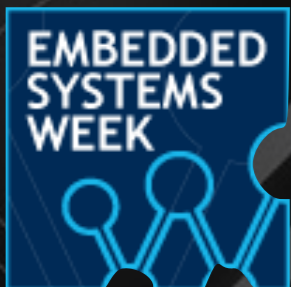


FPGA STREAM-MONITORING OF REAL-TIME PROPERTIES

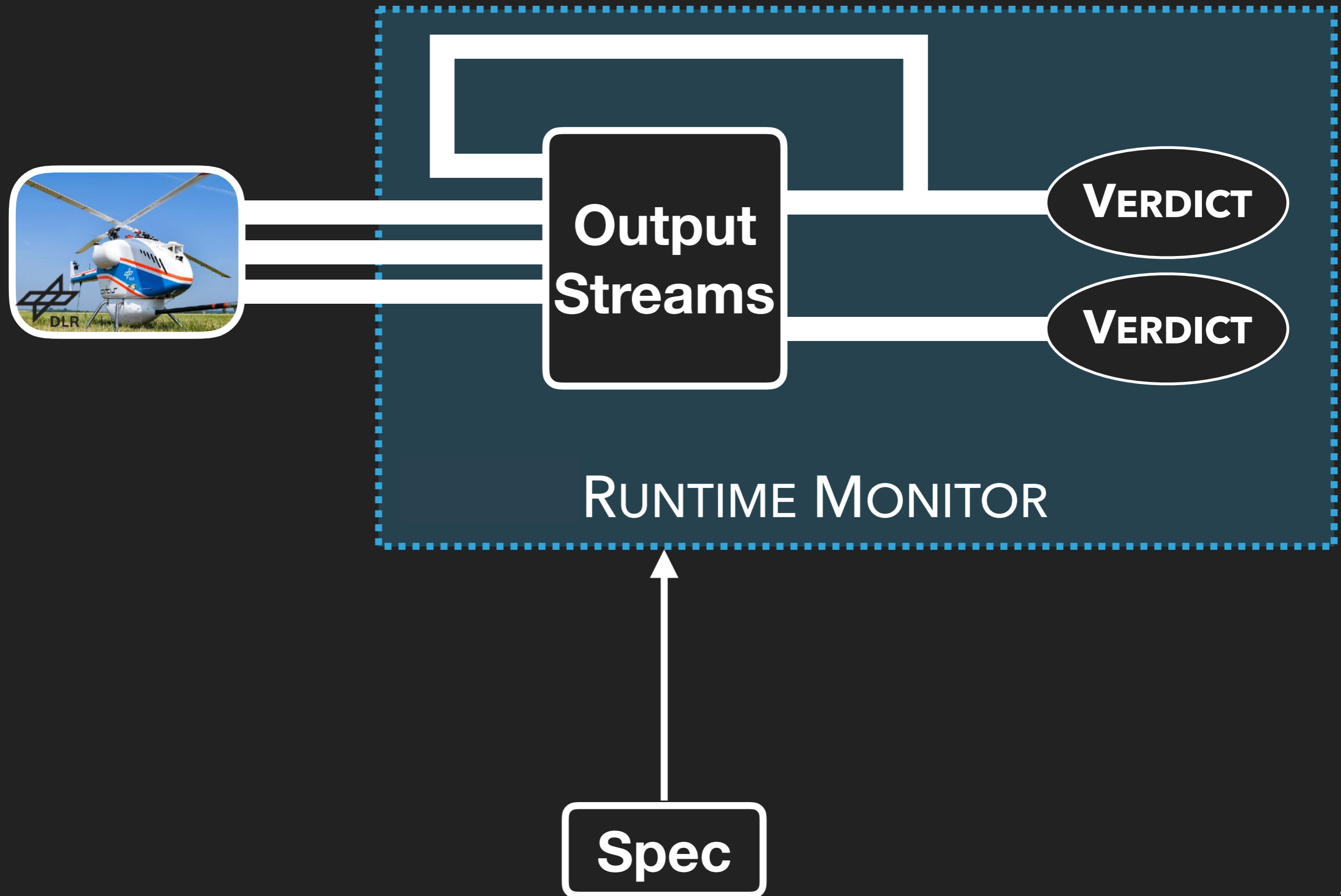
Jan Baumeister, Bernd Finkbeiner,
Maximilian Schwenger, Hazem Torfah



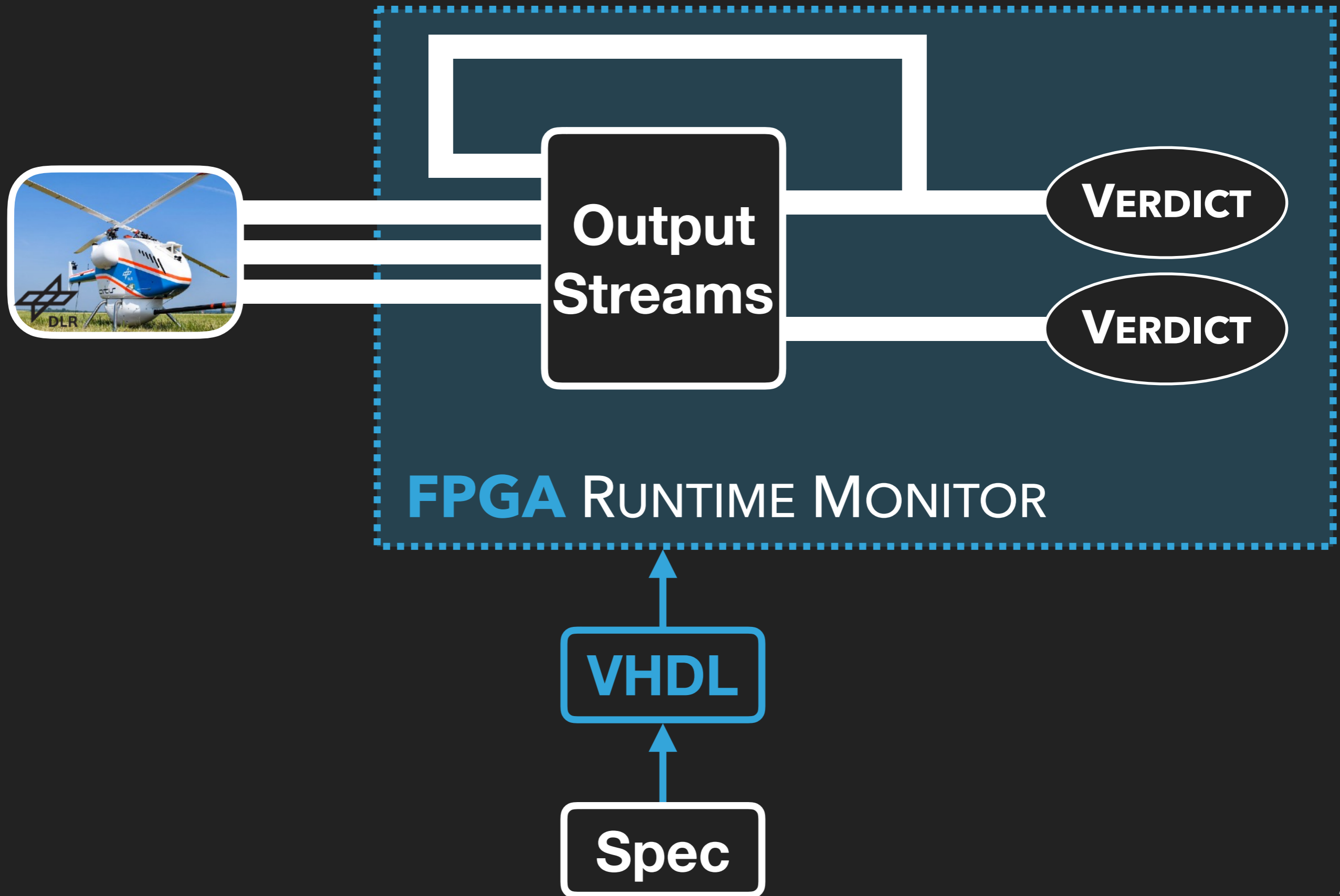
**Saarland
University**



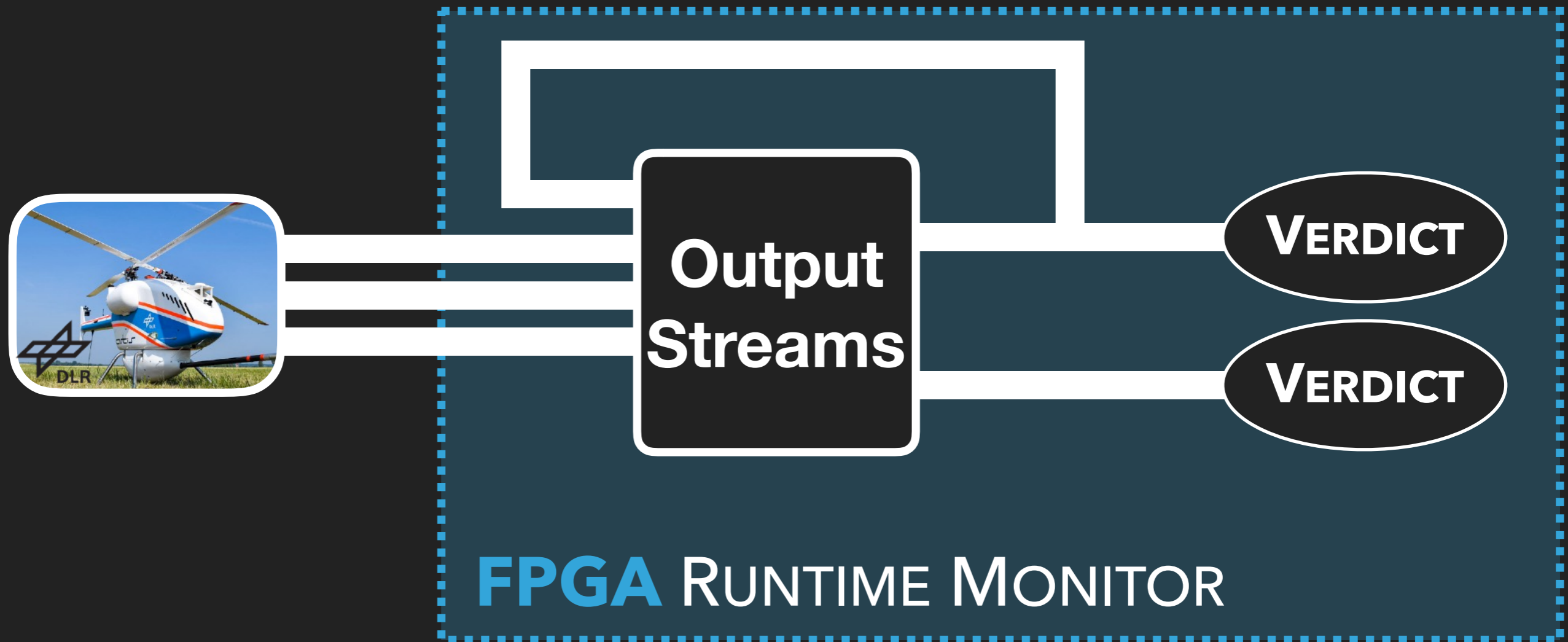
STREAM MONITORING



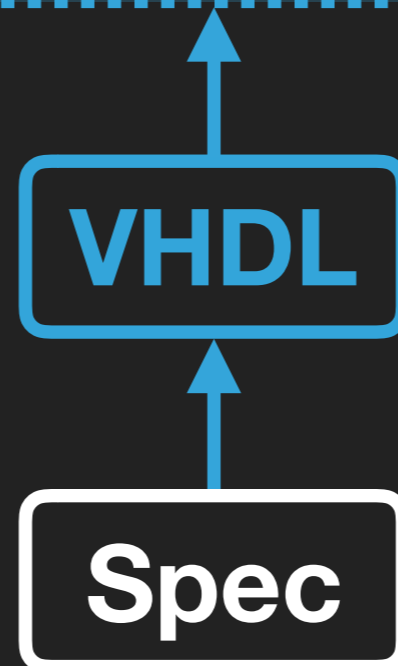
STREAM MONITORING



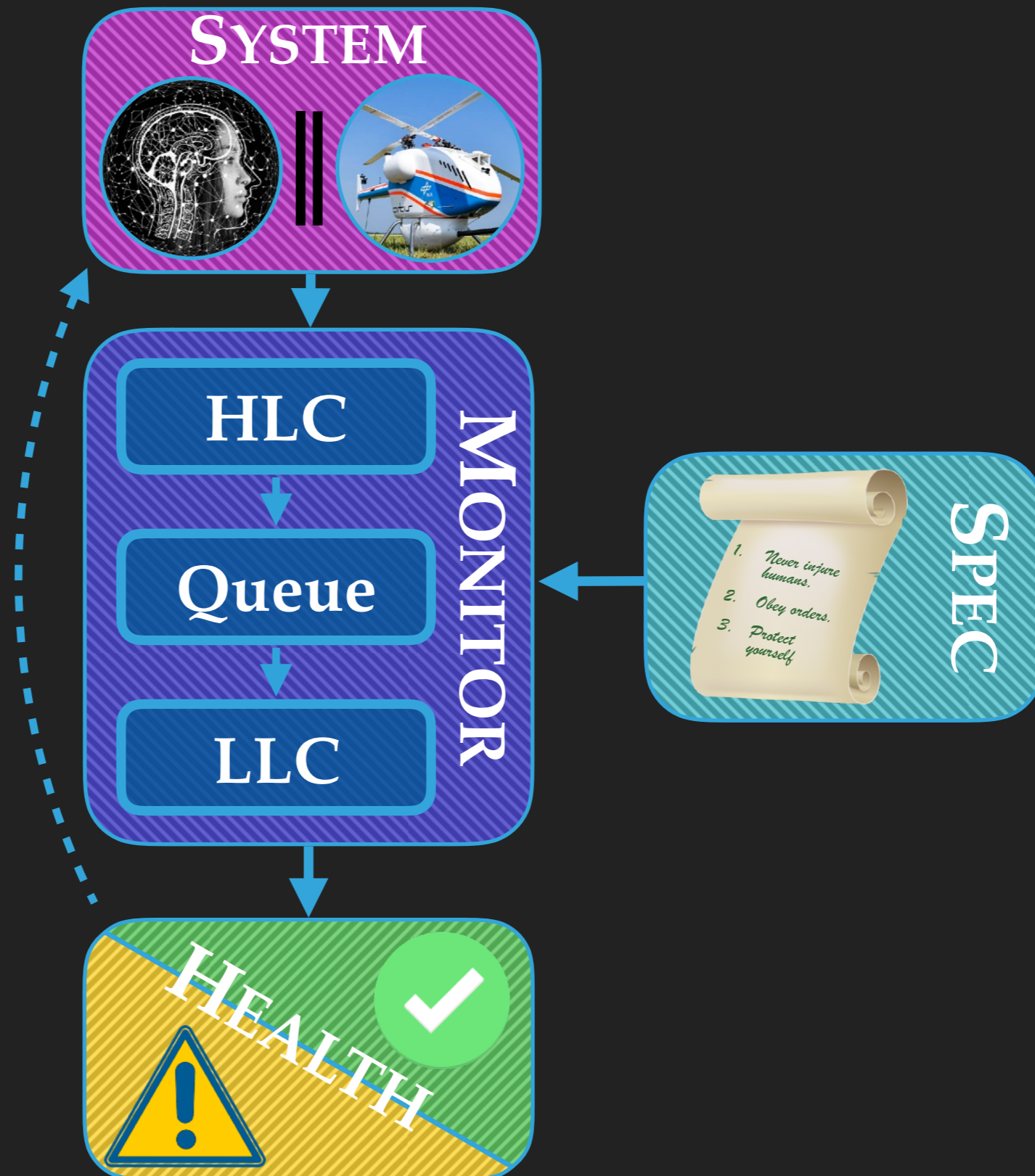
STREAM MONITORING



- ▶ Easy to Integrate
- ▶ Low Resource Consumption
- ▶ Formal Guarantees



OVERVIEW



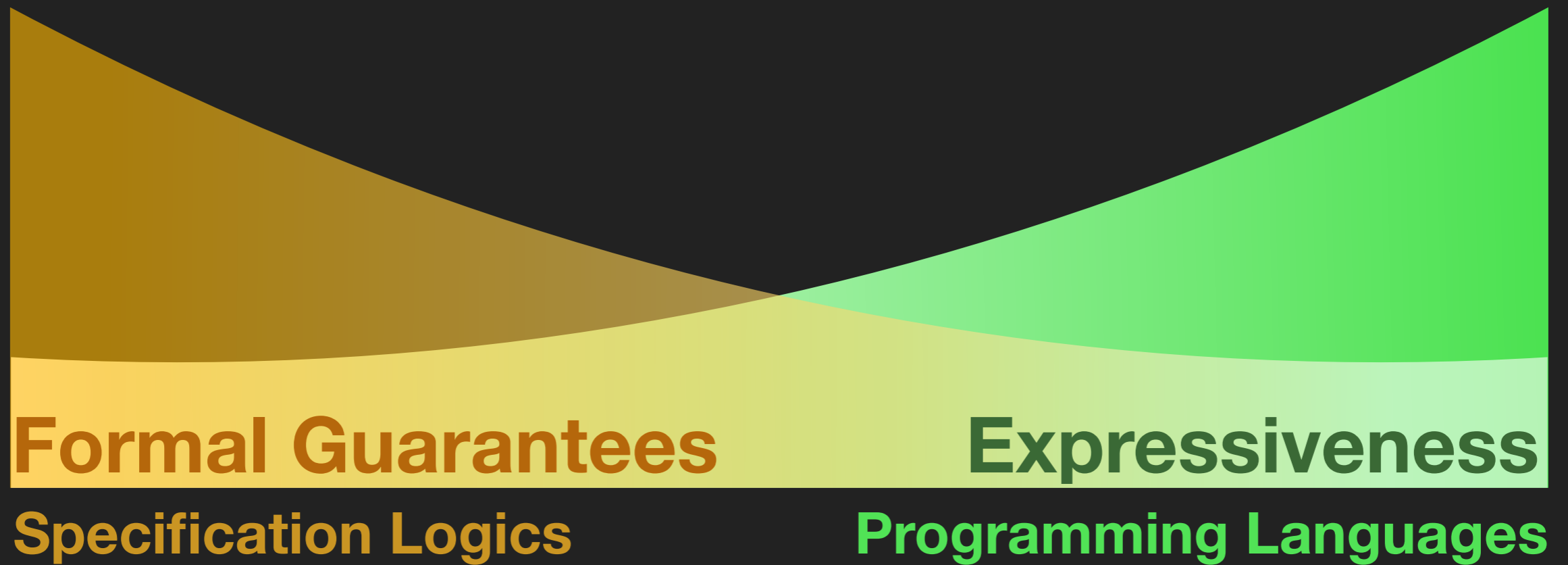
SPECIFICATION LANGUAGE



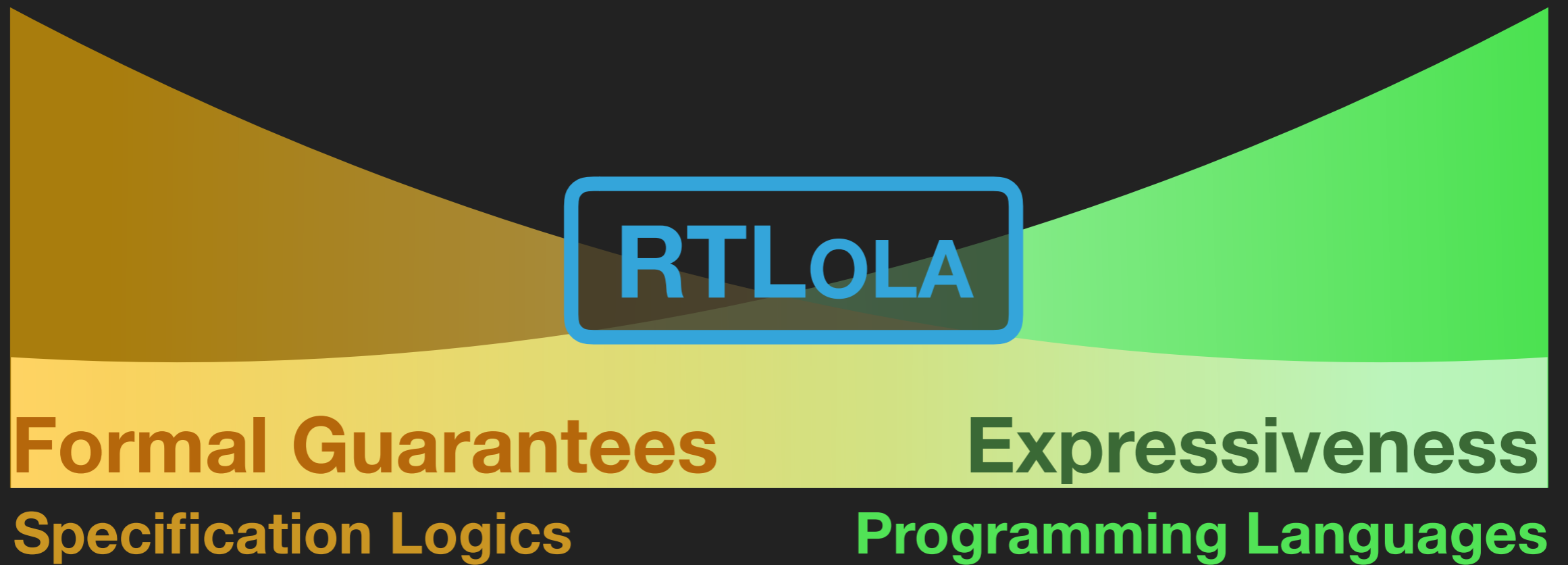
Formal Guarantees

Specification Logics

SPECIFICATION LANGUAGE



SPECIFICATION LANGUAGE



RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

The GPS module operates with at least 5Hz.

RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

output gps_freq **@1Hz** := lat.aggregate(over_exactly: 1s, using: count)
trigger gps_freq < 5 “GPS frequency less than 5 Hz.”

RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

output gps_freq **@1Hz** := lat.aggregate(over_exactly: 1s, using: count)
trigger gps_freq < 5 “GPS frequency less than 5 Hz.”

Measured and computed velocities coincide.

RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

output gps_freq **@1Hz** := lat.aggregate(over_exactly: 1s, using: count)

trigger gps_freq < 5 “GPS frequency less than 5 Hz.”

output gps_dist := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

output gps_velo := $\nabla(\text{gps_dist})$

trigger abs(gps_velo - velo) > 0.1 “Conflicting measurements for velocity.”

RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

output gps_freq **@1Hz** := lat.aggregate(over_exactly: 1s, using: count)

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output gps_velo := $\nabla(\text{gps_dist})$

trigger abs(gps_velo - velo) > 0.1 “Conflicting measurements for velocity.”

Deceleration is preceded by a slow-down command.

RTLOLA IN A NUTSHELL

input lat, lon, velo: **Float64**

input slow_down_cmd: **Bool**

output gps_freq @1Hz := lat.aggregate(over_exactly: 1s, using: count)

trigger gps_freq < 5 “GPS frequency less than 5 Hz.”

output gps_dist := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

output gps_velo := $\nabla(\text{gps_dist})$

trigger abs(gps_velo - velo) > 0.1 “Conflicting measurements for velocity.”

output fast := velo > 700

output slow_down := fast.offset(by: -1).defaults(to: false) \wedge \neg fast

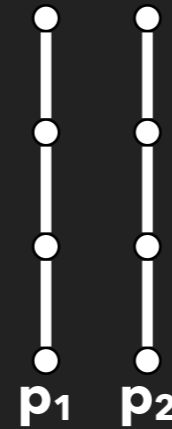
trigger @1Hz \neg slow_down_cmd.aggregate(over: 5s, using: \exists)

\wedge slow_down.hold().defaults(to: false) “Spurious Slow-Down.”

CHALLENGES



**Periodic
versus
Event-Based**



**Utilize
Parallel
Execution**



**Reduce
Circuit
Cost**

PERIODIC V. EVENT-BASED



input lat, lon, velo: **Float64**

input slow_down_cmd: **Bool**

output gps_freq **@1Hz** := lat.aggregate(over_exactly: 1s, using: count)

trigger gps_freq < 5 “GPS frequency less than 5 Hz.”

output gps_dist := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

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...

PERIODIC V. EVENT-BASED



input lat, lon, velo: **Float64**

input slow_down_cmd: **Bool**

output **gps_freq @1Hz** := lat.aggregate(over_exactly: 1s, using: count)

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output **gps_dist** := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

output **gps_velo** := $\nabla(\text{gps_dist})$

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...

PERIODIC V. EVENT-BASED



input lat, lon, velo: **Float64**

input slow_down_cmd: **Bool**

output **gps_freq @1Hz** := lat.aggregate(over_exactly: 1s, using: count)

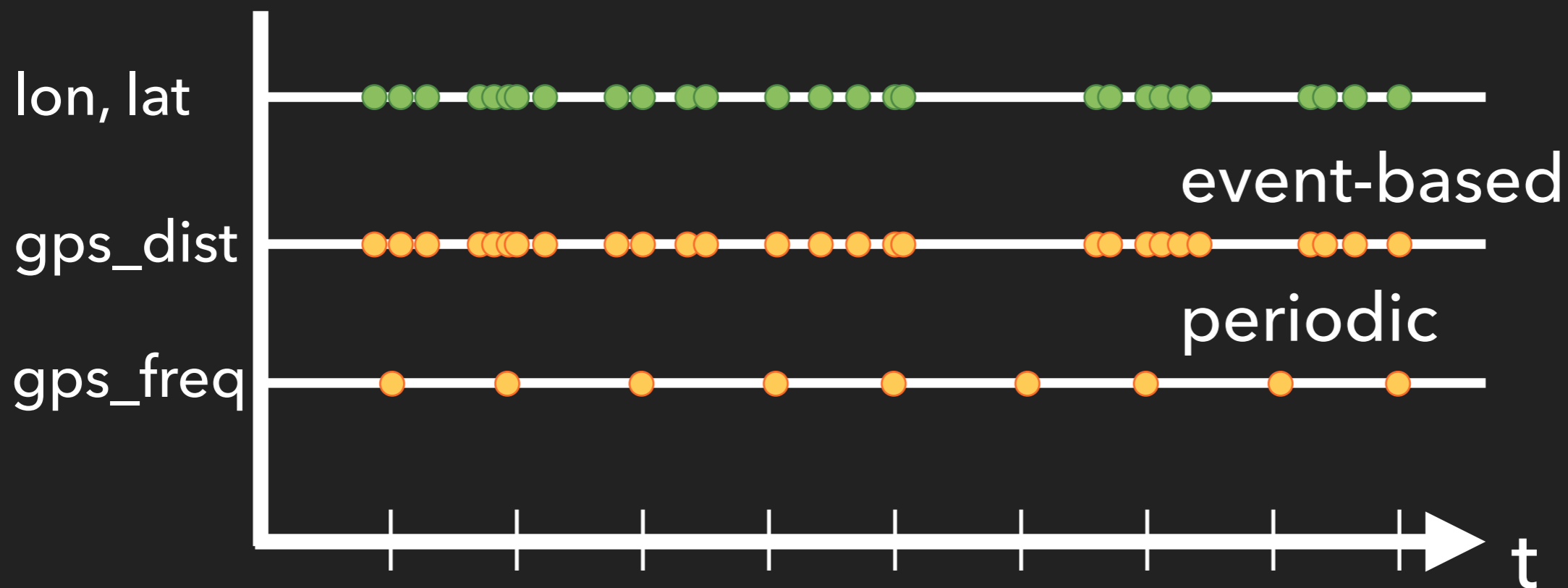
trigger **gps_freq < 5** “GPS frequency less than 5 Hz.”

output **gps_dist** := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

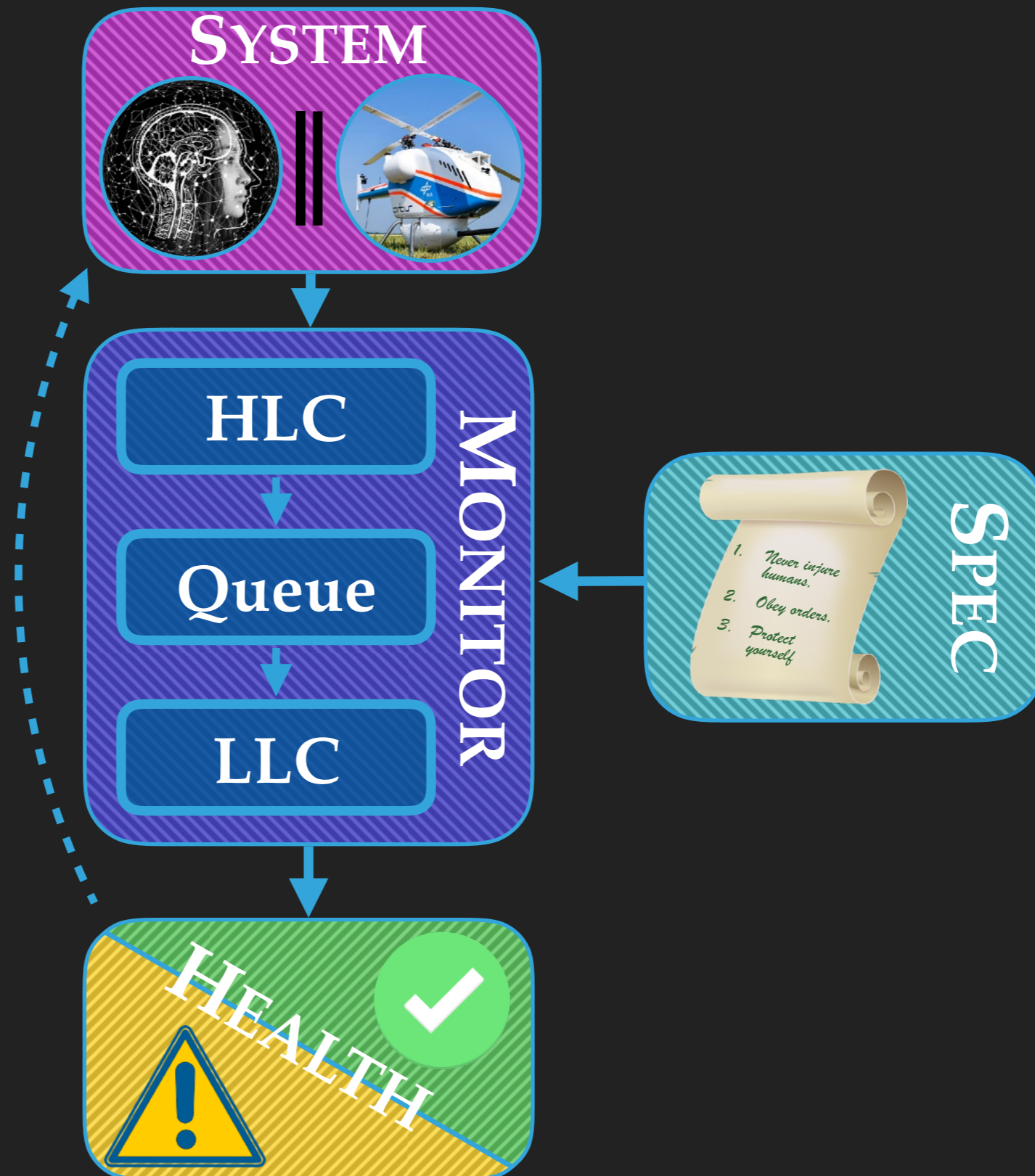
output **gps_velo** := $\nabla(\text{gps_dist})$

trigger **abs(gps_velo - velo) > 0.1** “Conflicting measurements for velocity.”

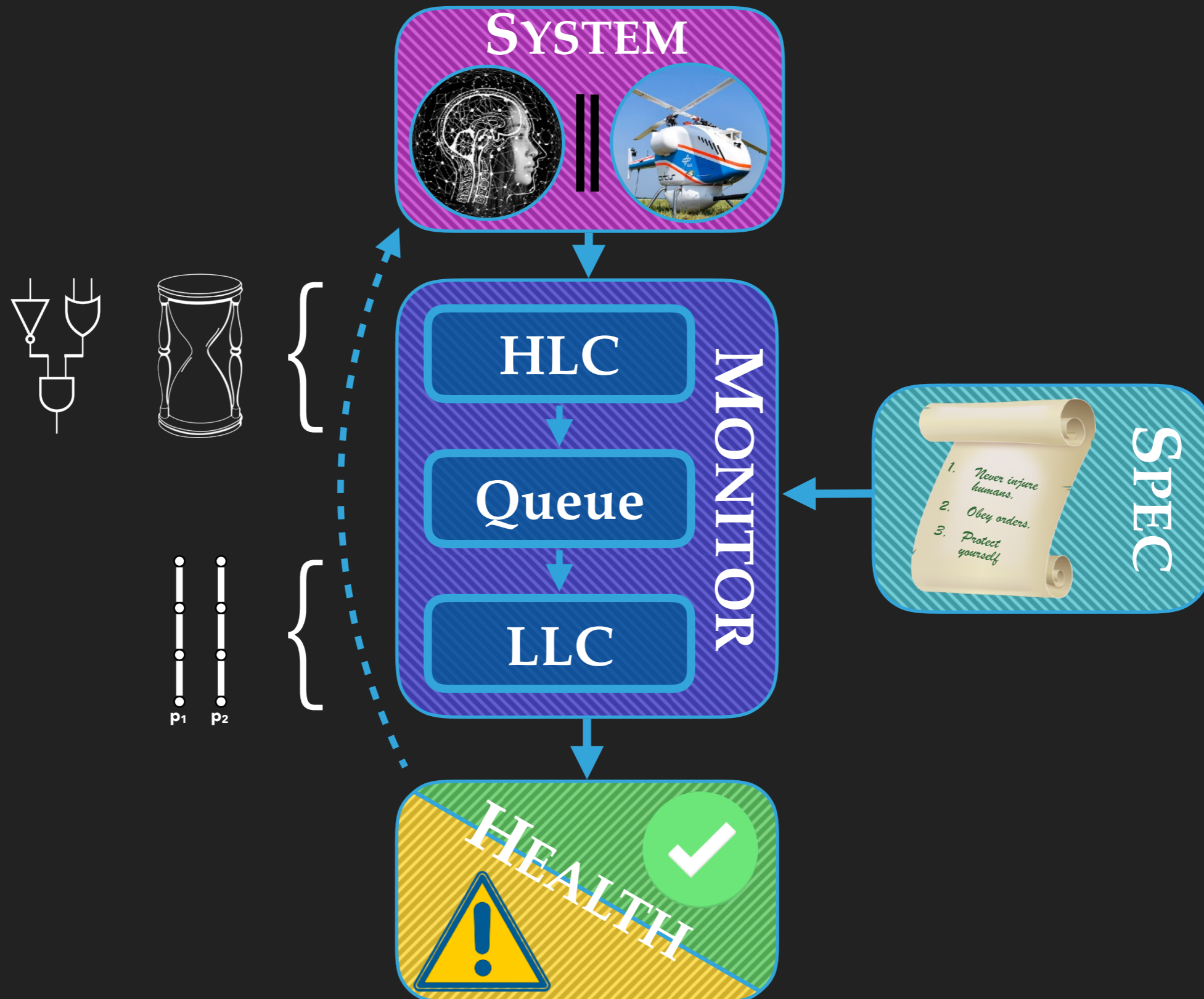
...



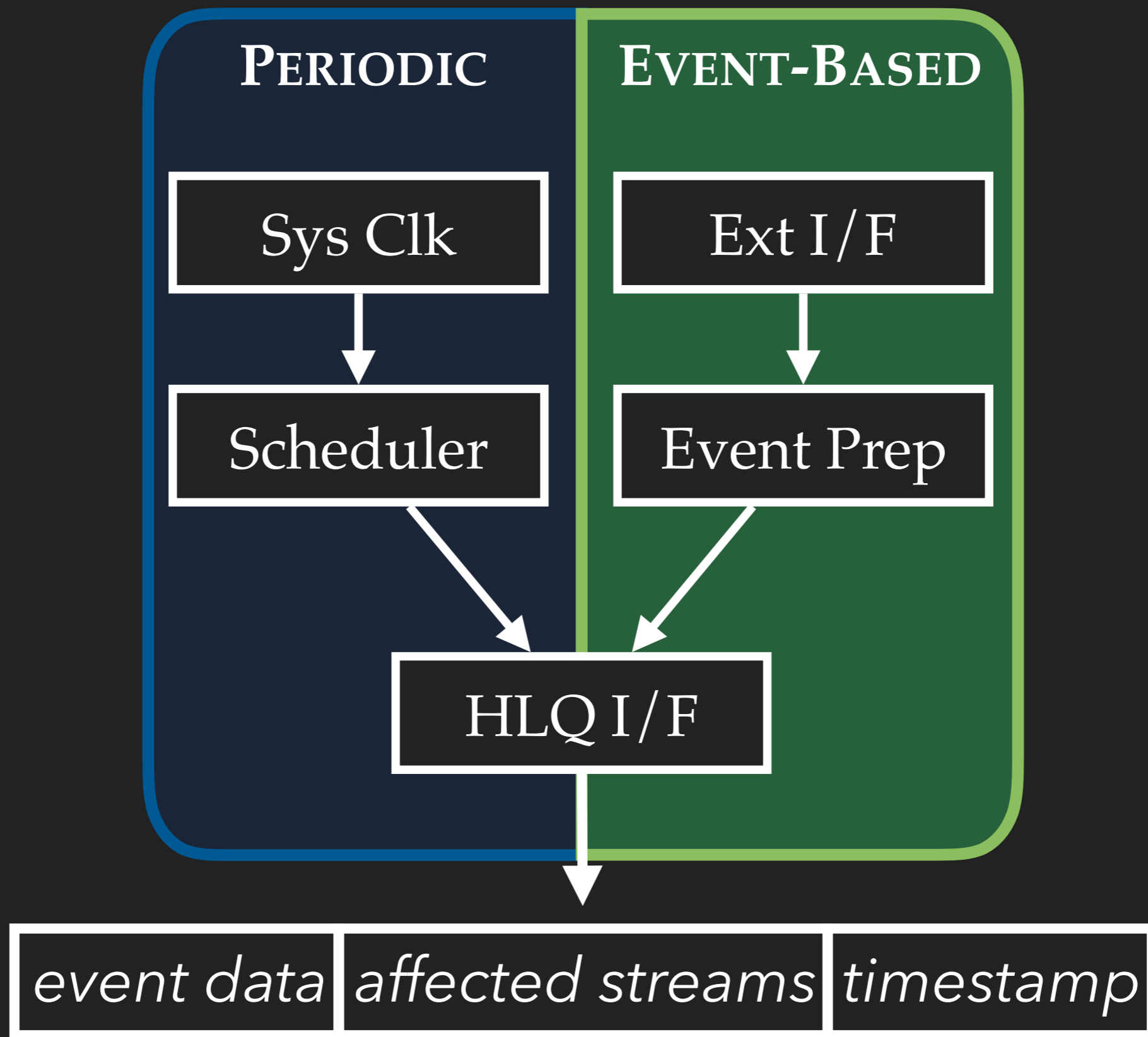
FROM RTLOLA TO VHDL



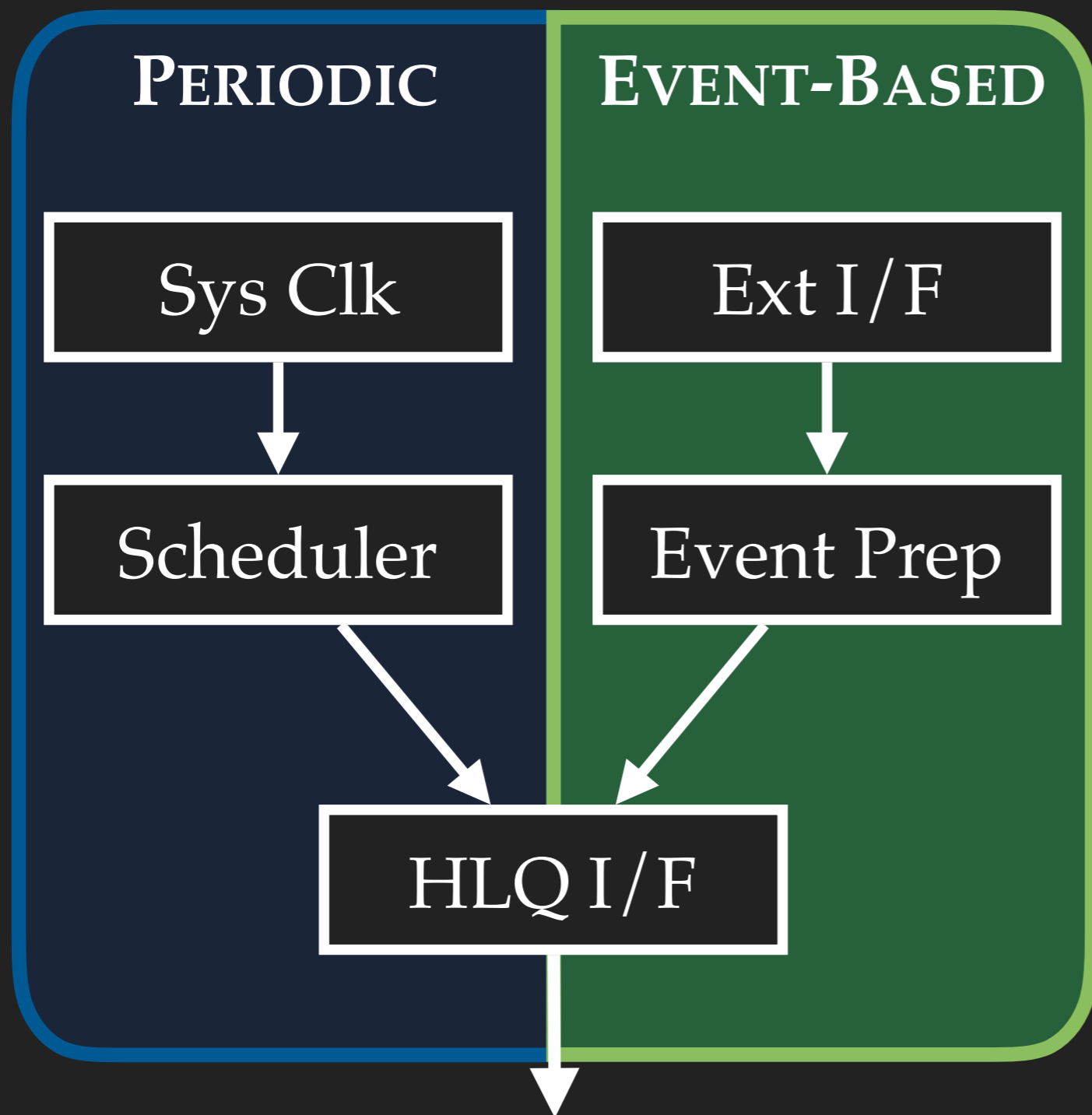
FROM RTLOLA TO VHDL



HIGH-LEVEL CONTROLLER



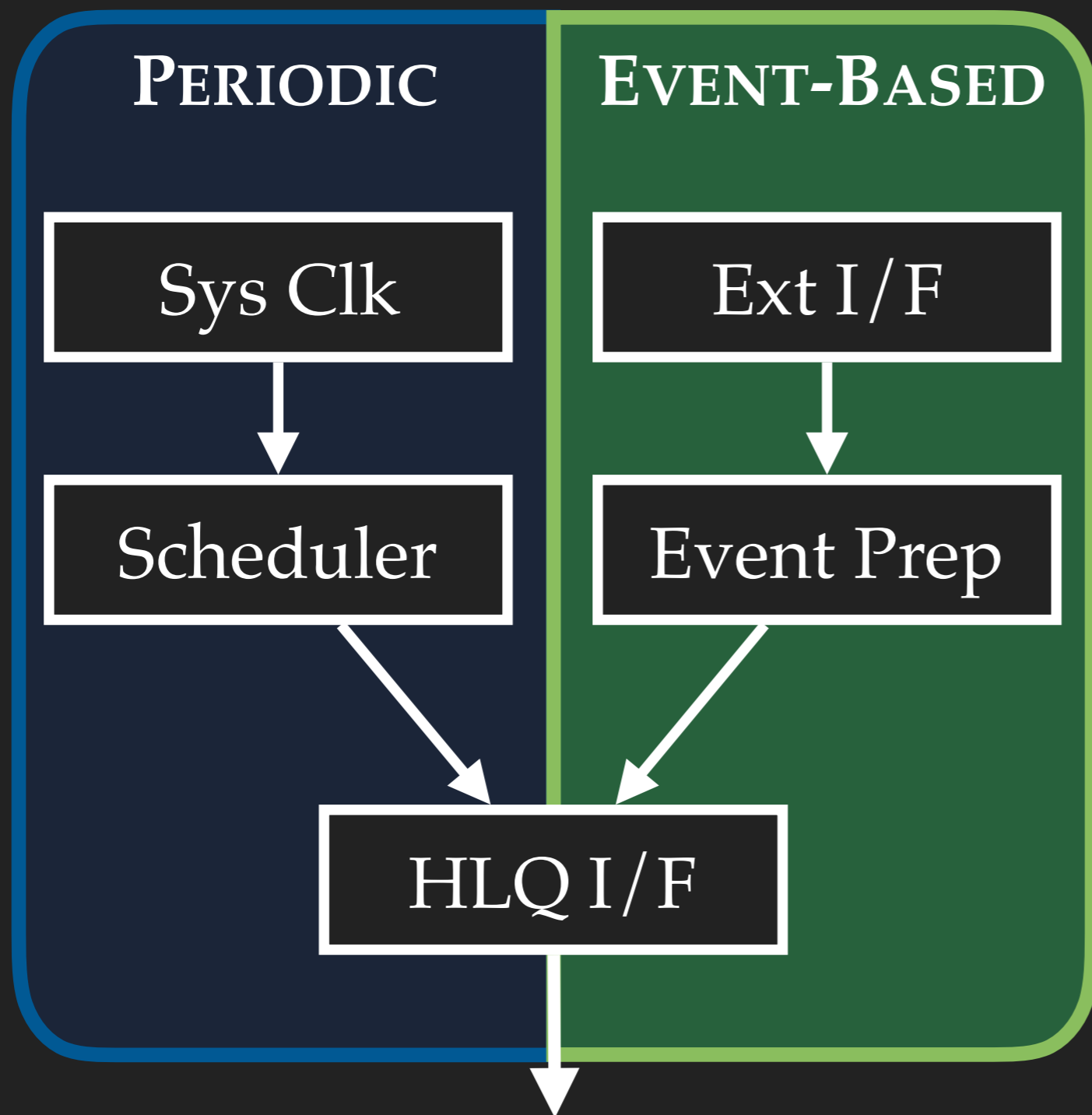
HIGH-LEVEL CONTROLLER



$in_1 \rightarrow 3.4$
 $in_2 \rightarrow T$
 $in_4 \rightarrow 9$
 $time \rightarrow 4:15pm$

<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER

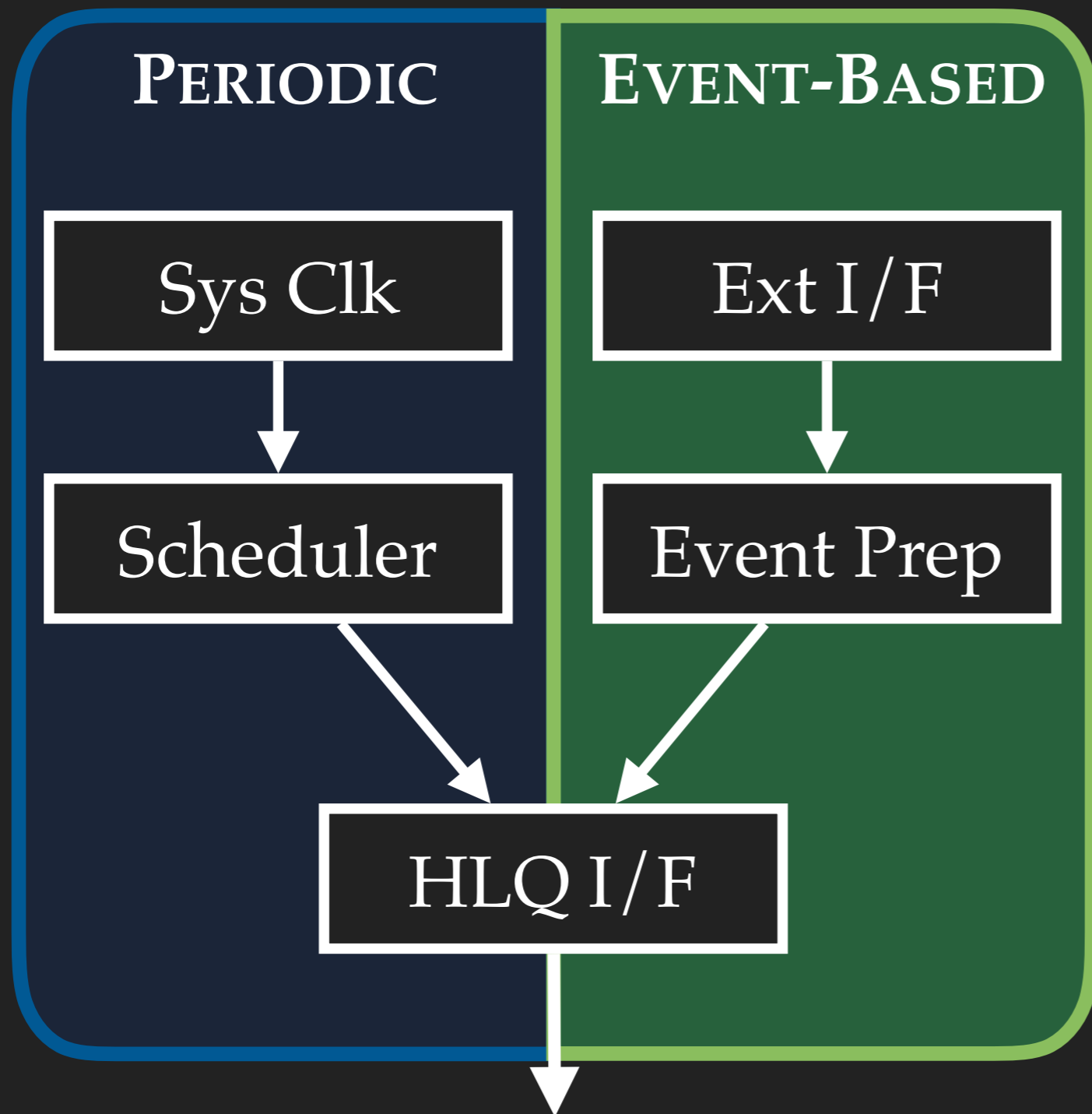


$in_1 \rightarrow 3.4$
 $in_2 \rightarrow \top$
 $in_4 \rightarrow 9$
 $time \rightarrow 4:15pm$

$3.4, \top, \#, 9;$
 $in_1, in_2, in_4, out_2, \dots$
 $4:15pm$

<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER



$in_1 \rightarrow 3.4$

$in_2 \rightarrow \top$

$in_4 \rightarrow 9$

$time \rightarrow 4:15pm$

$3.4, \top, \#, 9;$

$in_1, in_2, in_4, out_2, \dots$
 $4:15pm$

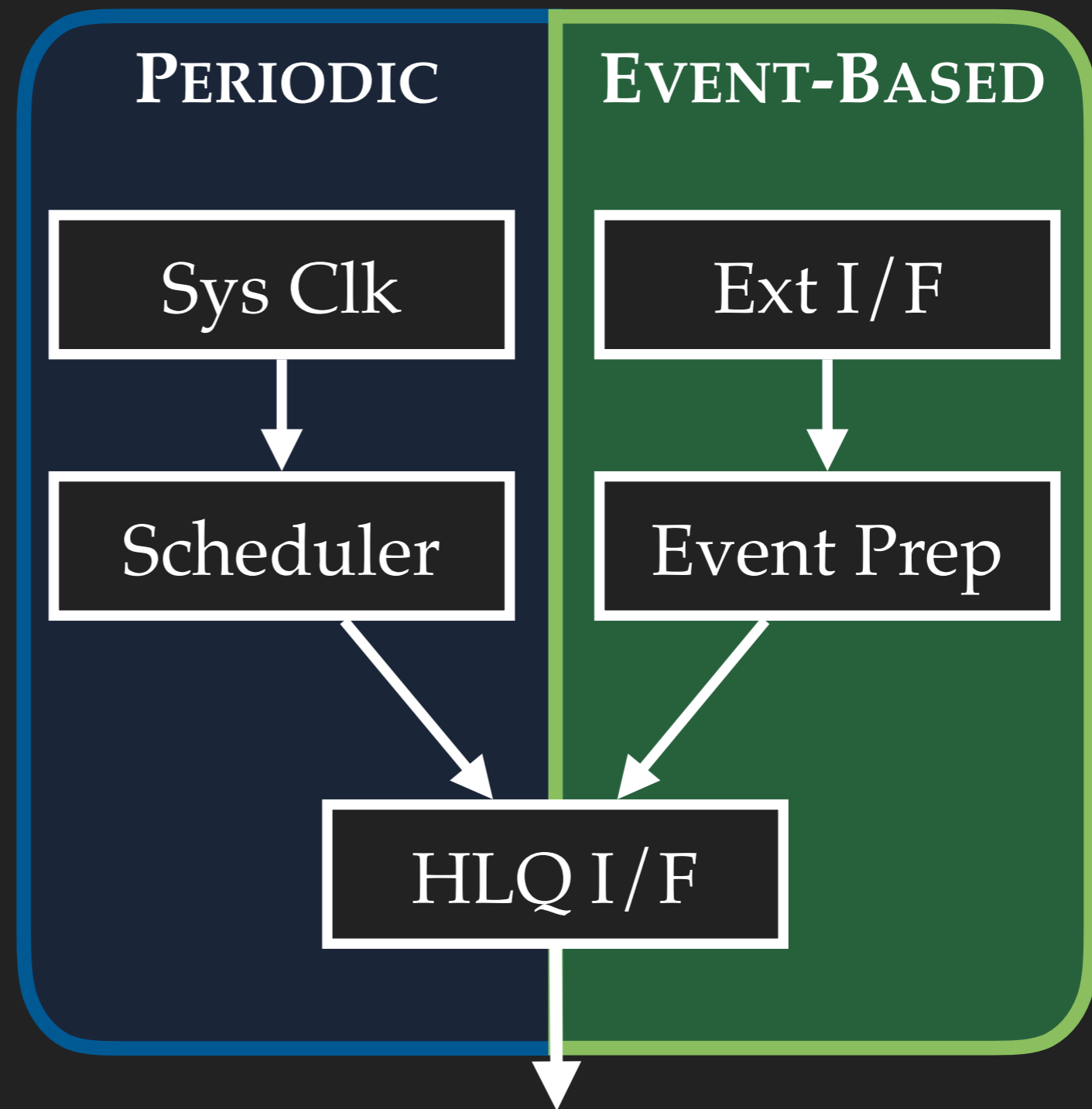
$3.4, \top, \#, 9;$

$110101\dots$

$4:15pm$

<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

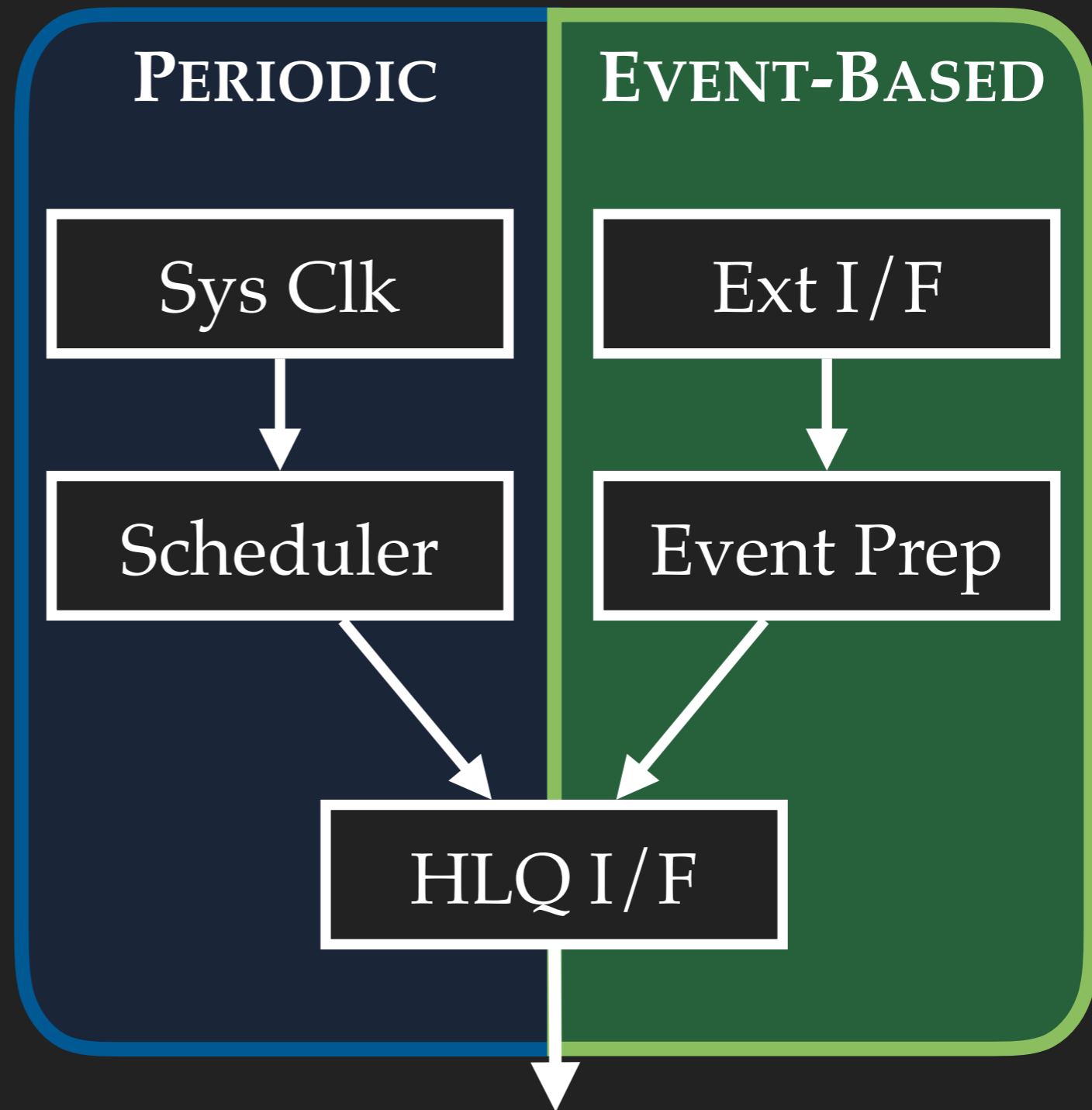
HIGH-LEVEL CONTROLLER



<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER

4:21pm

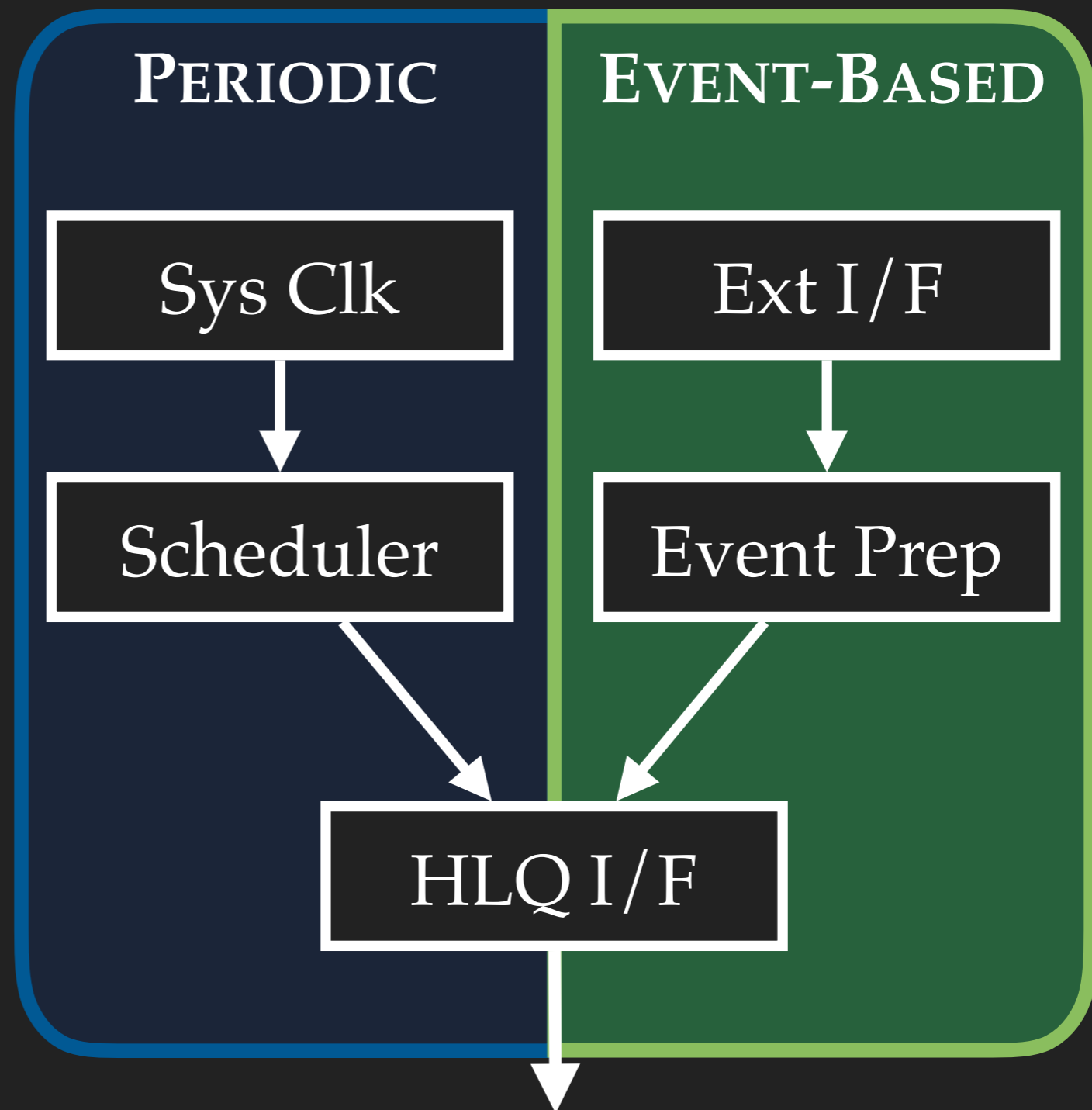


<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER

4:21pm

$out_1, out_3, out_4, \dots$



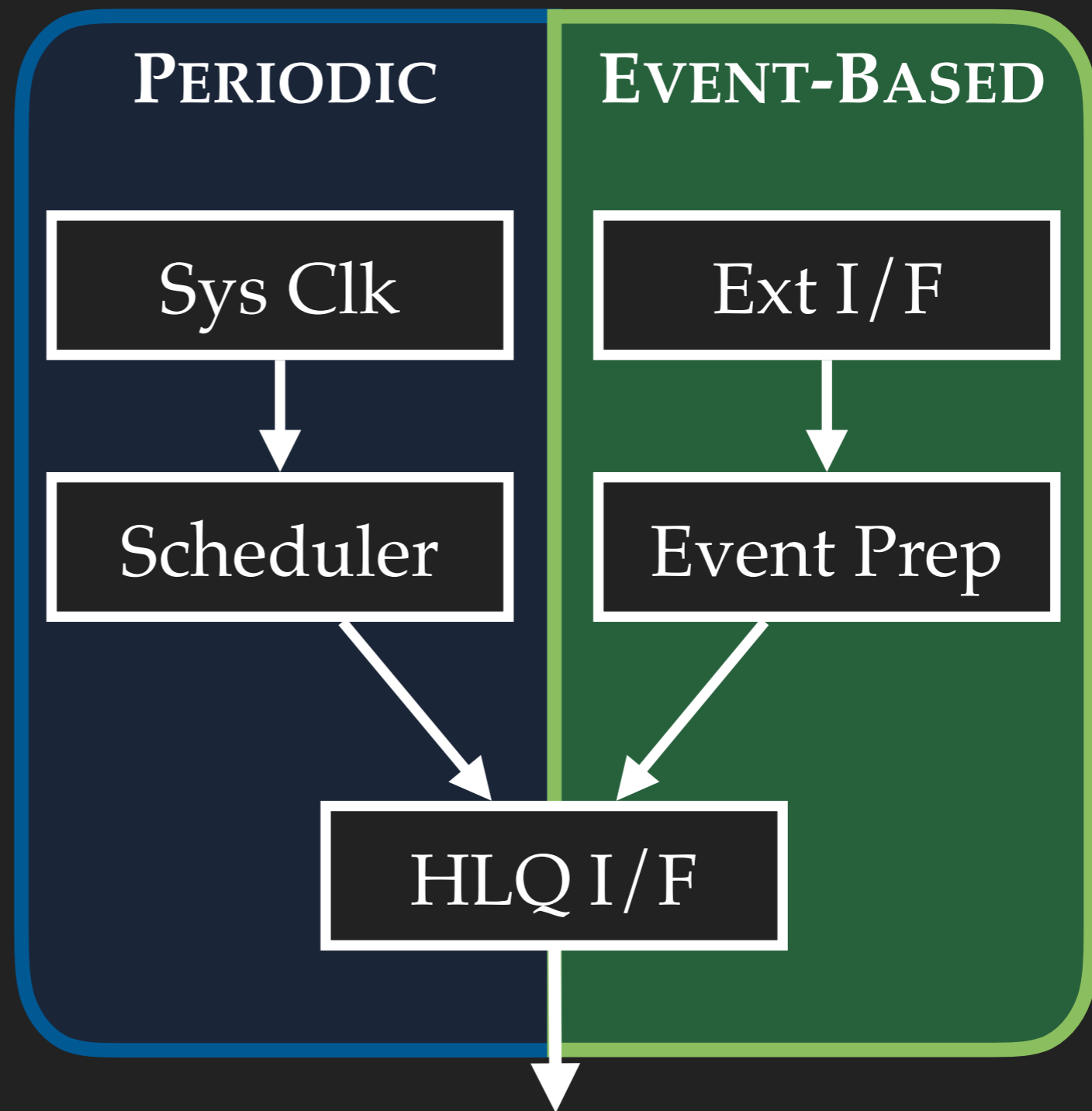
<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER

4:21pm

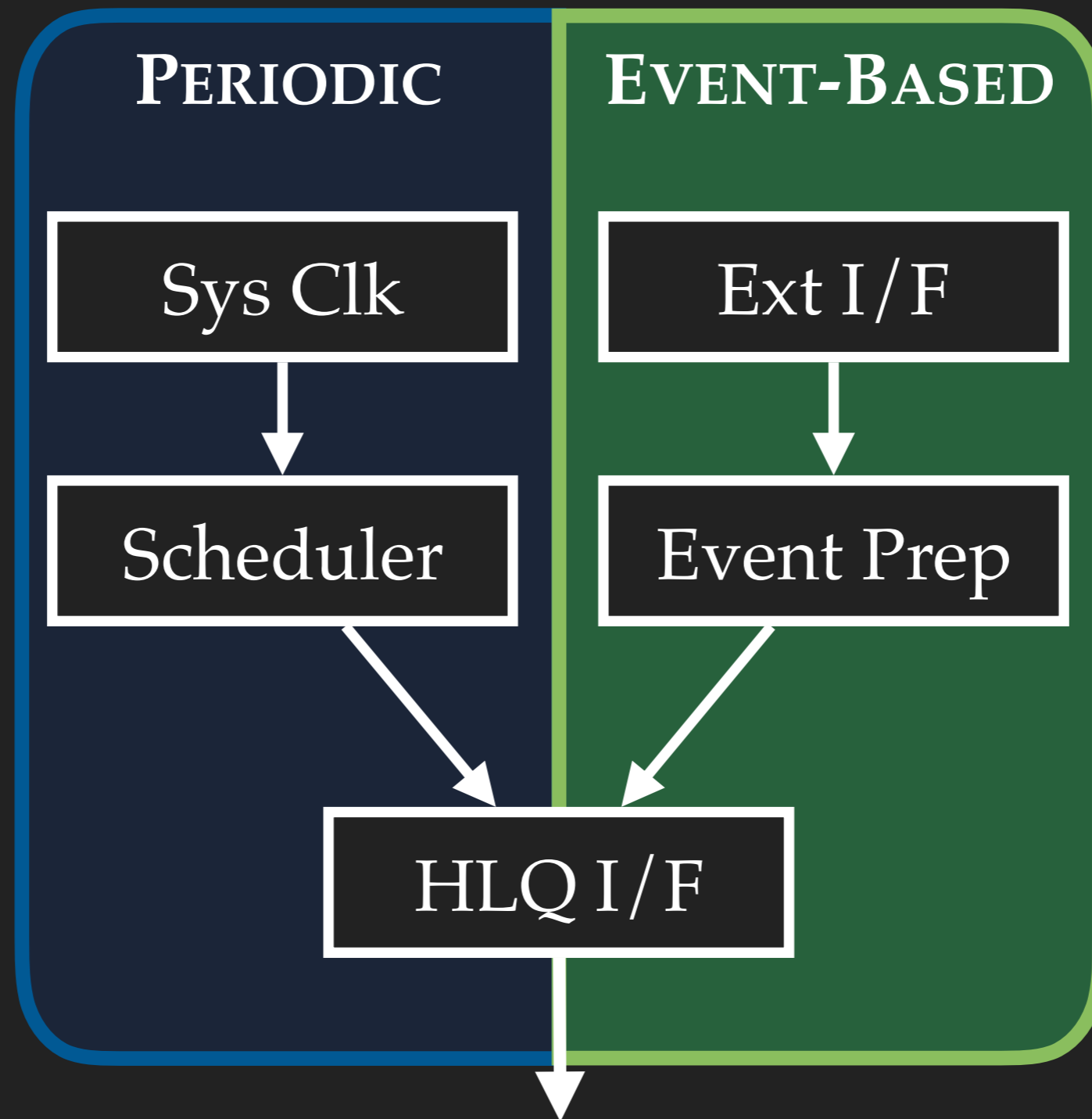
$out_1, out_3, out_4, \dots$

0...0;
00001011...
4:21pm



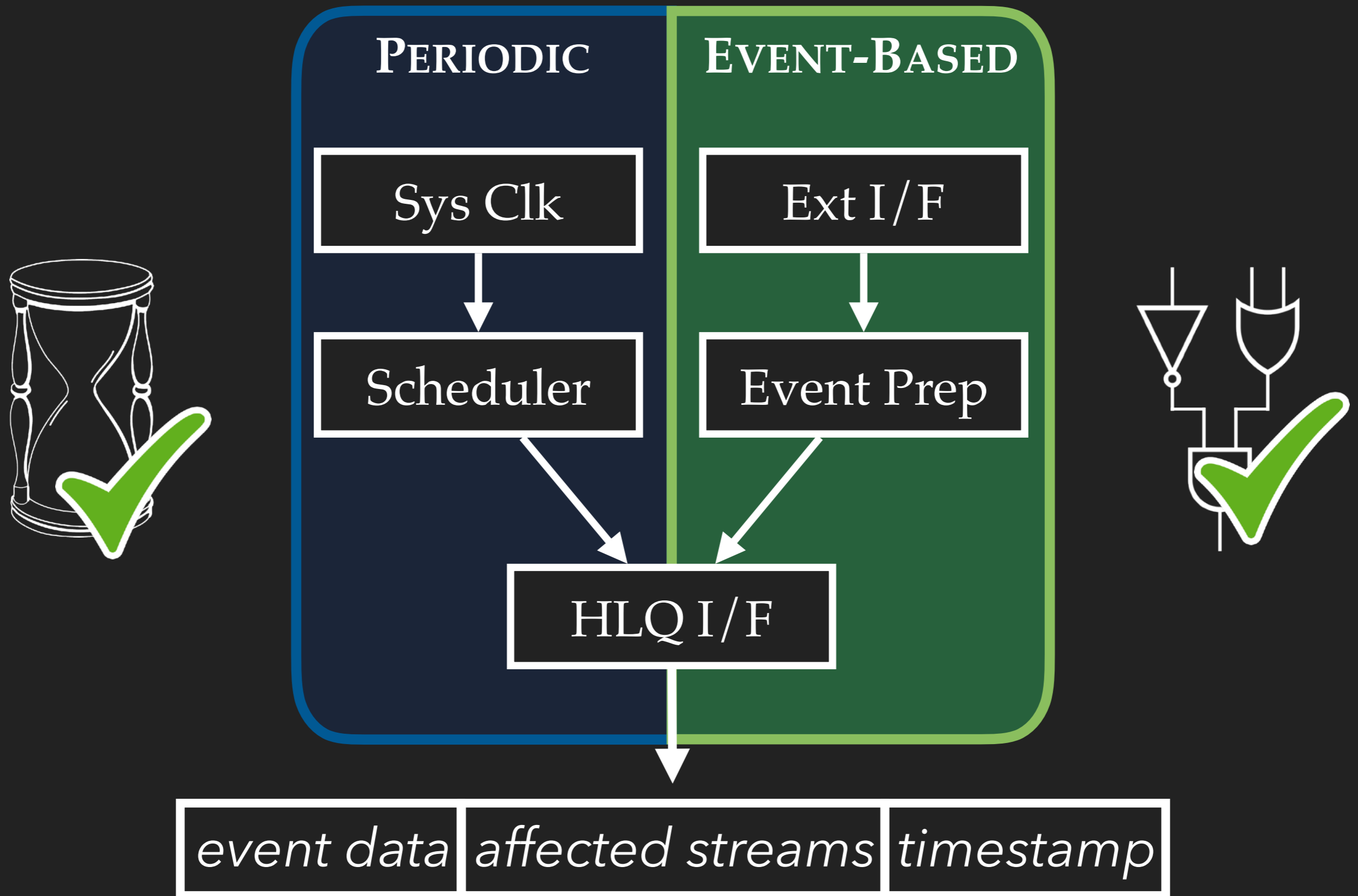
<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

HIGH-LEVEL CONTROLLER

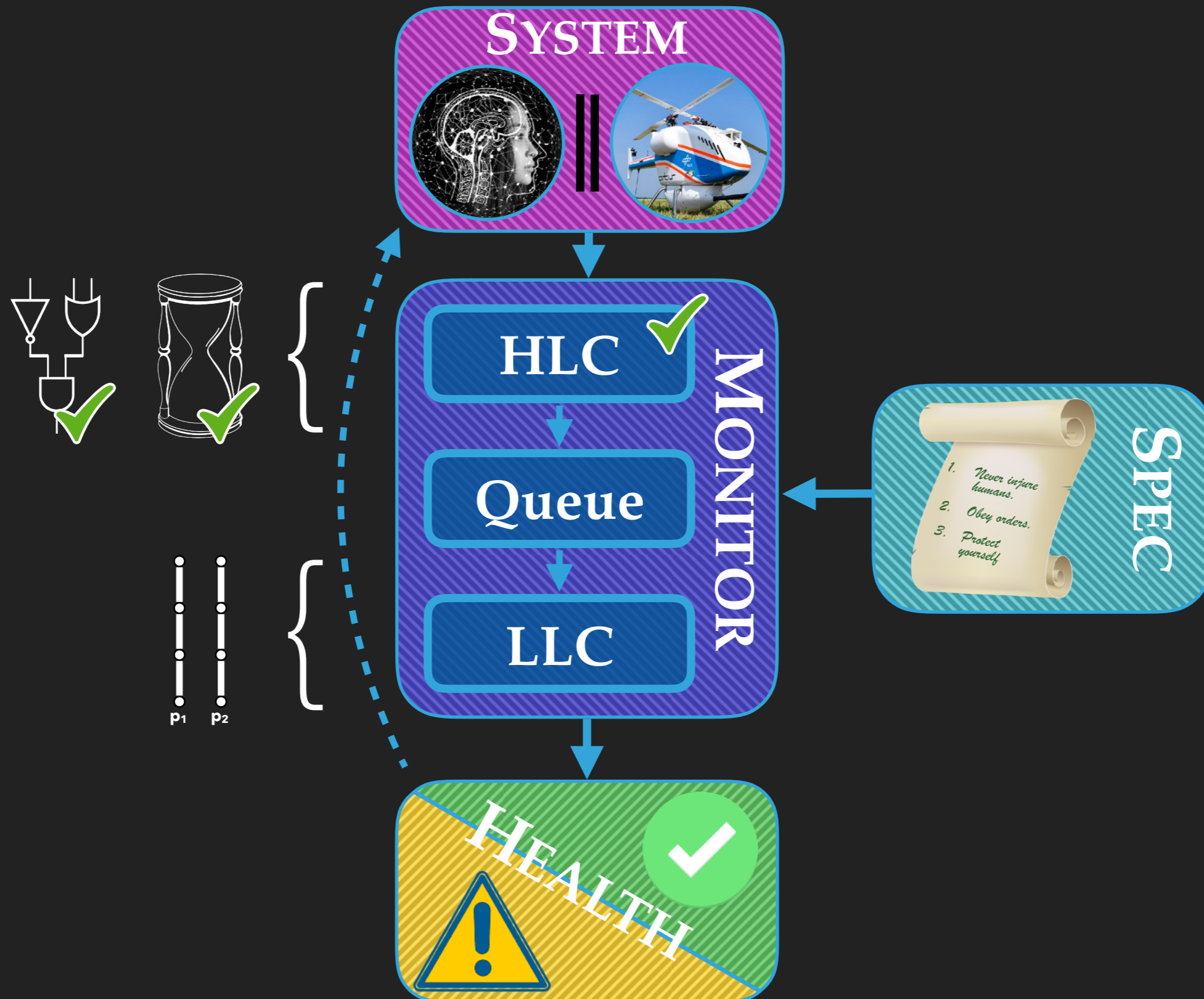


<i>event data</i>	<i>affected streams</i>	<i>timestamp</i>
-------------------	-------------------------	------------------

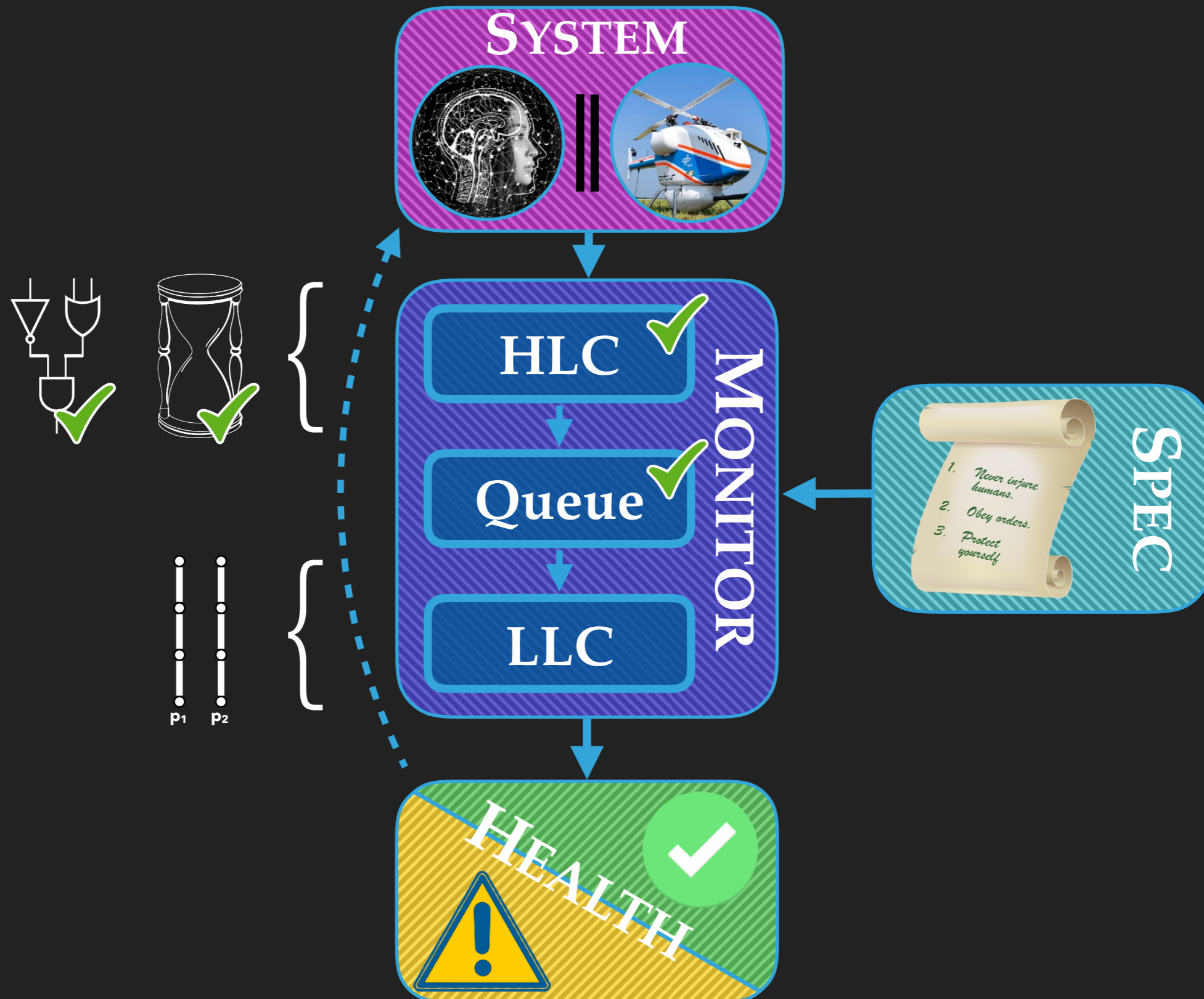
HIGH-LEVEL CONTROLLER



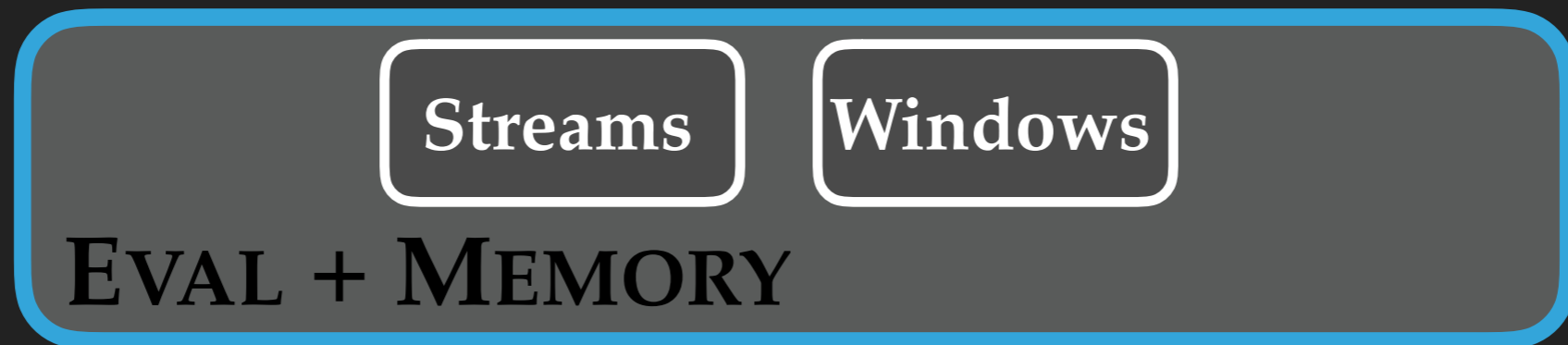
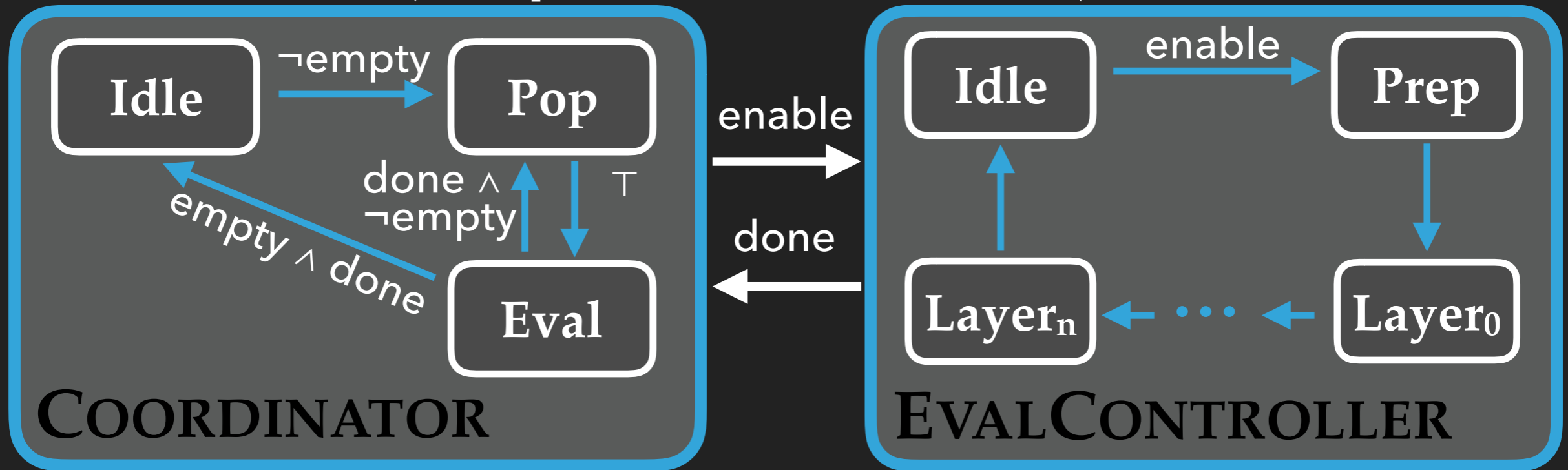
FROM RTLOLA TO VHDL



FROM RTLOLA TO VHDL



LOW-LEVEL CONTROLLER



LLC

SPECIFICATION

DEPENDENCY GRAPH

input lat, lon, velo: **Float64**

input slow_down_cmd: **Bool**

output gps_freq @1Hz :=

lat.aggregate(over_exactly: 1s, using: count)

trigger gps_freq < 5

“GPS frequency less than 5 Hz.”

output gps_dist := sqrt($\delta(\text{lon})^2 + \delta(\text{lat})^2$)

output gps_velo := $\nabla(\text{gps_dist})$

trigger abs(gps_velo - velo) > 0.1

“Conflicting measurements for velocity.”

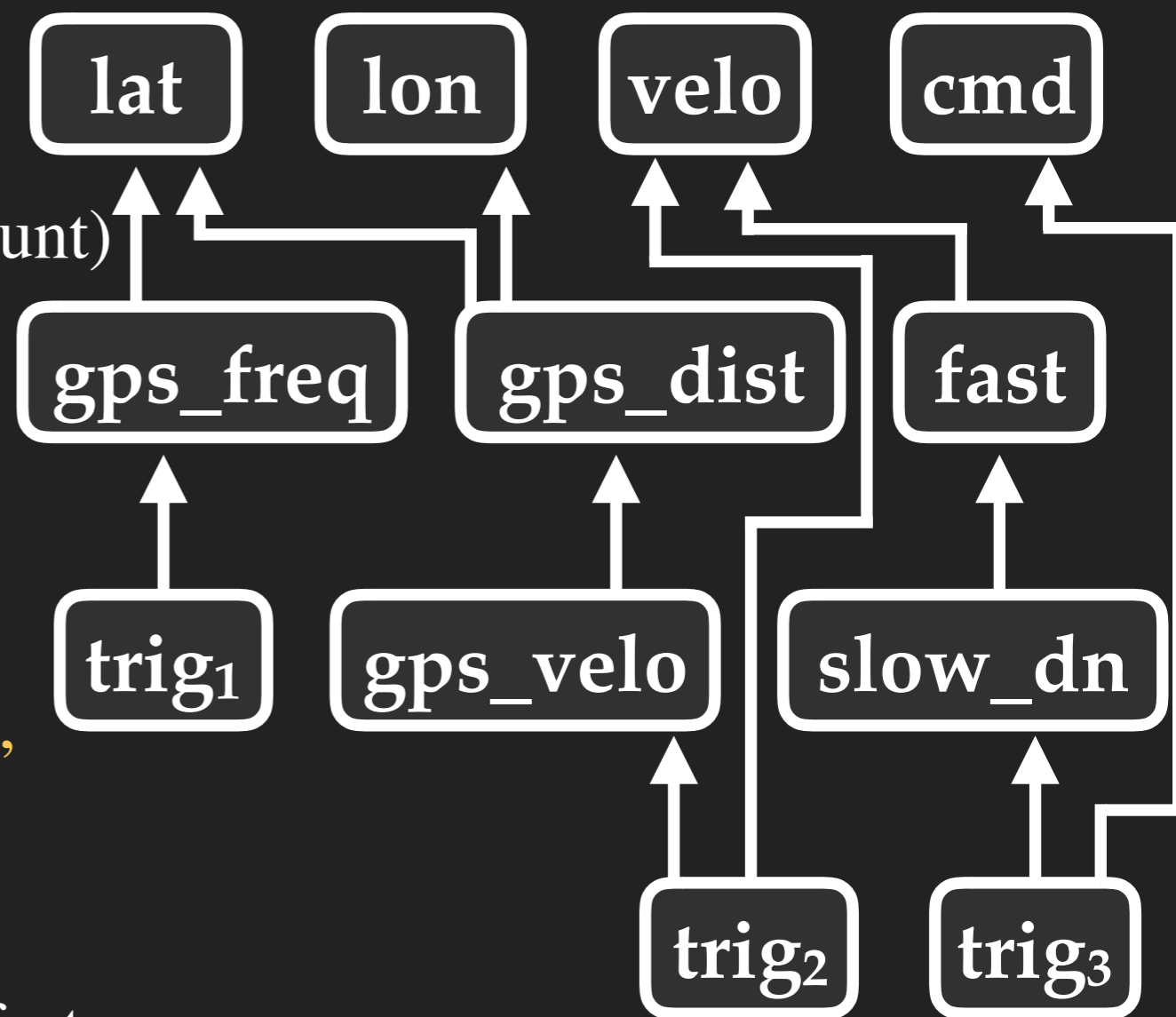
output fast := velo > 700

output slow_down :=

fast.offset(by: -1).defaults(to: false) \wedge \neg fast

trigger @1Hz \neg slow_down_cmd.aggregate(over: 5s, using: \exists)

\wedge slow_down.hold().defaults(to: false) “Spurious Slow-Down.”



SPECIFICATION

DEPENDENCY GRAPH

input lat, lon, velo: Float64

input slow_down_cmd: Bool

output gps_freq @1Hz :=

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trigger abs(gps_velo - velo) > 0.1

“Conflicting measurements for velocity.”

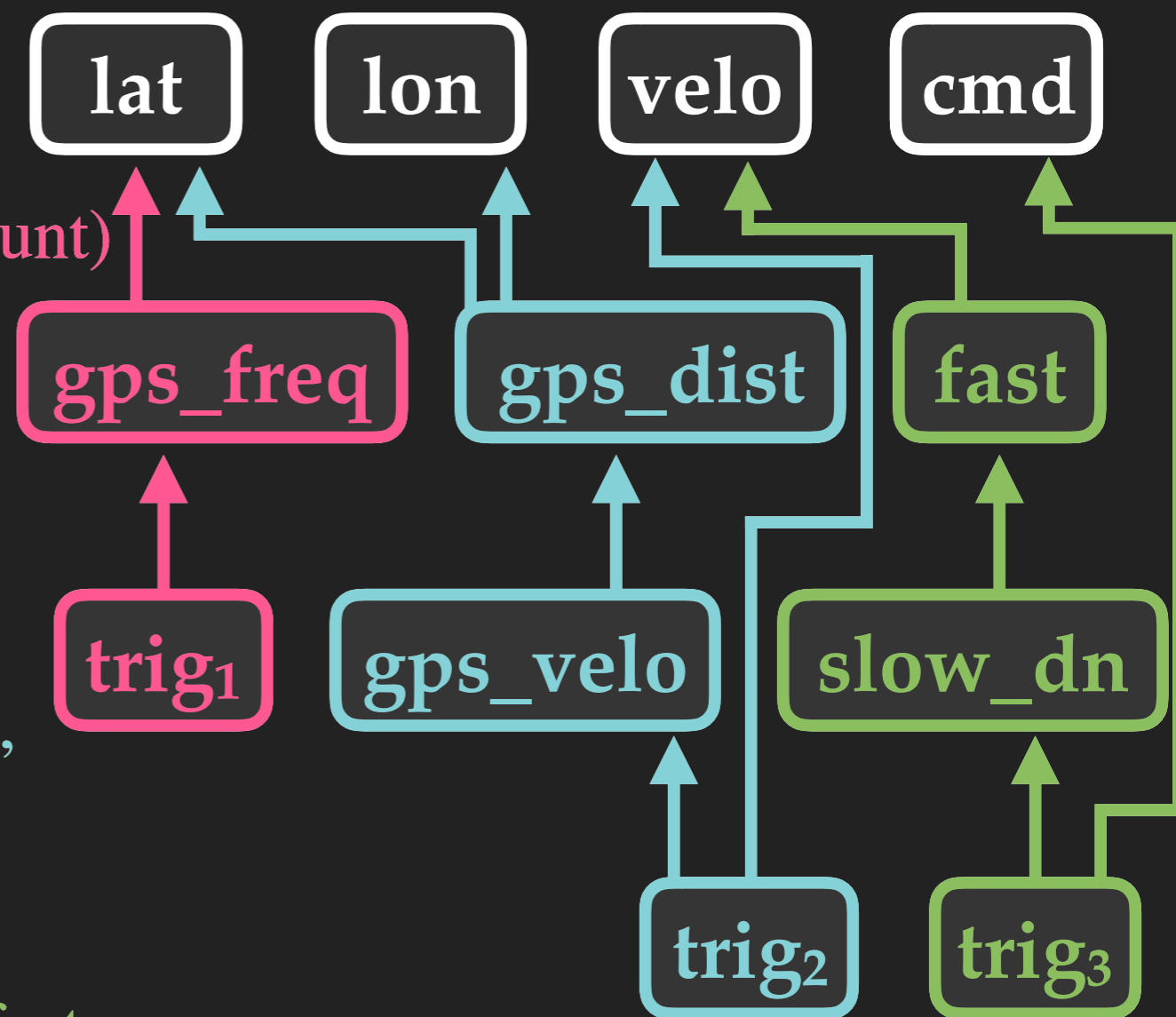
output fast := velo > 700

output slow_down :=

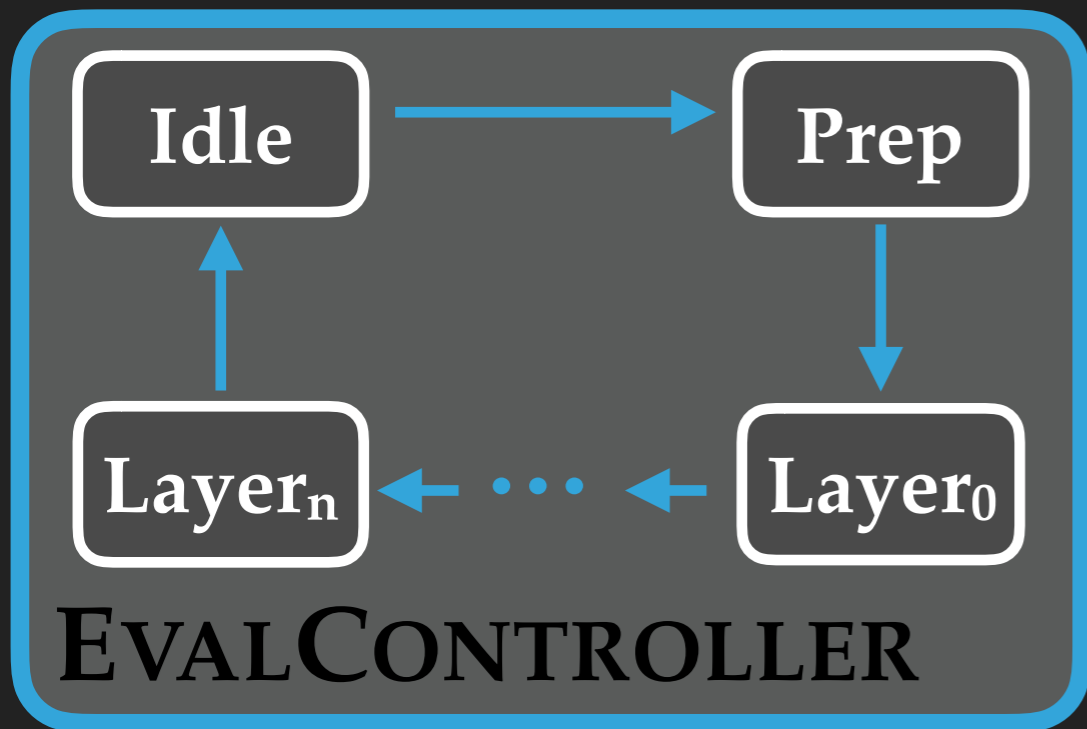
fast.offset(by: -1).defaults(to: false) \wedge \neg fast

trigger @1Hz \neg slow_down_cmd.aggregate(over: 5s, using: \exists)

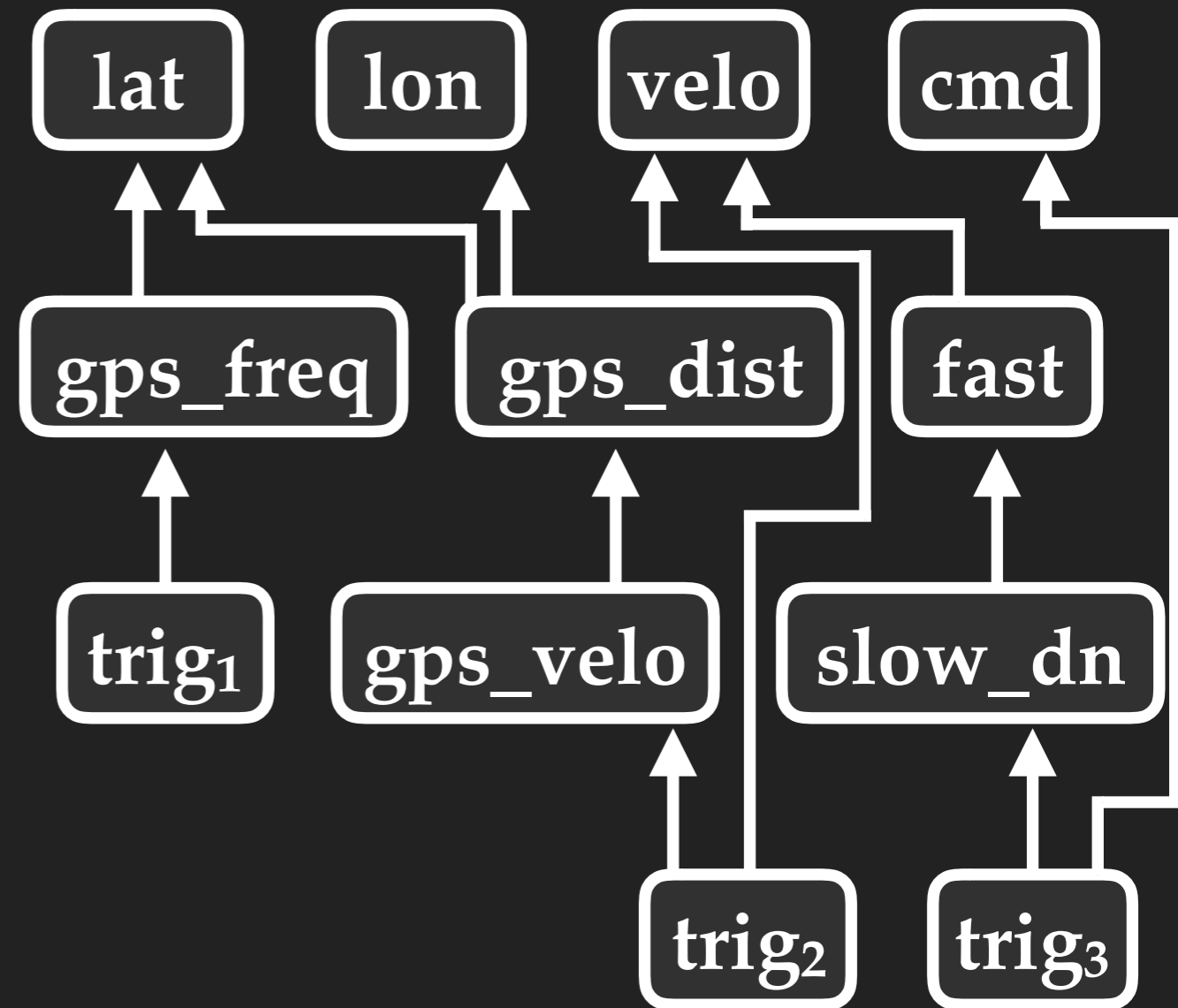
\wedge slow_down.hold().defaults(to: false) “Spurious Slow-Down.”



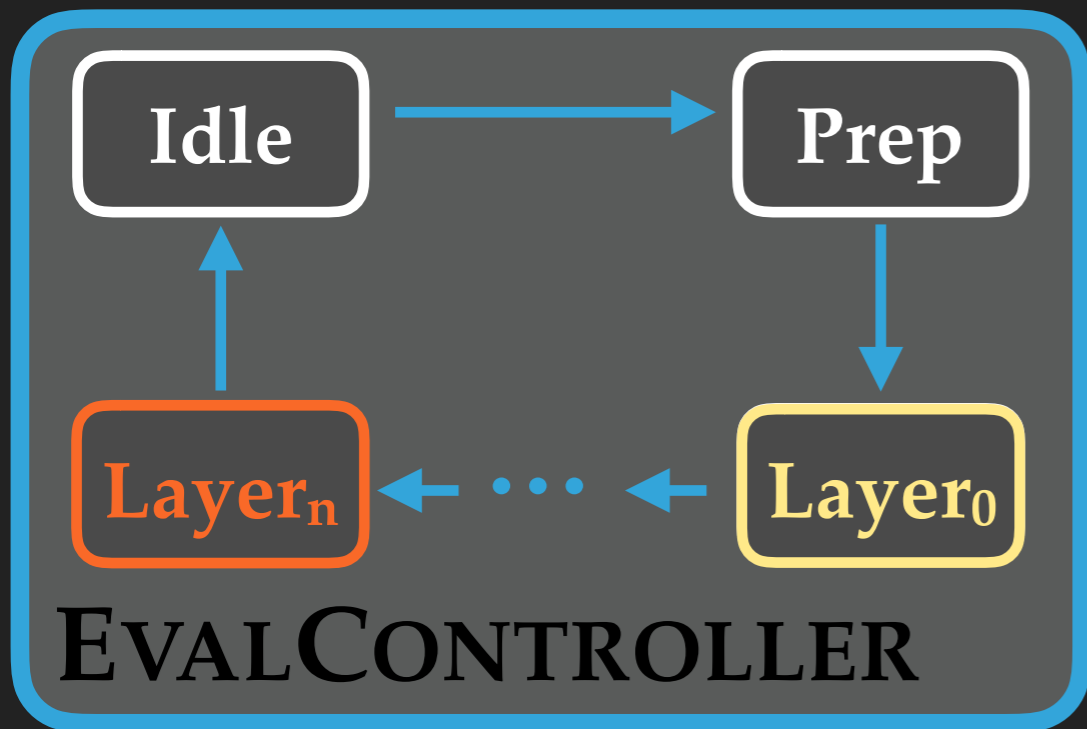
LOW-LEVEL CONTROLLER



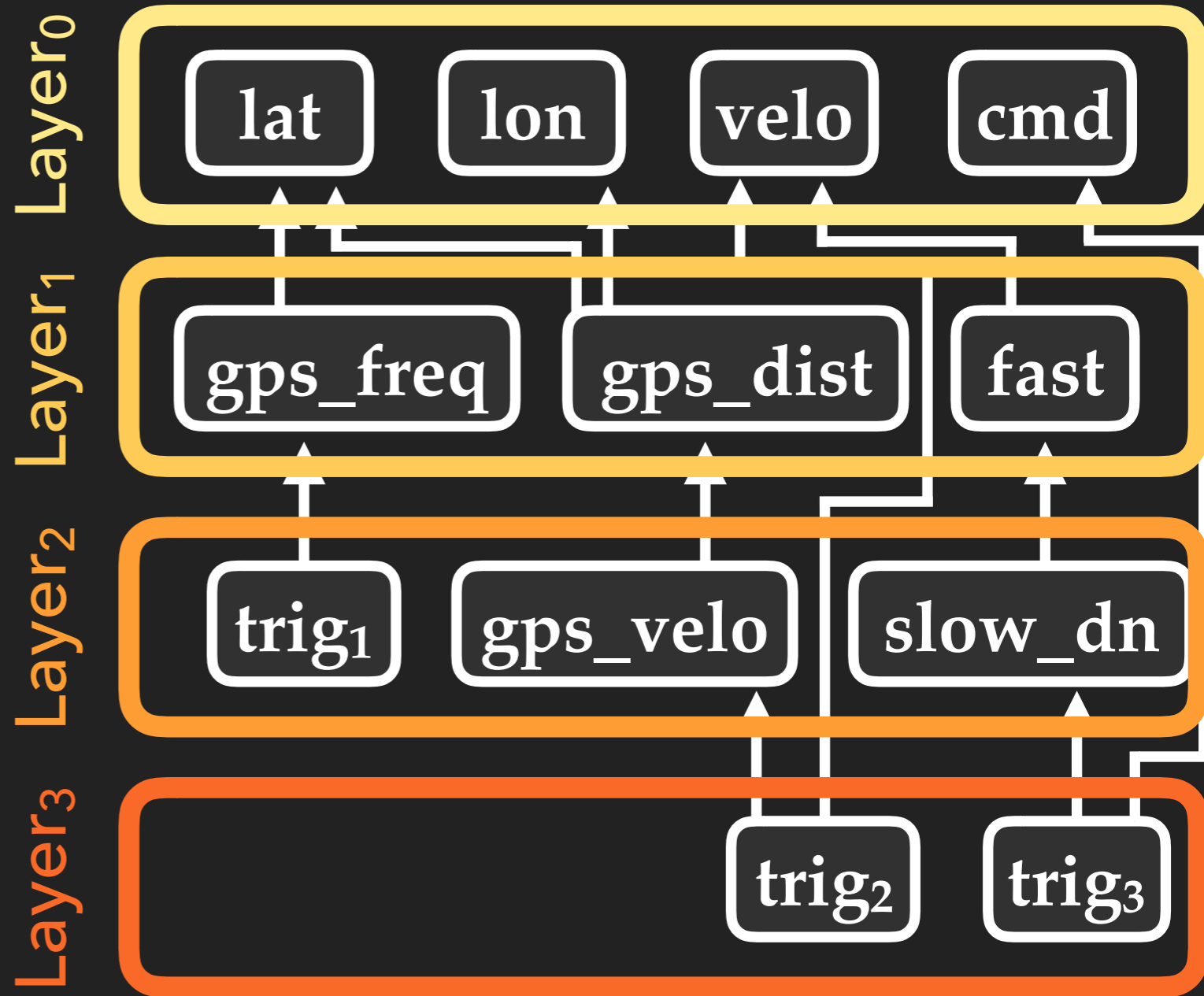
DEPENDENCY GRAPH



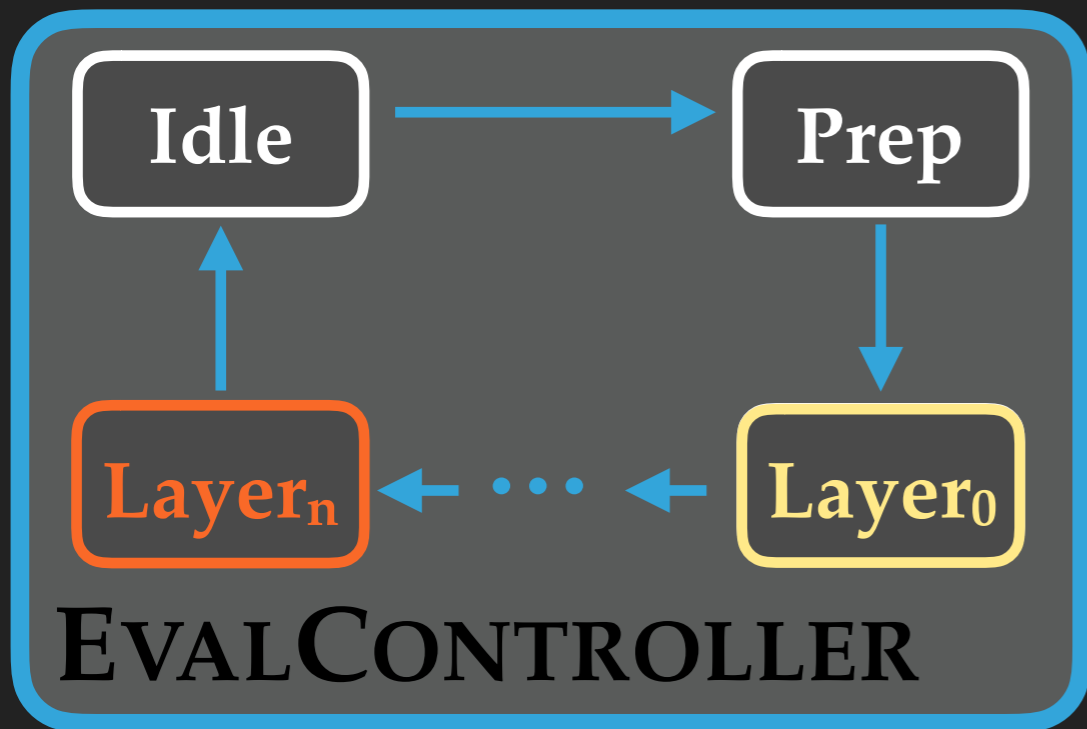
LOW-LEVEL CONTROLLER



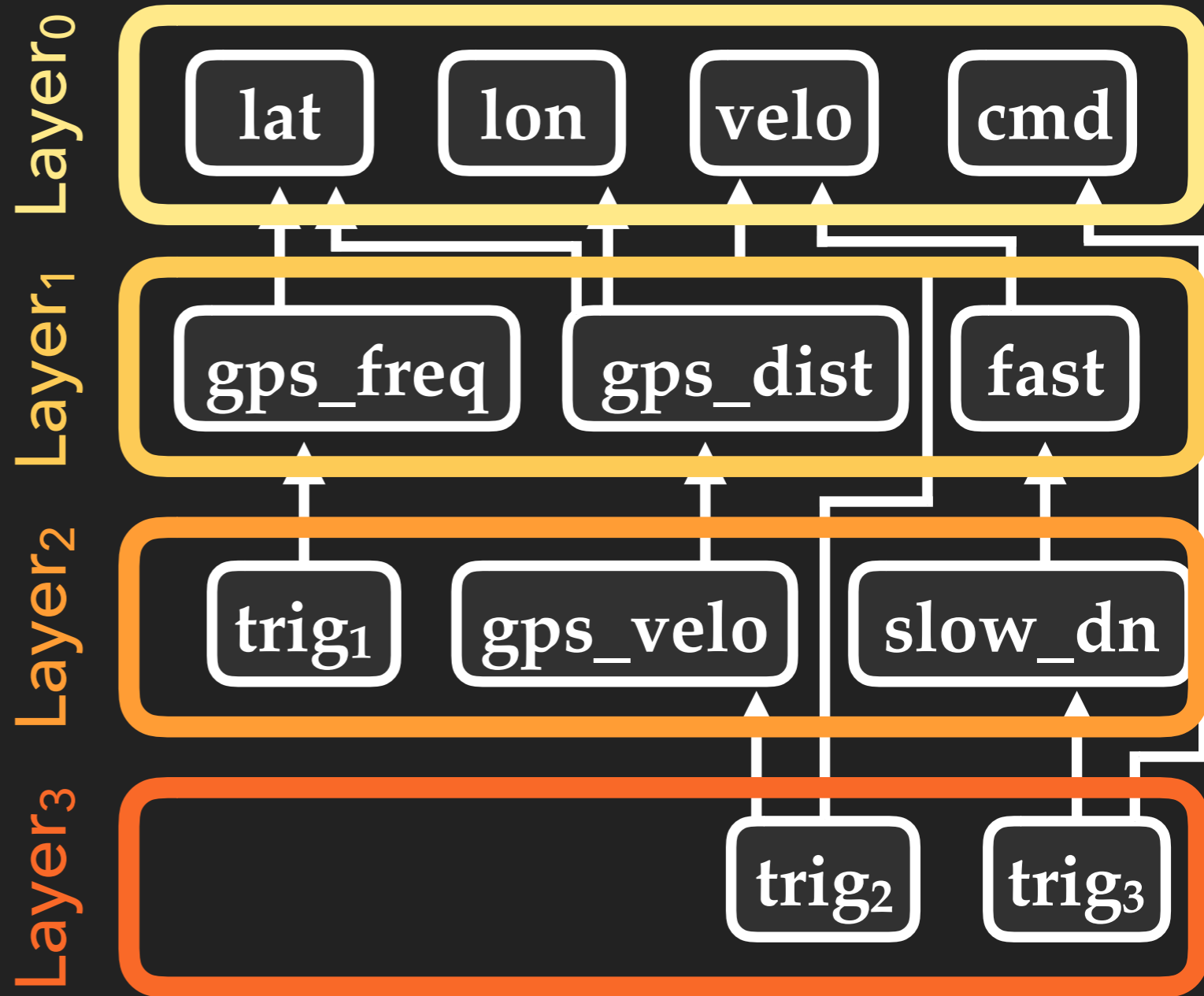
DEPENDENCY GRAPH



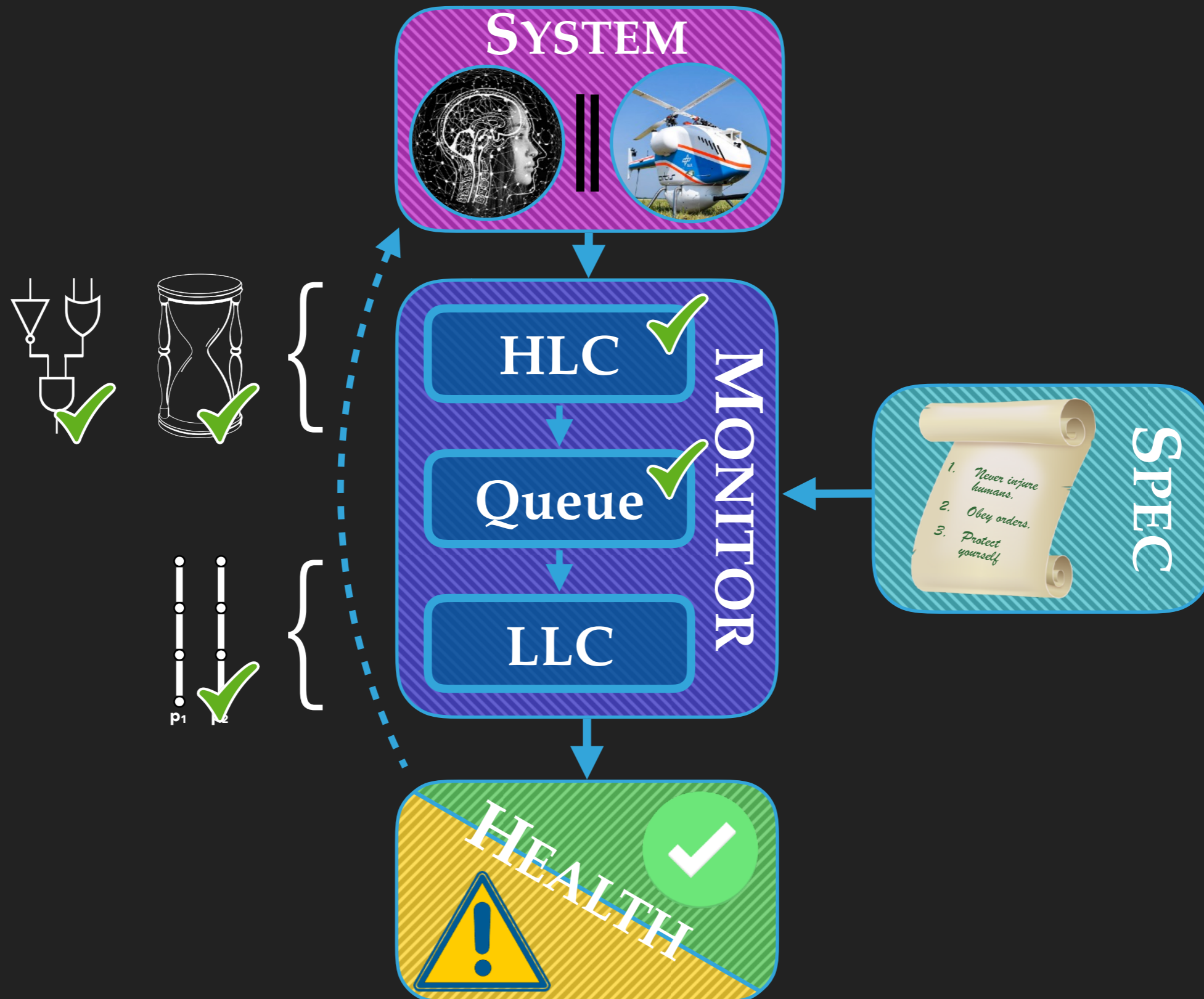
LOW-LEVEL CONTROLLER



DEPENDENCY GRAPH

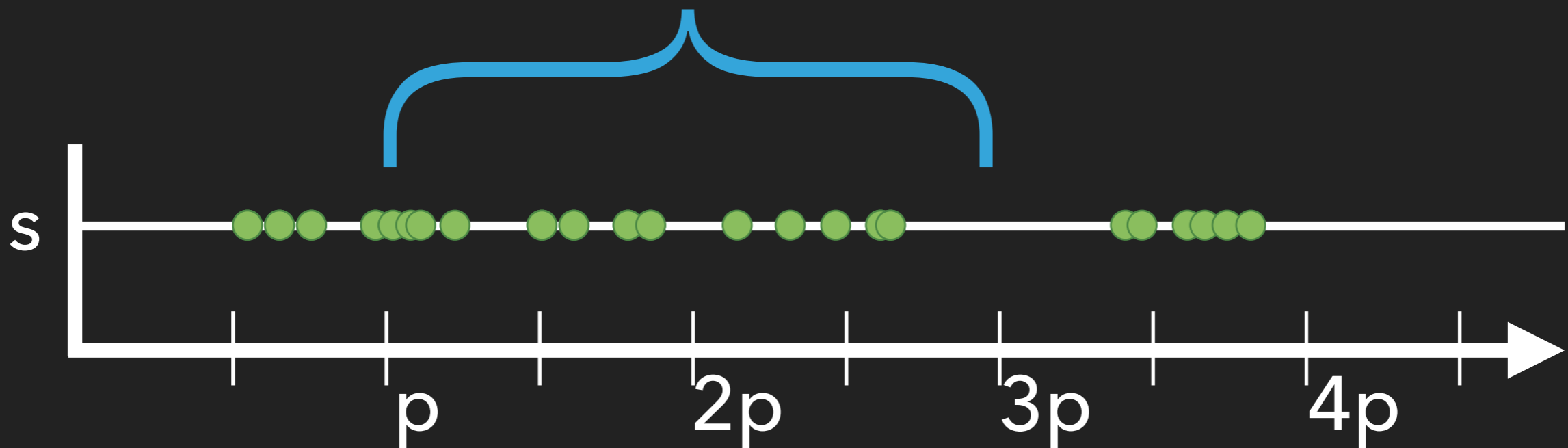


FROM RTLOLA TO VHDL



SLIDING WINDOWS

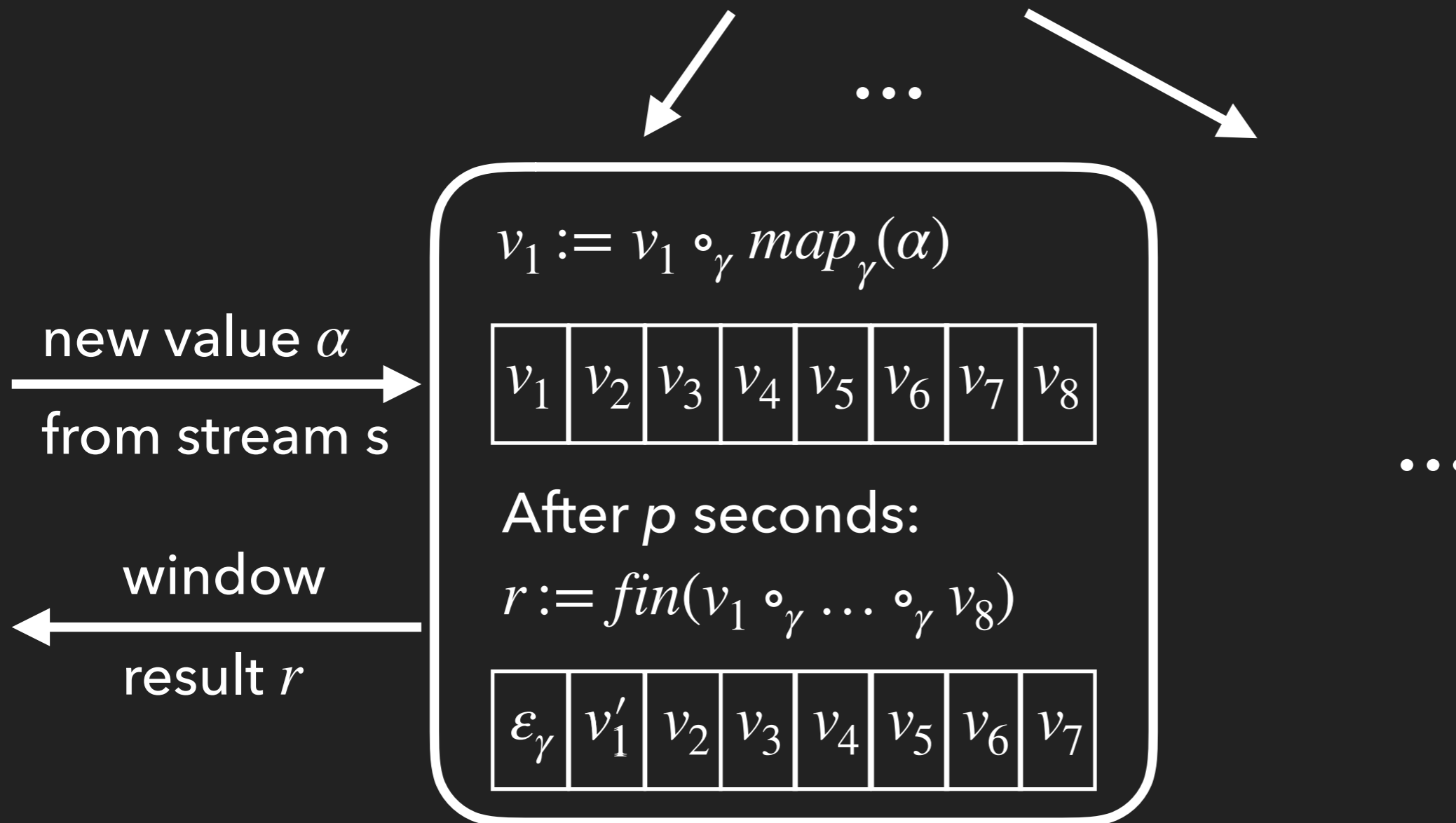
output $h @ p^{-1}\text{Hz} := s.\text{aggregate}(\text{over: } \eta\text{sec}, \text{using: } \gamma)$



- ▶ Li et al.: “No Pane, No Gain: Efficient Evaluation of Sliding-window Aggregates over Data Streams”, SIGMOD Rec. 2005
- ▶ Meertens: “Algorithmics: Towards programming as a mathematical activity”, 1986
- ▶ Schwenger: “Let’s not Trust Experience Blindly: Formal Monitoring of Humans and other CPS”, Master Thesis 2019
- ▶ Faymonville, Finkbeiner, Schledjewski, Schwenger, Stenger, Tentrup, Torfah, “StreamLAB: Stream-based Monitoring of Cyber-physical Systems”, CAV 2019

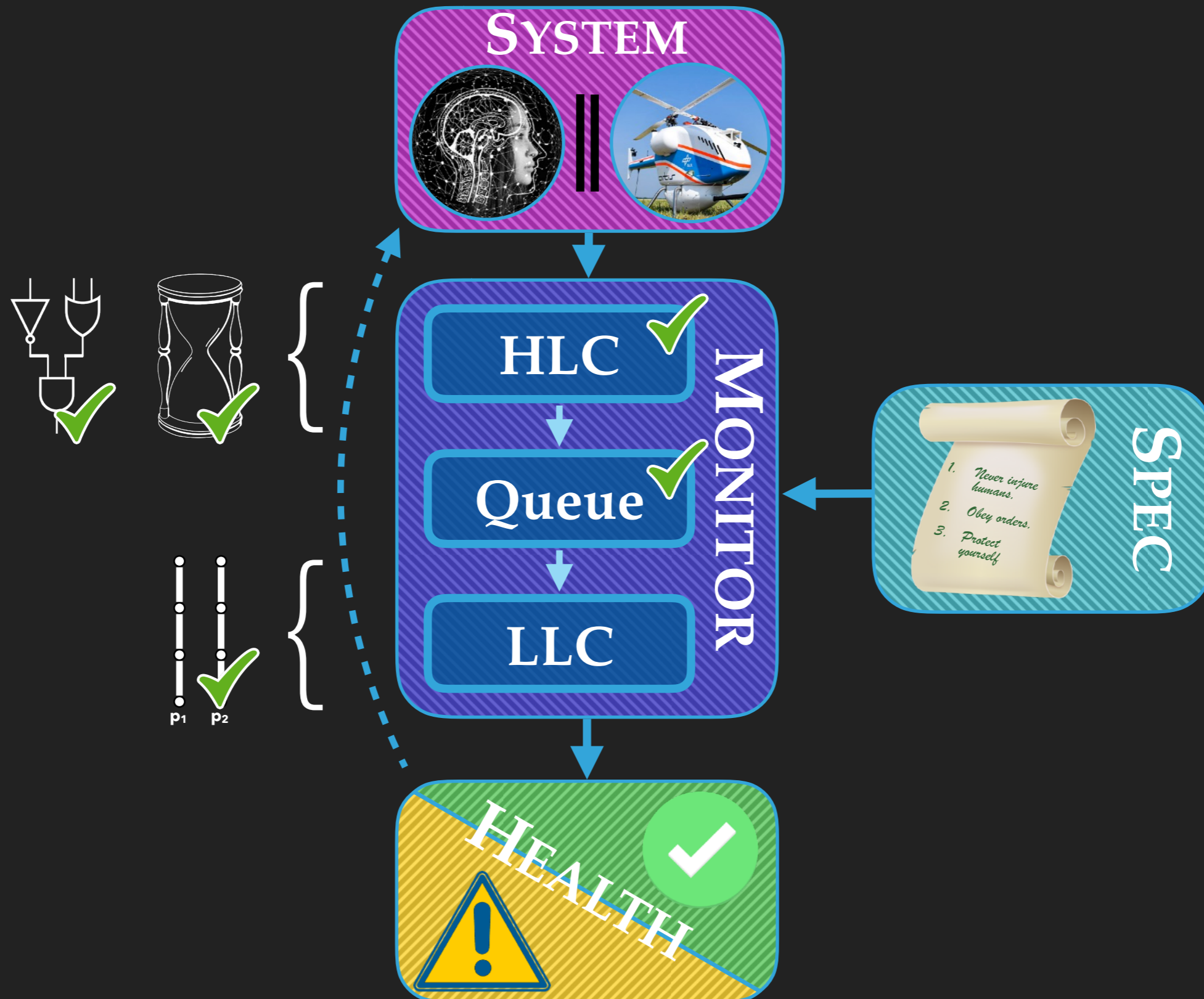
HONORABLE MENTION: SLIDING WINDOWS

output $h @ p^{-1}\text{Hz} := s.\text{aggregate}(\text{over: } \eta\text{sec}, \text{using: } \gamma)$

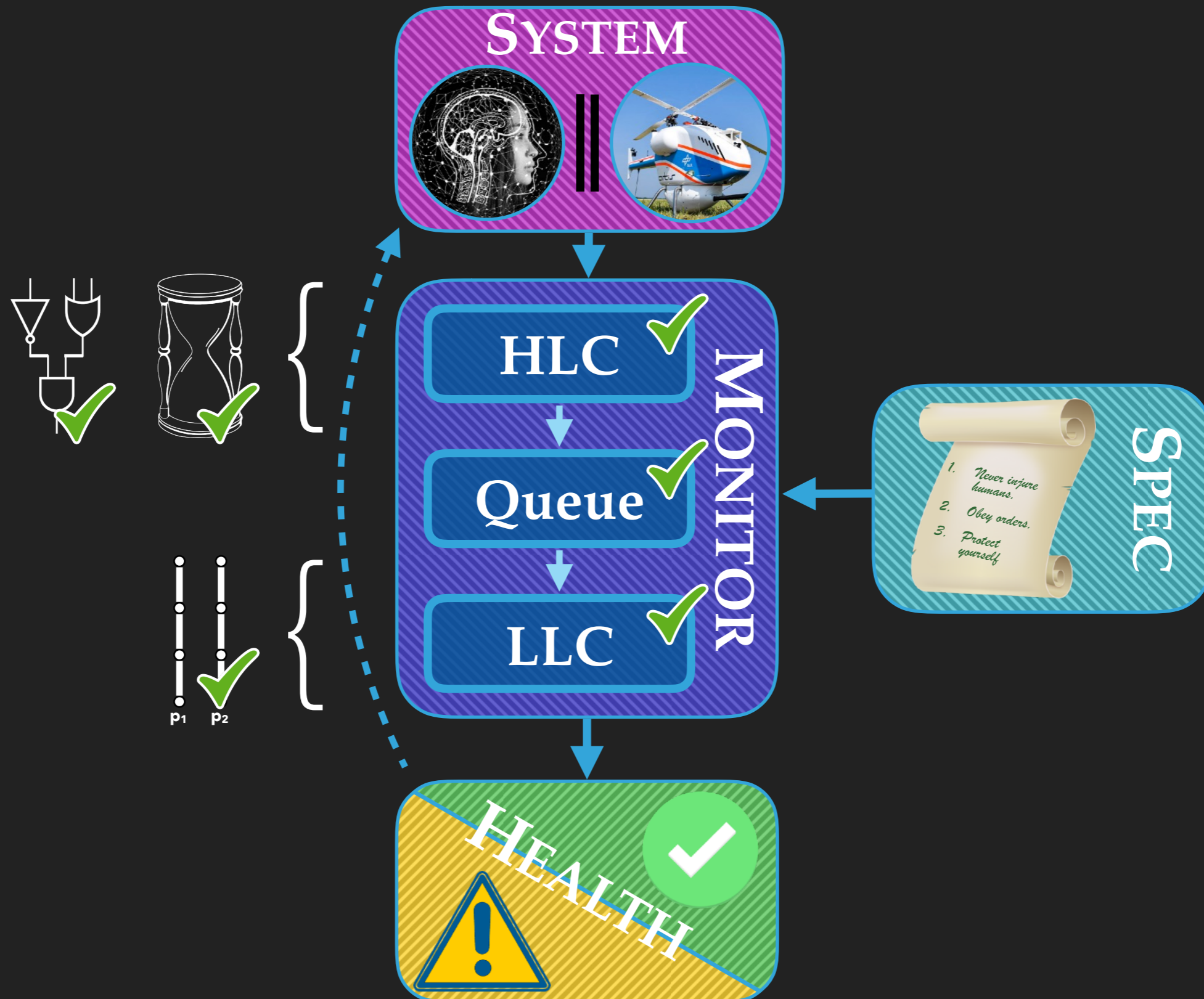


- ▶ Li et al.: “No Pane, No Gain: Efficient Evaluation of Sliding-window Aggregates over Data Streams”, SIGMOD Rec. 2005
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FROM RTLOLA TO VHDL




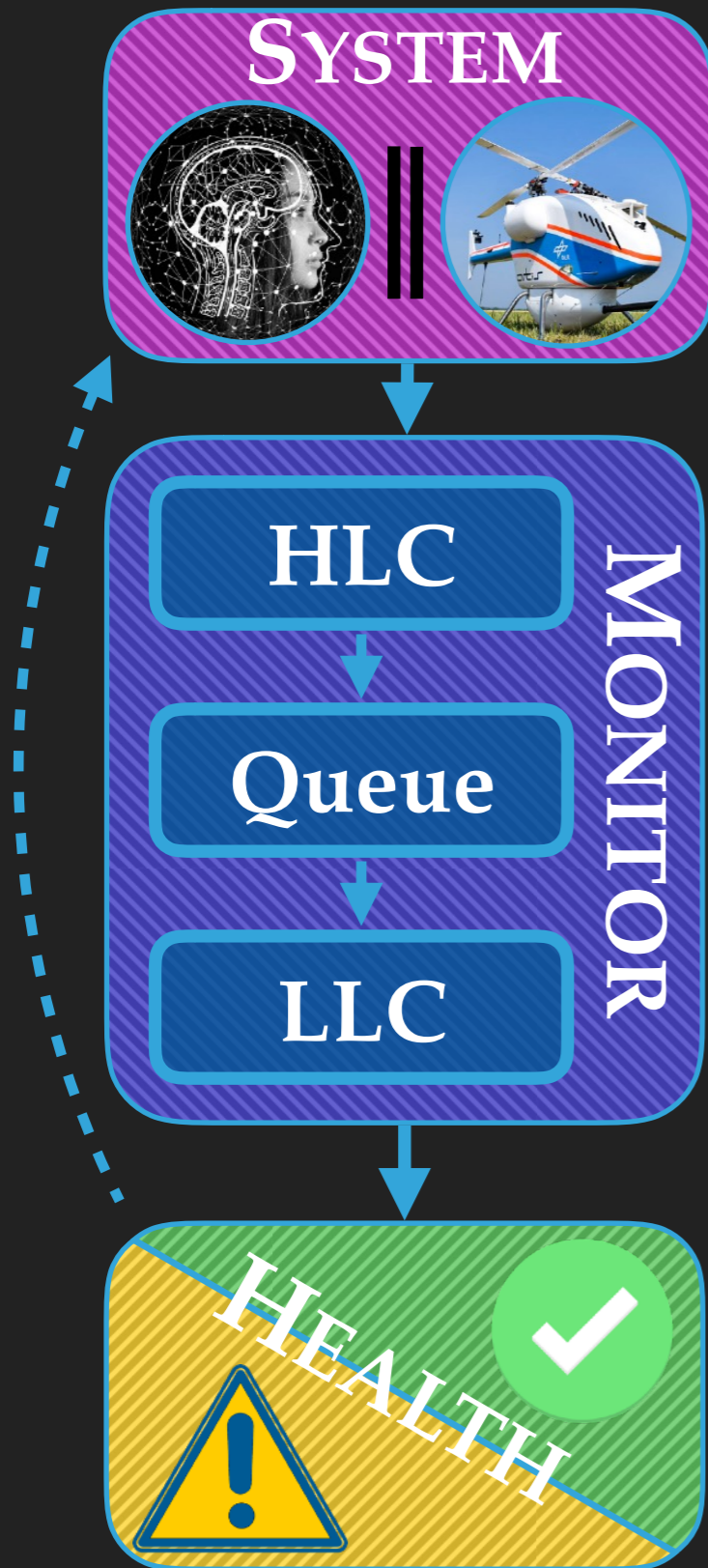
FROM RTLOLA TO VHDL



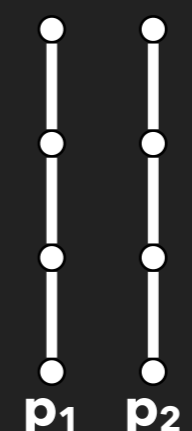
EVALUATION

		FF	LUT	MUX	CA	MULT	Pwr [W]	Time [μ s]
Drone	Mon	3036	3685	26	656	10	1.620	4.28
	HLC	901	156	0	22	0		
	Q	543	442	0	43	0		
	LLC	1281	2820	0	576	10		
Network	Mon	1905	1533	23	226	23	1.570	3.20
	HLC	550	161	0	37	0		
	Q	330	342	0	28	0		
	LLC	895	927	0	161	0		
Cmd Resp Par	Mon	6379	13794	0	849	0	1.582	3.77
	HLC	936	232	0	30	0		
	Q	540	326	0	28	0		
	LLC	4903	13236	0	971	0		
Cmd Resp Seq	Mon	6909	14768	0	851	0	1.581	43.83
	HLC	936	232	0	30	0		
	Q	534	326	0	28	0		
	LLC	5433	14210	0	973	0		


CONCLUSION



**Periodic
versus
Event-Based**



**Utilize
Parallel
Execution**



**Reduce
Circuit
Cost**

OUTLOOK



LEARN MORE:
stream-lab.eu