Control of Time-Varying Behavior

Proportional-Derivative (PD) controller: react to the immediate sensory inputs
- E.g.: yaw control
- Need a reference (or “desired”) heading

Where does this reference come from?
Control of Time-Varying Behavior

Where does the reference come from?

• Determined by what our task is (or subtask)

• E.g.: at the current state of a mission, it may be appropriate to orient the craft in a particular direction so that it can fly back “home”
Control of Time-Varying Behavior

Can often express a “mission” in terms of a sequence of sub-tasks (or a plan)
• But: we also want to handle contingencies when they arrive

Finite state machines are a simple way of expressing such plans and contingencies
Finite State Machines (FSMs)

Pure FSM form is composed of:

• A set of states
• A set of possible inputs (or events)
• A set of possible outputs (or actions)
• A transition function:
  – Given the current state and an input: defines the output and the next state
Finite State Machines (FSMs)

States:

- Represent all possible “situations” that must be distinguished
- At any given time, the system is in exactly one of the states
- There is a finite number of these states
Finite State Machines (FSMs)

An example: our synchronous counter
• States: ?
Finite State Machines (FSMs)

An example: our synchronous counter

• States: the different combinations of the digits: 000, 001, 010, … 111

• Inputs: ?
Finite State Machines (FSMs)

An example: our synchronous counter

• Inputs:
  – Really only one: the event associated with the clock transitioning from high to low
  – We will call this “C”

• Outputs: ?
Finite State Machines (FSMs)

An example: our synchronous counter

• Outputs: same as the set of states

• Transition function: ?
Finite State Machines (FSMs)

An example: our synchronous counter

• Transition function:
  – On the clock event, transition to the next state in the sequence
FSM Example: Synchronous Counter

A Graphical Representation:

A set of states
FSM Example: Synchronous Counter

A transition

C/001
FSM Example: Synchronous Counter

A transition

The event

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FSM Example: Synchronous Counter

A transition

The output
FSM Example: Synchronous Counter

The next transition

000 → 001 → 010 → 011 → 100 → 101 → 110 → 111
FSM Example: Synchronous Counter

The next transition

000 → 001 (C/001)
001 → 010 (C/010)
010 → 011 (C/011)
011 → 100
100 → 101
110 → 111
111

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FSM Example: Synchronous Counter

The full transition set

- C/010
- C/011
- C/100
- C/101
- C/110
- C/111
FSM Example: Synchronous Counter

Initial condition

Initial condition

000

001

010

011

100

101

110

111

x/000

C/000

C/001

C/100

C/110

C/111

C/010

C/011

C/101
Example II: An Up/Down Counter

Suppose we have two events (instead of one): Count up and count down

• How does this change our state transition diagram?
Example II: An Up/Down Counter

From state 000, there are now two possible transitions:

- From state 000, there is a transition to state 001 with input U.
- From state 000, there is a transition to state 111 with input D.

- From state 001, there is a transition to state 000 with input D.
- From state 001, there is a transition to state 010 with input U.

- From state 010, there is a transition to state 011 with input U.
- From state 010, there is a transition to state 100 with input D.

- From state 011, there is a transition to state 010 with input U.
- From state 011, there is a transition to state 101 with input D.

- From state 111, there is a transition to state 110 with input D.
- From state 111, there is a transition to state 101 with input U.
Example II: An Up/Down Counter

Likewise for state 001…

000 → 001
   U/001 D/000

001 → 010
   U/010

010 → 011

011 →

100 →

101 →

110 →

111 →
Example II: An Up/Down Counter

The full transition set
FSMs and Control

How do we relate FSMs to Control?
• States are?
FSMs and Control

How do we relate FSMs to Control?

• States are our memory of recent inputs

• Inputs are ?
FSMs and Control

How do we relate FSMs to Control?

• States are our memory of recent inputs

• Inputs are some processed representation of what the sensors are observing

• Outputs are
FSMs and Control

How do we relate FSMs to Control?

• States are our memory of recent inputs

• Inputs are some processed representation of what the sensors are observing

• Outputs are the control actions
FSMs: A Control Example

Suppose we have a vending machine:

• Accepts dimes and nickels
• Will dispense one of two things once $.20 has been entered: Jolt or Buzz Water
  – The “user” requests one of these by pressing a button
• Ignores select if < $.20 has been entered
• Immediately returns any coins above $.20
Vending Machine FSM

What are the states?
Vending Machine FSM

What are the states?

- $0
- $.05
- $.10
- $.15
- $.20
Vending Machine FSM

What are the inputs/events?
Vending Machine FSM

What are the inputs/events?

- Input nickel (N)
- Input dime (D)
- Select Jolt (J)
- Select Buzz Water (BW)
Vending Machine FSM

What are the outputs?
Vending Machine FSM

What are the outputs?

• Return nickel (RN)
• Return dime (RD)
• Dispense Jolt (DJ)
• Dispense Buzz Water (DBW)
• Nothing (Z)
Vending Machine Design

What is the initial state?
Vending Machine Design

What is the initial state?

• S = $0
Vending Machine Design

What can happen from $S = \$0$?

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<tr>
<th>Event</th>
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</table>
Vending Machine Design

What can happen from $S = 0$?

What does this part of the diagram look like?

<table>
<thead>
<tr>
<th>Event</th>
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</thead>
<tbody>
<tr>
<td>N</td>
<td>$.05</td>
<td>Z</td>
</tr>
<tr>
<td>D</td>
<td>$.10</td>
<td>Z</td>
</tr>
<tr>
<td>J</td>
<td>$0</td>
<td>Z</td>
</tr>
<tr>
<td>BW</td>
<td>$0</td>
<td>Z</td>
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</tbody>
</table>
Vending Machine Design

A piece of the state diagram:
Vending Machine Design

What can happen from $S = \$0.05$?

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</table>
Vending Machine Design

What can happen from $S = \$0.05$?

What does the modified diagram look like?

<table>
<thead>
<tr>
<th>Event</th>
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</thead>
<tbody>
<tr>
<td>N</td>
<td>$.10</td>
<td>Z</td>
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<tr>
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<td>$.15</td>
<td>Z</td>
</tr>
<tr>
<td>J</td>
<td>$.05</td>
<td>Z</td>
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<tr>
<td>BW</td>
<td>$.05</td>
<td>Z</td>
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</table>
Vending Machine Design

A piece of the state diagram:
Vending Machine Design

What can happen from $S = 0.10$?

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</table>
Vending Machine Design

What can happen from $S = $0.10? 

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<thead>
<tr>
<th>Event</th>
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</tr>
</thead>
<tbody>
<tr>
<td>N</td>
<td>$0.15</td>
<td>Z</td>
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<tr>
<td>D</td>
<td>$0.20</td>
<td>Z</td>
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<td>J</td>
<td>$0.10</td>
<td>Z</td>
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<tr>
<td>BW</td>
<td>$0.10</td>
<td>Z</td>
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</tbody>
</table>
Vending Machine Design

A piece of the state diagram:

- $0
- $.05
- $.10
- $.15
- $.20

States and transitions:
- $X/Z$
- $N/Z$
- $D/Z$
- $J/Z$
- $BW/Z$
What can happen from $S = $0.15?

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</table>
Vending Machine Design

What can happen from $S = $0.15? 

<table>
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<th>Event</th>
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</thead>
<tbody>
<tr>
<td>N</td>
<td>$.20</td>
<td>Z</td>
</tr>
<tr>
<td>D</td>
<td>$.20</td>
<td>RN</td>
</tr>
<tr>
<td>J</td>
<td>$.15</td>
<td>Z</td>
</tr>
<tr>
<td>BW</td>
<td>$.15</td>
<td>Z</td>
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</tbody>
</table>
Vending Machine Design

A piece of the state diagram:

[State diagram image]

Andrew H. Fagg: Embedded Real-Time Systems: FSMS
Finally: what can happen from $S = 0.20$?

<table>
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</tbody>
</table>
Finally, what can happen from $S = \$0.20$?

<table>
<thead>
<tr>
<th>Event</th>
<th>Next State</th>
<th>Output</th>
</tr>
</thead>
<tbody>
<tr>
<td>N</td>
<td>$.20</td>
<td>RN</td>
</tr>
<tr>
<td>D</td>
<td>$.20</td>
<td>RD</td>
</tr>
<tr>
<td>J</td>
<td>$0$</td>
<td>DJ</td>
</tr>
<tr>
<td>BW</td>
<td>$0$</td>
<td>DBW</td>
</tr>
</tbody>
</table>
Vending Machine Design

The complete state diagram:

[$0$]

[$.05$] $J/Z$ $N/Z$ $D/Z$

[$.10$] $N/Z$ $D/Z$

[$.15$] $J/Z$ $BW/Z$

[$.20$] $J/Z$ $BW/Z$

$x/Z$ $J/Z$ $BW/Z$

$N/RN$ $D/RN$ $N/RN$ $D/WD/WD$
Project Group Exercise

Design a FSM for control of the sonar

• What are the states?
• What are the events?
• What are the actions?
Project 4

Sonar FSM hints:

• Remember that the overflow ISR is called at regular intervals

• Each call to your ISR:
  – Depending on the current FSM state, you will:
    • Check the time on a clock
    • Check the input from the sonar
    • Generate an output to the sonar
ISR Trap: Shared Data Problem
Today

• Implementation of finite state machines in code

Homework 4 due next Tuesday
Project 4 due a week from Tuesday

Note: I am out of town next week (but accessible via email)
FSMs and Control

How do we relate FSMs to Control?
• States are ?
FSMs and Control

How do we relate FSMs to Control?

• States are our memory of recent inputs

• Inputs are ?
FSMs and Control

How do we relate FSMs to Control?
• States are our memory of recent inputs

• Inputs are some processed representation of what the sensors are observing

• Outputs are?
FSMs and Control

How do we relate FSMs to Control?

• States are our memory of recent inputs

• Inputs are some processed representation of what the sensors are observing

• Outputs are the control actions
A Robot Control Example

Consider the following task:

• The robot is to move toward the first beacon that it “sees”
• The robot searches for a beacon in the following order: right, left, front

What is the FSM representation?
Robot Control Example II

Consider the following task:
- The robot must lift off to some altitude
- Translate to some location
- Take pictures
- Return to base
- Land
- At any time: a detected failure should cause the craft to land

What is the FSM representation?
FSMs As Controllers

- Need code that translates sensory inputs into FSM events
- An FSM output can require an arbitrary amount of time
  - We will often implement this control action as a separate function call
- Control actions will not necessarily be fixed (but could be a function of sensory input)
FSMs As Controllers (cont)

• We might choose to leave some events out of the implementation
  – Only some events may be relevant to certain states

• When in a state, the FSM may also issue control actions (even when a new event has not arrived)
  – Again, this may be implemented as a function call
FSMs in C

```c
int state = 0;    // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
```
FSMs in C

```c
int state = 0; // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
```

Variable declaration and initialization
FSMs in C

```c
int state = 0; // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
```

Loop forever

```c
    }
}
```
FSMs in C

```c
int state = 0; // Initial state
while(1) {
    /* do some processing of the sensory inputs */
    switch(state) {
        case 0:
            /* handle state 0 */
            break;
        case 1:
            /* handle state 1 */
            break;
        case 2: ...
    }
}
```

“pseudo code”: not really code, but indicates what is to be done
FSMs in C

int state = 0; // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}

In this case: we will translate the current sensory inputs into a representation of an event (if one has happened)
FSMs in C

int state = 0; // Initial state
while(1) {
    // do some processing of the sensory inputs>
    switch(state) {
    case 0:
        // handle state 0
        break;
    case 1:
        // handle state 1
        break;
    case 2: ...
    }
}
FSMs in C

```c
int state = 0;   // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
```

If state==0, then execute the following code
int state = 0; // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
int state = 0;  // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
FSMs in C

```c
int state = 0;  // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
```

If state==1, then ...
int state = 0;  // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        case 1:
            <handle state 1>
            break;
        case 2: ...
    }
}
FSMs in C (some other possibilities)

```c
int state = 0;  // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        :
        default:
            <handle default case>
            break;
    }
    <do some low-level control>
}
```
FSMs in C (some other possibilities)

```c
int state = 0; // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        <default>
            <handle default case>
            break;
    }
    <do some low-level control>
}
```

Matches any state (if we reach this point)
FSMs in C (some other possibilities)

```c
int state = 0;  // Initial state
while(1) {
    <do some processing of the sensory inputs>
    switch(state) {
        case 0:
            <handle state 0>
            break;
        :
        default:
            <handle default case>
            break;
    }
    <do some low-level control>
}
(possibly) alter some control outputs (e.g., steering direction)
```
Handling Each State

• You will need to provide code that handles the event processing for each state

• Specifically:
  – You need to handle each event that can occur
  – For each event, you must specify:
    • What action is to be taken
    • What the next state is
Handling Each State

In our vending machine example:

• Events are easy to describe (only a few things can happen)
• It is convenient in this case to also “switch” on the event
FSMs in C: Processing for Individual States

case STATE_10cents:
   // $.10 has already been deposited
   switch(event) {
      case EVENT_NICKEL:  // Nickel
         state = STATE_15cents;  // Transition to $.15
         break;
      case EVENT_DIME:    // Dime
         state = STATE_20cents;  // Transition to $.2
         break;
      case EVENT_JOLT:    // Select Jolt
      case EVENT_BUZZ:    // Select Buzzwater
         display_NOT_ENOUGH();
         break;
      case EVENT_NONE:    // No event
         break;  // Do nothing
   }
   break;

FSMs in C: Processing for Individual States

```c
case STATE_10cents:
    // $.10 has already been deposited
    switch(event) {
        case EVENT_NICKEL: // Nickel
            state = STATE_15cents; // Transition to $.15
            break;
        case EVENT_DIME:   // Dime
            state = STATE_20cents; // Transition to $.2
            break;
        case EVENT_JOLT:   // Select Jolt
            case EVENT_BUZZ:   // Select Buzzwater
                display_NOT_ENOUGH();
                break;
        case EVENT_NONE:   // No event
            break;       // Do nothing
    }
};
break;
```
FSMs in C: Processing for Individual States

```c
case STATE_10cents:
    // $.10 has already been deposited
    switch(event) {
        case EVENT_NICKEL: // Nickel
            state = STATE_15cents; // Transition to $.15
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        case EVENT_DIME: // Dime
            state = STATE_20cents; // Transition to $.2
            break;
        case EVENT_JOLT: // Select Jolt
        case EVENT_BUZZ: // Select Buzzwater
            display_NOT_ENOUGH();
            break;
    case EVENT_NONE: // No event
            break; // Do nothing
```
FSMs in C: Processing for Individual States

case STATE_10cents:
    // $.10 has already been deposited
    switch(event) {
        case EVENT_NICKEL: // Nickel
            state = STATE_15cents; // Transition to $.15
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        case EVENT_DIME: // Dime
            state = STATE_20cents; // Transition to $.2
            break;
        case EVENT_JOLT: // Select Jolt
        case EVENT_BUZZ: // Select Buzzwater
            display_NOT_ENOUGH();
            break;

        case EVENT_NONE: // No event
            break; // Do nothing
    }

    break;
case STATE_10cents:
    // $.10 has already been deposited
    switch(event) {
        case EVENT_NICKEL:  // Nickel
            state = STATE_15cents;  // Transition to $.15
            break;
        case EVENT_DIME:    // Dime
            state = STATE_20cents;  // Transition to $.2
            break;
        case EVENT_JOLT:    // Select Jolt
            display_NOT_ENOUGH();
            break;
        case EVENT_BUZZ:    // Select Buzzwater
            display_NOT_ENOUGH();
            break;
        case EVENT_NONE:    // No event
            break;  // Do nothing
    };
    break;
Handling Each State

Some events do not fall neatly into one of several categories

- This precludes the use of the “switch” construct
- For example: an event that occurs when our helicopter reaches a goal orientation or a goal height
- For these continuous situations, we typically use an “if” construct:

```java
if(heading_error < 20 && heading_error > -20){...}
```
A Note on “Style” in C

• The numbers that we assigned to the different states are arbitrary (and at first glance, hard to interpret)
• Instead, we can define constant strings that have some meaning

• Replace: 0, 1, 2, 3, 4, 5
• With: STATE_00, STATE_05, STATE_10, STATE_15, STATE_20
A Note on “Style” in C

In C, this is done by adding some definitions to the beginning of your program (either in the .c file or the .h file):

```c
#define STATE_00cents 0
#define STATE_05cents 1
#define STATE_10cents 2
#define STATE_15cents 3
#define STATE_20cents 4
```
Shared Data Problem

Necessary conditions (in our context):

- Both the main program and an ISR share global variables
- The variable(s) is larger than one byte

The problem:

- The main program starts to access a variable & is then interrupted by the ISR
- The ISR changes the variable
- The main program “sees” a corrupted value
Shared Data Problem

The solution (in the main program):

- Disable the interrupts
  - E.g., timer0_disable()
- Access the shared variables
- Enable the interrupts
  - E.g., timer0_enable()

Note: do not leave interrupts disabled for very long (no loops or waits!)
Tasks for Today

• FSM for sonar control and processing
• FSM modifications for the “mission”
  (note that these are two different FSMs!)
Project Group Exercise

Design a FSM for control of the sonar

• What are the states?
• What are the events?
• What are the actions?
Project 4

Sonar FSM hints:

• Remember that the overflow ISR is called at regular intervals

• Each call to your ISR:
  – Depending on the current FSM state, you will:
    • Check the time on a clock
    • Check the input from the sonar
    • Generate an output to the sonar

• No need for the while(1){} loop!