

Systems Design Laboratory

ToolDef

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Recap on the Database Example with CIF and ESCET

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Version: v0.4

Eclipse ESCET™

The Eclipse ESCET project provides a model-based approach and toolkit for the development of supervisory controllers.

[Learn more](#)

Languages and tools



CIF

CIF is a modeling language and extensive toolset supporting the entire development process of supervisory controllers.

[Learn more](#)



Chi

Chi is a modeling language and toolset to analyze the performance of supervisory controllers.

[Learn more](#)



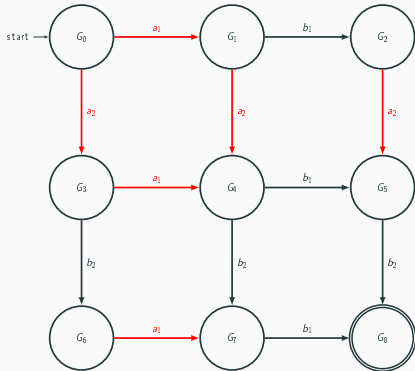
ToolDef

ToolDef is a cross-platform and machine-independent scripting language to automate CIF and Chi tools.

[Learn more](#)

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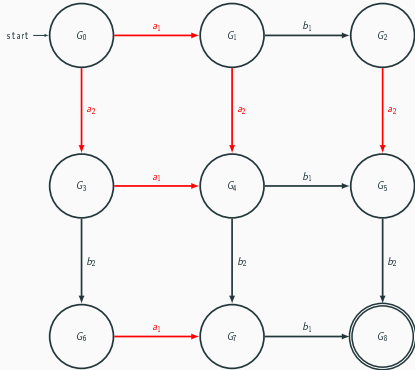
Example 1 - events.cif



- Events a_1, a_2 are uncontrollable
- Events b_1, b_2 are controllable

```
uncontrollable a1, a2;  
controllable b1, b2;
```

Example 1 - Plant - G.cif



```
import "events.cif";

plant G:
  location G0: initial;
    edge a1 goto G1;
    edge a2 goto G3;

  location G1:
    edge b1 goto G2;
    edge a2 goto G4;

  ...

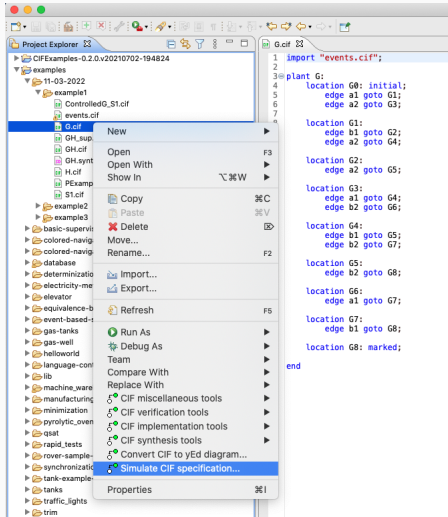
  location G7:
    edge b1 goto G8;

  location G8: marked;

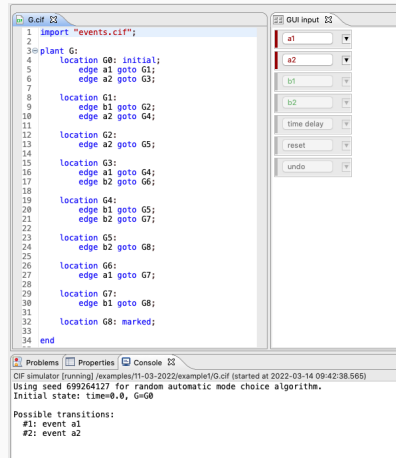
end
```

Example 1 - Simulation of the Uncontrolled Plant

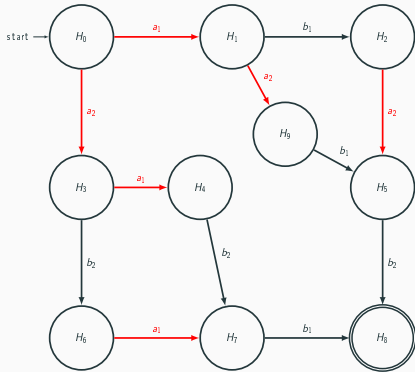
Simulation Menu



Interactive Simulation



Example 1 - Full Requirement - H.cif



Requirement: a_1 precedes a_2 if
and only if b_1 precedes b_2

```
import "events.cif";

requirement H:
    location H0: initial;
        edge a1 goto H1;
        edge a2 goto H3;
    ...

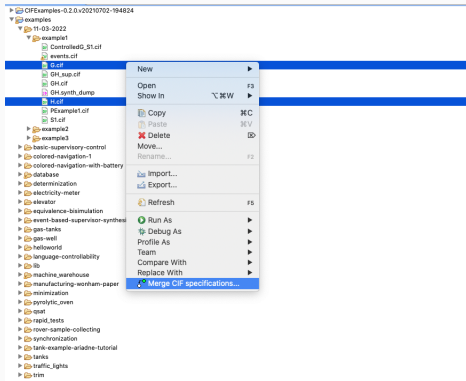
    location H4:
        edge b2 goto H7;

    location H9:
        edge b1 goto H5;
    ...

    location H8: marked;

end
```

Example 1 - Merge - GH.cif



```
uncontrollable a1;  
uncontrollable a2;  
controllable b1;  
controllable b2;
```

```
plant automaton G:
```

```
    location G0:  
        initial;
```

```
    ...
```

```
    location G8:  
        marked;
```

```
end
```

```
requirement automaton H:
```

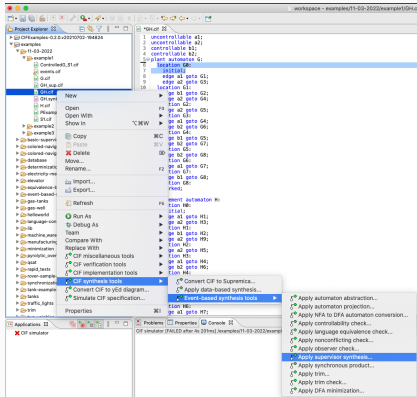
```
    location H0:
```

```
    ...
```

```
    location H8:  
        marked;
```

```
end
```

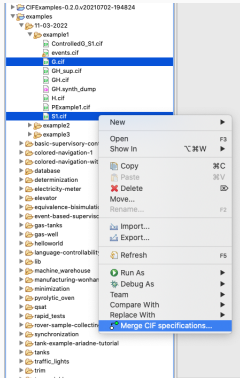
Example 1 - Supervisor Synthesis - S1.cif



```
uncontrollable a1;
uncontrollable a2;
controllable b1;
controllable b2;

supervisor automaton sup:
  alphabet a1, a2, b1, b2;
  location s1:
    initial;
    edge a2 goto s2;
    edge a1 goto s3;
  location s2:
    edge b2 goto s6;
    edge a1 goto s7;
    ...
  location s9:
    edge b1 goto s10;
  location s10:
    marked;
end
```


Example 1 - Supervisor Deployment - ControlledG_S1.cif



```
uncontrollable a1;  
uncontrollable a2;  
controllable b1;  
controllable b2;
```

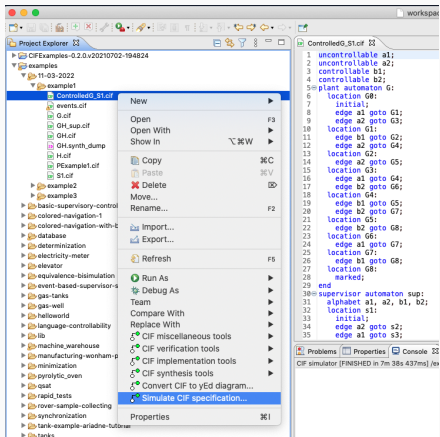
```
plant automaton G:  
  location G0:  
    initial;
```

```
  ...  
  location G8:  
    marked;  
end
```

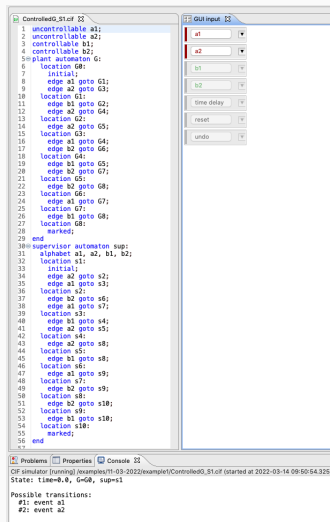
```
supervisor automaton S1:  
  alphabet a1, a2, b1, b2;  
  location s1:  
    initial;  
  ...  
  location s10:  
    marked;  
end
```

Example 1 - Simulation of the Controlled Plant

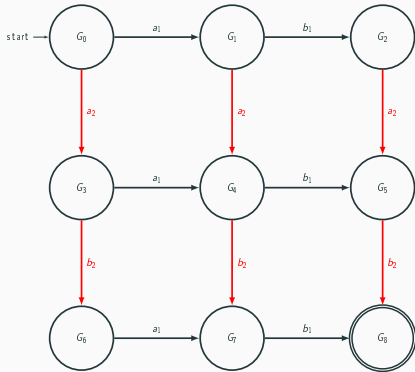
Simulation Menu



Interactive Simulation



Example 2 - Events, Plant, Requirement

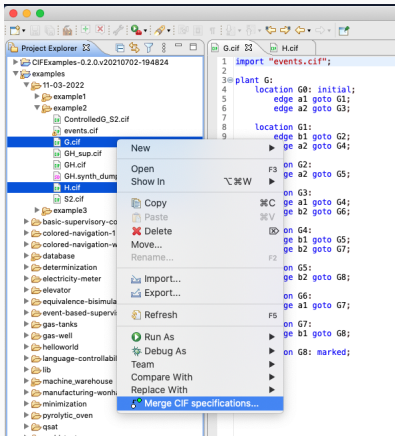


- Events a_1, b_1 are controllable
- Events a_2, b_2 are uncontrollable

```
controllable a1, b1;  
uncontrollable a2, b2;
```

- We changed only the event.cif file
- Plant file G.cif and Full requirement file H.cif are still the same

Example 2 - Merge - GH.cif



```
controllable a1;  
controllable b1;  
uncontrollable a2;  
uncontrollable b2;
```

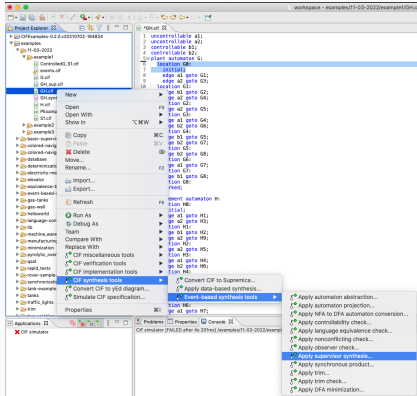
```
plant automaton G:  
  location G0:  
    initial;  
    ...  
  location G8:  
    marked;  
end
```

```
requirement automaton H:  
  location H0:  
    initial;  
    ...  
  location H8:  
    marked;  
end
```

Example 2 - Supervisor Synthesis - S2.cif

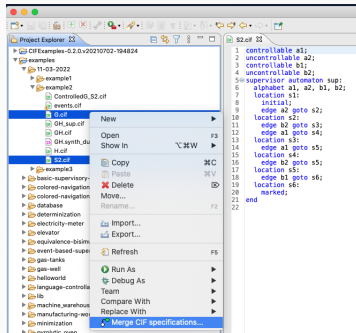
```
uncontrollable a1;  
uncontrollable a2;  
controllable b1;  
controllable b2;
```

```
supervisor automaton S2:  
  alphabet a1, a2, b1, b2;  
  location s1:  
    initial;  
    edge a2 goto s2;  
    edge a1 goto s3;  
  location s2:  
    edge b2 goto s6;  
    edge a1 goto s7;  
    ...  
  location s9:  
    edge b1 goto s10;  
  location s10:  
    marked;  
end
```



Example 2 - Supervisor Deployment - ControlledG_S2.cif

```
uncontrollable a1;  
uncontrollable a2;  
controllable b1;  
controllable b2;
```



```
plant automaton G:
```

```
location G0:  
initial;
```

```
...
```

```
location G8:  
marked;
```

```
end
```

```
supervisor automaton S2:  
alphabet a1, a2, b1, b2;
```

```
location s1:  
initial;
```

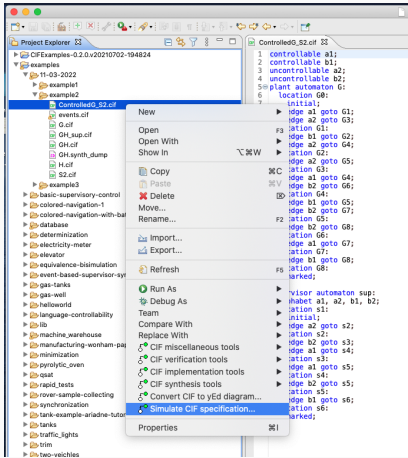
```
...
```

```
location s10:  
marked;
```

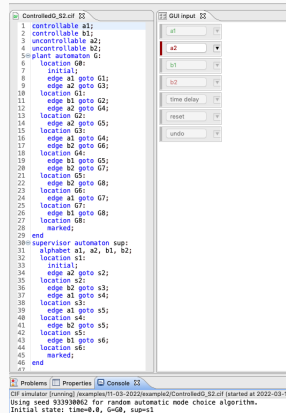
```
end
```

Example 2 - Simulation of the Controlled Plant

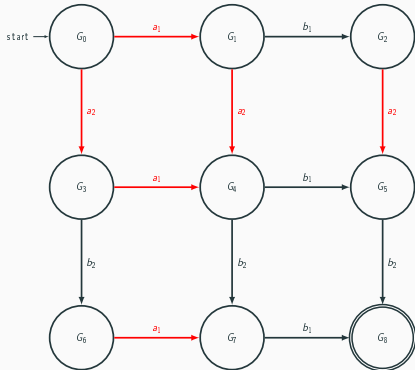
Simulation Menu



Interactive Simulation



Example 3 - Events, Plant, Requirement



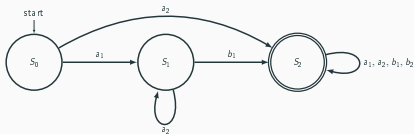
- Events a_1, a_2 are uncontrollable
- Events b_1, b_2 are controllable

uncontrollable a_1, a_2 ;
controllable b_1, b_2 ;

- The event.cif file is the same of that given in Example 1
- Plant file G.cif is still the same

Example 3 - Decomposition - R1.cif

Essential Requirement R_1



```
import "events.cif";

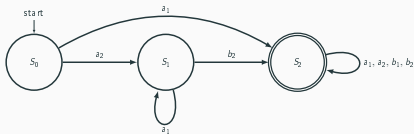
requirement R1:
    location S0: initial;
        edge a1 goto S1;
        edge a2 goto S2;

    location S1:
        edge a2;
        edge b1 goto S2;

    location S2: marked;
        edge a1,a2,b1,b2;
end
```

Example 3 - Decomposition - R2.cif

Essential Requirement R_2



```
import "events.cif";

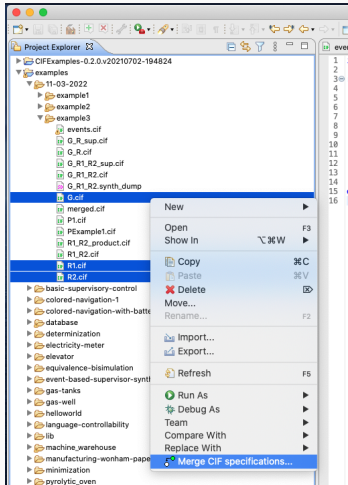
requirement R2:
    location S0: initial;
        edge a2 goto S1;
        edge a1 goto S2;

    location S1:
        edge a1;
        edge b2 goto S2;

    location S2: marked;
        edge a1,a2,b1,b2;

end
```

Example 2 - Merge - G_R1_R2.cif



```
uncontrollable a1;
uncontrollable a2;
controllable b1;
controllable b2;

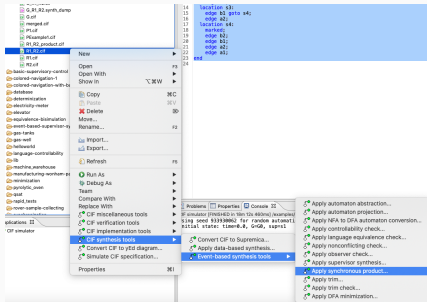
plant automaton G:
    location G0: initial;
    ...
end

requirement automaton R1:
    location S0: initial;
    ...
end

requirement automaton R2:
    location S0: initial;
    ...
end
```

Then, the supervisor is synthesized and deployed the same way

Example 3 - Product of Two Automata - $R := R_1 || R_2$



```

uncontrollable a1;
uncontrollable a2;
controllable b1;
controllable b2;

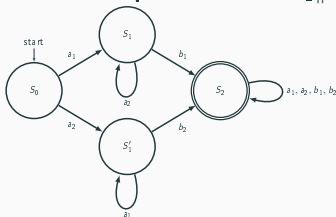
```

```

requirement automaton R:
  alphabet a1, a2, b1, b2;
  location s1:
    initial;
    edge a2 goto s2;
    edge a1 goto s3;
  location s2:
    edge b2 goto s4;
    edge a1;
  location s3:
    edge b1 goto s4;
    edge a2;
  location s4:
    marked;
    edge b2, b1, a2, a1;

```

Essential Requirement $R := R_1 || R_2$

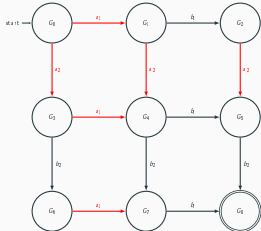


Then, merge, synthesize, and deploy.

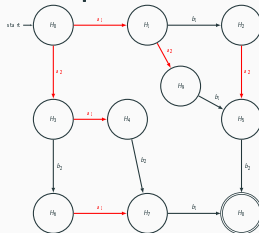
end

Equivalence of Requirements on the Same Plant

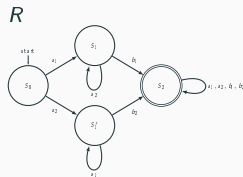
Plant G



Full Requirement H



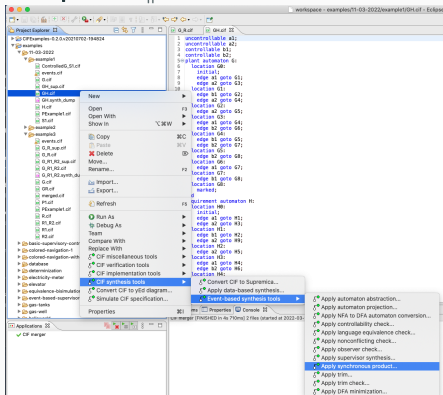
Essential Requirement



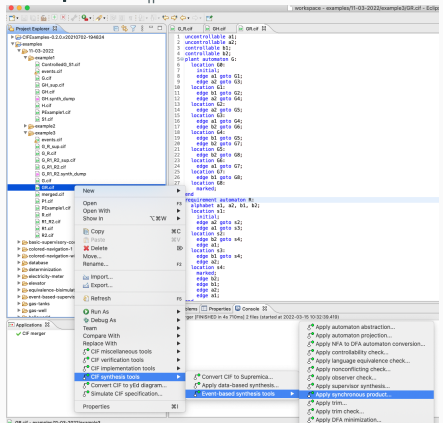
The effect of H on G is the same of the effect of R on G if and only if $G \parallel H$ is equivalent to $G \parallel R$.

Equivalence of Requirements on the Same Plant

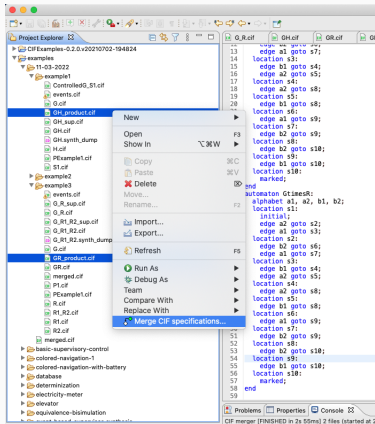
Example 1: $G \parallel H$



Example 3: $G \parallel R$

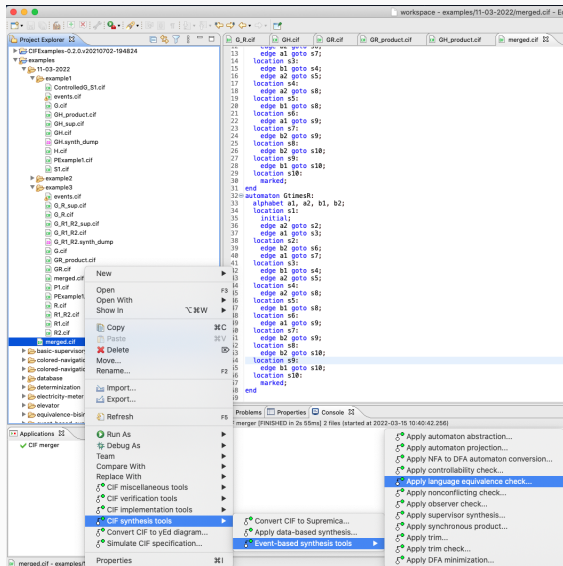


Example 3 - Merge - $G||H$ and $G||R$



```
uncontrollable a1;
uncontrollable a2;
controllable b1;
controllable b2;
automaton GtimesH:
    alphabet a1, a2, b1, b2;
    location s1:
        initial;
        ...
    location s10:
        marked;
end
automaton GtimesR:
    alphabet a1, a2, b1, b2;
    location s1:
        initial;
        ..
    location s10:
        marked;
end
```

Example 3 - Language Equivalence Check



Automata have the same language.

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Version: v0.4

ToolDef

Tired of scripting with Windows batch files and Linux shell scripts?

ToolDef is a cross-platform scripting language with the simplicity of Python and the power of Java.

[Learn more](#)

Features



Intuitive language

ToolDef features a simple and intuitive Python-inspired syntax that makes it easy to write scripts.



Reduce mistakes

Static typing reduces simple mistakes, compared to Windows batch files, Linux shell scripts and Python.



Powerful tools

ToolDef features many built-in data types and tools, and integrates well with Java and the Eclipse ESCET tools.

[Learn more](#)

Getting started

The ToolDef tooling is part of the Eclipse ESCET toolkit.

It is available for Windows, Linux and macOS, portable and ready to go.

[Download](#)

<https://www.eclipse.org/escet/tooldef/language-reference/index.html>

About ToolDef

ToolDef allows us to:

- **write scripts using a simple and intuitive syntax, loosely based on the better aspects of Python.**
- **catch simple mistakes early on due to static typing.**
- **work with data of all kinds, using a large number of built-in data types.**
- **manipulate data and paths, work with files and directories, and much more, with over 80 built-in tools.**
- **share your tools as ToolDef libraries.**
- **unleash the full power of Java by importing any Java static method and using it like any other ToolDef tool.**

ToolDef - First and Most Important

Each script is `File.tooldef`

The first line is:

```
from "lib:cif" import *;
```

ToolDef - Generating Text Files

```
from "lib:cif" import *;  
writefile("file.cif", "my text 1\n");  
writefile("file.cif", "my text 2\n", append=true);
```

ToolDef - Generating Text Files - Alternative Way

```
from "lib:cif" import *;  
string text1 = "my text";  
string text2 = "my text";  
writefile("file.cif", text1);  
writefile("file.cif", text2, append=true);
```

ToolDef - Merging CIF files

Help screen

```
cifmerge("-h");
```

Simple usage

```
cifmerge(  
    "InputFile1.cif",  
    "InputFile2.cif",  
    ...  
    "InputFileN.cif"  
);
```

Specifying the output file

```
cifmerge(  
    "InputFile1.cif",  
    "InputFile2.cif",  
    ...  
    "InputFileN.cif",  
    "-o OutputFile.cif"  
);
```

The CIF merger can be used to merge two or more CIF specifications into a single CIF specification

<https://www.eclipse.org/escet/cif/tools/mergecif.html>

ToolDef - Synthesizing a Supervisor

Help screen

```
cifsupsynth("-h");
```

Simple usage

```
cifsupsynth(  
    "InputFile.cif",  
);
```

Specifying the output file

```
cifsupsynth(  
    "InputFile.cif",  
    "-o OutputFile"  
);
```

Specifying a name for the OutputFile

```
cifsupsynth(  
    "InputFile.cif",  
    "-n Supervisor.cif",  
    "-o OutputFile.cif"  
);
```

Enabling the Debug

```
cifsupsynth(  
    "InputFile.cif",  
    "-n Supervisor.cif",  
    "-o OutputFile.cif"  
    "-d DebugFile.synth_dump"  
);
```

The tool takes a .cif file containing plant and requirement automata.

Debug (synthesis analysis):

<http://www.eclipse.org/escet/cif/tools/eventbased/supervisorsynthesis.html>

ToolDef - Deploying a Supervisor

Intuitive use

```
cifmerge(  
    "Plant.cif",  
    "Supervisor.cif",  
    "-o ControlledPlant.cif"  
);
```

General use

```
cifmerge(  
    "Plant1.cif",  
    ...  
    "PlantN.cif",  
    "Supervisor1.cif",  
    ...  
    "SupervisorN.cif",  
    "-o ControlledPlant.cif"  
);
```

Simply Merge the Plant with the Supervisor

ToolDef - Parallel Composition

Help screen

```
cifprod("-h");
```

Simple usage

```
cifprod(  
    "InputFile.cif",  
);
```

Specifying the output file

```
cifprod(  
    "InputFile.cif",  
    "-o OutputFile.cif"  
);
```

Specifying the output file and a name

```
cifprod(  
    "InputFile.cif",  
    "-n Name",  
    "-o OutputFile.cif"  
);
```

The tool takes a .cif file containing all automata to combine, and produces a new .cif file with the product automaton

<https://www.eclipse.org/escet/cif/tools/eventbased/product.html>

ToolDef - Language Equivalence Check

Help screen

```
ciflngeqv("-h");
```

The tool takes a .cif file containing exactly two automata, that must be deterministic, have the same alphabet, and have an initial location

<https://www.eclipse.org/escet/cif/tools/eventbased/>

[language-equivalence-check.html](https://www.eclipse.org/escet/cif/tools/eventbased/language-equivalence-check.html)

Usage

```
ciflngeqv(  
    "InputFile.cif",  
);
```

ToolDef - Executing ToolDef Scripts From ToolDef Scripts

Help screen

```
tooldef("-h");
```

The tool takes a `.tooldef` and executes it

Usage

```
tooldef(  
    "Script.tooldef",  
);
```

Have a look at

<https://www.eclipse.org/escet/cif/tools/scripting/tools.html>

for more scriptable tools.