State Machine Design

The following document outlines a design for a high level state machine to be implemented on the stm32L4 Micro controller

# System Functionality

The software will be broken down into two main parts:

1. The main Loop
2. Asynchronous Behavior

## Main Loop

The goal of the buoy is to sample environmental, gps and power data at a fixed rate. This rate will be used to describe the period between sampling the devices. Each Sample will be condensed into a byte packet and stored in flash memory at a sector. After every 4 samples, the device will load the packets from memory into a buffer and transmit the data. When the device exits this state, it will reset the sample count and repeat until the buoy is turned off or dies.

The primary loop can therefore be broken down into 4 main states:

1. **Reset State:** The device initializes the counter and verifies the sensors.
2. **Sample State**: During this state, the device actively receives data from the sensors and stores them into a packet which is then saved to Memory.
3. **Sleep State**: The device enters this state between samples and active states. Here, the device will remain in this state for a time . After which, the buoy will wake up
4. **Transmit State:** The device will load the data from memory and transfer to the Iridium Modem Buffer. Upon successful transmission, it will enter the Reset state

Each state will control which routines are performed during the function. A typical run looks like this

The inputs to the state machine are:

1. C: a 2 bit integer signifying the number of samples performed (0 =< N <4)
2. T: Variable that matters when the system is asleep. Signifies whether the system has slept for the required Tsample

The system has no explicit outputs however, the state machine is used to control which routines will be executed during the execution phase of the program. Therefore, the outputs can be considered as the Routine Rx as shown below:

Rsample -> Sensor sample routine, this can involve all the sensors or just a select number. For simplicities sake, this period implies all sensors will be sampled from

Rsleep-> Device is in a sleep state and will wake up when the periodic wake up unit counts to Twake

RTransmit -> Satellite Transmission Routine

Given the following information, we derive our ASM chart and PS/NS diagram

## Present State Next State Diagram

|  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| **Inputs** | | | **Present State** | | **Next State** | | **Outputs** | | |
| **C1** | **C0** | **T** | **Q1** | **Q0** | **D1** | **D0** | **Rsleep** | **Rtx** | **Rsample** |
| x | x | x | 0 | 0 | 0 | 1 | 0 | 0 | 0 |
| 0 | 0 | x | 0 | 1 | 1 | 0 | 0 | 0 | 1 |
| 0 | 1 | x | 0 | 1 | 1 | 0 | 0 | 0 | 1 |
| 1 | 0 | x | 0 | 1 | 1 | 0 | 0 | 0 | 1 |
| 1 | 1 | x | 0 | 1 | 1 | 1 | 0 | 0 | 1 |
| x | x | x | 1 | 1 | 1 | 0 | 0 | 1 | 0 |
| x | x | 0 | 1 | 0 | 1 | 0 | 1 | 0 | 0 |
| x | x | 1 | 1 | 0 | 0 | 1 | 1 | 0 | 0 |

## 

## Present State Next State Diagram

Note: Twake emits A High pulse when The system has Slept for a length of time T as defined by the user. In addition, the sample counter gets reset after every transmission state and when the buoy enters a reset state. The number of samples before transmission is chosen to be 4 to optimize packet size for the transmission buffer. Since the Iridium Buffer is 340 Bytes long and the Transmission rate is per 50 bytes, the goal is to transmit as much data that would fit into the buffer as possible. Too frequent transmissions incur a high data cost but result in data integrity. Too few transmissions can result in lost sample points if a transmission is not received.

# Asynchronous Behavior

Asynchronous behavior describes all functionality that occurs outside of the main loop. This can come from Interrupts/ External events which causes the system to exit the main loop regardless of state and execute the code. This can occur from the following sources:

1. Interrupts on the wake up pins for Iridium message reception (Ring alerts) and IMU event detection (collisions / freefall)
2. Events such as:
   1. Low power detection
   2. Brown Out Detection
   3. Software Resets
   4. Watch Dog Resets

These events take precedence over the main loop function. The table below shows the entry/exit conditions. Functionality as well as return state after exit.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Name** | **Type** | **Entry Condition** | **Function** | **Exit Condition** | **Return State** |
| Ring Alert | Interrupt | Buoy In any state other than reset with GPIO mapped to EXTI, with wake up from sleep mode. The WUP Pin receives a Digital High from Ring Indicator Pin on Iridium | The user has transmitted a packet to the buoy. Download the packet and execute/store the data based on the packet structure | Device has downloaded user data which has been used to update the system and store data. | If entry source was a wake up, device will return to sleep. Otherwise device will return to the main loop. |
| Event Detection | Interrupt | Buoy In any state other than reset with GPIO wake up pin mapped to EXTI, with wake up from sleep mode. The WUP Pin receives a Digital High from Interrupt pin | Device reads the interrupt source from the IMU, initializes I2C peripheral and begins sampling IMU data. Interrupt source determines the sampling rate, period and mode | Device will exit when the IMU has finished sampling and the data has been stored into memory | If entry source was a wake up, device will return to sleep. Otherwise device will return to the main loop. |
| Brown Out Detection | Event | Buoy is in run mode or in Standby mode with Brown out detection voltage enabled. Vbrownout has been configured in option bytes. Event occurs when the voltage supplied to the microcontroller is less than Vbrownout causing the device to be held under reset. When the Voltage rises above the threshold, the device will enter the handler | Device resets the relevant flags and checks for data corruption. IF no data is corrupted. Device will reload the last state and attempt to run it again. Otherwise the device performs a software reset | Vsupply > Vbrownout, device successfully executes code in handler | Returns to main loop |
| Low Power Detection | Event | Device is in run or sleep, Power Voltage thresholds set in PWR and interrupt enabled. Event occurs when Vsupply < Vpower generating an event interrupt. | Device will read INA sensor and transmit final packet to base. All peripherals switched off, Device placed into shut down mode | No Exit | No Return State |
| Software Reset | Event | The NRST internal line is pulled low for a few seconds. This is triggered in any state by triggering a software reset in the NVIC | Reset the buoy to an initial state. Clear any pending flags. Reset data in back up registers | Successful reset of voltage domains | Return to Reset state and start of main loop |

# Recommendations

Currently the device operates on a synchronized time basis. The value c is arbitrary and is chosen to ensure that sample periods are evenly spaced apart with a transmission period being a perfect multiple of the Sampling period. This dependency can be removed by triggering the Transmission state when the data buffer reaches a certain threshold. Therefore, the device can reduce the number of transmissions and increase the amount of data per each delivery. It may occur that the data packets may not fit nicely into the full 340 bytes. Therefore additional data processing is required. Finally, some devices will not be operated in transmission mode but will rather log the data to a secondary, high capacity storage. For this purpose, it is necessary to consider a log state. This will replace the transmission state and result in data being stored in a clear format on this storage. This will require additional driver code to be written depending on the device and the extra consideration of peripheral space and power consumption

# Conclusion

Therefore a Buoy state machine has been designed with additional information on asynchronous behavior. Each state will be used to activated sensors/ routines based on previous states according to the PS/NS diagram and ASM chart as shown above. Finally, sources of asynchronous behavior are described in the table above and the actions/return states are shown additionally to ensure that the main buoy firmware is easy to follow and the behavior of the code is predictable.