

Hardware Modeling [VU] (191.011)

– WS25 –

Synchronizers and Debouncers

Florian Huemer & Sebastian Wiedemann & Dylan Baumann

WS 2025/26

Recall: MTBU Estimation

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Sync. & Deb.
Recap
Synchronizers
Debouncing

- We can get a statistical estimate of the MTBU

$$MTBU = \frac{1}{\lambda_{in} \cdot f_{clk} \cdot T_W} \cdot e^{\frac{t_{res}}{\tau C}}$$

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 - Increasing t_{res} is a mechanism to increase the MTBU
 - However: MTBU can never become infinite!

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- Exponential dependence of MTBU on time to resolve t_{res}
 - Increasing t_{res} is a mechanism to increase the MTBU
 - However: MTBU can never become infinite!
- Harnessed by *synchronizers*
 - Trade-off performance for a higher MTBU

Waiting Synchronizers

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■ Chain of flip-flops

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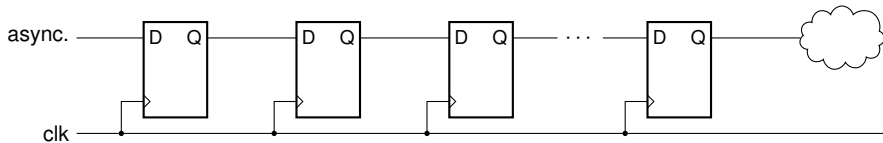
Recap

Synchronizers

VHDL

Take Aways

Debouncing



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Recap

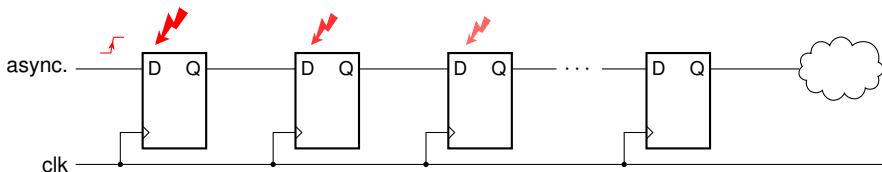
Synchronizers

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- Chain of flip-flops
 - Pass metastable output to next flip-flop in chain



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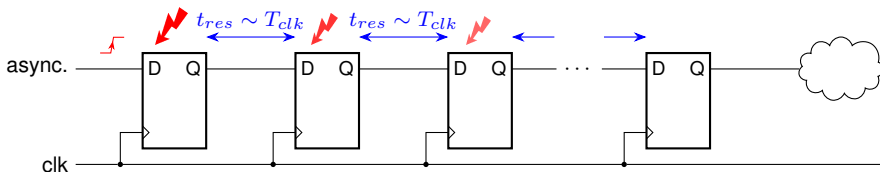
VHDL

Take Aways

Debouncing

■ Chain of flip-flops

- Pass metastable output to next flip-flop in chain
- No comb. logic between flip-flops \Rightarrow majority of clock period for resolution



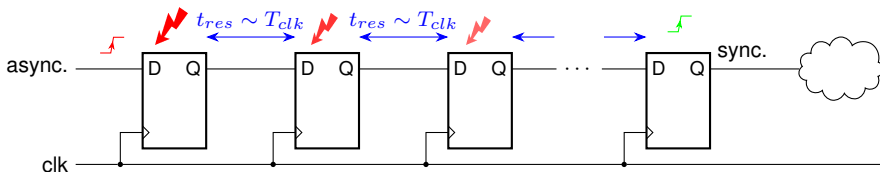
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■ Chain of flip-flops

- Pass metastable output to next flip-flop in chain
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- Asynchronous input is “synchronized” to the clock

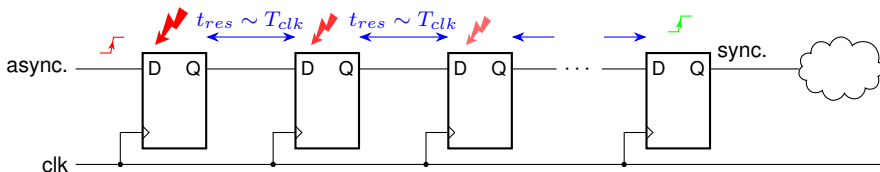


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- Chain of flip-flops
 - Pass metastable output to next flip-flop in chain
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 - Asynchronous input is “synchronized” to the clock
- Overall resolution time is the sum of the individual ones

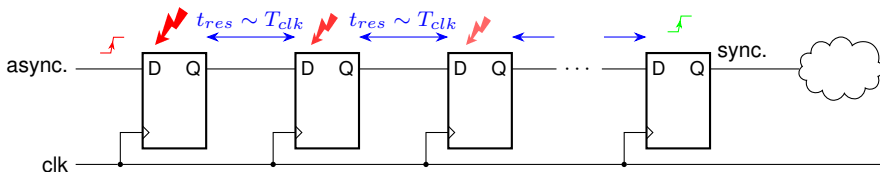


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 - \Rightarrow Exponential increase in MTBU **per** flip-flop

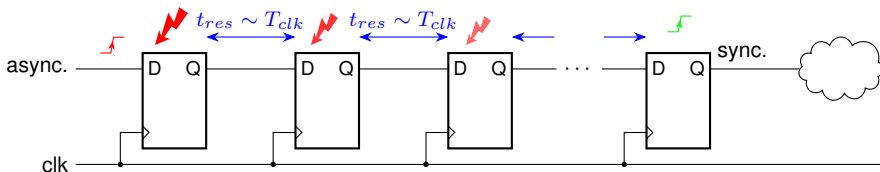


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 - No comb. logic between flip-flops \Rightarrow majority of clock period for resolution
 - Asynchronous input is “synchronized” to the clock
- Overall resolution time is the sum of the individual ones
 - \Rightarrow Exponential increase in MTBU **per** flip-flop
- In practice often two flip-flops, three to be on the safe side
 - Trade-off between latency and MTBU



VHDL Implementation

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Recap

Synchronizers

VHDL

Take Aways

Debouncing

```
1 library ieee;
2 use ieee.std_logic_1164.all;
3
4 entity synchronizer is
5     generic (
6         STAGES    : natural;
7         RES_VAL   : std_ulogic
8     );
9     port (
10         clk       : in std_ulogic;
11         res_n     : in std_ulogic;
12         async     : in std_ulogic;
13         sync      : out std_ulogic
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```
16 architecture arch of synchronizer is
17     signal ffs: std_ulogic_vector(0 to STAGES);
18 begin
19     process (clk, res_n) begin
20         if res_n = '0' then
21             ffs <= (others => RES_VAL);
22         elsif rising_edge(clk) then
23             ffs(0) <= async;
24             for i in 1 to STAGES loop
25                 ffs(i) <= ffs(i-1);
26             end loop;
27         end if;
28     end process;
29     sync <= ffs(STAGES);
30 end architecture;
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 - A synchronizer does **not** prevent metastability!

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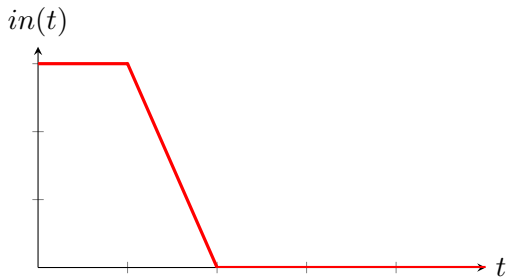
Take Aways

Debouncing

- MTBU can be made *arbitrarily* large by appropriate synchronizer
 - A synchronizer does **not** prevent metastability!
- A single flip-flop alone is not a synchronizer
- The MTBU is a statistical quantity
 - No guarantee for upset-freedom at any time

Bouncing Inputs

- Asynchronous inputs are not the only problem at interfaces

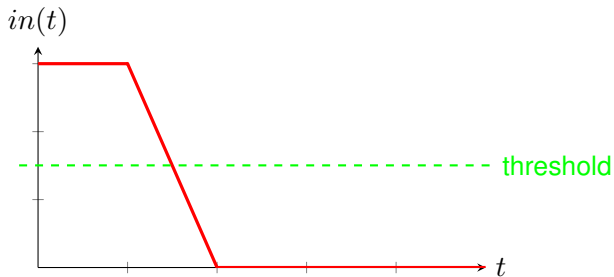


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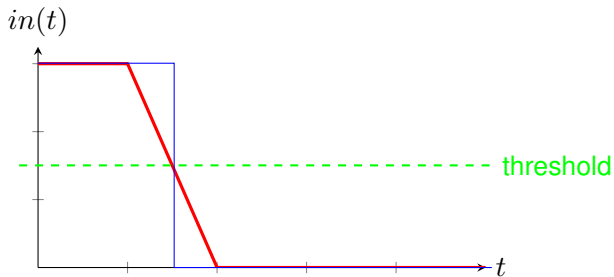


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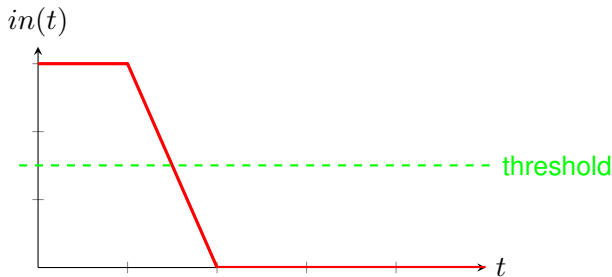


Bouncing Inputs

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- Asynchronous inputs are not the only problem at interfaces
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 - For example: Mechanical buttons, switches

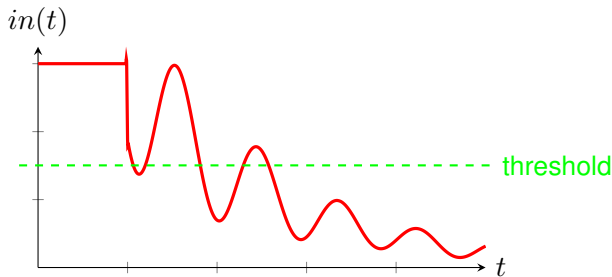


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 - Instead of clean transition dampened oscillation

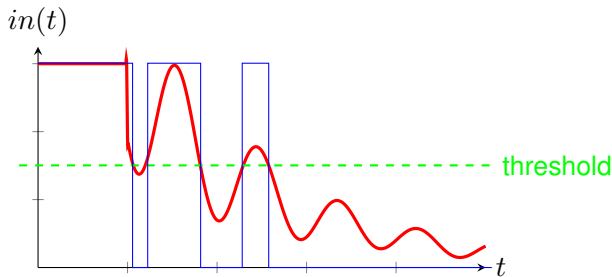


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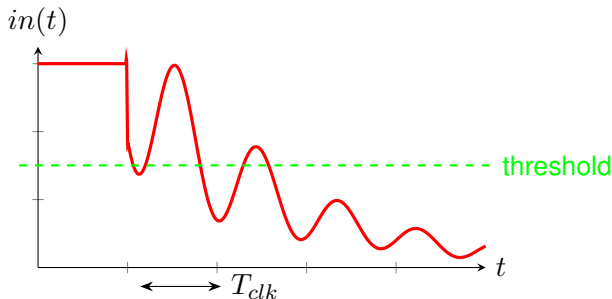


Bouncing Inputs

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 - Instead of clean transition dampened oscillation
 - Depending on clock frequency, takes multiple (hundred) clock cycles

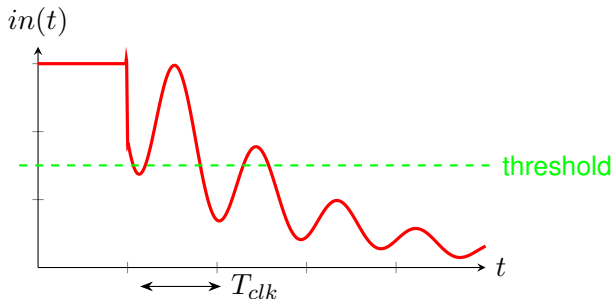


Bouncing Inputs

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- Asynchronous inputs are not the only problem at interfaces
- Some mechanical contacts may “bounce” due to their construction
 - For example: Mechanical buttons, switches
 - Instead of clean transition dampened oscillation
 - Depending on clock frequency, takes multiple (hundred) clock cycles
- May upset input FFs or leads to unwanted transitions



Counter Measures

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Recap

Synchronizers

Debouncing

- Simply filter-out sequence of input transitions that is “too fast”

Counter Measures

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- Simply filter-out sequence of input transitions that is “too fast”
 - Analog (low pass) filtering

Counter Measures

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- Simply filter-out sequence of input transitions that is “too fast”
 - Analog (low pass) filtering
 - Digital filtering to check if output stabilizes
 - Use timer to wait (FSM)
 - Alternatives exist

Counter Measures

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- Simply filter-out sequence of input transitions that is “too fast”
 - Analog (low pass) filtering
 - Digital filtering to check if output stabilizes
 - Use timer to wait (FSM)
 - Alternatives exist
 - Software-based debouncing

Debouncer Implementation

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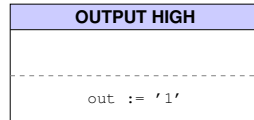
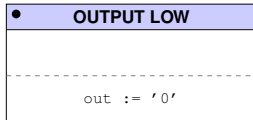
- Digital debouncing FSM

Debouncer Implementation

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- Digital debouncing FSM
 - Debouncer either outputs zero or high



Debouncer Implementation

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- Digital debouncing FSM
 - Debouncer either outputs zero or high

● OUTPUT LOW
s.old_in := in s.clk_cnt := s.clk_cnt+1
out := '0'

OUTPUT HIGH
s.old_in := in s.clk_cnt := s.clk_cnt+1
out := '1'

Debouncer Implementation

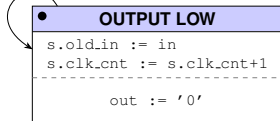
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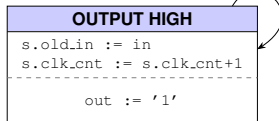
■ Digital debouncing FSM

- Debouncer either outputs zero or high
- If the input changes, reset counter to count time since transition

`in != \wedge s.old_in`
`c.clk_cnt := 0`



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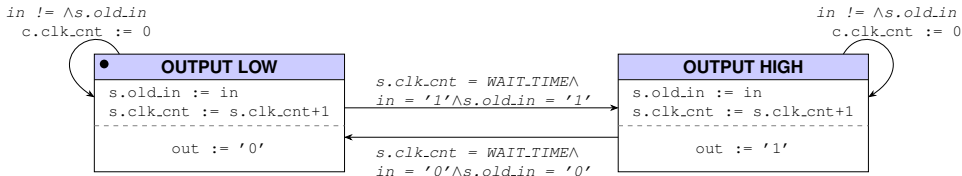
Debouncer Implementation

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■ Digital debouncing FSM

- Debouncer either outputs zero or high
- If the input changes, reset counter to count time since transition
- When input change is stable, change output



Lecture Complete!