Embedded System Design and Modeling

VI. Composition of State Machines

Composition of state machines

- How to combine multiple smaller FSMs into a bigger one?
- What problems arise?
- Two types of compositions:
    1. **Spatial** composition: how are the components connected?
    2. **Temporal** composition: how do the components react in time?

Spatial composition

Spatial composition = how are two components connected, how does the information flow between the components

- **Side-by-side** composition = no common inputs/outputs, no shared data
- **Cascade** composition = Outputs of one FSM are inputs to another one
- **Feedback** composition = (Some) outputs of a FSM are inputs to the same FSM, or to some other component which is in front

Side-by-side composition

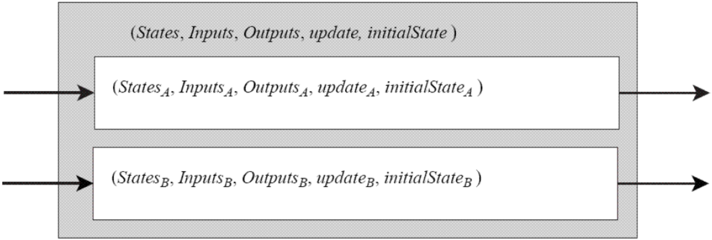


Figure 1: Side-by-side composition

Cascade composition

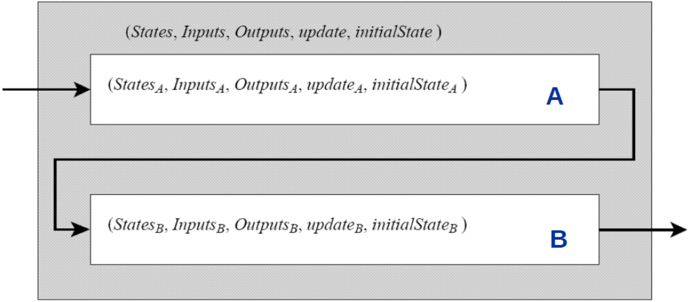


Figure 2: Cascade composition

- Outputs of FSM A are inputs to FSM B

Feedback composition

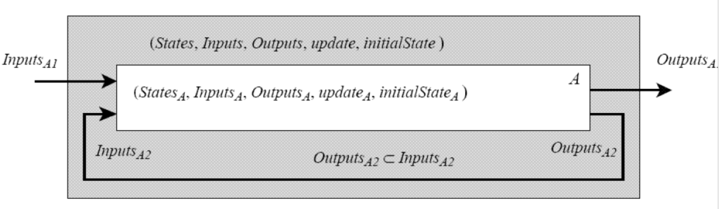


Figure 3: Feedback composition

- Some outputs of the FSM are coming back as inputs

Temporal composition

Temporal composition = when do two components react?

- **Sequential vs Parallel** composition:
  - **Sequential** = the two FSM do not work at the same time
  - **Parallel** = the two FSM work at the same time
- **Asynchonous vs Synchronous** composition = only for parallel composition
  - **Synchronous** = transitions are taken at the same time in both FSMs
  - **Asynchronous** = transitions are taken at independent times in the FSMs

Sequential composition

Figure 4: Example of Sequential composition

- 13579/:https://wwwoutubeom/watch?vD3QgGpzzIM
- The drone has three modes of operation, working **in sequence**

Parallel composition

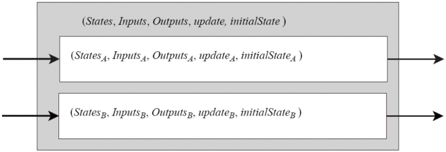


Figure 5: Side-by-side composition

- The two FSMs form an **equivalent model**
- When do the transitions in these FSM take place?
  - Synchronous: simultaneously
  - Asynchronous: independently

Synchronous composition

- Consider the two FSM on the left (A and B)
- The equivalent model is on the right

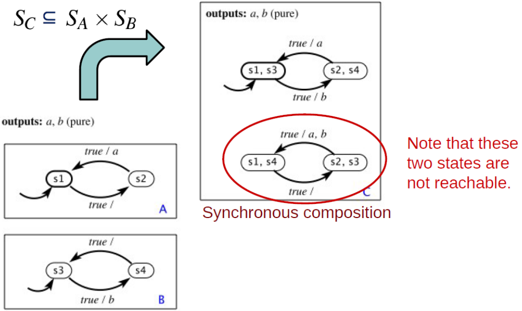


Figure 6: Synchronous composition

Synchronous composition

Redraw here

Synchronous composition

- In the equivalent model:
  - States = combination of states of the two FSMs
  - Transition = transition in FSM A and FSM B, happening simultaneously.
  - There might exist unreachable states in the equivalent model (states that will never be reached)

Asynchronous composition

Draw here

Asynchronous composition

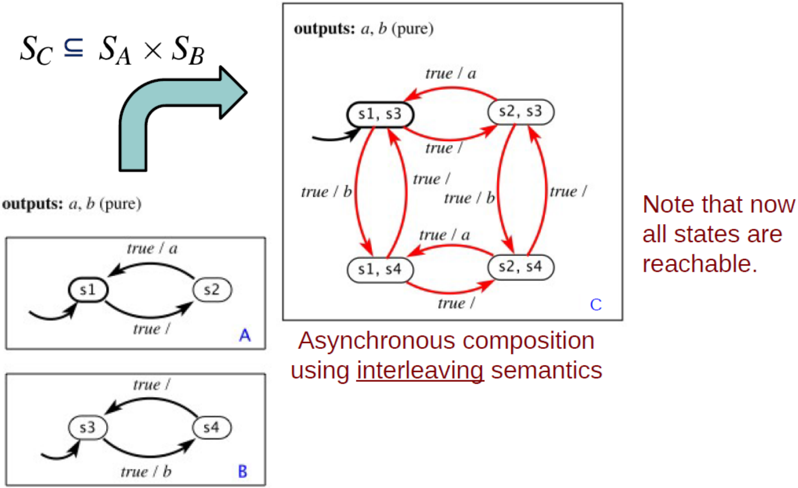


Figure 7: Asynchronous composition

Asynchronous composition

- In the equivalent model:
  - States = combination of states of the two FSMs
  - Transitions in the two FSMs can take place at irregular and independent (not synchronized) times
  - All states are reachable
    - because one model can be much faster than the other

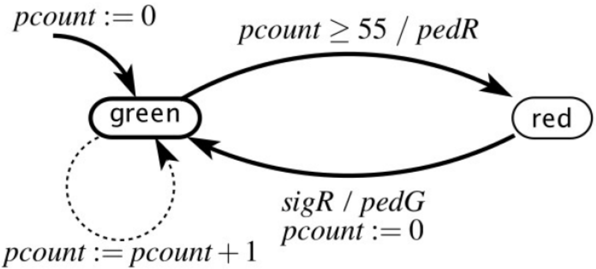
Asynchronous composition

Flavors of asynchronous composition

- How are simultaneous transitions handled?
- **Interleaving** semantics:
  - simultaneous transition in models A and B is not allowed (we may have either a transition in model A, or a transition in B)
  - i.e. transition from A takes place first, then transition from B takes place after a non-zero time delay (or vice-versa)
- **Simultaneous** semantics:
  - simultaneous transition in models A and B is allowed
  - for example, we may have either
    - transition only in model A
    - transition only in model B
    - Simultaneous transition in models A and B

Example

variable: *pcount*: $\{0, \cdots, 55\}$
input: *sigR*: pure
outputs: *pedG*, *pedR*: pure



This light stays green for 55 seconds, then goes red.
Upon receiving a sigR input, it repeats the cycle.

Figure 8: Composition - Pedestrian Light

Example

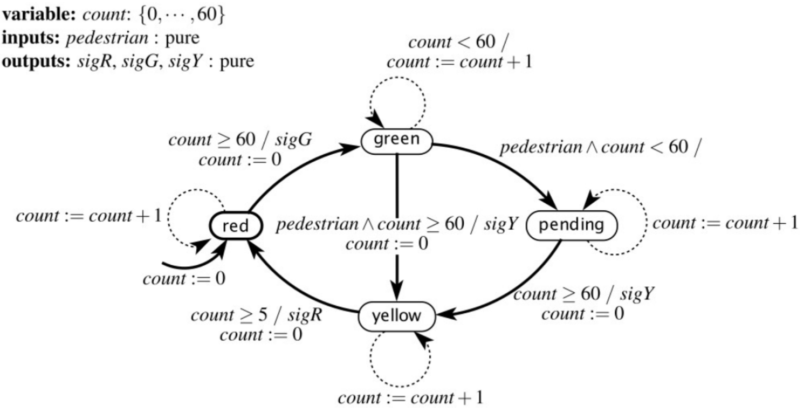
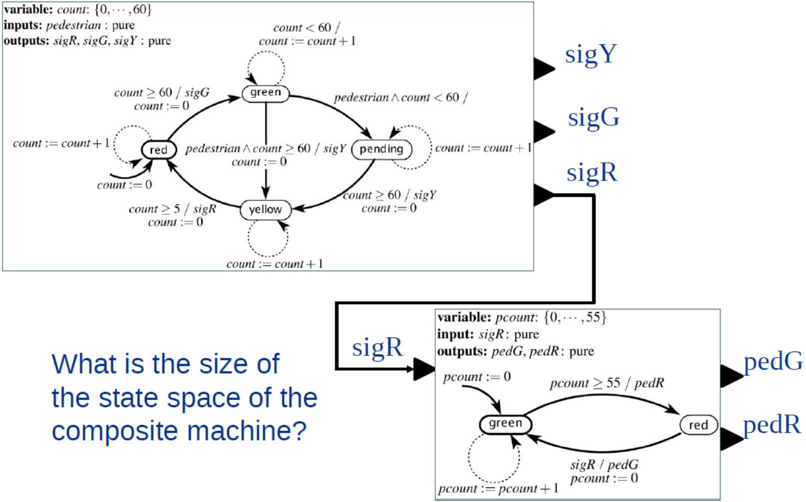


Figure 9: Composition - Car Light

Example

Pedestrian Light with Car Light



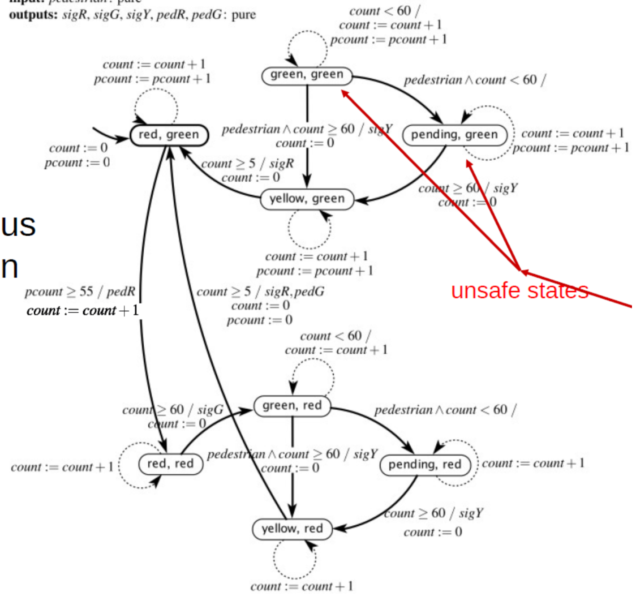
What is the size of the state space of the composite machine?

Figure 10: Cascade Composition - Both Lights

Example

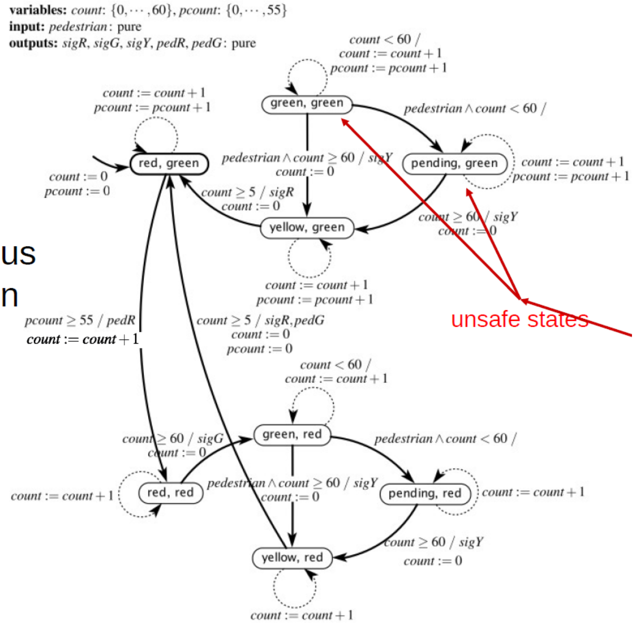
variables: *count*: $\{0, \cdots, 60\}$, *pcount*: $\{0, \cdots, 55\}$
input: *pedestrian*: pure
outputs: *sigR*, *sigG*, *sigY*, *pedR*, *pedG*: pure

Synchronous composition



Example

Synchronous composition



Models of communications

Models of communications

How do two different processes (e.g. two different FSM's) communicate with one another?

Two models:

- Shared memory
  - mutex (lock) for resource control
- Message passing
  - blocking (synchronous)
  - non-blocking (asynchronous)

Shared variables

Other possibilities for model composition:

- **Shared** variables = variables which can we written / read by both models
  - Analysis much harder
  - Potential problems: What happens if both models try to access (read or write) the variable at the same time?
    - Answer: something bad. Might end up with an incorrect value
    - Solution: access to shared variable must be via **atomic operations** and guarded with a **mutex**

Shared variables

- **Atomic** operation = an operation that is indivisible (once it starts, it can't be interrupted until it ends)
- **Mutex** (or **lock**) = a mechanism for ensuring only one process accesses a given resource (e.g. variable) at one time
  - A process first **acquires** the mutex, if it is available
  - Only afterwards it accesses the variable
  - While the mutex is acquired, no other process can access it
  - The process **releases** the mutex when it's done with the variable
  - The code between acquiring and releasing the mutex is known as a **critical section**

Message passing: blocking

- Message passing: blocking (synchronous)
- There is a sender process and a receiver process
- When the sender sends, it **waits** for the receiver to acknowledge that is has received the data
- When the receiver reads, it **waits** for the data
- Basically, the earlier one waits for the other one

Message passing: non-blocking

- Message passing: non-blocking (asynchronous)
- There is a sender process and a receiver process
- When the sender sends, it **stores** the data somewhere, and goes on
- When the receiver reads, it **collects** (if available) the data and goes on
- Neither process waits
- Works like **the post office**

Message passing

- Blocking vs non-blocking:
  - Non-blocking communication needs a storage mechanism (FIFO, LIFO, Queue, list etc.)
    - This storage space may overflow => need to have safety mechanisms in place
  - Blocking communication does not need any special soneeds a storage space (FIFO, LIFO, Queue, list etc.)
    - But delays one of the processes until the other one is ready