Modeling Resource Sharing using FSM-SADF

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***Abstract*—This paper proposes a modeling approach to capture the mapping of an application on a platform. The approach is based on Scenario-Aware Dataflow (SADF) models. In contrast to the related work, we express the complete design-space in a single formal SADF model. This allows us to have a compact and explorable state-space linked with an executable model capable of symbolically analyzing different mappings for their timing behavior. We can model different bindings for application tasks, different static-orders schedules for tasks bound in shared resources, as well as naturally capturing resource claiming/unclaiming using SADF semantics. Moreover, by using the inherent properties of dataflow graphs and the dynamic behavior of a Finite-State Machine, we can model different levels of pipelining, such as full application pipelining and interleaved pipelining of consecutive executions of the application. The size of the model is independent of the number of executions of the application. Since we are able to capture all this behavior in a single SADF model we can use available dataflow analysis, such as worst-case and best-case throughput and deadlock-freedom checking. Furthermore, since the model captures the design-space independently of the analysis technique, one can study and use different exploration approaches to analyze different sets of requirements.**

I. Introduction

In a traditional approach to system design, the first exploration phase focuses on iterating over different design alternatives to find the best solution that satisfies a given set of requirements and constraints. For example, real-time embedded systems have to perform under strict timing guarantees, or high-performance production systems focus on maximizing resource utilization to achieve maximal throughput. However, exploring different design alternatives is highly dependent on an efficient binding and scheduling of the application in order to analyze the performance of each design. Therefore, several approaches have been proposed to model and explore different mapping options for a system. However, current modeling approaches for the binding and scheduling are not transparent, use different models for application and platform or rely on later transformations to different models and formalisms to solve the actual state-space exploration problem.

A. Contribution

In this paper we present a modeling approach based on Scenario-Aware Dataflow (SADF) that provides a single, compact and formal model of the system which reflects the complete state-space for all binding and scheduling options of an application to be mapped on a given platform. Our approach allows for the modeling of both application and platform constraints, keeping all deterministic behavior of the application within static dataflow graphs and model explicitly the different choices of scheduling and binding decisions in a Finite-State Machine. The approach uses a rich formalism capable of capturing different applications or different levels of application pipelining. The resulting model uses an underlying symbolic executable flow to analyze the performance or specific scenario sequences or perform state-space exploration for timing analysis. In our model we want to capture the following cases:

1) *Resource Sharing*, e.g., if we bind two tasks to the same resource;
2) *Resource Binding*, e.g., if we one task is allowed to execute in two different resources;
3) *Application flow/Pipelining*, e.g., if the system allows for interleaved consecutive executions of the application, or if the system can have different bindings throughout application execution.

II. Related Work

Resource modeling has been explored in several works for different dataflow models. For SDFGs, a binding-aware model for task binding is proposed in [13]. In a similar fashion, in [3] static-order schedules are annotated on SDFGs without a conversion to Homogenous Synchronous Dataflow (HSDF) graphs. In both cases, graph annotations are required to encode the binding and schedule and therefore a new model is required per scheduling or resource binding option. In contrast, we can capture all options in a single model.

A different approach is the one of [14], which uses the concept of Dataflow Schedule Models (DSM) to model different scheduling policies for dataflow actors on top of the original application graph. Schedules are enforced on the original graph actors by means of *schedule control actors* that send control-flow tokens to direct the resource flow. In [9] an approach is taken to solve the optimization problem of binding and static-order scheduling for multiple HSDF graphs using SAT solvers, and [1] presents a modeling approach to find the maximal throughput for the problem of scheduling of SDFGs by converting the graph into a Timed Automata [2] model. Compared to our approach, these techniques rely on a transformation of dataflow models to other models of computation for the analysis.

Closely related to our work are [4], [15] and [16]. In [4], [15] an extended SDFG model, Resource-Aware Synchronous

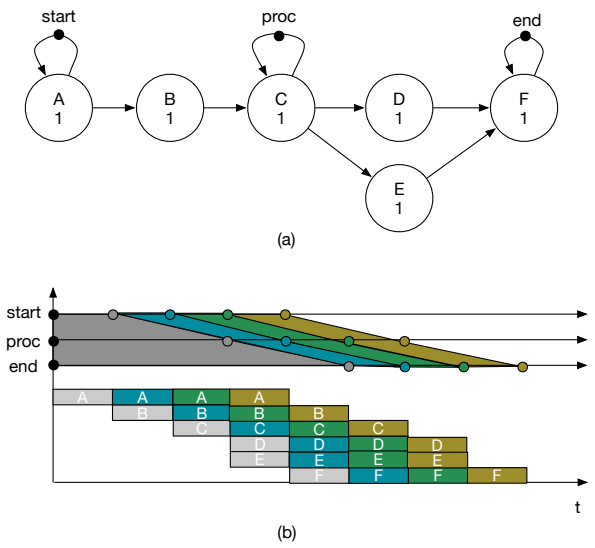

Fig. 1. (a) Example application graph modeled as an SDFG graph (b) Gantt chart execution of 4 iterations of the example application

Dataflow (RASDF), is proposed to account for resource binding and scheduling decisions during the design flow. The work is also extended for dynamic scheduling decisions using game-theory and SADF models to synthesize controllers that meet timing and resource constraints. However, since these models are extensions of SDF and SADF models, existing analysis and verification are no longer applicable. The work of [16] presents a modeling approach to annotate binding and schedule decision on SDFGs. In our approach we also use a combination of SDFG models and finite-state automata. However, instead of directly embedding the annotations in the original graph we define different scenarios to reflect the possible bindings and static-order schedules. This allows us to have a single model that reflects the whole mapping state-space that we can then orthogonally explore with different analysis approaches.

III. Preliminaries

Dataflow models, such as Synchronous Dataflow Graphs (SDFGs) have been widely used to model, design and map embedded applications. The semantics of dataflow models naturally capture the behavior of concurrent and dependency-driven applications, such as embedded or production systems. It allows the modeling of direct, cyclic, and pipelined dependencies. Several works have focused on the scheduling and timing analysis of streaming applications using SDFGs, such as [8], [7], [10]. We briefly introduce SDFG in this section. A more detailed explanation on SDFGs can be found in [5].

Consider the example of Figure 1(a), which depicts an application modeled as an SDFG. The application has 5 tasks, each of which has 1 time unit of execution time. Tasks are modeled as *actors*. Dependencies amongst tasks are modeled as directed *edges* between *actors*. Tokens are represented as black dots placed on edges between actors. According to dataflow semantics, an actor *fires*, i.e. executes its computation, when all its input edges have a number of tokens equal to the specified rate for that channel. For simplicity, throughout this paper we assume all rates to be 1. When an actor fires, it consumes all its input tokens and produces a number of tokens on its output edges equal to its defined rate. The act of firing takes a fixed amount of time called the execution time of the actor. The execution of 4 iterations of the example application is depicted in Figure 1(b).

In this case, since we are not assuming an execution platform for the example application, actors can fire as soon as possible, which results in a Self-Timed Schedule (STS). Execution of dataflow graphs can be captured by looking at the *start* and *execution* times of actor firings (Gantt Chart) or by analyzing the token production/consumption timeline (Token Timeline). The *Token Timeline* shows the production and consumption times of tokens throughout the graph execution. For each labeled token we define a timeline to register each consumption/production of that token. It provides less information in terms of the execution of the application graph, we do not see the individual firings of actors, but it allows us to visualize the transition between iterations of the application graph in time. We consider that an iteration of the graph is terminated once all the initial tokens are re-produced, and the graph returns to its initial state.

Binding and scheduling of actors in a static dataflow graph is usually done by encoding the information on the graph by using extra actors and edges, or by performing separate analysis techniques, which often leads to building several different graph models or model-transformation to other MoCs. Therefore, in our work we use a richer dataflow MoC: Scenario-Aware Dataflow.

A. Scenario-Aware Dataflow

Scenario-Aware Dataflow is a MoC that combines SDFGs with finite-state automata. The dynamic behavior of a system can be captured using multiple scenarios, where each individual scenario (a SDFG) models a specific mode of operation of the system/application. Therefore, a possible execution of the system/application can be analyzed with a sequence of different scenarios. The possible orderings of scenarios are explicit in a Finite-State Machine (FSM). SADF models exploit a combination of deterministic behavior in the scenario while allowing non-deterministic behavior in the selection of scenario sequences.

B. Example

We can use the example of Figure 1 to define two different application scenarios as depicted in Figure 2. In Figure 2(a) we have an application scenario with a static-order for actors D and E, ($D \rightarrow E$), and all actors have an execution time of 1 time unit. In Figure 2(b) we have a different scenario where the static-order is ($E \rightarrow D$) and the execution times of A, C, and F are of 2 time units. These represent two possible modes of operation of the initial application of Figure 1, which in reality

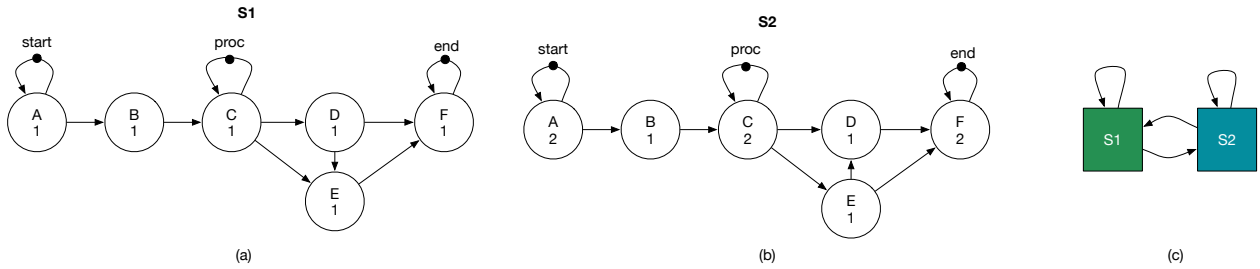

Fig. 2. Example FSM-SADF application graph: (a) Scenario S1 (b) Scenario S2 and (c) Finite-State Machine that models scenario flow

could be, for example, representing different power modes of an embedded application where actors A, C, and, F have different execution times. The possible orderings of scenario sequences are defined in the FSM (Figure 2(c)). The states of the FSM represent the possible application scenarios, while edges represent possible scenario transitions which result in the next scenario to execute. The flow of execution of scenarios is based on the token production/consumption of *labeled persistent tokens*. These tokens are represented by labeled black dots. The label is used to identify common tokens synchronizing between scenarios. This construct is fundamental to understand the execution and scenario transitions. Figure 3 depicts the execution of scenario sequence $S1 \rightarrow S2 \rightarrow S1$. If we look at the Gantt chart we can follow the scenario execution by using the coloring, green for S1 and blue for S2. We see that scenario executions can overlap in time, however in some cases firings of actors between different scenarios get delayed. In a scenario sequence, a scenario can start executing as soon as the persistent tokens of the actors of that scenario become available. This means that multiple scenarios can overlap in time. For example, in the first transition $S1 \rightarrow S2$, scenario $S2$ starts executing as soon as the persistent token of actor A_{S2} *start* is produced by actor A_{S1}. The same way that scenarios start executing depending on the production times of required persistent tokens, the execution of actors in a scenario might get delayed due to pending production of certain persistent tokens. For instance, in the second transition $S2 \rightarrow S1$, the execution of actor F_{S1} is delayed. Actor A_{S1} can start executing immediately after the firing of A_{S2} but actor F_{S1} is still dependent on the production of token *end*. Therefore, even-though F_{S1} could fire at time 9, it only fires at time 10, because it is the new production time of token *end*. This is the fundamental mechanism behind scenario transition in an FSM-SADF graph. The synchronization between scenarios using persistent tokens is the basis for our modeling approach since it allows us to model resource availability by using production and consumption of tokens as unclaiming and claiming of resources in the platform.

IV. Challenges in Modeling Resource Sharing

In this section, we explain in more detail the challenges in modeling resource sharing and the behaviors we want to capture in our model. For this purpose we will use the application of Figure 1, as a running example. Assume a platform with 5 resources, 3 specific resources *start*, *proc* and *end* and 2 shared resources *R1 and R2*. Assume the binding of A, C and F to *start*, *proc* and *end*, respectively, while B, D and E are not bound to any resource.

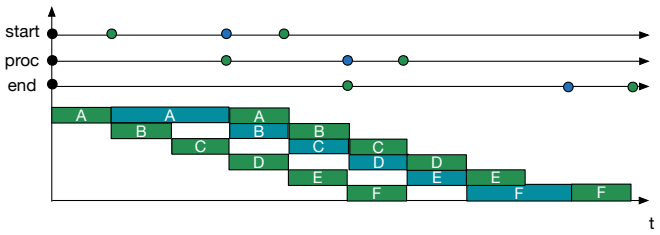

Fig. 3. Gantt Chart of Scenario Sequence: $S1 \rightarrow S2 \rightarrow S1$

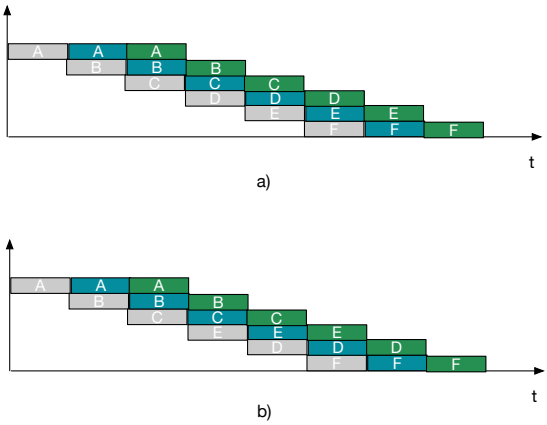

Fig. 4. Gantt chart of the SDF example with static order: a) (D→E) b) (E→D)

A. Resource Sharing

A simple resource sharing situation is the case when D and E, which have no direct dependencies in the graph structure, are bound to the same resource (assume R1). In this situation the order of execution of the actor is not static and can be either (D→E) or (E→D). Figure 4 depicts the two Gantt charts assuming the two different execution orders for D and E. We can see that throughput-wise there is no difference between the

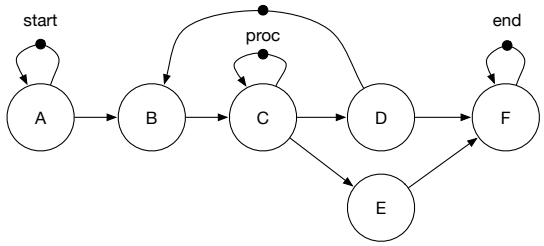

Fig. 5. Example with natural static-order between actors B and D

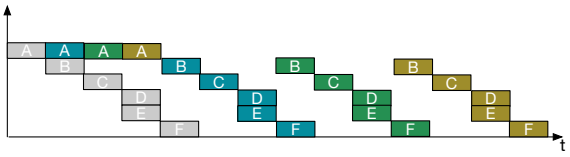

Fig. 6. Gantt chart of the execution of 4 iterations of Figure 5

orders. However, there can be latency or deadline constraints applied to one of the actors. Therefore, we want our approach to be able to explicitly capture and explore both of these choices in a single model.

B. Resource Binding

Another case we might encounter when exploring the mapping options of an application concerns alternative bindings of actors. For instance, we may allow that actor B can be bound either to resource R1 or R2. Again, this can be expressed by using two different models where the binding choices are different. However, this approach poses two main issues: 1) we are required to create two distinct models and 2) in a binding-aware model the binding is static, while modern applications can exhibit behavior that allows the mapping to be changed dynamically throughout the execution. Therefore, we want to capture dynamic binding options in an explicit way.

C. Application Flow/Pipelining

Modeling and capturing modern application flows, such as different power modes in embedded platforms, and the pipelining of applications and platforms is one of the driving factors of our work. A simple example is pipelining of different instances of the system application, which we call interleaved pipelining. This behavior is usually present in production or manufacturing systems, where throughput optimization focuses on the pipelining multiple processing steps of products. This cannot be captured in a static dataflow model, nor by using a traditional modeling approach with SADF since it requires the application to be executed in a partial fashion and not based on full graph iterations.

Figure 5 depicts a situation where actors B and D are sharing resource R1. In this case, since B and D have a direct dependency in the graph structure, we can impose a static-order. We can do so by adding a back edge from actor D to actor B with a single token. This enforces that B fires before

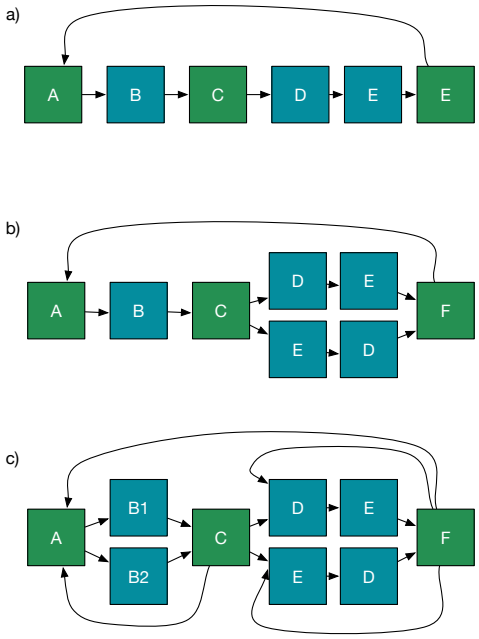

Fig. 7. FSM representing different stages of the modeling: a) Application flow with set bindings and actor order, b) Resource-Sharing (Orderings) and c) Resource Binding

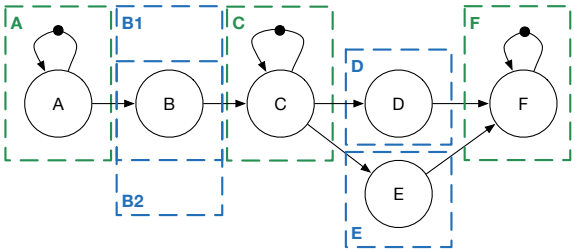

Fig. 8. Splitting of the original graph into deterministic (green) and non-deterministic (blue) parts into scenarios

D and that both actors cannot fire concurrently. If we observe the Gantt chart produced by this application graph, this indeed reflects the constraints imposed with the static-order schedule. However, if the modeled system allows for the pipelining of multiple data (or products), such is not captured with this static model. For example, notice that after the first firing of B we could make already a second firing of B concurrently with the first firing of C, but due to the imposed static order this is not possible. If this level of pipelining were captured then we could have a Gantt Chart of the application execution as depicted in Figure 10.

V. Solutions to the Modeling Challenges

In this section we present our proposed modeling solution for each of the challenges presented previously by using SADF models to capture both application and platform resources. Traditional modeling using scenarios in SADF would require the designer to build a unique scenario graph for each al-

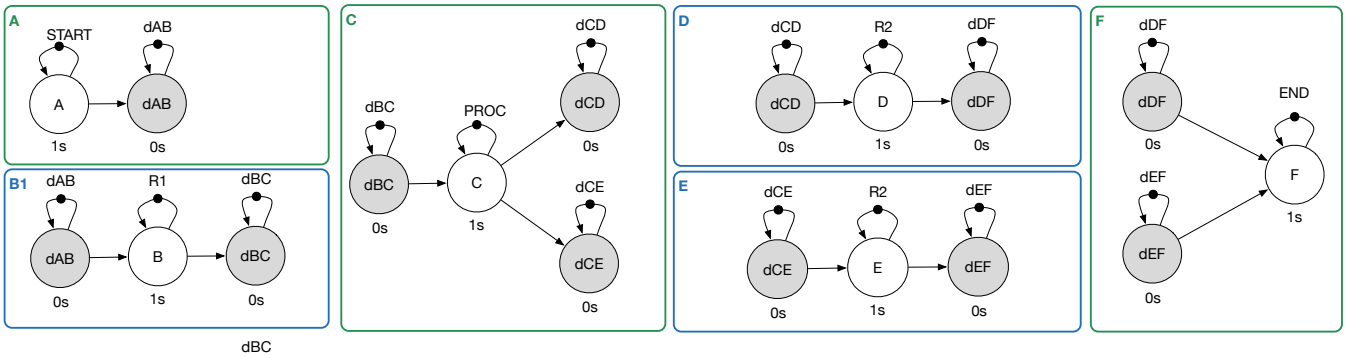

Fig. 9. Adaptation of the splitting of the SDFG of Figure 8 into scenarios of the SADF model

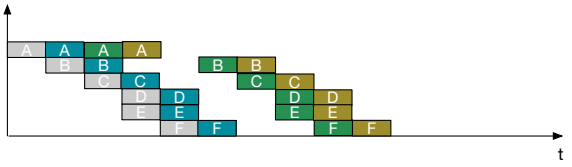

Fig. 10. Gantt chart of the execution of sequence 4 times of (A-B-C-D-E-F)

ternative in the system (binding or scheduling). Moreover, an execution of a scenario graph in SADF requires a full iteration of the graph, which does not allow for the modeling of interleaved pipelining. Therefore, we proposed a modeling approach where we *split* the original application graph into multiple scenarios and use a Finite-State Machine (FSM) to model the application flow.

A. Splitting the Application

Figure 8 depicts the division of the application graph into sets of actors that represent either static and deterministic executions (green) and sets of actors that can have scheduling freedom within their assigned binding (blue). This is the case of actors D and E, as well as, different bindings for actors, as is the case of actor B (B1 and B2). The actual splitting of the original graph to a set of scenario graphs requires the transformation of direct dependencies, modeled in the original application as edges between actors, as added *persistent tokens*. Figure 9 depicts this transformations, where each individual dashed box in Figure 8 is now fully described with dependencies as *persistent labeled tokens*. In this transformation we use *persistent tokens* to model both the original direct dependencies of the original graph as well as binding decisions. For instance, in this transformation we assume actors B and D are mapped on resource R1, E on R2, and the remaining actors on *start*, *proc* and *end*. Note that the splitting of the original application graph does not have necessarily to be done per actor in the graph. Ideally any set of actors that represent a static and deterministic behavior in the original application can be grouped together in the same scenario.

Let us consider scenario *A*, where the behavior of actor A is described. As in the original application actor A has a resource self-dependency with a labeled token *start*, but also, due to the dependency with actor B, an added *dummy actor* dAB, with a labeled token *dAB* that represents the dependency with actor B. If we now look at scenario *B*, we see that this dependency is also present by the means of a dummy actor dAB and a labeled token *dAB* that precedes the firing of actor B. This way the correct execution of the graph is preserved, if the scenario sequence *A-B* is imposed. Notice that for each direct dependency we add a pair of dummy actors in each of the corresponding scenarios, however, these have no impact on the timing analysis of the model since their execution time is 0 s. The same principle is then applied to all the scenarios regarding its original dependencies.

Crucial to the correct model of the system and its behavior is the FSM that accompanies the set of scenarios graphs, depicted in Figure 7 (a). For simplicity, we keep the same coloring and meaning in the states of the FSM as in the scenarios. Green states represent static deterministic parts of the application, while blue states represent scenario graphs that model parts with options in both binding and scheduling. Notice that the coloring of scenarios does not play a role in the operation semantics of SADF. The FSM-based SADF graph model can then capture the initial application flow of original graph. See that the FSM transitions enforce the original application execution (A-B-C-D-E-F). A fundamental construct of our modeling approach is the ability to do symbolic executions of scenario sequences that reflect the actual binding and scheduling choices per scenario sequence. Figure 10 depicts 4 iterations of the scenario sequence (A-B-C-D-E-F), given the scenario graphs of Figure 9 and the FSM of Figure 7(a). In this Gantt chart we can clearly see how the persistent tokens influence the execution of the application. We can see how all the *dummy* tokens representing the direct dependencies impose the sequentialization (e.g., A-B transition) or parallelization (e.g., D-E transition) of scenario executions. Furthermore, we see how modeling resource bindings as persistent labeled tokens allow us to naturally capture the resource utilization on the system. This is very clear on the execution gap between

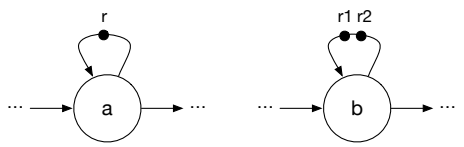

Fig. 11. Modeling resource binding in actors: (a) actor *a* is bound to resource *r* (b) actor *b* is bound two resource *r* with as a capacity of 2

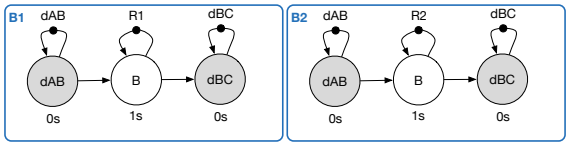

Fig. 12. Scenarios for each of the possible bindings of actor B

firings of actor B, since at the third firing resource R1 is being used by actor D of the previous firing. Therefore, the claiming and unclaiming of tokens is correctly captured as well as the mutual exclusion of shared resources.

B. Resource Binding

Let us apply our approach to address the case where an actor has multiple possible bindings. Assume that actor B can have two possible bindings, R1 and R2, we can model this creating two different scenario graphs. Figure 12 depicts these new scenarios to add to our state machine, depicted in Figure 7(b). Each scenario includes a different binding for actor B, by using a different *persistent token* labels, in this case *R1* and *R2* labels.

Generalization: Figure 11 depicts an actor *a* with a self-edge and a labeled token *r*. In our modeling approach we use such a construct to model a resource binding. The label on the token represents the resource where the actor has been bound and the self-edge imposes a non-concurrent claiming and unclaiming of the resource. Once the actor fires the labeled token is consumed. When a labeled token is consumed no other scenario actor can consume that same token, we can say that the represented resource has been claimed. Once the token is produced again, the resource is released and therefore, the token is again available for any other scenario actor. We can also model the capacity of the resource (e.g. a resource that can simultaneously process two products, depicted in Figure 11 by actor *b* by having multiple tokens in the self-edge, as long as each *persistent token* is labeled differently. For each binding possibility a scenario graph has to be added to the FSM-SADF model of the system.

C. Modeling Scheduling Options

If in our system application we have open scheduling options, such as the case of D and E, we can then use the FSM states as a mean to model both the options for the static-orders of actors D and E by using state *duplication*. This is captured in the FSM of Figure 7 (b), where we duplicate the states to model the different execution orders. However, notice that when we duplicate a state we do not duplicate a scenario graph. This means that we move the decision point from the application model to the FSM exploration.

Generalization: If in the original application graph there are groups of actors bound on the same resource with no direct dependencies and scheduling freedom, then they have different static-orders. As a generalization rule, for each possible order for the group of actors we model it as a different path in the FSM, with the same initial and ending states. This is done by duplicating the states in the FSM, which represent the same scenario graph.

D. Modeling Application Pipelining

Finally, we can also use the FSM-based SADF model to represent different application flows. This can be done by adding transition edges in the FSM. Looking at all the FSM's depicted in Figure 7 we see that the transition edge from (F-A) is always present. This is the transition edge that implies the full application pipelining, which is present in the original application. However, we would like to exploit pipelining in some systems. Therefore, we can add extra edges that reflect this behavior. For instances we can add the edges of Figure 7(d), such that we allow the interleaving of scenario sequences of (A-B-C) and (D-E-F). This means that we allow the system to do partial execution of different instances of the original application. This is a fundamental concept if we want to model applications such as Manufacturing or Operational Systems, which exploit maximally the pipelining of different processing of products throughout their execution stages. Furthermore, if the system indeed exhibits different modes of operations, such as power modes or execution times for certain tasks, then we need to model these as different scenarios within the FSM-SADF model, as it is done on traditional FSM-SADF modeling approaches [12][6].

VI. Modeling Approach

In this section we collect all the solutions for each of the modeling challenges and present them in a unified utilization and define a set of construction rules to build our final model. As an example of a utilization of all the concepts presented so far, consider the FSM in Figure 13. This describes the state-space of the application of Figure 1 on a platform with two resources, $R1$ and $R2$, where we allow all the actors to be bound to either resource. We see that for each binding, every actor has a duplicate scenario, as stated in Rule 1. Furthermore, we also have actors D and E, that can be enabled simultaneously and therefore have to have specified all the allowed static-order schedules and binding combinations. In the end, we get a model of the mapped system which can now be use for exploration, verification or symbolic execution of specific *scenario sequences*.

A. Construction Rules for the System Model

If we know the possible bindings for each resource (which can be done by matching *actor type* with *resource type*) we

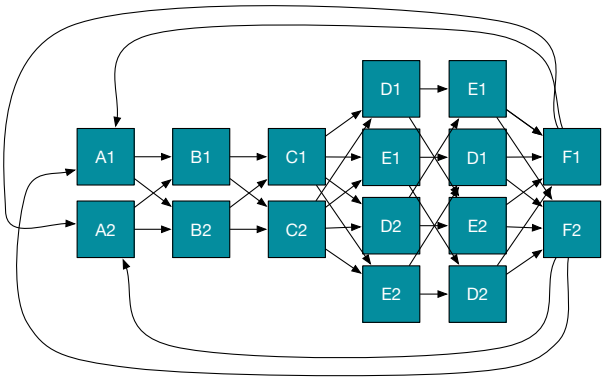

Fig. 13. FSM that holds all the behavior of our example application mapped on a 2-Homogenous resource platform

can then define the following rule:

Rule 1: For every binding of an actor we define an individual scenario graph, where the label of the persistent token in the self-edge of the actor is the label of the resource binding, and all the direct dependencies are transformed into inter-scenario dependencies by the use of persistent token labels.

However, we still need to define the possible orders and transitions to be allowed and explored by the FSM. For this purpose, we also need to gather information from the structure of the application regarding its natural static order schedules. In other words, we need to identify the actors that may be fired simultaneously with no direct dependencies (unordered actors). Therefore, every unordered group of actors needs to have explicitly in the model the different static order schedules. However, since we do not change the underlying scenario graph (for each actor) we do so by duplicating the states of the FSM and forcing the static order schedules as different path in the FSM transition sequences. This allows us to define the following rules:

Rule 2: For each unordered group of actors in the application and for each possible static-order of that group, a path in the FSM is created by duplicating exiting states in the FSM.

Rule 3: If an ordered group of actors in the application is composed only of bound actors then they can be concatenated in a single scenario that represents the fully static and combined ordered set of actor firings.

Once all the scenarios and scheduling transitions have been added to the FSM, we can add the extra set of edges that reflect the execution of the application, that it can be instantiated as full application pipelining, or interleaved pipelining.

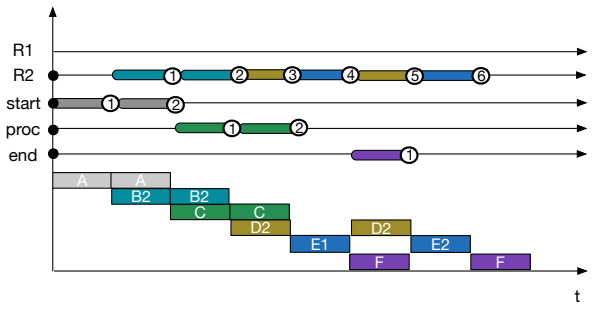

Fig. 14. Gantt chart and Token Timeline for the execution of scenario sequence (A1-B2-C1-A1-B2-C1-D2-E2-F1-D2-E2-F1)

B. Scenario Sequences and Analysis

Once we have the system model built as explained above, we reach a FSM-SADF model such as the one composed by the set of scenario graphs of Figure 9 combined with the FSM of Figure 13 (to avoid overloading the Figure, we do not show the interleaved pipelining transition edges (C-A), (F-E) and (F-D) in the image). With this model we can now explore the state-space for several executions of the application graph. We can do so by doing symbolic executions of scenario sequences. For example, if we explore *scenario sequence* (A1-B1-C1-D1-E1-F1) we are symbolically executing a full execution of the original application graph, where all the tasks are mapped on R1, and the static-order for D and E is $D \rightarrow E$. Furthermore, we can also explore *scenario sequences* for multiple consecutive executions of the application flow by using the transition edges which represent the levels of pipelining in the system. In this case, it could be for instance (A1-B2-C1-A1-B2-C1-D2-E2-F1-D2-E2-F1), which represents the interleaved pipelining of two products flowing in the system. We can then use SADF semantics to get a symbolic execution of this sequence that generates the Gantt Chart of Figure 14.

We can use the Gantt chart to follow the execution of different scenarios and use the Token Timeline the resource utilization in the system. When a token is consumed by an actor of a running scenario, the resource with that label is claimed. The duration of the claim is represented by the corresponding color bar on the timeline. When the actor terminates its firing, the token is produced again and the resource unclaimed. We can follow this trend throughout all the execution of the scenario sequence to view which resources are in use for the specified sequence. Moreover, we see that the second firing of scenario B2 is executed interleaved with the still on-going first execution of scenario C1. For example, using this symbolic execution we can use analysis techniques to explore the state-space to find maximal throughout solutions. In this case, a solution to provide maximal throughput, would be to opt for a sequence where the second firing of scenario D is executed in resource R1 instead of R2. Furthermore, since we are able to capture the whole state-space in the model, we can use and create different exploration methodologies to address different requirements. The modeling and analysis can

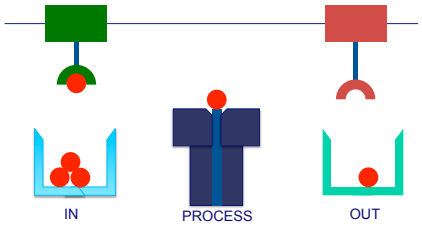

Fig. 15. Example of a Manufacturing System with 3-stages (IN,PROC and OUT) and 2 robot resources (R1 and R2)

be assumed orthogonal in our proposed approach.

VII. Case Study

Let us know look at an example of a system which exhibits all of the behavior we explored in the previous sections: resource sharing, binding and interleaved pipelining. Figure 15 depicts a simple example of a manufacturing system. This system simply picks up a product from the input bowl, moves it to the processing unit, where the product is processed, and then moves it out using output bowl. The application of the system is a systematic set of tasks that have to be performed to process the highest number of products in time. However, since the systems resources are placed with large physical distances in-between, we use specific resources to move the product across the system. In this case, this is done by the use of robots claws. For simplicity lets assume these robots never collide and that they both start and return to the same initial position, as we just want to focus on resource modeling, sharing and binding.

A. System Model

The system is composed of 3 stage activities IN, PROC, and OUT, and 2 transfer movements M1 and M2. All activities are then decomposed into several tasks. For our model we assume the application graph already split as seen in Figure 17, where we have 5 scenarios (IN, OUT, PROC, M1-R1 and M2-R1) to model the application, plus 2 scenarios (M1-R2, M2-R2) to capture the different bindings in the system. Scenarios IN, PROC and OUT, respectively represent the operation of the stage resources described in the system of Figure 15. While scenarios M1-R1, M2-R1, M1-R2 and M2-R2 represent the moves of each of the robots claws (R1,R2). In this case, we allow two movements M1 and M2, which correspond to the moves from IN to PROC and from PROC to OUT, respectively.

The system allows for different execution flows. A product can be process completly before another one is introduced, or while one product is being processed another one can be already introduced in the system to allow for product pipelining. We can model both these flows with the FSM of Figure 16. The two possible execution flows are captured in the following fashion: 1) a product as to enter and leave the system before another can, represented by the edge (OUT-IN); 2) pipelining of multiple products can occur, such that while a product is being processed another can already be loaded in the system, represented by the edges (PROC-IN) and (OUT-M2).

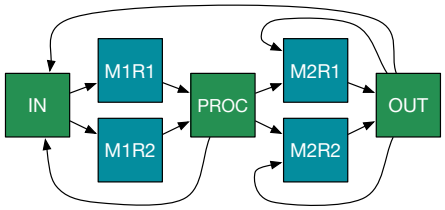

Fig. 16. FSM that holds the behavior and ordering of scenarios of Figure 17

B. Using SADF to Capture Synchronization

Since we are considering an actual manufacturing system, we have to capture the exchange of products between resources. For this purpose we can use persistent tokens to model the synchronization dependencies between resources as dependencies between scenarios. We add the *Receive* and *Release* with specific labels per synchronization point in the system (T1,T2,T3 and T4).

C. Using SADF to Capture Resources

Figure 18 depicts the execution flow of the system when processing 3 products. Looking at the production and consumption of tokens in the Token Timeline of Figure 18, we can see how resource utilization and sharing are captured using SADF. For instance, when scenario M1-R1 is executing, actor *Move* will consume token R1. During the firing, the consumed token is not available to any other actor, in any scenario, until it is produced again, by actor *Move* at time 10. As soon as the token is produced, a second execution of scenario M1-R1 claims and consumes the token R1. This example shows how consumption/production of tokens can model claiming and unclaiming of resources.

D. Model Analysis

The use of persistent token labels allows us to keep track of resource claiming and utilization throughout a symbolic execution of a scenario sequence. However, the order in which scenario graphs are executed, and consequently, the optimization of the resource utilization is only dependent on the exploration of the FSM. For example, we could explore the FSM for a number of products in the system to find the scenario sequence that maximizes throughput, using the symbolic execution of scenarios in SADF.

In Figure 18 we capture the interleaved pipelining of the three products in the system. Let us consider the first two products, which follows the scenario sequence:

$$(IN \rightarrow M1 - R1 \rightarrow PROC) \rightarrow (IN \rightarrow M1 - R1 \rightarrow PROC) \rightarrow (M2 - R2 \rightarrow OUT) \rightarrow (M2 - R2 \rightarrow OUT)$$

While the first product is still in PROC, we already introduce the second product in the system. This is allowed by the FSM of Figure 16. However, if we add a third product in the

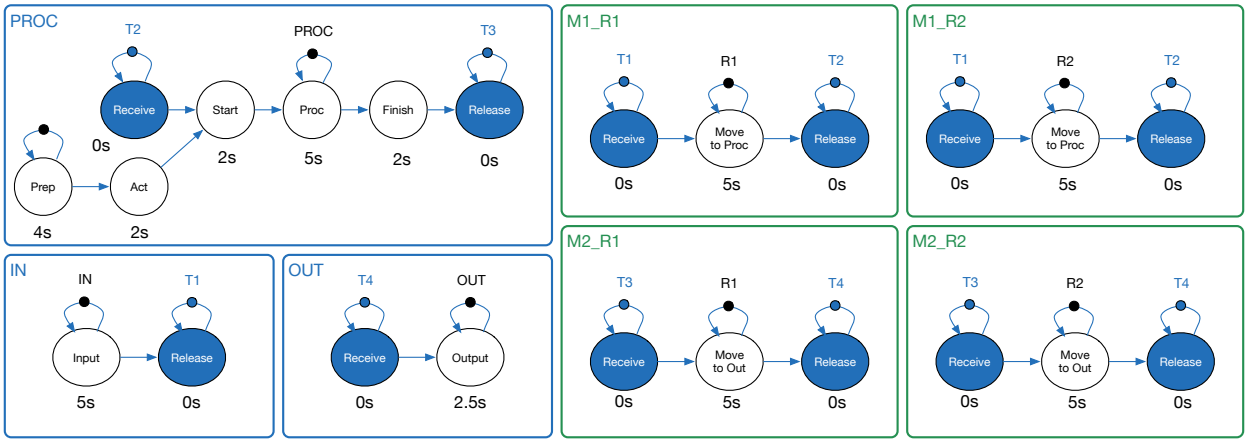

Fig. 17. Split SADF scenarios that model the application of the example of Figure 15

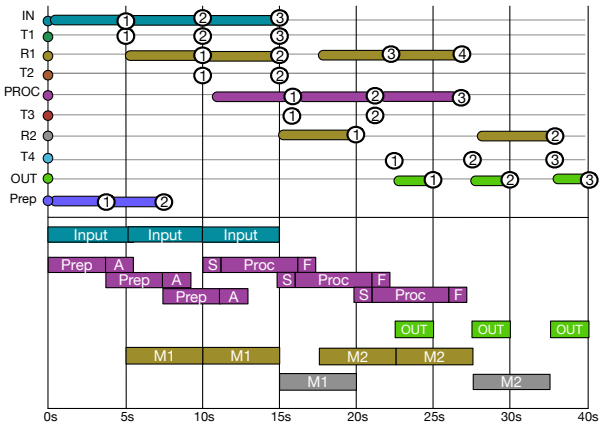

Fig. 18. Gantt Chart of the symbolic execution of the processing of two products in the system

system following the same flow, we have a resource conflict with resource R1. This happens when we can execute scenario $M1 - R1$ to move the third product or scenario $M2 - R1$ to move the first product to the output stage. We can solve this by delegating one of the moves to the unused resource $R2$, as depicted in Figure 18. Using this unified model of the system we can explore the state-space making different scheduling and binding decision dynamically with the flow of the application. Moreover, since the model contains the full state-space of binding and scheduling options we can independently use different analysis methods to find scenarios sequences that satisfy different sets of constraints.

An example would be all the analysis already existing for SADF models such as worst-case throughput analysis and latency analysis, which can be used with the SDF3 [11] tool. Also available in the tool is a simulator that is able to execute symbolic executions of scenario sequences.

Furthermore, it is important to notice that the size of the FSM that rules the exploration only depends on the number of binding options and scheduling freedom of the application. Other application characteristics such as the number of products, task synchronization, resource claiming/unclaiming is captured in scenario graphs of the model. Therefore, the exploration is only reduced to the actual design-space of application mapping.

VIII. Conclusions and Future Work

This paper presents a modeling approach using Scenario-Aware Dataflow to model a full system, both application and platform constraints. We demonstrate that the binding and scheduling exploration for the modeled system can be completely captured with this approach without added constructs to SADF or transformations to another model of computation. We show how we model the behavior of shared resources, different bindings and interleaved pipelining by using persistent token labels across different scenarios graphs. These capture resource claiming/unclaiming quite seamlessly by using the operational semantics of SADF. Moreover, we presented an example of a system that exhibits all these behaviors as a small manufacturing plant. With this example we show how the natural synchronization between tasks can be captured as well as the utilization of resources can be explored during the execution of the application with symbolic executions of scenarios sequences. The final model we propose is an FSM-based SADF graph, that consists in multiple scenarios to capture the full behavior of the application, but still allowing for a dynamic control of the application flow through the FSM. The fact that our model is representative of the full mapping problem and is as well an executable model, allows us to decouple modeling from analysis. Consequently making it possible to apply different analysis techniques to find scenario sequences that satisfy different sets of requirements. For future work we intend to explore different exploration methodologies for the model to analyze other objectives and also multi-objective analysis, such as latency and cost-performance trade-offs. We want to remove the assumption made about the physical behavior of Manufacturing Systems such that the

analysis can become more suitable, i.e. address collision or physical locations of the resources. This means that at different iterations of the application the binding and scheduling of tasks can change depending on the previous and current system state.

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