

In scenarios where distributed applications have both the driver and workers running on the same host, either within a Docker container or directly on the host, there’s a possibility of encountering “Address already in use” errors. A potential solution is to assign a different port number to the `HOLOSCAN_HEALTH_CHECK_PORT` environment variable (default: 8777), for example, by using `export HOLOSCAN_HEALTH_CHECK_PORT=8780`.

Note:**GXF UCX Extension**

Holoscan’s distributed application feature makes use of the [GXF UCX Extension](#). Its documentation may provide useful additional context into how data is transmitted between fragments.

Tip: Given a CMake project, a pre-built executable, or a python application, you can also use the [Holoscan CLI](#) to *package and run your Holoscan application* in a OCI-compliant container image.

10.2.1 Environment Variables for Distributed Applications

Holoscan SDK environment variables.

You can set environment variables to modify the default actions of services and the scheduler when executing a distributed application.

- **HOLOSCAN_ENABLE_HEALTH_CHECK** : determines if the health check service should be active, even without specifying `--driver` or `--worker` in the CLI. By default, initiating the AppDriver (`--driver`) or AppWorker (`--worker`) service automatically triggers the [GRPC Health Checking Service](#) so `grpc-health-probe` can monitor liveness/readiness. Interprets values like “true”, “1”, or “on” (case-insensitive) as true (to enable the health check). It defaults to false if left unspecified.
- **HOLOSCAN_HEALTH_CHECK_PORT** : designates the port number on which the Health Checking Service is launched. It must be an integer value representing a valid port number. If unspecified, it defaults to 8777.
- **HOLOSCAN_DISTRIBUTED_APP_SCHEDULER** : controls which scheduler is used for distributed applications. It can be set to either `greedy` or `multithread`. If unspecified, the default scheduler is `multithread`.

- **HOLOSCAN_STOP_ON_DEADLOCK** : can be used in combination with **HOLOSCAN_DISTRIBUTED_APP_SCHEDULER** to control whether or not the application will automatically stop on deadlock. Values of “True”, “1” or “ON” will be interpreted as true (enable stop on deadlock). It is true if unspecified. This environment variable is only used when **HOLOSCAN_DISTRIBUTED_APP_SCHEDULER** is explicitly set.
- **HOLOSCAN_STOP_ON_DEADLOCK_TIMEOUT** : controls the delay (in ms) without activity required before an application is considered to be in deadlock. It must be an integer value (units are ms).
- **HOLOSCAN_MAX_DURATION_MS** : sets the application to automatically terminate after the requested maximum duration (in ms) has elapsed. It must be an integer value (units are ms). This environment variable is only used when **HOLOSCAN_DISTRIBUTED_APP_SCHEDULER** is explicitly set.
- **HOLOSCAN_CHECK_RECESSION_PERIOD_MS** : controls how long (in ms) the scheduler waits before re-checking the status of operators in an application. It must be a floating point value (units are ms). This environment variable is only used when **HOLOSCAN_DISTRIBUTED_APP_SCHEDULER** is explicitly set.
- **HOLOSCAN_UCX_SERIALIZATION_BUFFER_SIZE** : can be used to override the default 7 kB serialization buffer size. This should typically not be needed as tensor types store only a small header in this buffer to avoid explicitly making a copy of their data. However, other data types do get directly copied to the serialization buffer and in some cases it may be necessary to increase it.
- **HOLOSCAN_UCX_DEVICE_ID** : The GPU ID of the device that will be used by UCX transmitter/receivers in distributed applications. If unspecified, it defaults to 0. A list of discrete GPUs available in a system can be obtained via `nvidia-smi -L`. GPU data sent between fragments of a distributed application must be on this device.
- **HOLOSCAN_UCX_PORTS** : This defines the preferred port numbers for the SDK when specific ports for UCX communication need to be predetermined, such as in a Kubernetes environment. If the distributed application requires three ports (UCX receivers) and the environment variable is unset, the SDK chooses three unused ports sequentially from the range 10000~32767. Specifying a value, for example, **HOLOSCAN_UCX_PORTS=10000**, results in the selection of ports 10000, 10001, and 10002. Multiple starting values can be comma-separated. The system increments from the last provided port if more ports are needed. Any unused specified ports are ignored.
- **HOLOSCAN_UCX_SOURCE_ADDRESS** : This environment variable specifies the local IP address (source) for the UCX connection. This variable is especially beneficial when a node has multiple network interfaces, enabling the user to determine which one should be utilized for establishing a UCX client (UCXTransmitter). If it is not explicitly specified, the default address is set to `0.0.0.0`, representing any available interface.

UCX-specific environment variables

Transmission of data between fragments of a multi-fragment application is done via the [Unified Communications X \(UCX\)](#) library, a point-to-point communication framework designed to utilize the best available hardware resources (shared memory, TCP, GPUDirect RDMA, etc). UCX has many parameters that can be controlled via environment variables. A few that are particularly relevant to Holoscan SDK distributed applications are listed below:

- The **UCX_TLS** environment variable can be used to control which transport layers are enabled. By default, **UCX_TLS=all** and UCX will attempt to choose the optimal transport layer automatically.
- The **UCX_NET_DEVICES** environment variable is by default set to **all** meaning that UCX may choose to use any available network interface controller (NIC). In some cases it may be necessary to restrict UCX to a specific device or set of devices, which can be done by setting **UCX_NET_DEVICES** to a comma separated list of the device names (i.e. as obtained by linux command `ifconfig -a` or `ip link show`).
- Setting **UCX_TCP_CM_REUSEADDR=y** is recommended to enable ports to be reused without having to wait the full socket **TIME_WAIT** period after a socket is closed.

- The `UCX_LOG_LEVEL` environment variable can be used to control the logging level of UCX. The default is setting is `WARN`, but changing to a lower level such as `INFO` will provide more verbose output on which transports and devices are being used.
- By default, Holoscan SDK will automatically set `UCX_PROTO_ENABLE=y` upon application launch to enable the newer “v2” UCX protocols. If for some reason, the older v1 protocols are needed, one can set `UCX_PROTO_ENABLE=n` in the environment to override this setting. When the v2 protocols are enabled, one can optionally set `UCX_PROTO_INFO=y` to enable detailed logging of what protocols are being used at runtime.
- By default, Holoscan SDK will automatically set `UCX_MEMTYPE_CACHE=n` upon application launch to disable the UCX memory type cache (See [UCX documentation](#) for more information. It can cause about [0.2 microseconds of pointer type checking overhead with the `cudaPointerGetAttributes\(\)` CUDA API](#)). If for some reason, the memory type cache is needed, one can set `UCX_MEMTYPE_CACHE=y` in the environment to override this setting.
- By default, the Holoscan SDK will automatically set `UCX_CM_USE_ALL_DEVICES=n` at application startup to disable consideration of all devices for data transfer. If for some reason the opposite behavior is desired, one can set `UCX_CM_USE_ALL_DEVICES=y` in the environment to override this setting. Setting `UCX_CM_USE_ALL_DEVICES=n` can be used to workaround an issue where UCX sometimes defaults to a device that might not be the most suitable for data transfer based on the host’s available devices. On a host with address 10.111.66.60, UCX, for instance, might opt for the `br-80572179a31d` (192.168.49.1) device due to its superior bandwidth as compared to `eno2` (10.111.66.60). With `UCX_CM_USE_ALL_DEVICES=n`, UCX will ensure consistency by using the same device for data transfer that was initially used to establish the connection. This ensures more predictable behavior and can avoid potential issues stemming from device mismatches during the data transfer process.
- Setting `UCX_TCP_PORT_RANGE=<start>-<end>` can be used to define a specific range of ports that UCX should utilize for data transfer. This is particularly useful in environments where ports need to be predetermined, such as in a Kubernetes setup. In such contexts, Pods often have ports that need to be exposed, and these ports must be specified ahead of time. Moreover, in scenarios where firewall configurations are stringent and only allow specified ports, having a predetermined range ensures that the UCX communication does not get blocked. This complements the `HOLOSCAN_UCX_SOURCE_ADDRESS`, which specifies the local IP address for the UCX connection, by giving further control over which ports on that specified address should be used. By setting a port range, users can ensure that UCX operates within the boundaries of the network and security policies of their infrastructure.

Tip: A list of all available UCX environment variables and a brief description of each can be obtained by running `ucx_info -f` from the Holoscan SDK container. Holoscan SDK uses UCX’s active message (AM) protocols, so environment variables related to other protocols such as `tag-mat`

10.3 Serialization

Distributed applications must serialize any objects that are to be sent between the fragments of a multi-fragment application. Serialization involves binary serialization to a buffer that will be sent from one fragment to another via the Unified Communications X (UCX) library. For tensor types (e.g. `holoscan::Tensor`), no actual copy is made, but instead transmission is done directly from the original tensor’s data and only a small amount of header information is copied to the serialization buffer.

A table of the types that have codecs pre-registered so that they can be serialized between fragments using Holoscan SDK is given below.

Type Class	Specific Types
integers	int8_t, int16_t, int32_t, int64_t, uint8_t, uint16_t, uint32_t, uint64_t
floating point	float, double, complex <float>, complex<double>
boolean	bool
strings	std::string
std::vector<T>	T is std::string or any of the boolean, integer or floating point types above
std::vector<std::vector<T>>	T is std::string or any of the boolean, integer or floating point types above
std::vector<HolovizOp::InputSpec>	a vector of InputSpec objects that are specific to HolovizOp
std::shared_ptr<%>	T is any of the scalar, vector or std::string types above
tensor types	holoscan::Tensor, nvidia::gxf::Tensor, nvidia::gxf::VideoBuffer, nvidia::gxf::AudioBuffer
GXF-specific types	nvidia::gxf::TimeStamp, nvidia::gxf::EndOfStream

10.3.1 Python

For the Python API, any array-like object supporting the [DLPack](#) interface, `__array_interface__` or `__cuda_array_interface__` will be transmitted using Tensor serialization. This is done to avoid data copies for performance reasons. Objects of type `list[holoscan.HolovizOp.InputSpec]` will be sent using the underlying C++ serializer for `std::vector<HolovizOp::InputSpec>`. All other Python objects will be serialized to/from a `std::string` using the [cloudpickle](#) library.

Warning: A restriction imposed by the use of cloudpickle is that all fragments in a distributed application [must be running the same Python version](#).

Warning: Distributed applications behave differently than single fragment applications when `op_output.emit()` is called to emit a tensor-like Python object. Specifically, for array-like objects such as a PyTorch tensor, the same Python object will **not** be received by any call to `op_input.receive()` in a downstream Python operator (even if the upstream and downstream operators are part of the same fragment). An object of type `holoscan.Tensor` will be received as a `holoscan.Tensor`. Any other array-like objects with data stored on device (GPU) will be received as a CuPy tensor. Similarly, any array-like object with data stored on the host (CPU) will be received as a NumPy array. The user must convert back to the original array-like type if needed (typically possible in a zero-copy fashion via DLPack or array interfaces).

10.3.2 C++

For any additional C++ classes that need to be serialized for transmission between fragments in a distributed application, the user must create their own codec and register it with the Holoscan SDK framework. As a concrete example, suppose that we had the following simple Coordinate class that we wish to send between fragments.

```
struct Coordinate {
    float x;
    float y;
    float z;
};
```

To create a codec capable of serializing and deserializing this type one should define a `holoscan::codec` class for it as shown below.

```

#include "holoscan/core/codec_registry.hpp"
#include "holoscan/core/errors.hpp"
#include "holoscan/core/expected.hpp"

namespace holoscan {

template <
struct codec<Coordinate> {
    static expected<size_t, RuntimeError> serialize(const Coordinate& value, Endpoint*
↪endpoint) {
        return serialize_trivial_type<Coordinate>(value, endpoint);
    }
    static expected<Coordinate, RuntimeError> deserialize(Endpoint* endpoint) {
        return deserialize_trivial_type<Coordinate>(endpoint);
    }
};

} // namespace holoscan

```

where the first argument to `serialize` is a `const` reference to the type to be serialized and the return value is an `expected` containing the number of bytes that were serialized. The `deserialize` method returns an `expected` containing the deserialized object. The `Endpoint` class is a base class representing the serialization endpoint (For distributed applications, the actual endpoint class used is `UcxSerializationBuffer`).

The helper functions `serialize_trivial_type` (`deserialize_trivial_type`) can be used to serialize (deserialize) any plain-old-data (POD) type. Specifically, POD types can be serialized by just copying `sizeof(Type)` bytes to/from the endpoint. The `read_trivial_type()` and `~holoscan::Endpoint::write_trivial_type` methods could be used directly instead.

```

template <
struct codec<Coordinate> {
    static expected<size_t, RuntimeError> serialize(const Coordinate& value, Endpoint*
↪endpoint) {
        return endpoint->write_trivial_type(&value);
    }
    static expected<Coordinate, RuntimeError> deserialize(Endpoint* endpoint) {
        Coordinate encoded;
        auto maybe_value = endpoint->read_trivial_type(&encoded);
        if (!maybe_value) { return forward_error(maybe_value); }
        return encoded;
    }
};

```

In practice, one would not actually need to define `codec<Coordinate>` at all since `Coordinate` is a trivially serializable type and the existing codec treats any types for which there is not a template specialization as a trivially serializable type. It is, however, still necessary to register the codec type with the `CodecRegistry` as described below.

For non-trivial types, one will likely also need to use the `read()` and `write()` methods to implement the codec. Example use of these for the built-in codecs can be found in `holoscan/core/codecs.hpp`.

Once such a codec has been defined, the remaining step is to register it with the static `CodecRegistry` class. This will make the UCX-based classes used by distributed applications aware of the existence of a codec for serialization of this object type. If the type is specific to a particular operator, then one can register it via the `register_codec()` class.

```
#include "holoscan/core/codec_registry.hpp"

namespace holoscan::ops {

void MyCoordinateOperator::initialize() {
    register_codec<Coordinate>("Coordinate");

    // ...

    // parent class initialize() call must be after the argument additions above
    Operator::initialize();
}

} // namespace holoscan::ops
```

Here, the argument provided to `register_codec` is the name the registry will use for the codec. This name will be serialized in the message header so that the deserializer knows which deserialization function to use on the received data. In this example, we chose a name that matches the class name, but that is not a requirement. If the name matches one that is already present in the `CodecRegistry` class, then any existing codec under that name will be replaced by the newly registered one.

It is also possible to directly register the type outside of the context of `initialize()` by directly retrieving the static instance of the codec registry as follows.

```
namespace holoscan {

CodecRegistry::get_instance().add_codec<Coordinate>("Coordinate");

} // namespace holoscan
```

Tip: CLI arguments (such as `--driver`, `--worker`, `--fragments`) are parsed by the `Application` (C++/Python) class and the remaining arguments are available as `app.argv` (C++/Python).

C++

A concrete example of using `app->argv()` in the `ping_distributed.cpp` example is covered in the section on *user-defined command line arguments*.

If you want to get access to the arguments before creating the C++ instance, you can access them through `holoscan::Application().argv()`.

The following example shows how to access the arguments in your application.

```
#include <holoscan/holoscan.hpp>

class MyPingApp : public holoscan::Application {
// ...
};

int main(int argc, char** argv) {
    auto my_argv =
        holoscan::Application({"myapp", "--driver", "my_arg1", "--address=10.0.0.1"}).
        argv();
```

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```

HOLOSCAN_LOG_INFO(" my_argv: {}", fmt::join(my_argv, " "));

HOLOSCAN_LOG_INFO(
    "    argv: {} (argc: {}) ",
    fmt::join(std::vector<std::string>(argv, argv + argc), " "),
    argc);

auto app_argv = holoscan::Application().argv(); // do not use reference ('auto&') here_
↳ (lifetime issue)
HOLOSCAN_LOG_INFO("app_argv: {} (size: {})", fmt::join(app_argv, " "), app_argv.
↳ size());

auto app = holoscan::make_application<MyPingApp>();
HOLOSCAN_LOG_INFO("app->argv() == app_argv: {}", app->argv() == app_argv);

app->run();
return 0;
}

// $ ./myapp --driver --input image.dat --address 10.0.0.20

// my_argv: myapp my_arg1
//     argv: ./myapp --driver --input image.dat --address 10.0.0.20 (argc: 6)
// app_argv: ./myapp --input image.dat (size: 3)
// app->argv() == app_argv: true

```

Please see other examples in the [Application unit tests](#) in the Holoscan SDK repository.

Python

A concrete example of usage of `app.argv` in the `ping_distributed.py` example is covered in the section on *user-defined command line arguments*.

If you want to get access to the arguments before creating the Python instance, you can access them through `Application().argv`.

The following example shows how to access the arguments in your application.

```

import argparse
import sys
from holoscan.core import Application

class MyApp(Application):
    def compose(self):
        pass

def main():
    app = MyApp() # or alternatively, MyApp([sys.executable, *sys.argv])
    app.run()

```

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```

if __name__ == "__main__":

    print("sys.argv:", sys.argv)
    print("Application().argv:", app.argv)

    parser = argparse.ArgumentParser()
    parser.add_argument("--input")
    args = parser.parse_args(app.argv[1:])
    print("args:", args)

    main()

# $ python cli_test.py --address 10.0.0.20 --input image.dat
# sys.argv: ['cli_test.py', '--address', '10.0.0.20', '--input', 'image.dat']
# Application().argv: ['cli_test.py', '--input', 'image.dat']
# args: Namespace(input='a')

```

```

>>> from holoscan.core import Application
>>> import sys
>>> Application().argv == sys.argv
True
>>> Application([]).argv == sys.argv
True
>>> Application([sys.executable, *sys.argv]).argv == sys.argv
True
>>> Application(["python3", "myapp.py", "--driver", "my_arg1", "--address=10.0.0.1"]).
↪argv
['myapp.py', 'my_arg1']

```

Please see other examples in the [Application unit tests](#) (`TestApplication` class) in the Holoscan SDK repository.

10.3.3 Adding user-defined command line arguments

When adding user-defined command line arguments to an application, one should avoid the use of any of the default command line argument names as `--help`, `--version`, `--config`, `--driver`, `--worker`, `--address`, `--worker-address`, `--fragments` as covered in the section on [running a distributed application](#). It is recommended to parse user-defined arguments from the `argv` ((C++/Python)) method/property of the application as covered in the note above instead of using C++ `char* argv[]` or Python `sys.argv` directly. This way, only the new, user-defined arguments will need to be parsed.

A concrete example of this for both C++ and Python can be seen in the existing [ping_distributed](#) example where an application-defined boolean argument (`--gpu`) is specified in addition to the default set of application arguments.

C++

```

int main() {
    auto app = holoscan::make_application<App>();

    // Parse args
    bool tensor_on_gpu = false;
    auto& args = app->argv();
    if (std::find(args.begin(), args.end(), "--gpu") != std::end(args)) { tensor_on_gpu =
    true; }

    // configure tensor on host vs. GPU
    app->gpu_tensor(tensor_on_gpu);

    // run the application
    app->run();

    return 0;
}

```

Python

```

def main(on_gpu=False):
    app = MyPingApp()

    tensor_str = "GPU" if on_gpu else "host"
    print(f"Configuring application to use {tensor_str} tensors")
    app.gpu_tensor = on_gpu

    app.run()

if __name__ == "__main__":

    # get the Application's arguments
    app_argv = Application().argv

    parser = ArgumentParser(description="Distributed ping application.")
    parser.add_argument(
        "--gpu",
        action="store_true",
        help="Use a GPU tensor instead of a host tensor",
    )
    # pass app_argv[1:] to parse_args (app_argv[0] is the path of the application)
    args = parser.parse_args(app_argv[1:])
    main(on_gpu=args.gpu)

```

For Python, `app.argv[1:]` can be used with an `ArgumentParser` from Python's `argparse` module.

Alternatively, it may be preferable to instead use `parser.parse_known_args()` to allow any arguments not defined by the user's parser to pass through to the application class itself. If one also sets `add_help=False` when constructing the `ArgumentParser`, it is possible to print the parser's help while still preserving the default application help (covering the default set of distributed application arguments). An example of this style is shown in the code block below.

```
parser = ArgumentParser(description="Distributed ping application.", add_help=False)
parser.add_argument(
    "--gpu",
    action="store_true",
    help="Use a GPU tensor instead of a host tensor",
)

# use parse_known_args to ignore other CLI arguments that may be used by Application
args, remaining = parser.parse_known_args()

# can print the parser's help here prior to the Application's help output
if "-h" in remaining or "--help" in remaining:
    print("Additional arguments supported by this application:")
    print(textwrap.indent(parser.format_help(), " "))
main(on_gpu=args.gpu)
```


PACKAGING HOLOSCAN APPLICATIONS

The *Holoscan App Packager*, included as part of the *Holoscan CLI* as the `package` command, allows you to package your Holoscan applications into a *HAP-compliant* container image for distribution and deployment.

11.1 Prerequisites

11.1.1 Dependencies

Ensure the following are installed in the environment where you want to run the *CLI*:

- **PIP dependencies** (automatically installed with the holoscan python wheel)
- **NVIDIA Container Toolkit with Docker**
 - Developer Kits (aarch64): already included in IGX Software and JetPack
 - x86_64: tested with NVIDIA Container Toolkit 1.13.3 w/Docker v24.0.1
- **Docker BuildX plugin**
 1. Check if it is installed:

```
$ docker buildx version
github.com/docker/buildx v0.10.5 86bdced
```

2. If not, run the following commands based on the [official doc](#):

```
# Install Docker dependencies
sudo apt-get update
sudo apt-get install ca-certificates curl gnupg

# Add Docker Official GPG Key
sudo install -m 0755 -d /etc/apt/keyrings
curl -fsSL https://download.docker.com/linux/ubuntu/gpg | sudo gpg --dearmor -o_
↪ /etc/apt/keyrings/docker.gpg
sudo chmod a+r /etc/apt/keyrings/docker.gpg

# Configure Docker APT Repository
echo \
"deb [arch="$(dpkg --print-architecture)" signed-by=/etc/apt/keyrings/docker.
↪ gpg] https://download.docker.com/linux/ubuntu \
"$(. /etc/os-release && echo "$VERSION_CODENAME")" stable" | \
sudo tee /etc/apt/sources.list.d/docker.list > /dev/null
```

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```
# Install Docker BuildX Plugin
sudo apt-get update
sudo apt-get install docker-buildx-plugin
```

- **QEMU** (Optional)
 - used for packaging container images of different architectures than the host (example: x86_64 -> arm64)

11.1.2 CLI Installation

The Holoscan CLI is installed as part of the Holoscan SDK and can be called with the following instructions depending on your installation:

If installed as a python wheel

- In a virtual environment: the holoscan CLI should already be in the PATH
- Globally: ensure that `$HOME/.local/bin` is added to your PATH. Run the following command make it available across sessions:

```
echo 'export PATH=$HOME/.local/bin:$PATH' >> ~/.bashrc
```

If installed as a debian package

Ensure that `/opt/nvidia/holoscan/` is added to your PATH. Run the following command make it available across sessions:

```
echo 'alias holoscan=/opt/nvidia/holoscan/bin/holoscan' >> ~/.bashrc
```

If built or installed from source (local only)

Ensure that `${BUILD_OR_INSTALL_DIR}/bin` is added to your PATH. Run the following command make it available across sessions:

```
echo 'alias holoscan=${BUILD_OR_INSTALL_DIR}/bin/holoscan' >> ~/.bashrc
```

Warning: The Holoscan CLI is not available inside the [NGC Container](#) nor the development container (from source).

11.2 Package an application

Tip: The packager feature is also illustrated in the [cli_packager](#) and [video_replayer_distributed](#) examples.

1. Ensure to use the *HAP environment variables* wherever possible when accessing data. For example:
Let's take a look at the distributed video replayer example ([examples/video_replayer_distributed](#)).

- **Using the Application Configuration File**

C++

In the main function, we call the `app->config(config_path)` function with the default configuration file. The `app->config(...)` checks to see if the application was executed with `--config` argument first. If `--config` was set, the method uses the configuration file from the `--config` argument. Otherwise, it checks if the environment variable `HOLOSCAN_CONFIG_PATH` is set and uses that value as the source. If neither were set, the default configuration file (`config_path`) is used.

```
int main(int argc, char** argv) {
    // Get the yaml configuration file
    auto config_path = std::filesystem::canonical(argv[0]).parent_path();
    config_path /= std::filesystem::path("video_replayer_distributed.yaml");

    auto app = holoscan::make_application<DistributedVideoReplayerApp>();
    app->config(config_path);
    app->run();

    return 0;
}
```

Python

In the main function, we call the `app.config(config_file_path)` function with the default configuration file. The `app.config(...)` method checks to see if the application was executed with `--config` argument first. If `--config` was set, the method uses the configuration file from the `--config` argument. Otherwise, it checks if the environment variable `HOLOSCAN_CONFIG_PATH` is set and uses that value as the source. If neither were set, the default configuration file (`config_file_path`) is used.

```
def main():
    input_path = get_input_path()
    config_file_path = os.path.join(os.path.dirname(__file__), "video_replayer_
distributed.yaml")

    logging.info(f"Reading application configuration from {config_file_path}")

    app = DistributedVideoReplayerApp(input_path)
    app.config(config_file_path)
    app.run()
```

- Using Environment Variable `HOLOSCAN_INPUT_PATH` for Data Input

C++

In `Fragment1`, we try to set the input video directory with the value defined in `HOLOSCAN_INPUT_PATH`. When we instantiate a new Video Stream Replayer operator, we pass in all configuration values from the `from_config("replayer")` call. In addition, we include args that we created with the value from `HOLOSCAN_INPUT_PATH` if available as the last argument to override the directory setting.

```
class Fragment1 : public holoscan::Fragment {
public:
    void compose() override {
        using namespace holoscan;
```

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```

ArgList args;
auto data_directory = std::getenv("HOLOSCAN_INPUT_PATH");
if (data_directory != nullptr && data_directory[0] != '\0') {
    auto video_directory = std::filesystem::path(data_directory);
    video_directory /= "racerx";
    args.add(Arg("directory", video_directory.string()));
    HOLOSCAN_LOG_INFO("Using video from {}", video_directory.string());
}
auto replayer =
    make_operator<ops::VideoStreamReplayerOp>("replayer", from_config(
↪ "replayer"), args);
    add_operator(replayer);
}
};

```

Python

In `Fragment1`, we try to set the input video directory with the value defined in `HOLOSCAN_INPUT_PATH`. When we instantiate a new Video Stream Replayer operator, we pass in the `video_path` along with all replayer configurations found in the configuration file.

```

class Fragment1(Fragment):
    def __init__(self, app, name):
        super().__init__(app, name)

    def __init__(self, app, name):
        super().__init__(app, name)

    def compose(self):
        # Set the video source
        video_path = self._get_input_path()
        logging.info(
            f"Using video from {video_path}"
        )

        # Define the replayer and holoviz operators
        replayer = VideoStreamReplayerOp(
            self, name="replayer", directory=video_path, **self.kwargs("replayer
↪ ")
        )

        self.add_operator(replayer)

    def _get_input_path(self):
        path = os.environ.get(
            "HOLOSCAN_INPUT_PATH", os.path.join(os.path.dirname(__file__), "data
↪ ")
        )
        return os.path.join(path, "racerx")

```

2. Include a YAML configuration file as described in the [Application Runner Configuration](#) page.

3. Use the `holoscan package` command to create a HAP container image. For example:

```
holoscan package --platform x64-workstation --tag my-awesome-app --config /path/to/
↳my/awesome/application/config.yaml /path/to/my/awesome/application/
```

11.3 Run a packaged application

The packaged Holoscan application container image can run with the *Holoscan App Runner*:

```
holoscan run -i /path/to/my/input -o /path/to/application/generated/output my-
↳application:1.0.1
```

Since the packaged Holoscan application container images are OCI-compliant, they're also compatible with [Docker](#), [Kubernetes](#), and [containerd](#).

Each packaged Holoscan application container image includes tools inside for extracting the embedded application, manifest files, models, etc. To access the tool and to view all available options, run the following:

```
docker run -it my-container-image[:tag] help
```

The command should prints following:

```
USAGE: /var/holoscan/tools [command] [arguments]...
Command List
  extract ----- Extract data based on mounted volume paths.
    /var/run/holoscan/export/app      extract the application
    /var/run/holoscan/export/config   extract app.json and pkg.json manifest files.
↳and application YAML.
    /var/run/holoscan/export/models   extract models
    /var/run/holoscan/export/docs     extract documentation files
    /var/run/holoscan/export         extract all of the above
    IMPORTANT: ensure the directory to be mounted for data extraction is created.
↳first on the host system.
                and has the correct permissions. If the directory had been created by
↳the container previously
                with the user and group being root, please delete it and manually
↳create it again.
  show ----- Print manifest file(s): [app|pkg] to the
↳terminal.
    app                                print app.json
    pkg                                print pkg.json
  env ----- Print all environment variables to the terminal.
```

Note: The tools can also be accessed inside the Docker container via `/var/holoscan/tools`.

For example, run the following commands to extract the manifest files and the application configuration file:

```
# create a directory on the host system first
mkdir -p config-files

# mount the directory created to /var/run/holoscan/export/config
```

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```
docker run -it --rm -v $(pwd)/config-files:/var/run/holoscan/export/config my-container-
↳image[:tag] extract

# include -u 1000 if the above command reports a permission error
docker run -it --rm -u 1000 -v $(pwd)/config-files:/var/run/holoscan/export/config my-
↳container-image[:tag] extract

# If the permission error continues to occur, please check if the mounted directory has
↳the correct permission.
# If it doesn't, please recreate it or change the permissions as needed.

# list files extracted
ls config-files/

# output:
# app.json  app.yaml  pkg.json
```

CREATING OPERATORS

Tip: Creating a custom operator is also illustrated in the *ping_custom_op* example.

12.1 C++ Operators

When assembling a C++ application, two types of operators can be used:

1. **Native C++ operators:** custom operators defined in C++ without using the GXF API, by creating a subclass of `holoscan::Operator`. These C++ operators can pass arbitrary C++ objects around between operators.
2. **GXF Operators:** operators defined in the underlying C++ library by inheriting from the `holoscan::ops::GXFOperator` class. These operators wrap GXF codelets from GXF extensions. Examples are `VideoStreamReplayerOp` for replaying video files, `FormatConverterOp` for format conversions, and `HolovizOp` for visualization.

Note: It is possible to create an application using a mixture of GXF operators and native operators. In this case, some special consideration to cast the input and output tensors appropriately must be taken, as shown in [a section below](#).

12.1.1 Native C++ Operators

Operator Lifecycle (C++)

The lifecycle of a `holoscan::Operator` is made up of three stages:

- `start()` is called once when the operator starts, and is used for initializing heavy tasks such as allocating memory resources and using parameters.
- `compute()` is called when the operator is triggered, which can occur any number of times throughout the operator lifecycle between `start()` and `stop()`.
- `stop()` is called once when the operator is stopped, and is used for deinitializing heavy tasks such as deallocating resources that were previously assigned in `start()`.

All operators on the workflow are scheduled for execution. When an operator is first executed, the `start()` method is called, followed by the `compute()` method. When the operator is stopped, the `stop()` method is called. The `compute()` method is called multiple times between `start()` and `stop()`.

If any of the scheduling conditions specified by *Conditions* are not met (for example, the `CountCondition` would cause the scheduling condition to not be met if the operator has been executed a certain number of times), the operator is stopped and the `stop()` method is called.

We will cover how to use Conditions in the *Specifying operator inputs and outputs (C++)* section of the user guide.

Typically, the `start()` and the `stop()` functions are only called once during the application's lifecycle. However, if the scheduling conditions are met again, the operator can be scheduled for execution, and the `start()` method will be called again.

Fig. 12.1: The sequence of method calls in the lifecycle of a Holoscan Operator

We can override the default behavior of the operator by implementing the above methods. The following example shows how to implement a custom operator that overrides `start`, `stop` and `compute` methods.

Listing 12.1: The basic structure of a Holoscan Operator (C++)

```
1  #include "holoscan/holoscan.hpp"
2
3  using holoscan::Operator;
4  using holoscan::OperatorSpec;
5  using holoscan::InputContext;
6  using holoscan::OutputContext;
7  using holoscan::ExecutionContext;
8  using holoscan::Arg;
9  using holoscan::ArgList;
10
11 class MyOp : public Operator {
12 public:
13     HOLOSCAN_OPERATOR_FORWARD_ARGS(MyOp)
14
15     MyOp() = default;
16
17     void setup(OperatorSpec& spec) override {
18     }
19
20     void start() override {
21         HOLOSCAN_LOG_TRACE("MyOp::start()");
22     }
23
24     void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
25         HOLOSCAN_LOG_TRACE("MyOp::compute()");
26     };
27
28     void stop() override {
29         HOLOSCAN_LOG_TRACE("MyOp::stop()");
30     }
31 };
```

Creating a custom operator (C++)

To create a custom operator in C++ it is necessary to create a subclass of `holoscan::Operator`. The following example demonstrates how to use native operators (the operators that do not have an underlying, pre-compiled GXF Codelet).

Code Snippet: `examples/ping_multi_port/cpp/ping_multi_port.cpp`

Listing 12.2: `examples/ping_multi_port/cpp/ping_multi_port.cpp`

```

21 #include "holoscan/holoscan.hpp"
22
23 class ValueData {
24 public:
25     ValueData() = default;
26     explicit ValueData(int value) : data_(value) {
27         HOLOSCAN_LOG_TRACE("ValueData::ValueData(): {}", data_);
28     }
29     ~ValueData() {
30         HOLOSCAN_LOG_TRACE("ValueData::~ValueData(): {}", data_);
31     }
32
33     void data(int value) { data_ = value; }
34
35     int data() const { return data_; }
36
37 private:
38     int data_;
39 };
40
41 namespace holoscan::ops {
42
43 class PingTxOp : public Operator {
44 public:
45     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingTxOp)
46
47     PingTxOp() = default;
48
49     void setup(OperatorSpec& spec) override {
50         spec.output<std::shared_ptr<ValueData>>("out1");
51         spec.output<std::shared_ptr<ValueData>>("out2");
52     }
53
54     void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
55         auto value1 = std::make_shared<ValueData>(index_++);
56         op_output.emit(value1, "out1");
57
58         auto value2 = std::make_shared<ValueData>(index_++);
59         op_output.emit(value2, "out2");
60     };
61     int index_ = 0;
62 };
63
64 class PingMiddleOp : public Operator {

```

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```

65 public:
66     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingMiddleOp)
67
68     PingMiddleOp() = default;
69
70     void setup(OperatorSpec& spec) override {
71         spec.input<std::shared_ptr<ValueData>>("in1");
72         spec.input<std::shared_ptr<ValueData>>("in2");
73         spec.output<std::shared_ptr<ValueData>>("out1");
74         spec.output<std::shared_ptr<ValueData>>("out2");
75         spec.param(multiplier_, "multiplier", "Multiplier", "Multiply the input by this value
↪", 2);
76     }
77
78     void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext&)
↪override {
79         auto value1 = op_input.receive<std::shared_ptr<ValueData>>("in1").value();
80         auto value2 = op_input.receive<std::shared_ptr<ValueData>>("in2").value();
81
82         HOLOSCAN_LOG_INFO("Middle message received (count: {})", count_++);
83
84         HOLOSCAN_LOG_INFO("Middle message value1: {}", value1->data());
85         HOLOSCAN_LOG_INFO("Middle message value2: {}", value2->data());
86
87         // Multiply the values by the multiplier parameter
88         value1->data(value1->data() * multiplier_);
89         value2->data(value2->data() * multiplier_);
90
91         op_output.emit(value1, "out1");
92         op_output.emit(value2, "out2");
93     };
94
95 private:
96     int count_ = 1;
97     Parameter<int> multiplier_;
98 };
99
100 class PingRxOp : public Operator {
101 public:
102     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingRxOp)
103
104     PingRxOp() = default;
105
106     void setup(OperatorSpec& spec) override {
107         spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {}
↪);
108     }
109
110     void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
111         auto value_vector =
112             op_input.receive<std::vector<std::shared_ptr<ValueData>>>("receivers").value();
113

```

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```

114 HOLOSCAN_LOG_INFO("Rx message received (count: {}, size: {})", count_++, value_
    ↳vector.size());
115
116 HOLOSCAN_LOG_INFO("Rx message value1: {}", value_vector[0]->data());
117 HOLOSCAN_LOG_INFO("Rx message value2: {}", value_vector[1]->data());
118 };
119
120 private:
121 Parameter<std::vector<IOSpec*>> receivers_;
122 int count_ = 1;
123 };
124
125 } // namespace holoscan::ops
126
127 class App : public holoscan::Application {
128 public:
129 void compose() override {
130     using namespace holoscan;
131
132     auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
133     auto mx = make_operator<ops::PingMiddleOp>("mx", Arg("multiplier", 3));
134     auto rx = make_operator<ops::PingRxOp>("rx");
135
136     add_flow(tx, mx, {{ "out1", "in1" }, { "out2", "in2" }});
137     add_flow(mx, rx, {{ "out1", "receivers" }, { "out2", "receivers" }});
138 }
139 };
140
141 int main(int argc, char** argv) {
142     auto app = holoscan::make_application<MyPingApp>();
143     app->run();
144
145     return 0;
146 }

```

Code Snippet: [examples/native_operator/cpp/app_config.yaml](#)

In this application, three operators are created: PingTxOp, PingMxOp, and PingRxOp

1. The PingTxOp operator is a source operator that emits two values every time it is invoked. The values are emitted on two different output ports, out1 (for even integers) and out2 (for odd integers).
2. The PingMxOp operator is a middle operator that receives two values from the PingTxOp operator and emits two values on two different output ports. The values are multiplied by the multiplier parameter.
3. The PingRxOp operator is a sink operator that receives two values from the PingMxOp operator. The values are received on a single input, receivers, which is a vector of input ports. The PingRxOp operator receives the values in the order they are emitted by the PingMxOp operator.

As covered in more detail below, the inputs to each operator are specified in the setup() method of the operator. Then inputs are received within the compute() method via op_input.receive() and outputs are emitted via op_output.emit().

Note that for native C++ operators as defined here, any object including a shared pointer can be emitted or received. For large objects such as tensors it may be preferable from a performance standpoint to transmit a shared pointer to the object rather than making a copy. When shared pointers are used and the same tensor is sent to more than one

downstream operator, one should avoid in-place operations on the tensor or race conditions between operators may occur.

Specifying operator parameters (C++)

In the example `holoscan::ops::PingMxOp` operator above, we have a parameter `multiplier` that is declared as part of the class as a private member using the `param()` templated type:

```
Parameter<int> multiplier_;
```

It is then added to the `OperatorSpec` attribute of the operator in its `setup()` method, where an associated string key must be provided. Other properties can also be mentioned such as description and default value:

```
// Provide key, and optionally other information
spec.param(multiplier_, "multiplier", "Multiplier", "Multiply the input by this value", 2);
```

Note: If your parameter is of a custom type, you must register that type and provide a YAML encoder/decoder, as documented under `holoscan::Operator::register_converter()`

See the [Configuring operator parameters](#) section to learn how an application can set these parameters.

Specifying operator inputs and outputs (C++)

To configure the input(s) and output(s) of C++ native operators, call the `spec.input()` and `spec.output()` methods within the `setup()` method of the operator.

The `spec.input()` and `spec.output()` methods should be called once for each input and output to be added. The `OperatorSpec` object and the `setup()` method will be initialized and called automatically by the `Application` class when its `run()` method is called.

These methods (`spec.input()` and `spec.output()`) return an `IOSpec` object that can be used to configure the input/output port.

By default, the `holoscan::MessageAvailableCondition` and `holoscan::DownstreamMessageAffordableCondition` conditions are applied (with a `min_size` of 1) to the input/output ports. This means that the operator's `compute()` method will not be invoked until a message is available on the input port and the downstream operator's input port (queue) has enough capacity to receive the message.

```
void setup(OperatorSpec& spec) override {
    spec.input<std::shared_ptr<ValueData>>("in");
    // Above statement is equivalent to:
    // spec.input<std::shared_ptr<ValueData>>("in")
    //     .condition(ConditionType::kMessageAvailable, Arg("min_size") = 1);

    spec.output<std::shared_ptr<ValueData>>("out");
    // Above statement is equivalent to:
    // spec.output<std::shared_ptr<ValueData>>("out")
    //     .condition(ConditionType::kDownstreamMessageAffordable, Arg("min_size") = 1);
    ...
}
```

In the above example, the `spec.input()` method is used to configure the input port to have the `holoscan::MessageAvailableCondition` with a minimum size of 1. This means that the operator's `compute()` method will not be invoked until a message is available on the input port of the operator. Similarly, the `spec.output()` method is used to configure the output port to have the `holoscan::DownstreamMessageAffordableCondition` with a minimum size of 1. This means that the operator's `compute()` method will not be invoked until the downstream operator's input port has enough capacity to receive the message.

If you want to change this behavior, use the `IOSpec::condition()` method to configure the conditions. For example, to configure the input and output ports to have no conditions, you can use the following code:

```
void setup(OperatorSpec& spec) override {
    spec.input<std::shared_ptr<ValueData>>("in")
        .condition(ConditionType::kNone);

    spec.output<std::shared_ptr<ValueData>>("out")
        .condition(ConditionType::kNone);
    // ...
}
```

The example code in the `setup()` method configures the input port to have no conditions, which means that the `compute()` method will be called as soon as the operator is ready to compute. Since there is no guarantee that the input port will have a message available, the `compute()` method should check if there is a message available on the input port before attempting to read it.

The `receive()` method of the `InputContext` object can be used to access different types of input data within the `compute()` method of your operator class, where its template argument (`DataT`) is the data type of the input. This method takes the name of the input port as an argument (which can be omitted if your operator has a single input port), and returns the input data. If input data is not available, the method returns an object of the `holoscan::RuntimeError` class which contains an error message describing the reason for the failure. The `holoscan::RuntimeError` class is a derived class of `std::runtime_error` and supports accessing more error information, for example, with `what()` method.

In the example code fragment below, the `PingRxOp` operator receives input on a port called "in" with data type `ValueData`. The `receive()` method is used to access the input data. The value is checked to be valid or not with the `if` condition. If value is of `holoscan::RuntimeError` type, then `if` condition will be false. Otherwise, the `data()` method of the `ValueData` class is called to get the value of the input data.

```
// ...

class PingRxOp : public holoscan::ops::GXFOperator {
public:
    HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER(PingRxOp, holoscan::ops::GXFOperator)
    PingRxOp() = default;
    void setup(OperatorSpec& spec) override {
        spec.input<ValueData>("in");
    }
    void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
        // The type of `value` is `ValueData`
        auto value = op_input.receive<ValueData>("in");
        if (value){
            HOLOSCAN_LOG_INFO("Message received (value: {})", value.data());
        }
    }
};
```

For GXF Entity objects (`holoscan::gxf::Entity` wraps underlying GXF `nvidia::gxf::Entity` class), the

receive() method will return the GXF Entity object for the input of the specified name. In the example below, the PingRxOp operator receives input on a port called “in” with data type holoscan::gxf::Entity.

```
// ...

class PingRxOp : public holoscan::ops::GXFOperator {
public:
    HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER(PingRxOp, holoscan::ops::GXFOperator)
    PingRxOp() = default;
    void setup(OperatorSpec& spec) override {
        spec.input<holoscan::gxf::Entity>("in");
    }
    void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
        // The type of `in_entity` is 'holoscan::gxf::Entity'.
        auto in_entity = op_input.receive<holoscan::gxf::Entity>("in");
        if (in_entity) {
            // Process with `in_entity`.
            // ...
        }
    }
};
```

For objects of type std::any, the receive() method will return a std::any object containing the input of the specified name. In the example below, the PingRxOp operator receives input on a port called “in” with data type std::any. The type() method of the std::any object is used to determine the actual type of the input data, and the std::any_cast<T>() function is used to retrieve the value of the input data.

```
// ...

class PingRxOp : public holoscan::ops::GXFOperator {
public:
    HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER(PingRxOp, holoscan::ops::GXFOperator)
    PingRxOp() = default;
    void setup(OperatorSpec& spec) override {
        spec.input<std::any>("in");
    }
    void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
        // The type of `in_any` is 'std::any'.
        auto in_any = op_input.receive<std::any>("in");
        auto& in_any_type = in_any.type();

        if (in_any_type == typeid(holoscan::gxf::Entity)) {
            auto in_entity = std::any_cast<holoscan::gxf::Entity>(in_any);
            // Process with `in_entity`.
            // ...
        } else if (in_any_type == typeid(std::shared_ptr<ValueData>)) {
            auto in_message = std::any_cast<std::shared_ptr<ValueData>>(in_any);
            // Process with `in_message`.
            // ...
        } else if (in_any_type == typeid(nullptr_t)) {
            // No message is available.
        } else {
            HOLOSCAN_LOG_ERROR("Invalid message type: {}", in_any_type.name());
            return;
        }
    }
};
```

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```

    }
  }
};

```

The Holoscan SDK provides built-in data types called **Domain Objects**, defined in the `include/holoscan/core/domain` directory. For example, the `holoscan::Tensor` is a Domain Object class that is used to represent a multi-dimensional array of data, which can be used directly by `OperatorSpec`, `InputContext`, and `OutputContext`.

Tip: This `holoscan::Tensor` class is a wrapper around the `DLManagedTensorCtx` struct holding a `DLManagedTensor` object. As such, it provides a primary interface to access Tensor data and is interoperable with other frameworks that support the `DLPack` interface.

Warning: Passing `holoscan::Tensor` objects to/from *GXF operators* directly is not supported. Instead, they need to be passed through `holoscan::gxf::Entity` objects. See the *interoperability section* for more details.

Receiving any number of inputs (C++)

Instead of assigning a specific number of input ports, it may be desired to have the ability to receive any number of objects on a port in certain situations. This can be done by defining `Parameter` with `std::vector<IOSpec*>` (`Parameter<std::vector<IOSpec*>> receivers_`) and calling `spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {})`; as done for `PingRxOp` in the *native operator ping example*.

Listing 12.3: `examples/ping_multi_port/cpp/ping_multi_port.cpp`

```

98 class PingRxOp : public Operator {
99 public:
100     HOLOSCAN_OPERATOR_FORWARD_ARGS(PingRxOp)
101
102     PingRxOp() = default;
103
104     void setup(OperatorSpec& spec) override {
105         spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {}
106         ↪);
107     }
108
109     void compute(InputContext& op_input, OutputContext&, ExecutionContext&) override {
110         auto value_vector = op_input.receive<std::vector<ValueData>>("receivers");
111
112         HOLOSCAN_LOG_INFO("Rx message received (count: {}, size: {})", count_++, value_
113         ↪vector.size());
114
115         HOLOSCAN_LOG_INFO("Rx message value1: {}", value_vector[0]->data());
116         HOLOSCAN_LOG_INFO("Rx message value2: {}", value_vector[1]->data());
117     };
118
119 private:
120     Parameter<std::vector<IOSpec*>> receivers_;
121     int count_ = 1;

```

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```

120 };
121
122 } // namespace holoscan::ops
123
124 class App : public holoscan::Application {
125 public:
126     void compose() override {
127         using namespace holoscan;
128
129         auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
130         auto mx = make_operator<ops::PingMiddleOp>("mx", Arg("multiplier", 3));
131         auto rx = make_operator<ops::PingRxOp>("rx");
132
133         add_flow(tx, mx, {"out1", "in1"}, {"out2", "in2"});
134         add_flow(mx, rx, {"out1", "receivers"}, {"out2", "receivers"});
135     }
136 };

```

Then, once the following configuration is provided in the `compose()` method, the `PingRxOp` will receive two inputs on the `receivers` port.

```
134: add_flow(mx, rx, {"out1", "receivers"}, {"out2", "receivers"});
```

By using a parameter (`receivers`) with `std::vector<holoscan::IOSpec*>` type, the framework creates input ports (`receivers:0` and `receivers:1`) implicitly and connects them (and adds the references of the input ports to the `receivers` vector).

Building your C++ operator

You can build your C++ operator using CMake, by calling `find_package(holoscan)` in your `CMakeLists.txt` to load the SDK libraries. Your operator will need to link against `holoscan::core`:

Listing 12.4: <src_dir>/CMakeLists.txt

```

# Your CMake project
cmake_minimum_required(VERSION 3.20)
project(my_project CXX)

# Finds the holoscan SDK
find_package(holoscan REQUIRED CONFIG PATHS "/opt/nvidia/holoscan")

# Create a library for your operator
add_library(my_operator SHARED my_operator.cpp)

# Link your operator against holoscan::core
target_link_libraries(my_operator
    PUBLIC holoscan::core
)

```

Once your `CMakeLists.txt` is ready in <src_dir>, you can build in <build_dir> with the command line below. You can optionally pass `Holoscan_ROOT` if the SDK installation you'd like to use differs from the `PATHS` given to `find_package(holoscan)` above.

```
# Configure
cmake -S <src_dir> -B <build_dir> -D Holoscan_ROOT="/opt/nvidia/holoscan"
# Build
cmake --build <build_dir> -j
```

Using your C++ Operator in an Application

- If the application is configured in the same CMake project as the operator, you can simply add the operator CMake target library name under the application executable `target_link_libraries` call, as the operator CMake target is already defined.

```
# operator
add_library(my_op my_op.cpp)
target_link_libraries(my_operator PUBLIC holoscan::core)

# application
add_executable(my_app main.cpp)
target_link_libraries(my_operator
    PRIVATE
    holoscan::core
    my_op
)
```

- If the application is configured in a separate project as the operator, you need to [export the operator](#) in its own CMake project, and import it in the application CMake project, before being able to list it under `target_link_libraries` also. This is the same as what is done for the SDK [built-in operators](#), available under the `holoscan::ops` namespace.

You can then include the headers to your C++ operator in your application code.

12.1.2 GXF Operators

With the Holoscan C++ API, we can also wrap [GXF Codelets](#) from GXF extensions as Holoscan Operators.

Note: If you do not have an existing GXF extension, we recommend developing native operators using the [C++](#) or [Python](#) APIs to skip the need for wrapping gxf codelets as operators. If you do need to create a GXF Extension, follow the [Creating a GXF Extension](#) section for a detailed explanation of the GXF extension development process.

Given an existing GXF extension, we can create a simple “identity” application consisting of a replayer, which reads contents from a file on disk, and our recorder from the last section, which will store the output of the replayer exactly in the same format. This allows us to see whether the output of the recorder matches the original input files.

The MyRecorderOp Holoscan Operator implementation below will wrap the MyRecorder GXF Codelet shown [here](#).

Operator definition

Listing 12.5: my_recorder_op.hpp

```
1  #ifndef APPS_MY_RECORDER_APP_MY_RECORDER_OP_HPP
2  #define APPS_MY_RECORDER_APP_MY_RECORDER_OP_HPP
3
4  #include "holoscan/core/gxf/gxf_operator.hpp"
5
6  namespace holoscan::ops {
7
8  class MyRecorderOp : public holoscan::ops::GXFOperator {
9  public:
10     HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER(MyRecorderOp, holoscan::ops::GXFOperator)
11
12     MyRecorderOp() = default;
13
14     const char* gxf_type_name() const override { return "MyRecorder"; }
15
16     void setup(OperatorSpec& spec) override;
17
18     void initialize() override;
19
20 private:
21     Parameter<holoscan::IOSpec*> receiver_;
22     Parameter<std::shared_ptr<holoscan::Resource>> my_serializer_;
23     Parameter<std::string> directory_;
24     Parameter<std::string> basename_;
25     Parameter<bool> flush_on_tick_;
26 };
27
28 } // namespace holoscan::ops
29
30 #endif /* APPS_MY_RECORDER_APP_MY_RECORDER_OP_HPP */
```

The `holoscan::ops::MyRecorderOp` class wraps a `MyRecorder` GXF Codelet by inheriting from the `holoscan::ops::GXFOperator` class. The `HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER` macro is used to forward the arguments of the constructor to the base class.

We first need to define the fields of the `MyRecorderOp` class. You can see that fields with the same names are defined in both the `MyRecorderOp` class and the `MyRecorder` GXF codelet .

Listing 12.6: Parameter declarations in
gxf_extensions/my_recorder/my_recorder.hpp

```

22  nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::Receiver>> receiver_;
23  nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::EntitySerializer>> my_
    serializer_;
24  nvidia::gxf::Parameter<std::string> directory_;
25  nvidia::gxf::Parameter<std::string> basename_;
26  nvidia::gxf::Parameter<bool> flush_on_tick_;

```

Comparing the MyRecorderOp holoscan parameter to the MyRecorder gxf codelet:

Holoscan Operator	GXF Codelet
holoscan::Parameter	nvidia::gxf::Parameter
holoscan::IOSpec*	nvidia::gxf::Handle<nvidia::gxf::Receiver>> or nvidia::gxf::Handle<nvidia::gxf::Transmitter>>
std::shared_ptr<holoscan::Resolver>	nvidia::gxf::Handle<T>> example: T is nvidia::gxf::EntitySerializer

We then need to implement the following functions:

- `const char* gxf_type_name()` `const` override: return the GXF type name of the Codelet. The fully-qualified class name (MyRecorder) for the GXF Codelet is specified.
- `void setup(OperatorSpec& spec)` override: setup the OperatorSpec with the inputs/outputs and parameters of the Operator.
- `void initialize()` override: initialize the Operator.

Setting up parameter specifications

The implementation of the `setup(OperatorSpec& spec)` function is as follows:

Listing 12.7: my_recorder_op.cpp

```

1  #include "../my_recorder_op.hpp"
2
3  #include "holoscan/core/fragment.hpp"
4  #include "holoscan/core/gxf/entity.hpp"
5  #include "holoscan/core/operator_spec.hpp"
6
7  #include "holoscan/core/resources/gxf/video_stream_serializer.hpp"
8
9  namespace holoscan::ops {
10
11  void MyRecorderOp::setup(OperatorSpec& spec) {
12      auto& input = spec.input<holoscan::gxf::Entity>("input");
13      // Above is same with the following two lines (a default condition is assigned to the
    input port if not specified):
14      //
15      //     auto& input = spec.input<holoscan::gxf::Entity>("input")
16      //         .condition(ConditionType::kMessageAvailable, Arg("min_size") = 1);

```

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```

17 spec.param(receiver_, "receiver", "Entity receiver", "Receiver channel to log", &
18 ↪input);
19 spec.param(my_serializer_,
20             "serializer",
21             "Entity serializer",
22             "Serializer for serializing input data");
23 spec.param(directory_, "out_directory", "Output directory path", "Directory path to
24 ↪store received output");
25 spec.param(basename_, "basename", "File base name", "User specified file name without
26 ↪extension");
27 spec.param(flush_on_tick_,
28             "flush_on_tick",
29             "Boolean to flush on tick",
30             "Flushes output buffer on every `tick` when true",
31             false);
32 }
33 void MyRecorderOp::initialize() {...}
34 } // namespace holoscan::ops

```

Here, we set up the inputs/outputs and parameters of the Operator. Note how the content of this function is very similar to the MyRecorder GXF codelet's *registerInterface* function.

- In the C++ API, GXF Receiver and Transmitter components (such as DoubleBufferReceiver and DoubleBufferTransmitter) are considered as input and output ports of the Operator so we register the inputs/outputs of the Operator with `input<T>` and `output<T>` functions (where T is the data type of the port).
- Compared to the pure *GXF application* that does the same job, the *SchedulingTerm* of an Entity in the *GXF Application YAML* are specified as Conditions on the input/output ports (e.g., `holoscan::MessageAvailableCondition` and `holoscan::DownstreamMessageAffordableCondition`).

The highlighted lines in `MyRecorderOp::setup` above match the following highlighted statements of *GXF Application YAML*:

Listing 12.8: A part of `apps/my_recorder_app_gxf/my_recorder_gxf.yaml`

```

35 name: recorder
36 components:
37   - name: input
38     type: nvidia::gxf::DoubleBufferReceiver
39   - name: allocator
40     type: nvidia::gxf::UnboundedAllocator
41   - name: component_serializer
42     type: nvidia::gxf::StdComponentSerializer
43     parameters:
44       allocator: allocator
45   - name: entity_serializer
46     type: nvidia::holoscan::stream_playback::VideoStreamSerializer # inheriting from
47 ↪nvidia::gxf::EntitySerializer
48     parameters:
49       component_serializers: [component_serializer]

```

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```

49 - type: MyRecorder
50   parameters:
51     receiver: input
52     serializer: entity_serializer
53     out_directory: "/tmp"
54     basename: "tensor_out"
55 - type: nvidia::gxf::MessageAvailableSchedulingTerm
56   parameters:
57     receiver: input
58     min_size: 1

```

In the same way, if we had a Transmitter GXF component, we would have the following statements (Please see available constants for `holoscan::ConditionType`):

```

auto& output = spec.output<holoscan::gxf::Entity>("output");
// Above is same with the following two lines (a default condition is assigned to the
// output port if not specified):
//
//   auto& output = spec.output<holoscan::gxf::Entity>("output")
//                               .condition(ConditionType::kDownstreamMessageAffordable, Arg(
// "min_size") = 1);

```

Initializing the operator

Next, the implementation of the `initialize()` function is as follows:

Listing 12.9: `my_recorder_op.cpp`

```

1  #include "../my_recorder_op.hpp"
2
3  #include "holoscan/core/fragment.hpp"
4  #include "holoscan/core/gxf/entity.hpp"
5  #include "holoscan/core/operator_spec.hpp"
6
7  #include "holoscan/core/resources/gxf/video_stream_serializer.hpp"
8
9  namespace holoscan::ops {
10
11  void MyRecorderOp::setup(OperatorSpec& spec) {...}
12
13  void MyRecorderOp::initialize() {
14    // Set up prerequisite parameters before calling GXFOperator::initialize()
15    auto frag = fragment();
16    auto serializer =
17        frag->make_resource<holoscan::VideoStreamSerializer>("serializer");
18    add_arg(Arg("serializer") = serializer);
19
20    GXFOperator::initialize();
21  }
22
23  } // namespace holoscan::ops

```

Here we set up the pre-defined parameters such as the serializer. The highlighted lines above matches the highlighted statements of *GXF Application YAML*:

Listing 12.10: Another part of apps/my_recorder_app_gxf/my_recorder_gxf.yaml

```
35 name: recorder
36 components:
37   - name: input
38     type: nvidia::gxf::DoubleBufferReceiver
39   - name: allocator
40     type: nvidia::gxf::UnboundedAllocator
41   - name: component_serializer
42     type: nvidia::gxf::StdComponentSerializer
43     parameters:
44       allocator: allocator
45   - name: entity_serializer
46     type: nvidia::holoscan::stream_playback::VideoStreamSerializer # inheriting from
47     ↪ nvidia::gxf::EntitySerializer
48     parameters:
49       component_serializers: [component_serializer]
50   - type: MyRecorder
51     parameters:
52       receiver: input
53       serializer: entity_serializer
54       out_directory: "/tmp"
55       basename: "tensor_out"
56   - type: nvidia::gxf::MessageAvailableSchedulingTerm
57     parameters:
58       receiver: input
59       min_size: 1
```

Note: The Holoscan C++ API already provides the `holoscan::VideoStreamSerializer` class which wraps the `nvidia::holoscan::stream_playback::VideoStreamSerializer` GXF component, used here as serializer.

Building your GXF operator

There are no differences in CMake between building a GXF operator and *building a native C++ operator*, since the GXF codelet is actually loaded through a GXF extension as a plugin, and does not need to be added to `target_link_libraries(my_operator ...)`.

Using your GXF Operator in an Application

There are no differences in CMake between using a GXF operator and *using a native C++ operator in an application*. However, the application will need to load the GXF extension library which holds the wrapped GXF codelet symbols, so the application needs to be configured to find the extension library in its yaml configuration file, as documented [here](#).

12.1.3 Interoperability between GXF and native C++ operators

To support sending or receiving tensors to and from operators (both GXF and native C++ operators), the Holoscan SDK provides the C++ classes below:

- A class template called `holoscan::MyMap` which inherits from `std::unordered_map<std::string, std::shared_ptr<T>>`. The template parameter `T` can be any type, and it is used to specify the type of the `std::shared_ptr` objects stored in the map.
-

A `holoscan::TensorMap` class defined as a specialization of `holoscan::Map` for the `holoscan::Tensor` type.

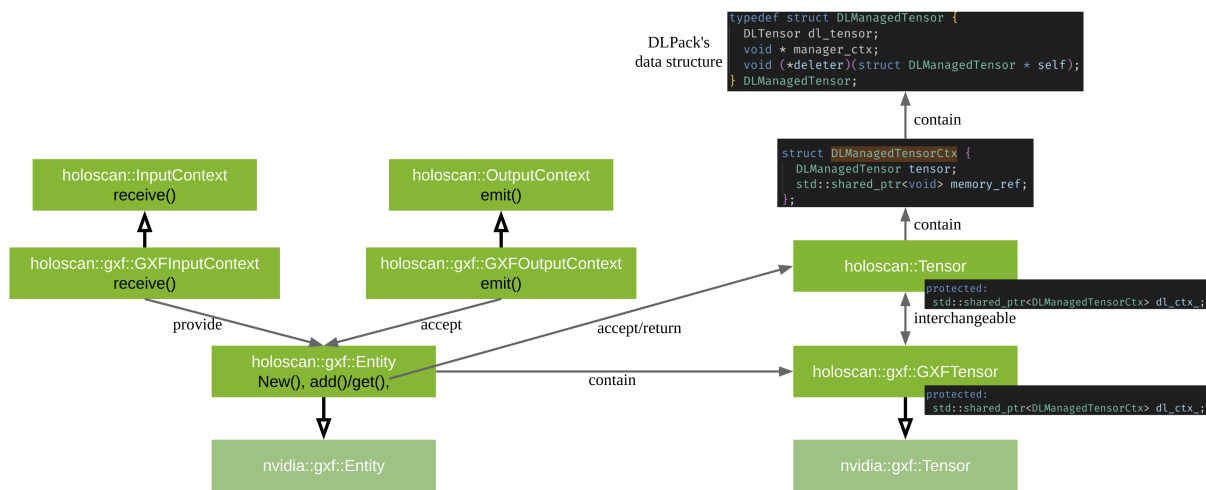


Fig. 12.2: Supporting Tensor Interoperability

Consider the following example, where `GXFSendTensorOp` and `GXFReceiveTensorOp` are GXF operators, and where `ProcessTensorOp` is a C++ native operator:

Fig. 12.3: The tensor interoperability between C++ native operator and GXF operator

The following code shows how to implement `ProcessTensorOp`'s `compute()` method as a C++ native operator communicating with GXF operators. Focus on the use of the `holoscan::gxf::Entity`:

Listing 12.11: examples/tensor_interop/cpp/tensor_interop.cpp

```

81 void compute(InputContext& op_input, OutputContext& op_output,
82             ExecutionContext& context) override {
83     // The type of `in_message` is 'holoscan::TensorMap'.
84     auto in_message = op_input.receive<holoscan::TensorMap>("in").value();
85     // the type of out_message is TensorMap
86     TensorMap out_message;
87
88     for (auto& [key, tensor] : in_message) { // Process with 'tensor' here.
89         cudaError_t cuda_status;
90         size_t data_size = tensor->nbytes();
91         std::vector<uint8_t> in_data(data_size);

```

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```

92     CUDA_TRY(cudaMemcpy(in_data.data(), tensor->data(), data_size,
93 ↪ cudaMemcpyDeviceToHost));
94     HOLOSCAN_LOG_INFO("ProcessTensorOp Before key: '{}', shape: ({}), data: [{}]",
95                       key,
96                       fmt::join(tensor->shape(), ","),
97                       fmt::join(in_data, ","));
98     for (size_t i = 0; i < data_size; i++) { in_data[i] *= 2; }
99     HOLOSCAN_LOG_INFO("ProcessTensorOp After key: '{}', shape: ({}), data: [{}]",
100                      key,
101                      fmt::join(tensor->shape(), ","),
102                      fmt::join(in_data, ","));
103     CUDA_TRY(cudaMemcpy(tensor->data(), in_data.data(), data_size,
104 ↪ cudaMemcpyHostToDevice));
105     out_message.insert({key, tensor});
106 }
107 // Send the processed message.
108 op_output.emit(out_message);
109 };

```

- The input message is of type `holoscan::TensorMap` object.
- Every `holoscan::Tensor` in the `TensorMap` object is copied on the host as `in_data`.
- The data is processed (values multiplied by 2)
- The data is moved back to the `holoscan::Tensor` object on the GPU.
- A new `holoscan::TensorMap` object `out_message` is created to be sent to the next operator with `op_output.emit()`.

Note: A complete example of the C++ native operator that supports interoperability with GXF operators is available in the `examples/tensor_interop/cpp` directory.

12.2 Python Operators

When assembling a Python application, two types of operators can be used:

1. **Native Python operators:** custom operators defined in Python, by creating a subclass of `holoscan.core.Operator`. These Python operators can pass arbitrary Python objects around between operators and are not restricted to the stricter parameter typing used for C++ API operators.
2. **Python wrappings of C++ Operators:** operators defined in the underlying C++ library by inheriting from the `holoscan::Operator` class. These operators have Python bindings available within the `holoscan.operators` module. Examples are `VideoStreamReplayerOp` for replaying video files, `FormatConverterOp` for format conversions, and `HolovizOp` for visualization.

Note: It is possible to create an application using a mixture of Python wrapped C++ operators and native Python operators. In this case, some special consideration to cast the input and output tensors appropriately must be taken, as shown in [a section below](#).

12.2.1 Native Python Operator

Operator Lifecycle (Python)

The lifecycle of a `holoscan.core.Operator` is made up of three stages:

- `start()` is called once when the operator starts, and is used for initializing heavy tasks such as allocating memory resources and using parameters.
- `compute()` is called when the operator is triggered, which can occur any number of times throughout the operator lifecycle between `start()` and `stop()`.
- `stop()` is called once when the operator is stopped, and is used for deinitializing heavy tasks such as deallocating resources that were previously assigned in `start()`.

All operators on the workflow are scheduled for execution. When an operator is first executed, the `start()` method is called, followed by the `compute()` method. When the operator is stopped, the `stop()` method is called. The `compute()` method is called multiple times between `start()` and `stop()`.

If any of the scheduling conditions specified by *Conditions* are not met (for example, the `CountCondition` would cause the scheduling condition to not be met if the operator has been executed a certain number of times), the operator is stopped and the `stop()` method is called.

We will cover how to use `Conditions` in the *Specifying operator inputs and outputs (Python)* section of the user guide.

Typically, the `start()` and the `stop()` functions are only called once during the application's lifecycle. However, if the scheduling conditions are met again, the operator can be scheduled for execution, and the `start()` method will be called again.

Fig. 12.4: The sequence of method calls in the lifecycle of a Holoscan Operator

We can override the default behavior of the operator by implementing the above methods. The following example shows how to implement a custom operator that overrides `start`, `stop` and `compute` methods.

Listing 12.12: The basic structure of a Holoscan Operator (Python)

```

1  from holoscan.core import (
2      ExecutionContext,
3      InputContext,
4      Operator,
5      OperatorSpec,
6      OutputContext,
7  )
8
9
10 class MyOp(Operator):
11
12     def __init__(self, fragment, *args, **kwargs):
13         super().__init__(fragment, *args, **kwargs)
14
15     def setup(self, spec: OperatorSpec):
16         pass
17
18     def start(self):
19         pass
20

```

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```

21     def compute(self, op_input: InputContext, op_output: OutputContext, context:
↪ ExecutionContext):
22         pass
23
24     def stop(self):
25         pass

```

setup method vs initialize vs __init__

The `setup` method aims to get the “operator’s spec” by providing `OperatorSpec` object as a spec param. When `__init__` is called, it calls C++’s `Operator::spec` method (and also sets `self.spec` class member), and calls `setup` method so that `Operator`’s `spec` property holds the operator’s specification. (See the [source code](#) for more details.)

Since the `setup` method can be called multiple times with other `OperatorSpec` object (e.g., to enumerate the operator’s description), in the `setup` method, a user shouldn’t initialize something in the `Operator` object. Such initialization needs to be done in `initialize` method. The `__init__` method is for creating the `Operator` object and it can be used for initializing the operator object itself by passing miscellaneous arguments. Still, it doesn’t ‘initialize’ the corresponding GXF entity object.

Creating a custom operator (Python)

To create a custom operator in Python it is necessary to create a subclass of `holoscan.core.Operator`. A simple example of an operator that takes a time-varying 1D input array named “signal” and applies convolution with a boxcar (i.e. `rect`) kernel.

For simplicity, this operator assumes that the “signal” that will be received on the input is already a `numpy.ndarray` or is something that can be cast to one via `(np.asarray)`. We will see more details in a later section on how we can interoperate with various tensor classes, including the GXF Tensor objects used by some of the C++-based operators.

Code Snippet: [examples/numpy_native/convolve.py](#)

Listing 12.13: `examples/numpy_native/convolve.py`

```

16 import os
17
18 from holoscan.conditions import CountCondition
19 from holoscan.core import Application, Operator, OperatorSpec
20 from holoscan.logger import LogLevel, set_log_level
21
22 import numpy as np
23
24
25 class SignalGeneratorOp(Operator):
26     """Generate a time-varying impulse.
27
28     Transmits an array of zeros with a single non-zero entry of a
29     specified `height`. The position of the non-zero entry shifts
30     to the right (in a periodic fashion) each time `compute` is
31     called.
32
33     Parameters

```

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```

34 -----
35 fragment : holoscan.core.Fragment
36 The Fragment (or Application) the operator belongs to.
37 height : number
38 The height of the signal impulse.
39 size : number
40 The total number of samples in the generated 1d signal.
41 dtype : numpy.dtype or str
42 The data type of the generated signal.
43 """
44
45 def __init__(self, fragment, *args, height=1, size=10, dtype=np.int32, **kwargs):
46     self.count = 0
47     self.height = height
48     self.dtype = dtype
49     self.size = size
50     super().__init__(fragment, *args, **kwargs)
51
52 def setup(self, spec: OperatorSpec):
53     spec.output("signal")
54
55 def compute(self, op_input, op_output, context):
56
57     # single sample wide impulse at a time-varying position
58     signal = np.zeros((self.size,), dtype=self.dtype)
59     signal[self.count % signal.size] = self.height
60     self.count += 1
61
62     op_output.emit(signal, "signal")
63
64
65 class ConvolveOp(Operator):
66     """Apply convolution to a tensor.
67
68     Convolves an input signal with a "boxcar" (i.e. "rect") kernel.
69
70     Parameters
71     -----
72     fragment : holoscan.core.Fragment
73     The Fragment (or Application) the operator belongs to.
74     width : number
75     The width of the boxcar kernel used in the convolution.
76     unit_area : bool, optional
77     Whether or not to normalize the convolution kernel to unit area.
78     If False, all samples have implitude one and the dtype of the
79     kernel will match that of the signal. When True the sum over
80     the kernel is one and a 32-bit floating point data type is used
81     for the kernel.
82     """
83
84     def __init__(self, fragment, *args, width=4, unit_area=False, **kwargs):
85         self.count = 0

```

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```

86     self.width = width
87     self.unit_area = unit_area
88     super().__init__(fragment, *args, **kwargs)
89
90     def setup(self, spec: OperatorSpec):
91         spec.input("signal_in")
92         spec.output("signal_out")
93
94     def compute(self, op_input, op_output, context):
95
96         signal = op_input.receive("signal_in")
97         assert isinstance(signal, np.ndarray)
98
99         if self.unit_area:
100             kernel = np.full((self.width,), 1/self.width, dtype=np.float32)
101         else:
102             kernel = np.ones((self.width,), dtype=signal.dtype)
103
104         convolved = np.convolve(signal, kernel, mode='same')
105
106         op_output.emit(convolved, "signal_out")
107
108
109 class PrintSignalOp(Operator):
110     """Print the received signal to the terminal."""
111
112     def setup(self, spec: OperatorSpec):
113         spec.input("signal")
114
115     def compute(self, op_input, op_output, context):
116         signal = op_input.receive("signal")
117         print(signal)
118
119
120 class ConvolveApp(Application):
121     """Minimal signal processing application.
122
123     Generates a time-varying impulse, convolves it with a boxcar kernel, and
124     prints the result to the terminal.
125
126     A `CountCondition` is applied to the generate to terminate execution
127     after a specific number of steps.
128     """
129
130     def compose(self):
131         signal_generator = SignalGeneratorOp(
132             self,
133             CountCondition(self, count=24),
134             name="generator",
135             **self.kwargs("generator"),
136         )
137         convolver = ConvolveOp(self, name="conv", **self.kwargs("convolve"))

```

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```

138     printer = PrintSignalOp(self, name="printer")
139     self.add_flow(signal_generator, convolver)
140     self.add_flow(convolver, printer)
141
142
143 def main(config_file):
144     app = ConvolveApp()
145     # if the --config command line argument was provided, it will override this config_
146     ↪ file`
147     app.config(config_file)
148     app.run()
149
150 if __name__ == "__main__":
151     config_file = os.path.join(os.path.dirname(__file__), 'convolve.yaml')
152     main(config_file=config_file)

```

Code Snippet: `examples/numpy_native/convolve.yaml`

Listing 12.14: `examples/numpy_native/convolve.yaml`

```

17 signal_generator:
18   height: 1
19   size: 20
20   dtype: int32
21
22 convolve:
23   width: 4
24   unit_area: false

```

In this application, three native Python operators are created: `SignalGeneratorOp`, `ConvolveOp` and `PrintSignalOp`. The `SignalGeneratorOp` generates a synthetic signal such as `[0, 0, 1, 0, 0, 0]` where the position of the non-zero entry varies each time it is called. `ConvolveOp` performs a 1D convolution with a boxcar (i.e. rect) function of a specified width. `PrintSignalOp` just prints the received signal to the terminal.

As covered in more detail below, the inputs to each operator are specified in the `setup()` method of the operator. Then inputs are received within the `compute` method via `op_input.receive()` and outputs are emitted via `op_output.emit()`.

Note that for native Python operators as defined here, any Python object can be emitted or received. When transmitting between operators, a shared pointer to the object is transmitted rather than a copy. In some cases, such as sending the same tensor to more than one downstream operator, it may be necessary to avoid in-place operations on the tensor in order to avoid any potential race conditions between operators.

Specifying operator parameters (Python)

In the example `SignalGeneratorOp` operator above, we added three keyword arguments in the operator's `__init__` method, used inside the `compose()` method of the operator to adjust its behavior:

```
def __init__(self, fragment, *args, width=4, unit_area=False, **kwargs):
    # Internal counter for the time-dependent signal generation
    self.count = 0

    # Parameters
    self.width = width
    self.unit_area = unit_area

    # To forward remaining arguments to any underlying C++ Operator class
    super().__init__(fragment, *args, **kwargs)
```

Note: As an alternative closer to C++, these parameters can be added through the `OperatorSpec` attribute of the operator in its `setup()` method, where an associated string key must be provided as well as a default value:

```
def setup(self, spec: OperatorSpec):
    spec.param("width", 4)
    spec.param("unit_area", False)
```

Other kwargs properties can also be passed to `spec.param` such as `headline`, `description` (used by GXF applications), or `kind` (used when *Receiving any number of inputs (Python)*).

Note: Native operator parameters added via either of these methods must **not** have a name that overlaps with any of the existing attribute or method names of the base `Operator` class.

See the [Configuring operator parameters](#) section to learn how an application can set these parameters.

Specifying operator inputs and outputs (Python)

To configure the input(s) and output(s) of Python native operators, call the `spec.input()` and `spec.output()` methods within the `setup()` method of the operator.

The `spec.input()` and `spec.output()` methods should be called once for each input and output to be added. The `holoscan.core.OperatorSpec` object and the `setup()` method will be initialized and called automatically by the `Application` class when its `run()` method is called.

These methods (`spec.input()` and `spec.output()`) return an `IOSpec` object that can be used to configure the input/output port.

By default, the `holoscan.conditions.MessageAvailableCondition` and `holoscan.conditions.DownstreamMessageAffordableCondition` conditions are applied (with a `min_size` of 1) to the input/output ports. This means that the operator's `compute()` method will not be invoked until a message is available on the input port and the downstream operator's input port (queue) has enough capacity to receive the message.

```
def setup(self, spec: OperatorSpec):
    spec.input("in")
    # Above statement is equivalent to:
```

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```
# spec.input("in")
#     .condition(ConditionType.MESSAGE_AVAILABLE, min_size = 1)
spec.output("out")
# Above statement is equivalent to:
# spec.output("out")
#     .condition(ConditionType.DOWNSTREAM_MESSAGE_AFFORDABLE, min_size = 1)
```

In the above example, the `spec.input()` method is used to configure the input port to have the `holoscan.conditions.MessageAvailableCondition` with a minimum size of 1. This means that the operator's `compute()` method will not be invoked until a message is available on the input port of the operator. Similarly, the `spec.output()` method is used to configure the output port to have a `holoscan.conditions.DownstreamMessageAffordableCondition` with a minimum size of 1. This means that the operator's `compute()` method will not be invoked until the downstream operator's input port has enough capacity to receive the message.

If you want to change this behavior, use the `IOSpec.condition()` method to configure the conditions. For example, to configure the input and output ports to have no conditions, you can use the following code:

```
from holoscan.core import ConditionType, OperatorSpec
# ...
def setup(self, spec: OperatorSpec):
    spec.input("in").condition(ConditionType.NONE)
    spec.output("out").condition(ConditionType.NONE)
```

The example code in the `setup()` method configures the input port to have no conditions, which means that the `compute()` method will be called as soon as the operator is ready to compute. Since there is no guarantee that the input port will have a message available, the `compute()` method should check if there is a message available on the input port before attempting to read it.

The `receive()` method of the `InputContext` object can be used to access different types of input data within the `compute()` method of your operator class. This method takes the name of the input port as an argument (which can be omitted if your operator has a single input port).

For standard Python objects, `receive()` will directly return the Python object for input of the specified name.

The Holoscan SDK also provides built-in data types called **Domain Objects**, defined in the `include/holoscan/core/domain` directory. For example, the `Tensor` is a Domain Object class that is used to represent a multi-dimensional array of data, which can be used directly by `OperatorSpec`, `InputContext`, and `OutputContext`.

Tip: This `holoscan.core.Tensor` class supports both `DLPack` and NumPy's array interface (`__array_interface__` and `__cuda_array_interface__`) so that it can be used with other Python libraries such as `CuPy`, `PyTorch`, `JAX`, `TensorFlow`, and `Numba`. See the [interoperability section](#) for more details.

In both cases, it will return `None` if there is no message available on the input port:

```
# ...
def compute(self, op_input, op_output, context):
    msg = op_input.receive("in")
    if msg:
        # Do something with msg
```

Receiving any number of inputs (Python)

Instead of assigning a specific number of input ports, it may be desired to have the ability to receive any number of objects on a port in certain situations. This can be done by calling `spec.param(port_name, kind='receivers')` as done for `PingRxOp` in the native operator ping example located at `examples/native_operator/python/ping.py`.

Code Snippet: `examples/native_operator/python/ping.py`

Listing 12.15: `examples/native_operator/python/ping.py`

```

124 class PingRxOp(Operator):
125     """Simple receiver operator.
126
127     This operator has:
128         input: "receivers"
129
130     This is an example of a native operator that can dynamically have any
131     number of inputs connected to is "receivers" port.
132     """
133
134     def __init__(self, fragment, *args, **kwargs):
135         self.count = 1
136         # Need to call the base class constructor last
137         super().__init__(fragment, *args, **kwargs)
138
139     def setup(self, spec: OperatorSpec):
140         spec.param("receivers", kind="receivers")
141
142     def compute(self, op_input, op_output, context):
143         values = op_input.receive("receivers")
144         print(f"Rx message received (count: {self.count}, size: {len(values)})")
145         self.count += 1
146         print(f"Rx message value1: {values[0].data}")
147         print(f"Rx message value2: {values[1].data}")

```

and in the `compose` method of the application, two parameters are connected to this “receivers” port:

```
self.add_flow(mx, rx, {("out1", "receivers"), ("out2", "receivers")})
```

This line connects both the `out1` and `out2` ports of operator `mx` to the `receivers` port of operator `rx`.

Here, values as returned by `op_input.receive("receivers")` will be a tuple of python objects.

12.2.2 Python wrapping of a C++ operator

Note: While we provide some utilities to simplify part of the process, this section is designed for advanced developers, since the wrapping of the C++ class using `pybind11` is mostly manual and can vary greatly between each operator.

For convenience while maintaining highest performance, *operators written in C++* can be wrapped in Python. In the Holoscan SDK, we’ve used `pybind11` to wrap all the built-in operators in `python/holoscan/operators`. We’ll highlight the main components below:

Trampoline classes for handling Python kwargs

In a C++ file (`my_op_pybind.cpp` in our skeleton code below), create a subclass of the C++ `Operator` class to wrap. In the subclass, define a new constructor which takes a `Fragment`, an explicit list of parameters with potential default values (`argA`, `argB` below...), and an operator name to fully initialize the operator similar to what is done in `Fragment::make_operator`:

Listing 12.16: `my_op_python/my_op_pybind.cpp`

```
#include <holoscan/core/fragment.hpp>
#include <holoscan/core/operator.hpp>
#include <holoscan/core/operator_spec.hpp>

#include "my_op.hpp"

class PyMyOp : public MyOp {
public:
    using MyOp::MyOp;

    PyMyOp(
        Fragment* fragment,
        TypeA argA, TypeB argB = 0, ...,
        const std::string& name = "my_op"
    ) : MyOp(ArgList{
        Arg{"argA", argA},
        Arg{"argB", argB},
        ...
    }) {
        # If you have arguments you can't pass directly to the `MyOp` constructor as an `Arg`,
        ↪do
        # the conversion and pass the result to `this->add_arg` before setting up the spec
        ↪below.
        name_ = name;
        fragment_ = fragment;
        spec_ = std::make_shared<OperatorSpec>(fragment);
        setup(*spec_.get());
    }
}
```

Example: Look at the implementation of `PyLSTMTensorRTInferenceOp` on [HoloHub](#) for a specific example, or any of the `Py*Op` classes used for the SDK built-in operators [here](#). In the latter, you can find examples of `add_arg` used for less straightforward arguments.

Documentation strings

Prepare documentation strings (`const char*`) for your python class and its parameters, which we'll use in the next step.

Note: Below we use a `PYDOC` macro defined in the [SDK](#) and available in [HoloHub](#) as a utility to remove leading spaces. In this skeleton example, the documentation code is located in a header file named `my_op_pybind_docs.hpp`, under a custom `doc::MyOp` namespace. None of this is required, you just need to make the strings available in some way for the next section.

Listing 12.17: my_op_python/my_op_pybind_docs.hpp

```
#include "../macros.hpp"

namespace doc::MyOp {

    PYDOC(cls, R"doc(
My operator.
)doc")

    PYDOC(constructor, R"doc(
Create the operator.

Parameters
-----
fragment : holoscan.core.Fragment
    The fragment that the operator belongs to.
argA : TypeA
    argA description
argB : TypeB, optional
    argB description
name : str, optional
    The name of the operator.
)doc")

    PYDOC(initialize, R"doc(
Initialize the operator.

This method is called only once when the operator is created for the first time,
and uses a light-weight initialization.
)doc")

    PYDOC(setup, R"doc(
Define the operator specification.

Parameters
-----
spec : holoscan.core.OperatorSpec
    The operator specification.
)doc")

}
```

Examples: Continuing with the LSTMTensorRTInferenceOp example on HoloHub, the documentation strings are defined in `lstm_tensor_rt_inference_pydoc.hpp`. The documentation strings for the SDK built-in operators are located in `operators_pydoc.hpp`.

Writing glue code

In the same C++ file as the first section, call `py::class_` within `PYBIND11_MODULE` to define your operator python class.

Note:

- If you are implementing the python wrapping in Holohub, the `<module_name>` passed to `PYBIND11_MODULE` **must** match `<CPP_CMAKE_TARGET>` (covered in more details in the next section), in this case, `_my_op`.
- If you are implementing the python wrapping in a standalone CMake project, the `<module_name>` passed to `PYBIND11_MODULE` **must** match the name of the module passed to the `pybind11::add_module` CMake function.

Listing 12.18: `my_op_python/my_op_pybind.cpp` (continued)

```
#include <pybind11/pybind11.h>

#include "my_op_pybind_docs.hpp"

using pybind11::literals::operator""_a;
namespace py = pybind11;

#define STRINGIFY(x) #x
#define MACRO_STRINGIFY(x) STRINGIFY(x)

// See notes above, value of `<module_name>` is important
PYBIND11_MODULE(<module_name>, m) {
    m.doc() = R"pbdoc(
        My Module Python Bindings
        -----
        .. currentmodule:: <module_name>
        .. autosummary::
           :toctree: _generate
           add
           subtract
    )pbdoc";

    #ifndef VERSION_INFO
        m.attr("__version__") = MACRO_STRINGIFY(VERSION_INFO);
    #else
        m.attr("__version__") = "dev";
    #endif

    py::class_<MyOp, PyMyOp, Operator, std::shared_ptr<MyOp>>(
        m, "MyOp", doc::MyOp::doc_cls)
        .def(py::init<Fragment*, TypeA, TypeB, ..., const std::string&>(),
            "fragment"_a,
            "argA"_a,
            "argB"_a = 0,
            ...,
            "name"_a = "my_op",
            doc::MyOp::doc_constructor)
        .def("initialize",
```

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```
&MyOp::initialize,  
doc::MyOp::doc_initialize)  
.def("setup",  
    &MyOp::setup,  
    "spec"_a,  
    doc::MyOp::doc_setup);  
}
```

Examples: Like the trampoline class, the `PYBIND11_MODULE` implementation of the `LSTMTensorRTInferenceOp` example on HoloHub is located in `lstm_tensor_rt_inference.cpp`. For the SDK built-in operators, their class bindings are all implemented within a single `PYBIND11_MODULE` in `operators.cpp`.

Configuring with CMake

We use CMake to configure `pybind11` and build the bindings for the C++ operator you wish to wrap. There are two approaches detailed below, one for HoloHub (recommended), one for standalone CMake projects.

Tip: To have your bindings built, ensure the CMake code below is executed as part of a CMake project which already defines the C++ operator as a CMake target, either built in your project (with `add_library`) or imported (with `find_package` or `find_library`).

In HoloHub

We provide a CMake utility function named `pybind11_add_holohub_module` in HoloHub to facilitate configuring and building your python bindings.

In our skeleton code below, a top-level `CMakeLists.txt` which already defined the `my_op` target for the C++ operator would need to do `add_subdirectory(my_op_python)` to include the following `CMakeLists.txt`. The `pybind11_add_holohub_module` lists that C++ operator target, the C++ class to wrap, and the path to the C++ binding source code we implemented above. Note how the `<module_name>` from the previous section would need to match `<CPP_CMAKE_TARGET>` i.e. `_my_op`.

Listing 12.19: my_op_python/CMakeLists.txt

```
include(pybind11_add_holohub_module)
pybind11_add_holohub_module(
    CPP_CMAKE_TARGET my_op
    CLASS_NAME "MyOp"
    SOURCES my_op_pybind.cpp
)
```

Example: the cmake configuration for the LSTMTensorRTInferenceOp python bindings on HoloHub can be found [here](#). This directory is reachable thanks to the `add_subdirectory(python)` in the CMakeLists.txt one folder above, but that's an arbitrary opinionated location and not a required directory structure.

Standalone CMake

Follow the [pybind11 documentation](#) to configure your CMake project to use pybind11. Then, use the `pybind11_add_module` function with the cpp files containing the code above, and link against `holoscan::core` and the library that exposes your C++ operator to wrap.

Listing 12.20: my_op_python/CMakeLists.txt

```
pybind11_add_module(my_python_module my_op_pybind.cpp)
target_link_libraries(my_python_module
    PRIVATE holoscan::core
    PUBLIC my_op
)
```

Example: in the SDK, this is done [here](#).

Importing the class in Python

In HoloHub

When building your project, two files will be generated inside `<build_or_install_dir>/python/lib/holohub/my_op`:

1. the shared library for your bindings (`_my_op.cpython-<pyversion>-<arch>-linux-gnu.so`)
2. an `__init__.py` file that makes the necessary imports to expose this in python

Assuming you have `export PYTHONPATH=<build_or_install_dir>/python/lib/`, you should then be able to create an application in HoloHub that imports your class via:

```
from holohub.my_op import MyOp
```

Example: LSTMTensorRTInferenceOp is imported in the Endoscopy Tool Tracking application on HoloHub [here](#).

Standalone CMake

When building your project, a shared library file holding the python bindings and named `my_python_module.cpython-<pyversion>-<arch>-linux-gnu.so` will be generated inside `<build_or_install_dir>/my_op_python` (configurable with `OUTPUT_NAME` and `LIBRARY_OUTPUT_DIRECTORY` respectively in CMake).

From there, you can import it in python via:

```
import holoscan.core
import holoscan.gxf # if your c++ operator uses gxf extensions

from <build_or_install_dir>.my_op_python import MyOp
```

Tip: To imitate HoloHub's behavior, you can also place that file alongside the `.so` file, name it `__init__.py`, and replace `<build_or_install_dir>` by `..`. It can then be imported as a python module, assuming `<build_or_install_dir>` is a module under the `PYTHONPATH` environment variable.

12.2.3 Interoperability between wrapped and native Python operators

As described in the *Interoperability between GXF and native C++ operators* section, `holoscan::Tensor` objects can be passed to GXF operators using a `holoscan::TensorMap` message that holds the tensor(s). In Python, this is done by sending dict type objects that have tensor names as the keys and `holoscan` Tensor or array-like objects as the values. Similarly, when a wrapped C++ operator that transmits a single `holoscan::Tensor` is connected to the input port of a Python native operator, calling `op_input.receive()` on that port will return a Python dict containing a single item. That item's key is the tensor name and its value is the corresponding `holoscan.core.Tensor`.

Consider the following example, where `VideoStreamReplayerOp` and `HolovizOp` are Python wrapped C++ operators, and where `ImageProcessingOp` is a Python native operator:

Fig. 12.5: The tensor interoperability between Python native operator and C++-based Python GXF operator

The following code shows how to implement `ImageProcessingOp`'s `compute()` method as a Python native operator communicating with C++ operators:

Listing 12.21: examples/tensor_interop/python/tensor_interop.py

```
62 def compute(self, op_input, op_output, context):
63     # in_message is of dict
64     in_message = op_input.receive("input_tensor")
65
66     # smooth along first two axes, but not the color channels
67     sigma = (self.sigma, self.sigma, 0)
68
69     # out_message is of dict
70     out_message = dict()
71
72     for key, value in in_message.items():
73         print(f"message received (count: {self.count})")
74         self.count += 1
75
76     cp_array = cp.asarray(value)
```

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```

77     # process cp_array
78     cp_array = ndi.gaussian_filter(cp_array, sigma)
79
80
81     out_message[key] = cp_array
82
83     op_output.emit(out_message, "output_tensor")

```

- The `op_input.receive()` method call returns a dict object.
- The `holoscan.core.Tensor` object is converted to a CuPy array by using `cupy.asarray()` method call.
- The CuPy array is used as an input to the `ndi.gaussian_filter()` function call with a parameter `sigma`. The result of the `ndi.gaussian_filter()` function call is a CuPy array.
- Finally, a new dict object is created, `out_message`, to be sent to the next operator with `op_output.emit()`. The CuPy array, `cp_array`, is added to it where the key is the tensor name. CuPy arrays do not have to explicitly be converted to a `holoscan.core.Tensor` object first since they implement a `DLPack` (and `__cuda__array_interface__`) interface.

Note: A complete example of the Python native operator that supports interoperability with Python wrapped C++ operators is available in the [examples/tensor_interop/python](#) directory.

You can add multiple tensors to a single dict object, as in the example below:

Operator sending a message:

```

out_message = {
    "video": output_array,
    "labels": labels,
    "bbox_coords": bbox_coords,
}

# emit the tensors
op_output.emit(out_message, "outputs")

```

Operator receiving the message, assuming the `outputs` port above is connected to the `inputs` port below with `add_flow()` has the corresponding tensors:

```

in_message = op_input.receive("inputs")
# Tensors and tensor names
video_tensor = in_message["video"]
labels_tensor = in_message["labels"]
bbox_coords_tensor = in_message["bbox_coords"]

```

Note: Some existing operators allow *configuring* the name of the tensors they send/receive. An example is the `tensors` parameter of `HolovizOp`, where the name for each tensor maps to the names of the tensors in the Entity (see the `holoviz` entry in [apps/endoscopy_tool_tracking/python/endoscopy_tool_tracking.yaml](#)).

A complete example of a Python native operator that emits multiple tensors to a downstream C++ operator is available in the [examples/holoviz/python](#) directory.

There is a special serialization code for tensor types for emit/receive of tensor objects over a UCX connection that avoids copying the tensor data to an intermediate buffer. For distributed apps, we cannot just send the Python object as

we do between operators in a single fragment app, but instead we need to cast it to `holoscan:Tensor` to use a special zero-copy code path. However, we also transmit a header indicating if the type was originally some other array-like object and attempt to return the same type again on the other side so that the behavior remains more similar to the non-distributed case.

Transmitted object	Received Object
<code>holoscan.Tensor</code>	<code>holoscan.Tensor</code>
dict of array-like	dict of <code>holoscan.Tensor</code>
host array-like object (with <code>__array_interface__</code>)	<code>numpy.ndarray</code>
device array-like object (with <code>__cuda_array_interface__</code>)	<code>cupy.ndarray</code>

This avoids NumPy or CuPy arrays being serialized to a string via cloudpickle so that they can efficiently be transmitted and the same type is returned again on the opposite side. Worth mentioning is that ,if the type emitted was e.g. a PyTorch host/device tensor on emit, the received value will be a numpy/cupy array since ANY object implementing the interfaces returns those types.

LOGGING

13.1 Overview

The Holoscan SDK uses the Logger module to convey messages to the user. These messages are categorized into different severity levels (see below) to inform users of the severity of a message and as a way to control the number and verbosity of messages that are printed to the terminal. There are two settings which can be used for this purpose:

- Logger level
- Logger format

13.1.1 Logger Level

Messages that are logged using the Logger module have a severity level, e.g., messages can be categorized as INFO, WARN, ERROR, etc.

The default logging level for an application is to print out messages with severity INFO or above, i.e., messages that are categorized as INFO, WARN, ERROR, and CRITICAL. You can modify this default by calling `set_log_level()` (C++/Python) in the application code to override the SDK default logging level and give it one of the following log levels.

- TRACE
- DEBUG
- INFO
- WARN
- ERROR
- CRITICAL
- OFF

CPP

```
1 #include <holoscan/holoscan.hpp>
2
3 int main() {
4     holoscan::set_log_level(holoscan::LogLevel::WARN);
5     // ...
6     return 0;
7 }
```

PYTHON

```
1 from holoscan.logger import set_log_level
2
3 def main():
4     set_log_level(LogLevel::WARN)
5     # ...
6
7 if __name__ == "__main__":
8     main()
```

Additionally, at runtime, the user can set the HOLOSCAN_LOG_LEVEL environment variable to one of the values listed above. This provides users with the flexibility to enable printing of diagnostic information for debugging purposes when an issue occurs.

```
export HOLOSCAN_LOG_LEVEL=TRACE
```

Note: Under the hood, Holoscan SDK uses GXF to execute the computation graph. By default, this GXF layer uses the same logging level as Holoscan SDK. If it is desired to override the logging level of this executor independently of the Holoscan SDK logging level, environment variable HOLOSCAN_EXECUTOR_LOG_LEVEL can be used. It supports the same levels as HOLOSCAN_LOG_LEVEL.

Note: For distributed applications, it can sometimes be useful to also enable additional logging for the UCX library used to transmit data between fragments. This can be done by setting the UCX environment variable UCX_LOG_LEVEL to one of: fatal, error, warn, info, debug, trace, req, data, async, func, poll. These have the behavior as described here: [UCX log levels](#).

Precedence

If the HOLOSCAN_LOG_LEVEL environment variable is set, this setting is used to set the logging level. If the environment variable is not set, then the application setting is used if available. If not, the SDK default setting of INFO is used as the logging level.

13.2 Logger Format

When a message is printed out, the default message format shows the message severity level, filename:linenumber, and the message to be printed.

For example:

```
[info] [ping_multi_port.cpp:114] Rx message value1: 51
[info] [ping_multi_port.cpp:115] Rx message value2: 54
```

You can modify this default by calling `set_log_pattern()` (C++/Python) in the application code to override the SDK default logging format.

The pattern string can be one of the following pre-defined values

- **SHORT** : prints message severity level, and message
- **DEFAULT** : prints message severity level, filename:linenumber, and message
- **LONG** : prints timestamp, application, message severity level, filename:linenumber, and message
- **FULL** : prints timestamp, thread id, application, message severity level, filename:linenumber, and message

CPP

```
1 #include <holoscan/holoscan.hpp>
2
3 int main() {
4     holoscan::set_log_pattern("SHORT")
5     // ...
6     return 0;
7 }
```

PYTHON

```
1 from holoscan.logger import set_log_pattern
2
3 def main():
4     set_log_pattern("SHORT")
5     # ...
6
7 if __name__ == "__main__":
8     main()
```

With this logger format, the above application would display messages with the following format:

```
[info] Rx message value1: 51
[info] Rx message value2: 54
```

Alternatively, the pattern string can be a custom pattern to customize the logger format. Using this string pattern

```
"[%Y-%m-%d %H:%M:%S.%e] [%n] [%^%l%$] [%s:%#] %v";
```

would display messages with the following format:

```
[2023-06-27 14:22:36.073] [holoscan] [info] [ping_multi_port.cpp:114] Rx message value1:↵  
↵51  
[2023-06-27 14:22:36.073] [holoscan] [info] [ping_multi_port.cpp:115] Rx message value2:↵  
↵54
```

For more details on custom formatting and details of each flag, please see the [spdlog wiki page](#).

Additionally, at runtime, the user can also set the `HOLOSCAN_LOG_FORMAT` environment variable to modify the logger format. The accepted string pattern is the same as the string pattern for the `set_log_pattern()` api mentioned above.

Note: If the `HOLOSCAN_LOG_FORMAT` environment variable is set, this setting is used to set the logger format. If the environment variable is not set, then the application setting is used if available. If not, the SDK default message format is used.

13.3 Calling the Logger in Your Application

The **C++ API** uses the `HOLOSCAN_LOG_XXX()` macros to log messages in the application. These macros use the [fmtlib format string syntax](#) for their format strings.

Note: Holoscan automatically checks `HOLOSCAN_LOG_LEVEL` environment variable and sets the log level when the Application class instance is created. However, those log level settings are for Holoscan core or C++ operator (C++)'s logging message (such as `HOLOSCAN_LOG_INFO` macro), not for Python's logging. Users of the **Python API** should use the built-in [logging](#) module to log messages. The user needs to configure the logger before use (`logging.basicConfig(level=logging.INFO)`):

```
>>> import logging  
>>> logger = logging.getLogger("main")  
>>> logger.info('hello')  
>>> logging.basicConfig(level=logging.INFO)  
>>> logger.info('hello')  
INFO:main:hello
```

DEBUGGING

14.1 Overview

The Holoscan SDK is designed to streamline the debugging process for developers working on advanced applications. This comprehensive guide covers the SDK's debugging capabilities, with a focus on Visual Studio Code integration, and provides detailed instructions for various debugging scenarios.

It includes methods for debugging both the C++ and Python components of applications, utilizing tools like GDB, UCX, and Python-specific debuggers.

14.2 Visual Studio Code Integration

14.2.1 VSCode Dev Container

The [Holoscan SDK](#) can be effectively developed using Visual Studio Code, leveraging the capabilities of a development container. This container, defined in the `.devcontainer` folder, is pre-configured with all the necessary tools and libraries, as detailed in [Visual Studio Code's documentation on development containers](#).

14.2.2 Launching VSCode with the Holoscan SDK

- **Local Development:** Use the `./run vscode` command to launch Visual Studio Code in a development container.
- **Remote Development:** For attaching to an existing dev container from a remote machine, use `./run vscode_remote`. Additional instructions can be accessed via `./run vscode_remote -h`.

Upon launching Visual Studio Code, the development container will automatically be built. This process also involves the installation of recommended extensions and the configuration of CMake.

14.2.3 Configuring CMake

For manual adjustments to the CMake configuration:

1. Open the command palette in VSCode (Ctrl + Shift + P).
2. Execute the CMake: Configure command.

14.2.4 Building the Source Code

To build the source code within the development container:

- Either press Ctrl + Shift + B.
- Or use the command palette (Ctrl + Shift + P) and run Tasks: Run Build Task.

14.2.5 Debugging Workflow

For debugging the source code:

1. Open the Run and Debug view in VSCode (Ctrl + Shift + D).
2. Select an appropriate debug configuration from the dropdown.
3. Press F5 to start the debugging session.

The launch configurations are defined in `.vscode/launch.json`([link](#)).

Please refer to [Visual Studio Code's documentation on debugging](#) for more information.

14.2.6 Integrated Debugging for C++ and Python in Holoscan SDK

The Holoscan SDK facilitates seamless debugging of both C++ and Python components within your applications. This is achieved through the integration of the Python C++ Debugger extension in Visual Studio Code, which can be found [here](#).

This powerful extension is specifically designed to enable effective debugging of Python operators that are executed within the C++ runtime environment. Additionally, it provides robust capabilities for debugging C++ operators and various SDK components that are executed via the Python interpreter.

To utilize this feature, debug configurations for Python C++ Debug should be defined within the `.vscode/launch.json` file, available [here](#).

Here's how to get started:

1. Open a Python file within your project, such as `examples/ping_vector/python/ping_vector.py`.
2. In the Run and Debug view of Visual Studio Code, select the Python C++ Debug debug configuration.
3. Set the necessary breakpoints in both your Python and C++ code.
4. Initiate the debugging session by pressing F5.

Upon starting the session, two separate debug terminals will be launched - one for Python and another for C++. In the C++ terminal, you will encounter a prompt regarding superuser access:

```
Superuser access is required to attach to a process. Attaching as superuser can
↪ potentially harm your computer. Do you want to continue? [y/N]
```

Respond with `y` to proceed.

Following this, the Python application initiates, and the C++ debugger attaches to the Python process. This setup allows you to simultaneously debug both Python and C++ code. The `CALL STACK` tab in the `Run` and `Debug` view will display `Python: Debug Current File` and `(gdb) Attach`, indicating active debugging sessions for both languages.

By leveraging this integrated debugging approach, developers can efficiently troubleshoot and enhance applications that utilize both Python and C++ components within the Holoscan SDK.

14.3 Debugging an Application Crash

This section outlines the procedures for debugging an application crash.

14.3.1 Core Dump Analysis

In the event of an application crash, you might encounter messages like `Segmentation fault (core dumped)` or `Aborted (core dumped)`. These indicate the generation of a core dump file, which captures the application's memory state at the time of the crash. This file can be utilized for debugging purposes.

Enabling coredump

There are instances where core dumps might be disabled or not generated despite an application crash.

To activate core dumps, it's necessary to configure the `ulimit` setting, which determines the maximum size of core dump files. By default, `ulimit` is set to 0, effectively disabling core dumps. Setting `ulimit` to unlimited enables the generation of core dumps.

```
ulimit -c unlimited
```

Additionally, configuring the `core_pattern` value is required. This value specifies the naming convention for the core dump file. To view the current `core_pattern` setting, execute the following command:

```
cat /proc/sys/kernel/core_pattern
# or
sysctl kernel.core_pattern
```

To modify the `core_pattern` value, execute the following command:

```
echo "coredump_%e_%p" | sudo tee /proc/sys/kernel/core_pattern
# or
sudo sysctl -w kernel.core_pattern=coredump_%e_%p
```

where in this case we have requested both the executable name (`%e`) and the process id (`%p`) be present in the generated file's name. The various options available are documented in the [core documentation](#).

If you encounter errors like `tee: /proc/sys/kernel/core_pattern: Read-only file system` or `sysctl: setting key "kernel.core_pattern", ignoring: Read-only file system` within a Docker container, it's advisable to set the `kernel.core_pattern` parameter on the host system instead of within the container.

As `kernel.core_pattern` is a system-wide kernel parameter, modifying it on the host should impact all containers. This method, however, necessitates appropriate permissions on the host machine.

Furthermore, when launching a Docker container using `docker run`, it's often essential to include the `--cap-add=SYS_PTRACE` option to enable core dump creation inside the container. Core dump generation typically requires elevated privileges, which are not automatically available to Docker containers.

Using GDB to Debug a coredump File

After the core dump file is generated, you can utilize GDB to debug the core dump file.

Consider a scenario where a segmentation fault is intentionally induced at line 29 in `examples/ping_simple/cpp/ping_simple.cpp` by adding the line `*(int*)0 = 0;` to trigger the fault.

```
--- a/examples/ping_simple/cpp/ping_simple.cpp
+++ b/examples/ping_simple/cpp/ping_simple.cpp
@@ -19,7 +19,6 @@
#include <holoscan/operators/ping_tx/ping_tx.hpp>
#include <holoscan/operators/ping_rx/ping_rx.hpp>

-
class MyPingApp : public holoscan::Application {
public:
    void compose() override {
@@ -27,6 +26,7 @@ class MyPingApp : public holoscan::Application {
    // Define the tx and rx operators, allowing the tx operator to execute 10 times
    auto tx = make_operator<ops::PingTxOp>("tx", make_condition<CountCondition>(10));
    auto rx = make_operator<ops::PingRxOp>("rx");
+    *(int*)0 = 0;
+}
```

Upon running `./examples/ping_simple/cpp/ping_simple`, the following output is observed:

```
$ ./examples/ping_simple/cpp/ping_simple
Segmentation fault (core dumped)
```

It's apparent that the application has aborted and a core dump file has been generated.

```
$ ls coredump*
coredump_ping_simple_2160275
```

The core dump file can be debugged using GDB by executing `gdb <application> <coredump_file>`.

```
$ gdb ./examples/ping_simple/cpp/ping_simple coredump_ping_simple_2160275
GNU gdb (Ubuntu 12.1-0ubuntu1~22.04) 12.1
Copyright (C) 2022 Free Software Foundation, Inc.
License GPLv3+: GNU GPL version 3 or later <http://gnu.org/licenses/gpl.html>
This is free software: you are free to change and redistribute it.
There is NO WARRANTY, to the extent permitted by law.
Type "show copying" and "show warranty" for details.
This GDB was configured as "x86_64-linux-gnu".
Type "show configuration" for configuration details.
For bug reporting instructions, please see:
<https://www.gnu.org/software/gdb/bugs/>.
Find the GDB manual and other documentation resources online at:
    <http://www.gnu.org/software/gdb/documentation/>.

For help, type "help".
Type "apropos word" to search for commands related to "word"...
Reading symbols from ./examples/ping_simple/cpp/ping_simple...
[New LWP 2160275]
[Thread debugging using libthread_db enabled]
```

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```
Using host libthread_db library "/usr/lib/x86_64-linux-gnu/libthread_db.so.1".
Core was generated by `./examples/ping_simple/cpp/ping_simple'.
Program terminated with signal SIGSEGV, Segmentation fault.
#0  MyPingApp::compose (this=0x563bd3a3de80) at ../examples/ping_simple/cpp/ping_simple.
    ↪cpp:29
29      *(int*)0 = 0;
(gdb)
```

It is evident that the application crashed at line 29 of `examples/ping_simple/cpp/ping_simple.cpp`.

To display the backtrace, the `bt` command can be executed.

```
(gdb) bt
#0  MyPingApp::compose (this=0x563bd3a3de80) at ../examples/ping_simple/cpp/ping_simple.
    ↪cpp:29
#1  0x00007f2a76cdb5ea in holoscan::Application::compose_graph (this=0x563bd3a3de80) at .
    ↪./src/core/application.cpp:325
#2  0x00007f2a76c3d121 in holoscan::AppDriver::check_configuration (this=0x563bd3a42920)
    ↪at ../src/core/app_driver.cpp:803
#3  0x00007f2a76c384ef in holoscan::AppDriver::run (this=0x563bd3a42920) at ../src/core/
    ↪app_driver.cpp:168
#4  0x00007f2a76cda70c in holoscan::Application::run (this=0x563bd3a3de80) at ../src/
    ↪core/application.cpp:207
#5  0x0000563bd2ec4002 in main (argc=1, argv=0x7ffea82c4c28) at ../examples/ping_simple/
    ↪cpp/ping_simple.cpp:38
```

14.3.2 UCX Segmentation Fault Handler

In cases where a distributed application using the UCX library encounters a segmentation fault, you might see stack traces from UCX. This is a default configuration of the UCX library to output stack traces upon a segmentation fault. However, this behavior can be modified by setting the `UCX_HANDLE_ERRORS` environment variable:

- `UCX_HANDLE_ERRORS=bt` prints a backtrace during a segmentation fault (default setting).
- `UCX_HANDLE_ERRORS=debug` attaches a debugger if a segmentation fault occurs.
- `UCX_HANDLE_ERRORS=freeze` freezes the application on a segmentation fault.
- `UCX_HANDLE_ERRORS=freeze, bt` both freezes the application and prints a backtrace upon a segmentation fault.
- `UCX_HANDLE_ERRORS=none` disables backtrace printing during a segmentation fault.

While the default action is to print a backtrace on a segmentation fault, it may not always be helpful.

For instance, if a segmentation fault is intentionally caused at line 129 in `examples/ping_distributed/cpp/ping_distributed_ops.cpp` (by adding `*(int*)0 = 0;`), running `./examples/ping_distributed/cpp/ping_distributed` will result in the following output:

```
[holoscan:2097261:0:2097311] Caught signal 11 (Segmentation fault: address not mapped to
    ↪object at address (nil))
==== backtrace (tid:2097311) ====
 0 /opt/ucx/1.15.0/lib/libucs.so.0(ucs_handle_error+0x2e4) [0x7f18db865264]
 1 /opt/ucx/1.15.0/lib/libucs.so.0(+0x3045f) [0x7f18db86545f]
 2 /opt/ucx/1.15.0/lib/libucs.so.0(+0x30746) [0x7f18db865746]
 3 /usr/lib/x86_64-linux-gnu/libc.so.6(+0x42520) [0x7f18da9ee520]
```

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```

4  ./examples/ping_distributed/cpp/ping_distributed(+0x103d2b) [0x5651dafc7d2b]
5  /workspace/holoscan-sdk/build-debug-x86_64/lib/libholoscan_core.so.1(_
→ZN8holoscan3gxf10GXFWrapper4tickEv+0x13d) [0x7f18dcbfaafd]
6  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem11tickCodeletERKNS0_6HandleINS0_
→7CodeletEEE+0x127) [0x7f18db2cb487]
7  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem4tickElPNS0_6RouterE+0x444) [0x7f18db2cde44]
8  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem7executeElPNS0_6RouterERl+0x3e9)
→[0x7f18db2ce859]
9  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor13executeEntityEll+0x41b) [0x7f18db2cf0cb]
10 /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_serialization.so(_
→ZN6nvidia3gxf20MultiThreadScheduler20workerThreadEntranceEPNS0_10ThreadPoolEl+0x3c0)
→[0x7f18daf0cc50]
11 /usr/lib/x86_64-linux-gnu/libstdc++.so.6(+0xdc253) [0x7f18dacb0253]
12 /usr/lib/x86_64-linux-gnu/libc.so.6(+0x94ac3) [0x7f18daa40ac3]
13 /usr/lib/x86_64-linux-gnu/libc.so.6(+0x126660) [0x7f18daad2660]
=====
Segmentation fault (core dumped)

```

Although a backtrace is provided, it may not always be helpful as it often lacks source code information. To obtain detailed source code information, using a debugger is necessary.

By setting the `UCX_HANDLE_ERRORS` environment variable to `freeze,bt` and running `./examples/ping_distributed/cpp/ping_distributed`, we can observe that the thread responsible for the segmentation fault is frozen, allowing us to attach a debugger to it for further investigation.

```

$ UCX_HANDLE_ERRORS=freeze,bt ./examples/ping_distributed/cpp/ping_distributed

[holoscan:2127091:0:2127105] Caught signal 11 (Segmentation fault: address not mapped to
→object at address (nil))
==== backtrace (tid:2127105) ====
0  /opt/ucx/1.15.0/lib/libucs.so.0(ucs_handle_error+0x2e4) [0x7f9995850264]
1  /opt/ucx/1.15.0/lib/libucs.so.0(+0x3045f) [0x7f999585045f]
2  /opt/ucx/1.15.0/lib/libucs.so.0(+0x30746) [0x7f9995850746]
3  /usr/lib/x86_64-linux-gnu/libc.so.6(+0x42520) [0x7f99949ee520]
4  ./examples/ping_distributed/cpp/ping_distributed(+0x103d2b) [0x555971617fd2b]
5  /workspace/holoscan-sdk/build-debug-x86_64/lib/libholoscan_core.so.1(_
→ZN8holoscan3gxf10GXFWrapper4tickEv+0x13d) [0x7f9996bfaafd]
6  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem11tickCodeletERKNS0_6HandleINS0_
→7CodeletEEE+0x127) [0x7f99952cb487]
7  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem4tickElPNS0_6RouterE+0x444) [0x7f99952cde44]
8  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor10EntityItem7executeElPNS0_6RouterERl+0x3e9)
→[0x7f99952ce859]
9  /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so(_
→ZN6nvidia3gxf14EntityExecutor13executeEntityEll+0x41b) [0x7f99952cf0cb]
10 /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_serialization.so(_
→ZN6nvidia3gxf20MultiThreadScheduler20workerThreadEntranceEPNS0_10ThreadPoolEl+0x3c0)
→[0x7f9994f0cc50]

```

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```

11 /usr/lib/x86_64-linux-gnu/libstdc++.so.6(+0xdc253) [0x7f9994cb0253]
12 /usr/lib/x86_64-linux-gnu/libc.so.6(+0x94ac3) [0x7f9994a40ac3]
13 /usr/lib/x86_64-linux-gnu/libc.so.6(+0x126660) [0x7f9994ad2660]
=====

```

```
[holoscan:2127091:0:2127105] Process frozen, press Enter to attach a debugger...
```

It is observed that the thread responsible for the segmentation fault is 2127105 (tid:2127105). To attach a debugger to this thread, simply press Enter.

Upon attaching the debugger, a backtrace will be displayed, but it may not be from the thread that triggered the segmentation fault. To handle this, use the `info threads` command to list all threads, and the `thread <thread_id>` command to switch to the thread that caused the segmentation fault.

```

(gdb) info threads
Id      Target Id                                     Frame
* 1      Thread 0x7f9997b36000 (LWP 2127091) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  2      Thread 0x7f9992731000 (LWP 2127093) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  3      Thread 0x7f9991f30000 (LWP 2127094) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  4      Thread 0x7f999172f000 (LWP 2127095) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  5      Thread 0x7f99909ec000 (LWP 2127096) "cuda-EvtHandler" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  6      Thread 0x7f99891ff000 (LWP 2127097) "async"                0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  7      Thread 0x7f997d7cd000 (LWP 2127098) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  8      Thread 0x7f997cfcc000 (LWP 2127099) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
  9      Thread 0x7f995ffff000 (LWP 2127100) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
 10      Thread 0x7f99577fe000 (LWP 2127101) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
 11      Thread 0x7f995f3e5000 (LWP 2127103) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
 12      Thread 0x7f995ebe4000 (LWP 2127104) "ping_distribute" 0x000007f9994a96612 in __
↳ libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
 13      Thread 0x7f995e3e3000 (LWP 2127105) "ping_distribute" 0x000007f9994a9642f in __GI__
↳ __wait4 (pid=pid@entry=2127631, stat_loc=stat_loc@entry=0x7f995e3ddd3c,
↳ options=options@entry=0, usage=usage@entry=0x0) at ../sysdeps/unix/sysv/linux/wait4.
↳ c:30

```

It's evident that thread ID 13 is responsible for the segmentation fault (LWP 2127105). To investigate further, we can switch to this thread using the command `thread 13` in GDB:

```
(gdb) thread 13
```

After switching, we can employ the `bt` command to examine the backtrace of this thread.

```

(gdb) bt
#0  0x000007f9994a9642f in __GI__wait4 (pid=pid@entry=2127631, stat_loc=stat_
↳ loc@entry=0x7f995e3ddd3c, options=options@entry=0, usage=usage@entry=0x0) at
↳ ../sysdeps/unix/sysv/linux/wait4.c:30

```

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```

#1 0x00007f9994a963ab in __GI___waitpid (pid=pid@entry=2127631, stat_loc=stat_
↳loc@entry=0x7f995e3ddd3c, options=options@entry=0) at ./posix/waitpid.c:38
#2 0x00007f999584d587 in ucs_debugger_attach () at /opt/ucx/src/contrib/./src/ucs/
↳debug/debug.c:816
#3 0x00007f999585031d in ucs_error_freeze (message=0x7f999586ec53 "address not mapped_
↳to object") at /opt/ucx/src/contrib/./src/ucs/debug/debug.c:919
#4 ucs_handle_error (message=0x7f999586ec53 "address not mapped to object") at /opt/ucx/
↳src/contrib/./src/ucs/debug/debug.c:1089
#5 ucs_handle_error (message=0x7f999586ec53 "address not mapped to object") at /opt/ucx/
↳src/contrib/./src/ucs/debug/debug.c:1077
#6 0x00007f999585045f in ucs_debug_handle_error_signal (signo=signo@entry=11,
↳cause=0x7f999586ec53 "address not mapped to object", fmt=fmt@entry=0x7f999586ecf5 " at_
↳address %p") at /opt/ucx/src/contrib/./src/ucs/debug/debug.c:1038
#7 0x00007f9995850746 in ucs_error_signal_handler (signo=11, info=0x7f995e3de3f0,
↳context=<optimized out>) at /opt/ucx/src/contrib/./src/ucs/debug/debug.c:1060
#8 <signal handler called>
#9 holoscan::ops::PingTensorTxOp::compute (this=0x559716f26fa0, op_output=..., context=.
↳..) at ../examples/ping_distributed/cpp/ping_distributed_ops.cpp:129
#10 0x00007f9996bfaafd in holoscan::gxf::GXFWrapper::tick (this=0x559716f6f740) at ../
↳src/core/gxf/gxf_wrapper.cpp:66
#11 0x00007f99952cb487 in
↳nvidia::gxf::EntityExecutor::EntityItem::tickCodelet(nvidia::gxf::Handle
↳<nvidia::gxf::Codelet> const&) () from /workspace/holoscan-sdk/build-debug-x86_64/lib/
↳libgxf_core.so
#12 0x00007f99952cde44 in nvidia::gxf::EntityExecutor::EntityItem::tick(long,
↳nvidia::gxf::Router*) () from /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_
↳core.so
#13 0x00007f99952ce859 in nvidia::gxf::EntityExecutor::EntityItem::execute(long,
↳nvidia::gxf::Router*, long&) () from /workspace/holoscan-sdk/build-debug-x86_64/lib/
↳libgxf_core.so
#14 0x00007f99952cf0cb in nvidia::gxf::EntityExecutor::executeEntity(long, long) () from
↳/workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_core.so
#15 0x00007f9994f0cc50 in
↳nvidia::gxf::MultiThreadScheduler::workerThreadEntrance(nvidia::gxf::ThreadPool*,
↳long) () from /workspace/holoscan-sdk/build-debug-x86_64/lib/libgxf_serialization.so
#16 0x00007f9994cb0253 in ?? () from /usr/lib/x86_64-linux-gnu/libstdc++.so.6
#17 0x00007f9994a40ac3 in start_thread (arg=<optimized out>) at ./nptl/pthread_create.
↳c:442
#18 0x00007f9994ad2660 in clone3 () at ../sysdeps/unix/sysv/linux/x86_64/clone3.S:81

```

Under the backtrace of thread 13, you will find:

```

#8 <signal handler called>
#9 holoscan::ops::PingTensorTxOp::compute (this=0x559716f26fa0, op_output=..., context=.
↳..) at ../examples/ping_distributed/cpp/ping_distributed_ops.cpp:129

```

This indicates that the segmentation fault occurred at line 129 in `examples/ping_distributed/cpp/ping_distributed_ops.cpp`.

To view the backtrace of all threads, use the `thread apply all bt` command.

```
(gdb) thread apply all bt
```

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```
...
Thread 13 (Thread 0x7f995e3e3000 (LWP 2127105) "ping_distribute"):
#0  0x000007f9994a9642f in __GI___wait4 (pid=pid@entry=2127631, stat_loc=stat_
    ↳loc@entry=0x7f995e3ddd3c, options=options@entry=0, usage=usage@entry=0x0) at ../
    ↳sysdeps/unix/sysv/linux/wait4.c:30
...

Thread 12 (Thread 0x7f995ebe4000 (LWP 2127104) "ping_distribute"):
#0  0x000007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29
...
```

14.4 Debugging Holoscan Python Application

The Holoscan SDK provides support for tracing and profiling tools, particularly focusing on the `compute` method of Python operators. Debugging Python operators using Python IDEs can be challenging since this method is invoked from the C++ runtime. This also applies to the `initialize`, `start`, and `stop` methods of Python operators.

Users can leverage IDEs like VSCode/PyCharm (which utilize the `PyDev.Debugger`) or other similar tools to debug Python operators:

- For VSCode, refer to [VSCode Python Debugging](#).
- For PyCharm, consult [PyCharm Python Debugging](#).

Subsequent sections will detail methods for debugging, profiling, and tracing Python applications using the Holoscan SDK.

14.4.1 pdb example

The following command initiates a Python application within a `pdb` debugger session:

```
python python/tests/system/test_pytracing.py pdb

# Type the following commands to check if the breakpoints are hit:
#
#  b test_pytracing.py:76
#  c
#  exit
```

This is an interactive session.

Please type the following commands to check `if` the breakpoints are hit.

```
(Pdb) b test_pytracing.py:76
Breakpoint 1 at /workspace/holoscan-sdk/python/tests/system/test_pytracing.py:76
(Pdb) c
...
> /workspace/holoscan-sdk/python/tests/system/test_pytracing.py(76)start()
-> print("Mx start")
(Pdb) exit
```

For more details, please refer to the `pdb_main()` method in `test_pytracing.py`.

14.4.2 Profiling a Holoscan Python Application

For profiling, users can employ tools like `cProfile` or `line_profiler` for profiling Python applications/operators.

Note that when using a multithreaded scheduler, `cProfile` or the `profile` module might not accurately identify worker threads, or errors could occur.

In such cases with multithreaded schedulers, consider using multithread-aware profilers like `pyinstrument`, `pprofile`, or `yappi`.

For further information, refer to the test case at `test_pytracing.py`.

Using `pyinstrument`

`pyinstrument` is a call stack profiler for Python, designed to highlight performance bottlenecks in an easily understandable format directly in your terminal as the code executes.

```
python -m pip install pyinstrument
pyinstrument python/tests/system/test_pytracing.py

## Note: With a multithreaded scheduler, the same method may appear multiple times
↪ across different threads.
# pyinstrument python/tests/system/test_pytracing.py -s multithread
```

```
...
0.107 [root] None
├─ 0.088 MainThread <thread>:140079743820224
│   └─ 0.088 <module> ../../bin/pyinstrument:1
│       └─ 0.088 main pyinstrument/__main__.py:28
│           [7 frames hidden] pyinstrument, <string>, runpy, <built-in>
│           0.087 _run_code runpy.py:63
│               └─ 0.087 <module> test_pytracing.py:1
│                   └─ 0.061 main test_pytracing.py:153
│                       └─ 0.057 MyPingApp.compose test_pytracing.py:141
│                           └─ 0.041 PingMxOp.__init__ test_pytracing.py:59
│                               └─ 0.041 PingMxOp.__init__ ../core/__init__.py:262
│                                   [35 frames hidden] .., numpy, re, sre_compile, sre_
↪ parse...
│                   └─ 0.015 [self] test_pytracing.py
│                       └─ 0.002 [self] test_pytracing.py
│                           └─ 0.024 <module> ../__init__.py:1
│                               [5 frames hidden] .., <built-in>
│                                   └─ 0.001 <module> ../conditions/__init__.py:1
│                                       [2 frames hidden] .., <built-in>
├─ 0.019 Dummy-1 <thread>:140078275749440
│   └─ 0.019 <module> ../../bin/pyinstrument:1
│       └─ 0.019 main pyinstrument/__main__.py:28
│           [5 frames hidden] pyinstrument, <string>, runpy
│           0.019 _run_code runpy.py:63
│               └─ 0.019 <module> test_pytracing.py:1
│                   └─ 0.019 main test_pytracing.py:153
│                       └─ 0.014 [self] test_pytracing.py
│                           └─ 0.004 PingRxOp.compute test_pytracing.py:118
│                               └─ 0.004 print <built-in>
```

Using pprofile

pprofile is a line-granularity, thread-aware deterministic and statistic pure-python profiler.

```
python -m pip install pprofile
pprofile --include test_pytracing.py python/tests/system/test_pytracing.py -s multithread
```

```
Total duration: 0.972872s
File: python/tests/system/test_pytracing.py
File duration: 0.542628s (55.78%)
Line #|      Hits|      Time| Time per hit|      %|Source code
-----+-----+-----+-----+-----+-----
...
33|         0|         0|         0| 0.00%|
34|         2| 2.86102e-06| 1.43051e-06| 0.00%| def setup(self, spec:
↳ OperatorSpec):
35|         1| 1.62125e-05| 1.62125e-05| 0.00%|         spec.output("out")
36|         0|         0|         0| 0.00%|
37|         2| 3.33786e-06| 1.66893e-06| 0.00%| def initialize(self):
38|         1| 1.07288e-05| 1.07288e-05| 0.00%|         print("Tx initialize")
39|         0|         0|         0| 0.00%|
40|         2| 1.40667e-05| 7.03335e-06| 0.00%| def start(self):
41|         1| 1.23978e-05| 1.23978e-05| 0.00%|         print("Tx start")
42|         0|         0|         0| 0.00%|
43|         2| 3.09944e-05| 1.54972e-05| 0.00%| def stop(self):
44|         1| 2.88486e-05| 2.88486e-05| 0.00%|         print("Tx stop")
45|         0|         0|         0| 0.00%|
46|         4| 4.05312e-05| 1.01328e-05| 0.00%| def compute(self, op_input, op_
↳ output, context):
47|         3| 2.57492e-05| 8.58307e-06| 0.00%|         value = self.index
48|         3| 2.12193e-05| 7.07308e-06| 0.00%|         self.index += 1
```

Using yappi

yappi is a tracing profiler that is multithreading, asyncio and gevent aware.

```
python -m pip install yappi
# yappi requires setting a context ID callback function to specify the correct context
↳ ID for
# Holoscan's worker threads.
# For more details, please see `yappi_main()` in `test_pytracing.py`.
python python/tests/system/test_pytracing.py yappi | grep test_pytracing.py

## Note: With a multithreaded scheduler, method hit counts are distributed across
↳ multiple threads.
#python python/tests/system/test_pytracing.py yappi -s multithread | grep test_pytracing.
↳ py
```

```
...
test_pytracing.py main:153 1
test_pytracing.py MyPingApp.compose:141 1
test_pytracing.py PingMxOp.__init__:59 1
```

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```

test_pytracing.py PingTxOp.__init__:29 1
test_pytracing.py PingMxOp.setup:65 1
test_pytracing.py PingRxOp.__init__:99 1
test_pytracing.py PingRxOp.setup:104 1
test_pytracing.py PingTxOp.setup:34 1
test_pytracing.py PingTxOp.initialize:37 1
test_pytracing.py PingRxOp.stop:115 1
test_pytracing.py PingRxOp.initialize:109 1
test_pytracing.py PingMxOp.initialize:72 1
test_pytracing.py PingMxOp.stop:78 1
test_pytracing.py PingMxOp.compute:81 3
test_pytracing.py PingTxOp.compute:46 3
test_pytracing.py PingRxOp.compute:118 3
test_pytracing.py PingTxOp.start:40 1
test_pytracing.py PingMxOp.start:75 1
test_pytracing.py PingRxOp.start:112 1
test_pytracing.py PingTxOp.stop:43 1

```

Using profile/cProfile

profile/cProfile is a deterministic profiling module for Python programs.

```
python -m cProfile python/tests/system/test_pytracing.py 2>&1 | grep test_pytracing.py
```

```

## Executing a single test case
#python python/tests/system/test_pytracing.py profile

```

```

1    0.001    0.001    0.107    0.107 test_pytracing.py:1(<module>)
1    0.000    0.000    0.000    0.000 test_pytracing.py:104(setup)
1    0.000    0.000    0.000    0.000 test_pytracing.py:109(initialize)
1    0.000    0.000    0.000    0.000 test_pytracing.py:112(start)
1    0.000    0.000    0.000    0.000 test_pytracing.py:115(stop)
3    0.000    0.000    0.000    0.000 test_pytracing.py:118(compute)
1    0.000    0.000    0.000    0.000 test_pytracing.py:140(MyPingApp)
1    0.014    0.014    0.073    0.073 test_pytracing.py:141(compose)
1    0.009    0.009    0.083    0.083 test_pytracing.py:153(main)
1    0.000    0.000    0.000    0.000 test_pytracing.py:28(PingTxOp)
1    0.000    0.000    0.000    0.000 test_pytracing.py:29(__init__)
1    0.000    0.000    0.000    0.000 test_pytracing.py:34(setup)
1    0.000    0.000    0.000    0.000 test_pytracing.py:37(initialize)
1    0.000    0.000    0.000    0.000 test_pytracing.py:40(start)
1    0.000    0.000    0.000    0.000 test_pytracing.py:43(stop)
3    0.000    0.000    0.000    0.000 test_pytracing.py:46(compute)
1    0.000    0.000    0.000    0.000 test_pytracing.py:58(PingMxOp)
1    0.000    0.000    0.058    0.058 test_pytracing.py:59(__init__)
1    0.000    0.000    0.000    0.000 test_pytracing.py:65(setup)
1    0.000    0.000    0.000    0.000 test_pytracing.py:72(initialize)
1    0.000    0.000    0.000    0.000 test_pytracing.py:75(start)
1    0.000    0.000    0.000    0.000 test_pytracing.py:78(stop)
3    0.001    0.000    0.001    0.000 test_pytracing.py:81(compute)

```

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```

1      0.000      0.000      0.000      0.000 test_pytracing.py:98(PingRxOp)
1      0.000      0.000      0.000      0.000 test_pytracing.py:99(__init__)

```

Using line_profiler

line_profiler is a module for doing line-by-line profiling of functions.

```
python -m pip install line_profiler
```

```

# Insert `@profile` before the function `def compute(self, op_input, op_output,
↪context):`.
# The original file will be backed up as `test_pytracing.py.bak`.
file="python/tests/system/test_pytracing.py"
pattern="    def compute(self, op_input, op_output, context):"
insertion="    @profile"

if ! grep -q "^$insertion" "$file"; then
    sed -i.bak "/^$pattern/i\\
$insertion" "$file"
fi

```

```
kernprof -lv python/tests/system/test_pytracing.py
```

```

# Remove the inserted `@profile` decorator.
mv "$file.bak" "$file"

```

```

...
Wrote profile results to test_pytracing.py.lprof
Timer unit: 1e-06 s

Total time: 0.000304244 s
File: python/tests/system/test_pytracing.py
Function: compute at line 46

```

Line #	Hits	Time	Per Hit	% Time	Line Contents
46					@profile
47					def compute(self, op_input, op_
↪output, context):					
48	3	2.3	0.8	0.8	value = self.index
49	3	9.3	3.1	3.0	self.index += 1
50					
51	3	0.5	0.2	0.2	output = []
52	18	5.0	0.3	1.6	for i in range(0, 5):
53	15	4.2	0.3	1.4	output.append(value)
54	15	2.4	0.2	0.8	value += 1
55					
56	3	280.6	93.5	92.2	op_output.emit(output, "out")
...					

14.4.3 Measuring Code Coverage

The Holoscan SDK provides support for measuring code coverage using `Coverage.py`.

```
python -m pip install coverage

coverage erase
coverage run examples/ping_vector/python/ping_vector.py
coverage report examples/ping_vector/python/ping_vector.py
coverage html

# Open the generated HTML report in a browser.
xdg-open htmlcov/index.html
```

To record code coverage programmatically, please refer to the `coverage_main()` method in `test_pytracing.py`.

You can execute the example application with code coverage enabled by running the following command:

```
python -m pip install coverage
python python/tests/system/test_pytracing.py coverage
# python python/tests/system/test_pytracing.py coverage -s multithread
```

The following command starts a Python application using the `trace` module:

```
python -m trace --trackcalls python/tests/system/test_pytracing.py | grep test_pytracing
```

```
...
test_pytracing.main -> test_pytracing.MyPingApp.compose
test_pytracing.main -> test_pytracing.PingMxOp.compute
test_pytracing.main -> test_pytracing.PingMxOp.initialize
test_pytracing.main -> test_pytracing.PingMxOp.start
test_pytracing.main -> test_pytracing.PingMxOp.stop
test_pytracing.main -> test_pytracing.PingRxOp.compute
test_pytracing.main -> test_pytracing.PingRxOp.initialize
test_pytracing.main -> test_pytracing.PingRxOp.start
test_pytracing.main -> test_pytracing.PingRxOp.stop
test_pytracing.main -> test_pytracing.PingTxOp.compute
test_pytracing.main -> test_pytracing.PingTxOp.initialize
test_pytracing.main -> test_pytracing.PingTxOp.start
test_pytracing.main -> test_pytracing.PingTxOp.stop
```

A test case utilizing the `trace` module programmatically can be found in the `trace_main()` method in `test_pytracing.py`.

```
python python/tests/system/test_pytracing.py trace
# python python/tests/system/test_pytracing.py trace -s multithread
```

BUILT-IN OPERATORS AND EXTENSIONS

The units of work of Holoscan applications are implemented within Operators, as described in the *core concepts* of the SDK. The operators included in the SDK provide domain-agnostic functionalities such as IO, machine learning inference, processing, and visualization, optimized for AI streaming pipelines, relying on a set of *Core Technologies*.

15.1 Operators

The operators below are defined under the `holoscan::ops` namespace for C++ and CMake, and under the `holoscan.operators` module in Python.

Class	CMake target/lib	Documentation
AJASourceOp	<code>aja</code>	C++/Python
BayerDemosaicOp	<code>bayer_demosaic</code>	C++/Python
FormatConverterOp	<code>format_converter</code>	C++/Python
HolovizOp	<code>holoviz</code>	C++/Python
InferenceOp	<code>inference</code>	C++/Python
InferenceProcessorOp	<code>inference_processor</code>	C++/Python
PingRxOp	<code>ping_rx</code>	C++/Python
PingTxOp	<code>ping_tx</code>	C++/Python
SegmentationPostprocessorOp	<code>segmentation_postprocessor</code>	C++/Python
VideoStreamRecorderOp	<code>video_stream_recorder</code>	C++/Python
VideoStreamReplayerOp	<code>video_stream_replayer</code>	C++/Python
V4L2VideoCaptureOp	<code>v4l2</code>	C++/Python

Given an instance of an operator class, you can print a human-readable description of its specification to inspect the inputs, outputs, and parameters that can be configured on that operator class:

C++

```
std::cout << operator_object->spec()->description() << std::endl;
```

Python

```
print(operator_object.spec)
```

Note: The Holoscan SDK uses meta-programming with templating and `std::any` to support arbitrary data types. Because of this, some type information (and therefore values) might not be retrievable by the `description` API. If more details are needed, we recommend inspecting the list of `Parameter` members in the operator `header` to identify their type.

15.2 Extensions

The Holoscan SDK also includes some GXF extensions with GXF codelets, which are typically wrapped as operators, or present for legacy reasons. In addition to the core GXF extensions (`std`, `cuda`, `serialization`, `multimedia`) listed [here](#), the Holoscan SDK includes the following GXF extensions:

- `bayer_demosaic`
- `gxf_holoscan_wrapper`
- `stream_playback`
- `ucx_holoscan`

15.2.1 GXF Holoscan Wrapper

The `gxf_holoscan_wrapper` extension includes the `holoscan::gxf::OperatorWrapper` codelet. It is used as a utility base class to wrap a holoscan operator to interface with the GXF framework.

Learn more about it in the *Using Holoscan Operators in GXF Applications* section.

15.2.2 Stream Playback

The `stream_playback` extension includes the `nvidia::holoscan::stream_playback::VideoStreamSerializer` entity serializer to/from a Tensor Object. This extension does not include any codelets: reading and writing video stream (gxf entity files) from the disk was implemented as native operators with `VideoStreamRecorderOp` and `VideoStreamReplayerOp`, though they leverage the `VideoStreamSerializer` from this extension.

Note: The `VideoStreamSerializer` codelet is based on the `nvidia::gxf::StdEntitySerializer` with the addition of a `repeat` feature. (If the `repeat` parameter is `true` and the frame count is out of the maximum frame index, unnecessary warning messages are printed with `nvidia::gxf::StdEntitySerializer`.)

15.2.3 UCX (Holoscan)

The `ucx_holoscan` extension includes `nvidia::holoscan::UcxHoloscanComponentSerializer` which is a `nvidia::gxf::ComponentSerializer` that handles serialization of `holoscan::Message` and `holoscan::Tensor` types for transmission using the Unified Communication X (UCX) library. UCX is the library used by Holoscan SDK to enable communication of data between fragments in distributed applications.

Note: The `UcxHoloscanComponentSerializer` is intended for use in combination with other UCX components defined in the GXF UCX extension. Specifically, it can be used by the `UcxEntitySerializer` where it can operate alongside the `UcxComponentSerializer` that serializes GXF-specific types (`nvidia::gxf::Tensor`, `nvidia::gxf::VideoBuffer`, etc.). This way both GXF and Holoscan types can be serialized by distributed applications.

15.2.4 HoloHub

Visit the HoloHub repository to find a collection of additional Holoscan operators and extensions.

VISUALIZATION

16.1 Overview

Holoviz provides the functionality to composite real time streams of frames with multiple different other layers like segmentation mask layers, geometry layers and GUI layers.

For maximum performance Holoviz makes use of [Vulkan](#), which is already installed as part of the Nvidia GPU driver.

Holoscan provides the *Holoviz operator* which is sufficient for many, even complex visualization tasks. The *Holoviz operator* is used by multiple Holoscan [example applications](#).

Additionally, for more advanced use cases, the *Holoviz module* can be used to create application specific visualization operators. The *Holoviz module* provides a C++ API and is also used by the *Holoviz operator*.

The term Holoviz is used for both the *Holoviz operator* and the *Holoviz module* below. Both the operator and the module roughly support the same features set. Where applicable information how to use a feature with the operator and the module is provided. It's explicitly mentioned below when features are not supported by the operator.

16.2 Layers

The core entity of Holoviz are layers. A layer is a two-dimensional image object. Multiple layers are composited to create the final output.

These layer types are supported by Holoviz:

- image layer
- geometry layer
- GUI layer

All layers have common attributes which define the look and also the way layers are finally composited.

The priority determines the rendering order of the layers. Before rendering the layers they are sorted by priority, the layers with the lowest priority are rendered first so that the layer with the highest priority is rendered on top of all other layers. If layers have the same priority then the render order of these layers is undefined.

The example below draws a transparent geometry layer on top of an image layer (geometry data and image data creation is omitted in the code). Although the geometry layer is specified first, it is drawn last because it has a higher priority (1) than the image layer (0).

Operator

The operator has a `receivers` port which accepts tensors and video buffers produced by other operators. Each tensor or video buffer will result in a layer.

The operator autodetects the layer type for certain input types (e.g. a video buffer will result in an image layer).

For other input types or more complex use cases input specifications can be provided either at initialization time as a parameter or dynamically at run time.

```
std::vector<ops::HolovizOp::InputSpec> input_specs;

auto& geometry_spec =
    input_specs.emplace_back(ops::HolovizOp::InputSpec("point_tensor",
↳ops::HolovizOp::InputType::POINTS));
geometry_spec.priority_ = 1;
geometry_spec.opacity_ = 0.5;

auto& image_spec =
    input_specs.emplace_back(ops::HolovizOp::InputSpec("image_tensor",
↳ops::HolovizOp::InputType::IMAGE));
image_spec.priority_ = 0;

auto visualizer = make_operator<ops::HolovizOp>("holoviz", Arg("tensors", input_specs));

// the source provides two tensors named "point_tensor" and "image_tensor" at the
↳"outputs" port.
add_flow(source, visualizer, {"outputs", "receivers"});
```

Module

The definition of a layer is started by calling one of the layer begin functions `viz::BeginImageLayer()`, `viz::BeginGeometryLayer()` or `viz::BeginImGuiLayer()`. The layer definition ends with `viz::EndLayer()`.

The start of a layer definition is resetting the layer attributes like priority and opacity to their defaults. So for the image layer, there is no need to set the opacity to `1.0` since the default is already `1.0`.

```
namespace viz = holoscan::viz;

viz::Begin();

viz::BeginGeometryLayer();
viz::LayerPriority(1);
viz::LayerOpacity(0.5);
/// details omitted
viz::EndLayer();

viz::BeginImageLayer();
viz::LayerPriority(0);
/// details omitted
viz::EndLayer();

viz::End();
```

16.2.1 Image Layers

Operator

Image data can either be on host or device (GPU), both tensors and video buffers are accepted.

```
std::vector<ops::HolovizOp::InputSpec> input_specs;

auto& image_spec =
    input_specs.emplace_back(ops::HolovizOp::InputSpec("image",
ops::HolovizOp::InputType::IMAGE));

auto visualizer = make_operator<ops::HolovizOp>("holoviz", Arg("tensors", input_specs));

// the source provides an image named "image" at the "outputs" port.
add_flow(source, visualizer, {"output", "receivers"});
```

Module

The function `viz::BeginImageLayer()` starts an image layer. An image layer displays a rectangular 2D image.

The image data is defined by calling `viz::ImageCudaDevice()`, `viz::ImageCudaArray()` or `viz::ImageHost()`. Various input formats are supported, see `viz::ImageFormat`.

For single channel image formats image colors can be looked up by defining a lookup table with `viz::LUT()`.

```
viz::BeginImageLayer();
viz::ImageHost(width, height, format, data);
viz::EndLayer();
```

Supported Image Formats

Operator

Supported formats for `nvidia::gxf::VideoBuffer`.

<code>nvidia::gxf::VideoFormat</code>	Supported	Description
<code>GXF_VIDEO_FORMAT_CUSTOM</code>	-	
<code>GXF_VIDEO_FORMAT_YUV420</code>	-	BT.601 multi planar 4:2:0 YUV
<code>GXF_VIDEO_FORMAT_YUV420_ER</code>	-	BT.601 multi planar 4:2:0 YUV ER
<code>GXF_VIDEO_FORMAT_YUV420_709</code>	-	BT.709 multi planar 4:2:0 YUV
<code>GXF_VIDEO_FORMAT_YUV420_709_ER</code>	-	BT.709 multi planar 4:2:0 YUV
<code>GXF_VIDEO_FORMAT_NV12</code>	-	BT.601 multi planar 4:2:0 YUV with interleaved UV
<code>GXF_VIDEO_FORMAT_NV12_ER</code>	-	BT.601 multi planar 4:2:0 YUV ER with interleaved UV
<code>GXF_VIDEO_FORMAT_NV12_709</code>	-	BT.709 multi planar 4:2:0 YUV with interleaved UV
<code>GXF_VIDEO_FORMAT_NV12_709_ER</code>	-	BT.709 multi planar 4:2:0 YUV ER with interleaved UV
<code>GXF_VIDEO_FORMAT_RGBA</code>	✓	RGBA-8-8-8-8 single plane
<code>GXF_VIDEO_FORMAT_BGRA</code>	✓	BGRA-8-8-8-8 single plane
<code>GXF_VIDEO_FORMAT_ARGB</code>	✓	ARGB-8-8-8-8 single plane
<code>GXF_VIDEO_FORMAT_ABGR</code>	✓	ABGR-8-8-8-8 single plane
<code>GXF_VIDEO_FORMAT_RGBX</code>	✓	RGBX-8-8-8-8 single plane

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Table 16.1 – continued from previous page

nvidia::gfx::VideoFormat	Supported	Description
GXF_VIDEO_FORMAT_BGRX	✓	BGRX-8-8-8-8 single plane
GXF_VIDEO_FORMAT_XRGB	✓	XRGB-8-8-8-8 single plane
GXF_VIDEO_FORMAT_XBGR	✓	XBGR-8-8-8-8 single plane
GXF_VIDEO_FORMAT_RGB	✓	RGB-8-8-8 single plane
GXF_VIDEO_FORMAT_BGR	✓	BGR-8-8-8 single plane
GXF_VIDEO_FORMAT_R8_G8_B8	-	RGB - unsigned 8 bit multiplanar
GXF_VIDEO_FORMAT_B8_G8_R8	-	BGR - unsigned 8 bit multiplanar
GXF_VIDEO_FORMAT_GRAY	✓	8 bit GRAY scale single plane
GXF_VIDEO_FORMAT_GRAY16	✓	16 bit GRAY scale single plane
GXF_VIDEO_FORMAT_GRAY32	-	32 bit GRAY scale single plane
GXF_VIDEO_FORMAT_GRAY32F	✓	float 32 bit GRAY scale single plane
GXF_VIDEO_FORMAT_RGB16	-	RGB-16-16-16 single plane
GXF_VIDEO_FORMAT_BGR16	-	BGR-16-16-16 single plane
GXF_VIDEO_FORMAT_RGB32	-	RGB-32-32-32 single plane
GXF_VIDEO_FORMAT_BGR32	-	BGR-32-32-32 single plane
GXF_VIDEO_FORMAT_R16_G16_B16	-	RGB - signed 16 bit multiplanar
GXF_VIDEO_FORMAT_B16_G16_R16	-	BGR - signed 16 bit multiplanar
GXF_VIDEO_FORMAT_R32_G32_B32	-	RGB - signed 32 bit multiplanar
GXF_VIDEO_FORMAT_B32_G32_R32	-	BGR - signed 32 bit multiplanar
GXF_VIDEO_FORMAT_NV24	-	multi planar 4:4:4 YUV with interleaved UV
GXF_VIDEO_FORMAT_NV24_ER	-	multi planar 4:4:4 YUV ER with interleaved UV
GXF_VIDEO_FORMAT_R8_G8_B8_D8	-	RGBD unsigned 8 bit multiplanar
GXF_VIDEO_FORMAT_R16_G16_B16_D16	-	RGBD unsigned 16 bit multiplanar
GXF_VIDEO_FORMAT_R32_G32_B32_D32	-	RGBD unsigned 32 bit multiplanar
GXF_VIDEO_FORMAT_RGBD8	-	RGBD 8 bit unsigned single plane
GXF_VIDEO_FORMAT_RGBD16	-	RGBD 16 bit unsigned single plane
GXF_VIDEO_FORMAT_RGBD32	-	RGBD 32 bit unsigned single plane
GXF_VIDEO_FORMAT_D32F	✓	Depth 32 bit float single plane
GXF_VIDEO_FORMAT_D64F	-	Depth 64 bit float single plane
GXF_VIDEO_FORMAT_RAW16_RGGB	-	RGGB-16-16-16-16 single plane
GXF_VIDEO_FORMAT_RAW16_BGGR	-	BGGR-16-16-16-16 single plane
GXF_VIDEO_FORMAT_RAW16_GRBG	-	GRBG-16-16-16-16 single plane
GXF_VIDEO_FORMAT_RAW16_GBRG	-	GBRG-16-16-16-16 single plane

Image format detection for `nvidia::gfx::Tensor`. Tensors don't have image format information attached. The Holoviz operator detects the image format from the tensor configuration.

nvidia::gfx::PrimitiveType	Channels	Color format	Index for color lookup
kUnsigned8	1	8 bit GRAY scale single plane	✓
kInt8	1	signed 8 bit GRAY scale single plane	✓
kUnsigned16	1	16 bit GRAY scale single plane	✓
kInt16	1	signed 16 bit GRAY scale single plane	✓
kUnsigned32	1	-	✓
kInt32	1	-	✓
kFloat32	1	float 32 bit GRAY scale single plane	✓
kUnsigned8	3	RGB-8-8-8 single plane	-
kInt8	3	signed RGB-8-8-8 single plane	-
kUnsigned8	4	RGBA-8-8-8-8 single plane	-
kInt8	4	signed RGBA-8-8-8-8 single plane	-
kUnsigned16	4	RGBA-16-16-16-16 single plane	-
kInt16	4	signed RGBA-16-16-16-16 single plane	-
kFloat32	4	RGBA-16-16-16-16 single plane	-

Module

See `viz::ImageFormat` for supported image formats. Additionally `viz::ImageComponentMapping()` can be used to map the color components of an image to the color components of the output.

16.2.2 Geometry Layers

A geometry layer is used to draw geometric primitives such as points, lines, rectangles, ovals or text.

Coordinates start with (0, 0) in the top left and end with (1, 1) in the bottom right.

Operator

See `holoviz_geometry.cpp` and `holoviz_geometry.py`.

Module

The function `viz::BeginGeometryLayer()` starts a geometry layer.

See `viz::PrimitiveTopology` for supported geometry primitive topologies.

There are functions to set attributes for geometric primitives like color (`viz::Color()`), line width (`viz::LineWidth()`) and point size (`viz::PointSize()`).

The code below draws a red rectangle and a green text.

```
namespace viz = holoscan::viz;

viz::BeginGeometryLayer();

// draw a red rectangle
viz::Color(1.f, 0.f, 0.f, 0.f);
const float data[]{0.1f, 0.1f, 0.9f, 0.9f};
viz::Primitive(viz::PrimitiveTopology::RECTANGLE_LIST, 1, sizeof(data) / sizeof(data[0]),
    ↪ data);
```

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```
// draw green text
viz::Color(0.f, 1.f, 0.f, 0.f);
viz::Text(0.5f, 0.5f, 0.2f, "Text");

viz::EndLayer();
```

16.2.3 ImGui Layers

Note: ImGui layers are not supported when using the Holoviz operator.

The Holoviz module supports user interface layers created with [Dear ImGui](#).

Calls to the Dear ImGui API are allowed between `viz::BeginImGuiLayer()` and `viz::EndImGuiLayer()` are used to draw to the ImGui layer. The ImGui layer behaves like other layers and is rendered with the layer opacity and priority.

The code below creates a Dear ImGui window with a checkbox used to conditionally show a image layer.

```
namespace viz = holoscan::viz;

bool show_image_layer = false;
while (!viz::WindowShouldClose()) {
    viz::Begin();

    viz::BeginImGuiLayer();

    ImGui::Begin("Options");
    ImGui::Checkbox("Image layer", &show_image_layer);
    ImGui::End();

    viz::EndLayer();

    if (show_image_layer) {
        viz::BeginImageLayer();
        viz::ImageHost(...);
        viz::EndLayer();
    }

    viz::End();
}
```

ImGui is a static library and has no stable API. Therefore the application and Holoviz have to use the same ImGui version. Therefore the link target `holoscan::viz::imgui` is exported, make sure to link your app against that target.

16.2.4 Depth Map Layers

A depth map is a single channel 2d array where each element represents a depth value. The data is rendered as a 3d object using points, lines or triangles. The color for the elements can also be specified.

Supported format for the depth map:

- 8-bit unsigned normalized format that has a single 8-bit depth component

Supported format for the depth color map:

- 32-bit unsigned normalized format that has an 8-bit R component in byte 0, an 8-bit G component in byte 1, an 8-bit B component in byte 2, and an 8-bit A component in byte 3

Depth maps are rendered in 3D and support camera movement.

The camera is operated using the mouse.

- Orbit (LMB)
- Pan (LMB + CTRL | MMB)
- Dolly (LMB + SHIFT | RMB | Mouse wheel)
- Look Around (LMB + ALT | LMB + CTRL + SHIFT)
- Zoom (Mouse wheel + SHIFT)

Operator

```
std::vector<ops::HolovizOp::InputSpec> input_specs;

auto& depth_map_spec =
    input_specs.emplace_back(ops::HolovizOp::InputSpec("depth_map",
ops::HolovizOp::InputType::DEPTH_MAP));
depth_map_spec.depth_map_render_mode_ = ops::HolovizOp::DepthMapRenderMode::TRIANGLES;

auto visualizer = make_operator<ops::HolovizOp>("holoviz",
    Arg("tensors", input_specs));

// the source provides an depth map named "depth_map" at the "output" port.
add_flow(source, visualizer, {"output", "receivers"});
```

Module

See [holoviz depth map demo](#).

16.3 Views

By default a layer will fill the whole window. When using a view, the layer can be placed freely within the window.

Layers can also be placed in 3D space by specifying a 3D transformation matrix.

Note: For geometry layers there is a default matrix which allows coordinates in the range of $[0 \dots 1]$ instead of the Vulkan $[-1 \dots 1]$ range. When specifying a matrix for a geometry layer, this default matrix is overwritten.

When multiple views are specified the layer is drawn multiple times using the specified layer view.

It's possible to specify a negative term for height, which flips the image. When using a negative height, one should also adjust the y value to point to the lower left corner of the viewport instead of the upper left corner.

Operator

See `holoviz_views.py`.

Module

Use `viz::LayerAddView()` to add a view to a layer.

16.4 Using a display in exclusive mode

Usually Holoviz opens a normal window on the Linux desktop. In that case the desktop compositor is combining the Holoviz image with all other elements on the desktop. To avoid this extra compositing step, Holoviz can render to a display directly.

16.4.1 Configure a display for exclusive use

Single display

SSH into the machine and stop the X server:

```
sudo systemctl stop display-manager
```

To resume the display manager, run:

```
sudo systemctl start display-manager
```

Multiple displays

The display to be used in exclusive mode needs to be disabled in the NVIDIA Settings application (nvidia-settings): open the X Server Display Configuration tab, select the display and under Configuration select Disabled. Press Apply.

16.4.2 Enable exclusive display in Holoviz

Operator

Arguments to pass to the Holoviz operator:

```
auto visualizer = make_operator<ops::HolovizOp>("holoviz",
  Arg("use_exclusive_display", true), // required
  Arg("display_name", "DP-2"), // optional
  Arg("width", 2560), // optional
  Arg("height", 1440), // optional
  Arg("framerate", 240) // optional
);
```

Module

Provide the name of the display and desired display mode properties to viz::Init().

If the name is nullptr then the first display is selected.

The name of the display can either be the EDID name as displayed in the NVIDIA Settings, or the output name used by xrandr.

Tip: In this example output of xrandr, DP-2 would be an adequate display name to use:

```
Screen 0: minimum 8 x 8, current 4480 x 1440, maximum 32767 x 32767
DP-0 disconnected (normal left inverted right x axis y axis)
DP-1 disconnected (normal left inverted right x axis y axis)
DP-2 connected primary 2560x1440+1920+0 (normal left inverted right x axis y axis) 600mm
↵x 340mm
 2560x1440    59.98 + 239.97* 199.99  144.00  120.00  99.95
 1024x768     60.00
  800x600     60.32
  640x480     59.94
USB-C-0 disconnected (normal left inverted right x axis y axis)
```

16.5 CUDA streams

By default Holoviz is using CUDA stream 0 for all CUDA operations. Using the default stream can affect concurrency of CUDA operations, see [stream synchronization behavior](#) for more information.

Operator

The operator is using a `holoscan::CudaStreamPool` instance if provided by the `cuda_stream_pool` argument. The stream pool is used to create a CUDA stream used by all Holoviz operations.

```
const std::shared_ptr<holoscan::CudaStreamPool> cuda_stream_pool =
    make_resource<holoscan::CudaStreamPool>("cuda_stream", 0, 0, 0, 1, 5);
auto visualizer =
    make_operator<holoscan::ops::HolovizOp>("visualizer",
        Arg("cuda_stream_pool") = cuda_stream_pool);
```

Module

When providing CUDA resources to Holoviz through e.g. `viz::ImageCudaDevice()` Holoviz is using CUDA operations to use that memory. The CUDA stream used by these operations can be set by calling `viz::SetCudaStream()`. The stream can be changed at any time.

16.6 Reading the framebuffer

The rendered frame buffer can be read back. This is useful when when doing offscreen rendering or running Holoviz in a headless environment.

Note: Reading the depth buffer is not supported when using the Holoviz operator.

Operator

To read back the color framebuffer set the `enable_render_buffer_output` parameter to `true` and provide an allocator to the operator.

The framebuffer is emitted on the `render_buffer_output` port.

```
std::shared_ptr<holoscan::ops::HolovizOp> visualizer =
    make_operator<ops::HolovizOp>("visualizer",
        Arg("enable_render_buffer_output", true),
        Arg("allocator") = make_resource<holoscan::UnboundedAllocator>("allocator"),
        Arg("cuda_stream_pool") = cuda_stream_pool);

add_flow(visualizer, destination, {"render_buffer_output", "input"});
```

Module

The rendered color or depth buffer can be read back using `viz::ReadFramebuffer()`.

16.7 Holoviz operator

16.7.1 Class documentation

C++

Python.

16.7.2 Examples

There are multiple [examples](#) both in Python and C++ showing how to use various features of the Holoviz operator.

16.8 Holoviz module

16.8.1 Concepts

The Holoviz module uses the concept of the immediate mode design pattern for its API, inspired by the [Dear ImGui](#) library. The difference to the retained mode, for which most APIs are designed for, is, that there are no objects created and stored by the application. This makes it fast and easy to make visualization changes in a Holoscan application.

16.8.2 Instances

The Holoviz module uses a thread-local instance object to store its internal state. The instance object is created when calling the Holoviz module is first called from a thread. All Holoviz module functions called from that thread use this instance.

When calling into the Holoviz module from other threads other than the thread from which the Holoviz module functions were first called, make sure to call `viz::GetCurrent()` and `viz::SetCurrent()` in the respective threads.

There are usage cases where multiple instances are needed, for example, to open multiple windows. Instances can be created by calling `viz::Create()`. Call `viz::SetCurrent()` to make the instance current before calling the Holoviz module function to be executed for the window the instance belongs to.

16.8.3 Getting started

The code below creates a window and displays an image.

First the Holoviz module needs to be initialized. This is done by calling `viz::Init()`.

The elements to display are defined in the render loop, termination of the loop is checked with `viz::WindowShouldClose()`.

The definition of the displayed content starts with `viz::Begin()` and ends with `viz::End()`. `viz::End()` starts the rendering and displays the rendered result.

Finally the Holoviz module is shutdown with `viz::Shutdown()`.

```
#include "holoviz/holoviz.hpp"

namespace viz = holoscan::viz;

viz::Init("Holoviz Example");

while (!viz::WindowShouldClose()) {
    viz::Begin();
    viz::BeginImageLayer();
    viz::ImageHost(width, height, viz::ImageFormat::R8G8B8A8_UNORM, image_data);
    viz::EndLayer();
    viz::End();
}

viz::Shutdown();
```

Result:

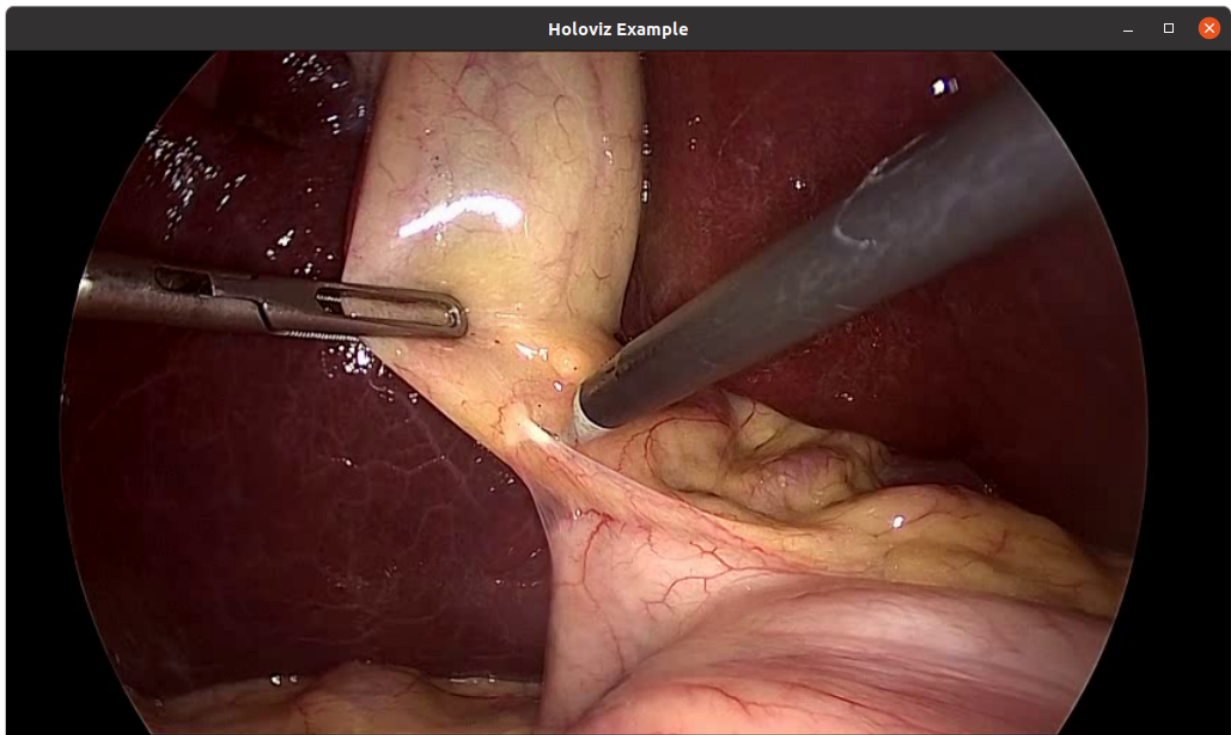


Fig. 16.1: Holoviz example app

16.8.4 API

Holoviz module API

16.8.5 Examples

There are multiple [examples](#) showing how to use various features of the Holoviz module.

INFERENCE

17.1 Overview

A Holoscan application that needs to run inference will use an inference operator. The built-in *Inference operator* (InferenceOp) can be used, and several related use cases are documented in the Inference operator section below. The use cases are created using the *parameter set* that must be defined in the configuration file of the holoscan application. If the built-in InferenceOp doesn't cover a specific use case, users can create their own custom inference operator as documented in *Creating an Inference operator* section.

The core inference functionality in the Holoscan SDK is provided by the Inference Module which is a framework that facilitates designing and executing inference and processing applications through its APIs. It is used by the built-in InferenceOp which supports the same parameters as the Inference Module. All parameters required by the Holoscan Inference Module are passed through a parameter set in the configuration file of an application.

17.2 Parameters and related Features

Required parameters and related features available with the Holoscan Inference Module are listed below.

- Data Buffer Parameters: Parameters are provided in the inference settings to enable data buffer locations at several stages of the inference. As shown in the figure below, three parameters `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` can be set by the user.
 - `input_on_cuda` refers to the location of the data going into the inference.
 - * If value is `true`, it means the input data is on the device
 - * If value is `false`, it means the input data is on the host
 - * Default value: `true`
 - `output_on_cuda` refers to the data location of the inferred data.
 - * If value is `true`, it means the inferred data is on the device
 - * If value is `false`, it means the inferred data is on the host
 - * Default value: `true`
 - `transmit_on_cuda` refers to the data transmission.
 - * If value is `true`, it means the data transmission from the inference extension will be on **Device**
 - * If value is `false`, it means the data transmission from the inference extension will be on **Host**
 - * Default value: `true`
- Inference Parameters

- backend parameter is set to either `trt` for TensorRT, `onnxrt` for Onnx runtime, or `torch` for libtorch. If there are multiple models in the inference application, all models will use the same backend. If it is desired to use different backends for different models, specify the `backend_map` parameter instead.
 - * TensorRT:
 - CUDA-based inference supported both on `x86_64` and `aarch64`
 - End-to-end CUDA-based data buffer parameters supported. `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` will all be true for end-to-end CUDA-based data movement.
 - `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` can be either `true` or `false`.
 - TensorRT backend expects input models to be in `tensorrt engine file` format or `onnx` format.
 - if models are in `tensorrt engine file` format, parameter `is_engine_path` must be set to `true`.
 - if models are in `onnx` format, it will be automatically converted into `tensorrt engine file` by the Holoscan inference module.
 - * Torch:
 - CUDA and CPU based inference supported both on `x86_64` and `aarch64`.
 - End-to-end CUDA-based data buffer parameters supported. `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` will all be true for end-to-end CUDA-based data movement.
 - `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` can be either `true` or `false`.
 - Libtorch and TorchVision are included in the Holoscan NGC container, initially built as part of the [PyTorch NGC container](#). To use the Holoscan SDK torch backend outside of these containers, we recommend you download libtorch and torchvision binaries from [Holoscan's third-party repository](#).
 - Torch backend expects input models to be in `torchscript` format.
 - It is recommended to use the same version of torch for `torchscript` model generation, as used in the HOLOSCAN SDK on the respective architectures.
 - Additionally, it is recommended to generate the `torchscript` model on the same architecture on which it will be executed. For example, `torchscript` model must be generated on `x86_64` to be executed in an application running on `x86_64` only.
 - * Onnx runtime:
 - Data flow via host only. `input_on_cuda`, `output_on_cuda` and `transmit_on_cuda` must be `false`.
 - CUDA based inference (supported on `x86_64`)
 - CPU based inference (supported on `x86_64` and `aarch64`)
- `infer_on_cpu` parameter is set to `true` if CPU based inference is desired.

The tables below demonstrate the supported features related to the data buffer and the inference with `trt` and `onnxrt` based backend, on `x86` and `aarch64` system respectively.

x86	input_on_cuda	output_on_cuda	transmit_on_cuda	infer_on_cpu
Supported values for <code>trt</code>	true or false	true or false	true or false	false
Supported values for <code>torch</code>	true or false	true or false	true or false	true or false
Supported values for <code>onnxrt</code>	false	false	true or false	true or false

Aarch64	input_on_cuda	output_on_cuda	transmit_on_cuda	infer_on_cpu
Supported values for trt	true or false	true or false	true or false	false
Supported values for torch	true or false	true or false	true or false	true or false
Supported values for onnxrt	false	false	true or false	true

- **model_path_map**: User can design single or multi AI inference pipeline by populating **model_path_map** in the config file.
 - * With a single entry it is single inference and with more than one entry, multi AI inference is enabled.
 - * Each entry in **model_path_map** has a unique keyword as key (used as an identifier by the Holoscan Inference Module), and the path to the model as value.
 - * All model entries must have the models either in **onnx** or **tensorrt engine file** or **torchscript** format.
- **pre_processor_map**: input tensor to the respective model is specified in **pre_processor_map** in the config file.
 - * The Holoscan Inference Module supports same input for multiple models or unique input per model.
 - * Each entry in **pre_processor_map** has a unique keyword representing the model (same as used in **model_path_map**), and a vector of tensor names as the value.
 - * The Holoscan Inference Module supports multiple input tensors per model.
- **inference_map**: output tensors per model after inference is specified in **inference_map** in the config file.
 - * Each entry in **inference_map** has a unique keyword representing the model (same as used in **model_path_map** and **pre_processor_map**), and a vector of the output tensor names as the value.
 - * The Holoscan Inference Module supports multiple output tensors per model.
- **parallel_inference**: Parallel or Sequential execution of inferences.
 - * If multiple models are input, then user can execute models in parallel.
 - * Parameter **parallel_inference** can be either **true** or **false**. Default value is **true**.
 - * Inferences are launched in parallel without any check of the available GPU resources, user must make sure that there is enough memory and compute available to run all the inferences in parallel.
- **enable_fp16**: Generation of the TensorRT engine files with FP16 option
 - * If **backend** is set to **trt**, and if the input models are in **onnx** format, then users can generate the engine file with **fp16** option to accelerate inferencing.
 - * It takes few mintues to generate the engine files for the first time.
 - * It can be either **true** or **false**. Default value is **false**.
- **is_engine_path**: if the input models are specified in **trt engine format** in **model_path_map**, this flag must be set to **true**. Default value is **false**.
- **in_tensor_names**: Input tensor names to be used by **pre_processor_map**. This parameter is optional. If absent in the parameter map, values are derived from **pre_processor_map**.
- **out_tensor_names**: Output tensor names to be used by **inference_map**. This parameter is optional. If absent in the parameter map, values are derived from **inference_map**.
- **device_map**: Multi-GPU inferencing is enabled if **device_map** is populated in the parameter set.

- * Each entry in `device_map` has a unique keyword representing the model (same as used in `model_path_map` and `pre_processor_map`), and GPU identifier as the value. This GPU ID is used to execute the inference for the specified model.
- * GPUs specified in the `device_map` must have P2P (peer to peer) access and they must be connected to the same PCIE configuration. If P2P access is not possible among GPUs, the host (CPU memory) will be used to transfer the data.
- * Multi-GPU inferencing is supported for all backends.
- `backend_map`: Multiple backends can be used in the same application with this parameter.
 - * Each entry in `backend_map` has a unique keyword representing the model (same as used in `model_path_map`), and the backend as the value.
 - * A sample `backend_map` is shown below. In the example, `model_1` uses the `tensorRT` backend, and `model_2` and `model_3` uses the `torch` backend for inference.

backend_map:

```
"model_1_unique_identifier": "trt"
"model_2_unique_identifier": "torch"
"model_3_unique_identifier": "torch"
```

- Other features: Table below illustrates other features and supported values in the current release.

Feature	Supported values
Data type	float32, int32, int8
Inference Backend	trt, torch, onnxrt
Inputs per model	Multiple
Outputs per model	Multiple
GPU(s) supported	Multi-GPU on same PCIE network
Tensor data dimension	2, 3, 4
Model Type	All onnx or all torchscript or all trt engine type or a combination of torch and trt engine

- Multi Receiver and Single Transmitter support
 - The Holoscan Inference Module provides an API to extract the data from multiple receivers.
 - The Holoscan Inference Module provides an API to transmit multiple tensors via a single transmitter.

17.2.1 Parameter Specification

All required inference parameters of the inference application must be specified. Below is a sample parameter set for an application that uses three models for inferencing. User must populate all required fields with appropriate values.

inference:

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
```

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```

    "model_3_unique_identifier": "path_to_model_3"
  pre_processor_map:
    "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
    "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
    "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
  inference_map:
    "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
    "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
    "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]
  parallel_inference: true
  infer_on_cpu: false
  enable_fp16: false
  input_on_cuda: true
  output_on_cuda: true
  transmit_on_cuda: true
  is_engine_path: false

```

17.3 Inference Operator

In Holoscan SDK, the built-in Inference operator (InferenceOp) is designed using the Holoscan Inference Module APIs. The Inference operator ingests the inference parameter set (from the configuration file) and the data receivers (from previous connected operators in the application), executes the inference and transmits the inferred results to the next connected operators in the application.

InferenceOp is a generic operator that serves multiple use cases via the parameter set. Parameter sets for some key use cases are listed below:

Note: Some parameters have default values set for them in the InferenceOp. For any parameters not mentioned in the example parameter sets below, their default is used by the InferenceOp. These parameters are used to enable several use cases.

- Single model inference using TensorRT backend.

```

  backend: "trt"
  model_path_map:
    "model_1_unique_identifier": "path_to_model_1"
  pre_processor_map:
    "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  inference_map:
    "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]

```

Value of backend can be modified for other supported backends, and other parameters related to each backend. User must ensure correct model type and model path is provided into the parameter set, along with supported values of all parameters for the respective backend.

In this example, path_to_model_1 must be an onnx file, which will be converted to a tensorRT engine file at first execution. During subsequent executions, the Holoscan inference module will automatically find the tensorRT engine file (if path_to_model_1 has not changed). Additionally, if user has a pre-built tensorRT engine file, path_to_model_1 must be path to the engine file and the parameter is_engine_path must be set to true in the parameter set.

- Single model inference using TensorRT backend with multiple outputs.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier",
                                "output_tensor_2_model_1_unique_identifier",
                                "output_tensor_3_model_1_unique_identifier"]
```

As shown in example above, Holoscan Inference module automatically maps the model outputs to the named tensors in the parameter set. Users must ensure to use the named tensors in the same sequence in which the model generates the output. Similar logic holds for multiple inputs.

- Single model inference using fp16 precision.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier",
                                "output_tensor_2_model_1_unique_identifier",
                                "output_tensor_3_model_1_unique_identifier"]

enable_fp16: true
```

If a tensorRT engine file is not available for fp16 precision, it will be automatically generated by the Holoscan Inference module on the first execution. The file is cached for future executions.

- Single model inference on CPU.

```
backend: "onnxrt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
infer_on_cpu: true
```

Note that the backend can only be onnxrt or torch for CPU based inference.

- Single model inference with input/output data on Host.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
input_on_cuda: false
output_on_cuda: false
```

Data in the core inference engine is passed through the host and is received on the host. Inference can happen on the GPU. Parameters `input_on_cuda` and `output_on_cuda` define the location of the data before and after inference respectively.

- Single model inference with data transmission via Host.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
transmit_on_host: true
```

Data from inference operator to the next connected operator in the application is transmitted via the host.

- Multi model inference with a single backend.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
  "model_3_unique_identifier": "path_to_model_3"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]
```

By default multiple model inferences are launched in parallel. The backend specified via parameter `backend` is used for all models in the application.

- Multi model inference with sequential inference.

```
backend: "trt"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
  "model_3_unique_identifier": "path_to_model_3"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]
parallel_inference: false
```

`parallel_inference` is set to `true` by default. To launch model inferences in sequence, `parallel_inference` must be set to `false`.

- Multi model inference with multiple backends.

```

backend_map:
  "model_1_unique_identifier": "trt"
  "model_2_unique_identifier": "torch"
  "model_3_unique_identifier": "torch"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
  "model_3_unique_identifier": "path_to_model_3"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]

```

In the above sample parameter set, the first model will do inference using the `tensorRT` backend, and model 2 and 3 will do inference using the `torch` backend.

Note: the combination of backends in `backend_map` must support all other parameters that will be used during the inference. For. e.g. `onnxrt` and `tensorRT` combination with CPU based inference will not be supported.

- Multi model inference with a single backend on multi-GPU.

```

backend: "trt"
device_map:
  "model_1_unique_identifier": "1"
  "model_2_unique_identifier": "0"
  "model_3_unique_identifier": "1"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
  "model_3_unique_identifier": "path_to_model_3"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]

```

In the sample above, model 1 and model 3 will do inference on the GPU with ID 1 and model 2 will do inference on the GPU with ID 0. GPUs must have P2P (peer to peer) access among them. If it is not enabled, the Holoscan inference module enables it by default. If P2P access is not possible between GPUs, then the data transfer will happen via the Host.

- Multi model inference with multiple backends on multiple GPUs.

```

backend_map:
  "model_1_unique_identifier": "trt"
  "model_2_unique_identifier": "torch"
  "model_3_unique_identifier": "torch"

```

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```

device_map:
  "model_1_unique_identifier": "1"
  "model_2_unique_identifier": "0"
  "model_3_unique_identifier": "1"
model_path_map:
  "model_1_unique_identifier": "path_to_model_1"
  "model_2_unique_identifier": "path_to_model_2"
  "model_3_unique_identifier": "path_to_model_3"
pre_processor_map:
  "model_1_unique_identifier": ["input_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["input_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["input_tensor_1_model_3_unique_identifier"]
inference_map:
  "model_1_unique_identifier": ["output_tensor_1_model_1_unique_identifier"]
  "model_2_unique_identifier": ["output_tensor_1_model_2_unique_identifier"]
  "model_3_unique_identifier": ["output_tensor_1_model_3_unique_identifier"]

```

In the sample above, three models are used during the inference. Model 1 uses the trt backend and runs on the GPU with ID 1, model 2 uses the torch backend and runs on the GPU with ID 0, and model 3 uses the torch backend and runs on the GPU with ID 1.

17.4 Creating an Inference operator

The Inference operator is the core inference unit in an inference application. The built-in Inference operator (InferenceOp) can be used for inference, or users can create their own custom inference operator as explained in this section. In Holoscan SDK, the inference operator can be designed using the Holoscan Inference Module APIs.

Arguments in the code sections below are referred to as

- Parameter Validity Check: Input inference parameters via the configuration (from step 1) are verified for correctness.

```
auto status = HoloInfer::inference_validity_check(...);
```

- Inference specification creation: For a single AI, only one entry is passed into the required entries in the parameter set. There is no change in the API calls below. Single AI or multi AI is enabled based on the number of entries in the parameter specifications from the configuration (in step 1).

```

// Declaration of inference specifications
std::shared_ptr<HoloInfer::InferenceSpecs> inference_specs_;

// Creation of inference specification structure
inference_specs_ = std::make_shared<HoloInfer::InferenceSpecs>(...);

```

- Inference context creation.

```

// Pointer to inference context.
std::unique_ptr<HoloInfer::InferContext> holoscan_infer_context_;
// Create holoscan inference context
holoscan_infer_context_ = std::make_unique<HoloInfer::InferContext>();

```

- Parameter setup with inference context: All required parameters of the Holoscan Inference Module are transferred in this step, and relevant memory allocations are initiated in the inference specification.

```
// Set and transfer inference specification to inference context
auto status = holoscan_infer_context_>set_inference_params(inference_specs_);
```

- Data extraction and allocation: The following API is used from the Holoinfer utility to extract and allocate data for the specified tensor.

```
// Extract relevant data from input, and update inference specifications
gxf_result_t stat = HoloInfer::get_data_per_model(...);
```

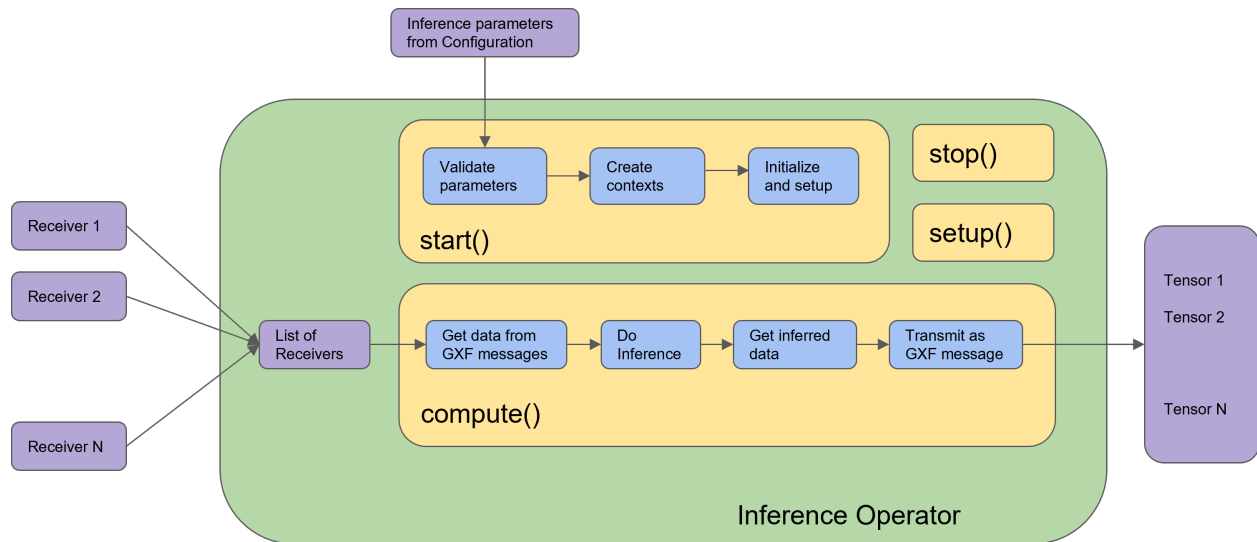
- Inference execution

```
// Execute inference and populate output buffer in inference specifications
auto status = holoscan_infer_context_>execute_inference(inference_specs_>data_per_
    ↪ model_,
                                                         inference_specs_>output_
    ↪ per_model_);
```

- Transmit inferred data:

```
// Transmit output buffers
auto status = HoloInfer::transmit_data_per_model(...);
```

Figure below demonstrates the Inference operator in the Holoscan SDK. All blocks with blue color are the API calls from the Holoscan Inference Module.



SCHEDULERS

The Scheduler component is a critical part of the system responsible for governing the execution of operators in a graph by enforcing conditions associated with each operator. Its primary responsibility includes orchestrating the execution of all operators defined in the graph while keeping track of their execution states.

The Holoscan SDK offers multiple schedulers that can cater to various use cases. These schedulers are:

1. *Greedy Scheduler*: This basic single-threaded scheduler tests conditions in a greedy manner. It is suitable for simple use cases and provides predictable execution. However, it may not be ideal for large-scale applications as it may incur significant overhead in condition execution.
2. *MultiThread Scheduler*: The MultiThread Scheduler is designed to handle complex execution patterns in large-scale applications. This scheduler consists of a dispatcher thread that monitors the status of each operator and dispatches it to a thread pool of worker threads responsible for executing them. Once execution is complete, worker threads enqueue the operator back on the dispatch queue. The MultiThread Scheduler offers superior performance and scalability over the Greedy Scheduler.

It is essential to select the appropriate scheduler for the use case at hand to ensure optimal performance and efficient resource utilization.

Note: Detailed APIs can be found here: C++/Python).

18.1 Greedy Scheduler

The greedy scheduler has a few parameters that the user can configure.

- The *clock* used by the scheduler can be set to either a *realtime* or *manual* clock.
 - The realtime clock is what should be used for applications as it pauses execution as needed to respect user specified conditions (e.g. operators with periodic conditions will wait the requested period before executing again).
 - The manual clock is of benefit mainly for testing purposes as it causes operators to run in a time-compressed fashion (e.g. periodic conditions are not respected and operators run in immediate succession).
- The user can specify a *max_duration_ms* that will cause execution of the application to terminate after a specified maximum duration. The default value of -1 (or any other negative value) will result in no maximum duration being applied.
- This scheduler also has a boolean parameter, *stop_on_deadlock* that controls whether the application will terminate if a deadlock occurs. A deadlock occurs when all operators are in a *WAIT* state, but there is no periodic condition pending to break out of this state. This parameter is *true* by default.

- When setting the `stop_on_deadlock_timeout` parameter, the scheduler will wait this amount of time (in ms) before determining that it is in deadlock and should stop. It will reset if a job comes in during the wait. A negative value means no stop on deadlock. This parameter only applies when `stop_on_deadlock=true`.

18.2 MultiThreadScheduler

The multithread scheduler has several parameters that the user can configure. These are a superset of the parameters available for the GreedyScheduler (described in the section above). Only the parameters unique to the multithread scheduler are described here.

- The number of worker threads used by the scheduler can be set via `worker_thread_number`, which defaults to 1. This should be set based on a consideration of both the workflow and the available hardware. For example, the topology of the computation graph will determine how many operators it may be possible to run in parallel. Some operators may potentially launch multiple threads internally, so some amount of performance profiling may be required to determine optimal parameters for a given workflow.
- The value of `check_recession_period_ms` controls how long the scheduler will sleep before checking a given condition again. In other words, this is the polling interval for operators that are in a `WAIT` state. The default value for this parameter is 5 ms.

CONDITIONS

The following table shows various states of the scheduling status of an operator:

Scheduling Status	Description
NEVER	Operator will never execute again
READY	Operator is ready for execution
WAIT	Operator may execute in the future
WAIT_TIME	Operator will be ready for execution after specified duration
WAIT_EVENT	Operator is waiting on an asynchronous event with unknown time interval

Note:

- A failure in execution of any single operator stops the execution of all the operators.
 - Operators are naturally unscheduled from execution when their scheduling status reaches NEVER state.
-

By default, operators are always READY, meaning they are scheduled to continuously execute their `compute()` method. To change that behavior, some condition classes can be passed to the constructor of an operator. There are various conditions currently supported in the Holoscan SDK:

- `MessageAvailableCondition`
- `DownstreamMessageAffordableCondition`
- `CountCondition`
- `BooleanCondition`
- `PeriodicCondition`
- `AsynchronousCondition`

Note: Detailed APIs can be found here: [C++/Python](#)).

Conditions are AND-combined

An Operator can be associated with multiple conditions which define its execution behavior. Conditions are AND combined to describe the current state of an operator. For an operator to be executed by the scheduler, all the conditions must be in READY state and conversely, the operator is unscheduled from execution whenever any one of the scheduling term reaches NEVER state. The priority of various states during AND combine follows the order NEVER, WAIT_EVENT, WAIT, WAIT_TIME, and READY.

19.1 MessageAvailableCondition

An operator associated with `MessageAvailableCondition` is executed when the associated queue of the input port has at least a certain number of elements. This condition is associated with a specific input port of an operator through the `condition()` method on the return value (`IOSpec`) of the `OperatorSpec`'s `input()` method.

The minimum number of messages that permits the execution of the operator is specified by `min_size` parameter (default: 1). An optional parameter for this condition is `front_stage_max_size`, the maximum front stage message count. If this parameter is set, the condition will only allow execution if the number of messages in the queue does not exceed this count. It can be used for operators which do not consume all messages from the queue.

19.2 DownstreamMessageAffordableCondition

This condition specifies that an operator shall be executed if the input port of the downstream operator for a given output port can accept new messages. This condition is associated with a specific output port of an operator through the `condition()` method on the return value (`IOSpec`) of the `OperatorSpec`'s `output()` method. The minimum number of messages that permits the execution of the operator is specified by `min_size` parameter (default: 1).

19.3 CountCondition

An operator associated with `CountCondition` is executed for a specific number of times specified using its `count` parameter. The scheduling status of the operator associated with this condition can either be in `READY` or `NEVER` state. The scheduling status reaches the `NEVER` state when the operator has been executed `count` number of times.

19.4 BooleanCondition

An operator associated with `BooleanCondition` is executed when the associated boolean variable is set to `true`. The boolean variable is set to `true/false` by calling the `enable_tick()/disable_tick()` methods on the `BooleanCondition` object. The `check_tick_enabled()` method can be used to check if the boolean variable is set to `true/false`. The scheduling status of the operator associated with this condition can either be in `READY` or `NEVER` state. If the boolean variable is set to `true`, the scheduling status of the operator associated with this condition is set to `READY`. If the boolean variable is set to `false`, the scheduling status of the operator associated with this condition is set to `NEVER`. The `enable_tick()/disable_tick()` methods can be called from any operator in the workflow.

C++

```
void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
    // ...
    if (<condition expression>) {           // e.g. if (index_ >= 10)
        auto my_bool_condition = condition<BooleanCondition>("my_bool_condition");
        if (my_bool_condition) {           // if condition exists (not true or false)
            my_bool_condition->disable_tick(); // this will stop the operator
        }
    }
    // ...
}
```

PYTHON

```
def compute(self, op_input, op_output, context):
    # ...
    if <condition expression>:           # e.g, self.index >= 10
        my_bool_condition = self.conditions.get("my_bool_condition")
        if my_bool_condition:           # if condition exists (not true or false)
            my_bool_condition.disable_tick() # this will stop the operator
    # ...
```

19.5 PeriodicCondition

An operator associated with `PeriodicCondition` is executed after periodic time intervals specified using its `recess_period` parameter. The scheduling status of the operator associated with this condition can either be in `READY` or `WAIT_TIME` state. For the first time or after periodic time intervals, the scheduling status of the operator associated with this condition is set to `READY` and the operator is executed. After the operator is executed, the scheduling status is set to `WAIT_TIME` and the operator is not executed until the `recess_period` time interval.

19.6 AsynchronousCondition

`AsynchronousCondition` is primarily associated with operators which are working with asynchronous events happening outside of their regular execution performed by the scheduler. Since these events are non-periodic in nature, `AsynchronousCondition` prevents the scheduler from polling the operator for its status regularly and reduces CPU utilization. The scheduling status of the operator associated with this condition can either be in `READY`, `WAIT`, `WAIT_EVENT` or `NEVER` states based on the asynchronous event it's waiting on.

The state of an asynchronous event is described using `AsynchronousEventState` and is updated using the `event_state()` API.

AsynchronousEventState	Description
READY	Init state, first execution of <code>compute()</code> method is pending
WAIT	Request to async service yet to be sent, nothing to do but wait
EVENT_WAITING	Request sent to an async service, pending event done notification
EVENT_DONE	Event done notification received, operator ready to be ticked
EVENT_NEVER	Operator does not want to be executed again, end of execution

Operators associated with this scheduling term most likely have an asynchronous thread which can update the state of the condition outside of its regular execution cycle performed by the scheduler. When the asynchronous event state is in `WAIT` state, the scheduler regularly polls for the scheduling state of the operator. When the asynchronous event state is in `EVENT_WAITING` state, schedulers will not check the scheduling status of the operator again until they receive an event notification. Setting the state of the asynchronous event to `EVENT_DONE` automatically sends the event notification to the scheduler. Operators can use the `EVENT_NEVER` state to indicate the end of its execution cycle.

RESOURCES

Resource classes represent resources such as allocators, clocks, transmitters or receivers that may be used as a parameter for operators or schedulers. The resource classes that are likely to be directly used by application authors are documented here.

Note: There are a number of other resources classes used internally which are not documented here, but appear in the API Documentation (C++/Python).

20.1 Allocator

20.1.1 UnboundedAllocator

An allocator that uses dynamic host or device memory allocation without an upper bound. This allocator does not take any user-specified parameters.

20.1.2 BlockMemoryPool

This is a memory pool which provides a user-specified number of equally sized blocks of memory.

- The `storage_type` parameter can be set to determine the memory storage type used by the operator. This can be 0 for page-locked host memory (allocated with `cudaMallocHost`), 1 for device memory (allocated with `cudaMalloc`) or 2 for system memory (allocated with C++ `new`).
- The `block_size` parameter determines the size of a single block in the memory pool in bytes. Any allocation requests made of this allocator must fit into this block size.
- The `num_blocks` parameter controls the total number of blocks that are allocated in the memory pool.
- The `dev_id` parameter is an optional parameter that can be used to specify the CUDA ID of the device on which the memory pool will be created.

20.1.3 CudaStreamPool

This allocator creates a pool of CUDA streams.

- The `stream_flags` parameter specifies the flags sent to `cudaStreamCreateWithPriority` when creating the streams in the pool.
- The `stream_priority` parameter specifies the priority sent to `cudaStreamCreateWithPriority` when creating the streams in the pool. Lower values have a higher priority.
- The `reserved_size` parameter specifies the initial number of CUDA streams created in the pool upon initialization.
- The `max_size` parameter is an optional parameter that can be used to specify a maximum number of CUDA streams that can be present in the pool. The default value of 0 means that the size of the pool is unlimited.
- The `dev_id` parameter is an optional parameter that can be used to specify the CUDA ID of the device on which the stream pool will be created.

20.2 Clock

Clock classes can be provided via a `clock` parameter to the `Scheduler` classes to manage the flow of time.

All clock classes provide a common set of methods that can be used at runtime in user applications.

- The `time()` method returns the current time in seconds (floating point).
- The `timestamp()` method returns the current time as an integer number of nanoseconds.
- The `sleep_for()` method sleeps for a specified duration in ns. An overloaded version of this method allows specifying the duration using a `std::chrono::duration<Rep, Period>` from the C++ API or a `date-time.timedelta` from the Python API.
- The `sleep_until()` method sleeps until a specified target time in ns.

20.2.1 Realtime Clock

The `RealtimeClock` respects the true duration of conditions such as `PeriodicCondition`. It is the default clock type and the one that would likely be used in user applications.

In addition to the general clock methods documented above:

- this class has a `set_time_scale()` method which can be used to dynamically change the time scale used by the clock.
- the parameter `initial_time_offset` can be used to set an initial offset in the time at initialization.
- the parameter `initial_time_scale` can be used to modify the scale of time. For instance, a scale of 2.0 would cause time to run twice as fast.
- the parameter `use_time_since_epoch` makes times relative to the `POSIX epoch` (`initial_time_offset` becomes an offset from epoch).

20.2.2 Manual Clock

The `ManualClock` compresses time intervals (e.g. `PeriodicCondition` proceeds immediately rather than waiting for the specified period). It is provided mainly for use during testing/development.

The parameter `initial_timestamp` controls the initial timestamp on the clock in ns.

20.3 Transmitter (advanced)

Typically users don't need to explicitly assign transmitter or receiver classes to the IOSpec ports of Holoscan SDK operators. For connections between operators a `DoubleBufferTransmitter` will automatically be used, while for connections between fragments in a distributed application, a `UcxTransmitter` will be used. When data frame flow tracking is enabled any `DoubleBufferTransmitter` will be replaced by an `AnnotatedDoubleBufferTransmitter` which also records the timestamps needed for that feature.

20.3.1 DoubleBufferTransmitter

This is the transmitter class used by output ports of operators within a fragment.

20.3.2 UcxTransmitter

This is the transmitter class used by output ports of operators that connect fragments in a distributed applications. It takes care of sending UCX active messages and serializing their contents.

20.4 Receiver (advanced)

Typically users don't need to explicitly assign transmitter or receiver classes to the IOSpec ports of Holoscan SDK operators. For connections between operators a `DoubleBufferReceiver` will be used, while for connections between fragments in a distributed application, the `UcxReceiver` will be used. When data frame flow tracking is enabled any `DoubleBufferReceiver` will be replaced by an `AnnotatedDoubleBufferReceiver` which also records the timestamps needed for that feature.

20.4.1 DoubleBufferReceiver

This is the receiver class used by input ports of operators within a fragment.

20.4.2 UcxReceiver

This is the receiver class used by input ports of operators that connect fragments in a distributed applications. It takes care of receiving UCX active messages and deserializing their contents.

HOLOSCAN APPLICATION PACKAGE SPECIFICATION (HAP)

21.1 Introduction

The Holoscan Application Package specification extends the MONAI Deploy Application Package specification to provide the streaming capabilities, multi-fragment and other features of the Holoscan SDK.

21.2 Overview

This document includes the specification of the Holoscan Application Package (HAP). A HAP is a containerized application or service which is self-descriptive, as defined by this document.

21.2.1 Goal

This document aims to define the structure and purpose of a HAP, including which parts are optional and which are required so that developers can easily create conformant HAPs.

21.2.2 Assumptions, Constraints, Dependencies

The following assumptions relate to HAP execution, inspection and general usage:

- Containerized applications will be based on Linux x64 (AMD64) and/or ARM64 (aarch64).
- Containerized applications' host environment will be based on Linux x64 (AMD64) and/or ARM64 (aarch64) with container support.
- Developers expect the local execution of their applications to behave identically to the execution of the containerized version.
- Developers expect the local execution of their containerized applications to behave identically to the execution in deployment.
- Developers and operations engineers want the application packages to be self-describing.
- Applications may be created using tool other than that provided in the Holoscan SDK or the MONAI Deploy App SDK.
- Holoscan Application Package may be created using a tool other than that provided in the Holoscan SDK or the MONAI Deploy App SDK.
- Pre-existing, containerized applications must be “converted” into Holoscan Application Packages.

- A Holoscan Application Package may contain a classical application (non-fragment based), a single-fragment application, or a multi-fragment application. (Please see the definition of fragment in [Definitions, Acronyms, Abbreviations](#))
- The scalability of a multi-fragment application based on Holoscan SDK is outside the scope of this document.
- Application packages are expected to be deployed in one of the supported environments. For additional information, see [Holoscan Operating Environments](#).

21.3 Definitions, Acronyms, Abbreviations

Term	Definition
ARM64	Or, AARCH64. See Wikipedia for details.
Container	See What's a container?
Fragment	A fragment is a building block of the Application. It is a directed graph of operators. For details, please refer to the MONAI Deploy App SDK or Holoscan App SDK.
Gigibytes (GiB)	A gibibyte (GiB) is a unit of measurement used in computer data storage that equals to 1,073,741,824 bytes.
HAP	Holoscan Application Package. A containerized application or service which is self-descriptive.
Hosting Service	A service that hosts and orchestrates HAP containers.
MAP	MONAI Application Package. A containerized application or service which is self-descriptive.
Mebibytes (MiB)	A mebibyte (MiB) is a unit of measurement used in computer data storage that equals to 1,048,576 bytes.
MONAI	Medical Open Network for Artificial Intelligence.
SDK	Software Development Kit.
Semantic Version	See Semantic Versioning 2.0 .
x64	Or, x86-64 or AMD64. See Wikipedia for details.

21.4 Requirements

The following requirements **MUST** be met by the HAP specification to be considered complete and approved. All requirements marked as **MUST** or **SHALL** **MUST** be implemented in order to be supported by a HAP-ready hosting service.

21.4.1 Single Artifact

- A HAP **SHALL** comprise a single container, meeting the minimum requirements set forth by this document.
- A HAP **SHALL** be a containerized application to maximize the portability of its application.

21.4.2 Self-Describing

- A HAP MUST be self-describing and provide a mechanism for extracting its description.
 - A HAP SHALL provide a method to print the metadata files to the console.
 - A HAP SHALL provide a method to copy the metadata files to a user-specified directory.
- The method of description SHALL be in a machine-readable and writable format.
- The method of description SHALL be in a human-readable format.
- The method of description SHOULD be a human writable format.
- The method of description SHALL be declarative and immutable.
- The method of description SHALL provide the following information about the HAP:
 - Execution requirements such as dependencies and restrictions.
 - Resource requirements include CPU cores, system memory, shared memory, GPU, and GPU memory.

21.4.3 Runtime Characteristics of the HAP

- A HAP SHALL start the packaged Application when it is executed by the users when arguments are specified.
- A HAP SHALL describe the packaged Application as a long-running service or an application so an external agent can manage its lifecycle.

21.4.4 IO Specification

- A HAP SHALL provide information about its expected inputs such that an external agent can determine if the HAP can receive a workload.
- A HAP SHALL provide sufficient information about its outputs so that an external agent knows how to handle the results.

21.4.5 Local Execution

A HAP MUST be in a format that supports local execution in a development environment.

[Note] See *Holoscan Operating Environments* for additional information about supported environments.

21.4.6 Compatible with Kubernetes

- A HAP SHALL support deployment using Kubernetes.

21.4.7 OCI Compliance

The containerized portion of a HAP SHALL comply with [Open Container Initiative](#) format standards.

Image Annotations

All annotations for the containerized portion of a HAP MUST adhere to the specifications laid out by [The OpenContainers Annotations Spec](#)

- `org.opencontainers.image.title`: A HAP container image SHALL provide a human-readable title (string).
- `org.opencontainers.image.version`: A HAP container image SHALL provide a version of the packaged application using the semantic versioning format. This value is the same as the value defined in `/etc/holoscan/app.json#version` in the *Table of Application Manifest Fields*.
- All other OpenContainers predefined keys SHOULD be provided when available.

21.4.8 Hosting Environment

The HAP Hosting Environment executes the HAP and provides the application with a customized set of environment variables and command line options as part of the invocation.

- The Hosting Service MUST, by default, execute the application as defined by `/etc/holoscan/app.json#command` and then exit when the application or the service completes.
- The Hosting Service MUST provide any environment variables specified by `/etc/holoscan/app.json#environment`.
- The Hosting Service SHOULD monitor the Application process and record its CPU, system memory, and GPU utilization metrics.
- The Hosting Service SHOULD monitor the Application process and enforce any timeout value specified in `/etc/holoscan/app.json#timeout`.

Table of Environment Variables

A HAP SHALL contain the following environment variables and their default values, if not specified by the user, in the Application Manifest `/etc/holoscan/app.json#environment`.

Variable	Default	Format	Description
HOLOSCAN_INPUT_PATH	<code>/var/holoscan/input/</code>	Folder Path	Path to the input folder for the Application.
HOLOSCAN_OUTPUT_PATH	<code>/var/holoscan/output/</code>	Folder Path	Path to the output folder for the Application.
HOLOSCAN_WORKDIR	<code>/var/holoscan/</code>	Folder Path	Path to the Application's working directory.
HOLOSCAN_MODEL_PATH	<code>/opt/holoscan/models/</code>	Folder Path	Path to the Application's models directory.
HOLOSCAN_CONFIG_PATH	<code>/var/holoscan/app.yaml</code>	File Path	Path to the Application's configuration file.
HOLOSCAN_APP_MANIFEST_PATH	<code>/var/holoscan/app.config</code>	File Path	Path to the Application's configuration file.
HOLOSCAN_PKG_MANIFEST_PATH	<code>/var/holoscan/pkg.config</code>	File Path	Path to the Application's configuration file.
HOLOSCAN_DOCS	<code>/opt/holoscan/docs</code>	Folder Path	Path to the folder containing application documentation and licenses.
HOLOSCAN_LOGS	<code>/var/holoscan/logs</code>	Folder Path	Path to the Application's logs.

21.5 Architecture & Design

21.5.1 Description

The Holoscan Application Package (HAP) is a functional package designed to act on datasets of a prescribed format. A HAP is a container image that adheres to the specification provided in this document.

21.5.2 Application

The primary component of a HAP is the application. The application is provided by an application developer and incorporated into the HAP using the Holoscan Application Packager.

All application code and binaries SHALL be in the `/opt/holoscan/app/` folder, except for any dependencies installed by the Holoscan Application Packager during the creation of the HAP.

All AI models (PyTorch, TensorFlow, TensorRT, etc.) SHOULD be in separate sub-folders of the `/opt/holoscan/models/` folder. In specific use cases where the app package developer is prevented from enclosing the model files in the package/container due to intellectual property concerns, the models can be supplied from the host system when the app package is run, e.g., via the volume mount mappings and the use of container env variables.

21.5.3 Manifests

A HAP SHALL contain two manifests: the Application Manifest and the Package Manifest. The Package Manifest shall be stored in `/etc/holoscan/pkg.json`, and the Application Manifest shall be stored in `/etc/holoscan/app.json`. Once a HAP is created, its manifests are expected to be immutable.

Application Manifest

Table of Application Manifest Fields

Name	Required	Default	Type	Format
<code>apiVersion</code>	No	0.0.0	string	semantic version
<code>command</code>	Yes	N/A	string	shell command
<code>environment</code>	No	N/A	object	object w/ name-value pairs
<code>input</code>	Yes	N/A	object	object
<code>input.formats</code>	Yes	N/A	array	array of objects
<code>input.path</code>	No	<code>input/</code>	string	relative file-system path
<code>readiness</code>	No	N/A	object	object
<code>readiness.type</code>	Yes	N/A	string	string
<code>readiness.command</code>	Yes (when type is <code>command</code>)	N/A	array	shell command
<code>readiness.port</code>	Yes (when type is <code>tcp</code> , <code>grpc</code> , or <code>http-get</code>)	N/A	integer	number
<code>readiness.path</code>	Yes (when type is <code>http-get</code>)	N/A	string	string
<code>readiness.initialDelaySeconds</code>	No	1	integer	number
<code>readiness.periodSeconds</code>	No	10	integer	number
<code>readiness.timeoutSeconds</code>	No	1	integer	number
<code>readiness.failureThreshold</code>	No	3	integer	number
<code>liveness</code>	No	N/A	object	object
<code>liveness.type</code>	Yes	N/A	string	string
<code>liveness.command</code>	Yes (when type is <code>command</code>)	N/A	array	shell command
<code>liveness.port</code>	Yes (when type is <code>tcp</code> , <code>grpc</code> , or <code>http-get</code>)	N/A	integer	number
<code>liveness.path</code>	Yes (when type is <code>http-get</code>)	N/A	string	string
<code>liveness.initialDelaySeconds</code>	No	1	integer	number
<code>liveness.periodSeconds</code>	No	10	integer	number
<code>liveness.timeoutSeconds</code>	No	1	integer	number
<code>liveness.failureThreshold</code>	No	3	integer	number
<code>output</code>	Yes	N/A	object	object
<code>output.format</code>	Yes	N/A	object	object
<code>output.path</code>	No	<code>output/</code>	string	relative file-system path
<code>sdk</code>	No	N/A	string	string
<code>sdkVersion</code>	No	0.0.0	string	semantic version
<code>timeout</code>	No	0	integer	number
<code>version</code>	No	0.0.0	string	semantic version
<code>workingDirectory</code>	No	<code>/var/holoscan/</code>	string	absolute file-system path

The Application Manifest file provides information about the HAP's Application.

- The Application Manifest MUST define the type of the containerized application (`/etc/holoscan/app.json#type`).
 - Type SHALL have the value of either `service` or `application`.

- The Application Manifest MUST define the command used to run the Application (`/etc/holoscan/app.json#command`).
- The Application Manifest SHOULD define the version of the manifest file schema (`/etc/holoscan/app.json#apiVersion`).
 - The Manifest schema version SHALL be provided as a [semantic version](#) string.
 - When not provided, the default value `0.0.0` SHALL be assumed.
- The Application Manifest SHOULD define the SDK used to create the Application (`/etc/holoscan/app.json#sdk`).
- The Application Manifest SHOULD define the version of the SDK used to create the Application (`/etc/holoscan/app.json#sdkVersion`).
 - SDK version SHALL be provided as a [semantic version](#) string.
 - When not provided, the default value `0.0.0` SHALL be assumed.
- The Application Manifest SHOULD define the version of the application itself (`/etc/holoscan/app.json#version`).
 - The Application version SHALL be provided as a [semantic version](#) string.
 - When not provided, the default value `0.0.0` SHALL be assumed.
- The Application Manifest SHOULD define the application's working directory (`/etc/holoscan/app.json#workingDirectory`).
 - The Application will execute with its current directory set to this value.
 - The value provided must be an absolute path (the first character is `/`).
 - The default path `/var/holoscan/` SHALL be assumed when not provided.
- The Application Manifest SHOULD define the data input path, relative to the working directory, used by the Application (`/etc/holoscan/app.json#input.path`).
 - The input path SHOULD be a relative to the working directory or an absolute file-system path to a directory.
 - * When the value is a relative file-system path (the first character is not `/`), it is relative to the application's working directory.
 - * When the value is an absolute file-system path (the first character is `/`), the file-system path is used as-is.
 - When not provided, the default value `input/` SHALL be assumed.
- The Application Manifest SHOULD define input data formats supported by the Application (`/etc/holoscan/app.json#input.formats`).
 - Possible values include, but are not limited to, `none`, `network`, `file`.
- The Application Manifest SHOULD define the output path relative to the working directory used by the Application (`/etc/holoscan/app.json#output.path`).
 - The output path SHOULD be relative to the working directory or an absolute file-system path to a directory.
 - * When the value is a relative file-system path (the first character is not `/`), it is relative to the application's working directory.
 - * When the value is an absolute file-system path (the first character is `/`), the file-system path is used as-is.
 - When not provided, the default value `output/` SHALL be assumed.

- The Application Manifest SHOULD define the output data format produced by the Application (`/etc/holoscan/app.json#output.format`).
 - Possible values include, but are not limited to, `none`, `screen`, `file`, `network`.
- The Application Manifest SHOULD configure a check to determine whether or not the application is “ready.”
 - The Application Manifest SHALL define the probe type to be performed (`/etc/holoscan/app.json#readiness.type`).
 - * Possible values include `tcp`, `grpc`, `http-get`, and `command`.
 - The Application Manifest SHALL define the probe commands to execute when the type is `command` (`/etc/holoscan/app.json#readiness.command`).
 - * The data structure is expected to be an array of strings.
 - The Application Manifest SHALL define the port to perform the readiness probe when the type is `grpc`, `tcp`, or `http-get`. (`/etc/holoscan/app.json#readiness.port`)
 - * The value provided must be a valid port number ranging from 1 through 65535. (Please note that port numbers below 1024 are root-only privileged ports.)
 - The Application Manifest SHALL define the path to perform the readiness probe when the type is `http-get` (`/etc/holoscan/app.json#readiness.path`).
 - * The value provided must be an absolute path (the first character is `/`).
 - The Application Manifest SHALL define the number of seconds after the container has started before the readiness probe is initiated. (`/etc/holoscan/app.json#readiness.initialDelaySeconds`).
 - * The default value `0` SHALL be assumed when not provided.
 - The Application Manifest SHALL define how often to perform the readiness probe (`/etc/holoscan/app.json#readiness.periodSeconds`).
 - * When not provided, the default value `10` SHALL be assumed.
 - The Application Manifest SHALL define the number of seconds after which the probe times out (`/etc/holoscan/app.json#readiness.timeoutSeconds`).
 - * When not provided, the default value `1` SHALL be assumed.
 - The Application Manifest SHALL define the number of times to perform the probe before considering the service is not ready (`/etc/holoscan/app.json#readiness.failureThreshold`).
 - * The default value `3` SHALL be assumed when not provided.
- The Application Manifest SHOULD configure a check to determine whether or not the application is “live” or not.
 - The Application Manifest SHALL define the type of probe to be performed (`/etc/holoscan/app.json#liveness.type`).
 - * Possible values include `tcp`, `grpc`, `http-get`, and `command`.
 - The Application Manifest SHALL define the probe commands to execute when the type is `command` (`/etc/holoscan/app.json#liveness.command`).
 - * The data structure is expected to be an array of strings.
 - The Application Manifest SHALL define the port to perform the liveness probe when the type is `grpc`, `tcp`, or `http-get`. (`/etc/holoscan/app.json#liveness.port`)
 - * The value provided must be a valid port number ranging from 1 through 65535. (Please note that port numbers below 1024 are root-only privileged ports.)

- The Application Manifest SHALL define the path to perform the liveness probe when the type is `http-get` (`/etc/holoscan/app.json#liveness.path`).
 - * The value provided must be an absolute path (the first character is `/`).
- The Application Manifest SHALL define the number of seconds after the container has started before the liveness probe is initiated. (`/etc/holoscan/app.json#liveness.initialDelaySeconds`).
 - * The default value `0` SHALL be assumed when not provided.
- The Application Manifest SHALL define how often to perform the liveness probe (`/etc/holoscan/app.json#liveness.periodSeconds`).
 - * When not provided, the default value `10` SHALL be assumed.
- The Application Manifest SHALL define the number of seconds after which the probe times out (`/etc/holoscan/app.json#liveness.timeoutSeconds`).
 - * The default value `1` SHALL be assumed when not provided.
- The Application Manifest SHALL define the number of times to perform the probe before considering the service is not alive (`/etc/holoscan/app.json#liveness.failureThreshold`).
 - * When not provided, the default value `3` SHALL be assumed.
- The Application Manifest SHOULD define any timeout applied to the Application (`/etc/holoscan/app.json#timeout`).
 - When the value is `0`, timeout SHALL be disabled.
 - When not provided, the default value `0` SHALL be assumed.
- The Application Manifest MUST enable the specification of environment variables for the Application (`/etc/holoscan/app.json#environment`).
 - The data structure is expected to be in `"name": "value"` members of the object.
 - The field's name will be the name of the environment variable verbatim and must conform to all requirements for environment variables and JSON field names.
 - The field's value will be the value of the environment variable and must conform to all requirements for environment variables.

Package Manifest

Table of Package Manifest Fields

Name	Re- quired	Default	Type	Format	Description
apiVersion	No	0.0.0	string	semantic version	Version of the manifest file schema.
applicationRoot	Yes	/opt/holoscan/app/	string	absolute file-system path	Absolute file-system path to the folder which contains the Application
modelRoot	No	/opt/holoscan/models/	string	absolute file-system path	Absolute file-system path to the folder which contains the model(s).
models	No	N/A	array	array of objects	Array of objects which describe models in the package.
models[*].name	Yes	N/A	string	string	Name of the model.
models[*].path	No	N/A	string	Relative file-system path	File-system path to the folder which contains the model that is relative to the value defined in modelRoot.
resources	No	N/A	object	object	Object describing resource requirements for the Application.
resources.cpu	No	1	decimal (2)	number	Number of CPU cores required by the Application or the Fragment.
resources.cpuLimit	No	N/A	decimal (2)	number	The CPU core limit for the Application or the Fragment. (1)
resources.gpu	No	0	decimal (2)	number	Number of GPU devices required by the Application or the Fragment.
resources.gpuLimit	No	N/A	decimal (2)	number	The GPU device limit for the Application or the Fragment. (1)
resources.memory	No	1Gi	string	memory size	The memory required by the Application or the Fragment.
resources.memoryLimit	No	N/A	string	memory size	The memory limit for the Application or the Fragment. (1)
resources.gpuMemory	No	N/A	string	memory size	The GPU memory required by the Application or the Fragment.
resources.gpuMemoryLimit	No	N/A	string	memory size	The GPU memory limit for the Application or the Fragment. (1)
resources.sharedMemory	No	64Mi	string	memory size	The shared memory required by the Application or the Fragment.
resources.fragments	No	N/A	object	objects	Nested objects which describe resources for a Multi-Fragment Application.
resources.fragments.<fragment-name>	Yes	N/A	string	string	Name of the fragment.
resources.fragments.<fragment-name>.cpu	No	1	decimal (2)	number	Number of CPU cores required by the Fragment.
resources.fragments.<fragment-name>.	No	N/A	decimal (2)	number	The CPU core limit for the Fragment. (1)
resources.fragments.<fragment-name>.gpu	No	0	decimal (2)	number	Number of GPU devices required by the Fragment.
resources.fragments.<fragment-name>.gpuLimit	No	N/A	decimal (2)	number	The GPU device limit for the Fragment. (1)

[Notes] (1) Use of resource limits depend on the orchestration service or the hosting environment's configuration and implementation. (2) Consider rounding up to a whole number as decimal values may not be supported by all orchestration/hosting services.

The Package Manifest file provides information about the HAP's package layout. It is not intended as a mechanism for controlling how the HAP is used or how the HAP's Application is executed.

- The Package Manifest **MUST** be UTF-8 encoded and use the JavaScript Object Notation (JSON) format.
- The Package Manifest **SHOULD** support either CRLF or LF style line endings.
- The Package Manifest **SHOULD** specify the folder which contains the application (`/etc/holoscan/pkg.json#applicationRoot`).
 - When not provided, the default path `/opt/holoscan/app/` will be assumed.
- The Package Manifest **SHOULD** provide the version of the package file manifest schema (`/etc/holoscan/pkg.json#apiVersion`).
 - The Manifest schema version **SHALL** be provided as a [semantic version](#) string.
- The Package Manifest **SHOULD** provide the package version of itself (`/etc/holoscan/pkg.json#version`).
 - The Package version **SHALL** be provided as a [semantic version](#) string.
- The Package Manifest **SHOULD** provide the directory path to the user-provided models. (`/etc/holoscan/pkg.json#modelRoot`).
 - The value provided must be an absolute path (the first character is `/`).
 - When not provided, the default path `/opt/holoscan/models/` **SHALL** be assumed.
- The Package Manifest **SHOULD** list the models used by the application (`/etc/holoscan/pkg.json#models`).
 - Models **SHALL** be defined by name (`/etc/holoscan/pkg.json#models[*].name`).
 - * Model names **SHALL NOT** contain any Unicode whitespace or control characters.
 - * Model names **SHALL NOT** exceed 128 bytes in length.
 - Models **SHOULD** provide a file-system path if they're included in the HAP itself (`/etc/holoscan/pkg.json#models[*].path`).
 - * When the value is a relative file-system path (the first character is not `/`), it is relative to the model root directory defined in `/etc/holoscan/pkg.json#modelRoot`.
 - * When the value is an absolute file-system path (the first character is `/`), the file-system path is used as-is.
 - * When no value is provided, the name is assumed as the name of the directory relative to the model root directory defined in `/etc/holoscan/pkg.json#modelRoot`.
- The Package Manifest **SHOULD** specify the resources required to execute the Application and the fragments for a Multi-Fragment Application.

This information is used to provision resources when running the containerized application using a compatible application deployment service.
- A classic Application or a single Fragment Application **SHALL** define its resources in the `/etc/holoscan/pkg.json#resource` object.
 - The `/etc/holoscan/pkg.json#resource` object is for the whole application. It **CAN** also be used as a catchall for all fragments in a multi-fragment application where applicable.
 - CPU requirements **SHALL** be denoted using the decimal count of CPU cores (`/etc/holoscan/pkg.json#resources.cpu`).

- Optional CPU limits SHALL be denoted using the decimal count of CPU cores (`/etc/holoscan/pkg.json#resources.cpuLimit`)
- GPU requirements SHALL be denoted using the decimal count of GPUs (`/etc/holoscan/pkg.json#resources.gpu`).
- Optional GPU limits SHALL be denoted using the decimal count of GPUs (`/etc/holoscan/pkg.json#resources.gpuLimit`)
- Memory requirements SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.memory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- Optional memory limits SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.memoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- GPU memory requirements SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.gpuMemory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- Optional GPU memory limits SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.gpuMemoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- Shared memory requirements SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.sharedMemory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- Optional shared memory limits SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.sharedMemoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
- Integer values MUST be positive and not contain any position separators.
 - * Example legal values: 1, 42, 2048
 - * Example illegal values: -1, 1.5, 2,048
- Decimal values MUST be positive, rounded to the nearest tenth, use the dot (.) character to separate whole and fractional values, and not contain any positional separators.
 - * Example legal values: 1, 1.0, 0.5, 2.5, 1024
 - * Example illegal values: 1,024, -1.0, 3.14
- When not provided, the default values of `cpu=1`, `gpu=0`, `memory="1Gi"`, and `sharedMemory="64Mi"` will be assumed.

- A Multi-Fragment Application SHOULD define its resources in the `/etc/holoscan/pkg.json#resource.fragments.<fragment-name>` object.
 - When a matching `fragment-name` cannot be found, the `/etc/holoscan/pkg.json#resource` definition is used.
 - Fragment names (`fragment-name`) SHALL NOT contain any Unicode whitespace or control characters.
 - Fragment names (`fragment-name`) SHALL NOT exceed 128 bytes in length.
 - CPU requirements for fragments SHALL be denoted using the decimal count of CPU cores (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.cpu`).
 - Optional CPU limits for fragments SHALL be denoted using the decimal count of CPU cores (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.cpuLimit`).
 - GPU requirements for fragments SHALL be denoted using the decimal count of GPUs (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.gpu`).
 - Optional GPU limits for fragments SHALL be denoted using the decimal count of GPUs (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.gpuLimit`).
 - Memory requirements for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.memory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - Optional memory limits for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.memoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - GPU memory requirements for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.gpuMemory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - Optional GPU memory limits for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.gpuMemoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - Shared memory requirements for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.sharedMemory`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - Optional shared memory limits for fragments SHALL be denoted using decimal values followed by units (`/etc/holoscan/pkg.json#resources.fragments.<fragment-name>.sharedMemoryLimit`).
 - * Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).
 - Example: 1.5Gi, 2048Mi
 - Integer values MUST be positive and not contain any position separators.
 - * Example legal values: 1, 42, 2048

- * Example illegal values: -1, 1.5, 2,048
- Decimal values MUST be positive, rounded to the nearest tenth, use the dot (.) character to separate whole and fractional values, and not contain any positional separators.
 - * Example legal values: 1, 1.0, 0.5, 2.5, 1024
 - * Example illegal values: 1,024, -1.0, 3.14
- When not provided, the default values of `cpu=1`, `gpu=0`, `memory="1Gi"`, and `sharedMemory="64Mi"` will be assumed.

21.6 Supplemental Application Files

- A HAP SHOULD package supplemental application files provided by the user.
 - Supplemental files SHOULD be in sub-folders of the `/opt/holoscan/docs/` folder.
 - Supplemental files include, but are not limited to, the following:
 - * `README.md`
 - * `License.txt`
 - * `Changelog.txt`
 - * `EULA`
 - * `Documentation`
 - * Third-party licenses

21.6.1 Container Behavior and Interaction

A HAP is a single container supporting the following defined behaviors when started.

Default Behavior

When a HAP is started from the CLI or other means without any parameters, the HAP shall execute the contained application. The HAP internally may use `Entrypoint`, `CMD`, or a combination of both.

Manifest Export

A HAP SHOULD provide at least one method to access the *embedded application*, *models*, *licenses*, *README*, or *manifest files*, namely, `app.json` and `package.json`.

- The Method SHOULD provide a container command, `show`, to print one or more manifest files to the console.
- The Method SHOULD provide a container command, `export`, to copy one or more manifest files to a mounted volume path, as described below
 - `/var/run/holoscan/export/app/`: when detected, the Method copies the contents of `/opt/holoscan/app/` to the folder.
 - `/var/run/holoscan/export/config/`: when detected, the Method copies `/var/holoscan/app.yaml`, `/etc/holoscan/app.json` and `/etc/holoscan/pkg.json` to the folder.
 - `/var/run/holoscan/export/models/`: when detected, the Method copies the contents of `/opt/holoscan/models/` to the folder.

- `/var/run/holoscan/export/docs/`: when detected, the Method copies the contents of `/opt/holoscan/docs/` to the folder.
- `/var/run/holoscan/export/`: when detected without any of the above being detected, the Method SHALL copy all of the above.

Since a HAP is an OCI compliant container, a user can also run a HAP and log in to an interactive shell, using a method supported by the container engine and its command line interface, e.g. Docker supports this by setting the `entrypoint` option. The files in the HAP can then be opened or copied to the mapped volumes with shell commands or scripts. A specific implementation of a HAP may choose to streamline such a process with scripts and applicable user documentation.

21.6.2 Table of Important Paths

Path	Purpose
<code>/etc/holoscan/</code>	HAP manifests and immutable configuration files.
<code>/etc/holoscan/app.json</code>	Application Manifest file.
<code>/etc/holoscan/pkg.json</code>	Package Manifest file.
<code>/opt/holoscan/app/</code>	Application code, scripts, and other files.
<code>/opt/holoscan/models/</code>	AI models. Each model should be in a separate sub-folder.
<code>/opt/holoscan/docs/</code>	Documentation, licenses, EULA, changelog, etc...
<code>/var/holoscan/</code>	Default working directory.
<code>/var/holoscan/input/</code>	Default input directory.
<code>/var/holoscan/output/</code>	Default output directory.
<code>/var/run/holoscan/export/</code>	Special case folder, causes the Script to export contents related to the app. (see: Manifest Export)
<code>/var/run/holoscan/export/app/</code>	Special case folder, causes the Script to export the contents of <code>/opt/holoscan/app/</code> to the folder.
<code>/var/run/holoscan/export/config/</code>	Special case folder, causes the Script to export <code>/etc/holoscan/app.json</code> and <code>/etc/holoscan/pkg.json</code> to the folder.
<code>/var/run/holoscan/export/models/</code>	Special case folder, causes the Script to export the contents of <code>/opt/holoscan/models/</code> to the folder.

21.7 Operating Environments

Holoscan SDK supports the following operating environments.

Operating Environment Name	Characteristics
AGX Devkit	Clara AGX devkit with RTX 6000 dGPU only
IGX Orin Devkit	Clara Holoscan devkit with A6000 dGPU only
IGX Orin Devkit - integrated GPU only	IGX Orin Devkit, iGPU only
IGX Orin Devkit with discrete GPU	IGX Orin Devkit, with RTX A6000 dGPU
Jetson AGX Orin Devkit	Jetson Orin Devkit, iGPU only
Jetson Orin Nano Devkit	Jetson Orin Nano Devkit, iGPU only
X86_64	dGPU only on Ubuntu 18.04 and 20.04

HOLOSCAN CLI

holoscan - a command-line interface for packaging and running your Holoscan applications into *HAP-compliant* containers.

22.1 Synopsis

holoscan [*--help|-h*] [*--log-level|-l* {*DEBUG,INFO,WARN,ERROR,CRITICAL*}] {*package,run,version*}

22.2 Positional Arguments

22.2.1 Holoscan CLI - Package Command

holoscan package - generate *HAP-compliant* container for your application.

Synopsis

holoscan package [*--help|-h*] [*--log-level|-l* {*DEBUG,INFO,WARN,ERROR,CRITICAL*}] *--config|-c* *CONFIG* [*--docs|-d* *DOCS*] [*--models|-m* *MODELS*] *--platform* *PLATFORM* [*--platform-config* *PLATFORM_CONFIG*] [*--timeout* *TIMEOUT*] [*--version* *VERSION*] [*--base-image* *BASE_IMAGE*] [*--build-image* *BUILD_IMAGE*] [*--build-cache* *BUILD_CACHE*] [*--cmake-args* *CMAKE_ARGS*] [*--no-cache|-n*] [*--sdk* *SDK*] [*--sdk-version* *SDK_VERSION*] [*--holoscan-sdk-file* *HOLOSCAN_SDK_FILE*] [*--monai-deploy-sdk-file* *MONAI_DEPLOY_SDK_FILE*] [*--output|-o* *OUTPUT*] *--tag|-t* *TAG* [*--username* *USERNAME*] [*--uid* *UID*] [*--gid* *GID*] *application*

Examples

The code below package a python application for x86_64 systems:

```
# Using a Python directory as input
# Required: a `__main__.py` file in the application directory to execute
# Optional: a `requirements.txt` file in the application directory to install dependencies
holoscan package --platform x64-workstation --tag my-awesome-app --config /path/to/my/
↳ awesome/application/config.yaml /path/to/my/awesome/application/

# Using a Python file as input
holoscan package --platform x64-workstation --tag my-awesome-app --config /path/to/my/
↳ awesome/application/config.yaml /path/to/my/awesome/application/my-app.py
```

The code below package a C++ application for the IGX Orin DevKit (aarch64) with a discrete GPU:

```
# Using a C++ source directory as input
# Required: a `CMakeLists.txt` file in the application directory
holoscan package --platform igx-orin-devkit --platform-config dgpu --tag my-awesome-app -
↪-config /path/to/my/awesome/application/config.yaml /path/to/my/awesome/application/

# Using a C++ pre-compiled executable as input
holoscan package --platform igx-orin-devkit --platform-config dgpu --tag my-awesome-app -
↪-config /path/to/my/awesome/application/config.yaml /path/to/my/awesome/bin/
↪application-executable
```

Note: The commands above load the generated image onto Docker to make the image accessible with docker images.

If you need to package for a different platform or want to transfer the generated image to another system, use the `--output /path/to/output` flag so the generated package can be saved to the specified location.

Positional Arguments

application

Path to the application to be packaged. The following inputs are supported:

- **C++ source code:** you may pass a directory path with your C++ source code with a `CMakeLists.txt` file in it, and the **Packager** will attempt to build your application using CMake and include the compiled application in the final package.
- **C++ pre-compiled executable:** A pre-built executable binary file may be directly provided to the **Packager**.
- **Python application:** you may pass either:
 - a directory which includes a `__main__.py` file to execute (required) and an optional `requirements.txt` file that defined dependencies for your Python application, or
 - the path to a single python file to execute

Warning: Python (PyPI) modules are installed into the user's (via `[--username USERNAME]` argument) directory with the user ID specified via `[--uid UID]`. Therefore, when running a packaged Holoscan application on Kubernetes or other service providers, running Docker with non root user, and running Holoscan CLI `run` command where the logged-on user's ID is different, ensure to specify the `USER` ID that is used when building the application package.

For example, include the `securityContext` when running a Holoscan packaged application with `UID=1000` using Argo:

```
spec:
  securityContext:
    runAsUser: 1000
    runAsNonRoot: true
```

Flags

`--config|-c CONFIG`

Path to the application's *configuration file*. The configuration file must be in YAML format with a `.yaml` file extension.

`[--docs|-d DOCS]`

An optional directory path of documentation, README, licenses that shall be included in the package.

`[--models|-m MODELS]`

An optional directory path to a model file, a directory with a single model, or a directory with multiple models.

Single model example:

```

my-model/
├── surgical_video.gxf_entities
└── surgical_video.gxf_index

my-model/
└── model
    ├── surgical_video.gxf_entities
    └── surgical_video.gxf_index

```

Multi-model example:

```

my-models/
├── model-1
│   ├── my-first-model.gxf_entities
│   └── my-first-model.gxf_index
└── model-2
    └── my-other-model.ts

```

`--platform PLATFORM`

A comma-separated list of platform types to generate. Each platform value specified generates a standalone container image. If you are running the **Packager** on the same architecture, the generated image is automatically loaded onto Docker and is available with `docker images`. Otherwise, use `--output` flag to save the generated image onto the disk.

PLATFORM must be one of: `clara-agx-devkit`, `igx-orin-devkit`, `jetson-agx-orin-devkit`, `x64-workstation`.

- `clara-agx-devkit`: Clara AGX DevKit
- `igx-orin-devkit`: IGX Orin DevKit
- `jetson-agx-orin-devkit`: Orin AGX DevKit
- `x64-workstation`: systems with a `x86-64` processor(s)

`[--platform-config PLATFORM_CONFIG]`

Specifies the platform configuration to generate. PLATFORM_CONFIG must be one of: `igpu`, `igpu-assist`, `dgpu`.

- `igpu`: Supports integrated GPU
- `igpu-assist`: Supports compute-only tasks on iGPU in presence of a dGPU
- `dgpu`: Supports dedicated GPU

Note: `--platform-config` is required when `--platform` is not `x64-workstation` (which uses `dgpu`).

`[--timeout TIMEOUT]`

An optional timeout value of the application for the supported orchestrators to manage the application's lifecycle. Defaults to 0.

`[--version VERSION]`

An optional version number of the application. When specified, it overrides the value specified in the *configuration file*.

`[--base-image BASE_IMAGE]`

Optionally specifies the base container image for building packaged application. It must be a valid Docker image tag either accessible online or via ``docker`` images. By default, the **Packager** picks a base image to use from NGC.

`[--build-image BUILD_IMAGE]`

Optionally specifies the build container image for building C++ applications. It must be a valid Docker image tag either accessible online or via ``docker`` images. By default, the **Packager** picks a build image to use from NGC.

`[--build-cache BUILD_CACHE]`

Specifies a directory path for storing Docker cache. Defaults to `~/holoscan_build_cache`.

`[--cmake-args CMAKE_ARGS]`

A comma-separated list of *cmake* arguments to be used when building C++ applications.

For example:

```
holoscan package --cmake-args "-DCMAKE_BUILD_TYPE=DEBUG -DCMAKE_ARG=VALUE"
```

[--no-cache|-n]

Do not use cache when building image.

[--sdk SDK]

SDK for building the application: Holoscan or MONAI-Deploy. SDK must be one of: holoscan, monai-deploy.

[--sdk-version SDK_VERSION]

Set the version of the SDK that is used to build and package the Application. If not specified, the packager attempts to detect the installed version.

[--holoscan-sdk-file HOLOSCAN_SDK_FILE]

Path to the Holoscan SDK Debian or PyPI package. If not specified, the packager downloads the SDK file from the internet depending on the SDK version detected/specified. The HOLOSCAN_SDK_FILE filename must have .deb or .whl file extension for Debian package or PyPI wheel package, respectively.

[--monai-deploy-sdk-file MONAI_DEPLOY_SDK_FILE]

Path to the MONAI Deploy App SDK Debian or PyPI package. If not specified, the packager downloads the SDK file from the internet based on the SDK version. The MONAI_DEPLOY_SDK_FILE package filename must have .whl or .gz file extension.

[--output|-o OUTPUT]

Output directory where result images will be written.

Note: If this flag isn't present, the packager will load the generated image onto Docker to make the image accessible with `docker images`. The `--output` flag is therefore required when building a packaging for a different target architecture than the host system that runs the packager.

--tag|-t TAG

Name and optionally a tag (format: `name:tag`).

For example:

```
my-company/my-application:latest
my-company/my-application:1.0.0
my-application:1.0.1
my-application
```

`[--username USERNAME]`

Optional *username* to be created in the container execution context. Defaults to `holoscan`.

`[--uid UID]`

Optional *user ID* to be associated with the user created with `--username` with default of `1000`.

Warning: A very large UID value may result in a very large image due to an open [issue](#) with Docker. It is recommended to use the default value of `1000` when packaging an application and use your current UID/GID when running the application.

`[--gid GID]`

Optional *group ID* to be associated with the user created with `--username` with default of `1000`.

22.2.2 Holoscan CLI - Run Command

`holoscan run` - simplifies running a packaged Holoscan application by reducing the number of arguments required compared to `docker run`. In addition, it follows the guidelines of [HAP specification](#) when launching your packaged Holoscan application.

Warning: When running a packaged Holoscan application on Kubernetes or other service providers, running Docker with non root user, and running Holoscan CLI `run` command where the logged-on user's ID is different, ensure to specify the `USER ID` that is used when building the application package.

For example, include the `securityContext` when running a Holoscan packaged application with `UID=1000` using Argo:

```
spec:
  securityContext:
    runAsUser: 1000
    runAsNonRoot: true
```

Synopsis

`holoscan run` `[--help|-h]` `[--log-level|-l {DEBUG,INFO,WARN,ERROR,CRITICAL}]` `[--address ADDRESS]` `[--driver]` `[--input|-i INPUT]` `[--output|-o OUTPUT]` `[--fragments|-f FRAGMENTS]` `[--worker]` `[--worker-address WORKER_ADDRESS]` `[--config CONFIG]` `[--network|-n NETWORK]` `[--nic NETWORK_INTERFACE]` `[--use-all-nics]` `[--render|-r]` `[--quiet|-q]` `[--shm-size]` `[--terminal]` `[--device]` `[--uid UID]` `[--gid GID]` `image:[tag]`

Examples

To run a packaged Holoscan application:

```
holoscan run -i /path/to/my/input -o /path/to/application/generated/output my-
↪application:1.0.1
```

Positional Arguments

image: [tag]

Name and tag of the Docker container image to execute.

Flags

[--address ADDRESS]

Address ([<IP or hostname>][:<port>]) of the *App Driver*. If not specified, the *App Driver* uses the default host address (0.0.0.0) with the default port number (8765).

For example:

```
--address my_app_network
--address my_app_network:8765
```

Note: Ensure that the IP address is not blocked and the port is configured with the firewall accordingly.

[--driver]

Run the **App Driver** on the current machine. Can be used together with the *[--worker]* option to run both the **App Driver** and the **App Worker** on the same machine.

[--input|-i INPUT]

Specifies a directory path with input data for the application to process. When specified, a directory mount is set up to the value defined in the environment variable HOLOSCAN_INPUT_PATH.

Note: Ensure that the directory on the host is accessible by the current user or the user specified with *-uid*.

`[--output|-o OUTPUT]`

Specifies a directory path to store application-generated artifacts. When specified, a directory mount is set up to the value defined in the environment variable `HOLOSCAN_OUTPUT_PATH`.

Note: Ensure that the directory on the host is accessible by the current user or the user specified with `-uid`.

`[--fragments|-f FRAGMENTS]`

A Comma-separated names of the fragments to be executed by the **App Worker**. If not specified, only one fragment (selected by the **App Driver**) will be executed. `all` can be used to run all the fragments.

`[--worker]`

Run the **App Worker**.

`[--worker-address WORKER_ADDRESS]`

The address (`[<IP or hostname>][:<port>]`) of the **App Worker**. If not specified, the **App Worker** uses the default host address (`0.0.0.0`) with a randomly chosen port number between `10000` and `32767` that is not currently in use. This argument automatically sets the `HOLOSCAN_UCX_SOURCE_ADDRESS` environment variable if the worker address is a local IP address. Refer to *Environment Variables for Distributed Applications* for details.

For example:

```
--worker-address my_app_network
--worker-address my_app_network:10000
```

Note: Ensure that the IP address is not blocked and the port is configured with the firewall accordingly.

`[--config CONFIG]`

Path to the application configuration file. If specified, it overrides the embedded configuration file found in the environment variable `HOLOSCAN_CONFIG_PATH`.

`[--network|-n NETWORK]`

The Docker network that the application connects to for communicating with other containers. The **Runner** use the host network by default if not specified. Otherwise, the specified value is used to create a network with the bridge driver.

For advanced usages, first create a network using `docker network create` and pass the name of the network to the `--network` option. Refer to *Docker Networking* documentation for additional details.

[--nic NETWORK_INTERFACE]

Name of the network interface to use with a distributed multi-fragment application. This option sets UCX_NET_DEVICES environment variable with the value specified and is required when running a distributed multi-fragment application across multiple nodes. See *UCX Network Interface Selection* for details.

[--use-all-nics]

When set, this option allows UCX to control the selection of network interface cards for data transfer. Otherwise, the network interface card specified with '--nic' is used. This option sets the environment variable UCX_CM_USE_ALL_DEVICES to y. (default: False)

When this option is not set, the CLI runner always sets UCX_CM_USE_ALL_DEVICES to n.

[--render|-r]

Enable graphic rendering from your application. Defaults to False.

[--quiet|-q]

Suppress the STDOUT and print only STDERR from the application. Defaults to False.

[--shm-size]

Sets the size of /dev/shm. The format is <number(int,float)>[MB|m|GB|g|Mi|MiB|Gi|GiB]. Use config to read the shared memory value defined in the app.json manifest. By default, the container is launched using --ipc=host with host system's /dev/shm mounted.

[--terminal]

Enters terminal with all configured volume mappings and environment variables.

[--device]

Map host devices into the application container.

By default, the CLI searches the /dev/ path for devices unless the specified string starts with /.

For example:

```
# mount all AJA capture cards
--device ajantv*
# mount AJA capture card 0 and 1
--device ajantv0 ajantv1
# mount V4L2 video device 1 and AJAX capture card 2
--device video1 --device /dev/ajantv2
```

Warning: When using the `--device` option, append `--` after the last item to avoid misinterpretation by the CLI.
E.g.

```
holoscan run --render --device ajantv0 video1 -- my-application-image:1.0
```

`[--uid UID]`

Run the application with the specified user ID (UID). Defaults to the current user's UID.

`[--gid GID]`

Run the application with the specified group ID (GID). Defaults to the current user's GID.

Note: The Holoscan Application supports various environment variables for configuration. Refer to [Environment Variables for Distributed Applications](#) for details.

22.2.3 Holoscan CLI - Version Command

`holoscan version` - print version information for the Holoscan SDK

Synopsis

`holoscan version` [`--help|-h`] [`--log-level|-l` {*DEBUG,INFO,WARN,ERROR,CRITICAL*}]

package

Package a Holoscan application

run

Run a packaged Holoscan application

version

Print version information for the Holoscan SDK

nics

Print all available network interface cards and its assigned IP address

22.3 CLI-Wide Flags

22.3.1 [`--help|-h`]

Display detailed help.

22.3.2 `--log-level|-l {DEBUG,INFO,WARN,ERROR,CRITICAL}`

Override the default logging verbosity. Defaults to INFO.

APPLICATION RUNNER CONFIGURATION

The Holoscan runner requires a YAML configuration file to define some properties necessary to deploy an application.

Note: That file is the same configuration file commonly used to configure other aspects of an application, documented [here](#).

23.1 Configuration

The configuration file can be defined in two ways:

- At package time, with the `--config` flag of the `holoscan package` command (Required/Default)
- At runtime, with the `--config` flag of the `holoscan run` command (Optional/Override)

23.2 Properties

The `holoscan run` command parses two specific YAML nodes from the configuration file:

- A required `application` parameter group to generate a *HAP-compliant* container image for the application, including:
 - the `title` (name) and `version` of the application.
 - optionally, `inputFormats` and `outputFormats` if the application expects any inputs or outputs respectively.
- An optional `resources` parameter group that defines the system resources required to run the application, such as the number of CPUs, GPUs and amount of memory required. If the application contains multiple fragments for distributed workloads, resource definitions can be assigned to each fragment.

23.3 Example

Below is an example configuration file with the application and optional resources parameter groups, for an application with two-fragments (first-fragment and second-fragment):

```
application:
  title: My Application Title
  version: 1.0.1
  inputFormats: ["files"] # optional
  outputFormats: ["screen"] # optional

resources: # optional
  # non-distributed app
  cpu: 1 # optional
  cpuLimit: 5 # optional
  gpu: 1 # optional
  gpuLimit: 5 # optional
  memory: 1Mi # optional
  memoryLimit: 2Gi # optional
  gpuMemory: 1Gi # optional
  gpuMemoryLimit: 1.5Gi # optional
  sharedMemory: 1Gi # optional

  # distributed app
  fragments: # optional
    first-fragment: # optional
      cpu: 1 # optional
      cpuLimit: 5 # optional
      gpu: 1 # optional
      gpuLimit: 5 # optional
      memory: 100Mi # optional
      memoryLimit: 1Gi # optional
      gpuMemory: 1Gi # optional
      gpuMemoryLimit: 10Gi # optional
      sharedMemory: 1Gi # optional
    second-fragment: # optional
      cpu: 1 # optional
      cpuLimit: 2 # optional
      gpu: 1 # optional
      gpuLimit: 2 # optional
      memory: 1Gi # optional
      memoryLimit: 2Gi # optional
      gpuMemory: 1Gi # optional
      gpuMemoryLimit: 5Gi # optional
      sharedMemory: 10Mi # optional
```

For details, please refer to the *HAP specification*.

GXF CORE CONCEPTS

Here is a list of the key GXF terms used in this section:

- **Applications** are built as compute graphs.
- **Entities** are nodes of the graph. They are nothing more than a unique identifier.
- **Components** are parts of an entity and provide their functionality.
- **Codelets** are special components which allow the execution of custom code. They can be derived by overriding the C++ functions `initialize`, `start`, `tick`, `stop`, `deinitialize`, and `registerInterface` (for defining configuration parameters).
- **Connections** are edges of the graph, which connect components.
- **Scheduler and Scheduling Terms**: components that determine how and when the `tick()` of a Codelet executes. This can be single or multithreaded, support conditional execution, asynchronous scheduling, and other custom behavior.
- **Memory Allocator**: provides a system for allocating a large contiguous memory pool up-front and then reusing regions as needed. Memory can be pinned to the device (enabling zero-copy between Codelets when messages are not modified) or host, or customized for other potential behavior.
- **Receivers, Transmitters, and Message Router**: a message passing system between Codelets that supports zero-copy.
- **Tensor**: the common message type is a tensor. It provides a simple abstraction for numeric data that can be allocated, serialized, sent between Codelets, etc. Tensors can be rank 1 to 7 supporting a variety of common data types like arrays, vectors, matrices, multi-channel images, video, regularly sampled time-series data, and higher dimensional constructs popular with deep learning flows.
- **Parameters**: configuration variables used by the Codelet. In GXF applications, they are loaded from the application YAML file and are modifiable without recompiling.

In comparison, the core concepts of the Holoscan SDK can be found [here](#).

HOLOSCAN AND GXF

25.1 Design differences

There are 2 main elements at the core of Holoscan and GXF designs:

1. How to define and execute application graphs
2. How to define nodes' functionality

How Holoscan SDK interfaces with GXF on those topics varies as Holoscan SDK evolves, as described below:

25.1.1 Holoscan SDK v0.2

Holoscan SDK was tightly coupled with GXF's existing interface:

1. GXF application graphs are defined in **YAML** configuration files. **GXE** (Graph Execution Engine) is used to execute AI application graphs. Its inputs are the YAML configuration file, and a list of GXF Extensions to load as plugins (manifest yaml file). This design allows entities to be swapped or updated without needing to recompile an application.
2. Components are made available by registering them within a **GXF extension**, each of which maps to a shared library and header(s).

Those concepts are illustrated in the *GXF by example* section.

The only additions that Holoscan provided on top of GXF were:

- domain specific reference applications
- new extensions
- CMake configurations for building extensions and applications

25.1.2 Holoscan SDK v0.3

The Holoscan SDK shifted to provide a more developer-friendly interface with C++:

1. GXF application graphs, memory allocation, scheduling, and message routing can be defined using a C++ API, with the ability to read parameters and required GXF extension names from a YAML configuration file. The backend used is still GXF as Holoscan uses the GXF C API, but this bypasses GXE and the full YAML definition.
2. The C++ **Operator** class was added to wrap and expose GXF extensions to that new application interface (See *dev guide*).

25.1.3 Holoscan SDK v0.4

The Holoscan SDK added Python wrapping and native operators to further increase ease of use:

1. The C++ API is also wrapped in Python. GXF is still used as the backend.
2. The Operator class supports **native operators**, i.e. operators that do not require to implement and register a GXF Extension. An important feature is the ability to support messaging between native and GXF operators without any performance loss (i.e. zero-copy communication of tensors).

25.1.4 Holoscan SDK v0.5

1. The built-in Holoscan GXF extensions are loaded automatically and don't need to be listed in the YAML configuration file of Holoscan applications. This allows Holoscan applications to be defined without requiring a YAML configuration file.
2. No significant changes to build operators. However, most built-in operators were switched to native implementations, with the ability to *convert native operators to GXF codelets* for GXF application developers.

25.1.5 Holoscan SDK v1.0

1. The remaining GXF-based DemosiacOp operator was switched to a native implementation. Now all operators provided by the SDK are native operators.

25.2 Current limitations

Here is a list of GXF capabilities not yet available in the Holoscan SDK which are planned to be supported in future releases:

- *Job Statistics*

The GXF capabilities below are not available in the Holoscan SDK either. There is no plan to support them at this time:

- *Graph Composer*
- *Behavior Trees*
- *Epoch Scheduler*
- *Target Time Scheduling Term*
- *Multi-Message Available Scheduling Term*
- *Expiring Message Available Scheduling Term*

GXF BY EXAMPLE

Warning: This section is legacy (0.2) as we recommend developing extensions and applications using the C++ or Python APIs. Refer to the developer guide for up-to-date recommendations.

26.1 Innerworkings of a GXF Entity

Let us look at an example of a GXF entity to try to understand its general anatomy. As an example let's start with the entity definition for an image format converter entity named `format_converter_entity` as shown below.

Listing 26.1: An example GXF Application YAML snippet

```
1 %YAML 1.2
2 ---
3 # other entities declared
4 ---
5 name: format_converter_entity
6 components:
7   - name: in_tensor
8     type: nvidia::gxf::DoubleBufferReceiver
9   - type: nvidia::gxf::MessageAvailableSchedulingTerm
10    parameters:
11      receiver: in_tensor
12      min_size: 1
13   - name: out_tensor
14     type: nvidia::gxf::DoubleBufferTransmitter
15   - type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
16    parameters:
17      transmitter: out_tensor
18      min_size: 1
19   - name: pool
20     type: nvidia::gxf::BlockMemoryPool
21    parameters:
22      storage_type: 1
23      block_size: 4919040 # 854 * 480 * 3 (channel) * 4 (bytes per pixel)
24      num_blocks: 2
25   - name: format_converter_component
26     type: nvidia::holoscan::formatconverter::FormatConverter
27    parameters:
28      in: in_tensor
```

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```

29     out: out_tensor
30     out_tensor_name: source_video
31     out_dtype: "float32"
32     scale_min: 0.0
33     scale_max: 255.0
34     pool: pool
35 ---
36 # other entities declared
37 ---
38 components:
39   - name: input_connection
40     type: nvidia::gxf::Connection
41     parameters:
42       source: upstream_entity/output
43       target: format_converter/in_tensor
44 ---
45 components:
46   - name: output_connection
47     type: nvidia::gxf::Connection
48     parameters:
49       source: format_converter/out_tensor
50       target: downstream_entity/input
51 ---
52 name: scheduler
53 components:
54   - type: nvidia::gxf::GreedyScheduler

```

Above:

1. The entity `format_converter_entity` receives a message in its `in_tensor` message from an upstream entity `upstream_entity` as declared in the `input_connection`.
2. The received message is passed to the `format_converter_component` component to convert the tensor element precision from `uint8` to `float32` and scale any input in the `[0, 255]` intensity range.
3. The `format_converter_component` component finally places the result in the `out_tensor` message so that its result is made available to a downstream entity (`downstream_entity` as declared in `output_connection`).
4. The `Connection` components tie the inputs and outputs of various components together, in the above case `upstream_entity/output -> format_converter_entity/in_tensor` and `format_converter_entity/out_tensor -> downstream_entity/input`.
5. The `scheduler` entity declares a `GreedyScheduler` “system component” which orchestrates the execution of the entities declared in the graph. In the specific case of `GreedyScheduler` entities are scheduled to run exclusively, where no more than one entity can run at any given time.

The YAML snippet above can be visually represented as follows.

In the image, as in the YAML, you will notice the use of `MessageAvailableSchedulingTerm`, `DownstreamReceptiveSchedulingTerm`, and `BlockMemoryPool`. These are components that play a “supporting” role to `in_tensor`, `out_tensor`, and `format_converter_component` components respectively. Specifically:

- `MessageAvailableSchedulingTerm` is a component that takes a `Receiver`` (in this case `Double-BufferReceivernamedin_tensor`) and alerts the graph `Executorthat` a message is available. This alert triggers `format_converter_component``.
- `DownstreamReceptiveSchedulingTerm` is a component that takes a `Transmitter` (in this case

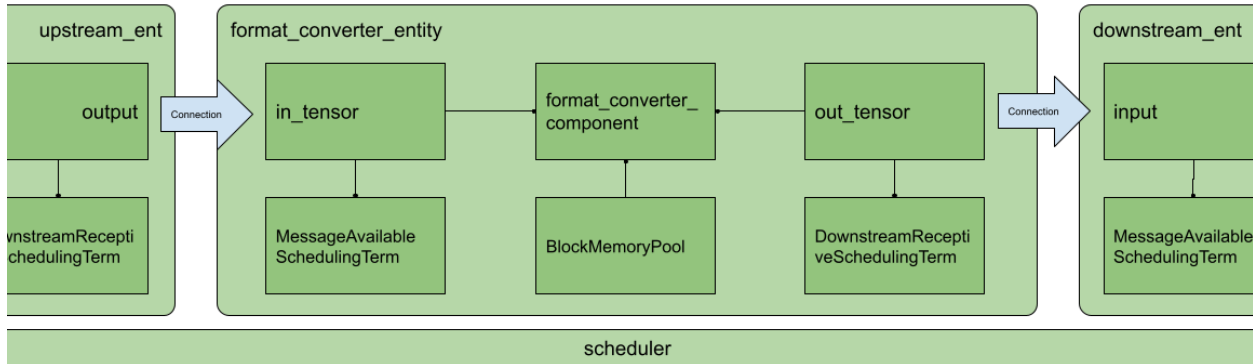


Fig. 26.1: Arrangement of components and entities in a Holoscan application

DoubleBufferTransmitter named `out_tensor`) and alerts the graph Executor that a message has been placed on the output.

- `BlockMemoryPool` provides two blocks of almost 5MB allocated on the GPU device and is used by `format_converter_entity` to allocate the output tensor where the converted data will be placed within the format converted component.

Together these components allow the entity to perform a specific function and coordinate communication with other entities in the graph via the declared scheduler.

More generally, an entity can be thought of as a collection of components where components can be passed to one another to perform specific subtasks (e.g. event triggering or message notification, format conversion, memory allocation), and an application as a graph of entities.

The scheduler is a component of type `nvidia::gxf::System` which orchestrates the execution components in each entity at application runtime based on triggering rules.

26.2 Data Flow and Triggering Rules

Entities communicate with one another via messages which may contain one or more payloads. Messages are passed and received via a component of type `nvidia::gxf::Queue` from which both `nvidia::gxf::Receiver` and `nvidia::gxf::Transmitter` are derived. Every entity that receives and transmits messages has at least one receiver and one transmitter queue.

Holoscan uses the `nvidia::gxf::SchedulingTerm` component to coordinate data access and component orchestration for a Scheduler which invokes execution through the `tick()` function in each `Codelet`.

Tip: A `SchedulingTerm` defines a specific condition that is used by an entity to let the scheduler know when it's ready for execution.

In the above example, we used a `MessageAvailableSchedulingTerm` to trigger the execution of the components waiting for data from `in_tensor` receiver queue, namely `format_converter_component`.

Listing 26.2: `MessageAvailableSchedulingTerm`

```
1 - type: nvidia::gxf::MessageAvailableSchedulingTerm
2 parameters:
```

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```

3 receiver: in_tensor
4 min_size: 1

```

Similarly, `DownStreamReceptiveSchedulingTerm` checks whether the `out_tensor` transmitter queue has at least one outgoing message in it. If there are one or more outgoing messages, `DownStreamReceptiveSchedulingTerm` will notify the scheduler which in turn attempts to place the message in the receiver queue of a downstream entity. If, however, the downstream entity has a full receiver queue, the message is held in the `out_tensor` queue as a means to handle back-pressure.

Listing 26.3: `DownstreamReceptiveSchedulingTerm`

```

1 - type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
2 parameters:
3 transmitter: out_tensor
4 min_size: 1

```

If we were to draw the entity in [Fig. 26.1](#) in greater detail it would look something like the following.

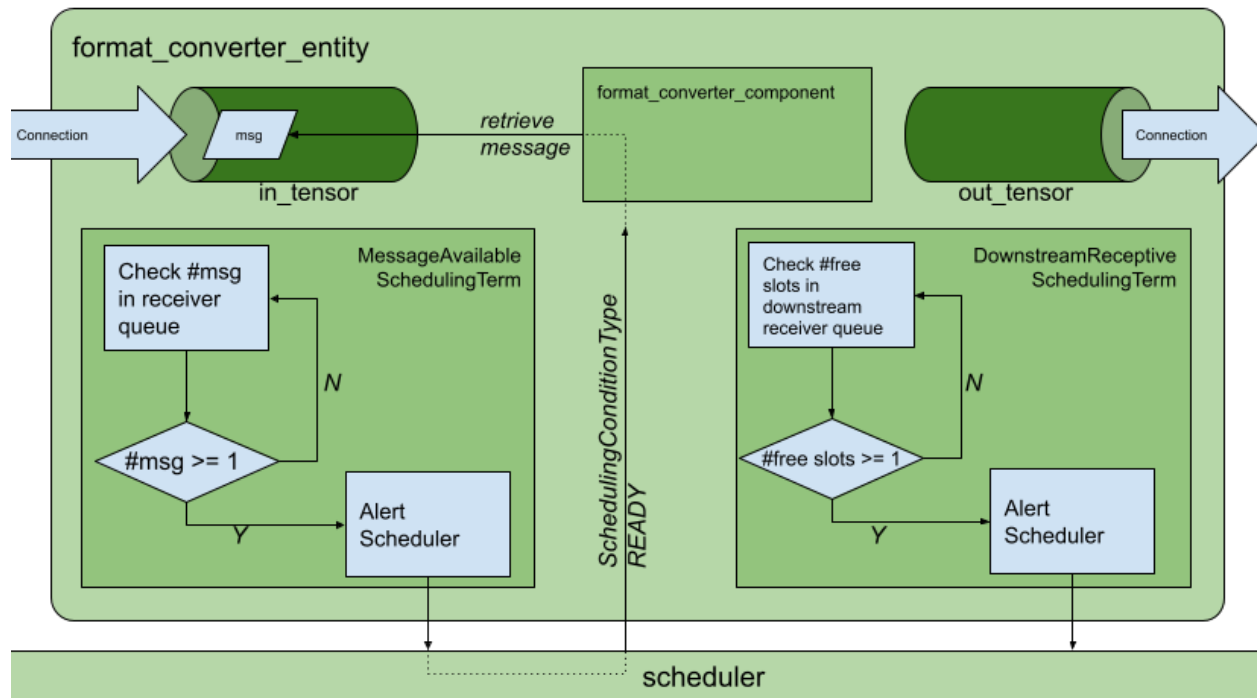


Fig. 26.2: Receive and transmit Queues and SchedulingTerms in entities.

Up to this point, we have covered the “entity component system” at a high level and showed the functional parts of an entity, namely, the messaging queues and the scheduling terms that support the execution of components in the entity. To complete the picture, the next section covers the anatomy and lifecycle of a component, and how to handle events within it.

26.3 Creating a GXF Extension

GXF components in Holoscan can perform a multitude of sub-tasks ranging from data transformations, to memory management, to entity scheduling. In this section, we will explore an `nvidia::gxf::Codelet` component which in Holoscan is known as a “GXF extension”. *Holoscan (GXF) extensions* are typically concerned with application-specific sub-tasks such as data transformations, AI model inference, and the like.

26.3.1 Extension Lifecycle

The lifecycle of a `Codelet` is composed of the following five stages.

1. **initialize** - called only once when the codelet is created for the first time, and use of light-weight initialization.
2. **deinitialize** - called only once before the codelet is destroyed, and used for light-weight deinitialization.
3. **start** - called multiple times over the lifecycle of the codelet according to the order defined in the lifecycle, and used for heavy initialization tasks such as allocating memory resources.
4. **stop** - called multiple times over the lifecycle of the codelet according to the order defined in the lifecycle, and used for heavy deinitialization tasks such as deallocation of all resources previously assigned in **start**.
5. **tick** - called when the codelet is triggered, and is called multiple times over the codelet lifecycle; even multiple times between **start** and **stop**.

The flow between these stages is detailed in [Fig. 26.3](#).

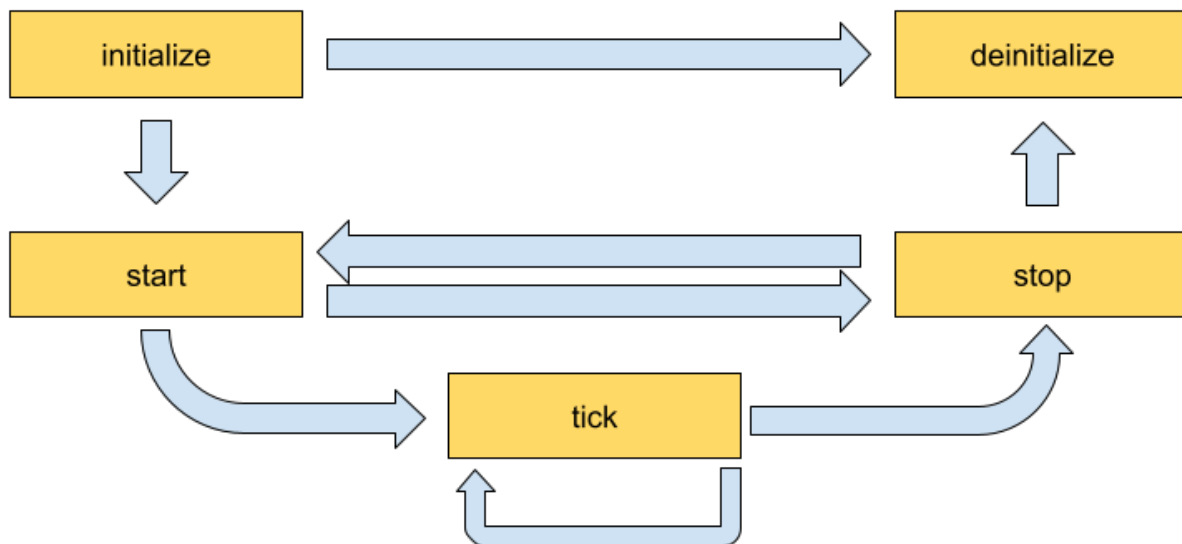


Fig. 26.3: Sequence of method calls in the lifecycle of a Holoscan extension

26.3.2 Implementing an Extension

In this section, we will implement a simple recorder that will highlight the actions we would perform in the lifecycle methods. The recorder receives data in the input queue and records the data to a configured location on the disk. The output format of the recorder files is the GXF-formatted index/binary replayer files (the format is also used for the data in the sample applications), where the `gxf_index` file contains timing and sequence metadata that refer to the binary/tensor data held in the `gxf_entities` file.

Declare the Class That Will Implement the Extension Functionality

The developer can create their Holoscan extension by extending the `Codelet` class, implementing the extension functionality by overriding the lifecycle methods, and defining the parameters the extension exposes at the application level via the `registerInterface` method. To define our recorder component we would need to implement some of the methods in the `Codelet`.

First, clone the Holoscan project from [here](#) and create a folder to develop our extension such as under `gxf_extensions/my_recorder`.

Tip: Using Bash we create a Holoscan extension folder as follows.

```
git clone https://github.com/nvidia-holoscan/holoscan-sdk.git
cd clara-holoscan-embedded-sdk
mkdir -p gxf_extensions/my_recorder
```

In our extension folder, we create a header file `my_recorder.hpp` with a declaration of our Holoscan component.

Listing 26.4: `gxf_extensions/my_recorder/my_recorder.hpp`

```
1  #include <string>
2
3  #include "gxf/core/handle.hpp"
4  #include "gxf/std/codelet.hpp"
5  #include "gxf/std/receiver.hpp"
6  #include "gxf/std/transmitter.hpp"
7  #include "gxf/serialization/file_stream.hpp"
8  #include "gxf/serialization/entity_serializer.hpp"
9
10
11 class MyRecorder : public nvidia::gxf::Codelet {
12 public:
13     gxf_result_t registerInterface(nvidia::gxf::Registrar* registrar) override;
14     gxf_result_t initialize() override;
15     gxf_result_t deinitialize() override;
16
17     gxf_result_t start() override;
18     gxf_result_t tick() override;
19     gxf_result_t stop() override;
20
21 private:
22     nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::Receiver>> receiver_;
23     nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::EntitySerializer>> my_
    ↪ serializer_;
```

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```

24  nvidia::gxf::Parameter<std::string> directory_;
25  nvidia::gxf::Parameter<std::string> basename_;
26  nvidia::gxf::Parameter<bool> flush_on_tick_;
27
28  // File stream for data index
29  nvidia::gxf::FileStream index_file_stream_;
30  // File stream for binary data
31  nvidia::gxf::FileStream binary_file_stream_;
32  // Offset into binary file
33  size_t binary_file_offset_;
34  };

```

Declare the Parameters to Expose at the Application Level

Next, we can start implementing our lifecycle methods in the `my_recorder.cpp` file, which we also create in `gxf_extensions/my_recorder` path.

Our recorder will need to expose the `nvidia::gxf::Parameter` variables to the application so the parameters can be modified by configuration.

Listing 26.5: `registerInterface` in `gxf_extensions/my_recorder/my_recorder.cpp`

```

1  #include "my_recorder.hpp"
2
3  gxf_result_t MyRecorder::registerInterface(nvidia::gxf::Registrar* registrar) {
4      nvidia::gxf::Expected<void> result;
5      result &= registrar->parameter(
6          receiver_, "receiver", "Entity receiver",
7          "Receiver channel to log");
8      result &= registrar->parameter(
9          my_serializer_, "serializer", "Entity serializer",
10         "Serializer for serializing input data");
11     result &= registrar->parameter(
12         directory_, "out_directory", "Output directory path",
13         "Directory path to store received output");
14     result &= registrar->parameter(
15         basename_, "basename", "File base name",
16         "User specified file name without extension",
17         nvidia::gxf::Registrar::NoDefaultParameter(), GXF_PARAMETER_FLAGS_OPTIONAL);
18     result &= registrar->parameter(
19         flush_on_tick_, "flush_on_tick", "Boolean to flush on tick",
20         "Flushes output buffer on every `tick` when true", false); // default value `false`
21     return nvidia::gxf::ToResultCode(result);
22 }

```

For pure GXF applications, our component's parameters can be specified in the following format in the YAML file:

Listing 26.6: Example parameters for `MyRecorder` component

```

1  name: my_recorder_entity
2  components:
3    - name: my_recorder_component

```

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```

4  type: MyRecorder
5  parameters:
6    receiver: receiver
7    serializer: my_serializer
8    out_directory: /home/user/out_path
9    basename: my_output_file # optional
10   # flush_on_tick: false    # optional

```

Note that all the parameters exposed at the application level are mandatory except for `flush_on_tick`, which defaults to `false`, and `basename`, whose default is handled at `initialize()` below.

Implement the Lifecycle Methods

This extension does not need to perform any heavy-weight initialization tasks, so we will concentrate on `initialize()`, `tick()`, and `deinitialize()` methods which define the core functionality of our component. At initialization, we will create a file stream and keep track of the bytes we write on `tick()` via `binary_file_offset`.

Listing 26.7: `initialize` in `gxf_extensions/my_recorder/my_recorder.cpp`

```

24 gxf_result_t MyRecorder::initialize() {
25   // Create path by appending receiver name to directory path if basename is not provided
26   std::string path = directory_.get() + '/';
27   if (const auto& basename = basename_.try_get()) {
28     path += basename.value();
29   } else {
30     path += receiver_>name();
31   }
32
33   // Initialize index file stream as write-only
34   index_file_stream_ = nvidia::gxf::FileStream("", path +
↳nvidia::gxf::FileStream::kIndexFileExtension);
35
36   // Initialize binary file stream as write-only
37   binary_file_stream_ = nvidia::gxf::FileStream("", path +
↳nvidia::gxf::FileStream::kBinaryFileExtension);
38
39   // Open index file stream
40   nvidia::gxf::Expected<void> result = index_file_stream_.open();
41   if (!result) {
42     return nvidia::gxf::ToResultCode(result);
43   }
44
45   // Open binary file stream
46   result = binary_file_stream_.open();
47   if (!result) {
48     return nvidia::gxf::ToResultCode(result);
49   }
50   binary_file_offset_ = 0;
51
52   return GXF_SUCCESS;
53 }

```

When de-initializing, our component will take care of closing the file streams that were created at initialization.

Listing 26.8: deinitialize in `gfx_extensions/my_recorder/my_recorder.cpp`

```

55 gfx_result_t MyRecorder::deinitialize() {
56     // Close binary file stream
57     nvidia::gfx::Expected<void> result = binary_file_stream_.close();
58     if (!result) {
59         return nvidia::gfx::ToResultCode(result);
60     }
61
62     // Close index file stream
63     result = index_file_stream_.close();
64     if (!result) {
65         return nvidia::gfx::ToResultCode(result);
66     }
67
68     return GFX_SUCCESS;
69 }

```

In our recorder, no heavy-weight initialization tasks are required so we implement the following, however, we would use `start()` and `stop()` methods for heavy-weight tasks such as memory allocation and deallocation.

Listing 26.9: start/stop in `gfx_extensions/my_recorder/my_recorder.cpp`

```

71 gfx_result_t MyRecorder::start() {
72     return GFX_SUCCESS;
73 }
74
75 gfx_result_t MyRecorder::stop() {
76     return GFX_SUCCESS;
77 }

```

Tip: For a detailed implementation of `start()` and `stop()`, and how memory management can be handled therein, please refer to the implementation of the [AJA Video source extension](#).

Finally, we write the component-specific functionality of our extension by implementing `tick()`.

Listing 26.10: tick in `gfx_extensions/my_recorder/my_recorder.cpp`

```

79 gfx_result_t MyRecorder::tick() {
80     // Receive entity
81     nvidia::gfx::Expected<nvidia::gfx::Entity> entity = receiver_>receive();
82     if (!entity) {
83         return nvidia::gfx::ToResultCode(entity);
84     }
85
86     // Write entity to binary file
87     nvidia::gfx::Expected<size_t> size = my_serializer_>serializeEntity(entity.value(), &
88     ↪ binary_file_stream_);
89     if (!size) {
90         return nvidia::gfx::ToResultCode(size);
91     }

```

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```

91
92 // Create entity index
93 nvidia::gxf::EntityIndex index;
94 index.log_time = std::chrono::system_clock::now().time_since_epoch().count();
95 index.data_size = size.value();
96 index.data_offset = binary_file_offset_;
97
98 // Write entity index to index file
99 nvidia::gxf::Expected<size_t> result = index_file_stream_.writeTrivialType(&index);
100 if (!result) {
101     return nvidia::gxf::ToResultCode(result);
102 }
103 binary_file_offset_ += size.value();
104
105 if (flush_on_tick_) {
106     // Flush binary file output stream
107     nvidia::gxf::Expected<void> result = binary_file_stream_.flush();
108     if (!result) {
109         return nvidia::gxf::ToResultCode(result);
110     }
111
112     // Flush index file output stream
113     result = index_file_stream_.flush();
114     if (!result) {
115         return nvidia::gxf::ToResultCode(result);
116     }
117 }
118
119 return GXF_SUCCESS;
120 }

```

Register the Extension as a Holoscan Component

As a final step, we must register our extension so it is recognized as a component and loaded by the application executor. For this we create a simple declaration in `my_recorder_ext.cpp` as follows.

Listing 26.11: `gxf_extensions/my_recorder/my_recorder_ext.cpp`

```

1 #include "gxf/std/extension_factory_helper.hpp"
2
3 #include "my_recorder.hpp"
4
5 GXF_EXT_FACTORY_BEGIN()
6 GXF_EXT_FACTORY_SET_INFO(0xb891cef3ce754825, 0x9dd3dcac9bbd8483, "MyRecorderExtension",
7     "My example recorder extension", "NVIDIA", "0.1.0", "LICENSE");
8 GXF_EXT_FACTORY_ADD(0x2464fabf91b34ccf, 0xb554977fa22096bd, MyRecorder,
9     nvidia::gxf::Codelet, "My example recorder codelet.");
10 GXF_EXT_FACTORY_END()

```

`GXF_EXT_FACTORY_SET_INFO` configures the extension with the following information in order:

- UUID which can be generated using `scripts/generate_extension_uuids.py` which defines the **extension**

id

- extension name
- extension description
- author
- extension version
- license text

GXF_EXT_FACTORY_ADD registers the newly built extension as a valid Codelet component with the following information in order:

- UUID which can be generated using `scripts/generate_extension_uuids.py` which defines the **component id** (this must be different from the extension id),
- fully qualified extension class,
- fully qualifies base class,
- component description

To build a shared library for our new extension which can be loaded by a Holoscan application at runtime we use a CMake file under `gxf_extensions/my_recorder/CMakeLists.txt` with the following content.

Listing 26.12: `gxf_extensions/my_recorder/CMakeLists.txt`

```

1  # Create library
2  add_library(my_recorder_lib SHARED
3      my_recorder.cpp
4      my_recorder.hpp
5  )
6  target_link_libraries(my_recorder_lib
7      PUBLIC
8          GXF::std
9          GXF::serialization
10         yaml-cpp
11 )
12
13 # Create extension
14 add_library(my_recorder SHARED
15     my_recorder_ext.cpp
16 )
17 target_link_libraries(my_recorder
18     PUBLIC my_recorder_lib
19 )
20
21 # Install GXF extension as a component 'holoscan-gxf_extensions'
22 install_gxf_extension(my_recorder) # this will also install my_recorder_lib
23 # install_gxf_extension(my_recorder_lib) # this statement is not necessary because this_
    ↳ library follows `<extension library name>_lib` convention.

```

Here, we create a library `my_recorder_lib` with the implementation of the lifecycle methods, and the extension `my_recorder` which exposes the C API necessary for the application runtime to interact with our component.

To make our extension discoverable from the project root we add the line

```
add_subdirectory(my_recorder)
```

to the CMake file `gxf_extensions/CMakeLists.txt`.

Tip: To build our extension, we can follow the steps in the [README](#).

At this point, we have a complete extension that records data coming into its receiver queue to the specified location on the disk using the GXF-formatted binary/index files.

26.4 Creating a GXF Application

For our application, we create the directory `apps/my_recorder_app_gxf` with the application definition file `my_recorder_gxf.yaml`. The `my_recorder_gxf.yaml` application is as follows:

Listing 26.13: `apps/my_recorder_app_gxf/my_recorder_gxf.yaml`

```

1 %YAML 1.2
2 ---
3 name: replayer
4 components:
5   - name: output
6     type: nvidia::gxf::DoubleBufferTransmitter
7   - name: allocator
8     type: nvidia::gxf::UnboundedAllocator
9   - name: component_serializer
10    type: nvidia::gxf::StdComponentSerializer
11    parameters:
12      allocator: allocator
13   - name: entity_serializer
14     type: nvidia::holoscan::stream_playback::VideoStreamSerializer # inheriting from
15     ↪ nvidia::gxf::EntitySerializer
16     parameters:
17       component_serializers: [component_serializer]
18   - type: nvidia::holoscan::stream_playback::VideoStreamReplayer
19     parameters:
20       transmitter: output
21       entity_serializer: entity_serializer
22       boolean_scheduling_term: boolean_scheduling
23       directory: "/workspace/data/racerox"
24       basename: "racerox"
25       frame_rate: 0 # as specified in timestamps
26       repeat: false # default: false
27       realtime: true # default: true
28       count: 0 # default: 0 (no frame count restriction)
29   - name: boolean_scheduling
30     type: nvidia::gxf::BooleanSchedulingTerm
31   - type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
32     parameters:
33       transmitter: output
34       min_size: 1

```

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```

34 ---
35 name: recorder
36 components:
37   - name: input
38     type: nvidia::gxf::DoubleBufferReceiver
39   - name: allocator
40     type: nvidia::gxf::UnboundedAllocator
41   - name: component_serializer
42     type: nvidia::gxf::StdComponentSerializer
43     parameters:
44       allocator: allocator
45   - name: entity_serializer
46     type: nvidia::holoscan::stream_playback::VideoStreamSerializer # inheriting from
47     ↪ nvidia::gxf::EntitySerializer
48     parameters:
49       component_serializers: [component_serializer]
50   - type: MyRecorder
51     parameters:
52       receiver: input
53       serializer: entity_serializer
54       out_directory: "/tmp"
55       basename: "tensor_out"
56   - type: nvidia::gxf::MessageAvailableSchedulingTerm
57     parameters:
58       receiver: input
59       min_size: 1
60 ---
61 components:
62   - name: input_connection
63     type: nvidia::gxf::Connection
64     parameters:
65       source: replayer/output
66       target: recorder/input
67 ---
68 name: scheduler
69 components:
70   - name: clock
71     type: nvidia::gxf::RealtimeClock
72   - name: greedy_scheduler
73     type: nvidia::gxf::GreedyScheduler
74     parameters:
75       clock: clock

```

Above:

- The replayer reads data from `/workspace/data/racerx/racerx.gxf_[index|entities]` files, deserializes the binary data to a `nvidia::gxf::Tensor` using `VideoStreamSerializer`, and puts the data on an output message in the `replayer/output` transmitter queue.
- The `input_connection` component connects the `replayer/output` transmitter queue to the `recorder/input` receiver queue.
- The recorder reads the data in the input receiver queue, uses `StdEntitySerializer` to convert the received `nvidia::gxf::Tensor` to a binary stream, and outputs to the `/tmp/tensor_out.gxf_[index|entities]`

location specified in the parameters.

- The scheduler component, while not explicitly connected to the application-specific entities, performs the orchestration of the components discussed in the *Data Flow and Triggering Rules*.

Note the use of the `component_serializer` in our newly built recorder. This component is declared separately in the entity

```
- name: entity_serializer
  type: nvidia::holoscan::stream_playback::VideoStreamSerializer # inheriting from
  ↪nvidia::gxf::EntitySerializer
  parameters:
    component_serializers: [component_serializer]
```

and passed into `MyRecorder` via the `serializer` parameter which we exposed in the *extension development section* (*Declare the Parameters to Expose at the Application Level*).

```
- type: MyRecorder
  parameters:
    receiver: input
    serializer: entity_serializer
    directory: "/tmp"
    basename: "tensor_out"
```

For our app to be able to load (and also compile where necessary) the extensions required at runtime, we need to declare a CMake file `apps/my_recorder_app_gxf/CMakeLists.txt` as follows.

Listing 26.14: `apps/my_recorder_app_gxf/CMakeLists.txt`

```
1 create_gxe_application(
2   NAME my_recorder_gxf
3   YAML my_recorder_gxf.yaml
4   EXTENSIONS
5     GXF::std
6     GXF::cuda
7     GXF::multimedia
8     GXF::serialization
9     my_recorder
10    stream_playback
11 )
12
13 # Download the associated dataset if needed
14 if(HOLOSCAN_DOWNLOAD_DATASETS)
15   add_dependencies(my_recorder_gxf racerx_data)
16 endif()
```

In the declaration of `create_gxe_application` we list:

- `my_recorder` component declared in the CMake file of the *extension development section* under the `EXTENSIONS` argument
- the existing `stream_playback` Holoscan extension which reads data from disk

To make our newly built application discoverable by the build, in the root of the repository, we add the following line to `apps/CMakeLists.txt`:

```
add_subdirectory(my_recorder_app_gxf)
```

We now have a minimal working application to test the integration of our newly built MyRecorder extension.

26.5 Running the GXF Recorder Application

To run our application in a local development container:

1. Follow the instructions under the [Using a Development Container](#) section steps 1-5 (try clearing the CMake cache by removing the build folder before compiling).

You can execute the following commands to build

```
./run build
# ./run clear_cache # if you want to clear build/install/cache folders
```

2. Our test application can now be run in the development container using the command

```
./apps/my_recorder_app_gxf/my_recorder_gxf
```

from inside the development container.

(You can execute `./run launch` to run the development container.)

```
@LINUX:/workspace/holoscan-sdk/build$ ./apps/my_recorder_app_gxf/my_recorder_gxf
2022-08-24 04:46:47.333 INFO gxf/gxe/gxe.cpp@230: Creating context
2022-08-24 04:46:47.339 INFO gxf/gxe/gxe.cpp@107: Loading app: 'apps/my_recorder_
↳ app_gxf/my_recorder_gxf.yaml'
2022-08-24 04:46:47.339 INFO gxf/std/yaml_file_loader.cpp@117: Loading GXF_
↳ entities from YAML file 'apps/my_recorder_app_gxf/my_recorder_gxf.yaml'...
2022-08-24 04:46:47.340 INFO gxf/gxe/gxe.cpp@291: Initializing...
2022-08-24 04:46:47.437 INFO gxf/gxe/gxe.cpp@298: Running...
2022-08-24 04:46:47.437 INFO gxf/std/greedy_scheduler.cpp@170: Scheduling 2_
↳ entities
2022-08-24 04:47:14.829 INFO /workspace/holoscan-sdk/gxf_extensions/stream_
↳ playback/video_stream_replayer.cpp@144: Reach end of file or playback count_
↳ reaches to the limit. Stop ticking.
2022-08-24 04:47:14.829 INFO gxf/std/greedy_scheduler.cpp@329: Scheduler stopped:_
↳ Some entities are waiting for execution, but there are no periodic or async_
↳ entities to get out of the deadlock.
2022-08-24 04:47:14.829 INFO gxf/std/greedy_scheduler.cpp@353: Scheduler finished.
2022-08-24 04:47:14.829 INFO gxf/gxe/gxe.cpp@320: Deinitializing...
2022-08-24 04:47:14.863 INFO gxf/gxe/gxe.cpp@327: Destroying context
2022-08-24 04:47:14.863 INFO gxf/gxe/gxe.cpp@333: Context destroyed.
```

A successful run (it takes about 30 secs) will result in output files (`tensor_out.gxf_index` and `tensor_out.gxf_entities` in `/tmp`) that match the original input files (`racerox.gxf_index` and `racerox.gxf_entities` under `data/racerox`) exactly.

```
@LINUX:/workspace/holoscan-sdk/build$ ls -al /tmp/
total 821384
drwxrwxrwt 1 root root      4096 Aug 24 04:37 .
drwxr-xr-x 1 root root      4096 Aug 24 04:36 ..
```

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```
drwxrwxrwt 2 root root      4096 Aug 11 21:42 .X11-unix
-rw-r--r-- 1 1000 1000      729309 Aug 24 04:47 gxf_log
-rw-r--r-- 1 1000 1000 840054484 Aug 24 04:47 tensor_out.gxf_entities
-rw-r--r-- 1 1000 1000      16392 Aug 24 04:47 tensor_out.gxf_index
```

```
@LINUX:/workspace/holoscan-sdk/build$ ls -al ../data/racerx
```

```
total 839116
drwxr-xr-x 2 1000 1000      4096 Aug 24 02:08 .
drwxr-xr-x 4 1000 1000      4096 Aug 24 02:07 ..
-rw-r--r-- 1 1000 1000 19164125 Jun 17 16:31 racerx-medium.mp4
-rw-r--r-- 1 1000 1000 840054484 Jun 17 16:31 racerx.gxf_entities
-rw-r--r-- 1 1000 1000      16392 Jun 17 16:31 racerx.gxf_index
```

USING HOLOSCAN OPERATORS IN GXF APPLICATIONS

For users who are familiar with the GXF development ecosystem (used in Holoscan SDK 0.2), we provide an export feature to leverage native Holoscan operators as GXF codelets to execute in GXF applications and GraphComposer.

We demonstrate how to wrap a native C++ holoscan operator as a GXF codelet in the [wrap_operator_as_gxf_extension](#) example on [GitHub](#), as described below.

27.1 1. Creating compatible Holoscan Operators

Note: This section assumes you are already familiar with *how to create a native C++ operator*.

To be compatible with GXF codelets, inputs and outputs specified in `Operator::setup(OperatorSpec& spec)` must be of type `holoscan::gxf::Entity`, as shown in the [PingTxNativeOp](#) and the [PingRxNativeOp](#) implementations of this example, in contrast to the [PingTxOp](#) and [PingRxOp](#) built-in operators of the SDK.

For more details regarding the use of `holoscan::gxf::Entity`, follow the documentation on *Interoperability between GXF and native C++ operators*.

27.2 2. Creating the GXF extension that wraps the operator

To wrap the native operator as a GXF codelet in a GXF extension, we provide the `CMake wrap_operator_as_gxf_extension` function in the SDK. An example of how it wraps `PingTxNativeOp` and `PingRxNativeOp` can be found [here](#).

- It leverages the CMake target names of the operators defined in their respective `CMakeLists.txt` (`ping_tx_native_op`, `ping_rx_native_op`)
- The function parameters are documented at the top of the [WrapOperatorAsGXFExtension.cmake](#) file (ignore implementation below).

Warning:

- A unique GXF extension is currently needed for each native operator to export (operators cannot be bundled in a single extension at this time).
- Wrapping other GXF entities than operators (as codelets) is not currently supported.

27.3 3. Using your wrapped operator in a GXF application

Note: This section assumes you are familiar with [how to create a GXF application](#).

As shown in the `gxf_app/CMakeLists.txt` [here](#), you need to list the following extensions in `create_gxe_application()` to use your wrapped codelets:

- `GXF::std`
- `gxf_holoscan_wrapper`
- the name of the CMake target for the created extension, defined by the `EXTENSION_TARGET_NAME` argument passed to `wrap_operator_as_gxf_extension` in the previous section

The codelet class name (defined by the `CODELET_NAMESPACE::CODELET_NAME` arguments passed to `wrap_operator_as_gxf_extension` in the previous section) can then be used as a component `type` in a GXF app node, as shown in the [YAML app definition](#) of the example, connecting the two ping operators.

28.1 Graph Specification

Graph Specification is a format to describe high-performance AI applications in a modular and extensible way. It allows writing applications in a standard format and sharing components across multiple applications without code modification. Graph Specification is based on entity-composition pattern. Every object in graph is represented with entity (aka Node) and components. Developers implement custom components which can be added to entity to achieve the required functionality.

28.1.1 Concepts

The graph contains nodes which follow an entity-component design pattern implementing the “composition over inheritance” paradigm. A node itself is just a light-weight object which owns components. Components define how a node interacts with the rest of the applications. For example, nodes be connected to pass data between each other. A special component, called compute component, is used to execute the code based on certain rules. Typically a compute component would receive data, execute some computation and publish data.

Graph

A graph is a data-driven representation of an AI application. Implementing an application by using programming code to create and link objects results in a monolithic and hard to maintain program. Instead a graph object is used to structure an application. The graph can be created using specialized tools and it can be analyzed to identify potential problems or performance bottlenecks. The graph is loaded by the graph runtime to be executed.

The functional blocks of a graph are defined by the set of nodes which the graph owns. Nodes can be queried via the graph using certain query functions. For example, it is possible to search for a node by its name.

SubGraph

A subgraph is a graph with additional node for interfaces. It points to the components which are accessible outside this graph. In order to use a subgraph in an existing graph or subgraph, the developer needs to create an entity where a component of the type `nvidia::gxf::Subgraph` is contained. Inside the Subgraph component a corresponding subgraph can be loaded from the yaml file indicated by *location* property and instantiated in the parent graph.

System makes the components from interface available to the parent graph when a sub-graph is loaded in the parent graph. It allows users to link sub-graphs in parent with defined interface.

A subgraph interface can be defined as follows:

```
---
interfaces:
  - name: iname # the name of the interface for the access from the parent graph
    target: n_entity/n_component # the true component in the subgraph that is represented_
    ↪by the interface
```

Node

Graph Specification uses an entity-component design principle for nodes. This means that a node is a light-weight object whose main purpose is to own components. A node is a composition of components. Every component is in exactly one node. In order to customize a node a developer does not derive from node as a base class, but instead composes objects out of components. Components can be used to provide a rich set of functionality to a node and thus to an application.

Components

Components are the main functional blocks of an application. Graph runtime provides a couple of components which implement features like properties, code execution, rules and message passing. It also allows a developer to extend the runtime by injecting her own custom components with custom features to fit a specific use case.

The most common component is a codelet or compute component which is used for data processing and code execution. To implement a custom codelet you'll need to implement a certain set of functions like *start* and *stop*. A special system - the *scheduler* - will call these functions at the specified time. Typical examples of triggering code execution are: receiving a new message from another node, or performing work on a regular schedule based on a time trigger.

Edges

Nodes can receive data from other nodes by connecting them with an edge. This essential feature allows a graph to represent a compute pipeline or a complicated AI application. An input to a node is called sink while an output is called source. There can be zero, one or multiple inputs and outputs. A source can be connected to multiple sinks and a sink can be connected to multiple sources.

Extension

An extension is a compiled shared library of a logical group of component type definitions and their implementations along with any other asset files that are required for execution of the components. Some examples of asset files are model files, shared libraries that the extension library links to and hence required to run, header and development files that enable development of additional components and extensions that use components from the extension.

An extension library is a runtime loadable module compiled with component information in a standard format that allows the graph runtime to load the extension and retrieve further information from it to:

- Allow the runtime to create components using the component types in the extension.
- Query information regarding the component types in the extension:
 - The component type name
 - The base type of the component
 - A string description of the component
 - Information of parameters of the component – parameter name, type, description etc.,

- Query information regarding the extension itself - Name of the extension, version, license, author and a string description of the extension.

The section :doc: *GraphComposer_Dev_Workflow* talks more about this with a focus on developing extensions and components.

28.1.2 Graph File Format

Graph file stores list of entities. Each entity has a unique name and list of components. Each component has a name, a type and properties. Properties are stored as key-value pairs.

```
%YAML 1.2
---
name: source
components:
- name: signal
  type: sample::test::ping
- type: nvidia::gxf::CountSchedulingTerm
  parameters:
    count: 10
---
components:
- type: nvidia::gxf::GreedyScheduler
  parameters:
    realtime: false
    max_duration_ms: 1000000
```

28.2 Graph Execution Engine

Graph Execution Engine is used to execute AI application graphs. It accepts multiple graph files as input, and all graphs are executed in same process context. It also needs manifest files as input which includes list of extensions to load. It must list all extensions required for the graph.

```
gxe --help
Flags from gxf/gxe/gxe.cpp:
  -app (GXF app file to execute. Multiple files can be comma-separated)
    type: string default: ""
  -graph_directory (Path to a directory for searching graph files.)
    type: string default: ""
  -log_file_path (Path to a file for logging.) type: string default: ""
  -manifest (GXF manifest file with extensions. Multiple files can be
    comma-separated) type: string default: ""
  -severity (Set log severity levels: 0=None, 1=Error, 2=Warning, 3=Info,
    4=Debug. Default: Info) type: int32 default: 3
```

28.3 Graph Specification TimeStamping

28.3.1 Message Passing

Once the graph is built, the communication between various entities occur by passing around messages (messages are entities themselves). Specifically, one component/codelet can publish a message entity and another can receive it. When publishing, a message should always have an associated `Timestamp` component with the name “`timestamp`”. A `Timestamp` component contains two different time values (See the `gxf/std/timestamp.hpp` header file for more information.):

1. `acqtime` - This is the time when the message entity is acquired, for instance, this would generally be the driver time of the camera when it captures an image. You must provide this timestamp if you are publishing a message in a codelet.
2. `pubtime` - This is the time when the message entity is published by a node in the graph. This will automatically get updated using the clock of the scheduler.

In a codelet, when publishing message entities using a `Transmitter (tx)`, there are two ways to add the required `Timestamp`:

1. `tx.publish(Entity message)`: You can manually add a component of type `Timestamp` with the name “`timestamp`” and set the `acqtime`. The `pubtime` in this case should be set to `0`. The message is published using the `publish(Entity message)`. **This will be deprecated in the next release.**
2. `tx.publish(Entity message, int64_t acqtime)`: You can simply call `publish(Entity message, int64_t acqtime)` with the `acqtime`. `Timestamp` will be added automatically.

28.4 The GXF Scheduler

The execution of entities in a graph is governed by the scheduler and the scheduling terms associated with every entity. A scheduler is a component responsible for orchestrating the execution of all the entities defined in a graph. A scheduler typically keeps track of the graph entities and their current execution states and passes them on to a `nvidia::gxf::EntityExecutor` component when ready for execution. The following diagram depicts the flow for an entity execution.

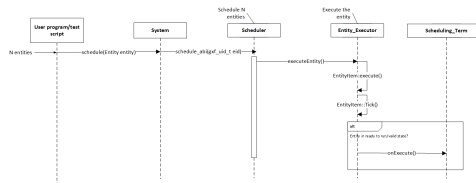


Figure: Entity execution sequence

As shown in the sequence diagram, the schedulers begin executing the graph entities via the `nvidia::gxf::System::runAsync_abi()` interface and continue this process until it meets the certain ending criteria. A single entity can have multiple codelets. These codelets are executed in the same order in which they were defined in the entity. A failure in execution of any single codelet stops the execution of all the entities. Entities are naturally unscheduled from execution when any one of their scheduling term reaches `NEVER` state.

Scheduling terms are components used to define the execution readiness of an entity. An entity can have multiple scheduling terms associated with it and each scheduling term represents the state of an entity using `SchedulingCondition`.

The table below shows various states of `nvidia::gxf::SchedulingConditionType` described using `nvidia::gxf::SchedulingCondition`.

SchedulingConditionType	Description
NEVER	Entity will never execute again
READY	Entity is ready for execution
WAIT	Entity may execute in the future
WAIT_TIME	Entity will be ready for execution after specified duration
WAIT_EVENT	Entity is waiting on an asynchronous event with unknown time interval

Schedulers define deadlock as a condition when there are no entities which are in READY, WAIT_TIME or WAIT_EVENT state which guarantee execution at a future point in time. This implies all the entities are in WAIT state for which the scheduler does not know if they ever will reach the READY state in the future. The scheduler can be configured to stop when it reaches such a state using the stop_on_deadlock parameter, else the entities are polled to check if any of them have reached READY state. max_duration configuration parameter can be used to stop execution of all entities regardless of their state after a specified amount of time has elapsed.

There are two types of schedulers currently supported by GXF

1. Greedy Scheduler
2. Multithread Scheduler

28.4.1 Greedy Scheduler

This is a basic single threaded scheduler which tests scheduling term greedily. It is great for simple use cases and predictable execution but may incur a large overhead of scheduling term execution, making it unsuitable for large applications. The scheduler requires a clock to keep track of time. Based on the choice of clock the scheduler will execute differently. If a Realtime clock is used the scheduler will execute in real-time. This means pausing execution - sleeping the thread, until periodic scheduling terms are due again. If a ManualClock is used scheduling will happen “time-compressed”. This means flow of time is altered to execute codelets in immediate succession.

The GreedyScheduler maintains a running count of entities which are in READY, WAIT_TIME and WAIT_EVENT states. The following activity diagram depicts the gist of the decision making for scheduling an entity by the greedy scheduler

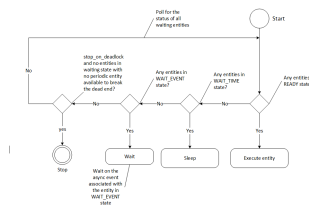


Figure: Greedy Scheduler Activity Diagram

Greedy Scheduler Configuration

The greedy scheduler takes in the following parameters from the configuration file

Parameter name	Description
clock	The clock used by the scheduler to define the flow of time. Typical choices are RealtimeClock or ManualClock
max_duration_ms	The maximum duration for which the scheduler will execute (in ms). If not specified, the scheduler will run until all work is done. If periodic terms are present this means the application will run indefinitely
stop_on_deadlock	If stop_on_deadlock is disabled, the GreedyScheduler constantly polls for the status of all the waiting entities to check if any of them are ready for execution.

Example usage - The following code snippet configures a Greedy scheduler with a ManualClock option specified.

```

name: scheduler
components:
- type: nvidia::gxf::GreedyScheduler
  parameters:
    max_duration_ms: 3000
    clock: misc/clock
    stop_on_deadlock: true
---
name: misc
components:
- name: clock
  type: nvidia::gxf::ManualClock

```

28.4.2 Multithread Scheduler

The MultiThread scheduler is more suitable for large applications with complex execution patterns. The scheduler consists of a dispatcher thread which checks the status of an entity and dispatches it to a thread pool of worker threads responsible for executing them. Worker threads enqueue the entity back on to the dispatch queue upon completion of execution. The number of worker threads can be configured using worker_thread_number parameter. The MultiThread scheduler also manages a dedicated queue and thread to handle asynchronous events. The following activity diagram demonstrates the gist of the multithread scheduler implementation.

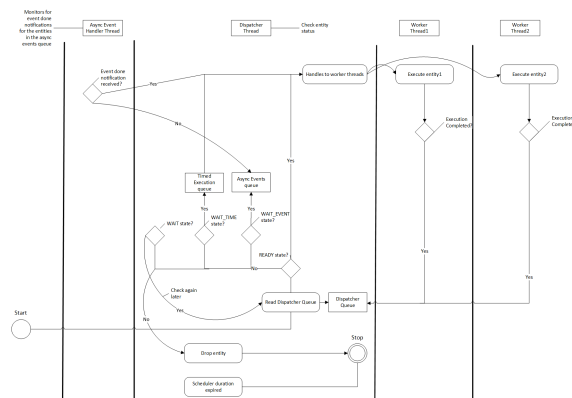


Figure: MultiThread Scheduler Activity Diagram

As depicted in the diagram, when an entity reaches WAIT_EVENT state, it's moved to a queue where they wait to receive event done notification. The asynchronous event handler thread is responsible for moving entities to the dispatcher upon receiving event done notification. The dispatcher thread also maintains a running count of the number of entities in READY, WAIT_EVENT and WAIT_TIME states and uses these statistics to check if the scheduler has

reached a deadlock. The scheduler also needs a clock component to keep track of time and it is configured using the clock parameter.

MultiThread scheduler is more resource efficient compared to the Greedy Scheduler and does not incur any additional overhead for constantly polling the states of scheduling terms. The `check_recession_period_ms` parameter can be used to configure the time interval the scheduler must wait to poll the state of entities which are in WAIT state.

Multithread Scheduler Configuration

The multithread scheduler takes in the following parameters from the configuration file

Parameter name	Description
clock	The clock used by the scheduler to define the flow of time. Typical choices are RealtimeClock or ManualClock.
max_duration_ms	The maximum duration for which the scheduler will execute (in ms). If not specified, the scheduler will run until all work is done. If periodic terms are present this means the application will run indefinitely.
check_recess_period_ms	Duration to sleep before checking the condition of an entity again [ms]. This is the maximum duration for which the scheduler would wait when an entity is not yet ready to run.
stop_on_deadlock	If enabled the scheduler will stop when all entities are in a waiting state, but no periodic entity exists to break the dead end. Should be disabled when scheduling conditions can be changed by external actors, for example by clearing queues manually.
worker_thread_number	Number of threads.

Example usage - The following code snippet configures a Multithread scheduler with the number of worked threads and max duration specified -

```

name: scheduler
components:
- type: nvidia::gxf::MultiThreadScheduler
  parameters:
    max_duration_ms: 5000
    clock: misc/clock
    worker_thread_number: 5
    check_recession_period_ms: 3
    stop_on_deadlock: false
---
name: misc
components:
- name: clock
  type: nvidia::gxf::RealtimeClock

```

28.4.3 Epoch Scheduler

The Epoch scheduler is used for running loads in externally managed threads. Each run is called an Epoch. The scheduler goes over all entities that are known to be active and executes them one by one. If the epoch budget is provided (in ms), it would keep running all codelets until the budget is consumed or no codelet is ready. It might run over budget since it guarantees to cover all codelets in epoch. In case the budget is not provided, it would go over all the codelets once and execute them only once.

The epoch scheduler takes in the following parameters from the configuration file -

Parameter name	Description
clock	The clock used by the scheduler to define the flow of time. Typical choice is a RealtimeClock.

Example usage - The following code snippet configures an Epoch scheduler -

```
name: scheduler
components:
- name: clock
  type: nvidia::gxf::RealtimeClock
- name: epoch
  type: nvidia::gxf::EpochScheduler
parameters:
  clock: clock
```

Note that the epoch scheduler is intended to run from an external thread. The `runEpoch(float budget_ms);` can be used to set the `budget_ms` and run the scheduler from the external thread. If the specified budget is not positive, all the nodes are executed once.

28.4.4 SchedulingTerms

A `SchedulingTerm` defines a specific condition that is used by an entity to let the scheduler know when it's ready for execution. There are various scheduling terms currently supported by GXF.

PeriodicSchedulingTerm

An entity associated with `nvidia::gxf::PeriodicSchedulingTerm` is ready for execution after periodic time intervals specified using its `recess_period` parameter. The `PeriodicSchedulingTerm` can either be in `READY` or `WAIT_TIME` state.

Example usage -

```
- name: scheduling_term
  type: nvidia::gxf::PeriodicSchedulingTerm
parameters:
  recess_period: 500000000
```

CountSchedulingTerm

An entity associated with `nvidia::gxf::CountSchedulingTerm` is executed for a specific number of times specified using its count parameter. The `CountSchedulingTerm` can either be in `READY` or `NEVER` state. The scheduling term reaches the `NEVER` state when the entity has been executed count number of times.

Example usage -

```
- name: scheduling_term
  type: nvidia::gxf::CountSchedulingTerm
  parameters:
    count: 42
```

MessageAvailableSchedulingTerm

An entity associated with `nvidia::gxf::MessageAvailableSchedulingTerm` is executed when the associated receiver queue has at least a certain number of elements. The receiver is specified using the `receiver` parameter of the scheduling term. The minimum number of messages that permits the execution of the entity is specified by `min_size`. An optional parameter for this scheduling term is `front_stage_max_size`, the maximum front stage message count. If this parameter is set, the scheduling term will only allow execution if the number of messages in the queue does not exceed this count. It can be used for codelets which do not consume all messages from the queue.

In the example shown below, the minimum size of the queue is configured to be 4. This means the entity will not be executed until there are at least 4 messages in the queue.

```
- type: nvidia::gxf::MessageAvailableSchedulingTerm
  parameters:
    receiver: tensors
    min_size: 4
```

MultiMessageAvailableSchedulingTerm

An entity associated with `nvidia::gxf::MultiMessageAvailableSchedulingTerm` is executed when a list of provided input receivers combined have at least a given number of messages. The `receivers` parameter is used to specify a list of the input channels/receivers. The minimum number of messages needed to permit the entity execution is set by `min_size` parameter.

Consider the example shown below. The associated entity will be executed when the number of messages combined for all the three receivers is at least the `min_size`, i.e. 5.

```
- name: input_1
  type: nvidia::gxf::test::MockReceiver
  parameters:
    max_capacity: 10
- name: input_2
  type: nvidia::gxf::test::MockReceiver
  parameters:
    max_capacity: 10
- name: input_3
  type: nvidia::gxf::test::MockReceiver
  parameters:
    max_capacity: 10
- type: nvidia::gxf::MultiMessageAvailableSchedulingTerm
```

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```

parameters:
  receivers: [input_1, input_2, input_3]
  min_size: 5

```

BooleanSchedulingTerm

An entity associated with `nvidia::gxf::BooleanSchedulingTerm` is executed when its internal state is set to tick. The parameter `enable_tick` is used to control the entity execution. The scheduling term also has two APIs `enable_tick()` and `disable_tick()` to toggle its internal state. The entity execution can be controlled by calling these APIs. If `enable_tick` is set to false, the entity is not executed (Scheduling condition is set to NEVER). If `enable_tick` is set to true, the entity will be executed (Scheduling condition is set to READY). Entities can toggle the state of the scheduling term by maintaining a handle to it.

Example usage -

```

- type: nvidia::gxf::BooleanSchedulingTerm
  parameters:
    enable_tick: true

```

AsynchronousSchedulingTerm

`AsynchronousSchedulingTerm` is primarily associated with entities which are working with asynchronous events happening outside of their regular execution performed by the scheduler. Since these events are non-periodic in nature, `AsynchronousSchedulingTerm` prevents the scheduler from polling the entity for its status regularly and reduces CPU utilization. `AsynchronousSchedulingTerm` can either be in READY, WAIT, WAIT_EVENT or NEVER states based on asynchronous event it's waiting on.

The state of an asynchronous event is described using `nvidia::gxf::AsynchronousEventState` and is updated using the `setEventState` API.

AsynchronousEventState	Description
READY	Init state, first tick is pending
WAIT	Request to async service yet to be sent, nothing to do but wait
EVENT_WAITING	Request sent to an async service, pending event done notification
EVENT_DONE	Event done notification received, entity ready to be ticked
EVENT_NEVER	Entity does not want to be ticked again, end of execution

Entities associated with this scheduling term most likely have an asynchronous thread which can update the state of the scheduling term outside of its regular execution cycle performed by the gxf scheduler. When the scheduling term is in WAIT state, the scheduler regularly polls for the state of the entity. When the scheduling term is in EVENT_WAITING state, schedulers will not check the status of the entity again until they receive an event notification which can be triggered using the `GxfEntityEventNotify` api. Setting the state of the scheduling term to EVENT_DONE automatically sends this notification to the scheduler. Entities can use the EVENT_NEVER state to indicate the end of its execution cycle.

Example usage -

```

- name: async_scheduling_term
  type: nvidia::gxf::AsynchronousSchedulingTerm

```

DownstreamReceptiveSchedulingTerm

This scheduling term specifies that an entity shall be executed if the receiver for a given transmitter can accept new messages.

Example usage -

```
- name: downstream_st
  type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
  parameters:
    transmitter: output
    min_size: 1
```

TargetTimeSchedulingTerm

This scheduling term permits execution at a user-specified timestamp. The timestamp is specified on the clock provided.

Example usage -

```
- name: target_st
  type: nvidia::gxf::TargetTimeSchedulingTerm
  parameters:
    clock: clock/manual_clock
```

ExpiringMessageAvailableSchedulingTerm

This scheduling waits for a specified number of messages in the receiver. The entity is executed when the first message received in the queue is expiring or when there are enough messages in the queue. The `receiver` parameter is used to set the receiver to watch on. The parameters `max_batch_size` and `max_delay_ns` dictate the maximum number of messages to be batched together and the maximum delay from first message to wait before executing the entity respectively.

In the example shown below, the associated entity will be executed when the number of messages in the queue is greater than `max_batch_size`, i.e 5, or when the delay from the first message to current time is greater than `max_delay_ns`, i.e 10000000.

```
- name: target_st
  type: nvidia::gxf::ExpiringMessageAvailableSchedulingTerm
  parameters:
    receiver: signal
    max_batch_size: 5
    max_delay_ns: 10000000
    clock: misc/clock
```

AND Combined

An entity can be associated with multiple scheduling terms which define its execution behavior. Scheduling terms are AND combined to describe the current state of an entity. For an entity to be executed by the scheduler, all the scheduling terms must be in READY state and conversely, the entity is unscheduled from execution whenever any one of the scheduling term reaches NEVER state. The priority of various states during AND combine follows the order NEVER, WAIT_EVENT, WAIT, WAIT_TIME, and READY.

Example usage -

```
components:
- name: integers
  type: nvidia::gxf::DoubleBufferTransmitter
- name: fibonacci
  type: nvidia::gxf::DoubleBufferTransmitter
- type: nvidia::gxf::CountSchedulingTerm
  parameters:
    count: 100
- type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
  parameters:
    transmitter: integers
    min_size: 1
```

BTSchedulingTerm

A BT (Behavior Tree) scheduling term is used to schedule a behavior tree entity itself and its child entities (if any) in a Behavior tree.

Example usage -

```
name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_codelet
  type: nvidia::gxf::SequenceBehavior
  parameters:
    children: [ child1/child1_st ]
    s_term: root_st
    controller: root_controller
```

28.5 Behavior Trees

Behavior tree codelets are one of the mechanisms to control the flow of tasks in GXF. They follow the same general behavior as classical behavior trees, with some useful additions for robotics applications. This document gives an overview of the general concept, the available behavior tree node types, and some examples of how to use them individually or in conjunction with each other.

28.5.1 General Concept

Behavior trees consist of n-ary trees of entities that can have zero or more children. The conditional execution of parent entity is based on the status of execution of the children. A behavior tree is graphically represented as a directed tree in which the nodes are classified as root, control flow nodes, or execution nodes (tasks). For each pair of connected nodes, the outgoing node is called parent and the incoming node is called child.

The execution of a behavior tree starts from the root which sends ticks with a certain frequency to its child. When the execution of a node in the behavior tree is allowed, it returns to the parent a status running if its execution has not finished yet, success if it has achieved its goal, or failure otherwise. The behavior tree also uses a controller component for controlling the entity's termination policy and the execution status. One of the controller behaviors currently implemented for Behavior Tree is `EntityCountFailureRepeatController`, which repeats the entity on failure up to `repeat_count` times before deactivating it.

GXF supports several behavior tree codelets which are explained in the following section.

28.5.2 Behavior Tree Codelets

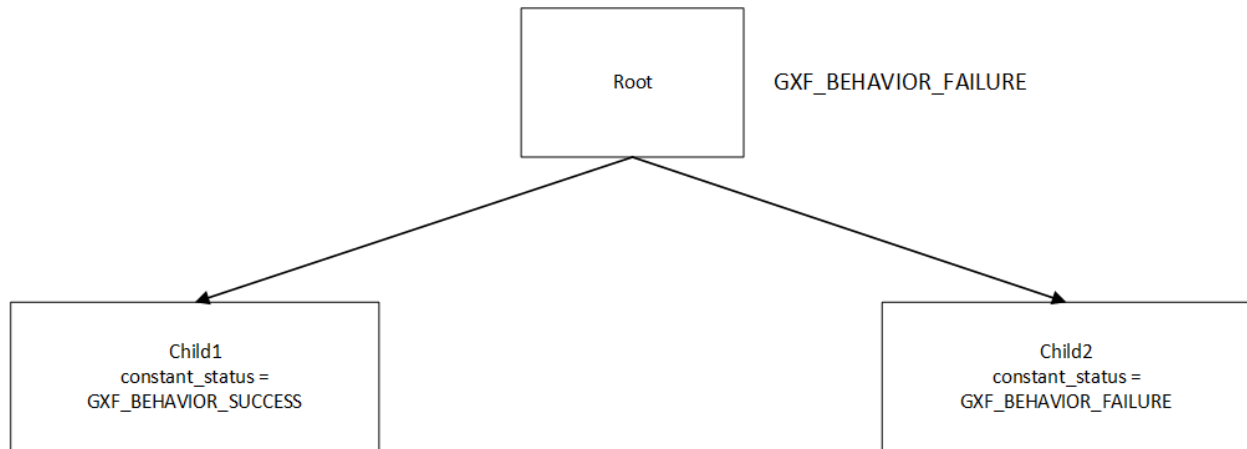
Each behavior tree codelet can have a set of parameters defining how it should behave. Note that in all the examples given below, the naming convention for configuring the children parameter for root codelets is `[child_codelet_name\child_codelet_scheduling_term]`.

Constant Behavior

After each tick period, switches its own status to the configured desired constant status.

Parameter	Description
<code>s_term</code>	scheduling term used for scheduling the entity itself
<code>constant_status</code>	The desired status to switch to during each tick time.

An example diagram depicting Constant behavior used in conjunction with a Sequence behavior defined for root entity is shown below



Here, the child1 is configured to return a constant status of success (`GXF_BEHAVIOR_SUCCESS`) and child2 returns failure (`GXF_BEHAVIOR_FAILURE`), resulting into the root node (configured to exhibit sequence behavior) returning `GXF_BEHAVIOR_FAILURE`.

The controller for each child can be configured to repeat the execution on failure. A code snippet of configuring the example described is shown below.

```

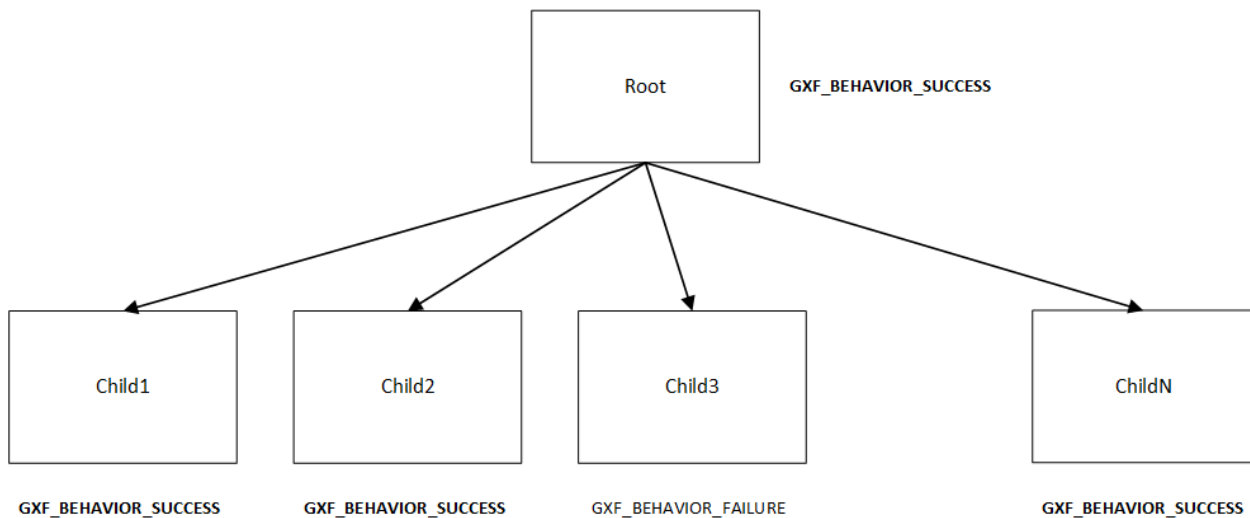
name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_codelet
  type: nvidia::gxf::SequenceBehavior
  parameters:
    children: [ child1/child1_st, child2/child2_st ]
    s_term: root_st
---
name: child2
components:
- name: child2_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 3
    return_behavior_running_if_failure_repeat: true
- name: child2_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: false
- name: child2_codelet
  type: nvidia::gxf::ConstantBehavior
  parameters:
    s_term: child2_st
    constant_status: 1
  
```

Parallel Behavior

Runs its child nodes in parallel. By default, succeeds when all child nodes succeed, and fails when all child nodes fail. This behavior can be customized using the parameters below.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
children	Child entities
success_threshold	Number of successful children required for success. A value of -1 means all children must succeed for this node to succeed.
failure_threshold	Number of failed children required for failure. A value of -1 means all children must fail for this node to fail.

The diagram below shows a graphical representation of a parallel behavior configured with failure_threshold configured as -1. Hence, the root node returns GXF_BEHAVIOR_SUCCESS even if one child returns a failure status.



A code snippet to configure the example described is shown below.

```

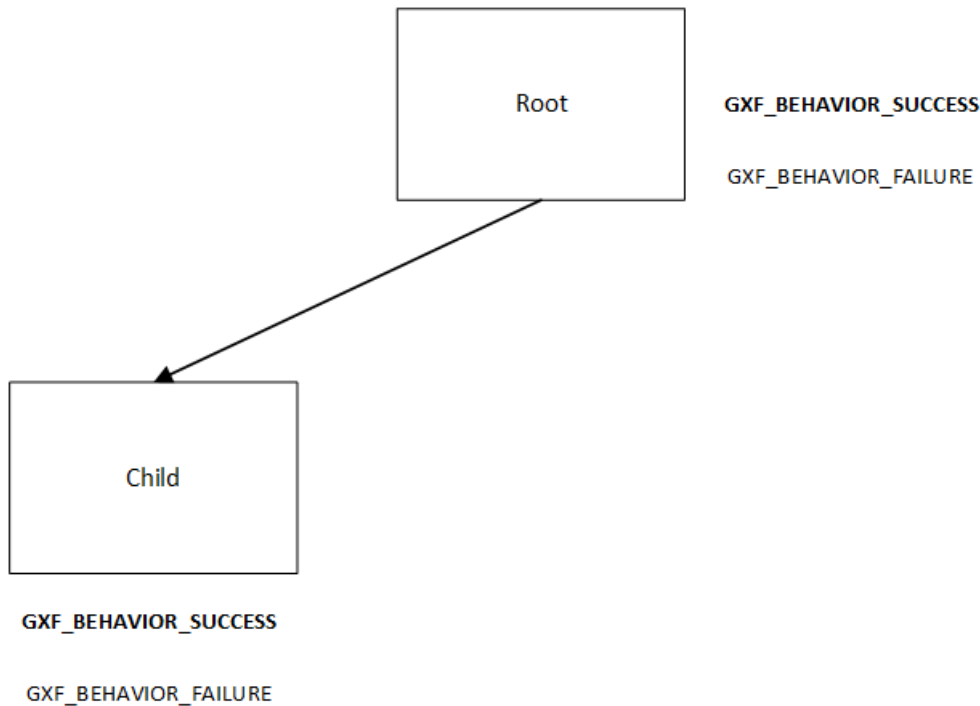
name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_codelet
  type: nvidia::gxf::ParallelBehavior
  parameters:
    children: [ child1/child1_st, child2/child2_st ]
    s_term: root_st
    success_threshold: 1
    failure_threshold: -1
  
```

Repeat Behavior

Repeats its only child entity. By default, won't repeat when the child entity fails. This can be customized using the parameters below.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
repeat_after_failure	Denotes whether to repeat the child after it has failed.

The diagram below shows a graphical representation of a repeat behavior. The root entity can be configured to repeat the only child to repeat after failure. It succeeds when the child entity succeeds.



A code snippet to configure a repeat behavior is as shown below -

```

name: repeat_knock
components:
- name: repeat_knock_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: repeat_knock_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: false
- name: repeat_codelet
  type: nvidia::gxf::RepeatBehavior
  parameters:
    s_term: repeat_knock_st
    children: [ knock_on_door/knock_on_door_st ]
    repeat_after_failure: true
  
```

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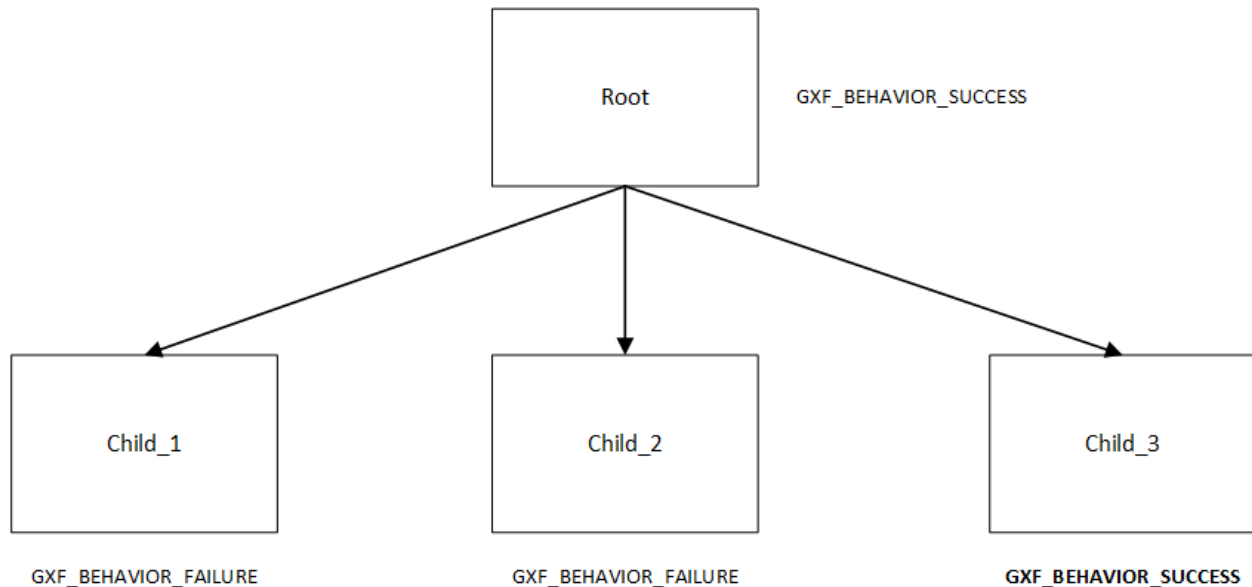
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Selector Behavior

Runs all child entities in sequence until one succeeds, then reports success. If all child entities fail (or no child entities are present), this codelet fails.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
children	Child entities

The diagram below shows a graphical representation of a Selector behavior. The root entity starts child_1, child_2 and child_3 in a sequence. Although child_1 and child_2 fail, the root entity will return success since child_3 returns successfully.



A code snippet to configure a selector behavior is as shown below -

```

name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_sel_codelet
  type: nvidia::gxf::SelectorBehavior
  parameters:
    children: [ door_distance/door_distance_st, door_detected/door_detected_st, knock/
↪knock_st ]
  
```

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```

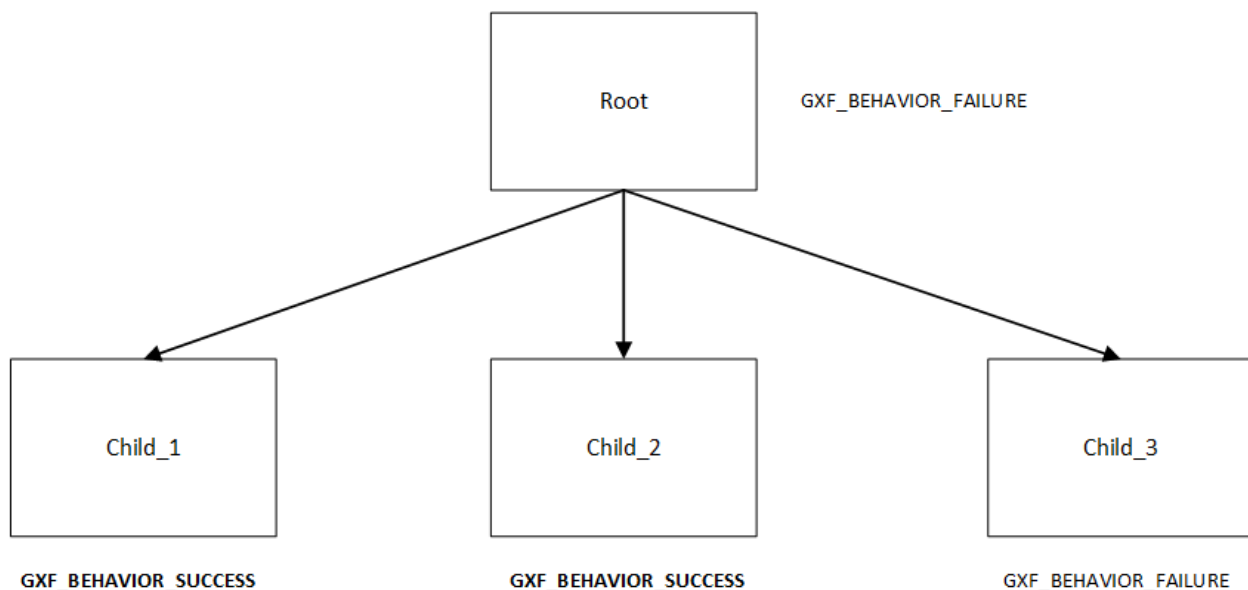
s_term: root_st
---
name: door_distance
components:
- name: door_distance_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: door_distance_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: false
- name: door_dist
  type: nvidia::gxf::SequenceBehavior
  parameters:
    children: []
    s_term: door_distance_st
---
```

Sequence Behavior

Runs its child entities in sequence, in the order in which they are defined. Succeeds when all child entities succeed or fails as soon as one child entity fails.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
children	Child entities

The diagram below shows a graphical representation of a Sequence behavior. The root entity starts child_1, child_2 and child_3 in a sequence. Although child_1 and child_2 pass, the root entity will return failure since child_3 returns failure.



A code snippet to configure a sequence behavior is as shown below -

```
name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_codelet
  type: nvidia::gxf::SequenceBehavior
  parameters:
    children: [ child1/child1_st, child2/child2_st ]
    s_term: root_st
```

Switch Behavior

Runs the child entity with the index defined as desired_behavior.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
children	Child entities
desired_behavior	The index of child entity to switch to when this entity runs

In the code snippet shown below, the desired behavior of the root entity is designated to be the the child at index 1. (scene). Hence, that is the entity that is run.

```
name: root
components:
- name: root_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
    max_repeat_count: 0
- name: root_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: true
- name: root_switch_codelet
  type: nvidia::gxf::SwitchBehavior
  parameters:
    children: [ scene/scene_st, ref/ref_st ]
    s_term: root_st
    desired_behavior: 0
---
name: scene
components:
- name: scene_controller
  type: nvidia::gxf::EntityCountFailureRepeatController
  parameters:
```

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```

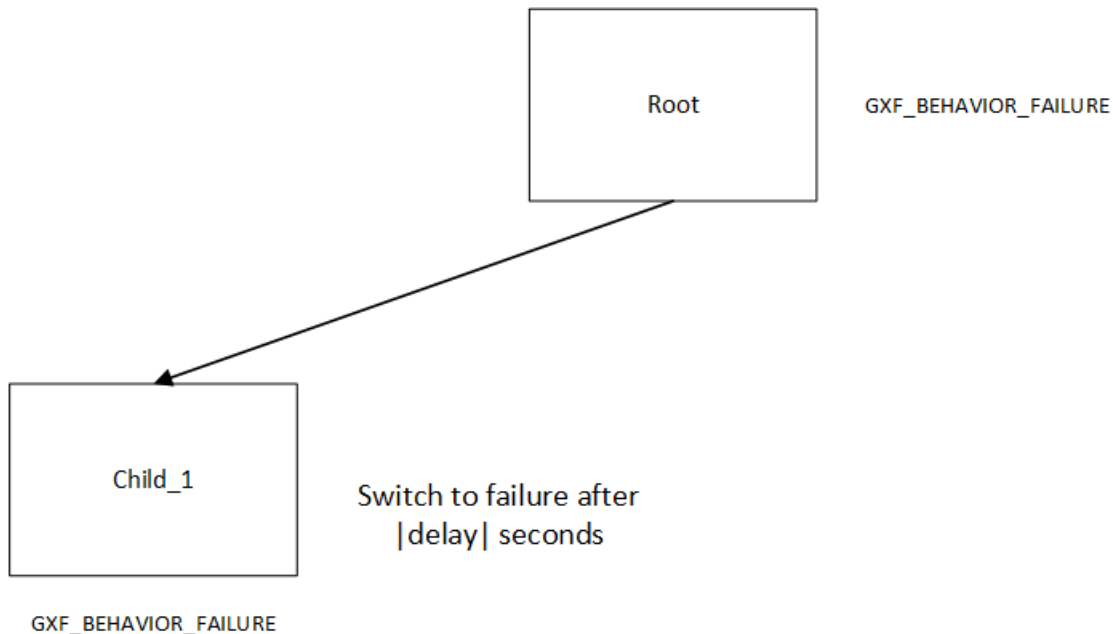
    max_repeat_count: 0
- name: scene_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: false
- name: scene_seq
  type: nvidia::gxf::SequenceBehavior
  parameters:
    children: [ pose/pose_st, det/det_st, seg/seg_st ]
    s_term: scene_st
---
```

Timer Behavior

Waits for a specified amount of time delay and switches to the configured result switch_status afterwards.

Parameter	Description
s_term	scheduling term used for scheduling the entity itself
clock	Clock
switch_status	Configured result to switch to after the specified delay
delay	Configured delay

In the diagram shown below, the child entity switches to failure after a configured delay period. The root entity hence returns failure.



A code snippet for the same shown below -

```

name: knock_on_door
components:
- name: knock_on_door_controller

```

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```

type: nvidia::gxf::EntityCountFailureRepeatController
parameters:
  max_repeat_count: 10
- name: knock_on_door_st
  type: nvidia::gxf::BTSchedulingTerm
  parameters:
    is_root: false
- name: knock
  type: nvidia::gxf::TimerBehavior
  parameters:
    switch_status: 1
    clock: sched/clock
    delay: 1
    s_term: knock_on_door_st
---
```

28.6 GXF Core C APIs

28.6.1 Context

Create context

```
gxf_result_t GxfContextCreate(gxf_context_t* context);
```

Creates a new GXF context

A GXF context is required for all almost all GXF operations. The context must be destroyed with ‘GxfContextDestroy’. Multiple contexts can be created in the same process, however they can not communicate with each other.

parameter: context The new GXF context is written to the given pointer.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Create a context from a shared context

```
gxf_result_t GxfContextCreate1(gxf_context_t shared, gxf_context_t* context);
```

Creates a new runtime context from shared context.

A shared runtime context is used for sharing entities between graphs running within the same process.

parameter: shared A valid GXF shared context.

parameter: context The new GXF context is written to the given pointer

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Destroy context

```
gxf_result_t GxfContextDestroy(gxf_context_t context);
```

Destroys a GXF context

Every GXF context must be destroyed by calling this function. The context must have been previously created with 'GxfContextCreate'. This will also destroy all entities and components which were created as part of the context.

parameter: `context` A valid GXF context.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

28.6.2 Extensions

Maximum number of extensions in a context can be 1024.

Load Extensions from a file

```
gxf_result_t GxfLoadExtension(gxf_context_t context, const char* filename);
```

Loads extension in the given context from file.

parameter: `context` A valid GXF context

parameter: `filename` A valid filename.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

This function will be deprecated.

Load Extension libraries

```
gxf_result_t GxfLoadExtensions(gxf_context_t context, const GxfLoadExtensionsInfo* info);
```

Loads GXF extension libraries

Loads one or more extensions either directly by their filename or indirectly by loading manifest files. Before a component can be added to a GXF entity the GXF extension shared library providing the component must be loaded. An extensions must only be loaded once.

To simplify loading multiple extensions at once the developer can create a manifest file which lists all extensions he needs. This function will then load all extensions listed in the manifest file. Multiple manifest may be loaded, however each extensions may still be loaded only a single time.

A manifest file is a YAML file with a single top-level entry 'extensions' followed by a list of filenames of GXF extension shared libraries.

Example: — START OF FILE — extensions: - gxf/std/libgxf_std.so - gxf/npp/libgxf_npp.so — END OF FILE —

parameter: `context` A valid GXF context

parameter: `filename` A valid filename.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

```
gxf_result_t GxfLoadExtensionManifest(gxf_context_t context, const char*
manifest_filename);
```

Loads extensions from manifest file.

parameter: `context` A valid GXF context.

parameter: `filename` A valid filename.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

This function will be deprecated.

Load Metadata files

```
gxf_result_t GxfLoadExtensionMetadataFiles(gxf_context_t context, const char* const*
filenames, uint32_t count);
```

Loads an extension registration metadata file

Reads a metadata file of the contents of an extension used for registration. These metadata files can be used to resolve typename and TID's of components for other extensions which depend on them. Metadata files do not contain the actual implementation of the extension and must be loaded only to run the extension query API's on extension libraries which have the actual implementation and only depend on the metadata for type resolution.

If some components of extension B depend on some components in extension A: - Load metadata file for extension A
- Load extension library for extension B using 'GxfLoadExtensions' - Run extension query api's on extension B and it's components.

parameter: `context` A valid GXF context.

parameter: `filenames` absolute paths of metadata files.

parameter: `count` The number of metadata files to be loaded

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Register component

```
gxf_result_t GxfRegisterComponent(gxf_context_t context, gxf_tid_t tid, const char* name,
const char* base_name);
```

Registers a component with a GXF extension

A GXF extension need to register all of its components in the extension factory function. For convenience the helper macros in `gxf/std/extension_factory_helper.hpp` can be used.

The developer must choose a unique GXF tid with two random 64-bit integers. The developer must ensure that every GXF component has a unique tid. The name of the component must be the fully qualified C++ type name of the component. A component may only have a single base class and that base class must be specified with its fully qualified C++ type name as the parameter 'base_name'.

ref: `gxf/std/extension_factory_helper.hpp` ref: `core/type_name.hpp`

parameter: `context` A valid GXF context

parameter: `tid` The chosen GXF tid

parameter: `name` The type name of the component

parameter: `base_name` The type name of the base class of the component

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

28.6.3 Graph Execution

Loads a list of entities from YAML file

```
gxf_result_t GxfGraphLoadFile(gxf_context_t context, const char* filename, const char* parameters_override[], const uint32_t num_overrides);
```

parameter: context A valid GXF context

parameter: filename A valid YAML filename.

parameter: params_override An optional array of strings used for override parameters in yaml file.

parameter: num_overrides Number of optional override parameter strings.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Set the root folder for searching YAML files during loading

```
gxf_result_t GxfGraphSetRootPath(gxf_context_t context, const char* path);
```

parameter: context A valid GXF context

parameter: path Path to root folder for searching YAML files during loading

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Loads a list of entities from YAML text

```
gxf_result_t GxfGraphParseString(gxf_context_t context, const char* tex, const char* parameters_override[], const uint32_t num_overrides);
```

parameter: context A valid GXF context

parameter: text A valid YAML text.

parameter: params_override An optional array of strings used for override parameters in yaml file.

parameter: num_overrides Number of optional override parameter strings.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Activate all system components

```
gxf_result_t GxfGraphActivate(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Deactivate all System components

```
gxf_result_t GxfGraphDeactivate(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Starts the execution of the graph asynchronously

```
gxf_result_t GxfGraphRunAsync(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Interrupt the execution of the graph

```
gxf_result_t GxfGraphInterrupt(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Waits for the graph to complete execution

```
gxf_result_t GxfGraphWait(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.`

Runs all System components and waits for their completion

```
gxf_result_t GxfGraphRun(gxf_context_t context);
```

parameter: context A valid GXF context

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

28.6.4 Entities**Create an entity**

```
gxf_result_t GxfEntityCreate(gxf_context_t context, gxf_uid_t* eid);
```

Creates a new entity and updates the eid to the unique identifier of the newly created entity.

This method will be deprecated.

```
gxf_result_t GxfCreateEntity((gxf_context_t context, const GxfEntityCreateInfo* info,
gxf_uid_t* eid);
```

Create a new GXF entity.

Entities are light-weight containers to hold components and form the basic building blocks of a GXF application. Entities are created when a GXF file is loaded, or they can be created manually using this function. Entities created with this function must be destroyed using 'GxfEntityDestroy'. After the entity was created components can be added

to it with ‘GxfComponentAdd’. To start execution of codelets on an entity the entity needs to be activated first. This can happen automatically using ‘GXF_ENTITY_CREATE_PROGRAM_BIT’ or manually using ‘GxfEntityActivate’.

parameter **context**: GXF context that creates the entity. parameter **info**: pointer to a GxfEntityCreateInfo structure containing parameters affecting the creation of the entity. parameter **eid**: pointer to a gxf_uid_t handle in which the resulting entity is returned. returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Activate an entity

```
gxf_result_t GxfEntityActivate(gxf_context_t context, gxf_uid_t eid);
```

Activates a previously created and inactive entity

Activating an entity generally marks the official start of its lifetime and has multiple implications: - If mandatory parameters, i.e. parameter which do not have the flag “optional”, are not set the operation will fail.

- All components on the entity are initialized.
- All codelets on the entity are scheduled for execution. The scheduler will start calling start, tick and stop functions as specified by scheduling terms.
- After activation trying to change a dynamic parameters will result in a failure.
- Adding or removing components of an entity after activation will result in a failure.

parameter: **context** A valid GXF context

parameter: **eid** UID of a valid entity

returns: GXF error code

Deactivate an entity

```
gxf_result_t GxfEntityDeactivate(gxf_context_t context, gxf_uid_t eid);
```

Deactivates a previously activated entity

Deactivating an entity generally marks the official end of its lifetime and has multiple implications:

- All codelets are removed from the schedule. Already running entities are run to completion.
- All components on the entity are deinitialized.
- Components can be added or removed again once the entity was deactivated.
- Mandatory and non-dynamic parameters can be changed again.

Note: In case that the entity is currently executing this function will wait and block until

the current execution is finished.

parameter: **context** A valid GXF context

parameter: **eid** UID of a valid entity

returns: GXF error code

Destroy an entity

```
gxf_result_t GxfEntityDestroy(gxf_context_t context, gxf_uid_t eid);
```

Destroys a previously created entity

Destroys an entity immediately. The entity is destroyed even if the reference count has not yet reached 0. If the entity is active it is deactivated first.

Note: This function can block for the same reasons as ‘GxfEntityDeactivate’.

parameter: `context` A valid GXF context

parameter: `eid` The returned UID of the created entity

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Find an entity

```
gxf_result_t GxfEntityFind(gxf_context_t context, const char* name, gxf_uid_t* eid);
```

Finds an entity by its name

parameter: `context` A valid GXF context

parameter: `name` A C string with the name of the entity. Ownership is not transferred.

parameter: `eid` The returned UID of the entity

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Find all entities

```
gxf_result_t GxfEntityFindAll(gxf_context_t context, uint64_t* num_entities, gxf_uid_t* entities);
```

Finds all entities in the current application

Finds and returns all entity ids for the current application. If more than *max_entities* exist only *max_entities* will be returned. The order and selection of entities returned is arbitrary.

parameter: `context` A valid GXF context

parameter: `num_entities` In/Out: the max number of entities that can fit in the buffer/the number of entities that exist in the application

parameter: `entities` A buffer allocated by the caller for returned UIDs of all entities, with capacity for *num_entities*.

returns: `GXF_SUCCESS` if the operation was successful, `GXF_QUERY_NOT_ENOUGH_CAPACITY` if more entities exist in the application than *max_entities*, or otherwise one of the GXF error codes.

Increase reference count of an entity

```
gxf_result_t GxfEntityRefCountInc(gxf_context_t context, gxf_uid_t eid);
```

Increases the reference count for an entity by 1.

By default reference counting is disabled for an entity. This means that entities created with ‘GxfEntityCreate’ are not automatically destroyed. If this function is called for an entity with disabled reference count, reference counting is enabled and the reference count is set to 1. Once reference counting is enabled an entity will be automatically destroyed if the reference count reaches zero, or if ‘GxfEntityCreate’ is called explicitly.

parameter: `context` A valid GXF context

parameter: `eid` The UID of a valid entity

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Decrease reference count of an entity

```
gxf_result_t GxfEntityRefCountDec(gxf_context_t context, gxf_uid_t eid);
```

Decreases the reference count for an entity by 1.

See ‘GxfEntityRefCountInc’ for more details on reference counting.

parameter: `context` A valid GXF context

parameter: `eid` The UID of a valid entity

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Get status of an entity

```
gxf_result_t GxfEntityGetStatus(gxf_context_t context, gxf_uid_t eid,  
gxf_entity_status_t* entity_status);
```

Gets the status of the entity.

See ‘gxf_entity_status_t’ for the various status.

parameter: `context` A valid GXF context

parameter: `eid` The UID of a valid entity

parameter: `entity_status` output; status of an entity `eid`

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Get state of an entity

```
gxf_result_t GxfEntityGetState(gxf_context_t context, gxf_uid_t eid, entity_state_t*  
entity_state);
```

Gets the state of the entity.

See ‘gxf_entity_status_t’ for the various status.

parameter: `context` A valid GXF context

parameter: `eid` The UID of a valid entity

parameter: `entity_state` output; behavior status of an entity `eid` used by the behavior tree parent codelet

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Notify entity of an event

```
gxf_result_t GxfEntityEventNotify(gxf_context_t context, gxf_uid_t eid);
```

Notifies the occurrence of an event and inform the scheduler to check the status of the entity

The entity must have an 'AsynchronousSchedulingTerm' scheduling term component and it must be in "EVENT_WAITING" state for the notification to be acknowledged.

See 'AsynchronousEventState' for various states

parameter: context A valid GXF context

parameter: eid The UID of a valid entity

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

28.6.5 Components

Maximum number of components in an entity or an extension can be up to 1024.

Get component type identifier

```
gxf_result_t GxfComponentTypeId(gxf_context_t context, const char* name, gxf_tid_t* tid);
```

Gets the GXF unique type ID (TID) of a component

Get the unique type ID which was used to register the component with GXF. The function expects the fully qualified C++ type name of the component including namespaces.

Example of a valid component type name: "nvidia::gxf::test::PingTx"

parameter: context A valid GXF context

parameter: name The fully qualified C++ type name of the component

parameter: tid The returned TID of the component

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get component type name

```
gxf_result_t GxfComponentTypeName(gxf_context_t context, gxf_tid_t tid, const char** name);
```

Gets the fully qualified C++ type name GXF component typename

Get the unique typename of the component with which it was registered using one of the GXF_EXT_FACTORY_ADD*() macros

parameter: context A valid GXF context

parameter: tid The unique type ID (TID) of the component with which the component was registered

parameter: name The returned name of the component

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get component name

```
gxf_result_t GxfComponentName(gxf_context_t context, gxf_uid_t cid, const char** name);
```

Gets the name of a component

Each component has a user-defined name which was used in the call to 'GxfComponentAdd'. Usually the name is specified in the GXF application file.

parameter: `context` A valid GXF context

parameter: `cid` The unique object ID (UID) of the component

parameter: `name` The returned name of the component

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Get unique identifier of the entity of given component

```
gxf_result_t GxfComponentEntity(gxf_context_t context, gxf_uid_t cid, gxf_uid_t* eid);
```

Gets the unique object ID of the entity of a component

Each component has a unique ID with respect to the context and is stored in one entity. This function can be used to retrieve the ID of the entity to which a given component belongs.

parameter: `context` A valid GXF context

parameter: `cid` The unique object ID (UID) of the component

parameter: `eid` The returned UID of the entity

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Add a new component

```
gxf_result_t GxfComponentAdd(gxf_context_t context, gxf_uid_t eid, gxf_tid_t tid, const char* name, gxf_uid_t* cid);
```

Adds a new component to an entity

An entity can contain multiple components and this function can be used to add a new component to an entity. A component must be added before an entity is activated, or after it was deactivated. Components must not be added to active entities. The order of components is stable and identical to the order in which components are added (see 'GxfComponentFind').

parameter: `context` A valid GXF context

parameter: `eid` The unique object ID (UID) of the entity to which the component is added.

parameter: `tid` The unique type ID (TID) of the component to be added to the entity.

parameter: `name` The name of the new component. Ownership is not transferred.

parameter: `cid` The returned UID of the created component

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Add component to entity interface

```
gxf_result_t GxfComponentAddToInterface(gxf_context_t context, gxf_uid_t eid, gxf_uid_t cid, const char* name);
```

Adds an existing component to the interface of an entity

An entity can hold references to other components in its interface, so that when finding a component in an entity, both the component this entity holds and those it refers to will be returned. This supports the case when an entity contains a subgraph, then those components that have been declared in the subgraph interface will be put to the interface of the parent entity.

parameter: `context` A valid GXF context

parameter: `eid` The unique object ID (UID) of the entity to which the component is added.

parameter: `cid` The unique object ID of the component.

parameter: `name` The name of the new component. Ownership is not transferred.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Find a component in an entity

```
gxf_result_t GxfComponentFind(gxf_context_t context, gxf_uid_t eid, gxf_tid_t tid, const char* name, int32_t* offset, gxf_uid_t* cid);
```

Finds a component in an entity

Searches components in an entity which satisfy certain criteria: component type, component name, and component min index. All three criteria are optional; in case no criteria is given the first component is returned. The main use case for “component min index” is a repeated search which continues at the index which was returned by a previous search.

In case no entity with the given criteria was found `GXF_ENTITY_NOT_FOUND` is returned.

parameter: `context` A valid GXF context

parameter: `eid` The unique object ID (UID) of the entity which is searched.

parameter: `tid` The component type ID (TID) of the component to find (optional)

parameter: `name` The component name of the component to find (optional). Ownership not transferred.

parameter: `offset` The index of the first component in the entity to search. Also contains the index of the component which was found.

parameter: `cid` The returned UID of the searched component

returns: `GXF_SUCCESS` if a component matching the criteria was found, `GXF_ENTITY_NOT_FOUND` if no component matching the criteria was found, or otherwise one of the GXF error codes.

Get type identifier for a component

```
gxf_result_t GxfComponentType(gxf_context_t context, gxf_uid_t cid, gxf_tid_t* tid);
```

Gets the component type ID (TID) of a component

parameter: `context` A valid GXF context

parameter: `cid` The component object ID (UID) for which the component type is requested.

parameter: `tid` The returned TID of the component

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Gets pointer to component

```
gxf_result_t GxfComponentPointer(gxf_context_t context, gxf_uid_t uid, gxf_tid_t tid, void** pointer);
```

Verifies that a component exists, has the given type, gets a pointer to it.

parameter: context A valid GXF context

parameter: uid The component object ID (UID).

parameter: tid The expected component type ID (TID) of the component

parameter: pointer The returned pointer to the component object.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

28.6.6 Primitive Parameters

64-bit floating point

Set

```
gxf_result_t GxfParameterSetFloat64(gxf_context_t context, gxf_uid_t uid, const char* key, double value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value a double value

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetFloat64(gxf_context_t context, gxf_uid_t uid, const char* key, double* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to get the double value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

64-bit signed integer

Set

```
gxf_result_t GxfParameterSetInt64(gxf_context_t context, gxf_uid_t uid, const char* key,
int64_t value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value 64-bit integer value to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetInt64(gxf_context_t context, gxf_uid_t uid, const char* key,
int64_t* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to get the 64-bit integer value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

64-bit unsigned integer

Set

```
gxf_result_t GxfParameterSetUInt64(gxf_context_t context, gxf_uid_t uid, const char* key,
uint64_t value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value unsigned 64-bit integer value to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetUInt64(gxf_context_t context, gxf_uid_t uid, const char* key,
uint64_t* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to get the unsigned 64-bit integer value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

32-bit signed integer

Set

```
gxf_result_t GxfParameterSetInt32(gxf_context_t context, gxf_uid_t uid, const char* key,
int32_t value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value 32-bit integer value to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetInt32(gxf_context_t context, gxf_uid_t uid, const char* key,
int32_t* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to get the 32-bit integer value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

String parameter

Set

```
gxf_result_t GxfParameterSetStr(gxf_context_t context, gxf_uid_t uid, const char* key,
const char* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value A char array containing value to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetStr(gxf_context_t context, gxf_uid_t uid, const char* key,
const char** value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to a char* array to get the value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Boolean

Set

```
gxf_result_t GxfParameterSetBool(gxf_context_t context, gxf_uid_t uid, const char* key,
bool value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value A boolean value to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetBool(gxf_context_t context, gxf_uid_t uid, const char* key,
bool* value);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value pointer to get the boolean value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Handle

Set

```
gxf_result_t GxfParameterSetHandle(gxf_context_t context, gxf_uid_t uid, const char* key, gxf_uid_t cid);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: cid Unique identifier to set.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get

```
gxf_result_t GxfParameterGetHandle(gxf_context_t context, gxf_uid_t uid, const char* key, gxf_uid_t* cid);
```

parameter: context A valid GXF context.

parameter: uid A valid component identifier.

parameter: key A valid name of a component to set.

parameter: value Pointer to a unique identifier to get the value.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

28.6.7 Vector Parameters

To set or get the vector parameters of a component, users can use the following C-APIs for various data types:

Set 1-D Vector Parameters

Users can call `gxf_result_t GxfParameterSet1D"DataType"Vector(gxf_context_t context, gxf_uid_t uid, const char* key, data_type* value, uint64_t length)`

value should point to an array of the data to be set of the corresponding type. The size of the stored array should match the length argument passed.

See the table below for all the supported data types and their corresponding function signatures.

parameter: key The name of the parameter

parameter: value The value to set of the parameter

parameter: length The length of the vector parameter

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Table 28.1: Supported Data Types to Set 1D Vector Parameters

Function Name	data_type
GxfParameterSet1DFloat64Vector(...)	double
GxfParameterSet1DInt64Vector(...)	int64_t
GxfParameterSet1DUInt64Vector(...)	uint64_t
GxfParameterSet1DInt32Vector(...)	int32_t

Set 2-D Vector Parameters

Users can call `gxf_result_t GxfParameterSet2D"DataType"Vector(gxf_context_t context, gxf_uid_t uid, const char* key, data_type** value, uint64_t height, uint64_t width)`

`value` should point to an array of array (and not to the address of a contiguous array of data) of the data to be set of the corresponding type. The length of the first dimension of the array should match the `height` argument passed and similarly the length of the second dimension of the array should match the `width` passed.

See the table below for all the supported data types and their corresponding function signatures.

parameter: `key` The name of the parameter

parameter: `value` The value to set of the parameter

parameter: `height` The height of the 2-D vector parameter

parameter: `width` The width of the 2-D vector parameter

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Table 28.2: Supported Data Types to Set 2D Vector Parameters

Function Name	data_type
GxfParameterSet2DFloat64Vector(...)	double
GxfParameterSet2DInt64Vector(...)	int64_t
GxfParameterSet2DUInt64Vector(...)	uint64_t
GxfParameterSet2DInt32Vector(...)	int32_t

Get 1-D Vector Parameters

Users can call `gxf_result_t GxfParameterGet1D"DataType"Vector(gxf_context_t context, gxf_uid_t uid, const char* key, data_type** value, uint64_t* length)` to get the value of a 1-D vector.

Before calling this method, users should call `GxfParameterGet1D"DataType"VectorInfo(gxf_context_t context, gxf_uid_t uid, const char* key, uint64_t* length)` to obtain the length of the vector parameter and then allocate at least that much memory to retrieve the value.

`value` should point to an array of size greater than or equal to `length` allocated by user of the corresponding type to retrieve the data. If the `length` doesn't match the size of stored vector then it will be updated with the expected size.

See the table below for all the supported data types and their corresponding function signatures.

parameter: `key` The name of the parameter

parameter: `value` The value to set of the parameter

parameter: `length` The length of the 1-D vector parameter obtained by calling `GxfParameterGet1D"DataType"VectorInfo(...)`

Table 28.3: Supported Data Types to Get the Value of 1D Vector Parameters

Function Name	data_type
GxfParameterGet1DFloat64Vector(...)	double
GxfParameterGet1DInt64Vector(...)	int64_t
GxfParameterGet1DUInt64Vector(...)	uint64_t
GxfParameterGet1DInt32Vector(...)	int32_t

Get 2-D Vector Parameters

Users can call `gxf_result_t GxfParameterGet2D"DataType"Vector(gxf_context_t context, gxf_uid_t uid, const char* key, data_type** value, uint64_t* height, uint64_t* width)` to get the value of a 2D vector.

Before calling this method, users should call `GxfParameterGet1D"DataType"VectorInfo(gxf_context_t context, gxf_uid_t uid, const char* key, uint64_t* height, uint64_t* width)` to obtain the height and width of the 2D-vector parameter and then allocate at least that much memory to retrieve the value.

value should point to an array of array of height (size of first dimension) greater than or equal to height and width (size of the second dimension) greater than or equal to width allocated by user of the corresponding type to get the data. If the height or width don't match the height and width of the stored vector then they will be updated with the expected values.

See the table below for all the supported data types and their corresponding function signatures.

parameter": key The name of the parameter

parameter": value Allocated array to get the value of the parameter

parameter": height The height of the 2-D vector parameter obtained by calling `GxfParameterGet2D"DataType"VectorInfo(...)`

parameter": width The width of the 2-D vector parameter obtained by calling `GxfParameterGet2D"DataType"VectorInfo(...)`

Table 28.4: Supported Data Types to Get the Value of 2D Vector Parameters

Function Name	data_type
GxfParameterGet2DFloat64Vector(...)	double
GxfParameterGet2DInt64Vector(...)	int64_t
GxfParameterGet2DUInt64Vector(...)	uint64_t
GxfParameterGet2DInt32Vector(...)	int32_t

28.6.8 Information Queries

Get Meta Data about the GXF Runtime

`gxf_result_t GxfRuntimeInfo(gxf_context_t context, gxf_runtime_info* info);`

parameter: context A valid GXF context.

parameter: info pointer to `gxf_runtime_info` object to get the meta data.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Get description and list of components in loaded Extension

```
gxf_result_t GxfExtensionInfo(gxf_context_t context, gxf_tid_t tid, gxf_extension_info_t* info);
```

parameter: context A valid GXF context.

parameter: tid The unique identifier of the extension.

parameter: info pointer to gxf_extension_info_t object to get the meta data.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get description and list of parameters of Component

```
gxf_result_t GxfComponentInfo(gxf_context_t context, gxf_tid_t tid, gxf_component_info_t* info);
```

Note: Parameters are only available after at least one instance is created for the Component.

parameter: context A valid GXF context.

parameter: tid The unique identifier of the component.

parameter: info pointer to gxf_component_info_t object to get the meta data.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

Get parameter type description

Gets a string describing the parameter type

```
const char* GxfParameterTypeStr(gxf_parameter_type_t param_type);
```

parameter: param_type Type of parameter to get info about.

returns: C-style string description of the parameter type.

Get flag type description

Gets a string describing the flag type

```
const char* GxfParameterFlagTypeStr(gxf_parameter_flags_t flag_type);
```

parameter: flag_type Type of flag to get info about.

returns: C-style string description of the flag type.

Get parameter description

Gets description of specific parameter. Fails if the component is not instantiated yet.

```
gxf_result_t GxfGetParameterInfo(gxf_context_t context, gxf_tid_t cid, const char* key, gxf_parameter_info_t* info);
```

parameter: context A valid GXF context.

parameter: cid The unique identifier of the component.

parameter: key The name of the parameter.

parameter: `info` Pointer to a `gxf_parameter_info_t` object to get the value.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

Redirect logs to a file

Redirect console logs to the provided file.

```
gxf_result_t GxfGetParameterInfo(gxf_context_t context, FILE* fp);
```

parameter: `context` A valid GXF context.

parameter: `fp` File path for the redirected logs.

returns: `GXF_SUCCESS` if the operation was successful, or otherwise one of the GXF error codes.

28.6.9 Miscellaneous

Get string description of error

```
const char* GxfResultStr(gxf_result_t result);
```

Gets a string describing an GXF error code.

The caller does not get ownership of the return C string and must not delete it.

parameter: `result` A GXF error code

returns: A pointer to a C string with the error code description.

28.7 CudaExtension

Extension for CUDA operations.

- UUID: d63a98fa-7882-11eb-a917-b38f664f399c
- Version: 2.0.0
- Author: NVIDIA
- License: LICENSE

28.7.1 Components

`nvidia::gxf::CudaStream`

Holds and provides access to native `cudaStream_t`.

`nvidia::gxf::CudaStream` handle must be allocated by `nvidia::gxf::CudaStreamPool`. Its lifecycle is valid until explicitly recycled through `nvidia::gxf::CudaStreamPool.releaseStream()` or implicitly until `nvidia::gxf::CudaStreamPool` is deactivated.

You may call `stream()` to get the native `cudaStream_t` handle, and to submit GPU operations. After the submission, GPU takes over the input tensors/buffers and keeps them in use. To prevent host carelessly releasing these in-use buffers, CUDA Codelet needs to call `record(event, input_entity, sync_cb)` to extend `input_entity`'s lifecycle until GPU completely consumes it. Alternatively, you may call `record(event, event_destroy_cb)` for native `cudaEvent_t` operations and free in-use resource via `event_destroy_cb`.

It is required to have a `nvidia::gxf::CudaStreamSync` in the graph pipeline after all the CUDA operations. See more details in `nvidia::gxf::CudaStreamSync`

- Component ID: 5683d692-7884-11eb-9338-c3be62d576be
- Defined in: `gxf/cuda/cuda_stream.hpp`

`nvidia::gxf::CudaStreamId`

Holds CUDA stream Id to deduce `nvidia::gxf::CudaStream` handle.

`stream_cid` should be `nvidia::gxf::CudaStream` component id.

- Component ID: 7982aeac-37f1-41be-ade8-6f00b4b5d47c
- Defined in: `gxf/cuda/cuda_stream_id.hpp`

`nvidia::gxf::CudaEvent`

Holds and provides access to native `cudaEvent_t` handle.

When a `nvidia::gxf::CudaEvent` is created, you'll need to initialize a native `cudaEvent_t` through `init(flags, dev_id)`, or set third party event through `initWithEvent(event, dev_id, free_fnc)`. The event keeps valid until `deinit` is called explicitly otherwise gets recycled in destructor.

- Component ID: f5388d5c-a709-47e7-86c4-171779bc64f3
- Defined in: `gxf/cuda/cuda_event.hpp`

`nvidia::gxf::CudaStreamPool`

`CudaStream` allocation.

You must explicitly call `allocateStream()` to get a valid `nvidia::gxf::CudaStream` handle. This component would hold all the its allocated `nvidia::gxf::CudaStream` entities until `releaseStream(stream)` is called explicitly or the `CudaStreamPool` component is deactivated.

- Component ID: 6733bf8b-ba5e-4fae-b596-af2d1269d0e7
- Base Type: `nvidia::gxf::Allocator`

Parameters

`dev_id`

GPU device id.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_INT32`
- Default Value: 0

stream_flags

Flag values to create CUDA streams.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT32
- Default Value: 0

stream_priority

Priority values to create CUDA streams.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT32
- Default Value: 0

reserved_size

User-specified file name without extension.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT32
- Default Value: 1

max_size

Maximum Stream Size.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT32
- Default Value: 0, no limitation.

nvidia::gxf::CudaStreamSync

Synchronize all CUDA streams which are carried by message entities.

This codelet is required to get connected in the graph pipeline after all CUDA ops codelets. When a message entity is received, it would find all of the `nvidia::gxf::CudaStreamId` in that message, and extract out each `nvidia::gxf::CudaStream`. With each `CudaStream` handle, it synchronizes all previous `nvidia::gxf::CudaStream.record()` events, along with all submitted GPU operations before this point.

Note: `CudaStreamSync` must be set in the graph when `nvidia::gxf::CudaStream.record()` is used, otherwise it may cause memory leak.

- Component ID: 0d1d8142-6648-485d-97d5-277eed00129c

- Base Type: `nvidia::gxf::Codelet`

Parameters

rx

Receiver to receive all messages carrying `nvidia::gxf::CudaStreamId`.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_HANDLE`
- Handle Type: `nvidia::gxf::Receiver`

tx

Transmitter to send messages to downstream.

- Flags: `GXF_PARAMETER_FLAGS_OPTIONAL`
- Type: `GXF_PARAMETER_TYPE_HANDLE`
- Handle Type: `nvidia::gxf::Transmitter`

28.8 MultimediaExtension

Extension for multimedia related data types, interfaces and components in GXF Core.

- UUID: `6f2d1afc-1057-481a-9da6-a5f61fed178e`
- Version: `2.0.0`
- Author: `NVIDIA`
- License: `LICENSE`

28.8.1 Components

`nvidia::gxf::AudioBuffer`

`AudioBuffer` is similar to `Tensor` component in the standard extension and holds memory and metadata corresponding to an audio buffer.

- Component ID: `a914cac6-5f19-449d-9ade-8c5cdcebe7c3`

`AudioBufferInfo` structure captures the following metadata:

Field	Description
channels	Number of channels in an audio frame
samples	Number of samples in an audio frame
sampling_rate	sampling rate in Hz
bytes_per_sample	Number of bytes required per sample
audio_format	AudioFormat of an audio frame
audio_layout	AudioLayout of an audio frame

Supported AudioFormat types:

AudioFormat	Description
GXF_AUDIO_FORMAT_S16LE	16-bit signed PCM audio
GXF_AUDIO_FORMAT_F32LE	32-bit floating-point audio

Supported AudioLayout types:

AudioLayout	Description
GXF_AUDIO_LAYOUT_INTERLEAVED	Data from all the channels to be interleaved - LRLRLR
GXF_AUDIO_LAYOUT_NON_INTERLEAVED	Data from all the channels not to be interleaved - LLLRRR

nvidia::gxf::VideoBuffer

VideoBuffer is similar to Tensor component in the standard extension and holds memory and metadata corresponding to a video buffer.

- Component ID: 16ad58c8-b463-422c-b097-61a9acc5050e

VideoBufferInfo structure captures the following metadata:

Field	Description
width	width of a video frame
height	height of a video frame
color_format	VideoFormat of a video frame
color_planes	ColorPlane(s) associated with the VideoFormat
surface_layout	SurfaceLayout of the video frame

Supported VideoFormat types:

VideoFormat	Description
GXF_VIDEO_FORMAT_YUV420	BT.601 multi planar 4:2:0 YUV
GXF_VIDEO_FORMAT_YUV420_ER	BT.601 multi planar 4:2:0 YUV ER
GXF_VIDEO_FORMAT_YUV420_709	BT.709 multi planar 4:2:0 YUV
GXF_VIDEO_FORMAT_YUV420_709_ER	BT.709 multi planar 4:2:0 YUV ER
GXF_VIDEO_FORMAT_NV12	BT.601 multi planar 4:2:0 YUV with interleaved UV
GXF_VIDEO_FORMAT_NV12_ER	BT.601 multi planar 4:2:0 YUV ER with interleaved UV
GXF_VIDEO_FORMAT_NV12_709	BT.709 multi planar 4:2:0 YUV with interleaved UV
GXF_VIDEO_FORMAT_NV12_709_ER	BT.709 multi planar 4:2:0 YUV ER with interleaved UV
GXF_VIDEO_FORMAT_RGBA	RGBA-8-8-8-8 single plane
GXF_VIDEO_FORMAT_BGRA	BGRA-8-8-8-8 single plane
GXF_VIDEO_FORMAT_ARGB	ARGB-8-8-8-8 single plane
GXF_VIDEO_FORMAT_ABGR	ABGR-8-8-8-8 single plane
GXF_VIDEO_FORMAT_RGBX	RGBX-8-8-8-8 single plane
GXF_VIDEO_FORMAT_BGRX	BGRX-8-8-8-8 single plane
GXF_VIDEO_FORMAT_XRGB	XRGB-8-8-8-8 single plane
GXF_VIDEO_FORMAT_XBGR	XBGR-8-8-8-8 single plane
GXF_VIDEO_FORMAT_RGB	RGB-8-8-8 single plane
GXF_VIDEO_FORMAT_BGR	BGR-8-8-8 single plane
GXF_VIDEO_FORMAT_R8_G8_B8	RGB - unsigned 8 bit multiplanar
GXF_VIDEO_FORMAT_B8_G8_R8	BGR - unsigned 8 bit multiplanar
GXF_VIDEO_FORMAT_GRAY	8 bit GRAY scale single plane

Supported SurfaceLayout types:

SurfaceLayout	Description
GXF_SURFACE_LAYOUT_PITCH_LINEAR	pitch linear surface memory
GXF_SURFACE_LAYOUT_BLOCK_LINEAR	block linear surface memory

28.9 NetworkExtension

Extension for communications external to a computation graph.

- UUID: f50665e5-ade2-f71b-de2a-2380614b1725
- Version: 1.0.0
- Author: NVIDIA
- License: LICENSE

28.9.1 Interfaces

28.9.2 Components

nvidia::gxf::TcpClient

Codelet that functions as a client in a TCP connection.

- Component ID: 9d5955c7-8fda-22c7-f18f-ea5e2d195be9
- Base Type: nvidia::gxf::Codelet

Parameters

receivers

List of receivers to receive entities from.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_CUSTOM`
- Custom Type: `std::vector<nvidia::gxf::Handle<nvidia::gxf::Receiver>>`

transmitters

List of transmitters to publish entities to.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_CUSTOM`
- Custom Type: `std::vector<nvidia::gxf::Handle<nvidia::gxf::Transmitter>>`

serializers

List of component serializers to serialize and de-serialize entities.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_CUSTOM`
- Custom Type: `std::vector<nvidia::gxf::Handle<nvidia::gxf::ComponentSerializer>>`

address

Address of TCP server.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_STRING`

port

Port of TCP server.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_INT32`

timeout_ms

Time in milliseconds to wait before retrying connection to TCP server.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

maximum_attempts

Maximum number of attempts for I/O operations before failing.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

nvidia::gxf::TcpServer

Codelet that functions as a server in a TCP connection.

- Component ID: a3e0e42d-e32e-73ab-ef83-fbb311310759
- Base Type: nvidia::gxf::Codelet

Parameters**receivers**

List of receivers to receive entities from.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_CUSTOM
- Custom Type: std::vector<nvidia::gxf::Handle<nvidia::gxf::Receiver>>

transmitters

List of transmitters to publish entities to.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_CUSTOM
- Custom Type: std::vector<nvidia::gxf::Handle<nvidia::gxf::Transmitter>>

serializers

List of component serializers to serialize and de-serialize entities.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_CUSTOM`
- Custom Type: `std::vector<nvidia::gxf::Handle<nvidia::gxf::ComponentSerializer>>`

address

Address of TCP server.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_STRING`

port

Port of TCP server.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_INT32`

timeout_ms

Time in milliseconds to wait before retrying connection to TCP client.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_UINT64`

maximum_attempts

Maximum number of attempts for I/O operations before failing.

- Flags: `GXF_PARAMETER_FLAGS_NONE`
- Type: `GXF_PARAMETER_TYPE_UINT64`

28.10 SerializationExtension

Extension for serializing messages.

- UUID: bc573c2f-89b3-d4b0-8061-2da8b11fe79a
- Version: 2.0.0
- Author: NVIDIA
- License: LICENSE

28.10.1 Interfaces

nvidia::gxf::ComponentSerializer

Interface for serializing components.

- Component ID: 8c76a828-2177-1484-f841-d39c3fa47613
- Base Type: nvidia::gxf::Component
- Defined in: gxf/serialization/component_serializer.hpp

28.10.2 Components

nvidia::gxf::EntityRecorder

Serializes incoming messages and writes them to a file.

- Component ID: 9d5955c7-8fda-22c7-f18f-ea5e2d195be9
- Base Type: nvidia::gxf::Codelet

Parameters

receiver

Receiver channel to log.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

serializers

List of component serializers to serialize entities.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_CUSTOM
- Custom Type: std::vector<nvidia::gxf::Handle<nvidia::gxf::ComponentSerializer>>

directory

Directory path for storing files.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_STRING

basename

User specified file name without extension.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_STRING

flush_on_tick

Flushes output buffer on every tick when true.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

nvidia::gxf::EntityReplayer

De-serializes and publishes messages from a file.

- Component ID: fe827c12-d360-c63c-8094-32b9244d83b6
- Base Type: nvidia::gxf::Codelet

Parameters

transmitter

Transmitter channel for replaying entities.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

serializers

List of component serializers to serialize entities.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_CUSTOM
- Custom Type: `std::vector<nvidia::gxf::Handle<nvidia::gxf::ComponentSerializer>>`

directory

Directory path for storing files.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_STRING

batch_size

Number of entities to read and publish for one tick.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

ignore_corrupted_entities

If an entity could not be de-serialized, it is ignored by default; otherwise a failure is generated.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

nvidia::gxf::StdComponentSerializer

Serializer for Timestamp and Tensor components.

- Component ID: `c0e6b36c-39ac-50ac-ce8d-702e18d8bff7`
- Base Type: `nvidia::gxf::ComponentSerializer`

Parameters

allocator

Memory allocator for tensor components.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: `nvidia::gxf::Allocator`

28.11 StandardExtension

Most commonly used interfaces and components in Gxf Core.

- UUID: 8ec2d5d6-b5df-48bf-8dee-0252606fdd7e
- Version: 2.1.0
- Author: NVIDIA
- License: LICENSE

28.11.1 Interfaces

nvidia::gxf::Codelet

Interface for a component which can be executed to run custom code.

- Component ID: 5c6166fa-6eed-41e7-bbf0-bd48cd6e1014
- Base Type: `nvidia::gxf::Component`
- Defined in: `gxf/std/codelet.hpp`

nvidia::gxf::Clock

Interface for clock components which provide time.

- Component ID: 779e61c2-ae70-441d-a26c-8ca64b39f8e7
- Base Type: `nvidia::gxf::Component`
- Defined in: `gxf/std/clock.hpp`

nvidia::gxf::System

Component interface for systems which are run as part of the application run cycle.

- Component ID: d1febca1-80df-454e-a3f2-715f2b3c6e69
- Base Type: `nvidia::gxf::Component`

nvidia::gxf::Queue

Interface for storing entities in a queue.

- Component ID: 792151bf-3138-4603-a912-5ca91828dea8
- Base Type: nvidia::gxf::Component
- Defined in: gxf/std/queue.hpp

nvidia::gxf::Router

Interface for classes which are routing messages in and out of entities.

- Component ID: 8b317aad-f55c-4c07-8520-8f66db92a19e
- Defined in: gxf/std/router.hpp

nvidia::gxf::Transmitter

Interface for publishing entities.

- Component ID: c30cc60f-0db2-409d-92b6-b2db92e02cce
- Base Type: nvidia::gxf::Queue
- Defined in: gxf/std/transmitter.hpp

nvidia::gxf::Receiver

Interface for receiving entities.

- Component ID: a47d2f62-245f-40fc-90b7-5dc78ff2437e
- Base Type: nvidia::gxf::Queue
- Defined in: gxf/std/receiver.hpp

nvidia::gxf::Scheduler

A simple poll-based single-threaded scheduler which executes codelets.

- Component ID: f0103b75-d2e1-4d70-9b13-3fe5b40209be
- Base Type: nvidia::gxf::System
- Defined in: nvidia/gxf/system.hpp

nvidia::gxf::SchedulingTerm

Interface for terms used by a scheduler to determine if codelets in an entity are ready to step.

- Component ID: 184d8e4e-086c-475a-903a-69d723f95d19
- Base Type: nvidia::gxf::Component
- Defined in: gxf/std/scheduling_term.hpp

nvidia::gxf::Allocator

Provides allocation and deallocation of memory.

- Component ID: 3cdd82d0-2326-4867-8de2-d565dbe28e03
- Base Type: nvidia::gxf::Component
- Defined in: nvidia/gxf/allocator.hpp

nvidia::gxf::Monitor

Monitors entities during execution.

- Component ID: 9ccf9421-b35b-8c79-e1f0-97dc23bd38ea
- Base Type: nvidia::gxf::Component
- Defined in: nvidia/gxf/monitor.hpp

28.11.2 Components

nvidia::gxf::RealtimeClock

A real-time clock which runs based off a system steady clock.

- Component ID: 7b170b7b-cf1a-4f3f-997c-bfea25342381
- Base Type: nvidia::gxf::Clock

Parameters

initial_time_offset

The initial time offset used until time scale is changed manually.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_FLOAT64

initial_time_scale

The initial time scale used until time scale is changed manually.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_FLOAT64

use_time_since_epoch

If true, clock time is time since epoch + initial_time_offset at initialize(). Otherwise clock time is initial_time_offset at initialize().

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

nvidia::gxf::ManualClock

A manual clock which is instrumented manually.

- Component ID: 52fa1f97-eba8-472a-a8ca-4cff1a2c440f
- Base Type: nvidia::gxf::Clock

Parameters

initial_timestamp

The initial timestamp on the clock (in nanoseconds).

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

nvidia::gxf::SystemGroup

A group of systems.

- Component ID: 3d23d470-0aed-41c6-ac92-685c1b5469a0
- Base Type: nvidia::gxf::System

nvidia::gxf::MessageRouter

A router which sends transmitted messages to receivers.

- Component ID: 84fd5d56-fda6-4937-0b3c-c283252553d8
- Base Type: nvidia::gxf::Router

nvidia::gxf::RouterGroup

A group of routers.

- Component ID: ca64ee14-2280-4099-9f10-d4b501e09117
- Base Type: nvidia::gxf::Router

nvidia::gxf::DoubleBufferTransmitter

A transmitter which uses a double-buffered queue where messages are pushed to a backstage after they are published.

- Component ID: 0c3c0ec7-77f1-4389-aef1-6bae85bddc13
- Base Type: nvidia::gxf::Transmitter

Parameters

capacity

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64
- Default: 1

policy

0: pop, 1: reject, 2: fault.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64
- Default: 2

nvidia::gxf::DoubleBufferReceiver

A receiver which uses a double-buffered queue where new messages are first pushed to a backstage.

- Component ID: ee45883d-bf84-4f99-8419-7c5e9deac6a5
- Base Type: nvidia::gxf::Receiver

Parameters

capacity

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64
- Default: 1

policy

0: pop, 1: reject, 2: fault

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64
- Default: 2

nvidia::gxf::Connection

A component which establishes a connection between two other components.

- Component ID: cc71afae-5ede-47e9-b267-60a5c750a89a
- Base Type: nvidia::gxf::Component

Parameters

source

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

target

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::PeriodicSchedulingTerm

A component which specifies that an entity shall be executed periodically.

- Component ID: d392c98a-9b08-49b4-a422-d5fe6cd72e3e
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**recess_period**

The recess period indicates the minimum amount of time which has to pass before the entity is permitted to execute again. The period is specified as a string containing of a number and an (optional) unit. If no unit is given the value is assumed to be in nanoseconds. Supported units are: Hz, s, ms. Example: 10ms, 10000000, 0.2s, 50Hz.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_STRING

nvidia::gxf::CountSchedulingTerm

A component which specifies that an entity shall be executed exactly a given number of times.

- Component ID: f89da2e4-fddf-4aa2-9a80-1119ba3fde05
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**count**

The total number of time this term will permit execution.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

nvidia::gxf::TargetTimeSchedulingTerm

A component where the next execution time of the entity needs to be specified after every tick.

- Component ID: e4aaf5c3-2b10-4c9a-c463-ebf6084149bf
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**clock**

The clock used to define target time.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

nvidia::gxf::DownstreamReceptiveSchedulingTerm

A component which specifies that an entity shall be executed if receivers for a certain transmitter can accept new messages.

- Component ID: 9de75119-8d0f-4819-9a71-2aeaefd23f71
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**min_size**

The term permits execution if the receiver connected to the transmitter has at least the specified number of free slots in its back buffer.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

transmitter

The term permits execution if this transmitter can publish a message, i.e. if the receiver which is connected to this transmitter can receive messages.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

nvidia::gxf::MessageAvailableSchedulingTerm

A scheduling term which specifies that an entity can be executed when the total number of messages over a set of input channels is at least a given number of messages.

- Component ID: fe799e65-f78b-48eb-beb6-e73083a12d5b
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**front_stage_max_size**

If set the scheduling term will only allow execution if the number of messages in the front stage does not exceed this count. It can for example be used in combination with codelets which do not clear the front stage in every tick.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_UINT64

min_size

The scheduling term permits execution if the given receiver has at least the given number of messages available.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

receiver

The scheduling term permits execution if this channel has at least a given number of messages available.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::MultiMessageAvailableSchedulingTerm

A component which specifies that an entity shall be executed when a queue has at least a certain number of elements.

- Component ID: f15dbeaa-afd6-47a6-9ffc-7afd7e1b4c52
- Base Type: nvidia::gxf::SchedulingTerm

Parameters**min_size**

The scheduling term permits execution if all given receivers together have at least the given number of messages available.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

receivers

The scheduling term permits execution if the given channels have at least a given number of messages available.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::ExpiringMessageAvailableSchedulingTerm

A component which tries to wait for specified number of messages in queue for at most specified time.

- Component ID: eb22280c-76ff-11eb-b341-cf6b417c95c9
- Base Type: nvidia::gxf::SchedulingTerm

Parameters

clock

Clock to get time from.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

max_batch_size

The maximum number of messages to be batched together.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

max_delay_ns

The maximum delay from first message to wait before submitting workload anyway.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

receiver

Receiver to watch on.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::BooleanSchedulingTerm

A component which acts as a boolean AND term that can be used to control the execution of the entity.

- Component ID: e07a0dc4-3908-4df8-8134-7ce38e60fbef
- Base Type: nvidia::gxf::SchedulingTerm

nvidia::gxf::AsynchronousSchedulingTerm

A component which is used to inform of that an entity is dependent upon an async event for its execution.

- Component ID: 56be1662-ff63-4179-9200-3fcd8dc38673
- Base Type: nvidia::gxf::SchedulingTerm

nvidia::gxf::GreedyScheduler

A simple poll-based single-threaded scheduler which executes codelets.

- Component ID: 869d30ca-a443-4619-b988-7a52e657f39b
- Base Type: nvidia::gxf::Scheduler

Parameters**clock**

The clock used by the scheduler to define flow of time. Typical choices are a `RealtimeClock` or a `ManualClock`.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

max_duration_ms

The maximum duration for which the scheduler will execute (in ms). If not specified the scheduler will run until all work is done. If periodic terms are present this means the application will run indefinitely.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_INT64

realtime

This parameter is deprecated. Assign a clock directly.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL

- Type: GXF_PARAMETER_TYPE_BOOL

stop_on_deadlock

If enabled the scheduler will stop when all entities are in a waiting state, but no periodic entity exists to break the dead end. Should be disabled when scheduling conditions can be changed by external actors, for example by clearing queues manually.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

nvidia::gxf::MultiThreadScheduler

A multi thread scheduler that executes codelets for maximum throughput.

- Component ID: de5e0646-7fa5-11eb-a5c4-330ebfa81bbf
- Base Type: nvidia::gxf::Scheduler

Parameters

check_recession_perios_ms

The maximum duration for which the scheduler would wait (in ms) when an entity is not ready to run yet.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

clock

The clock used by the scheduler to define flow of time. Typical choices are a `RealtimeClock` or a `ManualClock`.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

max_duration_ms

The maximum duration for which the scheduler will execute (in ms). If not specified the scheduler will run until all work is done. If periodic terms are present this means the application will run indefinitely.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_INT64

stop_on_deadlock

If enabled the scheduler will stop when all entities are in a waiting state, but no periodic entity exists to break the dead end. Should be disabled when scheduling conditions can be changed by external actors, for example by clearing queues manually.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

worker_thread_number

Number of threads.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64
- Default: 1

nvidia::gxf::BlockMemoryPool

A memory pools which provides a maximum number of equally sized blocks of memory.

- Component ID: 92b627a3-5dd3-4c3c-976c-4700e8a3b96a
- Base Type: nvidia::gxf::Allocator

Parameters

block_size

The size of one block of memory in byte. Allocation requests can only be fulfilled if they fit into one block. If less memory is requested still a full block is issued.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

do_not_use_cuda_malloc_host

If enabled operator new will be used to allocate host memory instead of cudaMallocHost.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL
- Default: True

num_blocks

The total number of blocks which are allocated by the pool. If more blocks are requested allocation requests will fail.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

storage_type

The memory storage type used by this allocator. Can be kHost (0) or kDevice (1) or kSystem (2).

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT32
- Default: 0

nvidia::gxf::UnboundedAllocator

Allocator that uses dynamic memory allocation without an upper bound.

- Component ID: c3951b16-a01c-539f-d87e-1dc18d911ea0
- Base Type: nvidia::gxf::Allocator

Parameters**do_not_use_cuda_malloc_host**

If enabled operator new will be used to allocate host memory instead of cudaMallocHost.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL
- Default: True

nvidia::gxf::Tensor

A component which holds a single tensor.

- Component ID: 377501d6-9abf-447c-a617-0114d4f33ab8
- Defined in: gxf/std/tensor.hpp

nvidia::gxf::Timestamp

Holds message publishing and acquisition related timing information.

- Component ID: d1095b10-5c90-4bbc-bc89-601134cb4e03
- Defined in: gxf/std/timestamp.hpp

nvidia::gxf::Metric

Collects, aggregates, and evaluates metric data.

- Component ID: f7cef803-5beb-46f1-186a-05d3919842ac
- Base Type: nvidia::gxf::Component

Parameters

aggregation_policy

Aggregation policy used to aggregate individual metric samples. Choices: {mean, min, max}.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_STRING

lower_threshold

Lower threshold of the metric's expected range.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_FLOAT64

upper_threshold

Upper threshold of the metric's expected range.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_FLOAT64

nvidia::gxf::JobStatistics

Collects runtime statistics.

- Component ID: 2093b91a-7c82-11eb-a92b-3f1304ecc959
- Base Type: nvidia::gxf::Component

Parameters

clock

The clock component instance to retrieve time from.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

codelet_statistics

If set to true, JobStatistics component will collect performance statistics related to codelets.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_BOOL

json_file_path

If provided, all the collected performance statistics data will be dumped into a json file.

- Flags: GXF_PARAMETER_FLAGS_OPTIONAL
- Type: GXF_PARAMETER_TYPE_STRING

nvidia::gxf::Broadcast

Messages arrived on the input channel are distributed to all transmitters.

- Component ID: 3daadb31-0bca-47e5-9924-342b9984a014
- Base Type: nvidia::gxf::Codelet

Parameters

mode

The broadcast mode. Can be Broadcast or RoundRobin.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_CUSTOM

source

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::Gather

All messages arriving on any input channel are published on the single output channel.

- Component ID: 85f64c84-8236-4035-9b9a-3843a6a2026f
- Base Type: nvidia::gxf::Codelet

Parameters

sink

The output channel for gathered messages.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

tick_source_limit

Maximum number of messages to take from each source in one tick. 0 means no limit.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_INT64

nvidia::gxf::TensorCopier

Copies tensor either from host to device or from device to host.

- Component ID: c07680f4-75b3-189b-8886-4b5e448e7bb6
- Base Type: nvidia::gxf::Codelet

Parameters**allocator**

Memory allocator for tensor data

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Allocator

mode

Configuration to select what tensors to copy:

1. kCopyToDevice (0) - copies to device memory, ignores device allocation
 2. kCopyToHost (1) - copies to pinned host memory, ignores host allocation
 3. kCopyToSystem (2) - copies to system memory, ignores system allocation.
- Flags: GXF_PARAMETER_FLAGS_NONE
 - Type: GXF_PARAMETER_TYPE_INT32

receiver

Receiver for incoming entities.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

transmitter

Transmitter for outgoing entities.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

nvidia::gxf::TimedThrottler

Publishes the received entity respecting the timestamp within the entity.

- Component ID: ccf7729c-f62c-4250-5cf7-f4f3ec80454b
- Base Type: nvidia::gxf::Codelet

Parameters

execution_clock

Clock on which the codelet is executed by the scheduler.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

receiver

Channel to receive messages that need to be synchronized.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

scheduling_term

Scheduling term for executing the codelet.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::TargetTimeSchedulingTerm

throttling_clock

Clock which the received entity timestamps are based on.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Clock

transmitter

Transmitter channel publishing messages at appropriate timesteps.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

nvidia::gxf::Vault

Safely stores received entities for further processing.

- Component ID: 1108cb8d-85e4-4303-ba02-d27406ee9e65
- Base Type: nvidia::gxf::Codelet

Parameters**drop_waiting**

If too many messages are waiting the oldest ones are dropped.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_BOOL

max_waiting_count

The maximum number of waiting messages. If exceeded the codelet will stop pulling messages out of the input queue.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_UINT64

source

Receiver from which messages are taken and transferred to the vault.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

nvidia::gxf::Subgraph

Helper component to import a subgraph.

- Component ID: 576eedd7-7c3f-4d2f-8c38-8baa79a3d231
- Base Type: nvidia::gxf::Component

Parameters

location

Yaml source of the subgraph.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_STRING

nvidia::gxf::EndOfStream

A component which represents end-of-stream notification.

- Component ID: 8c42f7bf-7041-4626-9792-9eb20ce33cce
- Defined in: gxf/std/eos.hpp

nvidia::gxf::Synchronization

Component to synchronize messages from multiple receivers based on the `acq_time`.

- Component ID: f1cb80d6-e5ec-4dba-9f9e-b06b0def4443
- Base Type: nvidia::gxf::Codelet

Parameters

inputs

All the inputs for synchronization. Number of inputs must match that of the outputs.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Receiver

outputs

All the outputs for synchronization. Number of outputs must match that of the inputs.

- Flags: GXF_PARAMETER_FLAGS_NONE
- Type: GXF_PARAMETER_TYPE_HANDLE
- Handle Type: nvidia::gxf::Transmitter

signed char

- Component ID: 83905c6a-ca34-4f40-b474-cf2cde8274de

unsigned char

- Component ID: d4299e15-0006-d0bf-8cbd-9b743575e155

short int

- Component ID: 9e1dde79-3550-307d-e81a-b864890b3685

short unsigned int

- Component ID: 958cbdef-b505-bcc7-8a43-dc4b23f8cead

int

- Component ID: b557ec7f-49a5-08f7-a35e-086e9d1ea767

unsigned int

- Component ID: d5506b68-5c86-fedb-a2a2-a7bae38ff3ef

long int

- Component ID: c611627b-6393-365f-d234-1f26bfa8d28f

long unsigned int

- Component ID: c4385f5b-6e25-01d9-d7b5-6e7cad704e8

float

- Component ID: a81bf295-421f-49ef-f24a-f59e9ea0d5d6

double

- Component ID: d57cee59-686f-e26d-95be-659c126b02ea

bool

- Component ID: c02f9e93-d01b-1d29-f523-78d2a9195128

DATA FLOW TRACKING

Warning: Data Flow Tracking is currently not supported between multiple fragments in a *distributed application*.

The Holoscan SDK provides the Data Flow Tracking APIs as a mechanism to profile your application and analyze the fine-grained timing properties and data flow between operators in the graph of a fragment.

Currently, data flow tracking is only supported between the root operators and leaf operators of a graph and in simple cycles in a graph (support for tracking data flow between any pair of operators in a graph is planned for the future).

- A *root operator* is an operator without any predecessor nodes
- A *leaf operator* (also known as a *sink operator*) is an operator without any successor nodes.

When data flow tracking is enabled, every message is tracked from the root operators to the leaf operators and in cycles. Then, the maximum (worst-case), average and minimum end-to-end latencies of one or more paths can be retrieved using the Data Flow Tracking APIs.

Tip:

- The end-to-end latency between a root operator and a leaf operator is the time taken between the start of a root operator and the end of a leaf operator. Data Flow Tracking enables the support to track the end-to-end latency of every message being passed between a root operator and a leaf operator.
- The reported end-to-end latency for a cyclic path is the time taken between the start of the first operator of a cycle and the time when a message is again received by the first operator of the cycle.

The API also provides the ability to retrieve the number of messages sent from the root operators.

Tip:

- The Data Flow Tracking feature is also illustrated in the [flow_tracker](#)
 - Look at the C++ and python API documentation for exhaustive definitions
-

29.1 Enabling Data Flow Tracking

Before an application (C++/python) is run with the `run()` method, data flow tracking can be enabled by calling the `track()` method in C++ and using the `Tracker` class in python.

C++

```
auto app = holoscan::make_application<MyPingApp>();
auto& tracker = app->track(); // Enable Data Flow Tracking
// Change tracker and application configurations
...
app->run();
```

Python

```
from holoscan.core import Tracker
...
app = MyPingApp()
with Tracker(app) as tracker:
    # Change tracker and application configurations
    ...
    app.run()
```

29.2 Retrieving Data Flow Tracking Results

After an application has been run, data flow tracking results can be accessed by various functions:

1. `print()` (C++/python)
 - Prints all data flow tracking results including end-to-end latencies and the number of source messages to the standard output.
2. `get_num_paths()` (C++/python)
 - Returns the number of paths between the root operators and the leaf operators.
3. `get_path_strings()` (C++/python)
 - Returns a vector of strings, where each string represents a path between the root operators and the leaf operators. A path is a comma-separated list of operator names.
4. `get_metric()` (C++/python)
 - Returns the value of different metrics based on the arguments.
 - `get_metric(std::string pathstring, holoscan::DataFlowMetric metric)` returns the value of a metric `metric` for a path `pathstring`. The metric can be one of the following:
 - `holoscan::DataFlowMetric::kMaxE2ELatency` (python): the maximum end-to-end latency in the path
 - `holoscan::DataFlowMetric::kAvgE2ELatency` (python): the average end-to-end latency in the path

- `holoscan::DataFlowMetric::kMinE2ELatency` (python): the minimum end-to-end latency in the path
- `holoscan::DataFlowMetric::kMaxMessageID` (python): the message number or ID which resulted in the maximum end-to-end latency
- `holoscan::DataFlowMetric::kMinMessageID` (python): the message number or ID which resulted in the minimum end-to-end latency
- `get_metric(holoscan::DataFlowMetric metric = DataFlowMetric::kNumSrcMessages)` returns a map of source operator and its edge, and the number of messages sent from the source operator to the edge.

In the *above example*, the data flow tracking results can be printed to the standard output like the following:

C++

```
auto app = holoscan::make_application<MyPingApp>();
auto& tracker = app->track(); // Enable Data Flow Tracking
// Change application configurations
...
app->run();
tracker.print();
```

Python

```
from holoscan.core import Tracker
...
app = MyPingApp()
with Tracker(app) as tracker:
    # Change tracker and application configurations
    ...
app.run()
tracker.print()
```

29.3 Customizing Data Flow Tracking

Data flow tracking can be customized using a few, optional configuration parameters. The `track()` method (C++/Tracker class in python) can be configured to skip a few messages at the beginning of an application's execution as a *warm-up* period. It is also possible to discard a few messages at the end of an application's run as a *wrap-up* period. Additionally, outlier end-to-end latencies can be ignored by setting a latency threshold value which is the minimum latency below which the observed latencies are ignored.

Tip: For effective benchmarking, it is common practice to include warm-up and cool-down periods by skipping the initial and final messages.

C++

Listing 29.1: Optional parameters to track()

```
Fragment::track(uint64_t num_start_messages_to_skip = kDefaultNumStartMessagesToSkip,
                uint64_t num_last_messages_to_discard =
↳ kDefaultNumLastMessagesToDiscard,
                int latency_threshold = kDefaultLatencyThreshold);
```

Python

Listing 29.2: Optional parameters to Tracker

```
Tracker(num_start_messages_to_skip=num_start_messages_to_skip,
        num_last_messages_to_discard=num_last_messages_to_discard,
        latency_threshold=latency_threshold)
```

The default values of these parameters of track() are as follows:

- kDefaultNumStartMessagesToSkip: 10
- kDefaultNumLastMessagesToDiscard: 10
- kDefaultLatencyThreshold: 0 (do not filter out any latency values)

These parameters can also be configured using the helper functions: `set_skip_starting_messages`, `set_discard_last_messages` and `set_skip_latencies`.

29.4 Logging

The Data Flow Tracking API provides the ability to log every message's graph-traversal information to a file. This enables developers to analyze the data flow at a granular level. When logging is enabled, every message's received and sent timestamps at every operator between the root and the leaf operators are logged after a message has been processed at the leaf operator.

The logging is enabled by calling the `enable_logging` method in C++ and by providing the `filename` parameter to Tracker in python.

C++

```
auto app = holoscan::make_application<MyPingApp>();
auto& tracker = app->track(); // Enable Data Flow Tracking
tracker.enable_logging("logging_file_name.log");
...
app->run();
```

Python

```
from holoscan.core import Tracker
...
app = MyPingApp()
with Tracker(app, filename="logger.log") as tracker:
    ...
    app.run()
```

The logger file logs the paths of the messages after a leaf operator has finished its `compute` method. Every path in the logfile includes an array of tuples of the form:

“(root operator name, message receive timestamp, message publish timestamp) -> ... -> (leaf operator name, message receive timestamp, message publish timestamp)”.

This log file can further be analyzed to understand latency distributions, bottlenecks, data flow and other characteristics of an application.

VIDEO PIPELINE LATENCY TOOL

The Holoscan Developer Kits excel as a high-performance computing platform by combining high-bandwidth video I/O components and the compute capabilities of an NVIDIA GPU to meet the needs of the most demanding video processing and inference applications.

For many video processing applications located at the edge—especially those designed to augment medical instruments and aid live medical procedures—minimizing the latency added between image capture and display, often referred to as the end-to-end latency, is of the utmost importance.

While it is generally easy to measure the individual processing time of an isolated compute or inference algorithm by simply measuring the time that it takes for a single frame (or a sequence of frames) to be processed, it is not always so easy to measure the complete end-to-end latency when the video capture and display is incorporated as this usually involves external capture hardware (e.g. cameras and other sensors) and displays.

In order to establish a baseline measurement of the minimal end-to-end latency that can be achieved with the Holoscan Developer Kits and various video I/O hardware and software components, the Holoscan SDK includes a sample latency measurement tool.

30.1 Requirements

30.1.1 Hardware

The latency measurement tool requires the use of a Holoscan Developer Kit in dGPU mode, and operates by having an output component generate a sequence of known video frames that are then transferred back to an input component using a physical loopback cable.

Testing the latency of any of the HDMI modes that output from the GPU requires a DisplayPort to HDMI adapter or cable (see *Example Configurations*, below). Note that this cable must support the mode that is being tested — for example, the UHD mode will only be available if the cable is advertised to support “4K Ultra HD (3840 x 2160) at 60 Hz”.

Testing the latency of an optional AJA Video Systems device requires a supported AJA SDI or HDMI capture device (see *AJA Video Systems* for the list of supported devices), along with the HDMI or SDI cable that is required for the configuration that is being tested (see *Example Configurations*, below).

30.1.2 Software

The following additional software components are required and are installed either by the Holoscan SDK installation or in the *Installation* steps below:

- CUDA 11.1 or newer (<https://developer.nvidia.com/cuda-toolkit>)
- CMake 3.10 or newer (<https://cmake.org/>)
- GLFW 3.2 or newer (<https://www.glfw.org/>)
- GStreamer 1.14 or newer (<https://gstreamer.freedesktop.org/>)
- GTK 3.22 or newer (<https://www.gtk.org/>)
- pkg-config 0.29 or newer (<https://www.freedesktop.org/wiki/Software/pkg-config/>)

The following is optional to enable DeepStream support (for RDMA support from the *GStreamer Producer*):

- DeepStream 5.1 or newer (<https://developer.nvidia.com/deepstream-sdk>)

The following is optional to enable AJA Video Systems support:

- AJA NTV2 SDK 16.1 or newer (See *AJA Video Systems* for details on installing the AJA NTV2 SDK and drivers).

30.2 Installation

30.2.1 Downloading the Source

The Video Pipeline Latency Tool can be found in the `loopback-latency` folder of the *Holoscan Performance Tools* GitHub repository, which is cloned with the following:

```
$ git clone https://github.com/nvidia-holoscan/holoscan-perf-tools.git
```

30.2.2 Installing Software Requirements

CUDA is installed automatically during the dGPU setup. The rest of the software requirements are installed with the following:

```
$ sudo apt-get update && sudo apt-get install -y \  
  cmake \  
  libglfw3-dev \  
  libgstreamer1.0-dev \  
  libgstreamer-plugins-base1.0-dev \  
  libgtk-3-dev \  
  pkg-config
```

30.2.3 Building

Start by creating a build folder within the `loopback-latency` directory:

```
$ cd clara-holoscan-perf-tools/loopback-latency
$ mkdir build
$ cd build
```

CMake is then used to build the tool and output the `loopback-latency` binary to the current directory:

```
$ cmake ..
$ make -j
```

Note: If the error `No CMAKE_CUDA_COMPILER could be found` is encountered, make sure that the `nvcc` executable can be found by adding the CUDA runtime location to your `PATH` variable:

```
$ export PATH=$PATH:/usr/local/cuda/bin
```

Enabling DeepStream Support

DeepStream support enables RDMA when using the *GStreamer Producer*. To enable DeepStream support, the `DEEPSTREAM_SDK` path must be appended to the `cmake` command with the location of the DeepStream SDK. For example, when building against DeepStream 5.1, replace the `cmake` command above with the following:

```
$ cmake -DDEEPSTREAM_SDK=/opt/nvidia/deepstream/deepstream-5.1 ..
```

Enabling AJA Support

To enable AJA support, the `NTV2_SDK` path must be appended to the `cmake` command with the location of the NTV2 SDK in which both the headers and compiled libraries (i.e. `libajantv2`) exist. For example, if the NTV2 SDK is in `/home/nvidia/ntv2`, replace the `cmake` command above with the following:

```
$ cmake -DNTV2_SDK=/home/nvidia/ntv2 ..
```

30.3 Example Configurations

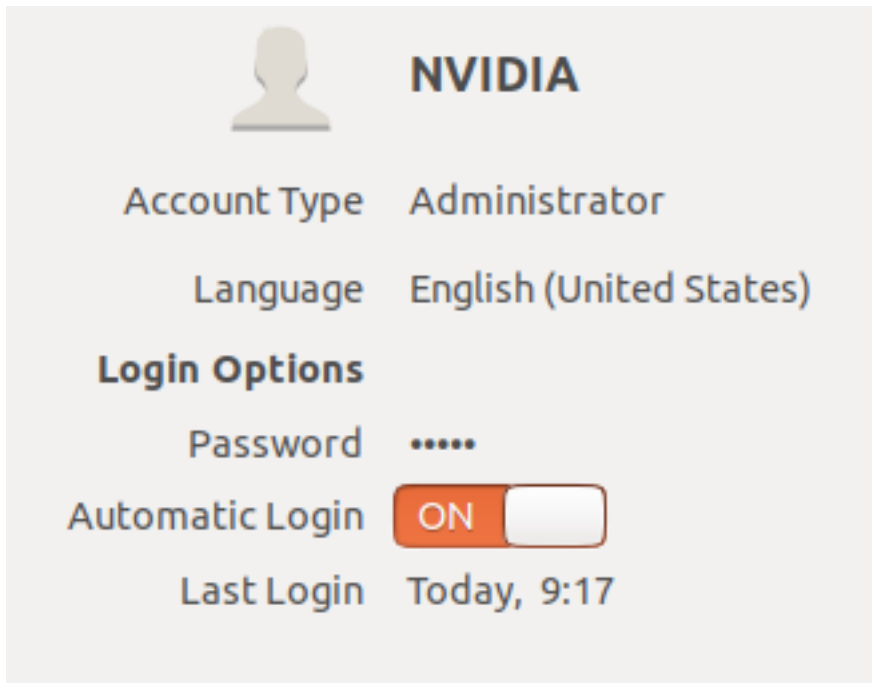
Note: When testing a configuration that outputs from the GPU, the tool currently only supports a display-less environment in which the loopback cable is the only cable attached to the GPU. Because of this, any tests that output from the GPU must be performed using a remote connection such as SSH from another machine. When this is the case, make sure that the `DISPLAY` environment variable is set to the ID of the X11 display you are using (e.g. in `~/.bashrc`):

```
export DISPLAY=:0
```

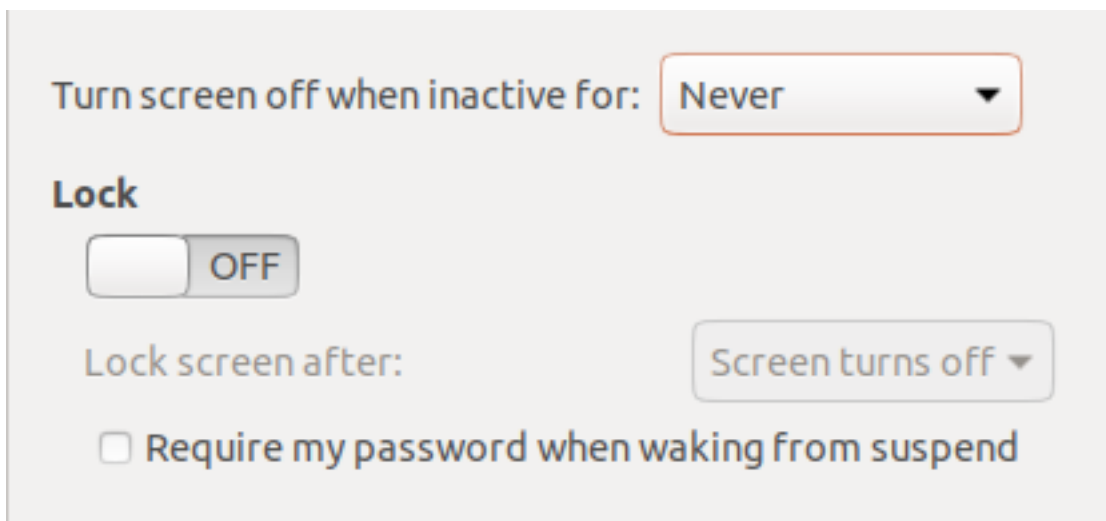
It is also required that the system is logged into the desktop and that the system does not sleep or lock when the latency tool is being used. This can be done by temporarily attaching a display to the system to do the following:

1. Open the **Ubuntu System Settings**

2. Open **User Accounts**, click **Unlock** at the top right, and enable **Automatic Login**:



3. Return to **All Settings** (top left), open **Brightness & Lock**, and disable sleep and lock as pictured:



Make sure that the display is detached again after making these changes.

See the [Producers](#) section for more details about GPU-based producers (i.e. [OpenGL](#) and [GStreamer](#)).

30.3.1 GPU To Onboard HDMI Capture Card

In this configuration, a DisplayPort to HDMI cable is connected from the GPU to the onboard HDMI capture card. This configuration supports the *OpenGL* and *GStreamer* producers, and the *V4L2* and *GStreamer* consumers.



Fig. 30.1: DP-to-HDMI Cable Between GPU and Onboard HDMI Capture Card

For example, an *OpenGL producer* to *V4L2 consumer* can be measured using this configuration and the following command:

```
$ ./loopback-latency -p gl -c v4l2
```

30.3.2 GPU to AJA HDMI Capture Card

In this configuration, a DisplayPort to HDMI cable is connected from the GPU to an HDMI input channel on an AJA capture card. This configuration supports the *OpenGL* and *GStreamer* producers, and the *AJA consumer* using an AJA HDMI capture card.



Fig. 30.2: DP-to-HDMI Cable Between GPU and AJA KONA HDMI Capture Card (Channel 1)

For example, an *OpenGL producer* to *AJA consumer* can be measured using this configuration and the following command:

```
$ ./loopback-latency -p gl -c aja -c.device 0 -c.channel 1
```

30.3.3 AJA SDI to AJA SDI

In this configuration, an SDI cable is attached between either two channels on the same device or between two separate devices (pictured is a loopback between two channels of a single device). This configuration must use the *AJA producer* and *AJA consumer*.

For example, the following can be used to measure the pictured configuration using a single device with a loopback between channels 1 and 2. Note that the tool defaults to use channel 1 for the producer and channel 2 for the consumer, so the `channel` parameters can be omitted.

```
$ ./loopback-latency -p aja -c aja
```

If instead there are two AJA devices being connected, the following can be used to measure a configuration in which they are both connected to channel 1:



Fig. 30.3: SDI Cable Between Channel 1 and 2 of a Single AJA Corvid 44 Capture Card

```
$ ./loopback-latency -p aja -p.device 0 -p.channel 1 -c aja -c.device 1 -c.  
channel 1
```

30.4 Operation Overview

The latency measurement tool operates by having a **producer** component generate a sequence of known video frames that are output and then transferred back to an input **consumer** component using a physical loopback cable. Timestamps are compared throughout the life of the frame to measure the overall latency that the frame sees during this process, and these results are summarized when all of the frames have been received and the measurement completes. See [Producers](#), [Consumers](#), and [Example Configurations](#) for more details.

30.4.1 Frame Measurements

Each frame that is generated by the tool goes through the following steps in order, each of which has its time measured and then reported when all frames complete.

1. CUDA Processing

In order to simulate a real-world GPU workload, the tool first runs a CUDA kernel for a user-specified amount of loops (defaults to zero). This step is described below in [Simulating GPU Workload](#).

2. Render on GPU

After optionally simulating a GPU workload, every producer then generates its frames using the GPU, either by a common CUDA kernel or by another method that is available to the producer's API (such as the OpenGL

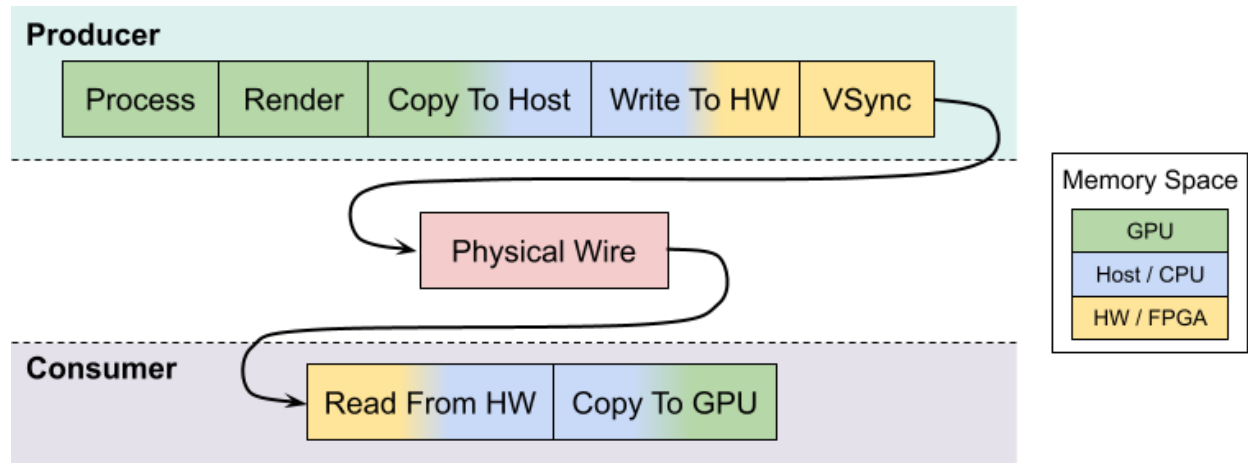


Fig. 30.4: Latency Tool Frame Lifespan (RDMA Disabled)

producer).

This step is expected to be very fast (<100us), but higher times may be seen if overall system load is high.

3. Copy To Host

Once the frame has been generated on the GPU, it may be necessary to copy the frame to host memory in order for the frame to be output by the producer component (for example, an AJA producer with RDMA disabled).

If a host copy is not required (i.e. RDMA is enabled for the producer), this time should be zero.

4. Write to HW

Some producer components require frames to be copied to peripheral memory before they can be output (for example, an AJA producer requires frames to be copied to the external frame stores on the AJA device). This copy may originate from host memory if RDMA is disabled for the producer, or from GPU memory if RDMA is enabled.

If this copy is not required, e.g. the producer outputs directly from the GPU, this time should be zero.

5. VSync Wait

Once the frame is ready to be output, the producer hardware must wait for the next VSync interval before the frame can be output.

The sum of this VSync wait and all of the preceding steps is expected to be near a multiple of the frame interval. For example, if the frame rate is 60Hz then the sum of the times for steps 1 through 5 should be near a multiple of 16666us.

6. Wire Time

The wire time is the amount of time that it takes for the frame to transfer across the physical loopback cable. This should be near the time for a single frame interval.

7. Read From HW

Once the frame has been transferred across the wire and is available to the consumer, some consumer components require frames to be copied from peripheral memory into host (RDMA disabled) or GPU (RDMA enable) memory. For example, an AJA consumer requires frames to be copied from the external frame store of the AJA device.

If this copy is not required, e.g. the consumer component writes received frames directly to host/GPU memory, this time should be zero.

8. Copy to GPU

If the consumer received the frame into host memory, the final step required for processing the frame with the GPU is to copy the frame into GPU memory.

If RDMA is enabled for the consumer and the frame was previously written directly to GPU memory, this time should be zero.

Note that if RDMA is enabled on the producer and consumer sides then the GPU/host copy steps above, 3 and 8 respectively, are effectively removed since RDMA will copy directly between the video HW and the GPU. The following shows the same diagram as above but with RDMA enabled for both the producer and consumer.

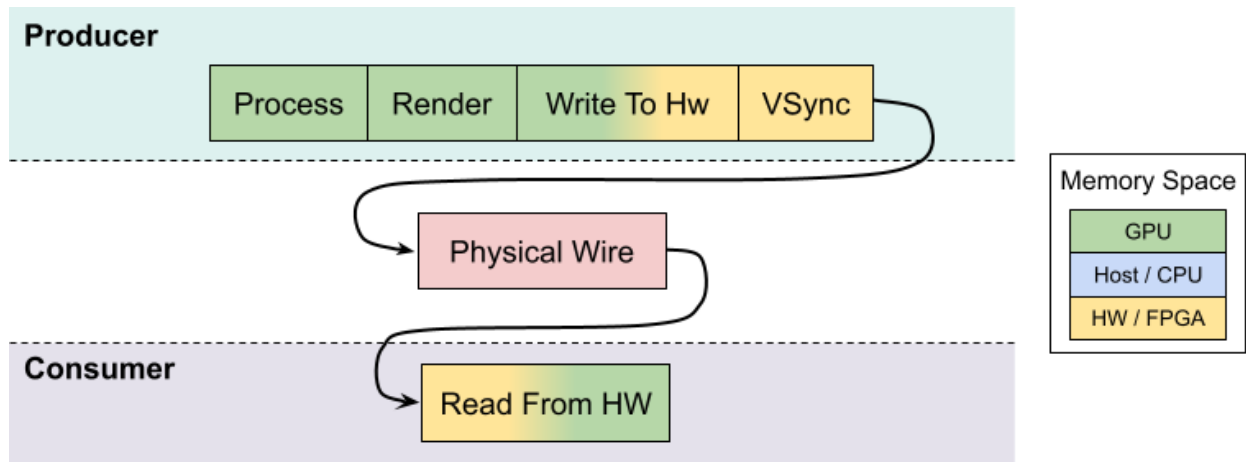


Fig. 30.5: Latency Tool Frame Lifespan (RDMA Enabled)

30.4.2 Interpreting The Results

The following shows example output of the above measurements from the tool when testing a 4K stream at 60Hz from an AJA producer to an AJA consumer, both with RDMA disabled, and no GPU/CUDA workload simulation. Note that all time values are given in microseconds.

```
$ ./loopback-latency -p aja -p.rdma 0 -c aja -c.rdma 0 -f 4k
```

```

Format: 4096x2160 RGBA @ 60Hz

Producer: AJA
  Device: 0
  Channel: NTV2_CHANNEL1
  RDMA: 0

Consumer: AJA
  Device: 0
  Channel: NTV2_CHANNEL2
  RDMA: 0

Measuring 600 frames...Done!

CUDA Processing: avg =      0, min =      0, max =      64
Render on GPU:   avg =    144, min =     94, max =    386
Copy To Host:    avg =   5788, min =   4145, max =   7024
Write To HW:     avg =   9468, min =   8219, max =   9916
Vsync Wait:     avg =   1245, min =    126, max =   2608
Wire Time:      avg =  16745, min =  16547, max =  17379
Read From HW:   avg =   7086, min =   6983, max =   7357
Copy To GPU:    avg =   4282, min =   3805, max =   6304
=====
Total:          avg =  44764, min =  44122, max =  46680

```

While this tool measures the producer times followed by the consumer times, the expectation for real-world video processing applications is that this order would be reversed. That is to say, the expectation for a real-world application is that it would capture, process, and output frames in the following order (with the component responsible for measuring that time within this tool given in parentheses):

1. **Read from HW** (consumer)
2. **Copy to GPU** (consumer)
3. **Process Frame** (producer)
4. **Render Results to GPU** (producer)
5. **Copy to Host** (producer)
6. **Write to HW** (producer)

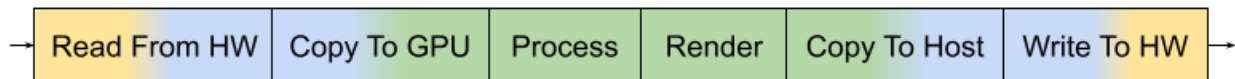


Fig. 30.6: Real Application Frame Lifespan

To illustrate this, the tool sums and displays the total producer and consumer times, then provides the **Estimated Application Times** as the total sum of all of these steps (i.e. steps 1 through 6, above).

(continued from above)

```

Producer (Process and Write to HW)
=====
Microseconds: avg = 15403, min = 14074, max = 16495
Frames: avg = 0.924, min = 0.844, max = 0.99

Consumer (Read from HW and Copy to GPU)
=====
Microseconds: avg = 11369, min = 10856, max = 13381
Frames: avg = 0.682, min = 0.651, max = 0.803

Estimated Application Times (Read + Process + Write)
=====
Microseconds: avg = 26772, min = 25101, max = 29204
Frames: avg = 1.61, min = 1.51, max = 1.75

```

Once a real-world application captures, processes, and outputs a frame, it would still be required that this final output waits for the next VSync interval before it is actually sent across the physical wire to the display hardware. Using this assumption, the tool then estimates one final value for the **Final Estimated Latencies** by doing the following:

1. Take the **Estimated Application Time** (from above)
2. Round it up to the next VSync interval
3. Add the physical wire time (i.e. a frame interval)

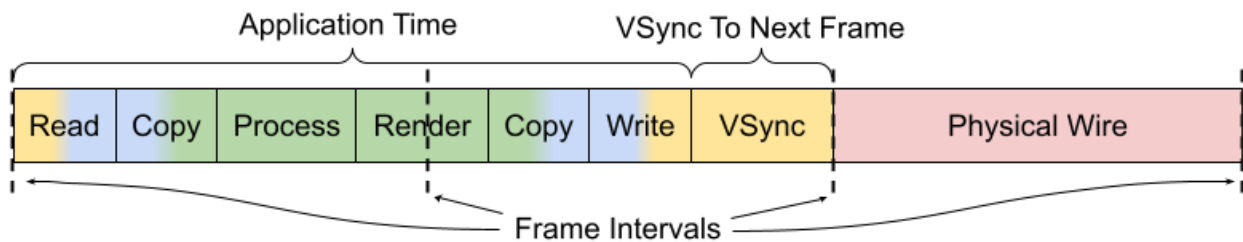


Fig. 30.7: Final Estimated Latency with VSync and Physical Wire Time

Continuing this example using a frame interval of 16666us (60Hz), this means that the average **Final Estimated Latency** is determined by:

1. Average application time = **26772**
2. Round up to next VSync interval = **33332**
3. Add physical wire time (+16666) = **49998**

These times are also reported as a multiple of frame intervals.

(continued from above)

```

Final Estimated Latencies (Processing + Vsync + Wire)
=====
Microseconds: avg = 49998, min = 49998, max = 49998
Frames: avg = 3, min = 3, max = 3

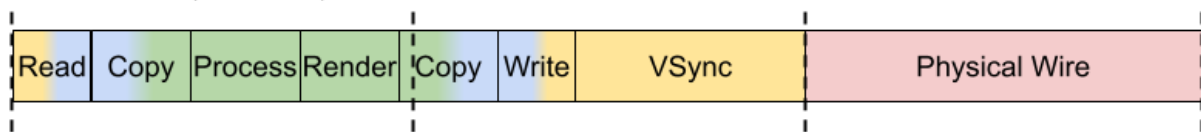
```

Using this example, we should then expect that the total end-to-end latency that is seen by running this pipeline using these components and configuration is 3 frame intervals (49998us).

30.4.3 Reducing Latency With RDMA

The previous example uses an AJA producer and consumer for a 4K @ 60Hz stream, however RDMA was disabled for both components. Because of this, the additional copies between the GPU and host memory added more than 10000us of latency to the pipeline, causing the application to exceed one frame interval of processing time per frame and therefore a total frame latency of 3 frames. If RDMA is enabled, these GPU and host copies can be avoided so the processing latency is reduced by more than 10000us. More importantly, however, this also allows the total processing time to fit within a single frame interval so that the total end-to-end latency can be reduced to just 2 frames.

RDMA Disabled (3 Frames)



RDMA Enabled (2 Frames)

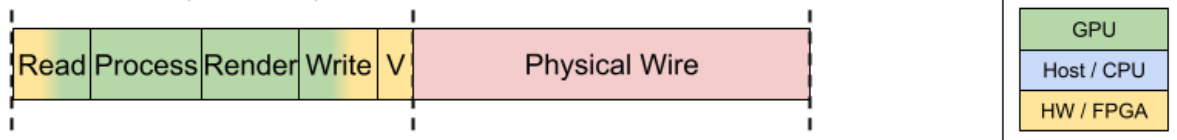


Fig. 30.8: Reducing Latency With RDMA

The following shows the above example repeated with RDMA enabled.

```
$ ./loopback-latency -p aja -p.rdma 1 -c aja -c.rdma 1 -f 4k
```

```

Format: 4096x2160 RGBA @ 60Hz

Producer: AJA
  Device: 0
  Channel: NTV2_CHANNEL1
  RDMA: 1

Consumer: AJA
  Device: 0
  Channel: NTV2_CHANNEL2
  RDMA: 1

Measuring 600 frames...Done!

CUDA Processing: avg =      0, min =      0, max =      74
Render on GPU:   avg =    122, min =     94, max =    356
Copy To Host:    avg =      0, min =      0, max =     35
Write To HW:     avg =   8209, min =   7453, max =   8856
Vsync Wait:     avg =   8314, min =   6338, max =  10036
Wire Time:      avg =  16650, min =  14814, max =  18391
Read From HW:   avg =   6041, min =   5962, max =   6931
Copy To GPU:    avg =      0, min =      0, max =     30
=====
Total:          avg =  39343, min =  37668, max =  41081

Producer (Process and Write to HW)
=====
  Microseconds: avg =   8334, min =   7580, max =   8988
    Frames: avg =    0.5, min =   0.455, max =   0.539

Consumer (Read from HW and Copy to GPU)
=====
  Microseconds: avg =   6042, min =   5962, max =   6932
    Frames: avg =   0.363, min =   0.358, max =   0.416

Estimated Application Times (Read + Process + Write)
=====
  Microseconds: avg =  14377, min =  13627, max =  15233
    Frames: avg =   0.863, min =   0.818, max =   0.914

Final Estimated Latencies (Processing + Vsync + Wire)
=====
  Microseconds: avg =  33332, min =  33332, max =  33332
    Frames: avg =      2, min =      2, max =      2

```

30.4.4 Simulating GPU Workload

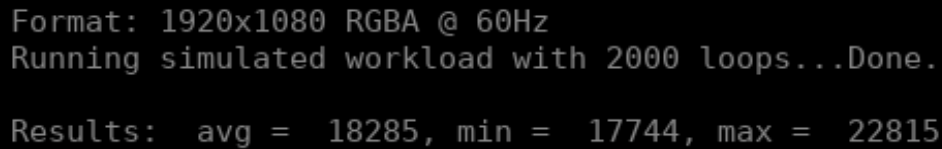
By default the tool measures what is essentially a pass-through video pipeline; that is, no processing of the video frames is performed by the system. While this is useful for measuring the minimum latency that can be achieved by the video input and output components, it's not very indicative of a real-world use case in which the GPU is used for compute-intensive processing operations on the video frames between the input and output — for example, an object detection algorithm that applies an overlay to the output frames.

While it may be relatively simple to measure the runtime latency of the processing algorithms that are to be applied to the video frames — by simply measuring the runtime of running the algorithm on a single or stream of frames — this may not be indicative of the effects that such processing might have on the overall system load, which may further increase the latency of the video input and output components.

In order to estimate the total latency when an additional GPU workload is added to the system, the latency tool has an `-s {count}` option that can be used to run an arbitrary CUDA loop the specified number of times before the producer actually generates a frame. The expected usage for this option is as follows:

1. The per-frame runtime of the actual GPU processing algorithm is measured outside of the latency measurement tool.
2. The latency tool is repeatedly run with just the `-s {count}` option, adjusting the `{count}` parameter until the time that it takes to run the simulated loop approximately matches the actual processing time that was measured in the previous step.

```
$ ./loopback-latency -s 2000
```



```
Format: 1920x1080 RGBA @ 60Hz
Running simulated workload with 2000 loops...Done.

Results:  avg = 18285, min = 17744, max = 22815
```

3. The latency tool is run with the full producer (`-p`) and consumer (`-c`) options used for the video I/O, along with the `-s {count}` option using the loop count that was determined in the previous step.

Note: The following example shows that approximately half of the frames received by the consumer were duplicate/repeated frames. This is due to the fact that the additional processing latency of the producer causes it to exceed a single frame interval, and so the producer is only able to output a new frame every second frame interval.

```
$ ./loopback-latency -p aja -c aja -s 2000
```

```

Format: 1920x1080 RGBA @ 60Hz

Producer: AJA
  Device: 0
  Channel: NTV2_CHANNEL1
  RDMA: 1

Consumer: AJA
  Device: 0
  Channel: NTV2_CHANNEL2
  RDMA: 1

Simulating processing with 2000 CUDA loops per frame.

Measuring 600 frames...Done!

WARNING: Frames were skipped or repeated!
Frames received: 301
Frames skipped: 0
Frames repeated: 299

CUDA Processing: avg = 17153, min = 16877, max = 17569
Render on GPU:   avg = 50, min = 34, max = 116
Copy To Host:    avg = 0, min = 0, max = 19
Write To HW:     avg = 1785, min = 1721, max = 1849
Vsync Wait:      avg = 14321, min = 13782, max = 14718
Wire Time:       avg = 16723, min = 16360, max = 33470
Read From HW:    avg = 1502, min = 1442, max = 1726
Copy To GPU:     avg = 0, min = 0, max = 0
=====
Total:           avg = 51541, min = 51164, max = 68238

Producer (Process and Write to HW)
=====
  Microseconds: avg = 18991, min = 18689, max = 19405
  Frames: avg = 1.14, min = 1.12, max = 1.16

Consumer (Read from HW and Copy to GPU)
=====
  Microseconds: avg = 1502, min = 1443, max = 1726
  Frames: avg = 0.0901, min = 0.0866, max = 0.104

Estimated Application Times (Read + Process + Write)
=====
  Microseconds: avg = 20493, min = 20191, max = 20967
  Frames: avg = 1.23, min = 1.21, max = 1.26

Final Estimated Latencies (Processing + Vsync + Wire)
=====
  Microseconds: avg = 49998, min = 49998, max = 49998
  Frames: avg = 3, min = 3, max = 3

WARNING: Frames were skipped or repeated. These times only
include frames that were actually received, and the times
include only the first instance each frame was received.

```

Tip: To get the most accurate estimation of the latency that would be seen by a real world application, the best thing to do would be to run the actual frame processing algorithm used by the application during the latency measurement. This could be done by modifying the `SimulateProcessing` function in the latency tool source code.

30.5 Graphing Results

The latency tool includes a `-o {file}` option that can be used to output a CSV file with all of the measured times for every frame. This file can then be used with the `graph_results.py` script that is included with the tool in order to generate a graph of the measurements.

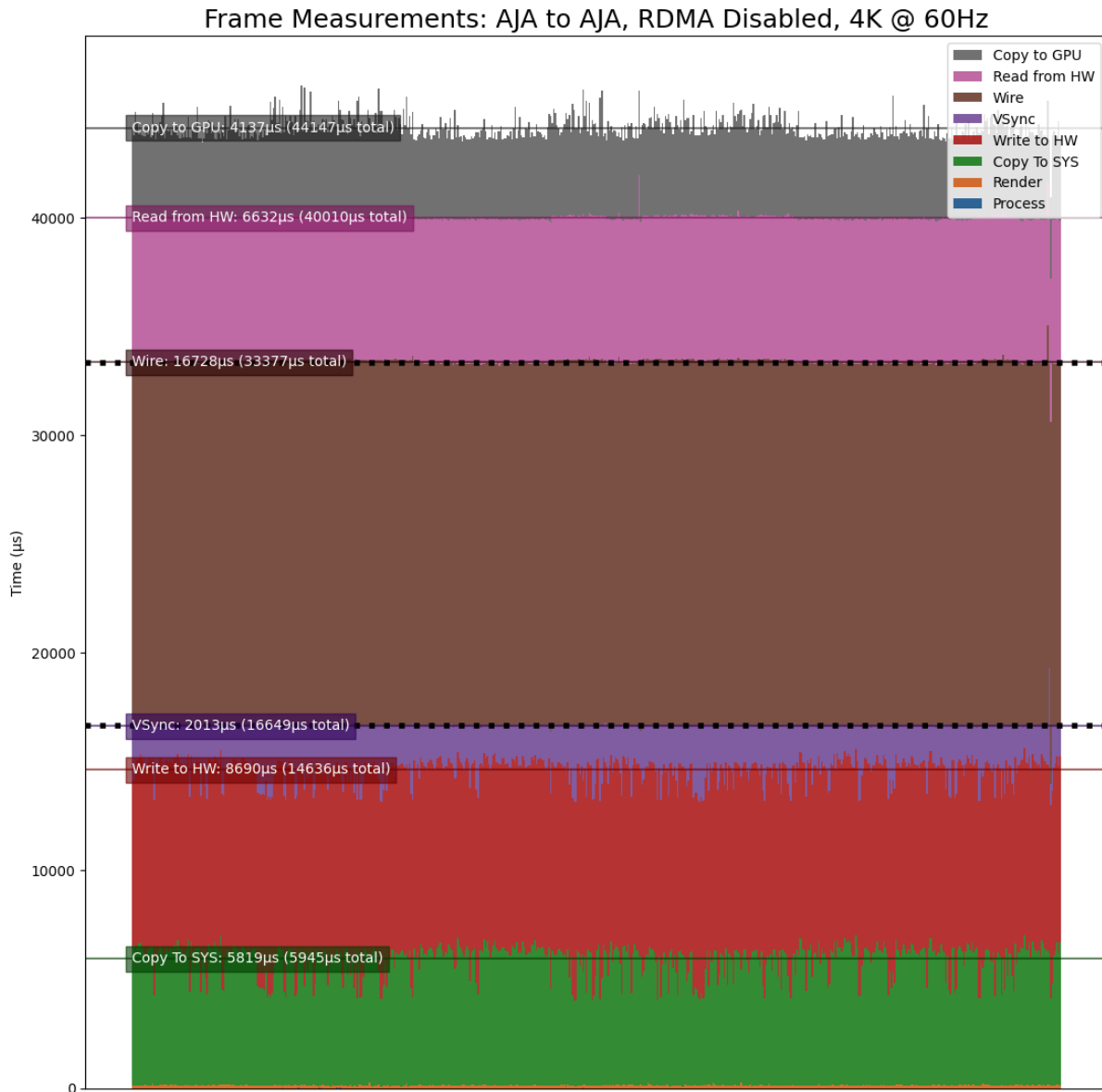
For example, if the latencies are measured using:

```
$ ./loopback-latency -p aja -c aja -o latencies.csv
```

The graph can then be generated using the following, which will open a window on the desktop to display the graph:

```
$ ./graph_results.py --file latencies.csv
```

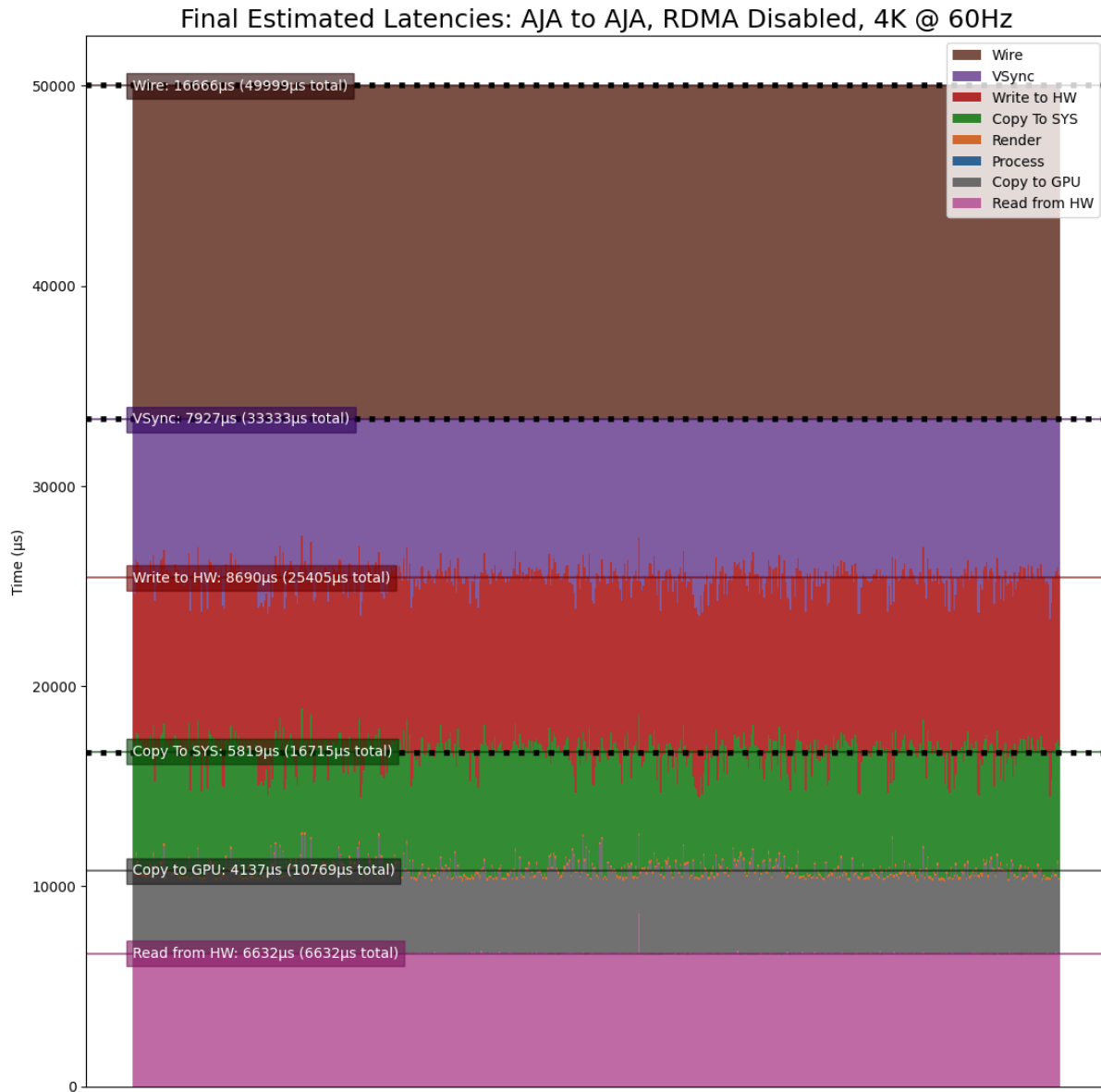
The graph can also be output to a PNG image file instead of opening a window on the desktop by providing the `--png {file}` option to the script. The following shows an example graph for an AJA to AJA measurement of a 4K @ 60Hz stream with RDMA disabled (as shown as an example in [Interpreting The Results](#), above).



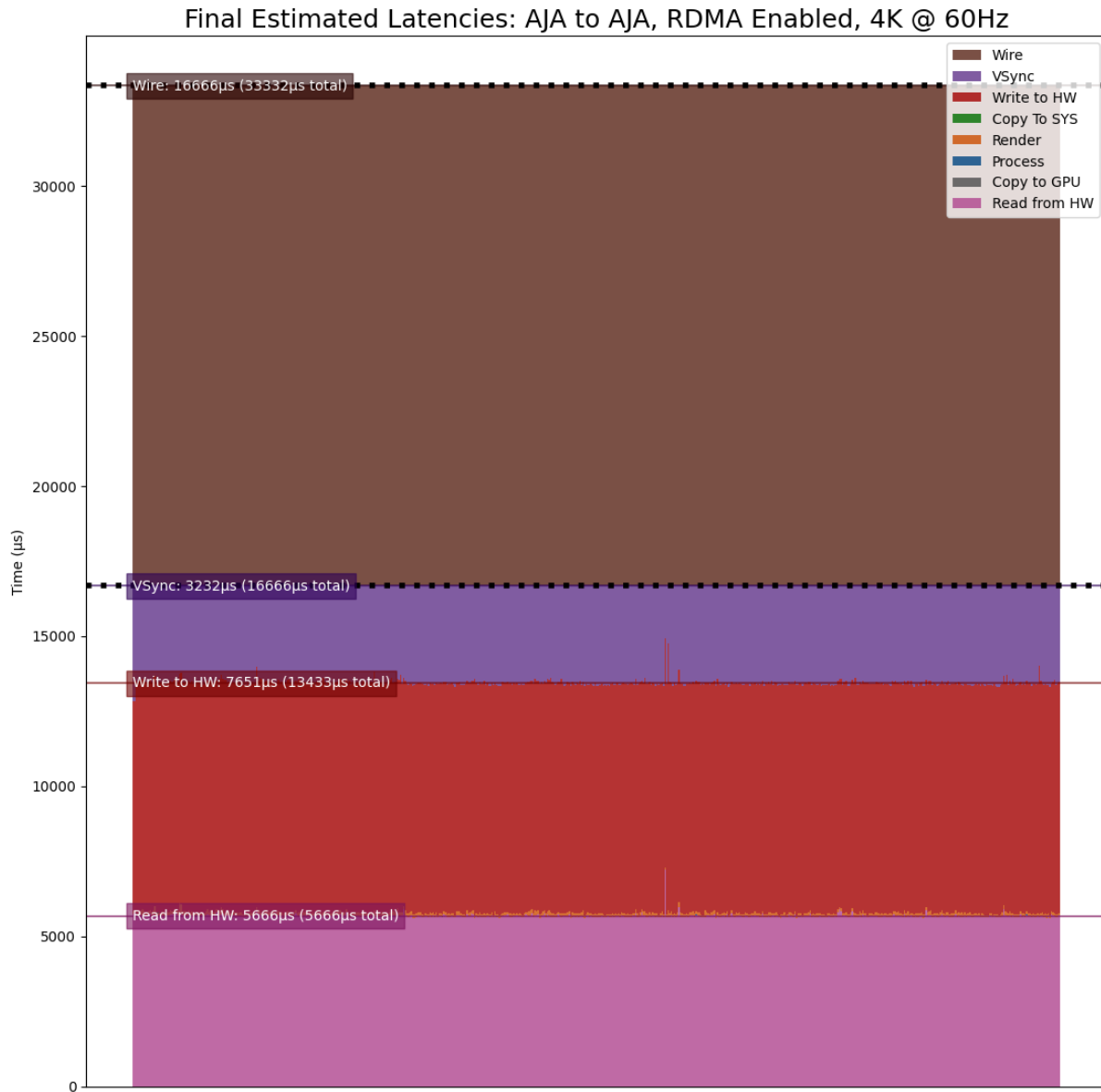
Note that this is showing the times for 600 frames, from left to right, with the life of each frame beginning at the bottom and ending at the top. The dotted black lines represent frame VSync intervals (every 16666μs).

The above example graphs the times directly as measured by the tool. To instead generate a graph for the **Final Estimated Latencies** as described above in *Interpreting The Results*, the `--estimate` flag can be provided to the script. As is done by the latency tool when it reports the estimated latencies, this reorders the producer and consumer steps then adds a VSync interval followed by the physical wire latency.

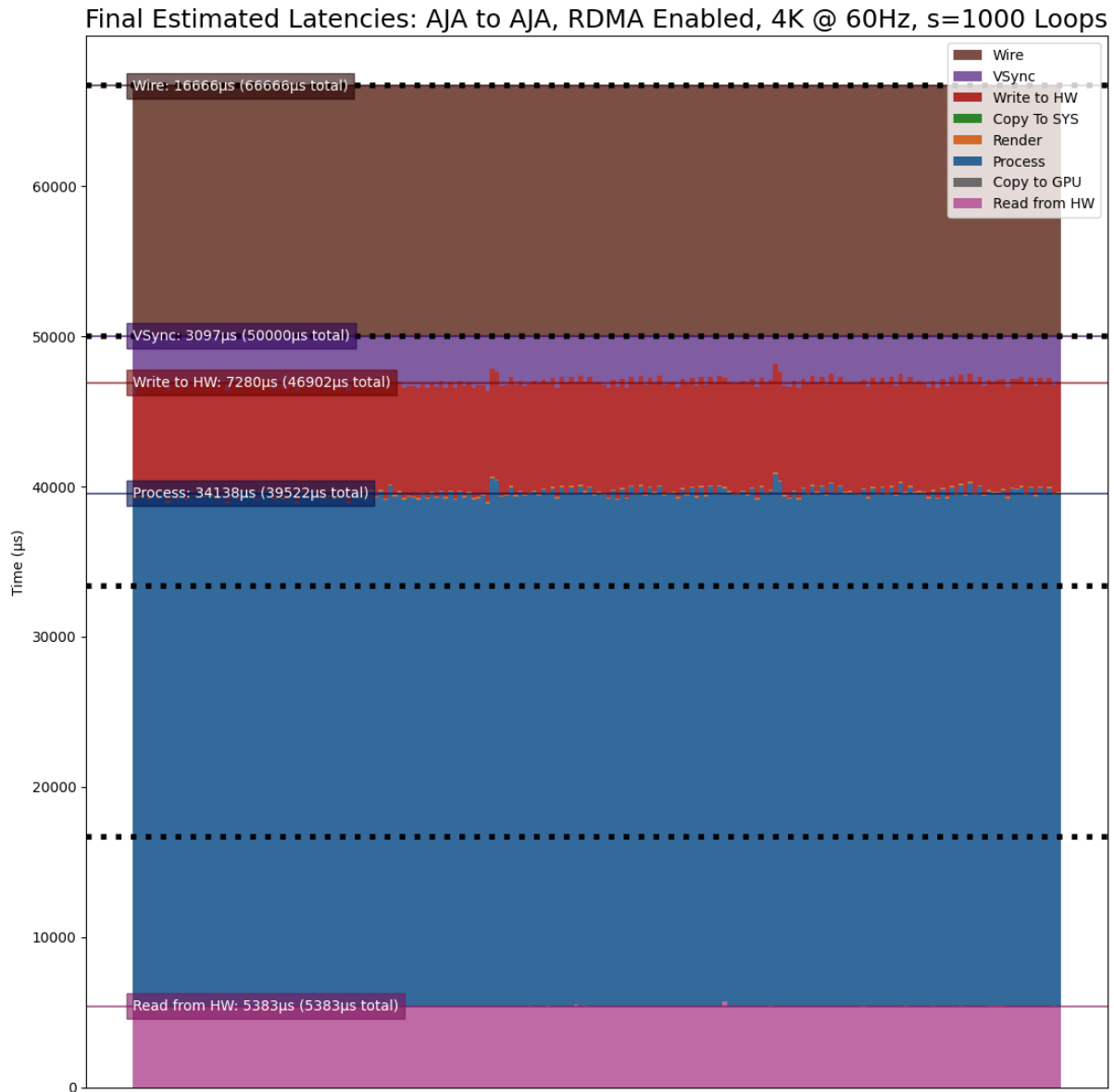
The following graphs the **Final Estimated Latencies** using the same data file as the graph above. Note that this shows a total of 3 frames of expected latency.



For the sake of comparison, the following graph shows the same test but with RDMA enabled. Note that the **Copy To GPU** and **Copy To SYS** times are now zero due to the use of RDMA, and this now shows just 2 frames of expected latency.



As a final example, the following graph duplicates the above test with RDMA enabled, but adds roughly 34ms of additional GPU processing time (`-s 1000`) to the pipeline to produce a final estimated latency of 4 frames.



30.6 Producers

There are currently 3 producer types supported by the Holoscan latency tool. See the following sections for a description of each supported producer.

30.6.1 OpenGL GPU Direct Rendering (HDMI)

This producer (`gl`) uses OpenGL to render frames directly on the GPU for output via the HDMI connectors on the GPU. This is currently expected to be the lowest latency path for GPU video output.

OpenGL Producer Notes:

- The video generated by this producer is rendered full-screen to the primary display. As of this version, this component has only been tested in a display-less environment in which the loop-back HDMI cable is the only cable attached to the GPU (and thus is the primary display). It may also be required to use the `xrandr` tool to configure the HDMI output — the tool will provide the `xrandr` commands needed if this is the case.
- Since OpenGL renders directly to the GPU, the `p.rdma` flag is not supported and RDMA is always considered to be enabled for this producer.

30.6.2 GStreamer GPU Rendering (HDMI)

This producer (`gst`) uses the `nveglglessink` GStreamer component that is included with Holopack in order to render frames that originate from a GStreamer pipeline to the HDMI connectors on the GPU.

GStreamer Producer Notes:

- The tool must be built with DeepStream support in order for this producer to support RDMA (see [Enabling DeepStream Support](#) for details).
- The video generated by this producer is rendered full-screen to the primary display. As of this version, this component has only been tested in a display-less environment in which the loop-back HDMI cable is the only cable attached to the GPU (and thus is the primary display). It may also be required to use the `xrandr` tool to configure the HDMI output — the tool will provide the `xrandr` commands needed if this is the case.
- Since the output of the generated frames is handled internally by the `nveglglessink` plugin, the timing of when the frames are output from the GPU are not known. Because of this, the *Wire Time* that is reported by this producer includes all of the time that the frame spends between being passed to the `nveglglessink` and when it is finally received by the consumer.

30.6.3 AJA Video Systems (SDI)

This producer (`aja`) outputs video frames from an AJA Video Systems device that supports video playback.

AJA Producer Notes:

- The latency tool must be built with AJA Video Systems support in order for this producer to be available (see [Building](#) for details).
- The following parameters can be used to configure the AJA device and channel that are used to output the frames:
 - `-p.device {index}`
Integer specifying the device index (i.e. 0 or 1). Defaults to 0.
 - `-p.channel {channel}`
Integer specifying the channel number, starting at 1 (i.e. 1 specifies NTV2_CHANNEL_1). Defaults to 1.
- The `p.rdma` flag can be used to enable (1) or disable (0) the use of RDMA with the producer. If RDMA is to be used, the AJA drivers loaded on the system must also support RDMA.
- The only AJA device that have currently been verified to work with this producer is the [Corvid 44 12G BNC \(SDI\)](#).

30.7 Consumers

There are currently 3 consumer types supported by the Holoscan latency tool. See the following sections for a description of each supported consumer.

30.7.1 V4L2 (Onboard HDMI Capture Card)

This consumer (`v4l2`) uses the V4L2 API directly in order to capture frames using the HDMI capture card that is onboard the Holoscan Developer Kits.

V4L2 Consumer Notes:

- The onboard HDMI capture card is locked to a specific frame resolution and frame rate (1080p @ 60Hz), and so **1080** is the only supported format when using this consumer.
- The `-c.device {device}` parameter can be used to specify the path to the device that is being used to capture the frames (defaults to `/dev/video0`).
- The V4L2 API does not support RDMA, and so the `c.rdma` option is ignored.

30.7.2 GStreamer (Onboard HDMI Capture Card)

This consumer (`gst`) also captures frames from the onboard HDMI capture card, but uses the `v4l2src` GStreamer plugin that wraps the V4L2 API to support capturing frames for using within a GStreamer pipeline.

GStreamer Consumer Notes:

- The onboard HDMI capture card is locked to a specific frame resolution and frame rate (1080p @ 60Hz), and so **1080** is the only supported format when using this consumer.
- The `-c.device {device}` parameter can be used to specify the path to the device that is being used to capture the frames (defaults to `/dev/video0`).
- The `v4l2src` GStreamer plugin does not support RDMA, and so the `c.rdma` option is ignored.

30.7.3 AJA Video Systems (SDI and HDMI)

This consumer (`aja`) captures video frames from an AJA Video Systems device that supports video capture. This can be either an SDI or an HDMI video capture card.

AJA Consumer Notes:

- The latency tool must be built with AJA Video Systems support in order for this producer to be available (see [Building](#) for details).
- The following parameters can be used to configure the AJA device and channel that are used to capture the frames:
 - `-c.device {index}`
Integer specifying the device index (i.e. 0 or 1). Defaults to 0.
 - `-c.channel {channel}`
Integer specifying the channel number, starting at 1 (i.e. 1 specifies `NTV2_CHANNEL_1`). Defaults to 2.
- The `c.rdma` flag can be used to enable (1) or disable (0) the use of RDMA with the consumer. If RDMA is to be used, the AJA drivers loaded on the system must also support RDMA.

- The only AJA devices that have currently been verified to work with this consumer are the [KONA HDMI](#) (for HDMI) and [Corvid 44 12G BNC](#) (for SDI).

30.8 Troubleshooting

If any of the loopback-latency commands described above fail with errors, the following steps may help resolve the issue.

1. **Problem:** The following error is output:

```
ERROR: Failed to get a handle to the display (is the DISPLAY environment variable
↪ set?)
```

Solution: Ensure that the DISPLAY environment variable is set with the ID of the X11 display you are using; e.g. for display ID 0:

```
$ export DISPLAY=:0
```

If the error persists, try changing the display ID; e.g. replacing 0 with 1:

```
$ export DISPLAY=:1
```

It might also be convenient to set this variable in your ~/.bashrc file so that it is set automatically whenever you login.

2. **Problem:** An error like the following is output:

```
ERROR: The requested format (1920x1080 @ 60Hz) does not match
       the current display mode (1024x768 @ 60Hz)
       Please set the display mode with the xrandr tool using
       the following command:

       $ xrandr --output DP-5 --mode 1920x1080 --panning 1920x1080 --rate 60
```

But using the xrandr command provided produces an error:

```
$ xrandr --output DP-5 --mode 1920x1080 --panning 1920x1080 --rate 60
xrandr: cannot find mode 1920x1080
```

Solution: Try the following:

1. Ensure that no other displays are connected to the GPU.
2. Check the output of an xrandr command to see that the requested format is supported. The following shows an example of what the onboard HDMI capture card should support. Note that each row of the supported modes shows the resolution on the left followed by all of the supported frame rates for that resolution to the right.

```
$ xrandr
Screen 0: minimum 8 x 8, current 1920 x 1080, maximum 32767 x 32767
DP-0 disconnected (normal left inverted right x axis y axis)
DP-1 disconnected (normal left inverted right x axis y axis)
DP-2 disconnected (normal left inverted right x axis y axis)
DP-3 disconnected (normal left inverted right x axis y axis)
DP-4 disconnected (normal left inverted right x axis y axis)
```

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```

DP-5 connected primary 1920x1080+0+0 (normal left inverted right x axis y axis)
↪1872mm x 1053mm
  1920x1080    60.00*+  59.94   50.00   29.97   25.00   23.98
  1680x1050    59.95
  1600x900     60.00
  1440x900     59.89
  1366x768     59.79
  1280x1024    75.02   60.02
  1280x800     59.81
  1280x720     60.00   59.94   50.00
  1152x864     75.00
  1024x768     75.03   70.07   60.00
   800x600     75.00   72.19   60.32
   720x576     50.00
   720x480     59.94
   640x480     75.00   72.81   59.94
DP-6 disconnected (normal left inverted right x axis y axis)
DP-7 disconnected (normal left inverted right x axis y axis)
USB-C-0 disconnected (normal left inverted right x axis y axis)

```

3. If a UHD or 4K mode is being requested, ensure that the DisplayPort to HDMI cable that is being used supports that mode.
 4. If the `xrandr` output still does not show the mode that is being requested but it should be supported by the cable and capture device, try rebooting the device.
3. **Problem:** One of the following errors is output:

```
ERROR: Select timeout on /dev/video0
```

```
ERROR: Failed to get the monitor mode (is the display cable attached?)
```

```
ERROR: Could not find frame color (0,0,0) in producer records.
```

These errors mean that either the capture device is not receiving frames, or the frames are empty (the producer will never output black frames, (0,0,0)).

Solution: Check the output of `xrandr` to ensure that the loopback cable is connected and the capture device is recognized as a display. If the following is output, showing no displays attached, this could mean that the loopback cable is either not connected properly or is faulty. Try connecting the cable again and/or replacing the cable.

```

$ xrandr
Screen 0: minimum 8 x 8, current 1920 x 1080, maximum 32767 x 32767
DP-0 disconnected (normal left inverted right x axis y axis)
DP-1 disconnected (normal left inverted right x axis y axis)
DP-2 disconnected (normal left inverted right x axis y axis)
DP-3 disconnected (normal left inverted right x axis y axis)
DP-4 disconnected (normal left inverted right x axis y axis)
DP-5 disconnected primary 1920x1080+0+0 (normal left inverted right x axis y axis)
↪0mm x 0mm
DP-6 disconnected (normal left inverted right x axis y axis)
DP-7 disconnected (normal left inverted right x axis y axis)

```

4. **Problem:** An error like the following is output:

ERROR: Could **not** find frame color (27,28,26) in producer records.

Colors near this particular value (27,28,26) are displayed on the Ubuntu lock screen, which prevents the latency tool from rendering frames properly. Note that the color value may differ slightly from (27,28,26).

Solution:

Follow the steps provided in the note at the top of the Example Configurations section to *enable automatic login and disable the Ubuntu lock screen*.