NVIDIA Holoscan SDK v2.1.0
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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.

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 NVIDIA 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

---

**Note**
In previous releases, the prefix `<a href="https://developer.nvidia.com/industries/healthcare">Clara</a>` was used to define Holoscan as a platform designed initially for medical devices. Starting with version 0.4.0, the Holoscan SDK is built to be domain-agnostic and can be used to build sensor AI applications in multiple domains. Domain specific content will be hosted on the HoloHub repository.
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

Rivermax and GPUDirect RDMA

The NVIDIA Developer Kits equipped with a ConnectX network adapter can be used along with the NVIDIA Rivermax SDK to provide an extremely efficient network connection 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.

**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.

**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 NVIDIA Developer Kits.

The inference module leverages TensorRT among other backends, and provides the ability to execute multiple inferences in parallel.

**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.

**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.

**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.

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.

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. 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.
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.

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.

6. Master the details

- Expand your understanding of the framework with details on the logging utility or the data flow tracking benchmarking tool and job statistics measurements.
- 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)](https://openembedded.org) 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.

**Prerequisites**

**Ingested Tab Module**

- 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.

**Install the SDK**

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

**Instructions**
Ingested Tab Module

**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), and should work on most Linux distributions. 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.

- 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, assuming you are on Ubuntu 22.04.

- 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. Finally, they are only formally supported on Ubuntu 22.04, though should support other linux distributions with glibc 2.35 or above.

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**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...
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.

[1]

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

[2](1,2,3,4,5)

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 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]

[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](1,2)

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 TensoRT backend of the Inference Operator.

[10](1,2)

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

[11]

Tested with MOFED 23.10
Additional Setup

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

- Enabling RDMA
- Enabling G-SYNC
- Disabling Variable Backlight
- Enabling Exclusive Display Mode
- Use both Integrated and Discrete GPUs on NVIDIA Developer Kits
- Deployment Software Stack

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

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 23.10 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="23.10-2.1.3.1"
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}/${MOFED_PACKAGE}.tgz sudo ./${MOFED_PACKAGE}/mlnxofedinstall
```

```
# add the --force flag to force uninstallation if necessary: #
sudo ${MOFED_PACKAGE}/mlnxofedinstall --force
```

```
rm -r ${MOFED_PACKAGE}*
```

```
sudo lsmod | grep ib_core
```

If nothing appears, run the following command:

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

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: 0x4ab02dfffee7a04 Link layer: Ethernet CA 'mlx5_1' CA type: MT4129 Number of ports: 1 Firmware version: 28.37.0190 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: 0x4ab02dfffee7a05 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.

   ```bash
   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:

   ```plaintext
   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 ETH(2) ETH(2) Link is actually the current value that was expected to be used at the next reboot, while New ETH(2) 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):
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...).

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

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 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)
```

```
$ 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.

**Enabling GPUDirect RDMA**

**Note**
Follow the instructions below to enable GPUDirect RDMA:

Ingested Tab Module

**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.

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 `enp9s0f0` 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 1000bt-fd 10000bt-fd autonegotiation configuration: autonegotiation=on broadcast=yes driver=mlx5_core driverversion=5.4-1.0.3
```

**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.*
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 | 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 `&lt;ctrl-c&gt;`.

### 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
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

---

**Fig. 1 Enable G-SYNC for the current display**
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.

![NVIDIA Settings]

**Fig. 2 Enable Visual Indicator for the current display**

**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,
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.

Use both Integrated and Discrete GPUs on NVIDIA Developer Kits

NVIDIA 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:

Ingested Tab Module

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

## 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 the NVIDIA IGX Developer Kits.

Holoscan OpenEmbedded/Yocto recipes add OpenEmbedded recipes and sample build configurations to build BSPs for the NVIDIA IGX Developer Kit 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 the NVIDIA IGX 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.

Table of Contents

- AJA Video Systems
  - Installing the AJA Hardware
  - Installing the AJA Software
    - Downloading the AJA NTV2 SDK Source
    - Installing the NVIDIA Open Kernel Modules for RDMA Support
    - Building the AJA NTV2 Drivers
    - Loading the AJA NTV2 Drivers
    - Building and Installing the AJA NTV2 SDK
    - Testing the AJA Device
  - Using AJA Devices in Containers
  - Troubleshooting
- Emergent Vision Technologies (EVT)
  - Installing EVT Hardware
  - Installing EVT Software
  - Testing the EVT Camera
  - Troubleshooting

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 provides ongoing support for the AJA
NTV2 SDK and device drivers.

The AJA drivers and SDK 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 sysmem 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 NVIDIA Developer Kits with a PCIe slot. 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, KONA XM, and KONA HDMI products, specifically.

![Note](image)

The addition of an AJA device to a NVIDIA 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.

### 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.
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/libajantv2.git
export NTV2=$(pwd)/libajantv2
```

Note
Installing the NVIDIA Open Kernel Modules for RDMA Support

If the AJA NTV2 drivers are going to be built with RDMA support, the open-source NVIDIA kernel modules must be installed instead of the default proprietary drivers. If the drivers were installed from an NVIDIA driver installer package then follow the directions on the NVIDIA Open GPU Kernel Module Source GitHub page. If the NVIDIA drivers were installed using an Ubuntu package via `apt`, then replace the installed `nvidia-kernel-source` package with the corresponding `nvidia-kernel-open` package. For example, the following shows that the 545 version drivers are installed:

```
S dpkg --list | grep nvidia-kernel-source ii nvidia-kernel-source-545 545.23.08-0ubuntu1 amd64 NVIDIA kernel source package
```

And the following will replace those with the corresponding `nvidia-kernel-open` drivers:

```
S sudo apt install -y nvidia-kernel-open-545 $ sudo dpkg-reconfigure nvidia-dkms-545
```

The system must then be rebooted to load the new open kernel modules.

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}/driver/bin` directory.
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.

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

**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}/driver/bin/load_ajantv2 loaded ajantv2 driver module
```

**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) 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 `rdmawhacker` utility can be used (use <ctrl-c> to
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`.

Troubleshooting

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

   **Solutions:**

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

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

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

   ```bash
   $ 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:**

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

   ```bash
   $ 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)
   ```

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

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

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

   ```bash
   ## 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.
Emergent Vision Technologies (EVT)

Thanks to a collaboration with Emergent Vision Technologies, the Holoscan SDK now supports EVT high-speed cameras on NVIDIA Developer Kits equipped with a ConnectX NIC using the Rivermax SDK.

Installing EVT Hardware

The EVT cameras can be connected to NVIDIA Developer Kits through a 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.
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.

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.

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. 3 Core concepts: Application
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.

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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**
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.

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:

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()`.
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.*

**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!

**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
Operators and Workflow

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

![Diagram of a linear workflow](image)

Fig. 5 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.

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()`.
Running the Application

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

<table>
<thead>
<tr>
<th>Rx message value: 1</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rx message value: 2</td>
</tr>
<tr>
<td>Rx message value: 3</td>
</tr>
<tr>
<td>Rx message value: 4</td>
</tr>
<tr>
<td>Rx message value: 5</td>
</tr>
<tr>
<td>Rx message value: 6</td>
</tr>
<tr>
<td>Rx message value: 7</td>
</tr>
<tr>
<td>Rx message value: 8</td>
</tr>
<tr>
<td>Rx message value: 9</td>
</tr>
<tr>
<td>Rx message value: 10</td>
</tr>
</tbody>
</table>

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.

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

![Diagram of operators and workflow](image)

**Fig. 6 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.

### 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)](#).

### 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.

**Ingested Tab Module**

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

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
```
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.

Operators and Workflow

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

Fig. 7 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.

**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.

**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:

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

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

**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().
Ingested Tab Module

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

Ingested Tab Module

- 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 \( rx/receivers \).

**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) [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
```
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

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.
Operators and Workflow

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

![Workflow diagram](image)

*Fig. 8 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.

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 (installed in `/opt/nvidia/holoscan/bin` or available on GitHub) 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.

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 it’s “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.

**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
%YAML 1.2
replayer: directory: "../data/racerx" # Path to gxf entity video data
basename: "racerx" # 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) 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
```
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++ /
In the distributed case we will:

- create one fragment that loads a video file from disk using the `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.

---

**Operators and Workflow**

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

![Workflow diagram](image)

Fig. 9 *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.

**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).

**Ingested Tab Module**

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.

**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.
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.

Operators and Workflow

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

![Diagram of operators and workflow](image)

**Fig. 10 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.

**Prerequisites**

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

```
$ 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 (installed in /opt/nvidia/holoscan/bin or on GitHub) to encode your video. Note that - using this script - the metadata in the generated GXF tensor files will indicate that the data should be copied to the GPU on read.

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 named graph_surgeon.py, installed in /opt/nvidia/holoscan/bin or available on GitHub. 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.

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

Ingested Tab Module

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

Ingested Tab Module

Finally, we define the application and workflow.

Ingested Tab Module

**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.

Ingested Tab Module

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](https://holohub.com) for additional implementations and ideas for operators.

### 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.

![Ultrasound Segmentation](image)

*Fig. 11 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):
Customizing the Inference Operator

The built-in \texttt{InferenceOp} operator provides the functionality of the \texttt{Inference}. This operator has a \texttt{receivers} port that can connect to any number of upstream ports to allow for multi-task inferencing, and one \texttt{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.

- \texttt{backend} : if the input models are in \texttt{tensorrt engine file} format, select \texttt{trt} as the backend. If the input models are in \texttt{onnx} format select either \texttt{trt} or \texttt{onnx} as the backend.

- \texttt{allocator} : Can be passed to this operator to specify how the output tensors are allocated.

- \texttt{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 \texttt{onnx} or in \texttt{tensorrt engine file} format. The Holoscan Inference Module will do the \texttt{onnx} to \texttt{tensorrt} model conversion if the TensorRT engine files do not exist.

- \texttt{pre_processor_map} : this dictionary should contain the same keys as \texttt{model_path_map}, mapping to the output tensor name for each model.

- \texttt{inference_map} : this dictionary should contain the same keys as \texttt{model_path_map}, mapping to the output tensor name for each model.

- \texttt{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.

- \texttt{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**

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.

Defining an Application Class

The following code snippet shows an example Application code skeleton:

Ingested Tab Module

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:

Ingested Tab Module

**Tip**

This is also illustrated in the `ping_simple_run_async` example.

**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.

**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.
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:

```yaml
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:

**Ingested Tab Module**

**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.

**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:

Ingested Tab Module

**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.

## 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:

Ingested Tab Module

**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:

Ingested Tab Module

Given this YAML configuration:

```yaml
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:

Ingested Tab Module

**Tip**

This is also illustrated in the `ping_custom_op` example.

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

Ingested Tab Module

**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`:

Ingested Tab Module
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.

Configuring operator resources

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

For example:

Ingested Tab Module

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 (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, the MultiThreadScheduler or EventBasedScheduler can instead be used. The difference between the two is that the MultiThreadScheduler is based on actively polling operators to determine if they are ready to execute, while the EventBasedScheduler will instead wait for an event indicating that an operator is ready to execute.

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

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.

One-operator Workflow

The simplest form of a workflow would be a single operator.
Fig. 12 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).

**Linear Workflow**

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

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).

**Ingested Tab Module**

**Complex Workflow (Multiple Inputs and Outputs)**

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

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).

Ingested Tab Module

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:

```
Operator A  Implicit Root  Operator E
    ^                                 ^
    |                                 |
    V                                 V
Operator B  Operator C  Operator D
```

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

Building and running your Application

Ingested Tab Module

**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

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.

Ingested Tab Module

**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.

**Building and running a Distributed Application**

Ingested Tab Module

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: \texttt{0.0.0.0}). It can be set without the port (e.g., \texttt{--address 192.168.50.68}).

- In a single-node application, the driver’s IP (or hostname) can be omitted, allowing any network interface (\texttt{0.0.0.0}) to be selected by the UCX library.

- The port is always optional (default: \texttt{8765}). It can be set without the IP (e.g., \texttt{--address :10000}).

The worker node’s address can be defined using the \texttt{--worker-address} command-line option (\texttt{[IPV4/IPv6 address or hostname][:port]}). If it’s not specified, the application worker will default to the host address (\texttt{0.0.0.0}) with a randomly chosen port number between \texttt{10000} and \texttt{32767} that is not currently in use. This argument automatically sets the \texttt{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 \texttt{--fragments} command-line option is used in combination with \texttt{--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 \texttt{--fragments all}.

The \texttt{--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 \texttt{my_app} on two separate nodes:

- The application driver is launched at \texttt{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.
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 \texttt{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 \texttt{HOLOSCAN\_HEALTH\_CHECK\_PORT} environment variable (default: 8777), for example, by using \texttt{export HOLOSCAN\_HEALTH\_CHECK\_PORT=8780}.

\begin{itemize}
  \item \textbf{Note}
  \end{itemize}

   **GXF UCX Extension**

   Holoscan’s distributed application feature makes use of the \texttt{GXF UCX Extension}. Its documentation may provide useful additional context.
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`, `multi_thread` or `event_based`, `multithread` is also allowed as a synonym for `multi_thread` for backwards compatibility. If unspecified, the default scheduler is `multi_thread`.

- **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

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.
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_SERIALIALIZATION_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
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.

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

If an operator transmitting both CPU and GPU tensors is to be used in distributed applications, the same output port cannot mix both GPU and CPU tensors. CPU and GPU tensor outputs should be placed on separate output ports. This is a limitation of the underlying UCX library being used for zero-copy tensor serialization between operators.

As a concrete example, assume an operator, `MyOperator` with a single output port named “out” defined in it’s setup method. If the output port is only ever going to connect to other operators within a fragment, but never across fragments then it is okay to have a `TensorMap` with a mixture of host and device arrays on that single port.

Ingested Tab Module

However, this mixing of CPU and GPU arrays on a single port will not work for distributed apps and instead separate ports should be used if it is necessary for an operator to communicate across fragments.

Ingested Tab Module

**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&lt;HolovizOp::InputSpec&gt;`. 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

```html
<a href="api/python/holoscan_python_api_core.html#holoscan.core.OutputContext.emit"> emissions</a>
```

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

```html
<a href="api/python/holoscan_python_api_core.html#holoscan.core.InputContext.receive"> receipts</a>
```

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).

### 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.

```cpp
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.

```cpp
#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.

```cpp
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.

```cpp
#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.

```cpp
namespace holoscan {
    CodecRegistry::get_instance().add_codec<Coordinate>("Coordinate"); } // namespace holoscan
```

Tip

CLI arguments (such as `--driver`, `--worker`, `--fragments`) are parsed by the `Application` (``
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.
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.

Prerequisites

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 gpg
# Install 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
```

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QEMU *(Optional)*

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

**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:

Ingested Tab Module

**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**
Ingested Tab Module

- **Using Environment Variable** `HOLOSCAN_INPUT_PATH` for Data Input

Ingested Tab Module

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/
```

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

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

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

Note

The tools can also be accessed inside the Docker container via

```
/var/holoscan/tools
```

Usage:
/var/holoscan/tools [command] [arguments]... Command List

- extract
  
  Extract data based on mounted volume paths.

  ```
  /var/run/holoscan/export/app extract
  /var/run/holoscan/export/config extract
  /var/run/holoscan/export/models extract
  /var/run/holoscan/export/docs extract
  /var/run/holoscan/export extract
  ```

- show
  
  Print manifest file(s): [app | pkg] to the terminal.

  ```
  app
  pkg
  ```

- env
  
  Print all environment variables to the terminal.
Creating Operators

**Tip**

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

**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.

**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.

![Sequence of method calls in the lifecycle of a Holoscan Operator](image)

Fig. 15 *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 2 The basic structure of a Holoscan Operator (C++)

```cpp
#include "holoscan/holoscan.hpp" using holoscan::Operator; using holoscan::OperatorSpec; using holoscan::InputContext; using holoscan::OutputContext; using holoscan::ExecutionContext; using holoscan::Arg; using holoscan::ArgList; class MyOp : public Operator { public:
HOLOSCAN_OPERATOR_FORWARD_ARGS(MyOp) MyOp() = default; void setup(OperatorSpec& spec) override {}
void start() override {
HOLOSCAN_LOG_TRACE("MyOp::start()");
} void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
HOLOSCAN_LOG_TRACE("MyOp::compute()");
} void stop() override {
HOLOSCAN_LOG_TRACE("MyOp::stop()");
}
```

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 3 examples/ping_multi_port/cpp/ping_multi_port.cpp

```cpp
#include "holoscan/holoscan.hpp" class ValueData { public: ValueData() = default;
explicit ValueData(int value) : data_(value) {
HOLOSCAN_LOG_TRACE("ValueData::ValueData(): {}", data_);
} ~ValueData() {
HOLOSCAN_LOG_TRACE("ValueData::~ValueData(): {}", data_);
} void data(int value) {
data_ = value;
} int data() const { return data_; }
private: int data_;
}; namespace holoscan::ops { class PingTxOp : public Operator { public:
HOLOSCAN_OPERATOR_FORWARD_ARGS(PingTxOp) PingTxOp() = default; void setup(OperatorSpec& spec) override {
spec.output<std::shared_ptr<ValueData>>("out1");
} void compute(InputContext&, OutputContext& op_output, ExecutionContext&) override {
auto value1 = std::make_shared<ValueData>(index_++);
op_output.emit(value1, "out1");
auto value2 = std::make_shared<ValueData>(index_++);
```
op_output.emit(value2, "out2"); } int index_ = 0; }; class PingMiddleOp : public Operator { public: HOLOSCAN_OPERATOR_FORWARD_ARGS(PingMiddleOp) PingMiddleOp() = default; void setup(OperatorSpec& spec) override {
    spec.input<std::shared_ptr<ValueData>>("in1");
    spec.input<std::shared_ptr<ValueData>>("in2");
    spec.output<std::shared_ptr<ValueData>>("out1");
    spec.output<std::shared_ptr<ValueData>>("out2"); spec.param(multiplier_, "multiplier", "Multiplier", "Multiply the input by this value", 2); } void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext&) override {
    auto value1 = op_input.receive<std::shared_ptr<ValueData>>("in1").value();
    auto value2 = op_input.receive<std::shared_ptr<ValueData>>("in2").value();
    HOLOGSCAN_LOG_INFO("Middle message received (count: {})", count_++);
    HOLOGSCAN_LOG_INFO("Middle message value1: {}", value1->data());
    HOLOGSCAN_LOG_INFO("Middle message value2: {}", value2->data()); // Multiply the values by the multiplier parameter
    value1->data(value1->data() * multiplier_);
    value2->data(value2->data() * multiplier_);
    op_output.emit(value1, "out1");
    op_output.emit(value2, "out2");
} private:
    int count_ = 1;
    Parameter<int> multiplier_; };
class PingRxOp : public Operator { public:
    HOLOGSCAN_OPERATOR_FORWARD_ARGS(PingRxOp) PingRxOp() = default; void setup(OperatorSpec& spec) override {
        spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {});
    } void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext&) override {
        auto value_vector = op_input.receive<std::vector<std::shared_ptr<ValueData>>>("receivers").value();
        HOLOGSCAN_LOG_INFO("Rx message received (count: {}, size: {})", count_++,
            value_vector.size());
        HOLOGSCAN_LOG_INFO("Rx message value1: {}", value_vector[0]->data());
        HOLOGSCAN_LOG_INFO("Rx message value2: {}", value_vector[1]->data());
    private:
        Parameter<std::vector<TSpec>*>& receivers_; int count_ = 1; } };

namespace holoscan::ops { class App : public holoscan::Application { public:
        void compose() override {
            using namespace holoscan;
            auto tx = make_operator<ops::PingTxOp>("tx");
            auto mx = make_operator<ops::PingMiddleOp>("mx", Arg("multiplier", 3));
            auto rx = make_operator<ops::PingRxOp>("rx");
            add_flow(tx, mx, {{"out1", "in1"}, {{"out2", "in2"}}});
            add_flow(mx, rx, {{"out1"}, "receivers"}, {{"out2"}, "receivers"});
        }
    };
    int main(int argc, char** argv) {
        auto app = holoscan::make_application<MyPingApp>();
        app->run();
        return 0;
    }
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](image)

If your parameter is of a custom type, you must register that type and provide a YAML encoder/decoder, as documented under

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.

```cpp
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:

```cpp
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.

```cpp
// ... 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`.

```cpp
// ... 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.

```cpp
// ... class PingRxOp : public holoscan::ops::GXFOperator {
public:
    HOLOSCANS_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 {
            HOLOSCANS_LOG_ERROR("Invalid message type: ", in_any_type.name());
            return;
        }
    }
};
```

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 `<a href="api/cpp/classholoscan_1_1Tensor.html#_CPPv4N8holoscan6TensorE">holoscan::Tensor</a>` class is a wrapper around the `DLManagedTensorCtx` struct holding a `DLManagedTensor` object. As such, it provides a primary interface to
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*>`:

```cpp
Parameter<std::vector<IOSpec*>> receivers_
```

and calling

```cpp
spec.param(receivers_, "receivers", "Input Receivers", "List of input receivers.", {});
```

as done for `PingRxOp` in the native operator ping example.

Listing 4 `examples/ping_multi_port/cpp/ping_multi_port.cpp`

```cpp
class PingRxOp : public Operator { public:
    HOLOSCAN_OPERATOR_FORWARD_ARGS(PingRxOp) PingRxOp() = default; void
    setup(OperatorSpec& spec) override { spec.param(receivers_, "receivers", "Input
    Receivers", "List of input receivers.", {}); }
    void compute(InputContext& op_input, ExecutionContext& context) override {
        auto value_vector = op_input.receive<
            std::vector<ValueData>>("receivers");
        HOLOSCAN_LOG_INFO("Rx message received (count: {}, size: {})", count_++,
            value_vector.size());
        HOLOSCAN_LOG_INFO("Rx message value1: {}", value_vector[0]->data());
        HOLOSCAN_LOG_INFO("Rx message value2: {}", value_vector[1]->data());
    } private:
    size_t count_;
};
```
Then, once the following configuration is provided in the `compose()` method, the `PingRxOp` will receive two inputs on the `receivers` port.

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`:

```
# 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.

```cmake
# 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.

  ```cmake
  # 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.

**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
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

```cpp
// Holoscan Operator implementation below will wrap the
// MyRecorder GXF Codelet shown here.
```
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 6 `my_recorder_op.hpp`

```cpp
#include "holoscan/core/gxf/gxf_operator.hpp" namespace holoscan::ops { class MyRecorderOp : public holoscan::ops::GXFOperator { public:
    HOLOSCAN_OPERATOR_FORWARD_ARGS_SUPER(MyRecorderOp,
    holoscan::ops::GXFOperator) MyRecorderOp() = default; const char* gxf_typename() const override { return "MyRecorder"; } void setup(OperatorSpec& spec) override;
    void initialize() override; private: Parameter<holoscan::IOSpec*> receiver_; Parameter<std::shared_ptr<holoscan::Resource>> my_serializer_; Parameter<std::string> directory_; Parameter<std::string> basename_; Parameter<bool> flush_on_tick_; } } // namespace holoscan::ops
```

### Listing 7 Parameter declarations in `gxf_extensions/my_recorder/my_recorder.hpp`

```cpp
nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::Receiver>> receiver_;
    nvidia::gxf::Parameter<nvidia::gxf::Handle<nvidia::gxf::EntitySerializer>>
    my_serializer_; nvidia::gxf::Parameter<std::string> directory_;
    nvidia::gxf::Parameter<std::string> basename_; nvidia::gxf::Parameter<bool>
    flush_on_tick_;
```

Comparing the `MyRecorderOp` holoscan parameter to the `MyRecorder` gxf codelet:
We then need to implement the following functions:

- **const char* gxf_typename() 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 8 my_recorder_op.cpp

```
#include "./my_recorder_op.hpp" #include "holoscan/core/fragment.hpp" #include "holoscan/core/gxf/entity.hpp" #include "holoscan/core/operator_spec.hpp" #include "holoscan/core/resources/gxf/video_stream_serializer.hpp" namespace holoscan::ops { void MyRecorderOp::setup(OperatorSpec& spec) { auto& input = spec.input<holoscan::gxf::Entity>("input"); // Above is same with the following two lines (a default condition is assigned to the input port if not specified): // // auto& input = spec.input<holoscan::gxf::Entity>("input") // .condition(ConditionType::kMessageAvailable, Arg("min_size") = 1); spec.param(receiver_, "receiver", "Entity receiver", "Receiver channel to log", &input); spec.param(my_serializer_, "serializer", "Entity serializer", "Serializer for serializing input data"); spec.param(directory_, "out_directory", "Output directory
```

nvidia::gxf::Parameter

nvidia::gxf::Handle&lt;nvidia::gxf::Receiver&

or

nvidia::gxf::Handle&lt;nvidia::gxf::Transmitter

std::shared_ptr&lt;holoscan::Resource

example: T is nvidia::gxf::EntitySerializer
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 `Condition`s 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 9 A part of `apps/my_recorder_app_gxf/my_recorder_gxf.yaml`

```yaml
name: recorder components
- name: input type: nvidia::gxf::DoubleBufferReceiver
  - name: allocator type: nvidia::gxf::UnboundedAllocator
  - name: component_serializer type: nvidia::gxf::StdComponentSerializer
    parameters: allocator: allocator
  - name: entity_serializer type: nvidia::gxf::StdEntitySerializer
    component_serializers: [component_serializer] - type: MyRecorder
    parameters: receiver: input serializer: entity_serializer
    out_directory: "/tmp"
    basename: "tensor_out" - type: nvidia::gxf::MessageAvailableSchedulingTerm
    parameters: receiver: input min_size: 1
```

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In the same way, if we had a Transmitter GXF component, we would have the following statements (Please see available constants for holoscan::ConditionType):

```cpp
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 10 my_recorder_op.cpp**

```cpp
#include "./my_recorder_op.hpp" #include "holoscan/core/fragment.hpp" #include "holoscan/core/gxf/entity.hpp" #include "holoscan/core/operator_spec.hpp"
#include "holoscan/core/resources/gxf/video_stream_serializer.hpp" namespace holoscan::ops { void MyRecorderOp::setup(OperatorSpec& spec) {...} void MyRecorderOp::initialize() { // Set up prerequisite parameters before calling GXFOperator::initialize() auto frag = fragment(); auto serializer = frag->make_resource<holoscan::StdEntitySerializer>("serializer");
add_arg(Arg("serializer") = serializer); GXFOperator::initialize(); } } // 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 11 Another part of apps/my_recorder_app_gxf/my_recorder_gxf.yaml**

```yaml
```
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.

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.

Note

The Holoscan C++ API already provides the

```
<a href="api/cpp/classholoscan_1_1StdEntitySerializer.html#_CPPv4N8holoscan19StdEntitySerializer"><a

```
class which wraps the `nvidia::gxf::StdEntitySerializer` GXF component, used here as `serializer`.

"tensor_out" - type: nvidia::gxf::MessageAvailableSchedulingTerm parameters:
receiver: input min_size: 1
A `holoscan::TensorMap` class defined as a specialization of `holoscan::Map` for the `holoscan::Tensor` type.

Consider the following example, where `GXFSendTensorOp` and `GXFReceiveTensorOp` are GXF operators, and where `ProcessTensorOp` is a C++ native operator:

![Diagram showing tensor interoperability between C++ native operator and GXF operator](image)

**Fig. 16 Supporting Tensor Interoperability**

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`:

```cpp
void compute(InputContext& op_input, OutputContext& op_output, ExecutionContext& context) override {
  // The type of 'in_message' is 'holoscan::TensorMap'.
  auto in_message = op_input.receive<holoscan::TensorMap>("in").value();
  // the type of out_message is TensorMap
  TensorMap out_message;
  for
```
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.

**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.

**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. 18 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 13 The basic structure of a Holoscan Operator (Python)

```python
from holoscan.core import (ExecutionContext, InputContext, Operator, OperatorSpec, OutputContext, )
class MyOp(Operator):
    def __init__(self, fragment, *args, **kwargs):
        super().__init__(fragment, *args, **kwargs)
        def setup(self, spec: OperatorSpec):
            pass
def start(self):
        pass
def stop(self):
    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 \texttt{self.spec} class member), and calls \texttt{setup} method so that Operator’s \texttt{spec} property holds the operator’s specification. (See the source code for more details.)

Since the \texttt{setup} method can be called multiple times with other \texttt{OperatorSpec} object (e.g., to enumerate the operator’s description), in the \texttt{setup} method, a user shouldn’t initialize something in the \texttt{Operator} object. Such initialization needs to be done in \texttt{initialize} method. The \texttt{__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.

\textbf{Creating a custom operator (Python)}

To create a custom operator in Python it is necessary to create a subclass of \texttt{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 \texttt{numpy.ndarray} or is something that can be cast to one via (\texttt{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.

\textbf{Code Snippet: examples/numpy_native/convolve.py}

Listing 14 examples/numpy_native/convolve.py

```python
import os from holoscan.conditions import CountCondition from holoscan.core import Application, Operator, OperatorSpec from holoscan.logger import LogLevel, set_log_level import numpy as np class SignalGeneratorOp(Operator): """Generate a time-varying impulse. Transmits an array of zeros with a single non-zero entry of a specified `height`. The position of the non-zero entry shifts to the right (in a periodic fashion) each time `compute` is called. Parameters

- `fragment` : holoscan.core.Fragment The Fragment (or Application) the operator belongs to.
- `height` : number The height of the signal impulse.
- `size` : number The total number of samples in the generated 1d signal.
- `dtype` : numpy.dtype or str The data type of the generated signal.

```
  def __init__(self, fragment, *args, height=1, size=10,
               dtype=np.int32, **kwargs): self.count = 0 self.height = height self.dtype = dtype self.size = size super().__init__(fragment, *args, **kwargs) def setup(self, spec:
```
```
context): # single sample wide impulse at a time-varying position
signal = np.zeros((self.size,), dtype=self.dtype)
signal[self.count % signal.size] = signal.size
self.count += 1
op_output.emit(signal, "signal")

class ConvolveOp(Operator):
    """Apply convolution to a tensor. Convolves an input signal with a "boxcar" (i.e. "rect") kernel.
Parameters

- width (number): The width of the boxcar kernel used in the convolution.
- unit_area (bool, optional): Whether or not to normalize the convolution kernel to unit area. If False, all samples have amplitude one and the dtype of the kernel will match that of the signal. When True the sum over the kernel is one and a 32-bit floating point data type is used for the kernel.
"""
    def __init__(self, fragment, *args, width=4, unit_area=False, **kwars):  
        super().__init__(fragment, *args, **kwars)
        self.count = 0
        self.width = width
        self.unit_area = unit_area
        super().__init__(fragment, *args, **kwars)

    def setup(self, spec: OperatorSpec):  
        spec.input("signal_in")
        spec.output("signal_out")

    def compute(self, op_input, op_output, context):  
        signal = op_input.receive("signal_in")
        assert isinstance(signal, np.ndarray)
        if self.unit_area:
            kernel = np.full((self.width,), 1/self.width, dtype=np.float32)
        else:
            kernel = np.ones((self.width,), dtype=signal.dtype)
        convolved = np.convolve(signal, kernel, mode='same')

    def compose(self):  
        signal_generator = SignalGeneratorOp(  
            self, CountCondition(self, count=24), name="generator",  
            **self.kwars("generator"))
        convolver = ConvolveOp(self, name="conv", **self.kwars("convolve"))
        printer = PrintSignalOp(self, name="printer")
        return

    def main(config_file):  
        app = ConvolveApp()  
        if the --config command line argument was provided, it will override this config_file`
        app.config(config_file)  
        app.run()  

Code Snippet: examples/numpy_native/convolve.yaml
In this application, three native Python operators are created: \texttt{SignalGeneratorOp}, \texttt{ConvolveOp} and \texttt{PrintSignalOp}. The \texttt{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. \texttt{ConvolveOp} performs a 1D convolution with a boxcar (i.e. rect) function of a specified width. \texttt{PrintSignalOp} just prints the received signal to the terminal.

As covered in more detail below, the inputs to each operator are specified in the \texttt{setup()} method of the operator. Then inputs are received within the \texttt{compute} method via \texttt{op\_input\_receive()} and outputs are emitted via \texttt{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 \texttt{SignalGeneratorOp} operator above, we added three keyword arguments in the operator's \texttt{\_init\_} method, used inside the \texttt{compose()} method of the operator to adjust its behavior:

```python
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)
```

\[\text{Note}\]

As an alternative closer to C++, these parameters can be added through the

\(\text{Listing 15} \ examples/\text{numpy\_native/convolve.yaml}\)

\[
\text{signal\_generator: height: 1 size: 20 dtype: int32 convolve: width: 4 unit\_area: false}
\]
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.

```python
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)).
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: # 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 class supports both DLPack and NumPy’s array interface (and ) 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:
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**

```python
Listing 16 examples/native_operator/python/ping.py

class PingRxOp(Operator): """Simple receiver operator. This operator has: input: "receivers" This is an example of a native operator that can dynamically have any number of inputs connected to is "receivers" port. """
    def __init__(self, fragment, *args, **kwargs):
        self.count = 1 # Need to call the base class constructor last
        super().__init__(fragment, *args, **kwargs)
    def setup(self, spec: OperatorSpec):
        spec.param("receivers", kind='receivers')
    def compute(self, op_input, op_output, context):
        values = op_input.receive("receivers")
        print(f"Rx message received (count: {self.count}, size:{len(values)})")
        self.count += 1
        print(f"Rx message value1: {values[0].data}")
        print(f"Rx message value2: {values[1].data}")

        self.add_flow(mx, rx, {"out1", "receivers"}, {"out2", "receivers"})
```

and in the `compose` method of the application, two parameters are connected to this "receivers" port:

```python
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.

**Python wrapping of a C++ operator**
Wrapping an operator developed in C++ for use from Python is covered in a separate section on creating C++ operator Python bindings.

**Tip**

As of Holoscan 2.1, there is a `<a href="api/python/holoscan_python_api_operators.html#holoscan.operators.GXFClass">class which can be used to easily wrap an existing GXF codelet from Python without having to first write an underlying C++ wrapper class for it. Similarly there is now also a `<a href="api/python/holoscan_python_api_resources.html">class which allows a GXF Component to be used as a Holoscan resource from Python applications. A detailed example of how to use each of these is provided for Python applications in the `examples/import_gxf_components` folder.

**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:
The following code shows how to implement \texttt{ImageProcessingOp}'s \texttt{compute()} method as a Python native operator communicating with C++ operators:


def compute(self, op_input, op_output, context):
    in_message = op_input.receive("input_tensor")
    sigma = (self.sigma, self.sigma, 0)
    out_message = dict()
    for key, value in in_message.items():
        print(f"message received (count:{self.count})")
        self.count += 1
        cp_array = cp.asarray(value)
        cp_array = ndi.gaussian_filter(cp_array, sigma)
        out_message[key] = cp_array
    op_output.emit(out_message, "output_tensor")

- The \texttt{op_input.receive()} method call returns a \texttt{dict} object.
- The \texttt{holoscan.core.Tensor} object is converted to a CuPy array by using \texttt{cupy.asarray()} method call.
- The CuPy array is used as an input to the \texttt{ndi.gaussian_filter()} function call with a parameter \texttt{sigma}. The result of the \texttt{ndi.gaussian_filter()} function call is a CuPy array.
- Finally, a new \texttt{dict} object is created, \texttt{out_message}, to be sent to the next operator with \texttt{op_output.emit()}. The CuPy array, \texttt{cp_array}, is added to it where the key is the tensor name. CuPy arrays do not have to explicitly be converted to a \texttt{holoscan.core.Tensor} object first since they implement a DLPack (and \texttt{__cuda__array_interface__}) interface.

\begin{itemize}
\item \texttt{op_input.receive()} method call returns a \texttt{dict} object.
\item \texttt{holoscan.core.Tensor} object is converted to a CuPy array by using \texttt{cupy.asarray()} method call.
\item The CuPy array is used as an input to the \texttt{ndi.gaussian_filter()} function call with a parameter \texttt{sigma}. The result of the \texttt{ndi.gaussian_filter()} function call is a CuPy array.
\item Finally, a new \texttt{dict} object is created, \texttt{out_message}, to be sent to the next operator with \texttt{op_output.emit()}. The CuPy array, \texttt{cp_array}, is added to it where the key is the tensor name. CuPy arrays do not have to explicitly be converted to a \texttt{holoscan.core.Tensor} object first since they implement a DLPack (and \texttt{__cuda__array_interface__}) interface.
\end{itemize}
You can add multiple tensors to a single `dict` object, as in the example below:

Operator sending a message:

```python
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:

```python
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

```
<ahref="api/python/holoscan_python_api_operators.html#holoscan.operators.Holov”, where the name for each tensor maps to the names of the tensors in the

```
<ahref="api/python/holoscan_python_api_gxf.html#holoscan.gxf.Entity">Entity</a>
```
(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

```
Advanced Topics

Further customizing inputs and outputs

This section complements the information above on basic input and output port configuration given separately in the C++ and Python operator creation guides. The concepts described here are the same for either the C++ or Python APIs.

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.

<table>
<thead>
<tr>
<th>Transmitted object</th>
<th>Received Object</th>
</tr>
</thead>
<tbody>
<tr>
<td>holoscan.Tensor</td>
<td>holoscan.Tensor</td>
</tr>
<tr>
<td>dict of array-like</td>
<td>dict of holoscan.Tensor</td>
</tr>
<tr>
<td>host array-like object (with</td>
<td>numpy.ndarray</td>
</tr>
<tr>
<td><strong>array_interface</strong></td>
<td></td>
</tr>
<tr>
<td>device array-like object (with</td>
<td>cupy.ndarray</td>
</tr>
<tr>
<td><strong>cuda_array_interface</strong>)</td>
<td></td>
</tr>
</tbody>
</table>

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.
By default, both the input and output ports of an Operator will use a double-buffered queue that has a capacity of one message and a policy that is set to error if a message arrives while the queue is already full. A single `MessageAvailableCondition` (C++ / Python) condition is automatically placed on the operator for each input port so that the `compute` method will not be called until a single message is available at each port. Similarly each output port has a `DownstreamMessageAffordableCondition` (C++ / Python) condition that does not let the operator call `compute` until any operators connected downstream have space in their receiver queue for a single message. These default conditions ensure that messages never arrive at a queue when it is already full and that a message has already been received whenever the `compute` method is called. These default conditions make it relatively easy to connect a pipeline where each operator calls compute in turn, but may not be suitable for all applications. This section covers how the default behavior can be overridden on request.

To override the properties of the queue used for a given port, the `connector` (C++ / Python) method can be used as shown in the example below. This example also shows how the `condition` (C++ / Python) method can be used to change the condition type placed on the Operator by a port. In general, when an operator has multiple conditions, they are AND combined, so the conditions on all ports must be satisfied before an operator can call `compute`.

To learn more about overriding connectors and/or conditions there is a `multi_branch_pipeline` example which overrides default conditions to allow two branches of a pipeline to run at different frame rates. There is also an example of increasing the queue sizes available in this Python queue policy test application.

**Note**

Overriding operator port properties is an advanced topic. Developers may want to skip this section until they come across a case where the default behavior is not sufficient for their application.
Logging

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

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
Ingested Tab Module

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.

```bash
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](#).

**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:
You can modify this default by calling `set_log_pattern()` ([C++](https://github.com/nvidia/holoscan) / [Python](https://docs.python.org/3/library/logging.html)) 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

**Ingested Tab Module**

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:

```
```
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 `Logger::set_log_pattern()` api mentioned above.

**Precedence of Logger Level and Logger Format**

The `HOLOSCAN_LOG_LEVEL` environment variable takes precedence and overrides the application settings, such as `Logger::set_log_level()` (C++ / Python).

When `HOLOSCAN_LOG_LEVEL` is set, it determines the logging level. If this environment variable is unset, the application settings are used if they are available. Otherwise, the SDK's default logging level of INFO is applied.

Similarly, the `HOLOSCAN_LOG_FORMAT` environment variable takes precedence and overrides the application settings, such as `Logger::set_log_pattern()` (C++ / Python).

When `HOLOSCAN_LOG_FORMAT` is set, it determines the logging format. If this environment variable is unset, the application settings are used if they are available. Otherwise, the SDK's default logging format depending on the current log level (FULL format for DEBUG and TRACE log levels. DEFAULT format for other log levels) is applied.

**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

---

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**Python API** should use the built-in `<a href="https://docs.python.org/3/howto/logging.html">logging</a>` module to log messages. The user needs to configure the logger before use (`logging.basicConfig(level=logging.INFO)`):

```python
>>> import logging
>>> logger = logging.getLogger("main")
>>> logger.info('hello')
>>> logging.basicConfig(level=logging.INFO)
>>> logger.info('hello')
INFO:main:hello
```
Debugging

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.

Visual Studio Code Integration

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.

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.
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.

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.

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.

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 the 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.

**Debugging an Application Crash**

This section outlines the procedures for debugging an application crash.

**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.

```bash
$ ./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.

```bash
$ ls coredump* coredump_ping_simple_2160275
```
The core dump file can be debugged using GDB by executing

gdb &lt;application&gt; &lt;coredump_file&gt;.

$ 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
&lt;http://gnu.org/licenses/gpl.html&gt; 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: &lt;https://www.gnu.org/software/gdb/bugs/&gt;. Find the GDB
manual and other documentation resources online at:
&lt;http://www.gnu.org/software/gdb/documentation/&gt;. 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] 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 \texttt{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
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] 4
./examples/ping_distributed/cpp/ping_distributed(+0x103d2b) [0x5651dafc7d2b] 5
```
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(+0x126660)
 4  /usr/lib/x86_64-linux-gnu/libc.so.6(+0x94ac3)
 5  /usr/lib/x86_64-linux-gnu/libstdc++.so.6(+0xdc253)
 6  /workspace/holoscan-sdk/build-debug-x86_64/lib/libholoscan_core.so.1(_ZN8holoscan3gxf10GXFWrapper4tickEv+0x13d)
```

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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 &lt;thread_id&gt;` 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" 0x00007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29 2 Thread 0x7f9992731000 (LWP 2127093) "ping_distribute" 0x00007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29 3 Thread 0x7f9991f30000 (LWP 2127094) "ping_distribute" 0x00007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29 4 Thread 0x7f9991f2f000 (LWP 2127095) "ping_distribute" 0x00007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29 5 Thread 0x7f9990ec000 (LWP 2127096) "cuda-EvtHandlr" 0x00007f9994a96612 in __libc_pause () at
```
It's evident that thread ID 13 is responsible for the segmentation fault (LWP 2127097).

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 0x00007f9994a9642f in __GI___wait4 (pid=pid@entry=2127631, 
stat_loc=stat_loc@entry=0x7f995e3dd3c, options=options@entry=0, 
usage=usage@entry=0x0) at ../sysdeps/unix/sysv/linux/wait4.c:30 #1
0x00007f9994a963ab in __GI___waitpid (pid=pid@entry=2127631, 
stat_loc=stat_loc@entry=0x7f995e3dd3c, 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
```
Under the backtrace of thread 13, you will find:
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 ... Thread 13 (Thread 0x7f995e3e3000 (LWP 2127105) "ping_distribute"): #0 0x00007f9994a9642f 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 0x00007f9994a96612 in __libc_pause () at ../sysdeps/unix/sysv/linux/pause.c:29 ...
```

### 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.

**pdb example**

The following command initiates a Python application within a `pdb` session:

```bash
#8 <signal handler called> #9 holoscan::ops::PingTensorTxOp::compute (this=0x559716f26fa0, op_output=..., context=...) at ../examples/ping_distributed/cpp/ping_distributed_ops.cpp:129
```
For more details, please refer to the `pdb_main()` method in `test_pytracing.py`.

**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.
Using `pprofile`

`pprofile` is a line-granularity, thread-aware deterministic and statistic pure-python profiler.

```bash
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 | 0.00% | 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 | 0.00% | 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 | 0.00% | 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 | 0.00% | 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 | 0.00% | 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.

```plaintext
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.

```plaintext
python python/tests/system/test_pytracing.py yappi -s multithread | grep test_pytracing.py
```

Using **profile/cProfile**

profile/cProfile is a deterministic profiling module for Python programs.

```plaintext
python -m cProfile python/tests/system/test_pytracing.py 2>&1 | grep test_pytracing.py
```

## Executing a single test case

```plaintext
python python/tests/system/test_pytracing.py profile
```

```plaintext
1 0.001 0.001 0.107 0.107 test_pytracing.py:1(<module>) 1 0.000 0.000 0.000 0.000 0.000 test_pytracing.py:104(setup) 1 0.000 0.000 0.000 0.000 0.000 test_pytracing.py:109(initialize) 1 0.000 0.000 0.000 0.000 0.000 test_pytracing.py:112(start) 1 0.000 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
```
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") ...
Measuring Code Coverage

The Holoscan SDK provides support for measuring code coverage using Coverage.py.

```bash
python -m pip install coverage coverage erase coverage run
test_pytracing.py coverage report
test_pytracing.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:

```bash
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`:

```bash
python -m trace --trackcalls python/tests/system/test_pytracing.py | grep test_pytracing
```

```bash
... 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.main -> test_pytracing.PingRxOp.compute test_pytracing.main ->
test_pytracing.PingRxOp.initialize test_pytracing.main ->
test_pytracing.main -> test_pytracing.PingTxOp.compute test_pytracing.main ->
test_pytracing.PingTxOp.initialize test_pytracing.main ->
```
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
```
Writing Python bindings for a C++ Operator

For convenience while maintaining high performance, operators written in C++ can be wrapped in Python. The general approach uses Pybind11 to concisely create bindings that provide a familiar, Pythonic experience to application authors.

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 between each operator.

The existing Pybind11 documentation is good and it is recommended to read at least the basics on wrapping functions and classes. The material below will assume some basic familiarity with Pybind11, covering the details of creation of the bindings of a C++ Operator. As a concrete example, we will cover creation of the bindings for ToolTrackingPostprocessorOp from Holohub as a simple case and then highlight additional scenarios that might be encountered.

Tip

There are several examples of bindings on Holohub in the operators folder. The subset of operators that provide a Python wrapper on top of a C++ implementation will have any C++ headers and sources together in a common folder, while any corresponding Python bindings will be in a “python” subfolder (see the tool_tracking_postprocessor folder layout, for example).
Tutorial: binding the ToolTrackingPostprocessorOp class

Creating a PyToolTrackingPostprocessorOp trampoline class

In a C++ file (tool_tracking_postprocessor.cpp in this case), create a subclass of the C++ Operator class to wrap. The general approach taken is to create a Python-specific class that provides a constructor that takes a Fragment*, an explicit list of the operators parameters with default values for any that are optional, and an operator name. This constructor needs to setup the operator as done in Fragment::make_operator, so that it is ready for initialization by the GXF executor. We use the convention of prepending “Py” to the C++ class name for this (so, PyToolTrackingPostprocessorOp in this case):

Listing 18 tool_tracking_post_processor/python/tool_tracking_post_processor.cpp

class PyToolTrackingPostprocessorOp : public ToolTrackingPostprocessorOp {
    public: /* Inherit the constructors */ using ToolTrackingPostprocessorOp::ToolTrackingPostprocessorOp; // Define a constructor that fully initializes the object. PyToolTrackingPostprocessorOp( Fragment* fragment, const py::args& args, std::shared_ptr<Allocator> device_allocator, std::shared_ptr<Allocator> host_allocator, float min_prob = 0.5f, std::vector<std::vector<float>> overlay_img_colors = VIZ_TOOL_DEFAULT_COLORS, std::shared_ptr<holoscan::CudaStreamPool> cuda_stream_pool = nullptr, const std::string& name = "tool_tracking_postprocessor") :
    ToolTrackingPostprocessorOp(ArgList{Arg("device_allocator", device_allocator), Arg("host_allocator", host_allocator), Arg("min_prob", min_prob), Arg("overlay_img_colors", overlay_img_colors), }) { if (cuda_stream_pool) { this->add_arg(Arg("cuda_stream_pool", cuda_stream_pool)); }
    add_positional_condition_and_resource_args(this, args); name_ = name; fragment_ = fragment; spec_ = std::make_shared<OperatorSpec>(fragment); setup(*spec_.get());
};
This constructor will allow providing a Pythonic experience for creating the operator. Specifically, the user can pass Python objects for any of the parameters without having to explicitly create any `holoscan::Arg` objects via `holoscan.core.Arg`. For example, a standard Python float can be passed to `min_prob` and a Python `list[list[float]]` can be passed for `overlay_img_colors` (Pybind11 handles conversion between the C++ and Python types). Pybind11 will also take care of conversion of a Python allocator class like `holoscan.resources.UnboundedAllocator` or `holoscan.resources.BlockMemoryPool` to the underlying C++ `std::shared_ptr<holoscan::Allocator>` type. The arguments `device_allocator` and `host_allocator` correspond to required Parameters of the C++ class and can be provided from Python either positionally or via keyword while the Parameters `min_prob` and `overlay_img_colors` will be optional keyword arguments. `cuda_stream_pool` is also optional, but is only conditionally passed as an argument to the underlying `ToolTrackingPostprocessorOp` constructor when it is not a `nullptr`.

- For all operators, the first argument should be `Fragment* fragment` and is the fragment the operator will be assigned to. In the case of a single fragment application (i.e. not a distributed application), the fragment is just the application itself.

- An (optional) `const std::string& name` argument should be provided to enable the application author to set the operator’s name.

- The `const py::args& args` argument corresponds to the `*args` notation in Python. It is a set of 0 or more positional arguments. It is not required to provide this in the function signature, but is recommended in order to enable passing additional conditions such as a `CountCondition` or `PeriodicCondition` as positional arguments to the operator. The call below to

  ```c++
  add_positional_condition_and_resource_args(this, args);
  ```

  uses a helper function defined in `operator_util.hpp` to add any `Condition` or `Resource` arguments found in the list of positional arguments.

- The other arguments all correspond to the various parameters (`holoscan::Parameter`) that are defined for the C++ `ToolTrackingPostProcessorOp`
class.

- All other parameters except `cuda_stream_pool` are passed directly in the argument list to the parent `ToolTrackingPostProcessorOp` class. The parameters present on the C++ operator can be seen in its header [here](#) with default values taken from the `setup` method of the source file [here](#). Note that `CudaStreamHandler` is a utility that will add a parameter of type `Parameter<std::shared_ptr<CudaStreamPool>>`. 

- The `cuda_stream_pool` argument is only conditionally added if it was not `nullptr` (Python’s `None`). This is done via

```cpp
if (cuda_stream_pool) {
    this->add_arg(Args{"cuda_stream_pool",
                     cuda_stream_pool});
}
```

instead of passing it as part of the `holoscan::ArgList` provided to the `ToolTrackingPostprocessorOp` constructor call above.

The remaining lines of the constructor

```cpp
name_ = name; fragment_ = fragment; spec_ = std::make_shared<OperatorSpec>(fragment); setup(*spec_.get());
```

are required to properly initialize it and should be the same across all operators. These correspond to equivalent code within the `Fragment::make_operator` method.

### Defining the Python module

For this operator, there are no other custom classes aside from the operator itself, so we define a module using `PYBIND11_MODULE` as shown below with only a single class definition. This is done in the same `tool_tracking_postprocessor.cpp` file where we defined the `PyToolTrackingPostprocessorOp` trampoline class.

The following header will always be needed.
Here, we typically also add defined the \texttt{py} namespace as a shorthand for \texttt{pybind11} and indicated that we will use the \texttt{a} literal (it provides a shorthand notation when defining keyword arguments).

Often it will be necessary to include the following header if any parameters to the operator involve C++ standard library containers such as \texttt{std::vector} or \texttt{std::unordered_map}.

```cpp
#include <pybind11/pybind11.h>
namespace py = pybind11;
using pybind11::literals::operator""_a;
```

This allows pybind11 to cast between the C++ container types and corresponding Python types (Python \texttt{dict} / C++ \texttt{std::unordered_map}, for example).

Listing 19 \texttt{tool\_tracking\_post\_processor/python/tool\_tracking\_post\_processor.cpp}

```cpp
PYBIND11_MODULE(_tool_tracking_postprocessor, m) {
  py::class_<ToolTrackingPostprocessorOp, PyToolTrackingPostprocessorOp, Operator, std::shared_ptr<ToolTrackingPostprocessorOp>>(m,
  "ToolTrackingPostprocessorOp",
  doc::ToolTrackingPostprocessorOp::doc_ToolTrackingPostprocessorOp_python)
    .def(py::init<Fragment*, const py::args& args, std::shared_ptr<Allocator>,
             std::shared_ptr<Allocator>, float, std::vector<std::vector<float>>,
             std::shared_ptr<holoscan::CudaStreamPool>, const std::string&>(),
             "fragment"_a,
             "device_allocator"_a, "host_allocator"_a, "min_prob"_a = 0.5f,
             "overlay_img_colors"_a = VIZ_TOOL_DEFAULT_COLORS,
             "cuda_stream_pool"_a = py::none(),
             "name"_a = "tool\_tracking\_postprocessor"s,
             doc::ToolTrackingPostprocessorOp::doc_ToolTrackingPostprocessorOp_python);
} // PYBIND11_MODULE NOLINT
```

\begin{itemize}
  \item \textbf{Note}
\end{itemize}
The order in which the classes are specified in the `py::class_` template call is important and should follow the convention shown here. The first in the list is the C++ class name (`ToolTrackingPostprocessorOp`) and second is the `PyToolTrackingPostprocessorOp` class we defined above with the additional, explicit constructor. We also need to list the parent `Operator` class so that all of the methods such as `start`, `stop`, `compute`, `add_arg`, etc. that were already wrapped for the parent class don't need to be redefined here.

The single `.def(py::init<...`) call wraps the `PyToolTrackingPostprocessorOp` constructor we wrote above. As such, the argument types provided to `py::init<...` must exactly match the order and types of arguments in that constructor’s function signature. The subsequent arguments to `def` are the names and default values (if any) for the named arguments in the same order as the function signature. Note that the `const py::args& args` (Python `*args`) argument is not listed as these are positional arguments that don’t have a corresponding name. The use of `py::none()` (Python’s `None`) as the default for `cuda_stream_pool` corresponds to the `nullptr` in the C++ function signature. The “_a” literal used in the definition is enabled by the following declaration earlier in the file.

The final argument to `.def` here is a documentation string that will serve as the Python docstring for the function. It is optional and we chose here to define it in a separate header as described in the next section.

**Documentation strings**
Prepare documentation strings (const char*) for your python class and its parameters.

**Note**

Below we use a `PYDOC` macro defined in the SDK and available in HoloHub as a utility to remove leading spaces. In this case, the documentation code is located in header file `tool_tracking_post_processor_pydoc.hpp`, under a custom `holoscan::doc::ToolTrackingPostprocessorOp` namespace. None of this is required, you just need to make any documentation strings available for use as an argument to the `py::class_` constructor or method definition calls.

Listing 20 `tool_tracking_post_processor/python/tool_tracking_post_processor_pydoc.hpp`

```cpp
#include "../macros.hpp"
namespace holoscan::doc {
    namespace ToolTrackingPostprocessorOp { // PyToolTrackingPostprocessorOp Constructor
        PYDOC(ToolTrackingPostprocessorOp_python, R"doc( Operator performing post-processing for the endoscopy tool tracking demo. **==Named Inputs==** in: nvidia::gxf::Entity containing multiple nvidia::gxf::Tensor Must contain input tensors named "probs", "scaled_coords" and "binary_masks" that correspond to the output of the LSTMTensorRtInferenceOp as used in the endoscopy tool tracking example applications. **==Named Outputs==** out_coords : nvidia::gxf::Tensor Coordinates tensor, stored on the host (CPU). out_mask : nvidia::gxf::Tensor Binary mask tensor, stored on device (GPU). Parameters: fragment : Fragment The fragment that the operator belongs to. device_allocator : "holoscan.resources.Allocator" Output allocator used on the device side. host_allocator : "holoscan.resources.Allocator" Output allocator used on the host side. min_prob : float, optional Minimum probability (in range [0, 1]). Default value is 0.5. overlay_img_colors : sequence of sequence of float, optional Color of the image overlays, a list of RGB values with components between 0 and 1. The default value is a qualitative colormap with a sequence of 12 colors. cuda_stream_pool : "holoscan.resources.CudaStreamPool" instance to allocate CUDA streams.
        )"doc
    }
}
```
We tend to use NumPy-style docstrings for parameters, but also encourage adding a custom section at the top that describes the input and output ports and what type of data is expected on them. This can make it easier for developers to use the operator without having to inspect the source code to determine this information.

**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\`).

**Warning**

The name chosen for \`CPP_CMAKE_TARGET\` must also be used (along with a preceding underscore) as the module name passed as the first argument to the \`PYBIND11_MODULE\` macro in the bindings.

Note that there is an initial underscore prepended to the name. This is the naming convention used for the shared library and corresponding \`__init__.py\` file that will be generated by the \`pybind11_add_holohub_module\` helper function above.
If the name is specified incorrectly, the build will still complete, but at application run time an `ImportError` such as the following would occur:

```
[command] python3
/workspace/holohub/applications/endoscopy_tool_tracking/python/endoscopy
--data /workspace/holohub/data/endoscopy Traceback (most recent call last):
"/workspace/holohub/applications/endoscopy_tool_tracking/python/endoscopy
line 38, in <module> from holohub.tool_tracking_postprocessor
import ToolTrackingPostprocessorOp File
"/workspace/holohub/build/python/lib/holohub/tool_tracking_postprocessor/__
line 19, in <module> from ._tool_tracking_postprocessor import
ToolTrackingPostprocessorOp
ImportError: dynamic module does not define module export function
(PyInit__tool_tracking_postprocessor)
```

### Importing the class in Python

Ingested Tab Module

### Additional Examples

In this section we will cover other cases that may occasionally be encountered when writing Python bindings for operators.

### Optional arguments

It is also possible to use `std::optional` to handle optional arguments. The `ToolTrackingProcessorOp` example above, for example, has a default argument defined in the spec for `min_prob`.

```cpp
constexpr float DEFAULT_MIN_PROB = 0.5f; // ... spec.param( min_prob_,
"min_prob", "Minimum probability", "Minimum probability.", DEFAULT_MIN_PROB);
```
In the tutorial for ToolTrackingProcessorOp above we reproduced this default of 0.5 in both the PyToolTrackingProcessorOp constructor function signature as well as the Python bindings defined for it. This carries the risk that the default could change at the C++ operator level without a corresponding change being made for Python.

An alternative way to define the constructor would have been to use std::optional as follows where now that min_prob and overlay_img_colors are optional, they are only conditionally added as an argument to ToolTrackingPostprocessorOp when they have a value. If this approach is used, the Python bindings for the constructor should be updated to use py::none() as the default as follows:

```cpp
// Define a constructor that fully initializes the object. PyToolTrackingPostprocessorOp(
Fragment* fragment, const py::args& args, std::shared_ptr<Allocator> device_allocator, std::shared_ptr<Allocator> host_allocator, std::optional<float> min_prob = 0.5f, std::optional<std::vector<std::vector<float>>> overlay_img_colors = VIZ_TOOL_DEFAULT_COLORS, std::shared_ptr<holoscan::CudaStreamPool> cuda_stream_pool = nullptr, const std::string& name =
"tool_tracking_postprocessor") :
ToolTrackingPostprocessorOp(ArgList{Arg("device_allocator", device_allocator),
Arg("host_allocator", host_allocator), }) { if (cuda_stream_pool) { this->
->add_arg(Arg("cuda_stream_pool", cuda_stream_pool)); } if (min_prob.has_value()) {
this->add_arg(Arg("min_prob", min_prob.value())); } if
(overlay_img_colors.has_value()) { this->add_arg(Arg("overlay_img_colors",
overlay_img_colors.value())); } add_positional_condition_and_resource_args(this,
args); name_ = name; fragment_ = fragment; spec_ =
std::make_shared<OperatorSpec>(fragment); setup(*spec_.get()); }
```

where now that min_prob and overlay_img_colors are optional, they are only conditionally added as an argument to ToolTrackingPostprocessorOp when they have a value. If this approach is used, the Python bindings for the constructor should be updated to use py::none() as the default as follows:

```python
@def(py::init<Fragment*, const py::args& args, std::shared_ptr<Allocator>,
std::shared_ptr<Allocator>, float, std::vector<std::vector<float>>,
std::shared_ptr<holoscan::CudaStreamPool>, const std::string&>(), "fragment"_a,
"device_allocator"_a, "host_allocator"_a, "min_prob"_a = py::none(),
"overlay_img_colors"_a = py::none(), "cuda_stream_pool"_a = py::none(), "name"_a =
```
C++ enum parameters as arguments

Sometimes, operators may use a Parameter with an enum type. It is necessary to wrap the C++ enum to be able to use it as a Python type when providing the argument to the operator.

The built-in `holoscan::ops::AJASourceOp` is an example of a C++ operator that takes a `enum Parameter` (an `NTV2Channel` enum).

The enum can easily be wrapped for use from Python via `py::enum_` as shown here. It is recommended in this case to follow Python's convention of using capitalized names in the enum.

(Advanced) Custom C++ classes as arguments

Sometimes it is necessary to accept a custom C++ class type as an argument in the operator’s constructor. In this case additional interface code and bindings will likely be necessary to support the type.

A relatively simple example of this is the `DataVecMap` type used by `InferenceProcessorOp`. In that case, the type is a structure that holds an internal `std::map<std::string, std::vector<std::string>>`. The bindings are written to accept a Python dict (`py::dict`) and a helper function is used within the constructor to convert that dictionary to the corresponding C++ `DataVecMap`.

A more complicated case is the use of a `InputSpec` type in the `HolovizOp` bindings. This case involves creating Python bindings for classes `InputSpec` and `View` as well as a couple of enum types. To avoid the user having to build a `list[holoscan.operators.HolovizOp.InputSpec]` directly to pass as the `tensors` argument, an additional Python wrapper class was defined in the `__init__.py` to allow passing a simple Python dict for the `tensors` argument and any corresponding InputSpec classes are automatically created in its constructor before calling the underlying Python bindings class.

Customizing the C++ types a Python operator can emit or receive
In some instances, users may wish to be able to have a Python operator receive and/or emit a custom C++ type. As a first example, suppose we are wrapping an operator that emits a custom C++ type. We need any downstream native Python operators to be able to receive that type. By default the SDK is able to handle the needed C++ types for built in operators like `std::vector<holoscan::ops::HolovizOp::InputSpec>`.

The SDK provides an `EmitterReceiverRegistry` class that 3rd party projects can use to register receiver and emitter methods for any custom C++ type that needs to be handled. To handle a new type, users should implement an `emitter_receiver<T>` struct for the desired type as in the example below. We will first cover the general steps necessary to register such a type and then cover where some steps may be omitted in certain simple cases.

**Step 1: define emitter_receiver::emit and emitter_receiver::receive methods**

Here is an example for the built-in `std::vector<holoscan::ops::HolovizOp::InputSpec>` used by `HolovizOp` to define the input specifications for its received tensors.

```cpp
#include <holoscan/python/core/emitter_receiver_registry.hpp>
namespace py = pybind11; namespace holoscan {
    /* Implements emit and receive capability for the HolovizOp::InputSpec type. */
    template <> struct emitter_receiver<
      std::vector<holoscan::ops::HolovizOp::InputSpec>> {
        static void emit(py::object& data, const std::string& name,
          PyOutputContext& op_output) {
          auto input_spec = data.cast<std::vector<holoscan::ops::HolovizOp::InputSpec>>();
          py::gil_scoped_release release;
          op_output.emit<std::vector<holoscan::ops::HolovizOp::InputSpec>>(input_spec,
            name.c_str()); return; }
        static py::object receive(std::any result, const std::string& name,
          PyInputContext& op_input) { HOLOSCAN_LOG_DEBUG("py_receive: std::vector<HolovizOp::InputSpec> case"); // can directly return vector<InputSpec>
          auto specs = std::any_cast<std::vector<holoscan::ops::HolovizOp::InputSpec>> (result);
          py::object py_specs = py::cast(specs); return py_specs; };
    }
}
```

This `emitter_receiver` class defines a `receive` method that takes a `std::any` message and casts it to the corresponding Python `list[HolovizOp::InputSpec]` object. Here the `pybind11::cast` call works because we have wrapped the `HolovizOp::InputSpec` class here.
Similarly, the emit method takes a pybind11::object (of type list[HolovizOp.InputSpec]) and casts it to the corresponding C++ type, std::vector&lt;holoscan::ops::HolovizOp::InputSpec&gt;. The conversion between std::vector and a Python list is one of Pybind11’s built-in conversions (available as long as "pybind11/stl.h" has been included).

The signature of the emit and receive methods must exactly match the case shown here.

**Step 2: Create a register_types method for adding custom types to the EmitterReceiverRegistry.**

The bindings in this operators module, should define a method named register_types that takes a reference to an EmitterReceiverRegistry as its only argument. Within this function there should be a call to EmitterReceiverRegistry::add_emitter_receiver for each type that this operator wished to register. The HolovizOp defines this method using a lambda function

```cpp
// Import the emitter/receiver registry from holoscan.core and pass it to this function to
// register this new C++ type with the SDK. m.def("register_types", []
(EmitterReceiverRegistry& registry) {
    registry.add_emitter_receiver<std::vector<holoscan::ops::HolovizOp::InputSpec> >("std::vector<HolovizOp::InputSpec>"s); // array camera pose object
    registry.add_emitter_receiver<std::shared_ptr<std::array<float, 16>>>("std::shared_ptr<std::array<float, 16>>"s); // Pose3D camera pose object
    registry.add_emitter_receiver<std::shared_ptr<nvidia::gxf::Pose3D>>("std::shared_ptr<nvidia::gxf::Pose3D>"s); // camera_eye_input, camera_look_at_input, camera_up_input registry.add_emitter_receiver<std::array<float, 3>>("std::array<float, 3>"s); });
```

Here the following line registers the std::vector&lt;holoscan::ops::HolovizOp::InputSpec&gt; type that we wrote an emitter_receiver for above.

```cpp
registry.add_emitter_receiver<std::vector<holoscan::ops::HolovizOp::InputSpec> >("std::vector<HolovizOp::InputSpec>"s);
```
Internally the registry stores a mapping between the C++ `std::type_index` of the type specified in the template argument and the `emitter_receiver` defined for that type. The second argument is a string that the user can choose which is a label for the type. As we will see later, this label can be used from Python to indicate that we want to emit using the `emitter_receiver::emit` method that was registered for a particular label.

**Step 3: In the init.py file for the Python module defining the operator call register_types**

To register types with the core SDK, we need to import the `io_type_registry` class (of type `EmitterReceiverRegistry`) from `holoscan.core`. We then pass that class as input to the `register_types` method defined in step 2 to register the 3rd party types with the core SDK.

```python
from holoscan.core import io_type_registry from ._holoviz import register_types as _register_types # register methods for receiving or emitting list[HolovizOp.InputSpec] and camera pose types _register_types(io_type_registry)
```

where we chose to import `register_types` with an initial underscore as a common Python convention to indicate it is intended to be “private” to this module.

**In some cases steps 1 and 3 as shown above are not necessary.**

When creating Python bindings for an Operator on Holohub, the `pybind11_add_holohub_module.cmake` utility mentioned above will take care of autogenerating the `__init__.py` as shown in step 3, so it will not be necessary to manually create it in that case.

For types for which Pybind11’s default casting between C++ and Python is adequate, it is not necessary to explicitly define the `emitter_receiver` class as shown in step 1. This is true because there are a couple of default implementations for `emitter_receiver&lt;T&gt;` and `emitter_receiver&lt;std::shared_ptr&lt;T&gt;&gt;` that already cover common cases. The default emitter_receiver works for the `std::vector&lt;HolovizOp::InputSpec&gt;` type shown above, which is why the code shown for illustration there is not found within the operator’s bindings. In that case one could immediately implement `register_types` from step 2 without having to explicitly create an `emitter_receiver` class.
An example where the default emitter_receiver would not work is the custom one defined by the SDK for `pybind11::dict`. In this case, to provide convenient emit of multiple tensors via passing a `dict[holoscan::Tensor]` to `op_output.emit` we have special handling of Python dictionaries. The dictionary is inspected and if all keys are strings and all values are tensor-like objects, a single C++ `nvidia::gxf::Entity` containing all of the tensors as an `nvidia::gxf::Tensor` is emitted. If the dictionary is not a tensor map, then it is just emitted as a shared pointer to the Python dict object. The emitter_receiver implementations used for the core SDK are defined in `emitter_receivers.hpp`. These can serve as a reference when creating new ones for additional types.

**Runtime behavior of emit and receive**

After registering a new type, receive of that type on any input port will automatically be handled. This is because due to the strong typing of C++, any `op_input.receive` call in an operator's `compute` method can find the registered receive method that matches the `std::type_index` of the type and use that to convert to a corresponding Python object.

Because Python is not strongly typed, on emit, the default behavior remains emitting a shared pointer to the Python object itself. If we instead want to emit a C++ type, we can pass a 3rd argument to `op_output.emit` to specify the name that we used when registering the types via the `add_emitter_receiver` call as above.

**Example of emitting a C++ type**

As a concrete example, the SDK already registers `std::string` by default. If we wanted, for instance, to emit a Python string as a C++ `std::string` for use by a downstream operator that is wrapping a C++ operator expecting string input, we would add a 3rd argument to the `op_output.emit` call as follows

```plaintext
# emit a Python filename string on port "filename_out" using registered type "std::string"
my_string = "filename.raw" op_output.emit(my_string, "filename_out", "std::string")
```

This specifies that the `emit` method that converts to C++ `std::string` should be used instead of the default behavior of emitting the Python string.
Another example would be to emit a Python `List[float]` as a `std::array<float, 3>` parameter as input to the `camera_eye`, `camera_look_at` or `camera_up` input ports of `HolovizOp`.

```python
op_output.emit([0.0, 1.0, 0.0], "camera_eye_out", "std::array<float, 3>")
```

Only types registered with the SDK can be specified by name in this third argument to `emit`.

**Table of types registered by the core SDK**

The list of types that are registered with the SDK's `EmitterReceiverRegistry` are given in the table below.

<table>
<thead>
<tr>
<th>C++ Type</th>
<th>name in the EmitterReceiverRegistry</th>
</tr>
</thead>
<tbody>
<tr>
<td>holoscan::Tensor</td>
<td>“holoscan::Tensor”</td>
</tr>
<tr>
<td>std::shared_ptr</td>
<td>“PyObject”</td>
</tr>
<tr>
<td>std::string</td>
<td>“std::string”</td>
</tr>
<tr>
<td>pybind11::dict</td>
<td>“pybind11::dict”</td>
</tr>
<tr>
<td>holoscan::gxf::Entity</td>
<td>“holoscan::gxf::Entity”</td>
</tr>
<tr>
<td>holoscan::PyEntity</td>
<td>“holoscan::PyEntity”</td>
</tr>
<tr>
<td>nullptr_t</td>
<td>“nullptr_t”</td>
</tr>
<tr>
<td>CloudPickleSerializedObject</td>
<td>“CloudPickleSerializedObject”</td>
</tr>
<tr>
<td>std::array</td>
<td>“std::array ”</td>
</tr>
<tr>
<td>std::shared_ptr &gt;</td>
<td>“std::shared_ptr &gt;”</td>
</tr>
<tr>
<td>std::shared_ptr</td>
<td>“std::shared_ptr ”</td>
</tr>
<tr>
<td>std::vector</td>
<td>“std::vector ”</td>
</tr>
</tbody>
</table>

**Note**

There is no requirement that the registered name match any particular convention. We generally used the C++ type as the name to
The sections above explain how a `register_types` function can be added to bindings to expand this list. It is also possible to get a list of all currently registered types, including those that have been registered by any additional imported 3rd party modules. This can be done via

```python
from holoscan.core import io_type_registry
print(io_type_registry.registered_types())
```
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.

Operators

The operators below are defined under the holoscan::ops namespace for C++ and CMake, and under the holoscan.operators module in Python.

<table>
<thead>
<tr>
<th>Class</th>
<th>CMake target/lib</th>
<th>Documentation</th>
</tr>
</thead>
<tbody>
<tr>
<td>AJASourceOp</td>
<td>aja</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>BayerDemosaicOp</td>
<td>bayer_demosaic</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>FormatConverterOp</td>
<td>format_converter</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>HolovizOp</td>
<td>holoviz</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>InferenceOp</td>
<td>inference</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>InferenceProcessorOp</td>
<td>inference_processor</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>PingRxOp</td>
<td>ping_rx</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>PingTxOp</td>
<td>ping_tx</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>SegmentationPostprocessorOp</td>
<td>segmentation_postprocessor</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>VideoStreamRecorderOp</td>
<td>video_stream_recorder</td>
<td>C++ / Python</td>
</tr>
<tr>
<td>VideoStreamReplayerOp</td>
<td>video_stream_replayer</td>
<td>C++ / Python</td>
</tr>
</tbody>
</table>
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:

Ingested Tab Module

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.

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:

- `gxf_holoscan_wrapper`
- `ucx_holoscan`

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.
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.

---

HoloHub

Visit the HoloHub repository to find a collection of additional Holoscan operators and extensions.
Visualization

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.

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).

**Image Layers**

**Supported Image Formats**

**Geometry Layers**

A geometry layer is used to draw 2d or 3d geometric primitives. 2d primitives are points, lines, line strips, rectangles, ovals or text and are defined with 2d coordinates (x, y). 3d primitives are points, lines, line strips or triangles and are defined with 3d coordinates (x, y, z).

Coordinates start with (0, 0) in the top left and end with (1, 1) in the bottom right for 2d primitives.

**ImGui Layers**

**Note**
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.

```cpp
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.

**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.

Ingested Tab Module

**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 ... 1] instead of the Vulkan [-1 ... 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.

Ingested Tab Module

**Camera**

When rendering 3d geometry using a geometry layer with 3d primitives or using a depth map layer the camera properties can either be set by the application or interactively changed by the user.

To interactively change the camera, use 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)

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.

Configure a display for exclusive use

Enable exclusive display in Holoviz

The name of the display can either be the EDID name as displayed in the NVIDIA Settings, or the output name provided by `xrandr` or `hwinfo --monitor`.

Tip

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.
Reading the framebuffer

The rendered frame buffer can be read back. This is useful when doing offscreen rendering or running Holoviz in a headless environment.

**Note**

Reading the depth buffer is not supported when using the Holoviz operator.

Ingested Tab Module

Holoviz operator

Class documentation

C++

Python

Examples

There are multiple examples both in Python and C++ showing how to use various features of the Holoviz operator.

Holoviz module

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.

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.

**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()`.

```cpp
#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. 20 Holoviz example app

**API**

Holoviz module API

**Examples**

There are multiple examples showing how to use various features of the Holoviz module.
Inference

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.

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.

<table>
<thead>
<tr>
<th>x86</th>
<th>input_on_cuda</th>
<th>output_on_cuda</th>
<th>transmit_on_cuda</th>
<th>infer_on_cpu</th>
</tr>
</thead>
<tbody>
<tr>
<td>Supported values for <code>trt</code></td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
<td>false</td>
</tr>
<tr>
<td>Supported values for <code>torch</code></td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
</tr>
<tr>
<td>Supported values for <code>onnxrt</code></td>
<td>false</td>
<td>false</td>
<td>true or false</td>
<td>true or false</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Aarch64</th>
<th>input_on_cuda</th>
<th>output_on_cuda</th>
<th>transmit_on_cuda</th>
<th>infer_on_cpu</th>
</tr>
</thead>
<tbody>
<tr>
<td>Supported values for <code>trt</code></td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
<td>false</td>
</tr>
<tr>
<td>Supported values for torch</td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
<td>true or false</td>
</tr>
<tr>
<td>---------------------------</td>
<td>---------------</td>
<td>---------------</td>
<td>---------------</td>
<td>---------------</td>
</tr>
<tr>
<td>Supported values for onnxr</td>
<td>false</td>
<td>false</td>
<td>true or false</td>
<td>true</td>
</tr>
</tbody>
</table>

- **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 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 minutes 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.

- `temporal_map`: Temporal inferencing is enabled if `temporal_map` is populated in the parameter set.
  - Each entry in `temporal_map` has a unique keyword representing the model (same as used in `model_path_map` and `pre_processor_map`), and frame delay as the value. Frame delay represents the frame count that are skipped by the operator in doing the inference for that particular model. A model with the value of 1, is inferred per frame. A model with a value of 10 is inferred for every 10th frame coming into the operator, which is the 1st frame, 11th frame, 21st frame and so on. Additionally, the operator will transmit the last inferred result for all the frames that are not inferred. For example, a model with a value of 10 will be inferred at 11th frame and from 12th to 20th frame, the result from 11th frame is transmitted.
  - If the `temporal_map` is absent in the parameter set, all models are inferred for all the frames.
  - All models are not mandatory in the `temporal_map`. The missing models are inferred per frame.
- Temporal map based 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.

<table>
<thead>
<tr>
<th>Feature</th>
<th>Supported values</th>
</tr>
</thead>
<tbody>
<tr>
<td>Data type</td>
<td>float32, int32, int8</td>
</tr>
<tr>
<td>Inference Backend</td>
<td>trt, torch, onnxrt</td>
</tr>
<tr>
<td>Inputs per model</td>
<td>Multiple</td>
</tr>
<tr>
<td>Outputs per model</td>
<td>Multiple</td>
</tr>
<tr>
<td>GPU(s) supported</td>
<td>Multi-GPU on same PCIE network</td>
</tr>
<tr>
<td>Tensor data dimension</td>
<td>2, 3, 4</td>
</tr>
<tr>
<td>Model Type</td>
<td>All onnx or all torchscript or all trt engine type or a combination of torch and trt engine</td>
</tr>
</tbody>
</table>

- 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.

**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.

```plaintext
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: true infer_on_cpu: false enable_fp16: false input_on_cuda: true output_on_cuda: true transmit_on_cuda: true is_engine_path: false
```

**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.

```json
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.

```json
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.
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.

- Single model inference with input/output data on Host.

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.
Data from inference operator to the next connected operator in the application is transmitted via the host.

- Multi model inference with a single backend.

- Multi model inference with sequential inference.
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"]
```

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"]
```
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.

```plaintext
backend_map: "model_1_unique_identifier": "trt" "model_2_unique_identifier": "torch" "model_3_unique_identifier": "torch"
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"
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.

### 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.

```cpp
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).

```cpp
// 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.

```cpp
// 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.

```cpp
// 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.
Inference execution

```c
// Extract relevant data from input, and update inference specifications
gxf_result_t stat = HoloInfer::get_data_per_model(...);
```

- Transmit inferred data:

```c
// 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_);
```

```c
// 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.

3. **Event-Based Scheduler**: The event-based scheduler is also a multi-thread scheduler, but as the name indicates it is event-based rather than polling based. Instead of having a thread that constantly polls for the execution readiness of each operator, it instead waits for an event to be received which indicates that an operator is ready to execute. The event-based scheduler will have a lower latency than using the multi-thread scheduler with a long polling interval (\texttt{check_recession_period_ms}), but without the high CPU usage seen for a multi-thread scheduler with a very short polling interval.

It is essential to select the appropriate scheduler for the use case at hand to ensure optimal performance and efficient resource utilization. Since most parameters of the schedulers overlap, it is easy to switch between them to test which may be most performant for a given application.
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.
Multithread Scheduler

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 multi-thread scheduler uses a dedicated thread to poll the status of operators and schedule any that are ready to execute. This will lead to high CPU usage by this polling thread when `check_recession_period_ms` is close to 0.

- 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.

Event-Based Scheduler

The event-based scheduler is also a multi-thread scheduler, but it is event-based rather than polling based. As such, there is no `check_recession_period_ms` parameter, and this scheduler will not have the high CPU usage that can occur when polling at a short interval. Instead, the scheduler only wakes up when an event is received indicating that an operator is ready to execute. The parameters of this scheduler are a superset of the parameters available for the [GreedyScheduler](#) (described above). Only the parameters unique to the event-based 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.
Conditions

The following table shows various states of the scheduling status of an operator:

<table>
<thead>
<tr>
<th>Scheduling Status</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>NEVER</td>
<td>Operator will never execute again</td>
</tr>
<tr>
<td>READY</td>
<td>Operator is ready for execution</td>
</tr>
<tr>
<td>WAIT</td>
<td>Operator may execute in the future</td>
</tr>
<tr>
<td>WAIT_TIME</td>
<td>Operator will be ready for execution after specified duration</td>
</tr>
<tr>
<td>WAIT_EVENT</td>
<td>Operator is waiting on an asynchronous event with unknown time interval</td>
</tr>
</tbody>
</table>

**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

```
<a href="../api/python/holoscan_python_api_conditions.html#module-holoscan.conditions">Python</a>
```

**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 terms reaches NEVER state. The priority of various states during AND combine follows the order NEVER, WAIT_EVENT, WAIT, WAIT_TIME, and READY.

**MessageAvailableCondition**

An operator associated with MessageAvailableCondition (C++ / Python) 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.

**DownstreamMessageAffordableCondition**

The `DownstreamMessageAffordableCondition` (C++ / Python) 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).

**CountCondition**

An operator associated with `CountCondition` (C++ / Python) 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.

**BooleanCondition**

An operator associated with `BooleanCondition` (C++ / Python) 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.

Ingested Tab Module

**PeriodicCondition**
An operator associated with PeriodicCondition (C++ / Python) 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.

**AsynchronousCondition**

AsynchronousCondition (C++ / Python) 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.

<table>
<thead>
<tr>
<th>AsynchronousEventState</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>READY</td>
<td>Init state, first execution of compute() method is pending</td>
</tr>
<tr>
<td>WAIT</td>
<td>Request to async service yet to be sent, nothing to do but wait</td>
</tr>
<tr>
<td>EVENT_WAITING</td>
<td>Request sent to an async service, pending event done notification</td>
</tr>
<tr>
<td>EVENT_DONE</td>
<td>Event done notification received, operator ready to be ticked</td>
</tr>
<tr>
<td>EVENT_NEVER</td>
<td>Operator does not want to be executed again, end of execution</td>
</tr>
</tbody>
</table>

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. As for all of the condition types, the condition type can be used with any of the schedulers.
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).

Allocate

**UnboundedAllocator**

An allocator that uses dynamic host or device memory allocation without an upper bound. This allocator does not take any user-specified parameters. This memory pool is easy to use and is recommended for initial prototyping. Once an application is working, switching to a BlockMemoryPool instead may help provide additional performance.

**BlockMemoryPool**

This is a memory pool which provides a user-specified number of equally sized blocks of memory. Using this memory pool provides a way to allocate memory blocks once and reuse the blocks on each subsequent call to an Operator's `compute` method. This saves overhead relative to allocating memory again each time `compute` is called. For the built-in operators which accept a memory pool parameter, there is a section in it's API.
docstrings titled “Device Memory Requirements” which provides guidance on the
num_blocks and block_size needed for use with this memory pool.

- 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.

### 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.

### 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 `datetime.timedelta` from the Python API.
- The `sleep_until()` method sleeps until a specified target time in ns.

**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).

**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.

**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.

**DoubleBufferTransmitter**

This is the transmitter class used by output ports of operators within a fragment.

**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.

**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.

**DoubleBufferReceiver**

This is the receiver class used by input ports of operators within a fragment.
**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.
Analytics

Data Exporter API

The new Data Exporter C++ API (\texttt{DataExporter} and \texttt{CsvDataExporter}) is now available. This API can be used to export output from Holoscan applications to comma separated value (CSV) files for Holoscan Federated Analytics applications. \texttt{DataExporter} is a base class to support exporting Holoscan application output in different formats. \texttt{CsvDataExporter} is a class derived from \texttt{DataExporter} to support exporting Holoscan application output to CSV files.

The data root directory can be specified using the environment variable \texttt{HOLOSCAN_ANALYTICS_DATA_DIRECTORY}. If not specified, it defaults to the current directory. The data file name can be specified using the environment variable \texttt{HOLOSCAN_ANALYTICS_DATA_FILE_NAME}. If not specified, it defaults to the name \texttt{data.csv}. All the generated data will be stored inside a directory with the same name as the application name that is passed to the \texttt{DataExporter} constructor. On each run, a new directory inside the \texttt{\&lt;root_dir\&gt;\&lt;app_dir\&gt;} will be created and a new data file will be created inside it. Each new data directory will be named with the current timestamp. This timestamp convention prevents a given run of the application from overwriting any data stored previously by an earlier run of that same application.

Sample usage of the API

```
// Include Header #include <holoscan/core/analytics/csv_data_exporter.hpp> // Define CsvDataExporter member variable CsvDataExporter exporter // Initialize CsvDataExporter exporter("app_name", std::vector<std::string>({"column1", "column2", "column3"})) // Export data (typically called within an Operator::compute method) exporter.export_data(std::vector<std::string>({"value1", "value2", "value3"}))
```

Using Data Exporter API with DataProcessor
The Holoscan applications like Endoscopy Out of Body Detection uses Inference Processor operator (InferenceProcessorOp) to output the binary classification results. The DataProcessor class used by the inference processor operator (InferenceProcessorOp) is now updated to support writing output to CSV files which can then be used as input to analytics applications. Also any other application using InferenceProcessorOp can now export the binary classification output to the CSV files.

Below is an example application config using the new export operation:

```
inference_processor_op: process_operations: "out_of_body_inferred":
  ["export_results_to_csv, out_of_body_detection, In-body, Out-of-body, ConfidenceScore"] in_tensor_names: ["out_of_body_inferred"]
```

This will create a folder named out_of_body_detection in the specified root directory, creates another folder inside it with current timestamp on each run, and creates a .csv file with specified name and three columns - In-body, Out-of-body, Confidence Score. The lines in the data.csv file will look like:

```
In-body,Out-of-body,Confidence Score 1,0,0.972435 1,0,0.90207 1,0,0.897973 0,1,0.939281 0,1,0.948691 0,1,0.94994
```
Holoscan Application Package Specification (HAP)

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.

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.

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.

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.

### Definitions, Acronyms, Abbreviations

<table>
<thead>
<tr>
<th>Term</th>
<th>Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>ARM64</td>
<td>Or, AARCH64. See Wikipedia for details.</td>
</tr>
<tr>
<td>Container</td>
<td>See What’s a container?</td>
</tr>
<tr>
<td>Fragment</td>
<td>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.</td>
</tr>
<tr>
<td>Gigabytes (GiB)</td>
<td>A gibibyte (GiB) is a unit of measurement used in computer data storage that equals to 1,073,741,824 bytes.</td>
</tr>
<tr>
<td>HAP</td>
<td>Holoscan Application Package. A containerized application or service which is self-descriptive.</td>
</tr>
</tbody>
</table>
## 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.

### 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.

### 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.

**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.

**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.

**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.

**Compatible with Kubernetes**

- A HAP SHALL support deployment using Kubernetes.
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.

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`.

<table>
<thead>
<tr>
<th>Variable</th>
<th>Default</th>
<th>Format</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>HOLOSCAN_INPUT_PATH</td>
<td>/var/holoscan/input/</td>
<td>Folder Path</td>
<td>Path to the input folder for the Application.</td>
</tr>
<tr>
<td>HOLOSCAN_OUTPUT_PATH</td>
<td>/var/holoscan/output/</td>
<td>Folder Path</td>
<td>Path to the output folder for the Application.</td>
</tr>
<tr>
<td>HOLOSCAN_WORKDIR</td>
<td>/var/holoscan/</td>
<td>Folder Path</td>
<td>Path to the Application's working directory.</td>
</tr>
<tr>
<td>HOLOSCAN_MODEL_PATH</td>
<td>/opt/holoscan/models/</td>
<td>Folder Path</td>
<td>Path to the Application's models directory.</td>
</tr>
<tr>
<td>HOLOSCAN_CONFIG_PATH</td>
<td>/var/holoscan/app.yaml</td>
<td>File Path</td>
<td>Path to the Application's configuration file.</td>
</tr>
<tr>
<td>HOLOSCAN_APP_MANIFEST_PATH</td>
<td>/etc/holoscan/app.config</td>
<td>File Path</td>
<td>Path to the Application's configuration file.</td>
</tr>
<tr>
<td>HOLOSCAN_PKG_MANIFEST_PATH</td>
<td>/etc/holoscan/pkg.config</td>
<td>File Path</td>
<td>Path to the Application's configuration file.</td>
</tr>
<tr>
<td>HOLOSCAN_DOCS</td>
<td>/opt/holoscan/docs</td>
<td>Folder Path</td>
<td>Path to the folder containing application documentation and licenses.</td>
</tr>
<tr>
<td>HOLOSCAN_LOGS</td>
<td>/var/holoscan/logs</td>
<td>Folder Path</td>
<td>Path to the Application's logs.</td>
</tr>
</tbody>
</table>

**Architecture & Design**

**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.

**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.

**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**

<table>
<thead>
<tr>
<th>Name</th>
<th>Required</th>
<th>Default</th>
<th>Type</th>
<th>Format</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>apiVersion</td>
<td>No</td>
<td>0.0.0</td>
<td>string</td>
<td>semantic version</td>
<td>Version of the manifest file schema.</td>
</tr>
<tr>
<td>command</td>
<td>Yes</td>
<td>N/A</td>
<td>string</td>
<td>shell command</td>
<td>Shell command used to run the Application.</td>
</tr>
<tr>
<td>environment</td>
<td>No</td>
<td>N/A</td>
<td>object</td>
<td>object w/ name-value pairs</td>
<td>An object of name-value pairs that will be passed to the application during execution.</td>
</tr>
<tr>
<td>input</td>
<td>Yes</td>
<td>N/A</td>
<td>object</td>
<td>object</td>
<td>Data structure which provides information about Application</td>
</tr>
<tr>
<td>input.formats</td>
<td>Yes</td>
<td>N/A</td>
<td>array</td>
<td>array of objects</td>
<td>List of input data formats accepted by the Application.</td>
</tr>
<tr>
<td>--------------</td>
<td>-----</td>
<td>-----</td>
<td>-------</td>
<td>------------------</td>
<td>------------------------------------------------------</td>
</tr>
<tr>
<td>input.path</td>
<td>No</td>
<td>input/</td>
<td>string</td>
<td>relative file-system path</td>
<td>Folder path relative to the working directory from which the application will read inputs.</td>
</tr>
<tr>
<td>readiness</td>
<td>No</td>
<td>N/A</td>
<td>object</td>
<td>object</td>
<td>An object of name-value pairs that defines the readiness probe.</td>
</tr>
<tr>
<td>readiness.type</td>
<td>Yes</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td>Type of the probe: tcp, grpc, http-get or command.</td>
</tr>
<tr>
<td>readiness.command</td>
<td>Yes (when type is command)</td>
<td>N/A</td>
<td>array</td>
<td>shell command</td>
<td>Shell command and arguments in string array form.</td>
</tr>
<tr>
<td>readiness.port</td>
<td>Yes (when type is tcp, grpc, or http-get)</td>
<td>N/A</td>
<td>integer</td>
<td>number</td>
<td>The port number of readiness probe.</td>
</tr>
<tr>
<td>readiness.path</td>
<td>Yes (when type is http-get)</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td>HTTP path and query to access the readiness probe.</td>
</tr>
<tr>
<td>readiness.initialDelaySeconds</td>
<td>No</td>
<td>1</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds after the container has started before the readiness probe is initialized and performed.</td>
</tr>
<tr>
<td>readiness.periodSeconds</td>
<td>No</td>
<td>10</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds between performing the readiness probe.</td>
</tr>
<tr>
<td>readiness.timeoutSeconds</td>
<td>No</td>
<td>1</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds after which the probe times out.</td>
</tr>
<tr>
<td><strong>readiness.failurerTreshold</strong></td>
<td>No</td>
<td>3</td>
<td>integer</td>
<td>number</td>
<td>Number of retries to be performed before considering the application is unhealthy.</td>
</tr>
<tr>
<td>-------------------------------</td>
<td>----</td>
<td>---</td>
<td>---------</td>
<td>--------</td>
<td>-------------------------------------------------------------------</td>
</tr>
<tr>
<td><strong>liveness</strong></td>
<td>No</td>
<td>N/A</td>
<td>object</td>
<td>object</td>
<td>An object of name-value pairs that defines the liveness probe. Recommended for service applications.</td>
</tr>
<tr>
<td><strong>liveness.type</strong></td>
<td>Yes</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td>Type of the probe: tcp, grpc, http-get or command.</td>
</tr>
<tr>
<td><strong>liveness.command</strong></td>
<td>Yes (when type is command)</td>
<td>N/A</td>
<td>array</td>
<td>shell command</td>
<td>Shell command and arguments in string array form.</td>
</tr>
<tr>
<td><strong>liveness.port</strong></td>
<td>Yes (when type is tcp, grpc, or http-get)</td>
<td>N/A</td>
<td>integer</td>
<td>number</td>
<td>The port number of the liveness probe.</td>
</tr>
<tr>
<td><strong>liveness.path</strong></td>
<td>Yes (when type is http-get)</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td>HTTP path and query to access the liveness probe.</td>
</tr>
<tr>
<td><strong>liveness.initialDelaySeconds</strong></td>
<td>No</td>
<td>1</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds after the container has started before the liveness probe is initialized and performed.</td>
</tr>
<tr>
<td><strong>liveness.periodSeconds</strong></td>
<td>No</td>
<td>10</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds between performing the liveness probe.</td>
</tr>
<tr>
<td><strong>liveness.timeoutSeconds</strong></td>
<td>No</td>
<td>1</td>
<td>integer</td>
<td>number</td>
<td>Number of seconds after which the probe times out.</td>
</tr>
<tr>
<td>Parameter</td>
<td>Default Value</td>
<td>Type</td>
<td>Description</td>
<td></td>
<td></td>
</tr>
<tr>
<td>-------------------------</td>
<td>---------------</td>
<td>--------</td>
<td>-----------------------------------------------------------------------------</td>
<td></td>
<td></td>
</tr>
<tr>
<td>liveness</td>
<td>No</td>
<td>integer</td>
<td>Number of retries to be performed before considering the application is unhealthy.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>s.failureThreshold</td>
<td>N/A</td>
<td>object</td>
<td>Data structure which provides information about Application output.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>output</td>
<td>Yes</td>
<td>object</td>
<td>Number of retries to be performed before considering the application is unhealthy.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>output.format</td>
<td>N/A</td>
<td>object</td>
<td>Details about the format of the outputs produced by the application.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>output.path</td>
<td>N/A</td>
<td>string</td>
<td>Folder path relative to the working directory to which the application will write outputs.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>sdk</td>
<td>N/A</td>
<td>string</td>
<td>SDK used for the Application.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>sdkVersion</td>
<td>0.0.0</td>
<td>string</td>
<td>Version of the SDK used the Application.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>timeout</td>
<td>0</td>
<td>integer</td>
<td>The maximum number of seconds the application should execute before being timed out and terminated. Recommended for a single batch/execution type of applications.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>version</td>
<td>0.0.0</td>
<td>string</td>
<td>Version of the Application.</td>
<td></td>
<td></td>
</tr>
<tr>
<td>workingDirectory</td>
<td>/var/holoscan/</td>
<td>string</td>
<td>Folder, or directory, in which the application will be executed.</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

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`).

NVIDIA Holoscan SDK v2.1.0
- 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#inputformats`).
  - 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#outputformat`).
  - 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.

  o The Application Manifest SHALL define the type of probe to be performed (\texttt{/etc/holoscan/app.json\#liveness.type}).

    ▪ Possible values include tcp, grpc, http-get, and command.

  o The Application Manifest SHALL define the probe commands to execute when the type is command (\texttt{/etc/holoscan/app.json\#liveness.command}).

    ▪ The data structure is expected to be an array of strings.

  o The Application Manifest SHALL define the port to perform the liveness probe when the type is grpc, tcp, or http-get (\texttt{/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.)

  o The Application Manifest SHALL define the path to perform the liveness probe when the type is http-get (\texttt{/etc/holoscan/app.json\#liveness.path}).

    ▪ The value provided must be an absolute path (the first character is /).

  o The Application Manifest SHALL define the number of seconds after the container has started before the liveness probe is initiated. (\texttt{/etc/holoscan/app.json\#liveness.initialDelaySeconds}).

    ▪ The default value 0 SHALL be assumed when not provided.

  o The Application Manifest SHALL define how often to perform the liveness probe (\texttt{/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

<table>
<thead>
<tr>
<th>Name</th>
<th>Required</th>
<th>Default</th>
<th>Type</th>
<th>Format</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>apiVersion</td>
<td>No</td>
<td>0.0.0</td>
<td>string</td>
<td>semantic version</td>
<td>Version of the manifest file schema.</td>
</tr>
<tr>
<td><strong>applicationRoot</strong></td>
<td>Yes</td>
<td>/opt/holoscan/app/</td>
<td>string</td>
<td>absolute file-system path</td>
<td>Absolute file-system path to the folder which contains the Application</td>
</tr>
<tr>
<td><strong>modelRoot</strong></td>
<td>No</td>
<td>/opt/holoscan/models/</td>
<td>string</td>
<td>absolute file-system path</td>
<td>Absolute file-system path to the folder which contains the model(s).</td>
</tr>
<tr>
<td><strong>models</strong></td>
<td>No</td>
<td>N/A</td>
<td>array</td>
<td>array of objects</td>
<td>Array of objects which describe models in the package.</td>
</tr>
<tr>
<td><strong>models[*].name</strong></td>
<td>Yes</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td>Name of the model.</td>
</tr>
<tr>
<td><strong>models[*].path</strong></td>
<td>No</td>
<td>N/A</td>
<td>string</td>
<td>Relative file-system path</td>
<td>File-system path to the folder which contains the model that is relative to the value defined in <strong>modelRoot</strong>.</td>
</tr>
<tr>
<td><strong>resources</strong></td>
<td>No</td>
<td>N/A</td>
<td>object</td>
<td>object</td>
<td>Object describing resource requirements for the Application.</td>
</tr>
<tr>
<td><strong>resources.cpu</strong></td>
<td>No</td>
<td>1</td>
<td>decimal (2)</td>
<td>number</td>
<td>Number of CPU cores required by the Application or the Fragment.</td>
</tr>
<tr>
<td><strong>resources.cpuLimit</strong></td>
<td>No</td>
<td>N/A</td>
<td>decimal (2)</td>
<td>number</td>
<td>The CPU core limit for the Application or the Fragment. (1)</td>
</tr>
<tr>
<td><strong>resources.gpu</strong></td>
<td>No</td>
<td>0</td>
<td>decimal (2)</td>
<td>number</td>
<td>Number of GPU devices required by the Application or the Fragment.</td>
</tr>
<tr>
<td><strong>resources.gpuLimit</strong></td>
<td>No</td>
<td>N/A</td>
<td>decimal (2)</td>
<td>number</td>
<td>The GPU device limit for the Application or the Fragment. (1)</td>
</tr>
<tr>
<td><strong>resources.memory</strong></td>
<td>No</td>
<td>1Gi</td>
<td>string</td>
<td>memory size</td>
<td>The memory required by the Application or the Fragment.</td>
</tr>
<tr>
<td>Field</td>
<td>Required</td>
<td>Value</td>
<td>Type</td>
<td>Description</td>
<td></td>
</tr>
<tr>
<td>------------------------</td>
<td>----------</td>
<td>---------</td>
<td>----------</td>
<td>-----------------------------------------------------------------------------</td>
<td></td>
</tr>
<tr>
<td>resources.memoryLimit</td>
<td>No</td>
<td>N/A</td>
<td>string</td>
<td>memory size</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>The memory limit for the Application or the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.gpuMemory</td>
<td>No</td>
<td>N/A</td>
<td>string</td>
<td>memory size</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>The GPU memory required by the Application or the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.gpuMemoryLimit</td>
<td>No</td>
<td>N/A</td>
<td>string</td>
<td>memory size</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>The GPU memory limit for the Application or the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.sharedMemory</td>
<td>No</td>
<td>64Mi</td>
<td>string</td>
<td>memory size</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>The shared memory required by the Application or the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments</td>
<td>No</td>
<td>N/A</td>
<td>object</td>
<td>objects</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Nested objects which describe resources for a Multi-Fragment Application.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;</td>
<td>Yes</td>
<td>N/A</td>
<td>string</td>
<td>string</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Name of the fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.cpu</td>
<td>No</td>
<td>1</td>
<td>decimal (2)</td>
<td>number</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Number of CPU cores required by the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.cpuLimit</td>
<td>No</td>
<td>N/A</td>
<td>decimal (2)</td>
<td>number</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>The CPU core limit for the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.gpu</td>
<td>No</td>
<td>0</td>
<td>decimal (2)</td>
<td>number</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Number of GPU devices required by the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resource</td>
<td>required</td>
<td>limit</td>
<td>type</td>
<td>description</td>
<td></td>
</tr>
<tr>
<td>---------------------------------</td>
<td>----------</td>
<td>---------</td>
<td>-----------------</td>
<td>--------------------------------------------------------------------------------------------------</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.gpu Limit</td>
<td>No</td>
<td>N/A</td>
<td>decimal number</td>
<td>The GPU device limit for the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.memory</td>
<td>No</td>
<td>1Gi</td>
<td>string memory size</td>
<td>The memory required by the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.memoryLimit</td>
<td>No</td>
<td>N/A</td>
<td>string memory size</td>
<td>The memory limit for the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.gpu Memory</td>
<td>No</td>
<td>N/A</td>
<td>string memory size</td>
<td>The GPU memory required by the Fragment.</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.gpu MemoryLimit</td>
<td>No</td>
<td>N/A</td>
<td>string memory size</td>
<td>The GPU memory limit for the Fragment. (1)</td>
<td></td>
</tr>
<tr>
<td>resources.fragments.&lt;fragment-name&gt;.sharedMemory</td>
<td>No</td>
<td>64Mi</td>
<td>string memory size</td>
<td>The shared memory required by the Fragment.</td>
<td></td>
</tr>
<tr>
<td>version</td>
<td>No</td>
<td>0.0.0</td>
<td>semantic version</td>
<td>Version of the package.</td>
<td></td>
</tr>
</tbody>
</table>

[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 (\texttt{/etc/holoscan/pkg.json#resources.gpuLimit}).

- Memory requirements SHALL be denoted using decimal values followed by units (\texttt{/etc/holoscan/pkg.json#resources.memory}).
  - Supported units SHALL be mebibytes (\texttt{MiB}) and gibibytes (\texttt{GiB}).
  - Example: \texttt{1.5Gi, 2048Mi}

- Optional memory limits SHALL be denoted using decimal values followed by units (\texttt{/etc/holoscan/pkg.json#resources.memoryLimit}).
  - Supported units SHALL be mebibytes (\texttt{MiB}) and gibibytes (\texttt{GiB}).
  - Example: \texttt{1.5Gi, 2048Mi}

- GPU memory requirements SHALL be denoted using decimal values followed by units (\texttt{/etc/holoscan/pkg.json#resources.gpuMemory}).
  - Supported units SHALL be mebibytes (\texttt{MiB}) and gibibytes (\texttt{GiB}).
  - Example: \texttt{1.5Gi, 2048Mi}

- Optional GPU memory limits SHALL be denoted using decimal values followed by units (\texttt{/etc/holoscan/pkg.json#resources.gpuMemoryLimit}).
  - Supported units SHALL be mebibytes (\texttt{MiB}) and gibibytes (\texttt{GiB}).
  - Example: \texttt{1.5Gi, 2048Mi}

- Shared memory requirements SHALL be denoted using decimal values followed by units (\texttt{/etc/holoscan/pkg.json#resources.sharedMemory}).
  - Supported units SHALL be mebibytes (\texttt{MiB}) and gibibytes (\texttt{GiB}).
  - Example: \texttt{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.&lt;fragment-name&gt; 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.&lt;fragment-name&gt;.cpu).
Optional CPU limits for fragments SHALL be denoted using the decimal count of CPU cores (\[etc/holoscan/pkg.json#resources.fragments.&lt;fragment-name&gt;.cpuLimit\]).

GPU requirements for fragments SHALL be denoted using the decimal count of GPUs (\[etc/holoscan/pkg.json#resources.fragments.&lt;fragment-name&gt;.gpu\]).

Optional GPU limits for fragments SHALL be denoted using the decimal count of GPUs (\[etc/holoscan/pkg.json#resources.fragments.&lt;fragment-name&gt;.gpuLimit\]).

Memory requirements for fragments SHALL be denoted using decimal values followed by units (\[etc/holoscan/pkg.json#resources.fragments.&lt;fragment-name&gt;.memory\]).

- Supported units SHALL be mebibytes (\text{MiB}) and gibibytes (\text{GiB}).
- Example: \text{1.5Gi}, \text{2048Mi}

Optional memory limits for fragments SHALL be denoted using decimal values followed by units (\[etc/holoscan/pkg.json#resources.fragments.&lt;fragment-name&gt;.memoryLimit\]).

- Supported units SHALL be mebibytes (\text{MiB}) and gibibytes (\text{GiB}).
- Example: \text{1.5Gi}, \text{2048Mi}

GPU memory requirements for fragments SHALL be denoted using decimal values followed by units (\text{MiB}) and gibibytes (\text{GiB}).
Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).

Example: \texttt{1.5Gi, 2048Mi}

Optional GPU memory limits for fragments SHALL be denoted using decimal values followed by units (CuArray is not supported).

Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).

Example: \texttt{1.5Gi, 2048Mi}

Shared memory requirements for fragments SHALL be denoted using decimal values followed by units (CuArray is not supported).

Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).

Example: \texttt{1.5Gi, 2048Mi}

Optional shared memory limits for fragments SHALL be denoted using decimal values followed by units (CuArray is not supported).

Supported units SHALL be mebibytes (MiB) and gibibytes (GiB).

Example: \texttt{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, 2048

  - 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: 1024, -1.0, 3.14

  - When not provided, the default values of cpu=1, gpu=0, memory="1Gi", and sharedMemory="64Mi" will be assumed.

**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

**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.
### Table of Important Paths

<table>
<thead>
<tr>
<th>Path</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>/etc/holoscan/</code></td>
<td>HAP manifests and immutable configuration files.</td>
</tr>
<tr>
<td><code>/etc/holoscan/app.json</code></td>
<td>Application Manifest file.</td>
</tr>
<tr>
<td><code>/etc/holoscan/pkg.json</code></td>
<td>Package Manifest file.</td>
</tr>
<tr>
<td><code>/opt/holoscan/app/</code></td>
<td>Application code, scripts, and other files.</td>
</tr>
<tr>
<td><code>/opt/holoscan/models/</code></td>
<td>AI models. Each model should be in a separate sub-folder.</td>
</tr>
<tr>
<td><code>/opt/holoscan/docs/</code></td>
<td>Documentation, licenses, EULA, changelog, etc...</td>
</tr>
<tr>
<td><code>/var/holoscan/</code></td>
<td>Default working directory.</td>
</tr>
<tr>
<td><code>/var/holoscan/input/</code></td>
<td>Default input directory.</td>
</tr>
<tr>
<td><code>/var/holoscan/output/</code></td>
<td>Default output directory.</td>
</tr>
<tr>
<td><code>/var/run/holoscan/export/</code></td>
<td>Special case folder, causes the Script to export contents related to the app. (see: <a href="#">Manifest Export</a>)</td>
</tr>
<tr>
<td><code>/var/run/holoscan/export/app/</code></td>
<td>Special case folder, causes the Script to export the contents of <code>/opt/holoscan/app/</code> to the folder.</td>
</tr>
<tr>
<td><code>/var/run/holoscan/export/config/</code></td>
<td>Special case folder, causes the Script to export <code>/etc/holoscan/app.json</code> and <code>/etc/holoscan/pkg.json</code> to the folder.</td>
</tr>
<tr>
<td><code>/var/run/holoscan/export/models/</code></td>
<td>Special case folder, causes the Script to export the contents of <code>/opt/holoscan/models/</code> to the folder.</td>
</tr>
</tbody>
</table>

### Operating Environments

Holoscan SDK supports the following operating environments.
<table>
<thead>
<tr>
<th>Operating Environment Name</th>
<th>Characteristics</th>
</tr>
</thead>
<tbody>
<tr>
<td>AGX Devkit</td>
<td>Clara AGX devkit with RTX 6000 dGPU only</td>
</tr>
<tr>
<td>IGX Orin Devkit</td>
<td>Clara Holoscan devkit with A6000 dGPU only</td>
</tr>
<tr>
<td>IGX Orin Devkit - integrated GPU only</td>
<td>IGX Orin Devkit, iGPU only</td>
</tr>
<tr>
<td>IGX Orin Devkit with discrete GPU</td>
<td>IGX Orin Devkit, with RTX A6000 dGPU</td>
</tr>
<tr>
<td>Jetson AGX Orin Devkit</td>
<td>Jetson Orin Devkit, iGPU only</td>
</tr>
<tr>
<td>Jetson Orin Nano Devkit</td>
<td>Jetson Orin Nano Devkit, iGPU only</td>
</tr>
<tr>
<td>X86_64</td>
<td>dGPU only on Ubuntu 18.04 and 20.04</td>
</tr>
</tbody>
</table>
Holoscan CLI

holoscan - a command-line interface for packaging and running your Holoscan applications into HAP-compliant containers.

Synopsis

`holoscan [--help | -h] [--log-level | -l {DEBUG,INFO,WARN,ERROR,CRITICAL}] {package,run,version,nics}`

Positional Arguments

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

CLI-Wide Flags

[--help | -h]

Display detailed help.
[--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.

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)

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.

**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`):

```yaml
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

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:

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

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).

**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).

**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.

**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.

**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.

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 23 An example GXF Application YAML snippet

```yaml
%YAML 1.2 --- # other entities declared --- name: format_converter_entity components: - name: in_tensor type: nvidia::gxf::DoubleBufferReceiver - type: nvidia::gxf::MessageAvailableSchedulingTerm parameters: receiver: in_tensor min_size: 1 - name: out_tensor type: nvidia::gxf::DoubleBufferTransmitter - type: nvidia::gxf::DownstreamReceptiveSchedulingTerm parameters: transmitter: out_tensor min_size: 1 - name: pool type: nvidia::gxf::BlockMemoryPool parameters: storage_type: 1 block_size: 4919040 # 854 * 480 * 3 (channel) * 4 (bytes per pixel) num_blocks: 2 - name: format_converter_component type: nvidia::holoscan::formatconverter::FormatConverter parameters: in: in_tensor out: out_tensor out_tensor_name: source_video out_dtype: "float32" scale_min: 0.0 scale_max: 255.0 pool: pool --- # other entities declared --- components: - name: input_connection type: nvidia::gxf::Connection parameters: source: upstream_entity/output target: format_converter/in_tensor --- components: - name: output_connection type: nvidia::gxf::Connection parameters: source:```

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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 -&gt; format_converter_entity/in_tensor` and `format_converter_entity/out_tensor -&gt; 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.
Fig. 21 *Arrangement of components and entities in a Holoscan application*

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 `DoubleBufferReceiver` named `in_tensor`) and alerts the graph `Executor` that a message is available. This alert triggers `format_converter_component`.

- `DownstreamReceptiveSchedulingTerm` is a component that takes a `Transmitter` (in this case `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_converted_ent` 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.

**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 the `in_tensor` receiver queue, namely `format_converter_component`.

Listing 24 `MessageAvailableSchedulingTerm`

```
- type: nvidia::gxf::MessageAvailableSchedulingTerm
  parameters: receiver: in_tensor
  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 25 `DownstreamReceptiveSchedulingTerm`

```
- type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
  parameters: transmitter: out_tensor
  min_size: 1
```

If we were to draw the entity in Fig. 21 in greater detail it would look something like the following.
Fig. 22 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.

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.

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 de initialization.

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. 23**.

**Fig. 23 Sequence of method calls in the lifecycle of a Holoscan extension**

**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 \texttt{gxf\_index} file contains timing and sequence metadata that refer to the binary/tensor data held in the \texttt{gxf\_entities} file.

**Declare the Class That Will Implement the Extension Functionality**

The developer can create their Holoscan extension by extending the \texttt{Codelet} class, implementing the extension functionality by overriding the lifecycle methods, and defining the parameters the extension exposes at the application level via the \texttt{registerInterface} method. To define our recorder component we would need to implement some of the methods in the \texttt{Codelet}.

First, clone the Holoscan project from [here](https://github.com/nvidia-holoscan/holoscan-sdk.git) and create a folder to develop our extension such as under \texttt{gxf\_extensions/my\_recorder}.

**Tip**

Using Bash we create a Holoscan extension folder as follows.

```
```

In our extension folder, we create a header file \texttt{my\_recorder.hpp} with a declaration of our Holoscan component.

**Listing 26** \texttt{gxf\_extensions/my\_recorder/my\_recorder.hpp}

```cpp
#include <string>
#include "gxf/core/handle.hpp"
#include "gxf/std/codelet.hpp"
#include "gxf/std/receiver.hpp"
#include "gxf/std/transmitter.hpp"
#include "gxf/serialization/file_stream.hpp"
#include "gxf/serialization/entity_serializer.hpp"

class MyRecorder : public nvidia::gxf::Codelet {
public:
    gxf_result_t
```

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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 27 registerInterface in gxf_extensions/my_recorder/my_recorder.cpp

```
#include "my_recorder.hpp"

MyRecorder::registerInterface(nvidia::gxf::Registrar* registrar) {
    nvidia::gxf::Expected<void> result; result &= registrar->parameter("receiver", "receiver", "Entity receiver", "Receiver channel to log");
    result &= registrar->parameter( my_serializer_, "serializer", "Entity serializer", "Serializer for serializing input data");
    result &= registrar->parameter( directory_, "out_directory", "Output directory path", "Directory path to store received output");
    result &= registrar->parameter( basename_, "basename", "File base name", "User specified file name without extension", nvidia::gxf::Registrar::NoDefaultParameter(), GXF_PARAMETER_FLAGS_OPTIONAL);
    result &= registrar->parameter( flush_on_tick_, "flush_on_tick", "Boolean to flush on tick", "Flushes output buffer on every `tick` when true", false); // default value `false` return nvidia::gxf::ToResultCode(result); }
```
For pure GXF applications, our component’s parameters can be specified in the following format in the YAML file:

List 28 Example parameters for MyRecorder component

```yaml
name: my_recorder_entity
components: - name: my_recorder_component
  type: MyRecorder
  parameters:
    receiver: receiver
    serializer: my_serializer
    out_directory: /home/user/out_path
    basename: my_output_file # optional #
    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`.

List 29 initialize in gxf_extensions/my_recorder/my_recorder.cpp

```cpp
gxf_result_t MyRecorder::initialize() { // Create path by appending receiver name to directory path if basename is not provided
  std::string path = directory_.get() + '/';
  if (const auto& basename = basename_.try_get()) {
    path += basename.value();
  } else {
    path += receiver_->name();
  } // Initialize index file stream as write-only
  index_file_stream_ = nvidia::gxf::FileStream("", path +
    nvidia::gxf::FileStream::kIndexFileExtension); // Initialize binary file stream as write-only
  binary_file_stream_ = nvidia::gxf::FileStream("", path +
    nvidia::gxf::FileStream::kBinaryFileExtension); // Open index file stream
  nvidia::gxf::Expected<void> result = index_file_stream_.open();
  if (!result) { return nvidia::gxf::ToResultCode(result); }
  // Open binary file stream
  result = binary_file_stream_.open();
  if (!result) { return nvidia::gxf::ToResultCode(result); }
  binary_file_offset_ = 0;
  return GXF_SUCCESS;
}
```
When de-initializing, our component will take care of closing the file streams that were created at initialization.

Listing 30 **deinitialize in gxf_extensions/my_recorder/my_recorder.cpp**

```cpp
gxf_result_t MyRecorder::deinitialize() {
    // Close binary file stream
    nvidia::gxf::Expected<void> result = binary_file_stream_.close();
    if (!result) {
        return nvidia::gxf::ToResultCode(result);
    }
    // Close index file stream
    result = index_file_stream_.close();
    if (!result) {
        return nvidia::gxf::ToResultCode(result);
    }
    return GXF_SUCCESS;
}
```

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 31 **start/stop in gxf_extensions/my_recorder/my_recorder.cpp**

```cpp
gxf_result_t MyRecorder::start() { return GXF_SUCCESS; } gxf_result_t MyRecorder::stop() { return GXF_SUCCESS; }
```

**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 32 **tick in gxf_extensions/my_recorder/my_recorder.cpp**

```cpp
gxf_result_t MyRecorder::tick() {
    // Receive entity
    nvidia::gxf::Expected<nvidia::gxf::Entity> entity = receiver_ -> receive();
    if (!entity) {
        return nvidia::gxf::ToResultCode(entity);
    }
    // Write entity to binary file
```
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.

```cpp
#include "gxf/std/extension_factory_helper.hpp" #include "my_recorder.hpp"
GXF_EXT_FACTORY_BEGIN() GFX_EXT_FACTORY_SET_INFO(0xb891cef3ce754825, 0x9dd3dcac9bbd8483, "MyRecorderExtension", "My example recorder extension", "NVIDIA", "0.1.0", "LICENSE"); GFX_EXT_FACTORY_ADD(0x2464fabf91b34ccf, 0xb554977fa22096bd, MyRecorder, nvidia::gxf::Codelet, "My example recorder codelet."); GFX_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
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 34 gxf_extensions/my_recorder/CMakeLists.txt

```
# Create library add_library(my_recorder_lib SHARED my_recorder.cpp my_recorder.hpp ) target_link_libraries(my_recorder_lib PUBLIC GXF::std GXF::serialization yaml-cpp ) # Create extension add_library(my_recorder SHARED my_recorder_ext.cpp ) target_link_libraries(my_recorder PUBLIC my_recorder_lib ) # Install GXF extension as a component 'holoscan-gxf_extensions' install_gxf_extension(my_recorder) # this will also install my_recorder_lib # 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
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.

### 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 35 `apps/my_recorder_app_gxf/my_recorder_gxf.yaml`

```yaml
---
name: replayer components:
  - name: output
type: nvidia::gxf::DoubleBufferTransmitter

name: allocator
parameters: allocator: UnboundedAllocator
type: nvidia::gxf::UnboundedAllocator

name: component_serializer
type: nvidia::gxf::StdComponentSerializer
parameters:
  allocator: allocator

name: entity_serializer
type: nvidia::holoscan::stream_playback::VideoStreamSerializer
parameters:
  component_serializers:
    component_serializer
    type: nvidia::holoscan::stream_playback::VideoStreamReplayer
    parameters:
      transmitter: output
      entity_serializer: entity_serializer
      boolean_scheduling_term: boolean_scheduling
      directory: "/workspace/data/racerx"
      basename: "racerx"
      frame_rate: 0 # as specified in timestamps
      repeat: false # default: false
      realtime: true # default: true
      count: 0 # default: 0 (no frame count restriction)
      boolean_scheduling_type: nvidia::gxf::DownstreamReceptiveSchedulingTerm
      parameters:
        transmitter: output
        min_size: 1

name: recorder components:
  - name: input
type: nvidia::gxf::DoubleBufferTransmitter
```

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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.
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).

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 36 `apps/my_recorder_app_gxf/CMakeLists.txt`

```makefile
create_gxe_application( NAME my_recorder_gxf YAML my_recorder_gxf.yaml EXTENSIONS GXF::std GXF::cuda GXF::multimedia GXF::serialization my_recorder stream_playback ) # Download the associated dataset if needed if(HOLOSCAN_DOWNLOAD_DATASETS) add_dependencies(my_recorder_gxf racerx_data) 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.

**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

   ```bash
   ./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

   ```bash
   ./apps/my_recorder_app_gxf/my_recorder_gxf
   ```

   from inside the development container.

   (You can execute ./run launch to run the development container.)
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 (`racerx.gxf_index` and `racerx.gxf_entities`) under `data/racerx` exactly.
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`, as described below.

1. Creating compatible Holoscan Operators

   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.

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.

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.
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.

Concepts

The graph contains nodes which follow an entity-component design pattern implementing the “composition over inheritance” paradigm. A node itself is just a lightweight 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 subgraph 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:

```yaml
--- 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.

**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
---
name: source
components:
-
  name: signal
type: sample::test::ping

parameters:
count: 10
---
components:
```
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

Graph Specification TimeStamping

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.

### 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.

![Diagram: Entity execution sequence](image)

**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.

<table>
<thead>
<tr>
<th>SchedulingConditionType</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>NEVER</td>
<td>Entity will never execute again</td>
</tr>
<tr>
<td>READY</td>
<td>Entity is ready for execution</td>
</tr>
<tr>
<td>WAIT</td>
<td>Entity may execute in the future</td>
</tr>
<tr>
<td>WAIT_TIME</td>
<td>Entity will be ready for execution after specified duration</td>
</tr>
<tr>
<td>WAIT_EVENT</td>
<td>Entity is waiting on an asynchronous event with unknown time interval</td>
</tr>
</tbody>
</table>

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
**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 -

![Greedy Scheduler Activity Diagram](image)

**Figure: Greedy Scheduler Activity Diagram**

**Greedy Scheduler Configuration**

The greedy scheduler takes in the following parameters from the configuration file
<table>
<thead>
<tr>
<th>Parameter name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>clock</td>
<td>The clock used by the scheduler to define the flow of time. Typical choices are RealtimeClock or ManualClock</td>
</tr>
<tr>
<td>max_duration_ms</td>
<td>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</td>
</tr>
<tr>
<td>stop_on_deadlock</td>
<td>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.</td>
</tr>
</tbody>
</table>

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
```

**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
<table>
<thead>
<tr>
<th>Parameter name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>clock</td>
<td>The clock used by the scheduler to define the flow of time. Typical choices are RealtimeClock or ManualClock.</td>
</tr>
<tr>
<td>max_duration_ms</td>
<td>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.</td>
</tr>
<tr>
<td>check_recess_period_ms</td>
<td>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.</td>
</tr>
<tr>
<td>stop_on_deadlock</td>
<td>If enabled the scheduler will stop when all entities are in a waiting state, but no periodic entity exists to break the deadlock. Should be disabled when scheduling conditions can be changed by external actors, for example by clearing queues manually.</td>
</tr>
<tr>
<td>worker_thread_number</td>
<td>Number of threads.</td>
</tr>
</tbody>
</table>

Example usage - The following code snippet configures a Multithread scheduler with the number of worked threads and max duration specified -

```yaml
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
```

**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 -
<table>
<thead>
<tr>
<th>Parameter name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>clock</td>
<td>The clock used by the scheduler to define the flow of time. Typical choice is a RealtimeClock.</td>
</tr>
</tbody>
</table>

Example usage - The following code snippet configures an Epoch scheduler -

```cpp
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.

**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 -

```cpp
- name: scheduling_term type: nvidia::gxf::PeriodicSchedulingTerm parameters: recess_period: 50000000
```

**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 -
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.

<table>
<thead>
<tr>
<th>AsynchronousEventState</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>READY</td>
<td>Init state, first tick is pending</td>
</tr>
<tr>
<td>WAIT</td>
<td>Request to async service yet to be sent, nothing to do but wait</td>
</tr>
<tr>
<td>EVENT_WAITING</td>
<td>Request sent to an async service, pending event done notification</td>
</tr>
<tr>
<td>EVENT_DONE</td>
<td>Event done notification received, entity ready to be ticked</td>
</tr>
<tr>
<td>------------------</td>
<td>-------------------------------------------------------------</td>
</tr>
<tr>
<td>EVENT_NEVER</td>
<td>Entity does not want to be ticked again, end of execution</td>
</tr>
</tbody>
</table>

Entities associated with this scheduling term most likely have an asynchronous thread which can update the state of the scheduling term outside of it's 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 -

```yaml
- 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 -

```yaml
- 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 -

```yaml
- 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 it’s 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 -

```text
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
```

**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.

**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.

## 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.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>constant_status</td>
<td>The desired status to switch to during each tick time.</td>
</tr>
</tbody>
</table>

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.
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.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>children</td>
<td>Child entities</td>
</tr>
<tr>
<td>success_threshold</td>
<td>Number of successful children required for success. A value of -1 means all children must succeed for this node to succeed.</td>
</tr>
<tr>
<td>failure_threshold</td>
<td>Number of failed children required for failure. A value of -1 means all children must fail for this node to fail.</td>
</tr>
</tbody>
</table>

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.

```plaintext
```

**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.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>repeat_after_failure</td>
<td>Denotes whether to repeat the child after it has failed.</td>
</tr>
</tbody>
</table>

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 -

```plaintext
```

**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.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>children</td>
<td>Child entities</td>
</tr>
</tbody>
</table>
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 -

```plaintext
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 ]
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: []
```

**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.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
</tr>
</tbody>
</table>
### Schedule Term

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>children</td>
<td>Child entities</td>
</tr>
</tbody>
</table>

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:

```cpp
```

### Switch Behavior

Runs the child entity with the index defined as desired_behavior.

---

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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 child at index 1. (scene). Hence, that is the entity that is run.

```
```

**Timer Behavior**

Waits for a specified amount of time delay and switches to the configured result switch_status afterwards.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_term</td>
<td>scheduling term used for scheduling the entity itself</td>
</tr>
<tr>
<td>clock</td>
<td>Clock</td>
</tr>
<tr>
<td>switch_status</td>
<td>Configured result to switch to after the specified delay</td>
</tr>
<tr>
<td>delay</td>
<td>Configured delay</td>
</tr>
</tbody>
</table>

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 -

```c
name: knock_on_door components:
- name: knock_on_door_controller
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
```

**GXF Core C APIs**

**Context**

**Create context**

```c
gxf_result_t GxfContextCreate(gxf_context_t* context);
```

Creates a new GXF context
A GXF context is required for 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.

Extensions

Maximum number of extensions in a context can be 1024.

Load Extensions from a file

```c
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

```c
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 ——

```c
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.

```c
const char* manifest_filename);
```

Loads extensions from manifest file.

```c
context A valid GXF context.

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**

```c
const char* const* filenames, uint32_t count);
```

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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
Graph Execution

Loads a list of entities from YAML file

```c
 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

```c
 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

```c
int 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

```c
int 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

```c
int 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**

```c
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**

```c
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**

```c
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.

**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.*

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

 activat e 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. parameters 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**

```c
void GxfEntityDestroy(gxf_context_t context, gxf_uid_t eid);
```

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**

```c
void 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**

```c
gx_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**

```c
gx_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: \texttt{context} A valid GXF context

parameter: \texttt{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**

\begin{verbatim}
gxf_result_t GxfEntityRefCountDec(gxf_context_t context, gxf_uid_t eid);
\end{verbatim}

Decreases the reference count for an entity by 1.

See ‘GxfEntityRefCountInc’ for more details on reference counting.

parameter: \texttt{context} A valid GXF context

parameter: \texttt{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**

\begin{verbatim}
gxf_result_t GxfEntityGetStatus(gxf_context_t context, gxf_uid_t eid, gxf_entity_status_t* entity_status);
\end{verbatim}

Gets the status of the entity.

See ‘gxf_entity_status_t’ for the various status.
Get state of an entity

```c
#include <gxf/gxf_entity.h>

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
- `eid` The UID of a valid entity
- `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

```c
#include <gxf/gxf_entity.h>

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.

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**

```c
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**

```c
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**

```c
void 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 holds 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 has 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**

```c
void 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
- `eid` The unique object ID (UID) of the entity which is searched.
- `tid` The component type ID (TID) of the component to find (optional)
- `name` The component name of the component to find (optional). Ownership not transferred.
- `offset` The index of the first component in the entity to search. Also contains the index of the component which was found.
- `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
- `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**

```c
#define 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.

**Primitive Parameters**

**64-bit floating point**

**Set**

```c
#define 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**

```c
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**

```c
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**

```c
void 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**

```c
void 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

```c
#include <gxf.h>

uint64_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

```c
#include <gxf.h>

int32_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**

```c
void 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**

```c
void 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**

```c
get_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**

```c
get_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.
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: \texttt{context} A valid GXF context.

parameter: \texttt{uid} A valid component identifier.

parameter: \texttt{key} A valid name of a component to set.

parameter: \texttt{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.

**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)
```

\texttt{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 \texttt{length} argument passed.

See the table below for all the supported data types and their corresponding function signatures.

parameter: \texttt{key} The name of the parameter

parameter: \texttt{value} The value to set of the parameter

parameter: \texttt{length} The length of the vector parameter

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.
Table 1 Supported Data Types to Set 1D Vector Parameters

<table>
<thead>
<tr>
<th>Function Name</th>
<th>data_type</th>
</tr>
</thead>
<tbody>
<tr>
<td>GxfParameterSet1DFloat64Vector(...)</td>
<td>double</td>
</tr>
<tr>
<td>GxfParameterSet1DInt64Vector(...)</td>
<td>int64_t</td>
</tr>
<tr>
<td>GxfParameterSet1DUInt64Vector(...)</td>
<td>uint64_t</td>
</tr>
<tr>
<td>GxfParameterSet1DInt32Vector(...)</td>
<td>int32_t</td>
</tr>
</tbody>
</table>

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 2 Supported Data Types to Set 2D Vector Parameters

<table>
<thead>
<tr>
<th>Function Name</th>
<th>data_type</th>
</tr>
</thead>
<tbody>
<tr>
<td>GxfParameterSet2DFloat64Vector(...)</td>
<td>double</td>
</tr>
</tbody>
</table>
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.

<table>
<thead>
<tr>
<th>Function Name</th>
<th>data_type</th>
</tr>
</thead>
<tbody>
<tr>
<td>GxfParameterGet1DFloat64Vector(...)</td>
<td>double</td>
</tr>
<tr>
<td>GxfParameterGet1DInt64Vector(...)</td>
<td>int64_t</td>
</tr>
</tbody>
</table>

Table 3 Supported Data Types to Get the Value of 1D Vector Parameters
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

```c
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.

<table>
<thead>
<tr>
<th>Function</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>GxfParameterGet1DUInt64Vector(...)</td>
<td>uint64_t</td>
</tr>
<tr>
<td>GxfParameterGet1DInt32Vector(...)</td>
<td>int32_t</td>
</tr>
</tbody>
</table>

Table 4 Supported Data Types to Get the Value of 2D Vector Parameters
<table>
<thead>
<tr>
<th>Function Name</th>
<th>data_type</th>
</tr>
</thead>
<tbody>
<tr>
<td>GxfParameterGet2DFloat64Vector(...)</td>
<td>double</td>
</tr>
<tr>
<td>GxfParameterGet2DInt64Vector(...)</td>
<td>int64_t</td>
</tr>
<tr>
<td>GxfParameterGet2DUInt64Vector(...)</td>
<td>uint64_t</td>
</tr>
<tr>
<td>GxfParameterGet2DInt32Vector(...)</td>
<td>int32_t</td>
</tr>
</tbody>
</table>

**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

```c
const char* GxfParameterFlagTypeStr(gxf_parameter_flags_t_ flag_type);
```

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

```c
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

```c
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.

```c
void GxfGetParameterInfo(gxf_context_t context, gxf_tid_t cid, const char* key, gxf_parameter_info_t* info);
```

- **context** A valid GXF context.
- **tid** The unique identifier of the component.
- **key** The name of the 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.

```c
void GxfGetParameterInfo(gxf_context_t context, FILE* fp);
```

- **context** A valid GXF context.
- **fp** File path for the redirected logs.

returns: GXF_SUCCESS if the operation was successful, or otherwise one of the GXF error codes.

**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.

---

**CudaExtension**

Extension for CUDA operations.

- UUID: d63a98fa-7882-11eb-a917-b38f664f399c
- Version: 2.0.0
- Author: NVIDIA
- License: LICENSE

**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.
-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

**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

**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:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>channels</td>
<td>Number of channels in an audio frame</td>
</tr>
<tr>
<td>samples</td>
<td>Number of samples in an audio frame</td>
</tr>
<tr>
<td>sampling_rate</td>
<td>sampling rate in Hz</td>
</tr>
<tr>
<td>bytes_per_sample</td>
<td>Number of bytes required per sample</td>
</tr>
<tr>
<td>audio_format</td>
<td>AudioFormat of an audio frame</td>
</tr>
<tr>
<td>audio_layout</td>
<td>AudioLayout of an audio frame</td>
</tr>
</tbody>
</table>

Supported **AudioFormat** types:

<table>
<thead>
<tr>
<th>AudioFormat</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>GXF_AUDIO_FORMAT_S16LE</td>
<td>16-bit signed PCM audio</td>
</tr>
<tr>
<td>GXF_AUDIO_FORMAT_F32LE</td>
<td>32-bit floating-point audio</td>
</tr>
</tbody>
</table>

Supported **AudioLayout** types:
## AudioLayout

<table>
<thead>
<tr>
<th>AudioLayout</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>GXF_AUDIO_LAYOUT_INTERLEAVED</td>
<td>Data from all the channels to be interleaved - LRLRLR</td>
</tr>
<tr>
<td>GXF_AUDIO_LAYOUT_NON_INTERLEAVED</td>
<td>Data from all the channels not to be interleaved - LLLRRR</td>
</tr>
</tbody>
</table>

### 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:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>width</td>
<td>width of a video frame</td>
</tr>
<tr>
<td>height</td>
<td>height of a video frame</td>
</tr>
<tr>
<td>color_format</td>
<td>VideoFormat of a video frame</td>
</tr>
<tr>
<td>color_planes</td>
<td>ColorPlane(s) associated with the VideoFormat</td>
</tr>
<tr>
<td>surface_layout</td>
<td>SurfaceLayout of the video frame</td>
</tr>
</tbody>
</table>

Supported VideoFormat types:

<table>
<thead>
<tr>
<th>VideoFormat</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>GXF_VIDEO_FORMAT_YUV420</td>
<td>BT.601 multi planar 4:2:0 YUV</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_YUV420_ER</td>
<td>BT.601 multi planar 4:2:0 YUV ER</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_YUV420_709</td>
<td>BT.709 multi planar 4:2:0 YUV</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_YUV420_709_ ER</td>
<td>BT.709 multi planar 4:2:0 YUV ER</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_NV12</td>
<td>BT.601 multi planar 4:2:0 YUV with interleaved UV</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_NV12_ER</td>
<td>BT.601 multi planar 4:2:0 YUV ER with interleaved UV</td>
</tr>
<tr>
<td>Video Format</td>
<td>Description</td>
</tr>
<tr>
<td>----------------------------------</td>
<td>--------------------------------------------------</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_NV12_709</td>
<td>BT.709 multi planar 4:2:0 YUV with interleaved UV</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_NV12_709_ER</td>
<td>BT.709 multi planar 4:2:0 YUV ER with interleaved UV</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_RGBA</td>
<td>RGBA-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_BGRA</td>
<td>BGRA-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_ARGB</td>
<td>ARGB-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_ABGR</td>
<td>ABGR-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_RGBX</td>
<td>RGBX-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_BGRX</td>
<td>BGRX-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_XRGB</td>
<td>XRGB-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_XBGR</td>
<td>XBGR-8-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_RGB</td>
<td>RGB-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_BGR</td>
<td>BGR-8-8-8 single plane</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_R8_G8_B8</td>
<td>RGB - unsigned 8 bit multiplanar</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_B8_G8_R8</td>
<td>BGR - unsigned 8 bit multiplanar</td>
</tr>
<tr>
<td>GXF_VIDEO_FORMAT_GRAY</td>
<td>8 bit GRAY scale single plane</td>
</tr>
</tbody>
</table>

Supported SurfaceLayout types:

<table>
<thead>
<tr>
<th>SurfaceLayout</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>GXF_SURFACE_LAYOUT_PITCH_LINEAR</td>
<td>pitch linear surface memory</td>
</tr>
<tr>
<td>GXF_SURFACE_LAYOUT_BLOCK_LINEAR</td>
<td>block linear surface memory</td>
</tr>
</tbody>
</table>

**NetworkExtension**

Extension for communications external to a computation graph.

- **UUID**: f50665e5-ade2-f71b-de2a-2380614b1725
• Version: 1.0.0
• Author: NVIDIA
• License: LICENSE

Interfaces

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&lt;nvidia::gxf::Handle&lt;nvidia::gxf::Receiver&gt;&gt;

transmitters
List of transmitters to publish entities to.

• Flags: GXF_PARAMETER_FLAGS_NONE
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::Transmitter>>&`

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.
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
SerializationExtension

Extension for serializing messages.

- UUID: bc573c2f-89b3-d4b0-8061-2da8b11fe79a
- Version: 2.0.0
- Author: NVIDIA
- License: LICENSE

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

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

StandardExtension

Most commonly used interfaces and components in Gxf Core.

- UUID: 8ec2d5d6-b5df-48bf-8dee-0252606fdd7e
- Version: 2.1.0
- Author: NVIDIA
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-a3f2-715f2b3c6c69
- 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

**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.
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::gfx::SystemGroup**

A group of systems.

- Component ID: 3d23d470-0aed-41c6-ac92-685c1b5469a0
- Base Type: nvidia::gfx::System

**nvidia::gfx::MessageRouter**

A router which sends transmitted messages to receivers.

- Component ID: 84fd5d56-fda6-4937-0b3c-c283252553d8
- Base Type: nvidia::gfx::Router

**nvidia::gfx::RouterGroup**

A group of routers.

- Component ID: ca64ee14-2280-4099-9f10-d4b501e09117
- Base Type: nvidia::gfx::Router

**nvidia::gfx::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-ae01-6bae85bddd13
- Base Type: nvidia::gfx::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 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.
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-af6-47a6-9f7c-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.
nvidia::gxf::ExpandingMessageAvailableSchedulingTerm

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: e07a0dc4-3908-4df8-8134-7ce38e60fbe
- 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
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_period_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
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
- **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 \(\text{acq\_time}\).

- 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-d7b5-6e7cadc704e8

**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 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 API documentation for exhaustive definitions

---

**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.

**Ingested Tab Module**

**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:

Ingested Tab Module

**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.

Ingested Tab Module

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`. 
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.

Ingested Tab Module

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.
GXF job statistics

Holoscan can have the underlying graph execution framework (GXF) collect job statistics during application execution. Collection of these statistics causes a small amount of runtime overhead, so they are disabled by default, but can be enabled on request via the environment variables documented below. The job statistics will appear in the console on application shutdown, but can optionally also be saved to a JSON file.

The statistics collected via this method correspond to individual entities (operators) in isolation. To track execution times along specific paths through the computation graph, see the documentation on flow tracking instead.

Note

The job statistics will be collected by the underlying Graph Execution Framework (GXF) runtime. Given that, the terms used in the report correspond to GXF concepts (entity and codelet) rather than Holoscan classes.

From the GXF perspective, each Holoscan Operator is a unique entity which contains a single codelet as well as its associated components (corresponding to Holoscan Condition or Resource classes). Any additional entities and codelets that get implicitly created by Holoscan will also appear in the report. For example, if an output port of an operator connects to multiple downstream operators, you will see a corresponding implicit “broadcast” codelet appearing in the report.

Holoscan SDK environment variables related to GXF job statistics

Collection of GXF job statistics can be enabled by setting HOLOSCAN_ENABLE_GXF_JOB_STATISTICS.
- **HOLOSCAN_ENABLE_GXF_JOB_STATISTICS**: Determines if job statistics should be collected. Interprets values like "true", "1", or "on" (case-insensitive) as true (to enable job statistics). It defaults to false if left unspecified.

- **HOLOSCAN_GXF_JOB_STATISTICS_CODELET**: Determines if a codelet statistics summary table should be created in addition to the entity statistics. Interprets values like "true", "1", or "on" (case-insensitive) as true (to enable codelet statistics). It defaults to false if left unspecified.

- **HOLOSCAN_GXF_JOB_STATISTICS_COUNT**: Count of the number of events to be maintained in history per entity. Statistics such as median and maximum correspond to a history of this length. If unspecified, it defaults to 100.

- **HOLOSCAN_GXF_JOB_STATISTICS_PATH**: Output JSON file name where statistics should be stored. The default if unspecified (or given an empty string) is to output the statistics only to the console. Statistics will still be shown in the console when a file path is specified.
Video Pipeline Latency Tool

The NVIDIA 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 NVIDIA Developer Kits and various video I/O hardware and software components, the Holoscan SDK includes a sample latency measurement tool.

Requirements

Hardware

The latency measurement tool requires the use of a NVIDIA 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”.

NVIDIA Holoscan SDK v2.1.0
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).

**Software**

The following additional software components are required and are installed either by the Holoscan SDK installation or in the Installation steps below:

- CMake 3.10 or newer ([https://cmake.org/](https://cmake.org/))
- GLFW 3.2 or newer ([https://www.glfw.org/](https://www.glfw.org/))
- GStreamer 1.14 or newer ([https://gstreamer.freedesktop.org/](https://gstreamer.freedesktop.org/))
- GTK 3.22 or newer ([https://www.gtk.org/](https://www.gtk.org/))
- pkg-config 0.29 or newer ([https://www.freedesktop.org/wiki/Software/pkg-config/](https://www.freedesktop.org/wiki/Software/pkg-config/))

The following is optional to enable DeepStream support (for RDMA support from the GStreamer Producer):


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).

**Installation**

**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
```
**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
```

**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..
```

**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**:

   ![ubuntu_automatic_login.png](images/ubuntu_automatic_login.png)

3. Return to **All Settings** (top left), open **Brightness & Lock**, and disable sleep and lock as pictured:

   ![ubuntu_lock_settings.png](images/ubuntu_lock_settings.png)

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**).

---

**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.
For example, an OpenGL producer to V4L2 consumer can be measured using this configuration and the following command:
$ ./loopback-latency -p gl -c v4l2

**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. 25 *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
```

**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.
Fig. 26 SDI Cable Between Channel 1 and 2 of a Single AJA Corvid 44 Capture Card

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:

```
$ ./loopback-latency -p aja -p.device 0 -p.channel 1 -c aja -c.device 1 -c.channel 1
```

**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.

**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 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. 28 Latency Tool Frame Lifespan (RDMA Enabled)**

**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
```
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. 29 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)

<table>
<thead>
<tr>
<th>Producer (Process and Write to HW)</th>
</tr>
</thead>
<tbody>
<tr>
<td>_________________________________</td>
</tr>
<tr>
<td>Microseconds: avg = 15403, min = 14074, max = 16495</td>
</tr>
<tr>
<td>Frames: avg = 0.924, min = 0.844, max = 0.99</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Consumer (Read from HW and Copy to GPU)</th>
</tr>
</thead>
<tbody>
<tr>
<td>_________________________________</td>
</tr>
<tr>
<td>Microseconds: avg = 11369, min = 10856, max = 13381</td>
</tr>
<tr>
<td>Frames: avg = 0.682, min = 0.651, max = 0.803</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Estimated Application Times (Read + Process + Write)</th>
</tr>
</thead>
<tbody>
<tr>
<td>_________________________________</td>
</tr>
<tr>
<td>Microseconds: avg = 26772, min = 25101, max = 29204</td>
</tr>
<tr>
<td>Frames: avg = 1.61, min = 1.51, max = 1.75</td>
</tr>
</tbody>
</table>

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)
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.

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).

**Reducing Latency With RMDA**

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.
Fig. 31 Reducing Latency With RDMA

The following shows the above example repeated with RDMA enabled.

```bash
$ ./loopback-latency -p aja -p.rdma 1 -c aja -c.rdma 1 -f 4k
```
### Simulating GPU Workload

**Producer: AJA**
- **Device:** 0
- **Channel:** NTV2_CHANNEL1
- **RDMA:** 1

**Consumer: AJA**
- **Device:** 0
- **Channel:** NTV2_CHANNEL2
- **RDMA:** 1

**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:** 10336

**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)**

<table>
<thead>
<tr>
<th>Microseconds</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>8334</td>
<td>7580</td>
<td>8988</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Frames</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>0.5</td>
<td>0.455</td>
<td>0.539</td>
</tr>
</tbody>
</table>

**Consumer (Read from HW and Copy to GPU)**

<table>
<thead>
<tr>
<th>Microseconds</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>6041</td>
<td>5962</td>
<td>6932</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Frames</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>0.363</td>
<td>0.358</td>
<td>0.416</td>
</tr>
</tbody>
</table>

**Estimated Application Times (Read + Process + Write)**

<table>
<thead>
<tr>
<th>Microseconds</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>14377</td>
<td>13627</td>
<td>15233</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Frames</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>0.863</td>
<td>0.818</td>
<td>0.914</td>
</tr>
</tbody>
</table>

**Final Estimated Latencies (Processing + Vsync + Wire)**

<table>
<thead>
<tr>
<th>Microseconds</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>33332</td>
<td>33332</td>
<td>33332</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Frames</th>
<th>avg</th>
<th>min</th>
<th>max</th>
</tr>
</thead>
<tbody>
<tr>
<td>avg</td>
<td>2</td>
<td>2</td>
<td>2</td>
</tr>
</tbody>
</table>
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
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)
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 16666us).

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.
Producers

There are currently 3 producer types supported by the Holoscan latency tool. See the following sections for a description of each supported producer.

OpenGL GPU Direct Rendering (HDMI)

This producer 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.

**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.

**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).

Consumers

There are currently 3 consumer types supported by the Holoscan latency tool. See the following sections for a description of each supported consumer.

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 some of the NVIDIA 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.

**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.

**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).

**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) DP-5 connected primary 1920x1080+0+0 (normal left
```
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:

<table>
<thead>
<tr>
<th>Error Message</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ERROR: Select timeout on /dev/video0</td>
<td></td>
</tr>
<tr>
<td>ERROR: Failed to get the monitor mode (is the display cable attached?)</td>
<td></td>
</tr>
<tr>
<td>ERROR: Could not find frame color (0,0,0) in producer records.</td>
<td></td>
</tr>
</tbody>
</table>

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 (normal left inverted right x axis y axis) 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) 
```
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](link) and disable the Ubuntu lock screen.