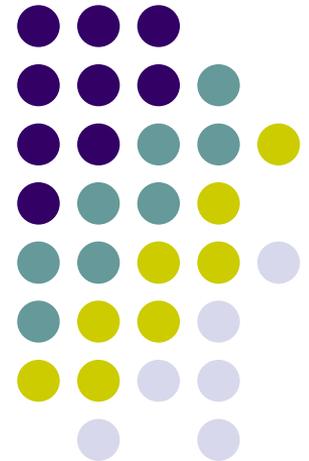
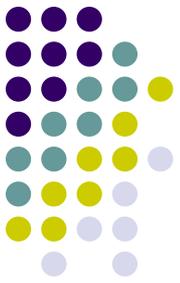


Chapter 7 Sequential ATPG

循序電路自動輸入樣本產生器

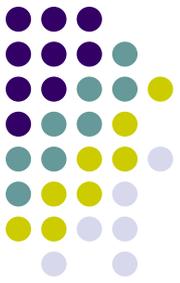


Outline



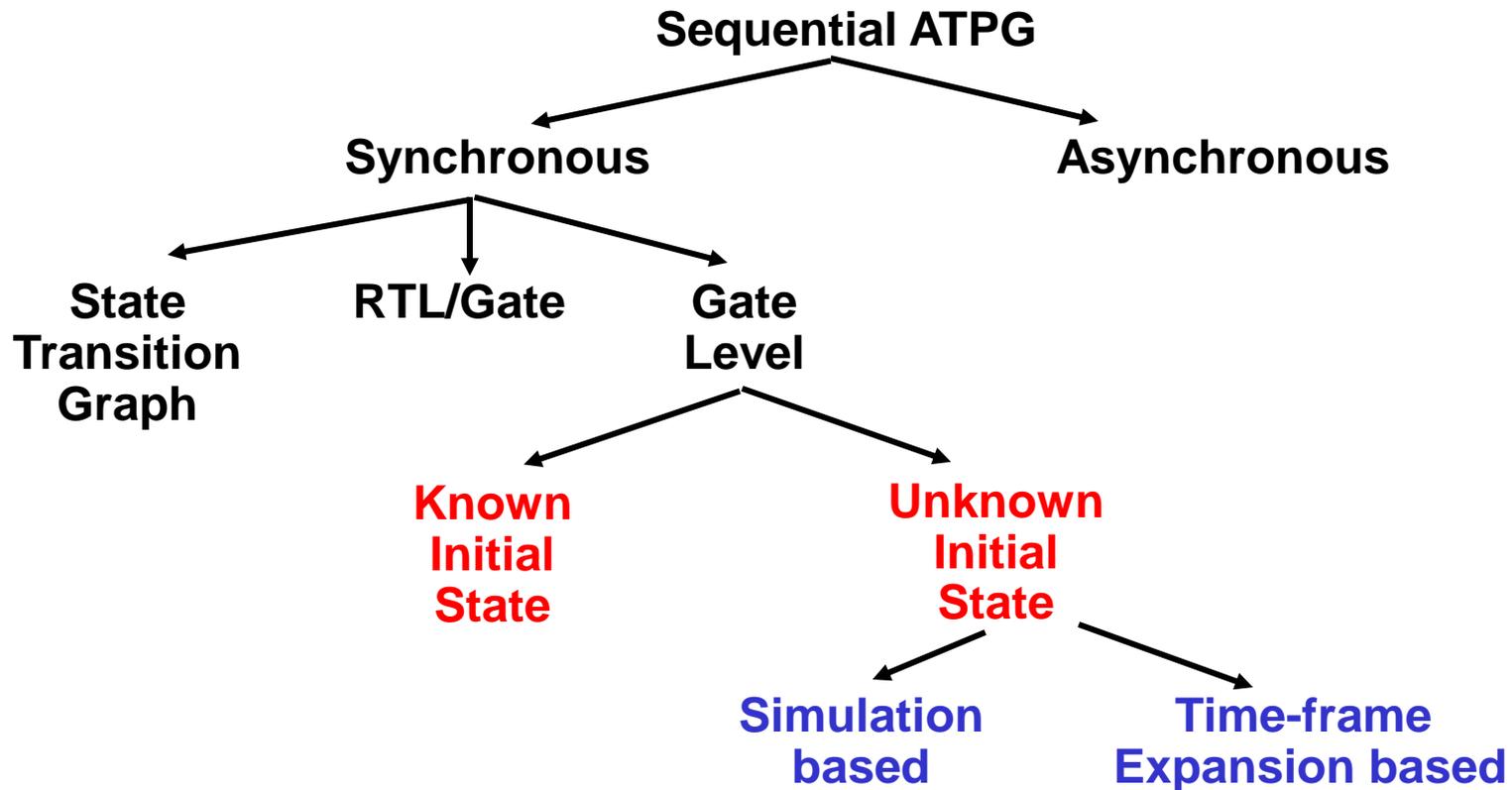
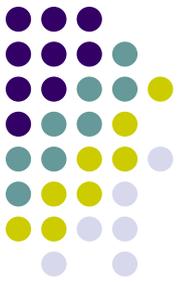
- Introduction
- Techniques for unknown initial states
 - Time-frame-based
 - Simulation-based
- Techniques for known initial states

Sequential Circuits

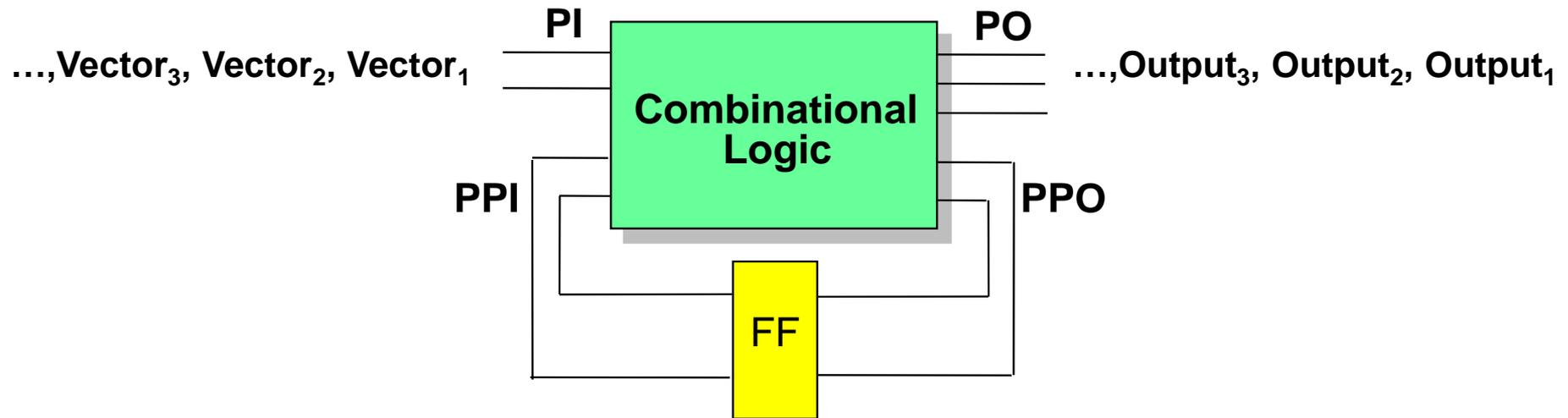
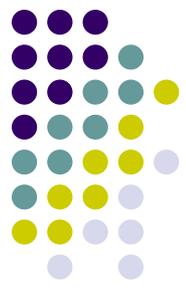


- Combination circuits + Memory elements
- Sequential circuits can be used to spread computations over time to reduce hardware
- Difficulties for test generation
 - Internal **memory states** unknown
 - After test applied, **final states** must be inferred indirectly
 - **Long test sequence** required
 - Initialization + fault activation and propagation + observation

Sequential ATPG: Taxonomy



Test Generation for Synchronous Sequential Circuits



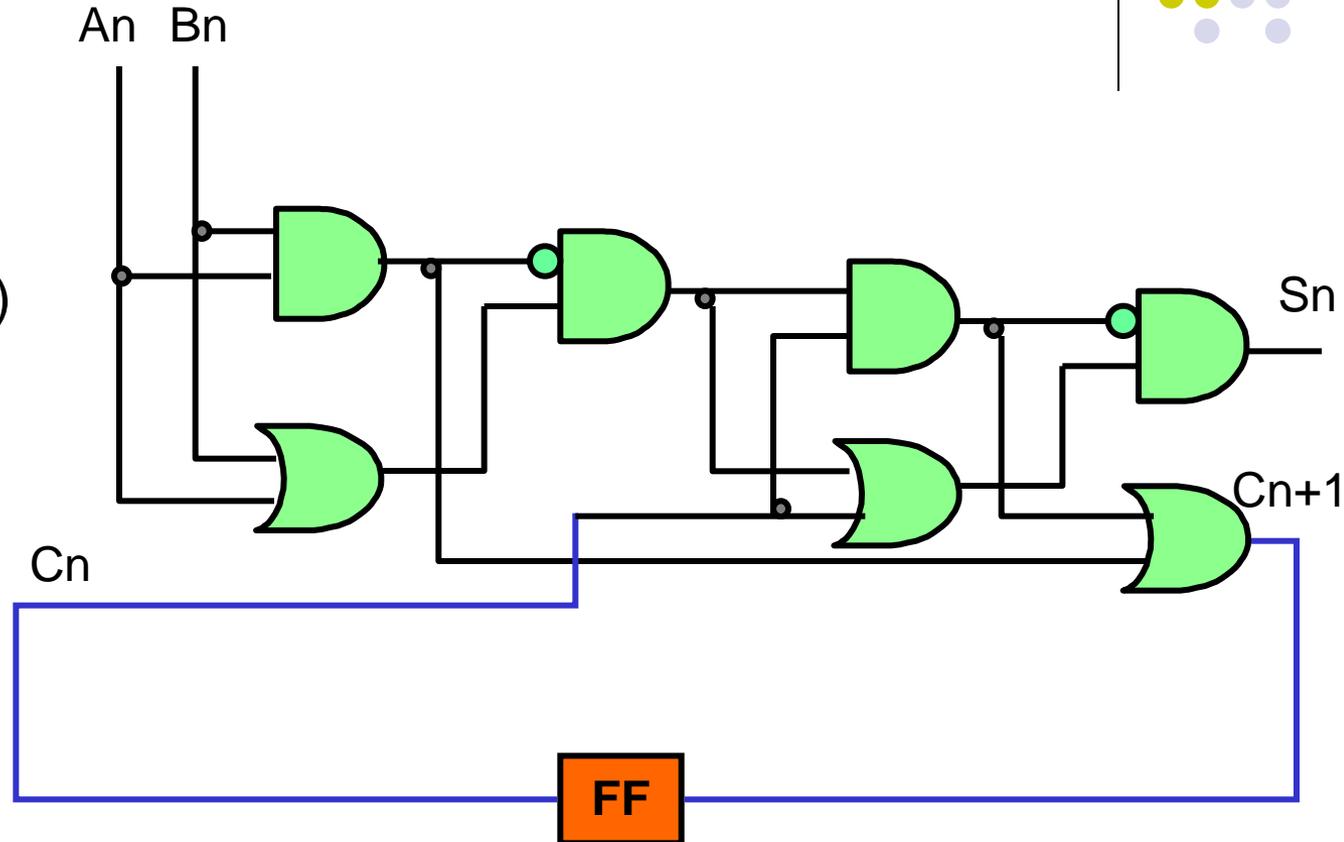
- Assumptions

- All signal propagation times through combinational logics do not exceed the clock period
- Flip-flops are ideal memories with an implicit clock
 - no fault at clocks and inside of FFs

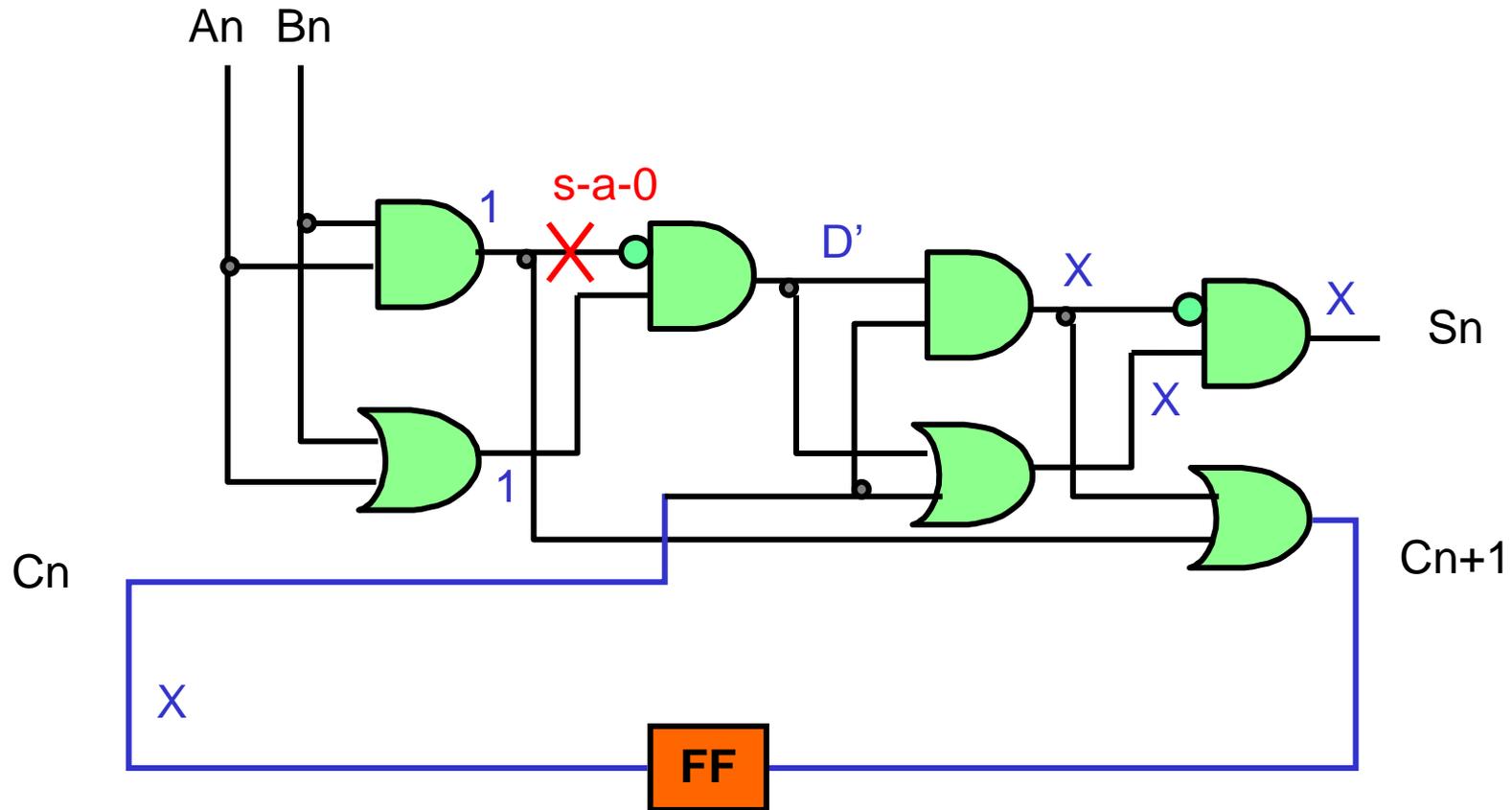
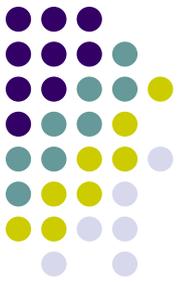
An Example: Serial Adder



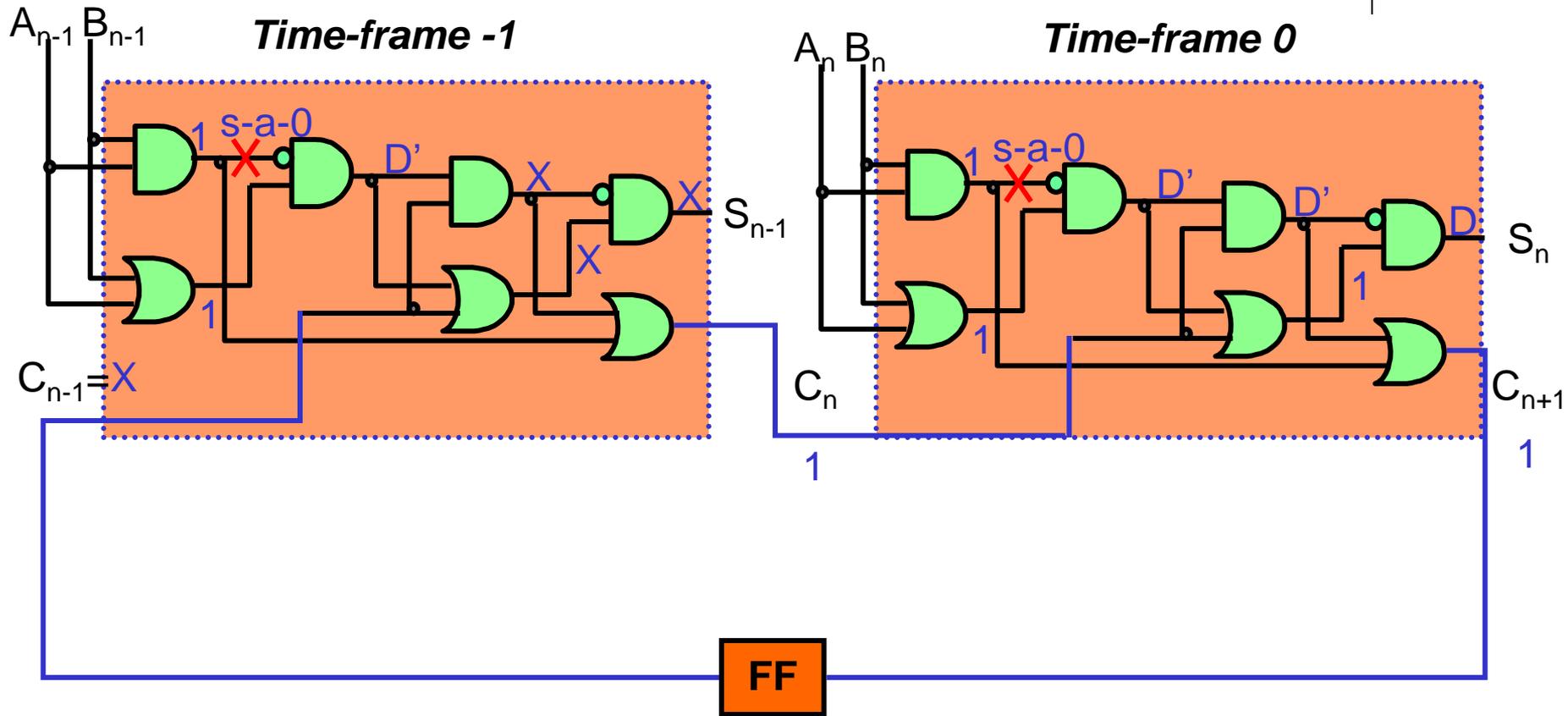
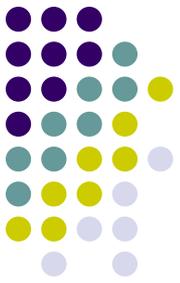
- Use one-bit adder to implement multiple-bit adder
- Initialize $(A,B)=(0,0)$
- $(A_0,B_0) \rightarrow S_0$
- $(A_1,B_1) \rightarrow S_1$
-
- $(A_{31},B_{31}) \rightarrow S_{31}$
- $(0,0)$
 - S_{32} (carry bit)



An Example: Serial Adder



An Example: Serial Adder



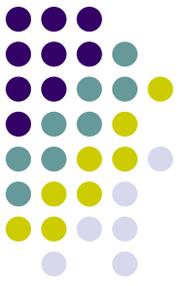
Outline



- For Circuits with **Unknown Initial States**
 - **Time-frame Expansion Based:**
 - Extended D-algorithm (IEEE TC, 1971)
 - 9-V Algorithm (IEEE TC, 1976)
 - EBT (DAC, 1978 & 1986)
 - BACK (ICCD, 1988), ...
 - **Simulation-Based:**
 - CONTEST (IEEE TCAD, 1989)
- For Circuits with **Known Initial States**
 - STALLION (IEEE TCAD, 1988)
 - STEED (IEEE TCAD, May 1991), ...

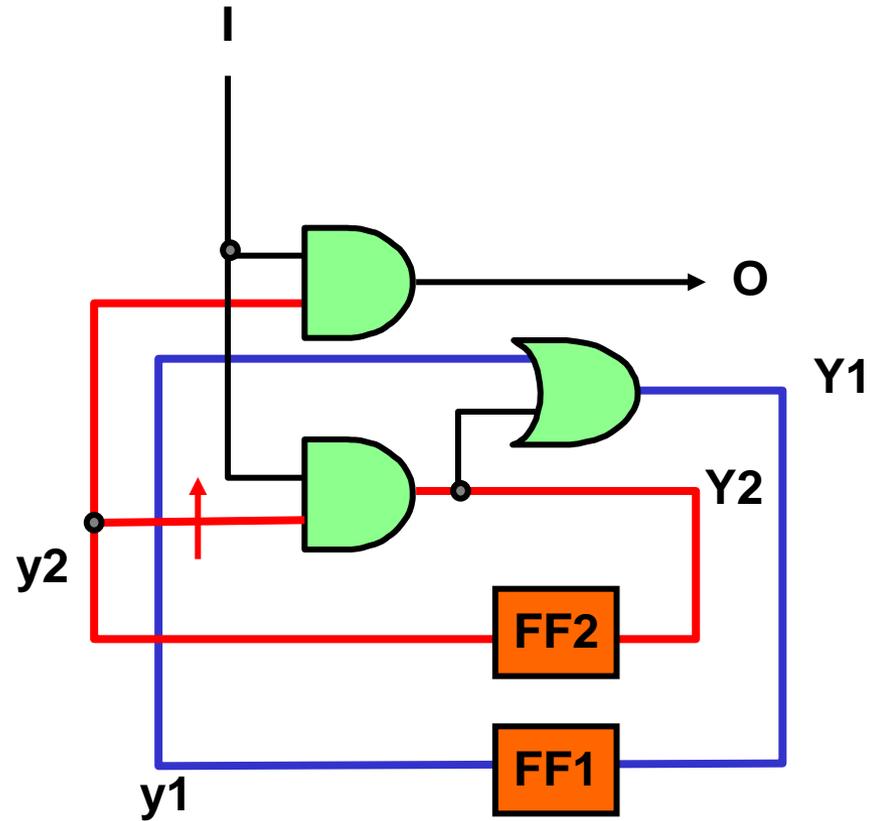
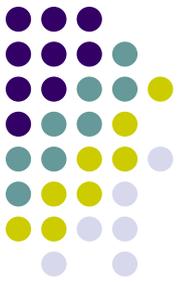
Extended D-Algorithm [1]

(Kubo, NEC Research & Development, Oct. 1968)
(Putzolu and Roth, IEEE TC, June 1971)

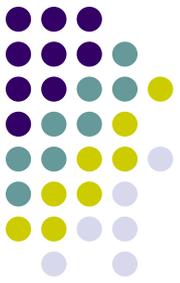


1. Pick up a target fault **f**.
2. Create a copy of a combinational logic, set it time-frame 0.
3. Generate a test for **f** using **D-algorithm for time-frame 0**.
4. When the fault effect is propagated to the DFFs, continue the **fault propagation in the next time-frame**.
5. When there are values required in the DFFs, continue the **justification in the previous time-frame**.

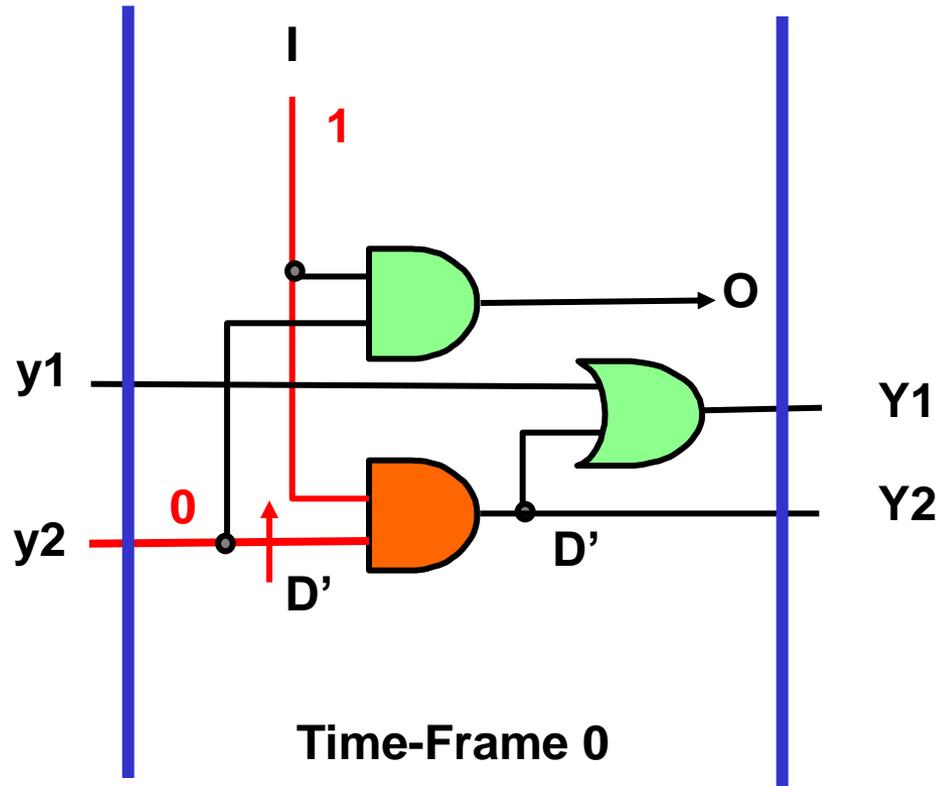
Example for Extended D-Algorithm



Example: Step 1

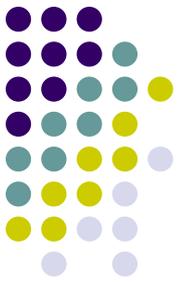


Fault Activation

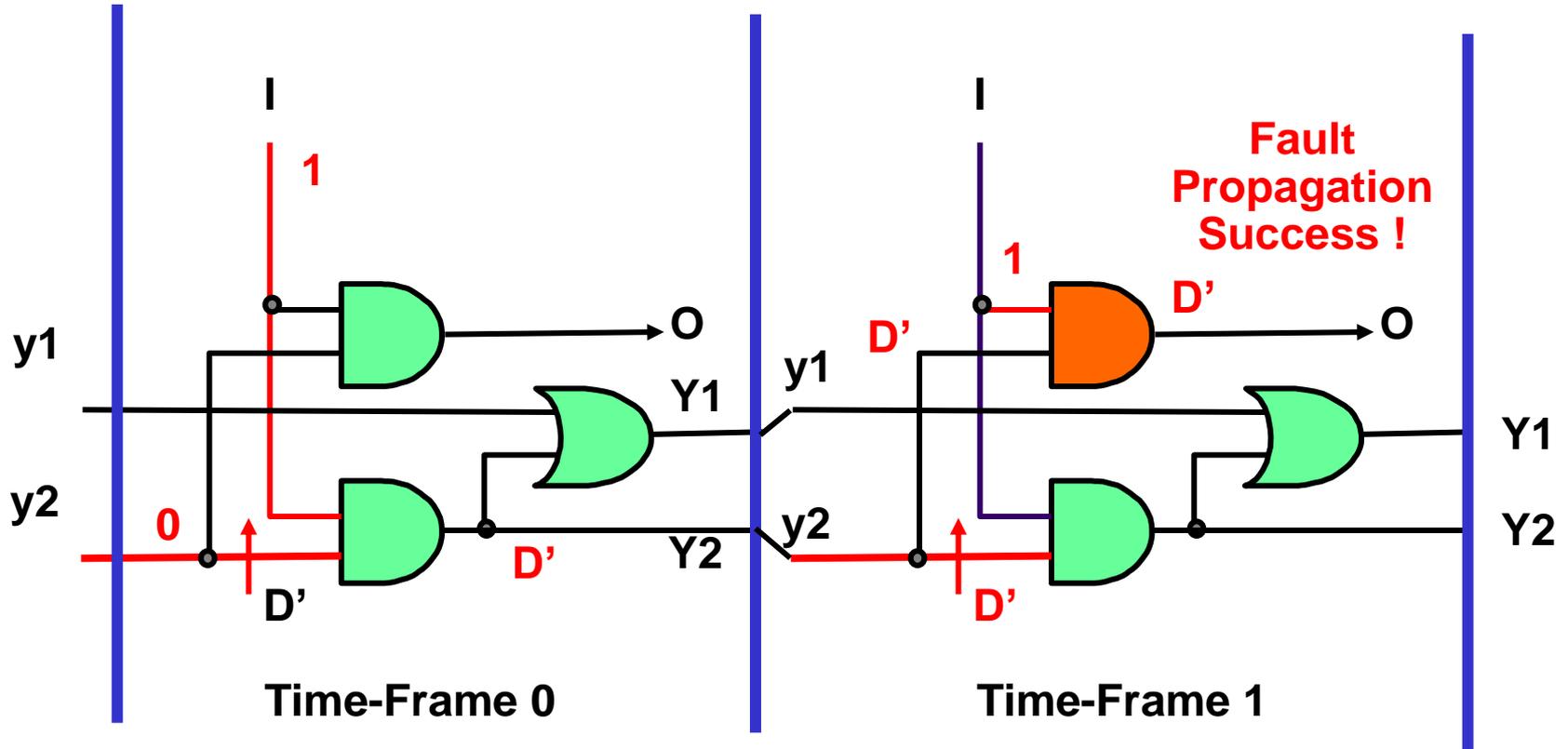


State requirement:
value assignments at
present-state lines
→ a **state-cube**
($y_1y_2 = x_0$)

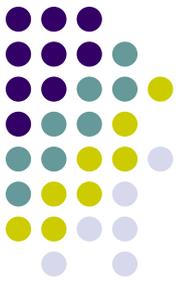
Example: Step 2



Forward Fault Propagation

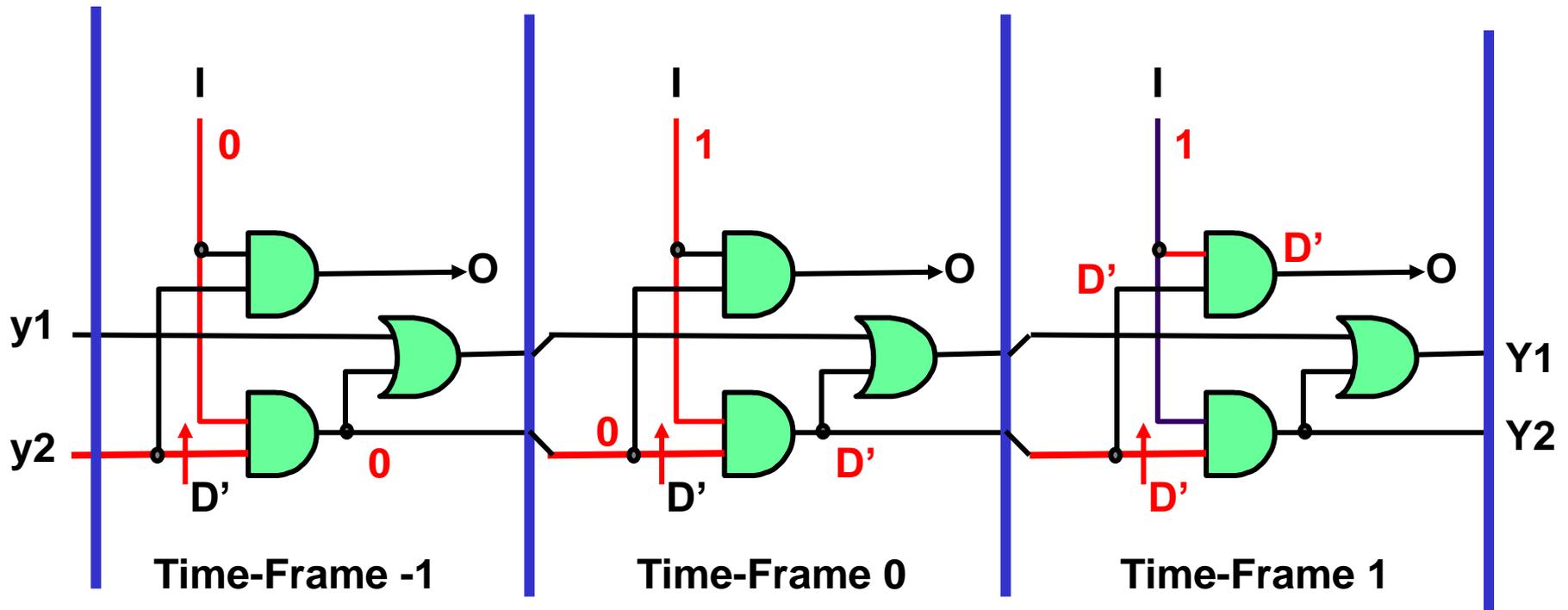


Example: Step 3



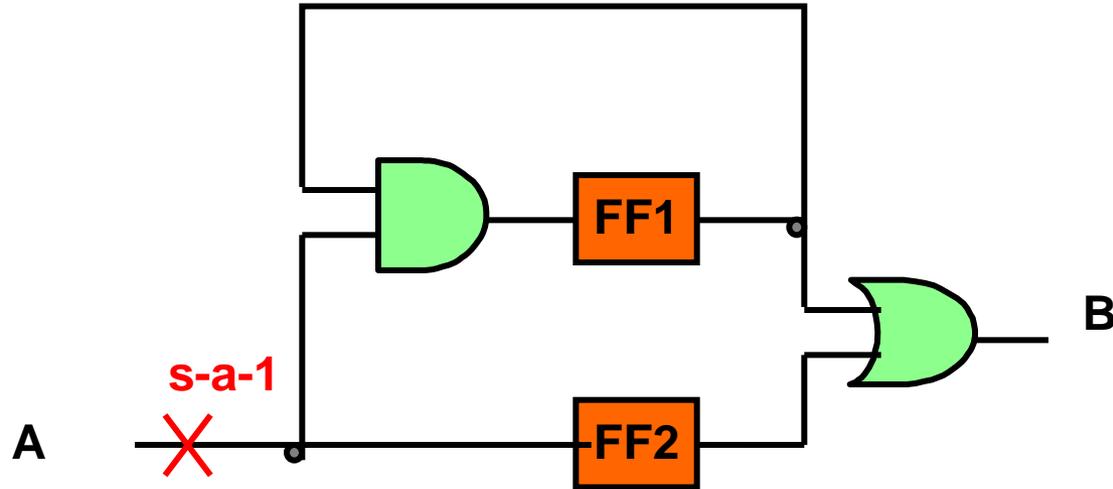
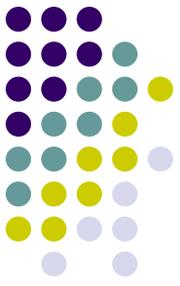
Backward Line Justification

→ binary values at PPI's needs to be justified from PI's



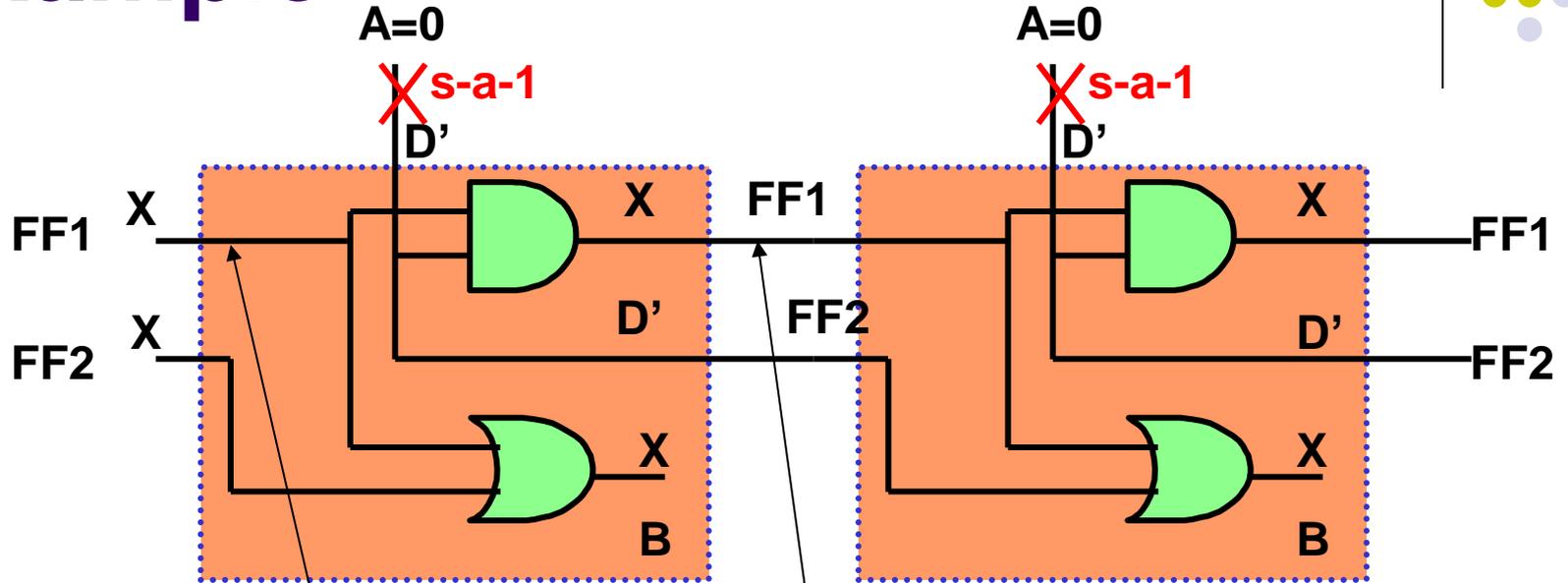
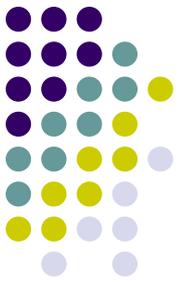
A Test Sequence (0, 1, 1) is found !

Need for 9-Value Logic: An Example



- FF2 is initialized by any input at A
- FF1 is initialized by $A=0$

Need for 9-Value Logic: An Example

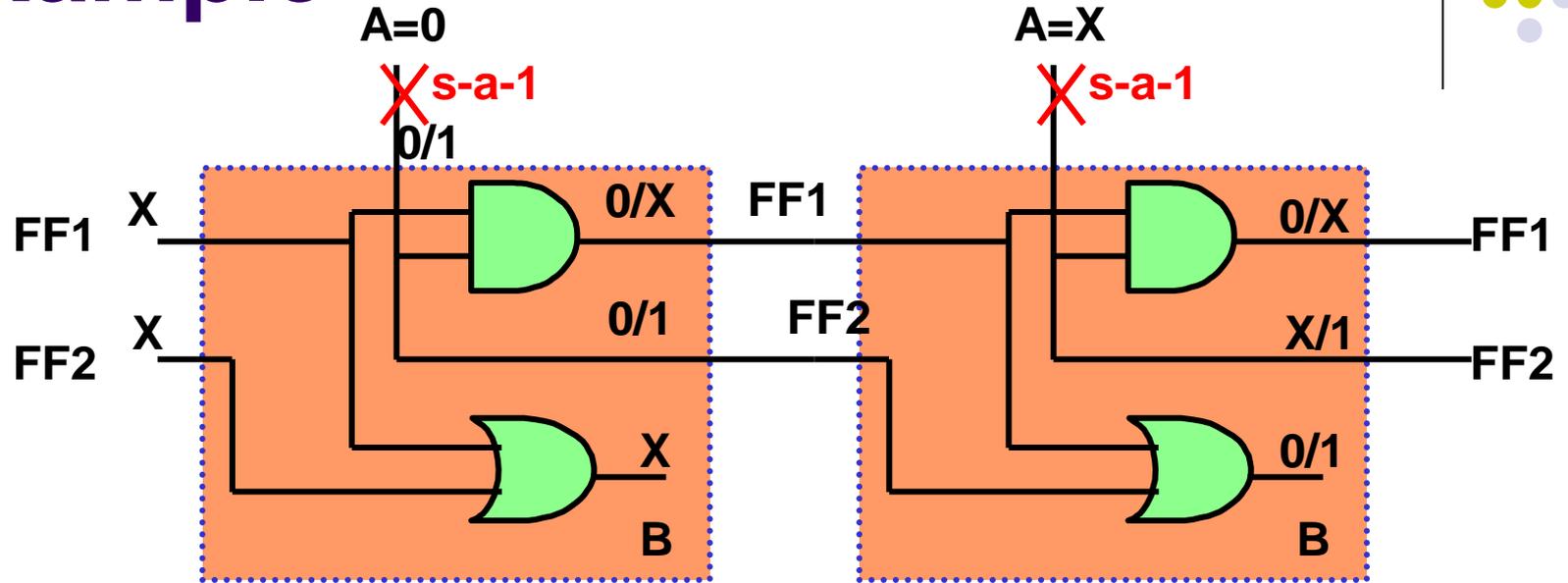
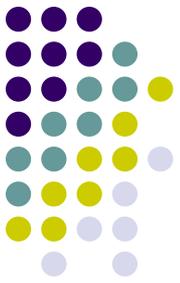


To propagate D' through B , require $FF1=0 \rightarrow$ Cyclic justification

To propagate D' through AND gate, require $FF1=1 \rightarrow$ Failed justification

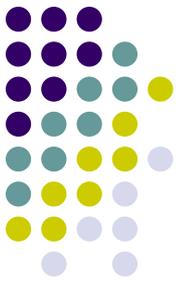
- 5-value logic can't handle situations when faults affect initialization

Need for 9-Value Logic: An Example



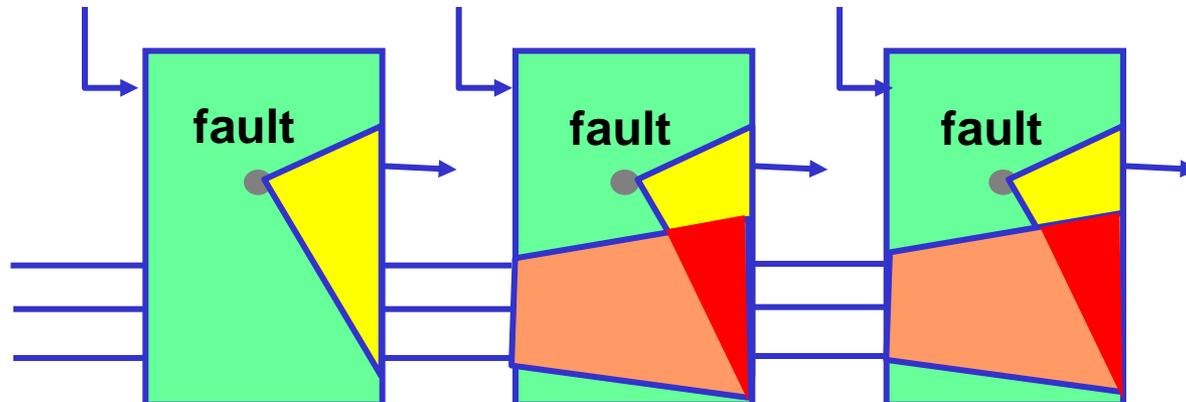
- 9-value logic finds an test $A_0=0, A_1=X \rightarrow B_1=D'$ at second cycle

9-V Sequential TG [2]

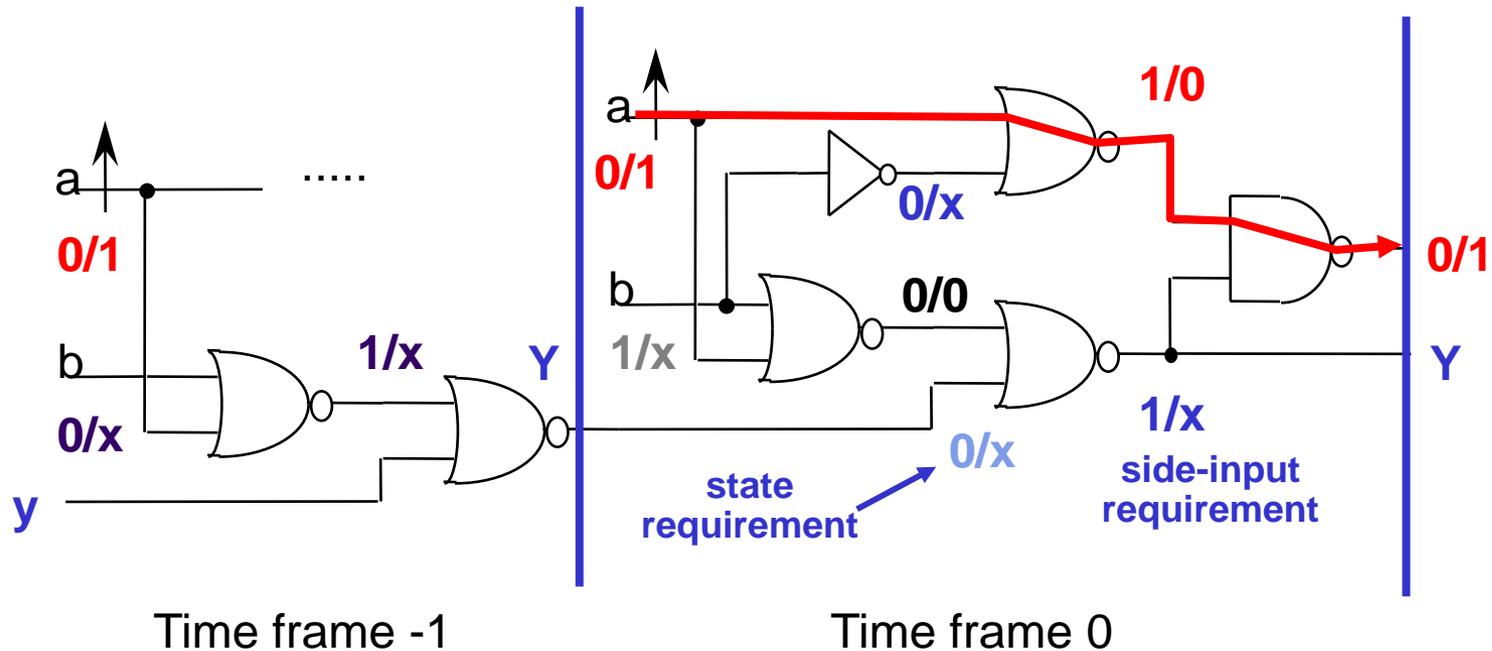
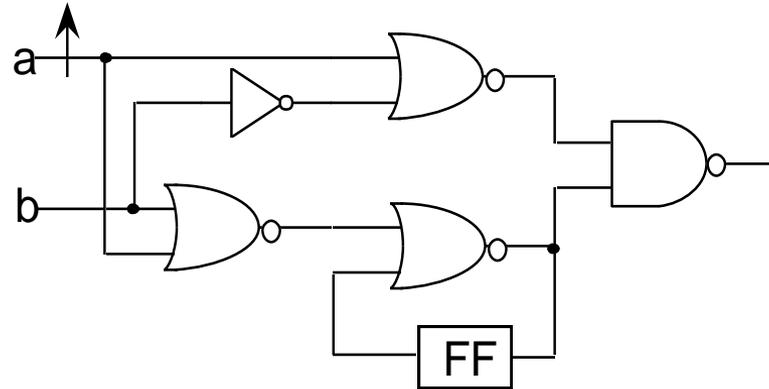
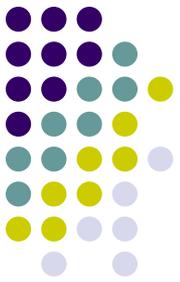


(Muth, IEEE TC, June 1976)

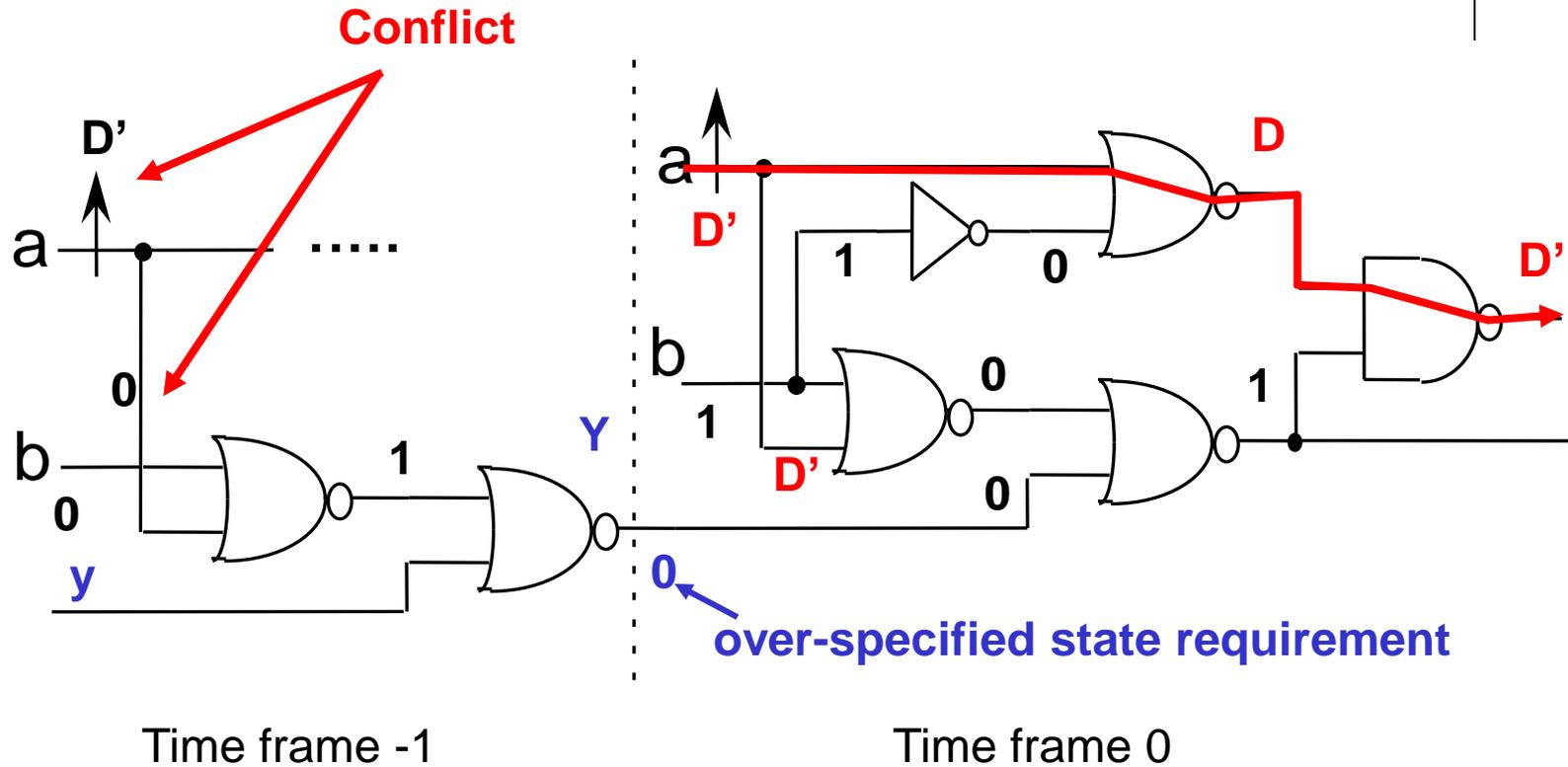
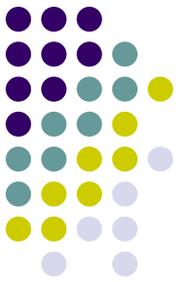
- Extended D-algorithm is **not complete**.
- If **nine-value**, instead of five-value, is used, it will be a complete algorithm.
- Nine-value logic can consider cases where faults affect initialization



Example: Nine-Value TG

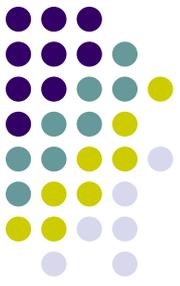


If Five-Value TG Is Used



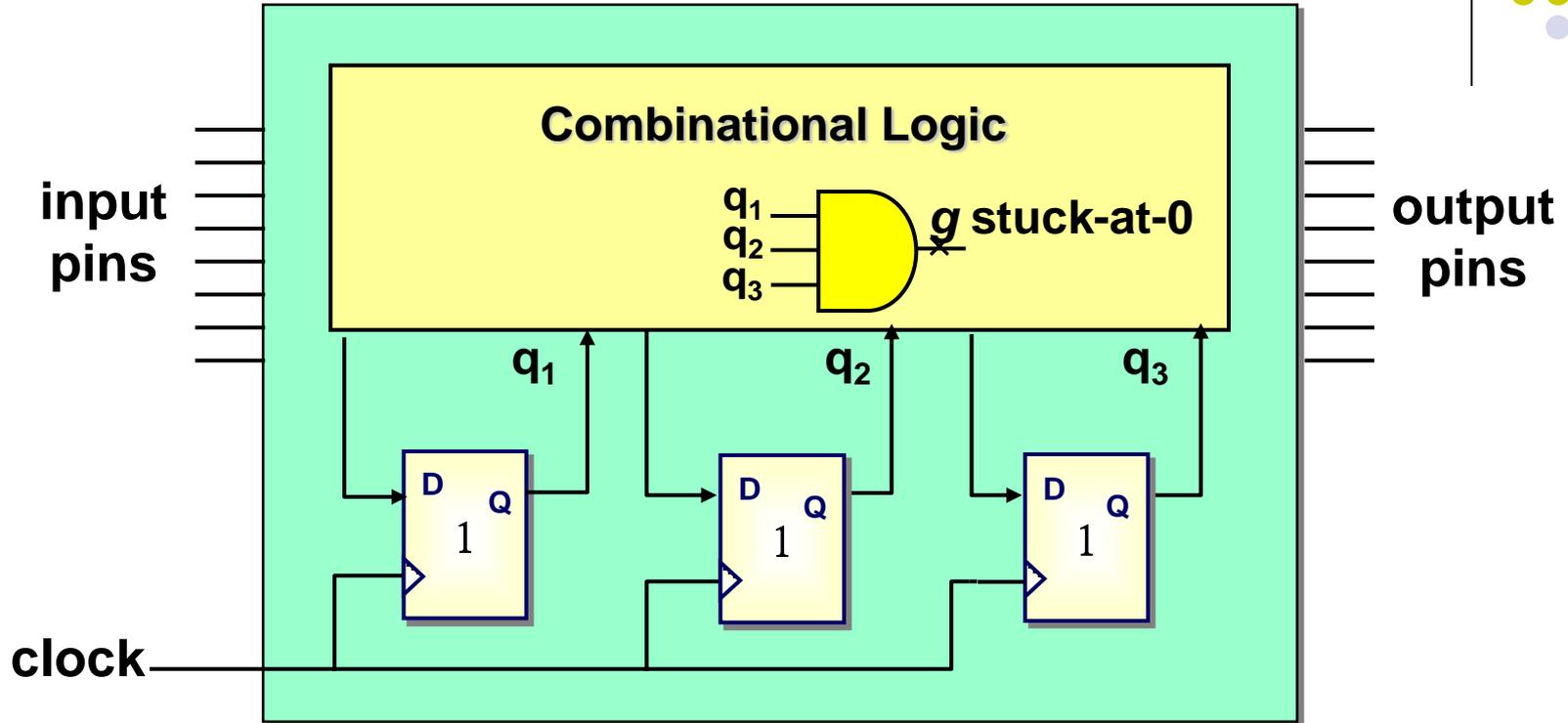
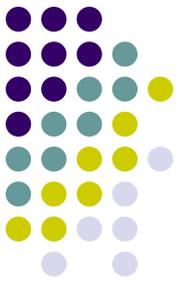
The test can not be generated by five-value TG.

Problems of Mixed Forward and Reverse Time Processing Approaches



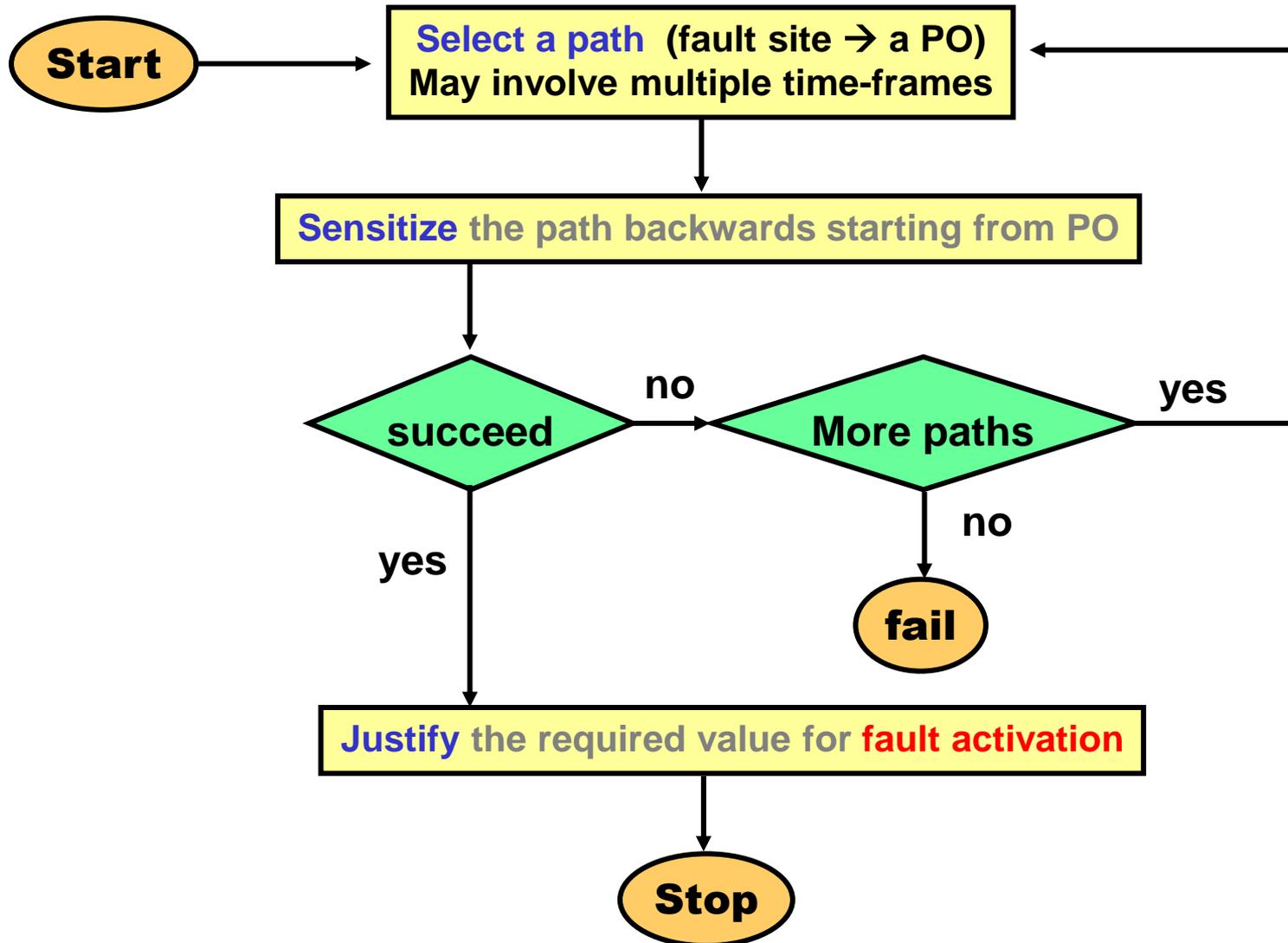
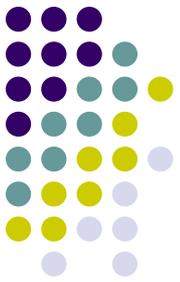
- The requirements created during the forward process (fault propagation) have to be justified by the backward process later.
 - Need going both forward and backward time frames.
 - May need to maintain **a large number of time-frames** during test generation.
 - Implementation is complicated.
 - Can't detect repetition of states

Example: A 3-stage Counter

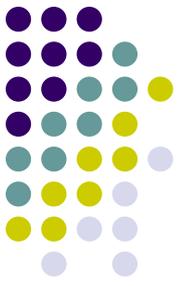


It takes **8 clock cycles** to set the flip-flops to be **(1, 1, 1)**,
for detecting the target fault **g stuck-at-0** fault
(2^{20} cycles for a 20-stage counter !)

EBT (Extended Backtrace) Algorithm



EBT Algorithm (con't)



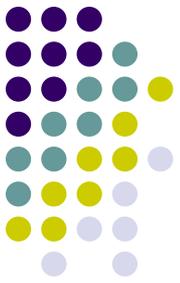
- **Advantages**

- At any time during test generation process, only **two time-frames** need to be maintained:
 - Current time-frame
 - Previous time-frame
- Easier to identify repetition of states and unjustifiable states

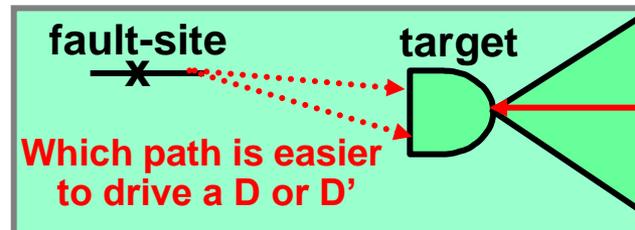
- **Disadvantages**

- Only single-path is selected
- The number of possible paths from fault site to POs is very large, trying **path by path may not be practical**

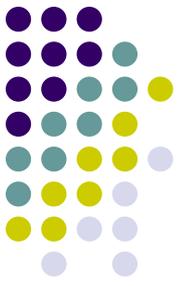
Drivability Definition



- A measure which can quantify the **difficulty of driving the fault effect from the fault-site to each line toward primary outputs**
 - Calculate from fault-site
 - Calculate for **each faulty machine**
 - Separate values for D and D'
- For searching fault propagation paths.
 - BACK algorithm



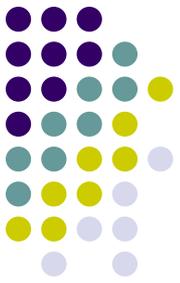
Drivability Calculation



- SCOAP controllability for both faulty/fault free circuits
 - Faults injected with extra gates (e.g., 2-input AND for S-A-0).
 - $CC0g(s)$, $CC1g(s)$, $CC0f(s)$, $CC1f(s)$
 - D-drive at fault site is 0 if S-A-0 is injected (D'-drive is infinity)
 - Example: 3-input AND gate G with inputs A, B and C.
 - To propagate a D from inputs to G (off-inputs of **fault free** circuit are 1)
 - $D_drive(G) = \min\{ D_drive(A) + CC1g(B) + CC1g(C), D_drive(B) + CC1g(A) + CC1g(C), D_drive(C) + CC1g(A) + CC1g(B) \}$
 - To propagate a D' from inputs to G (off-inputs of **faulty** circuit are 1)
 - $D'_drive(G) = \min\{ D'_drive(A) + CC1f(B) + CC1f(C), D'_drive(B) + CC1f(A) + CC1f(C), D'_drive(C) + CC1f(A) + CC1f(C) \}$

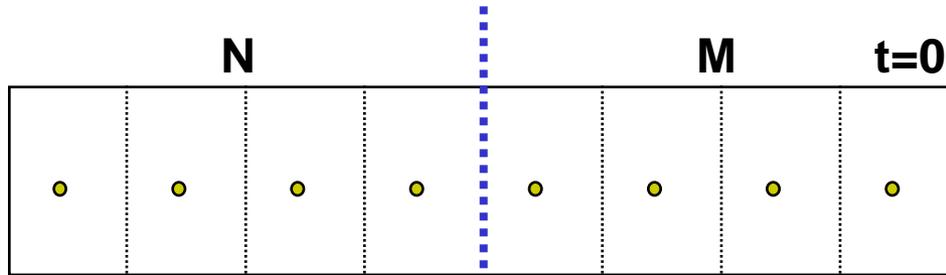
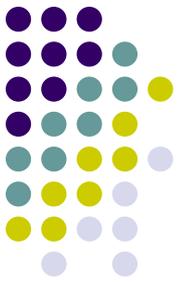
Back Algorithm

(Cheng, ICCD Oct. 1988)



- An improvement of EBT algorithm
- Assign a D or D' to a primary output and justify it backwards
- Use **drivability** to guide the **backward search** from the PO to the fault site
 - To justify a D at the output of a gate, select the **input with the smallest drivability** as the D input
 - Note that: **smaller drivability** means **smaller effort** for fault propagation
- The sensitized paths will be created implicitly

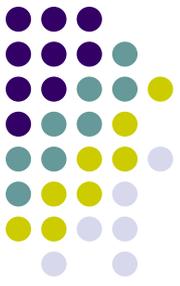
Back Algorithm



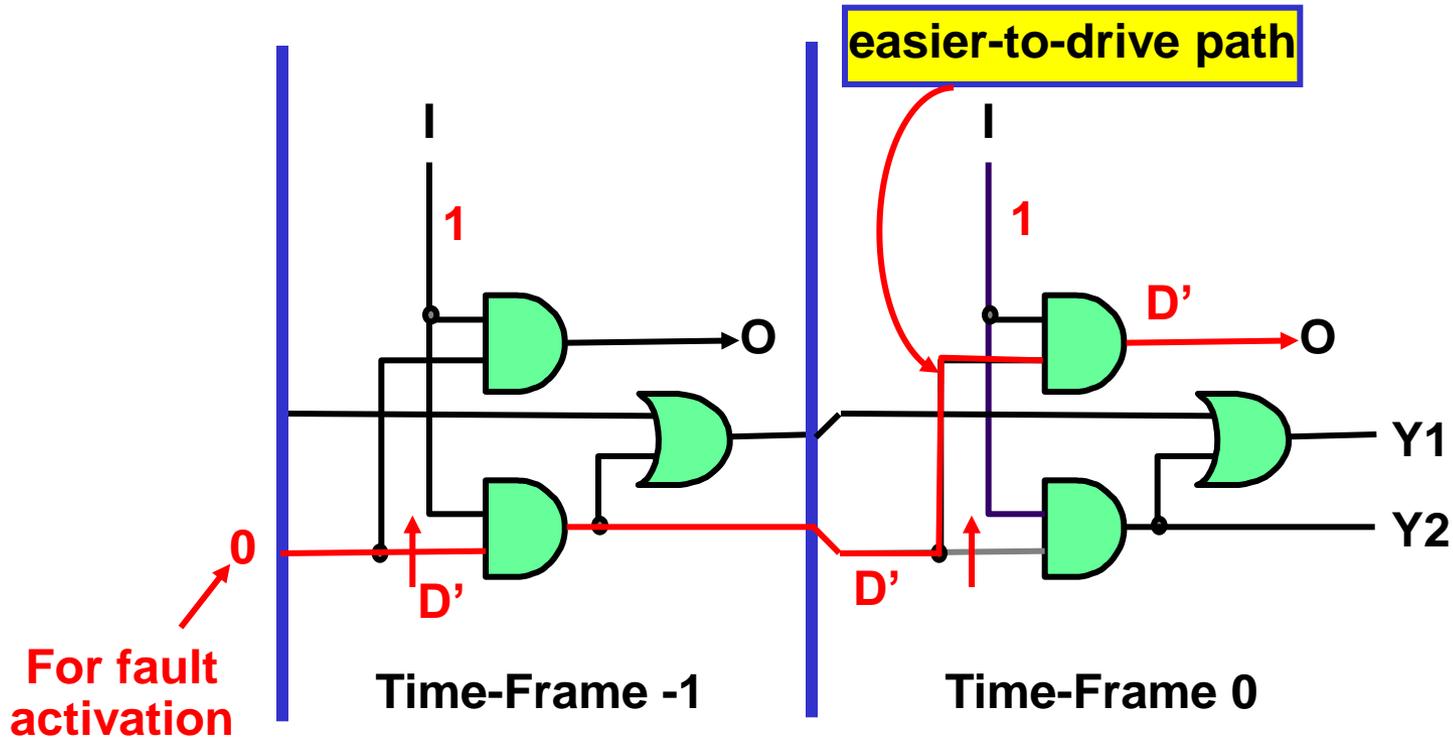
backward justification **fault propagation**

- **Good machine controllability calculation**
- Pick a fault and calculate bad machine **controllability** and **drivability**
 - Pick a **primary output** to have a sensitized value and set **t=0**
 - **Justify** all the values required at the current time frame
 - If **state matched**, test found
 - Else set **T=T-1** and continue another **time-frame processing**

Example: BACK Algorithm

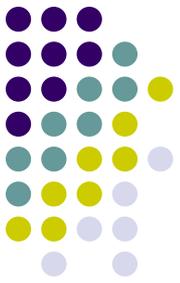


Step 1: Drive a D or D' from a PO to the fault site

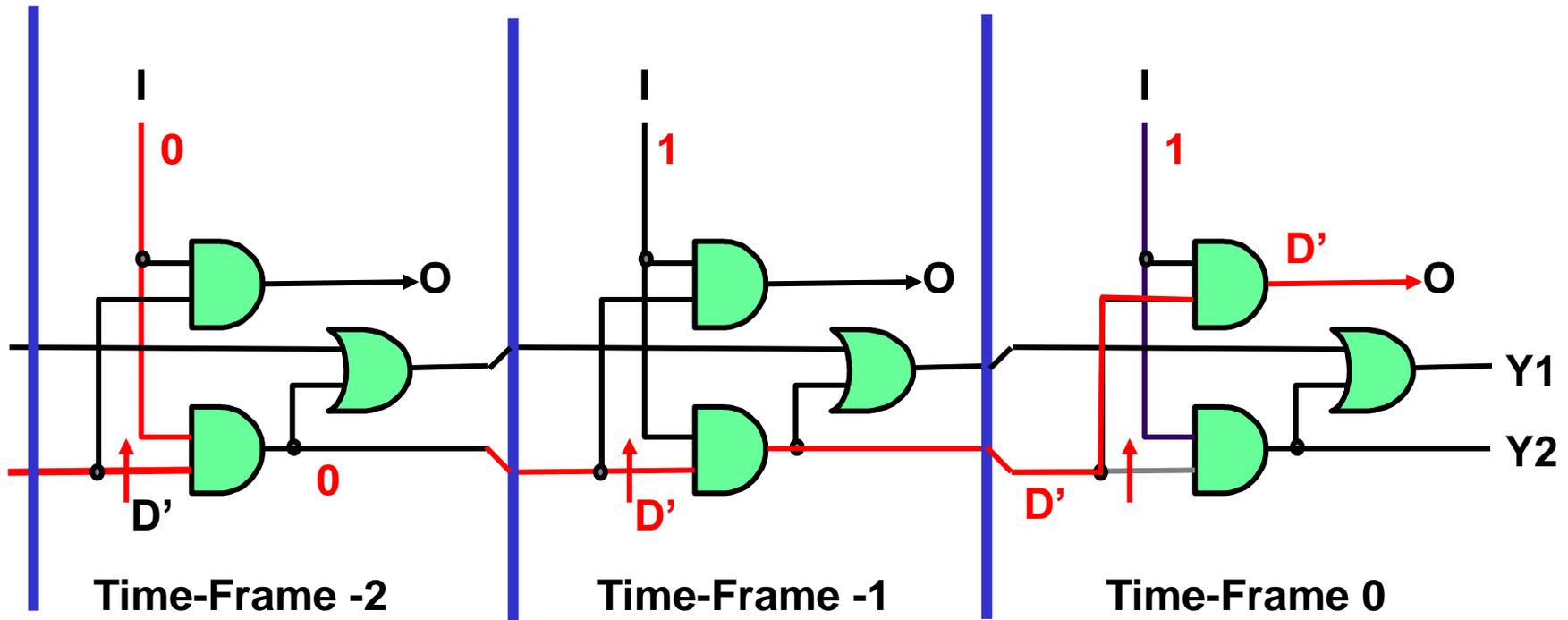


BACK algorithm involves only reverse-time processing

Example: BACK Algorithm

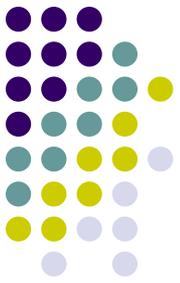


Step 2: Backward Line Justification



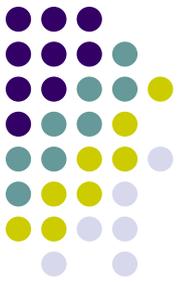
A Test Sequence (0, 1, 1) is found !

The BACK Algorithm



- **Main activities:**
 - Pre-select a primary output to have value D or D' guided by drivability
 - Backward line justification
 - Implication
- **Memory requirement:**
 - Two snapshots only
- **Scheduling of justification requirement:**
 - Simple

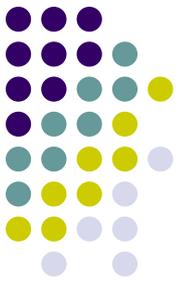
Outline



- **For Circuits with Unknown Initial States**
 - Time-frame Expansion Based:
 - Extended D-algorithm (IEEE TC, 1971)
 - 9-V Algorithm (IEEE TC, 1976)
 - EBT (DAC, 1978 & 1986)
 - BACK (ICCD, 1988), ...
 - **Simulation-Based:**
 - **CONTEST (IEEE TCAD, 1989)**
- **For Circuits with Known Initial States**
 - STALLION (IEEE TCAD, 1988)
 - STEED (IEEE TCAD, May 1991), ...

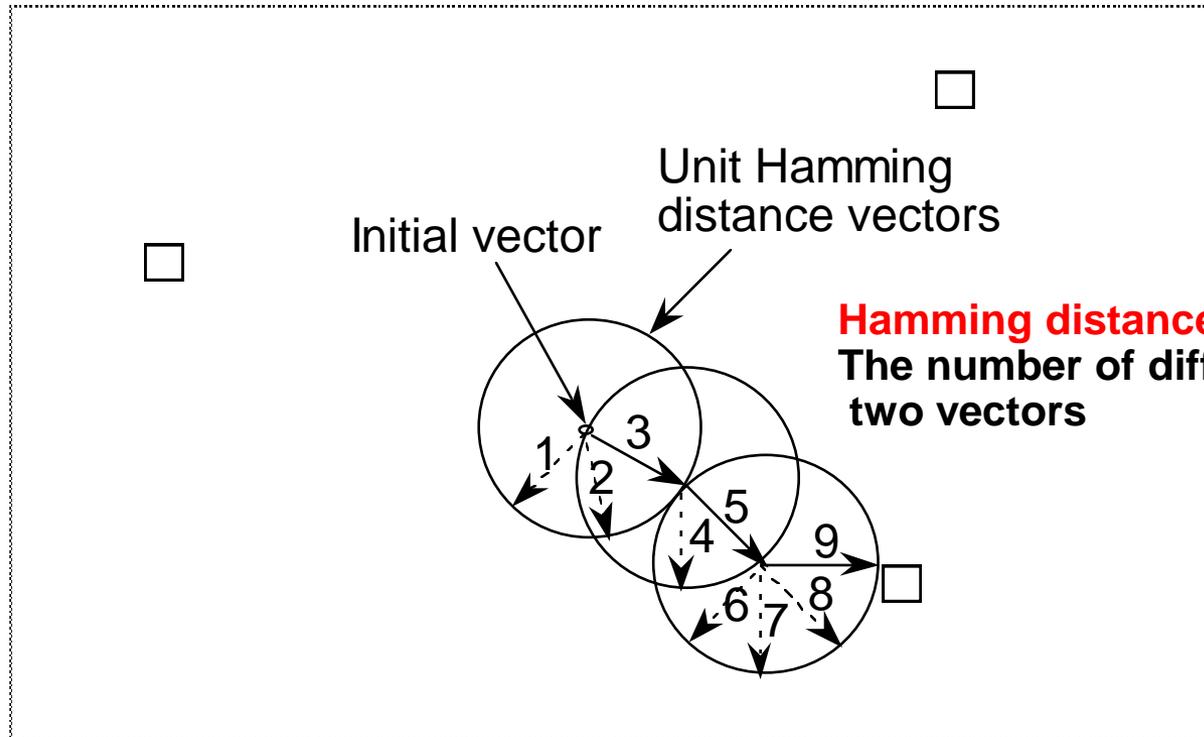
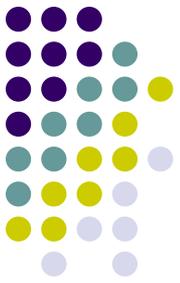
CONTEST: A Concurrent Test Generator for Sequential Circuits [3,4]

(Agrawal and Cheng, IEEE TCAD, Feb. 1989)



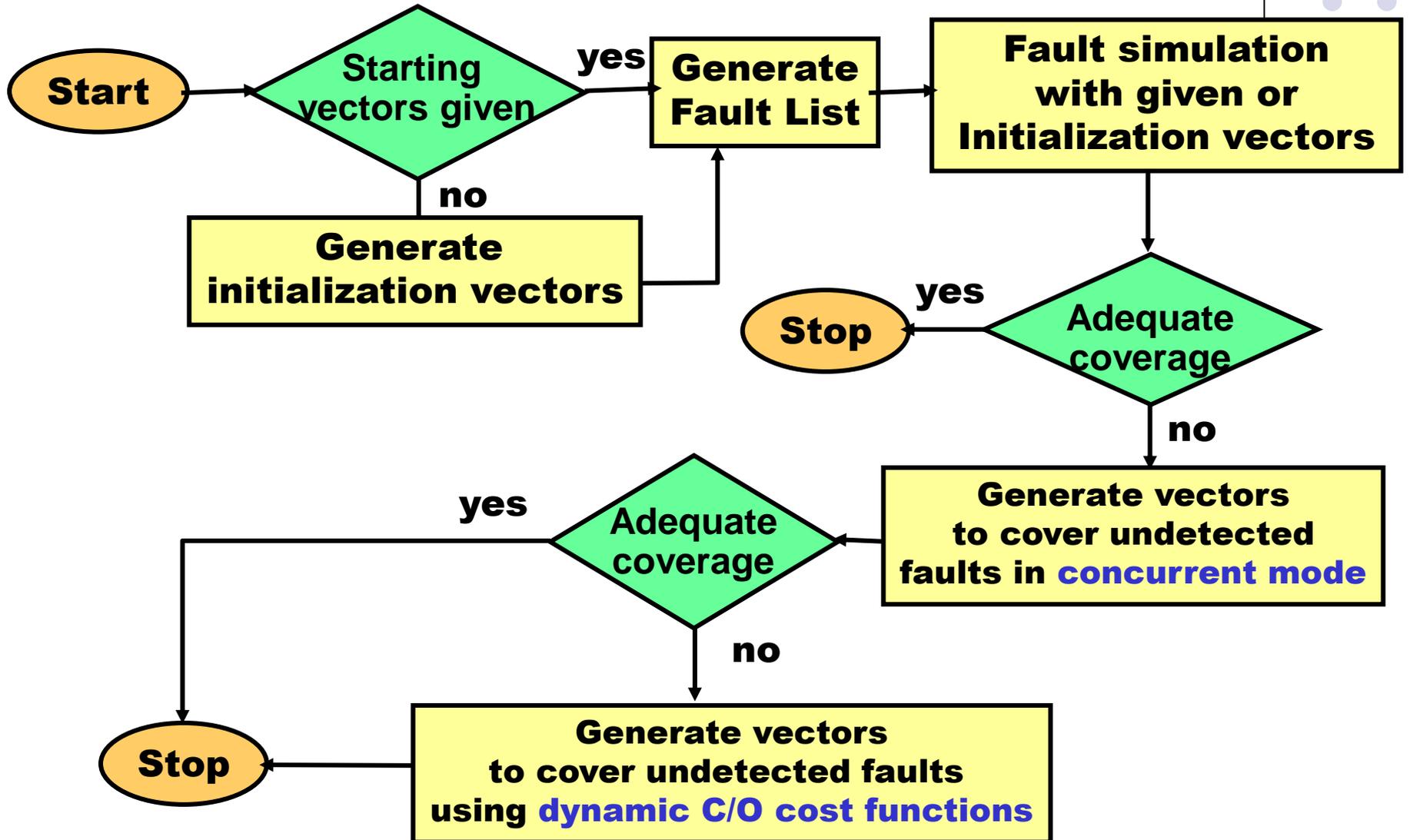
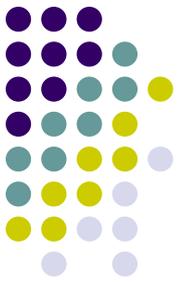
- **Simulation-based** test generation.
- It is subdivided into three phases :
 - Initialization
 - Concurrent fault detection
 - Single fault detection
- For different phases, different **cost functions** are defined to guide the searching for vectors.

Directed-Search in Input Vector Space

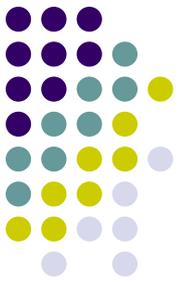


- the possible tests for the given target fault
- ➔ the trial vectors that are simulated but not accepted because of their higher costs.
- ➔ the accepted moves

Flow Chart of CONTEST

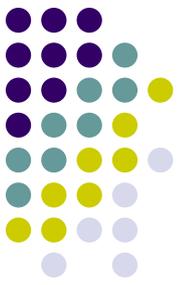


Phase 1 : Initialization



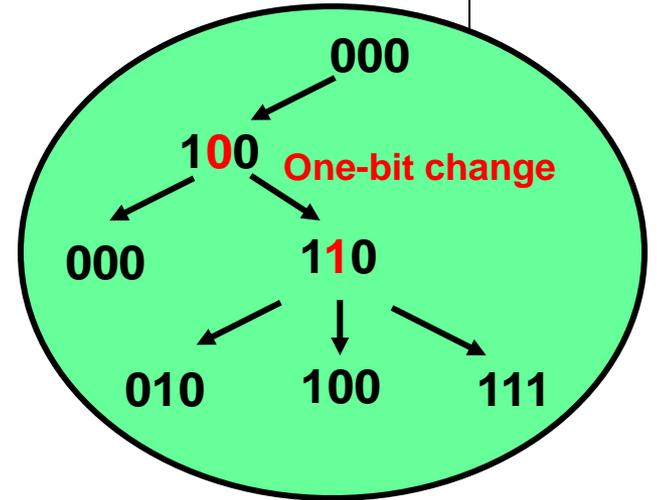
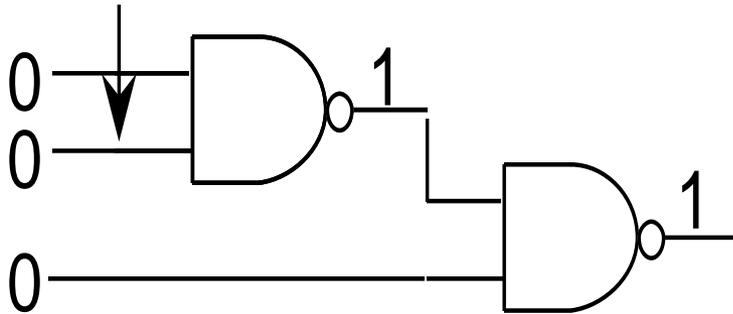
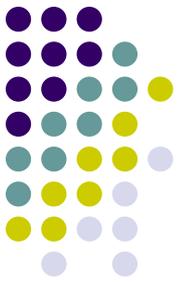
- **Start with arbitrary vector.**
- **Start with all flip-flops in unknown state.**
- **Use only true-value simulation**
 - **Cost = number of flip-flops in unknown state.**
 - **Generate new vectors to reduce the cost by one-bit change in the present vector.**
- **Stop when the cost drops below desired value.**

Phase 2 : Concurrent Fault Detection



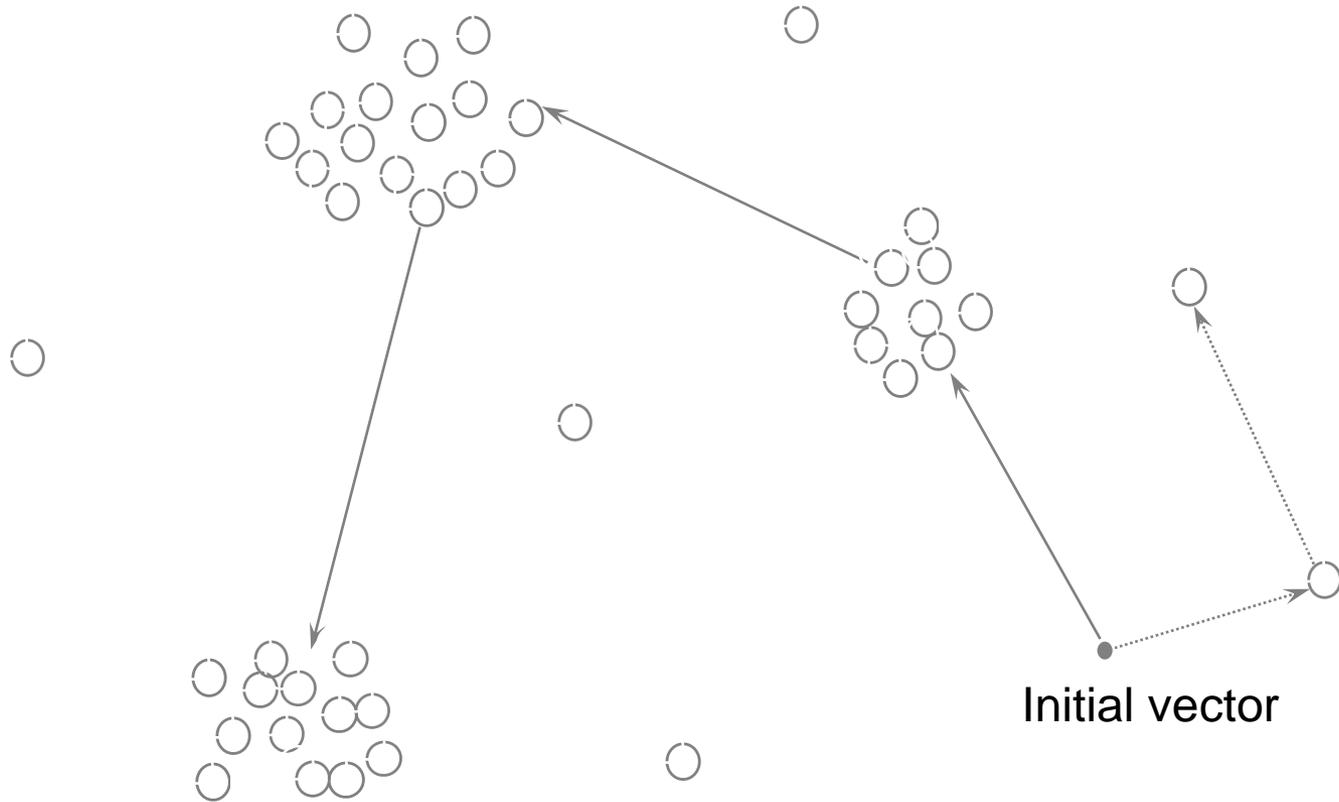
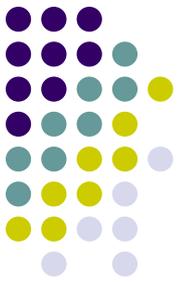
- Start with initialization vectors.
- Fault simulate the vectors and remove detected faults.
- Compute cost function for the last vector.
 - Cost of an undetected fault = minimum distance of its effect from a PO.
 - Cost of the vector = Sum of costs of some undetected faults (e.g., 10% of lowest cost faults).
- Generate new vectors by accepting only those one-bit changes that reduce **vector cost**.
- Switch to phase 3 when no cost can be reduced.

Example : Distance Cost Function



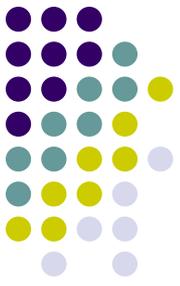
	0	1	0	1	0	1	1
Trial vectors	0	0	0	1	1	0	1
	0	0	0	0	0	0	1
Distance	∞	2	∞	1	∞	2	0

Multi-Target Guidance



-> **Search directed by a single target fault**
- > **Search directed concurrently by a set of faults**

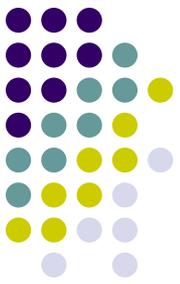
Phase 3 : Single Fault Detection



- Start with the last vector obtained from Phase 2.
- **Cost(F) = K x AC(F) + PC(i)** when F i-s-a-v not activated
= min PC(Nf) when faulty effects of F at Nf
 - AC: **Activation cost** is the dynamic controllability (SCOAP) of faulty line.
 - PC: **Propagation cost** is the minimum (over all paths) dynamic observability (SCOAP) of the faulty line.
 - Dynamic testability measures are calculated based on both the circuit structure and the signal states
 - K is a large weighting factor.
- Generate new vectors by accepting only those one-bit changes that **reduce vector cost** until the fault is detected or the search is abandoned.

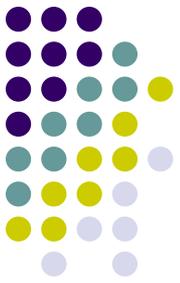
Genetic Algorithms

(CRIS, GATEST, GATTO, STRATEGATE)



- Improve simulation-based algorithm by “learning” past success of vectors
- Define fitness functions
 - Should involve fault simulation data
- Create an initial population of vectors
- Create new generations of vectors by *crossover, mutation, selection*
 - Crossover: combine bits from two vectors
 - Mutation: manipulate bits of a vector
 - Selection: select the best-fit vectors

Simulation-Based Approaches



Advantages:

- Timing is considered.
- Asynchronous circuits can be handled.
- Can be easily implemented by modifying a fault simulator.

Disadvantages:

- Can not identify undetectable faults.
- Hard-to-activate faults may not be detected.

Results for Simulation-based Approach [8]



Circuit	Total faults	HITEC [7]		GATEST [15, 26]		CRIS [12]		GATTO [16]		DIGATE		
		Det	Vec	Det	Vec	Det	Vec	Det	Vec	Det	Vec	Dist
s298	308	265	306	264	161	253	476	-	-	264	239	7
s344	342	328	142	329	95	328	115	-	-	329	109	8
s382	399	363	4931	347	281	273	246	-	-	363	581	6
s400	426	383	4309	365	280	357	758	-	-	382	3369	11
s444	474	414	2240	405	275	397	519	-	-	420	1393	9
s526	555	365	2232	417	281	428	692	-	-	446	2867	9
s641	467	404	216	404	139	398	628	-	-	404	180	17
s713	581	476	194	476	128	475	1124	-	-	476	147	17
s820	850	813	984	517	146	451	1381	-	-	621	465	9
s832	870	817	981	539	150	370	1328	-	-	606	703	9
s1196	1242	1239	453	1232	347	1180	2744	1226	5202	1236	549	13
s1238	1355	1283	478	1274	383	1229	4313	1274	4672	1281	504	12
s1423	1515	776	177	1222	663	1167	2696	1265	3394	1393	4044	30
s1488	1486	1444	1294	1392	243	1355	1960	1344	631	1378	542	5
s1494	1506	1453	1407	1416	245	1357	1928	1277	912	1354	581	6
s5378	4603	3238	941	3175	511	3029	1255	3277	1132	3447	10500	94
s35932	39094	34902	240	35009	197	34481	1525	32943	563	35100	386	301
am2910	2391	2164	874	2163	745	-	-	-	-	2195	2206	71
mult16	1708	1640	273	1653	204	-	-	-	-	1664	915	32
div16	2147	1665	189	1739	634	-	-	-	-	1802	4481	3
pcont2	11300	3354	7	6826	272	-	-	-	-	6837	3452	0
piir8o	19920	14221	347	15013	531	-	-	-	-	15072	506	0
piir8	29689	11131	31	-	-	-	-	-	-	18140	603	0

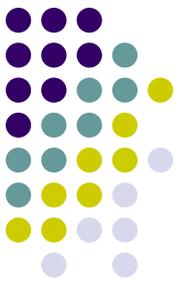
Det: number of faults detected

Vec: test set length

Dist: number of distinguishing sequences generated

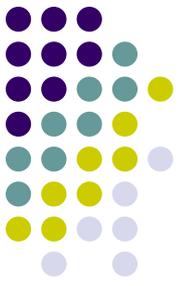
Highest numbers of detections are highlighted

Results for Time-Frame-Based Approach [9]



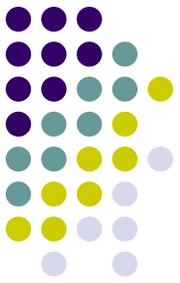
Circuit	ATOMS				HITEC			
	Det	Unt	Vect	Time	Det	Unt	Vect	Time
s298	265	30	312	5.5s	265	26	322	16.2m
s344	329	11	127	24.9s	324	11	115	8.1m
s349	335	13	118	23.9s	332	13	128	7.7m
s382	364	18	5169	2.9m	301	9	1463	1.5h
s386	314	70	328	3.2s	314	70	286	7.3s
s400	384	27	3868	3.2m	341	17	1845	1.2h
s444	424	29	4433	5.5m	373	25	1761	1.5h
s510	0	564	0	1.0s	-	-	-	-
s526	451	18	6552	29.0m	316	23	436	5.8h
s641	404	63	184	2.0s	404	63	209	4.8s
s713	476	105	172	2.4s	476	105	173	6.7s
s820	814	36	997	19.9s	813	37	1115	3.5m
s832	818	52	998	19.4s	817	53	1137	5.8m
s953	89	990	13	6.2s	-	-	-	-
s1196	1239	3	373	2.6s	1239	3	435	5.5s
s1238	1283	72	409	3.2s	1283	72	475	8.2s
s1423	1095	10	570	40.6m	723	14	150	13.9h
s1488	1444	42	1101	1.1m	1444	41	1170	16.5m
s1494	1453	53	1162	36.7s	1453	52	1245	9.6m
s5378	3379	148	839	34.2m	3231	217	912	18.4h
s35932	34,908	3984	272	1.8h	34,901	3984	496	4.7h

Outline



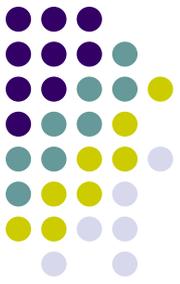
- **For Circuits with Unknown Initial States**
 - Time-frame Expansion Based:
 - Extended D-algorithm (IEEE TC, 1971)
 - 9-V Algorithm (IEEE TC, 1976)
 - EBT (DAC, 1978 & 1986)
 - BACK (ICCD, 1988), ...
 - Simulation-Based:
 - CONTEST (IEEE TCAD, 1989)
- **For Circuits with Known Initial States**
 - STALLION (IEEE TCAD, 1988)
 - STEED (IEEE TCAD, May 1991), ...

Test Generation Assuming A known Initial State

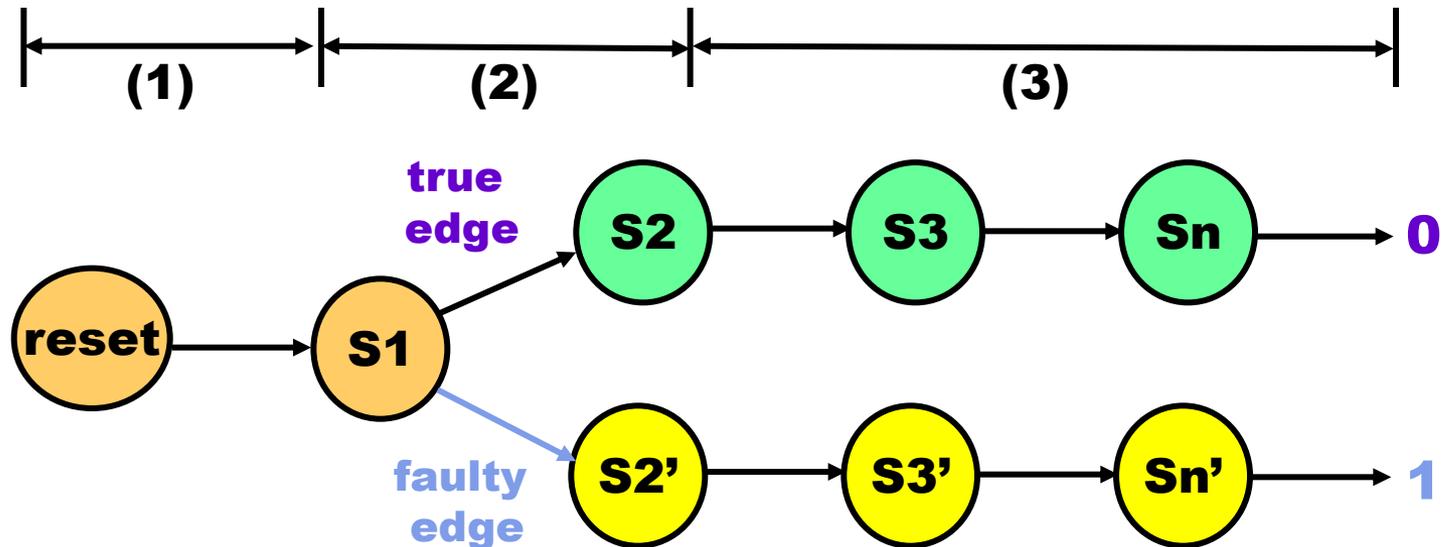


- Initialization is avoided.
- Valid for pure controllers that usually have a reset mechanism (reset PI, resettable flip-flops, ...)

Test Generation for State-Transition Fault

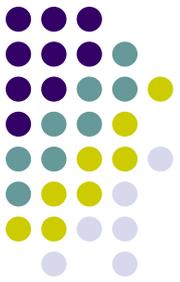


- A test sequence for a state-transition fault has
 - (1) initialization sequence
 - (2) input label of the faulty transition
 - (3) state pair **differentiating sequence** between good and faulty states



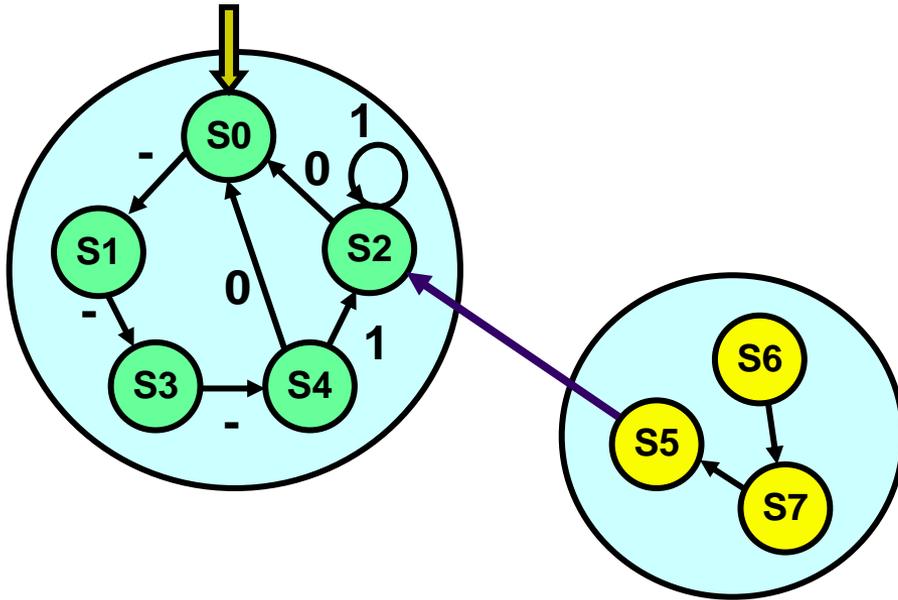
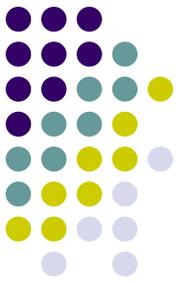
STALLION [5]

(Ma et al, IEEE TCAD, Oct. 1988)

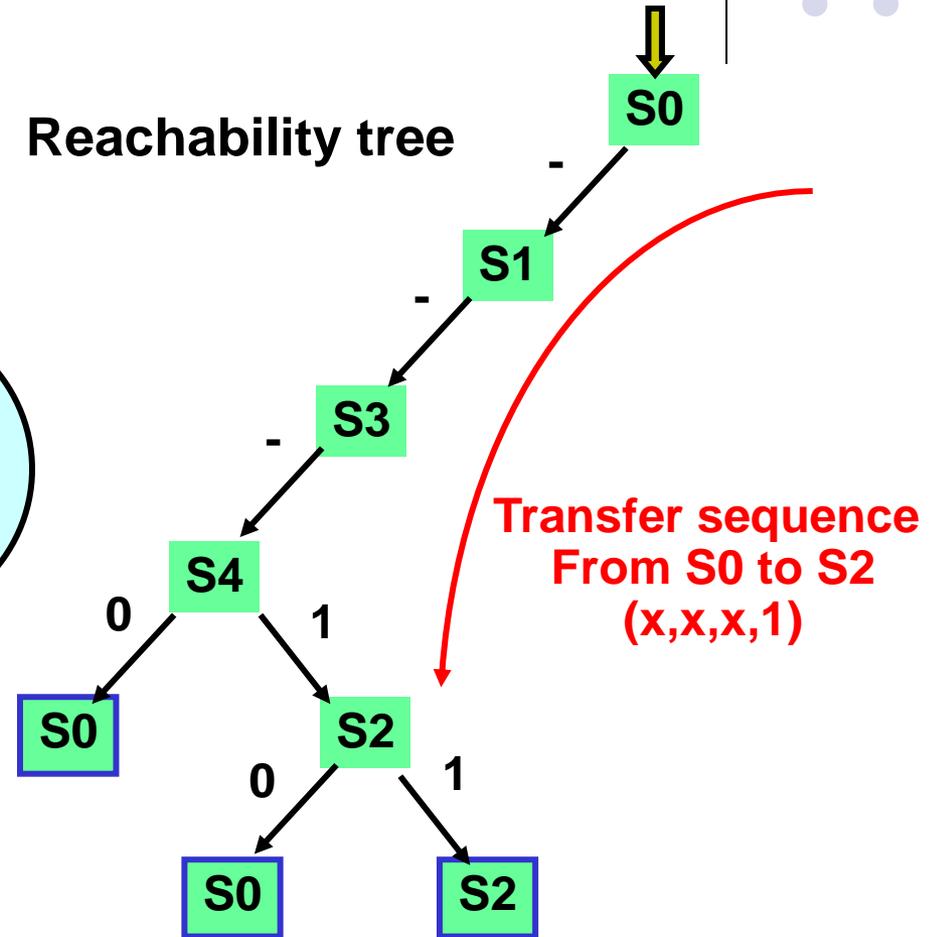


1. Generate **State Transition Graph (STG)** for **fault-free circuit**
2. For the fault, find an activation state **S** and a fault propagation sequence **T** to a PO using **PODEM** and the time-frame expansion models
3. When there are values required in PPI's, say state **S**, find a **transfer sequence T0** from initial state **S0** to **S** **using the STG**
4. Fault simulate sequence **T0+T**. If it is not a valid test, go to step 2 or 3 to find another sequence

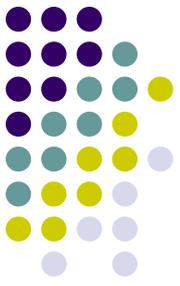
Finding Transfer Sequence



Reachability tree



STALLION



Advantages:

- Transfer sequences are easily derived from STG.
- Good performance for controllers whose STG can be extracted easily.

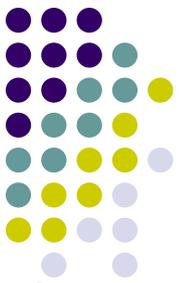
Disadvantages:

- Fault-free transfer sequence may not be valid.
 - Approximation only
- Extraction of STG may not be feasible for large circuits.

Heuristics:

- Construct **partial STG** only.
- If the required transfer sequence can not be derived from partial STG, augment the partial STG.

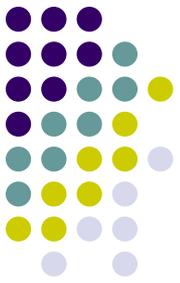
STEED



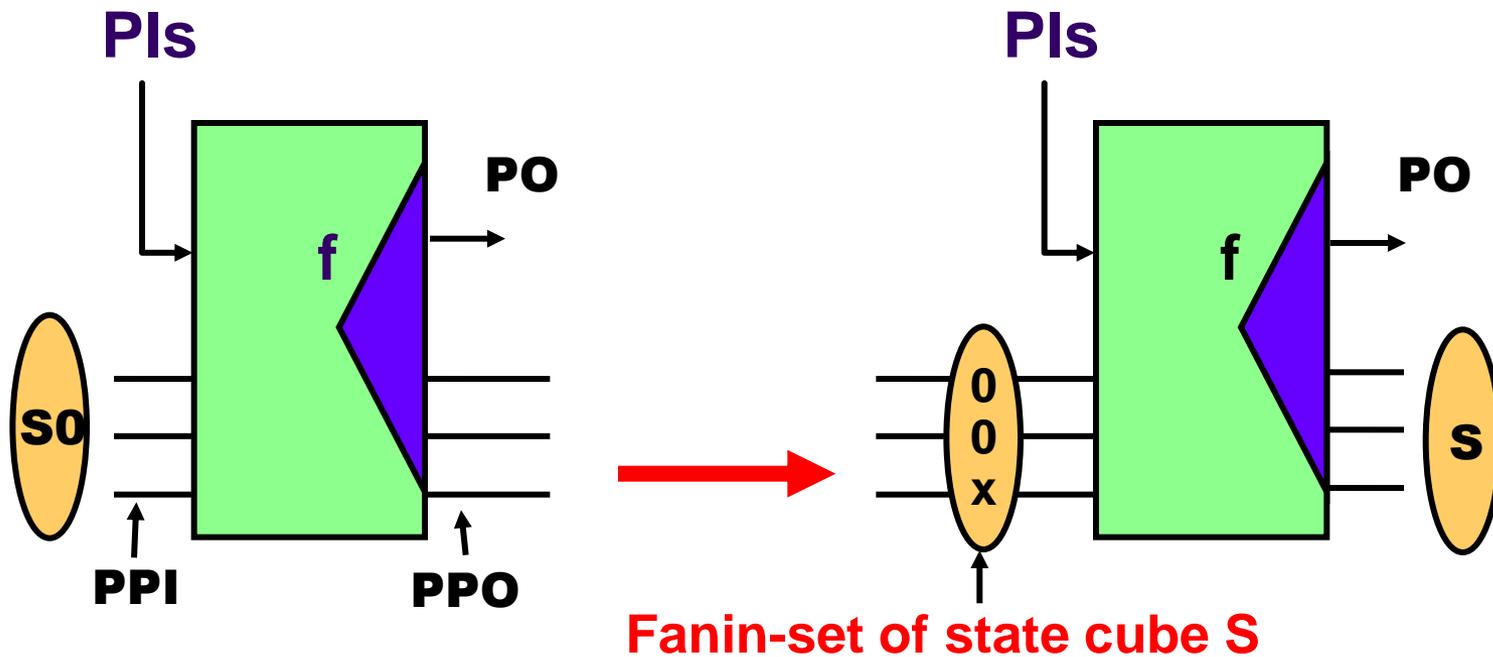
(Ghosh et al, IEEE TCAD, May 1991)

- Generate **ON/OFF sets** for each PO and Next State line for fault-free circuit
- Generate a **combinational test vector $V=(I,S)$** .
 - Assume that the PO and NS values are O_g and S_g for fault-free circuit and O_f and S_f for faulty circuit
- Find a **transfer sequence from S_0 to S**
 - Pick On-set (Off-set) of NS line if corresponding PS line has a 1 (0) in S
 - Intersect the picked On and Off sets (**Fanin-set of S**)
 - If any cube in **Fanin-set covers S_0** stops. Otherwise select a cube in fanin-set and continue
- If $O_g \neq O_f$ stops. Otherwise, find a **differentiating sequence** for S_g and S_f
 - Find a PO and **an input pattern I that $(I, S_g) \in \text{On-set}$ and $(I, S_f) \in \text{Off-set}$** (or vice-versa)
 - If not possible, find a **differentiating sequence** of length greater than 1 using similar procedure

Transfer Sequence



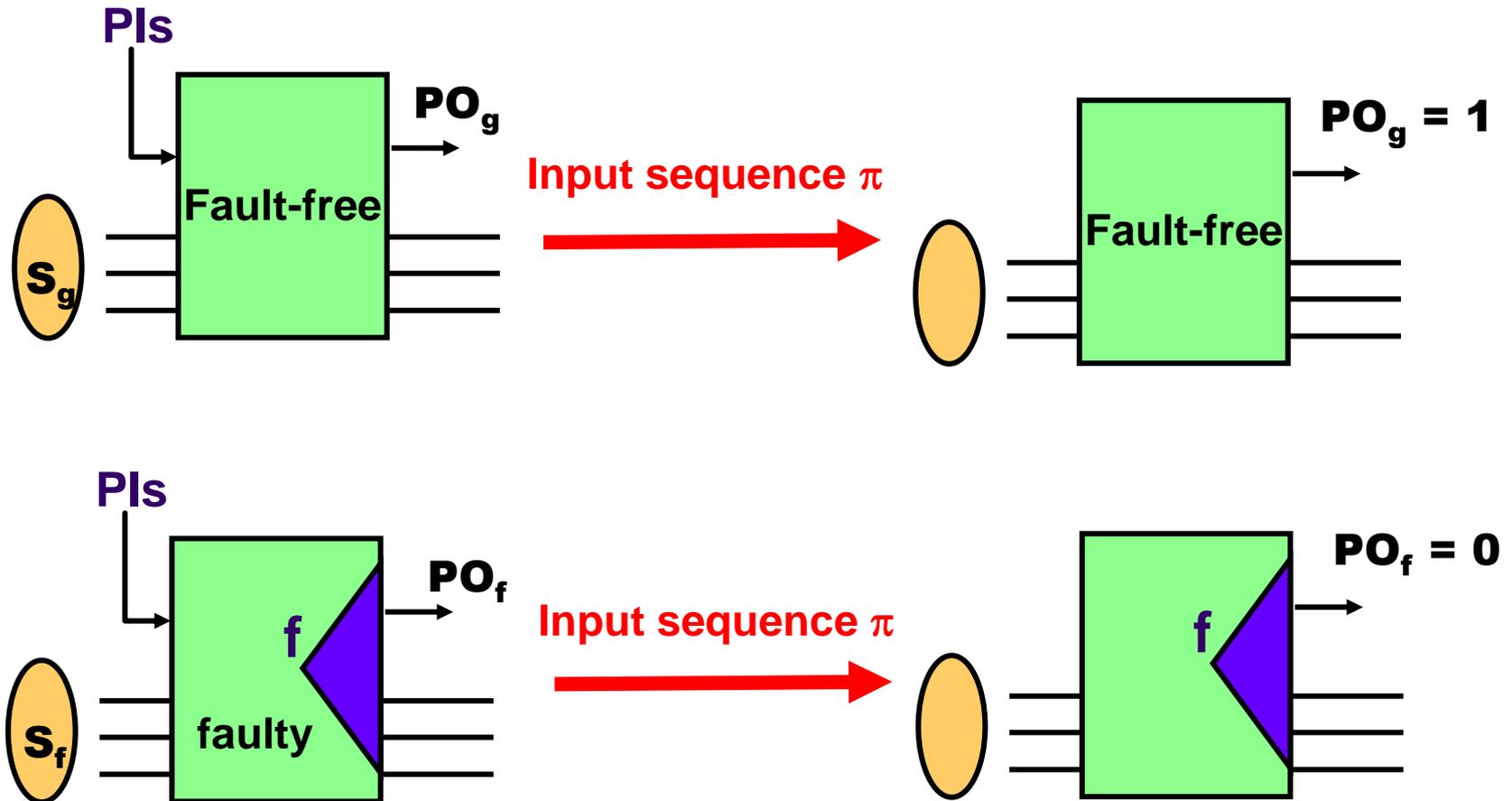
An input sequence causes a state sequence ($S_0 \rightarrow \dots \rightarrow S$)



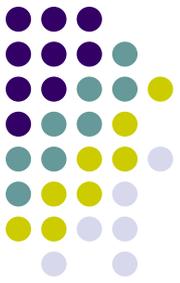
Differentiating Sequence



An input sequence that can differentiate a state pair (S_g, S_f)
i.e., final $PO_{\text{fault-free}} \neq PO_{\text{faulty}}$

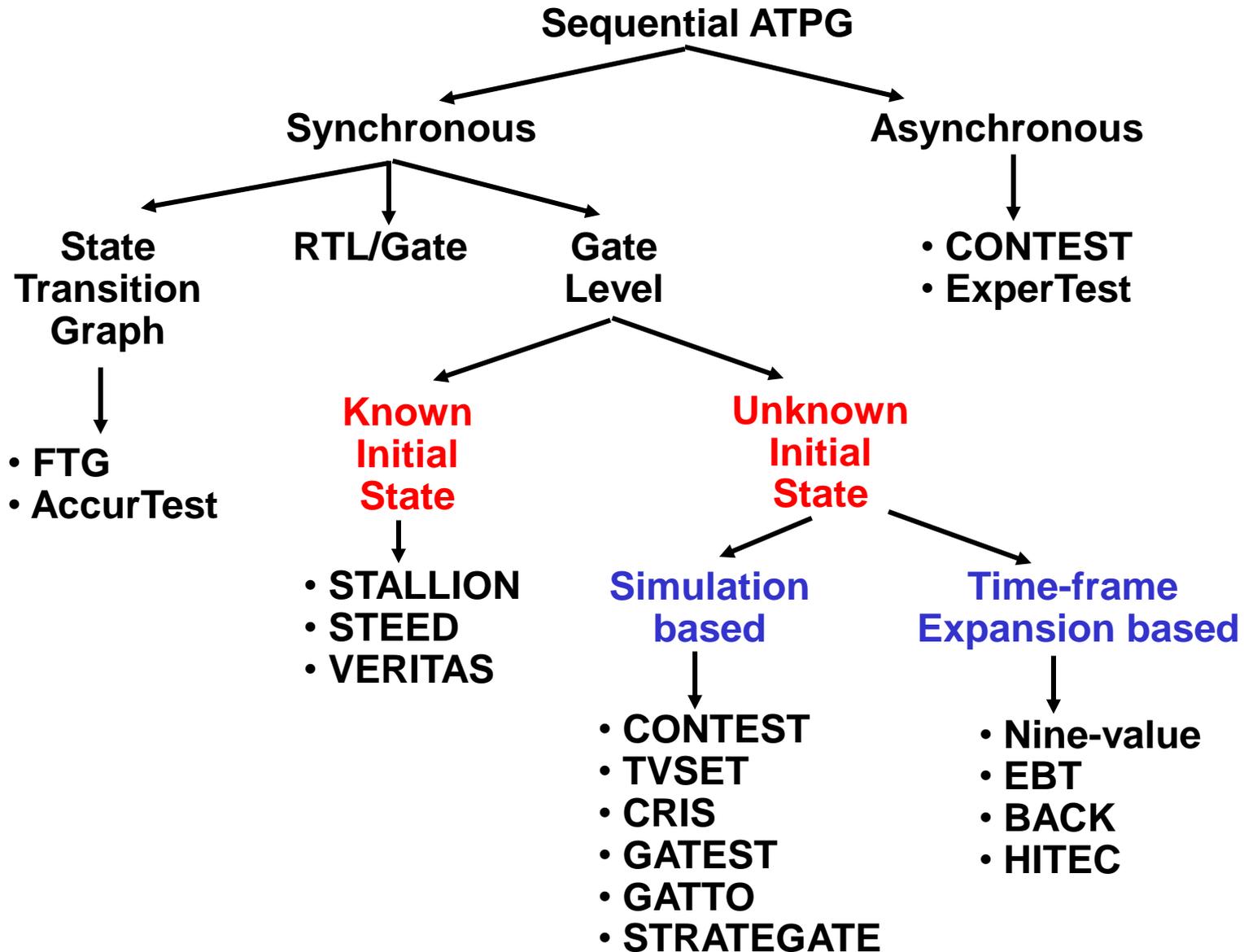
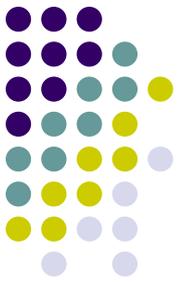


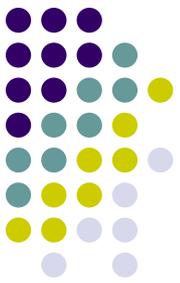
STEED



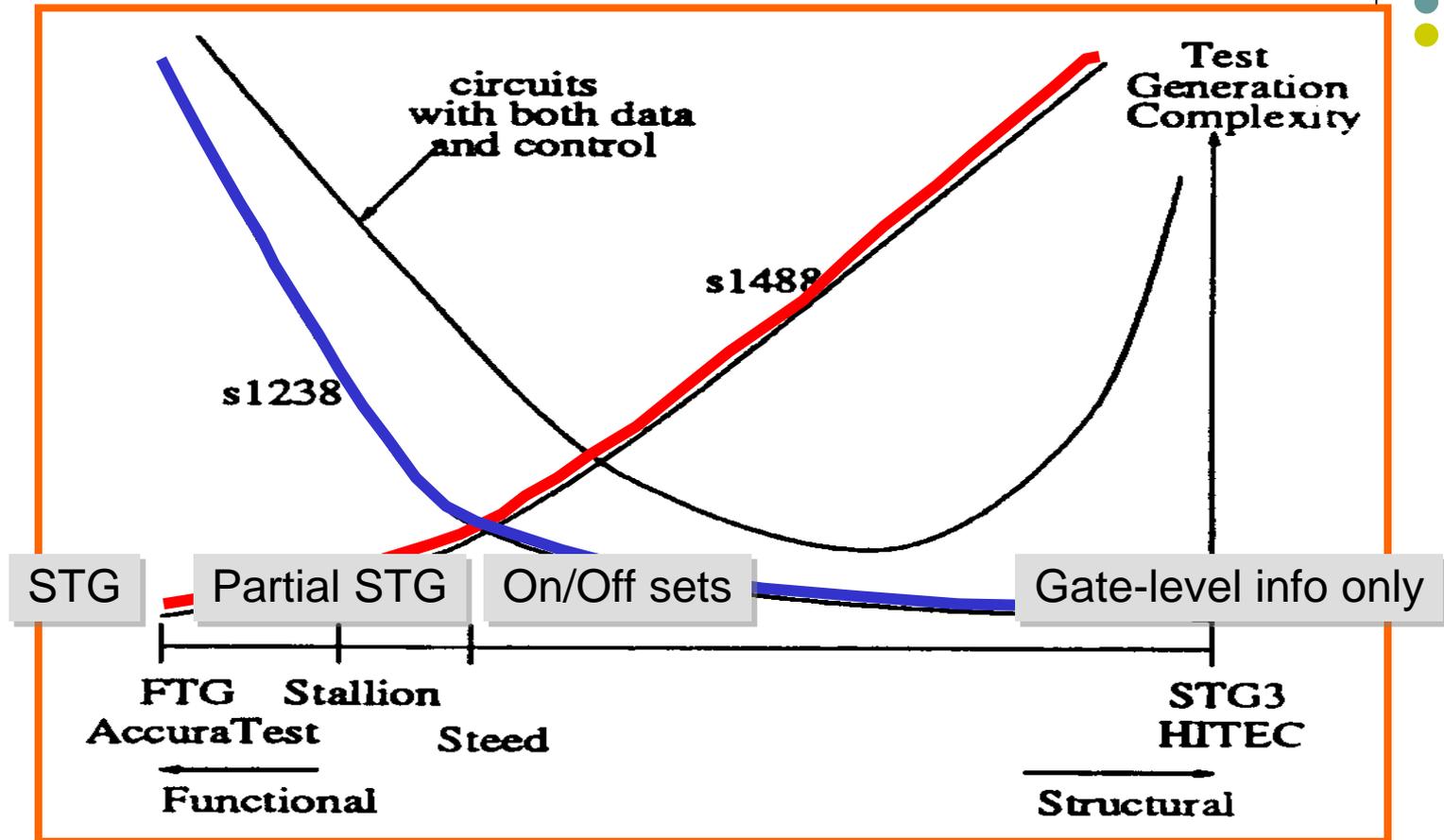
- Advantages
 - ON/OFF-set is a more compact representation than STG
 - Good performance for circuits that have relatively small ON/OFF-sets
- Disadvantages
 - Fault-free transfer and propagation sequences may not be valid
 - Approximation only
 - Generating, storing and intersecting the ON/OFF sets may be very expensive for certain functions, e.g., parity trees

Sequential ATPG: Taxonomy



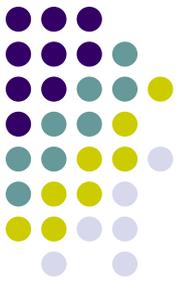


Circuit Contents And ATPG Algorithms



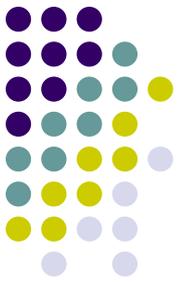
- Algorithms using functional information (FTG, etc) runs faster on pure control circuits (small # of F.F.; complex NS/PO functions, e.g., s1488).
- STG3 and HITEC runs faster on s1238 (and most larger benchmarks).
- Hybrid ATPG is required

General Issues on Sequential ATPG (I)

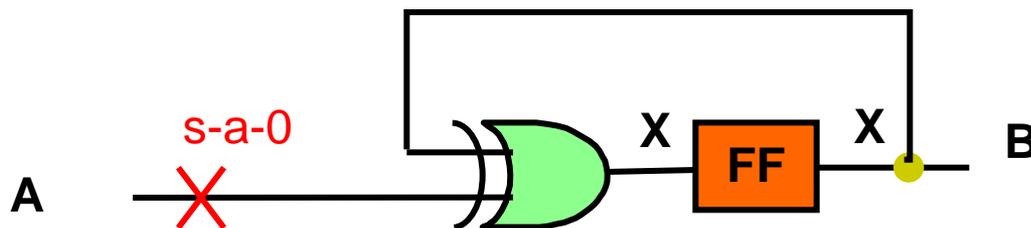


- May not be able to handle highly sequential circuits
 - Consider the stuck-at-0 fault at the MSB of a 20-bit counter....
- Timing may not be accurately modeled in ATPG process
 - The sequence generated may cause races and hazards
 - The sequence must be verified by a simulator
- Tools must guarantee that there is no hazard on asynchronous preset and clear
- Tools must guarantee that test sequence will not cause bus contention
- Multiple-clock/ multiple-phase designs
 - Include clock signals into ATPG process
 - Remodeling of flip-flops
- Efficient Identification of undetectable faults

General Issues on Sequential ATPG (II)



- Potentially detected faults
 - 1/X, 0/X at primary outputs
- Multiple-observation test
 - Need to observe multiple cycles of outputs
 - For the example circuits
 - Fault-free: $A=1 \rightarrow B=(0 \rightarrow 1 \rightarrow 0 \dots)$, $A=0 \rightarrow B=0$ or 1
 - A difficult circuit for 3-state simulator
 - A multiple-observation test: $A=1$ for two cycles
 - Fault-free $B=0 \rightarrow 1$ or $1 \rightarrow 0$
 - Faulty $B=1 \rightarrow 1$ or $0 \rightarrow 0$
 - An expensive test: need to observe some unknown outputs

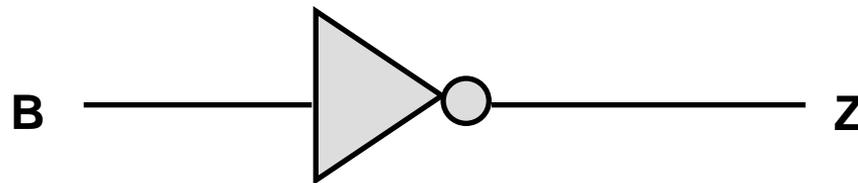
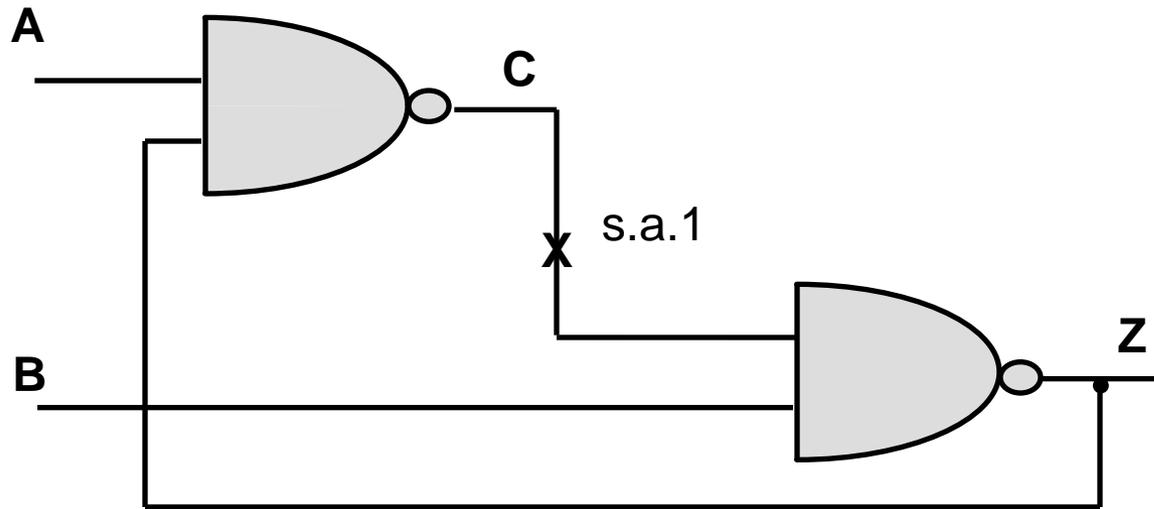
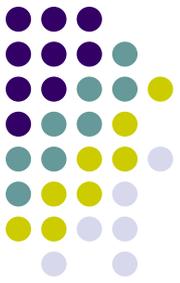


Test Generation for an Asynchronous Circuit



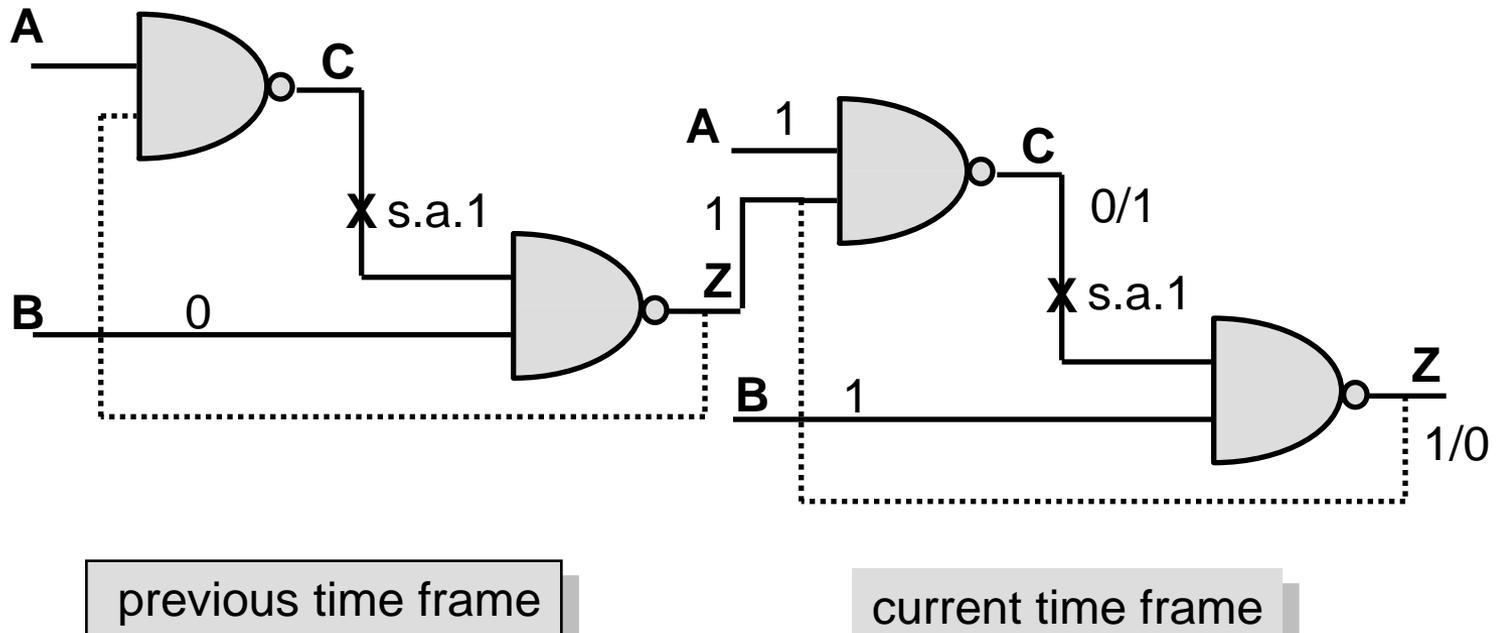
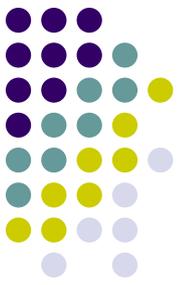
- Test generation for Circuits with combinational loops
 - Apply time-frame expansion techniques with additional constraints
 - Signal values on combinational loops have to be stable for a given PI, i.e., PS/NS have to have the same values under the current inputs.

Example of an Asynchronous Circuit



Faulty function

Time-Frame Expansion for Asynchronous Test Generation



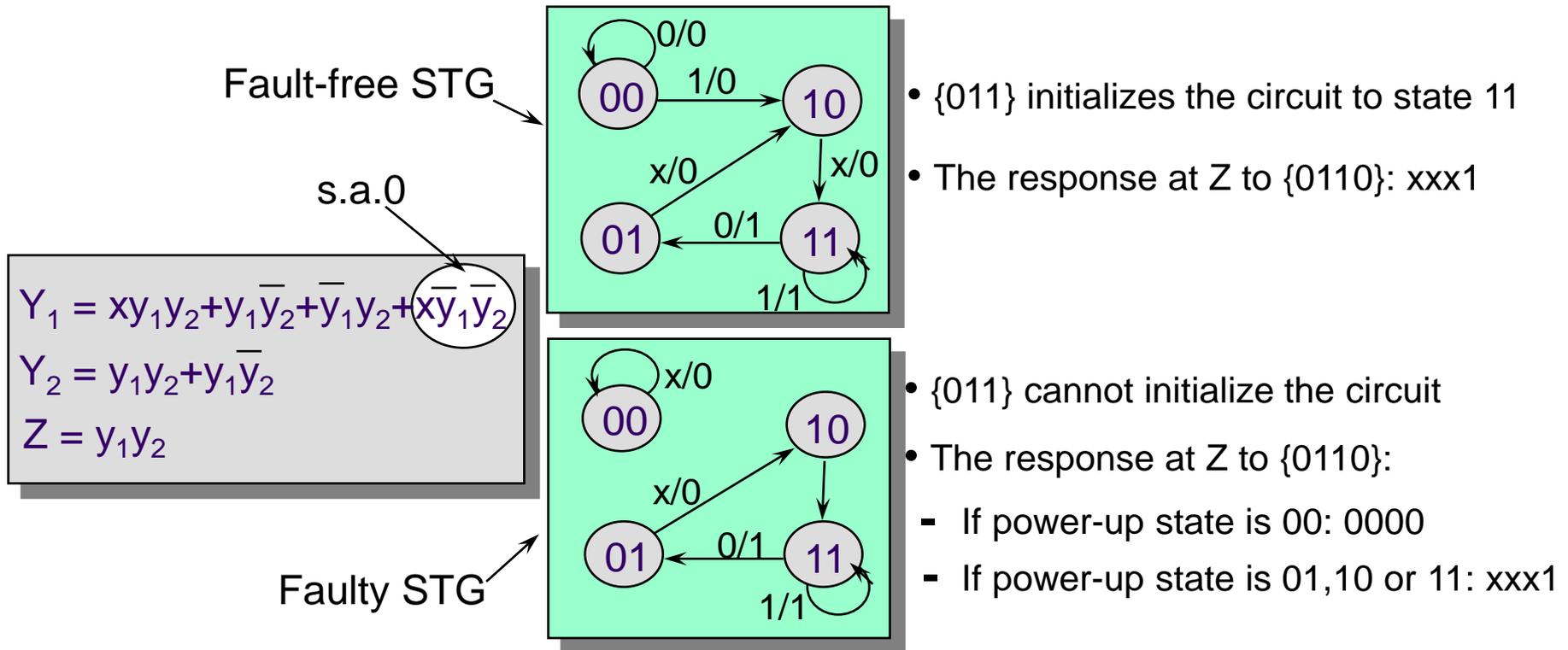
Test needs to be verified by a fault simulator with proper timing model !!

$(A B)=(X 0)$ and $(1 1)$ will detect the fault at Z, but assign $(A B)=(0 0)$ will cause a race in the fault-free circuit

Potentially Detectable Faults

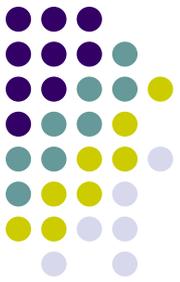


- Faults that are detectable for some initial power-up states & undetectable for other initial power-up states.

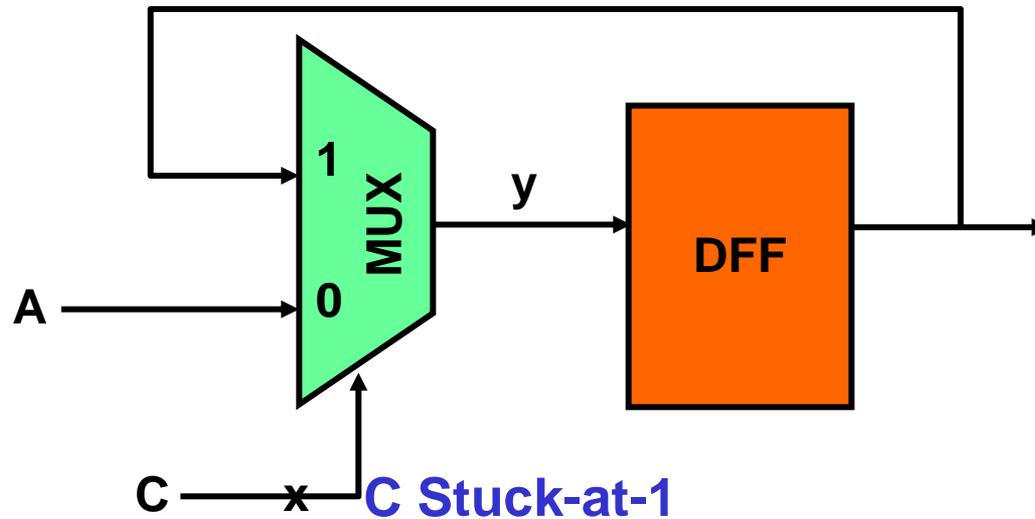


The fault is detectable if the power-up state of the faulty circuit is 00, otherwise, it is undetectable => It is potentially detectable.

Detectability V.S. Redundancy



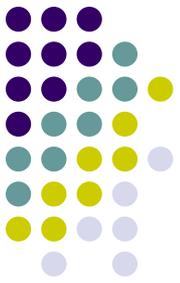
- A fault is not detectable under some test strategy (e.g. single observation) may not be redundant.



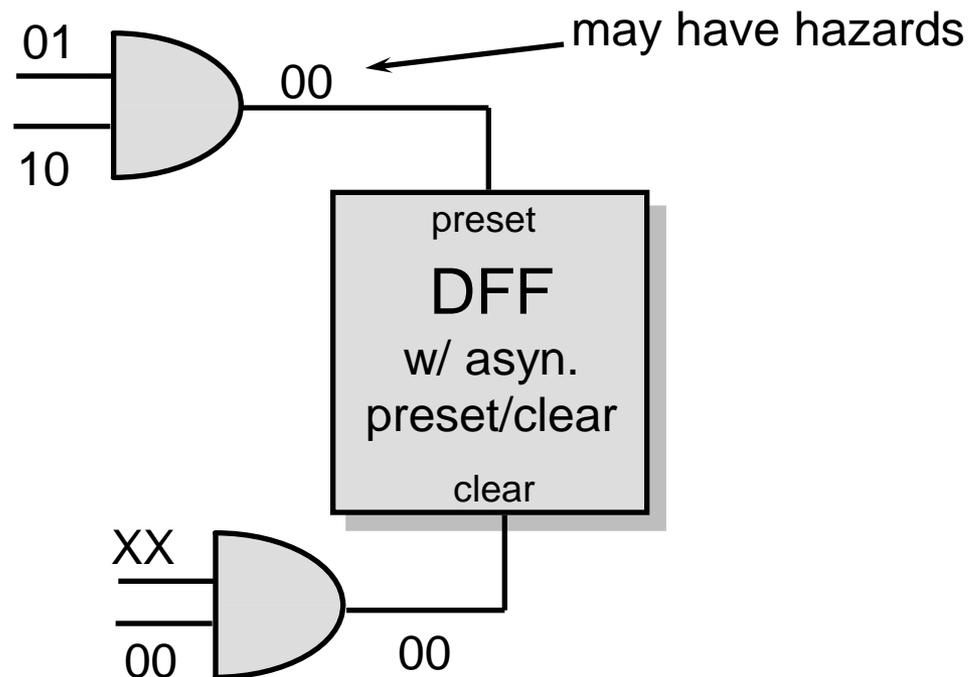
Sequence	A	C	Initial state = X/0	Initial state = X/1
V ₁	1	0	1/0	1/1
V ₂	0	0	0/0	0/1

(A C)=(1 0) (0 0) will test the fault under multiple observation tests.

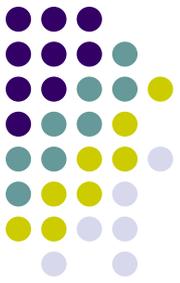
Hazards on Asynchronous Preset and Clear



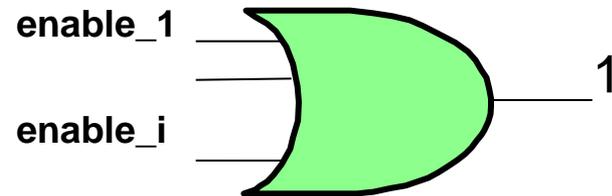
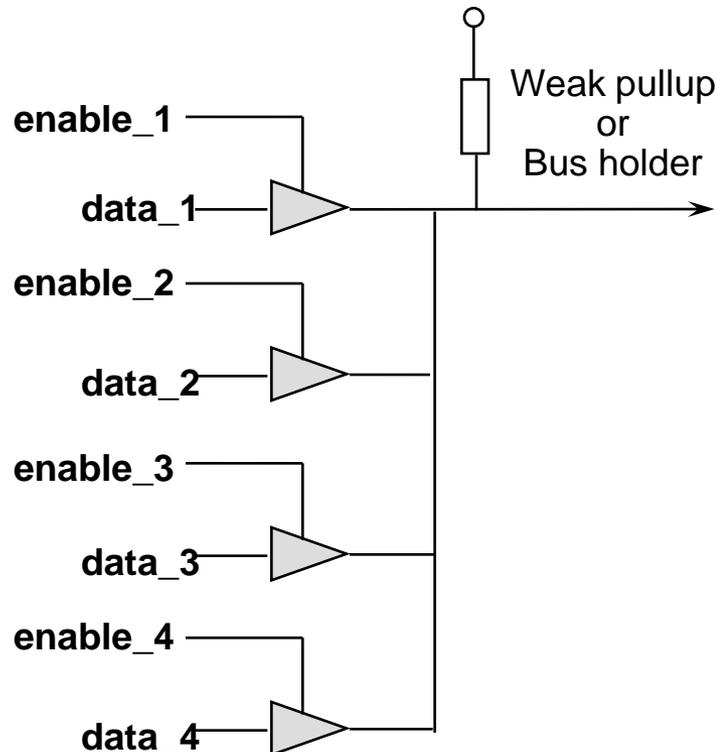
- Require careful logic simulation of ATPG patterns to prevent unwanted results



Bus Contention Resolution

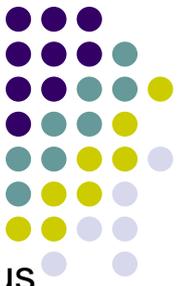


- **Add ATPG constraints (pseudo logic) to confirm**
 - At least one driver is enabled
 - Only drivers with the same data can be enabled



At least one driver is enabled

References



- [1] G. R. Putzolu and T. P. Roth, "A Heuristic Algorithm for the Testing of Asynchronous Circuits", IEEE Trans. Computers, pp. 639-647, June 1971.
- [2] P. Muth, "**A Nine-Valued Circuit Model for Test Generation**", IEEE Trans. Computers, pp. 630-636, June 1976.
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- [4] K. T. Cheng and V. D. Agrawal, "Unified Methods for VLSI Simulation and Test Generation", Chapter 7, Kluwer Academic Publishers, 1989.
- [5] H-K. T. Ma, et al, "**Test Generation for Sequential Circuits**", IEEE Trans. CAD, pp. 1081-1093, Oct. 1988.
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- [8] M. S. Hsiao, E. M. Rudnick, and J. H. Patel, 1996. "Automatic test generation using genetically-engineered distinguishing sequences." VTS 1996.
- [9] I. Hamzaoglut and J. H. Patel, "Deterministic test pattern generation techniques for sequential circuits", ICCAD 2000.