

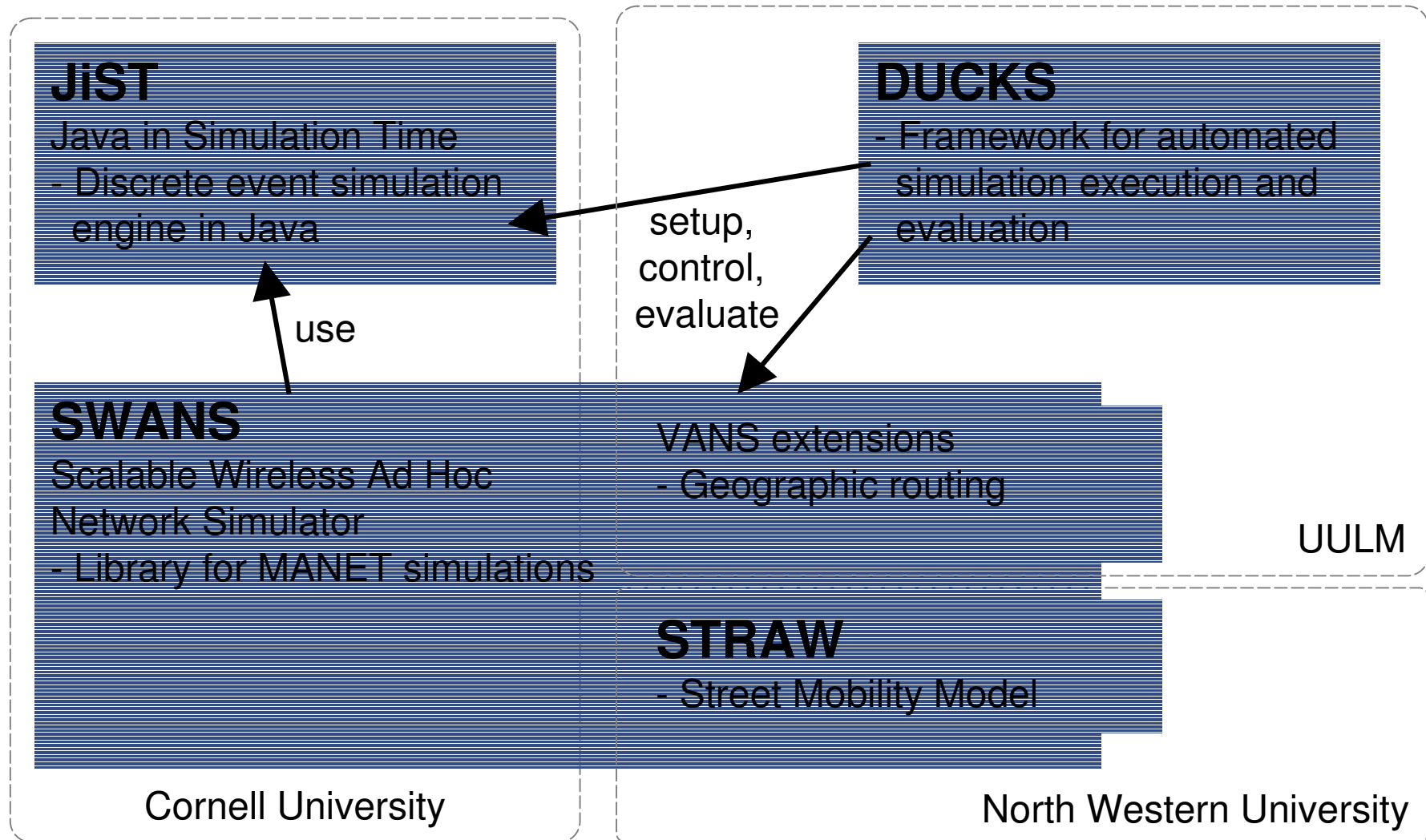


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VANET Simulations with JiST/ SWANS

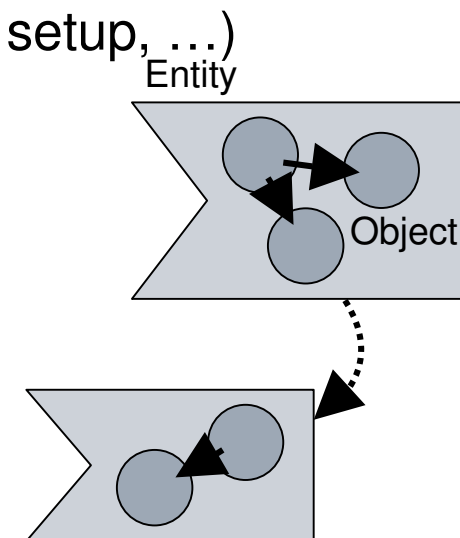
SEVECOM Kick-off Workshop
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Overview



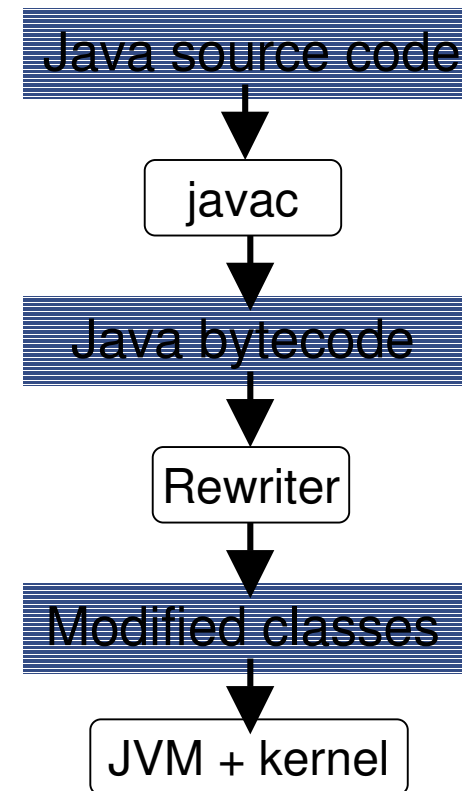
JiST – Simulation Kernel

- Basic idea: Convert virtual machine into simulation platform
 - Introduce virtual time
 - Make use of modern language concepts
- Base: Java and JVM
 - All components are pure Java
(Rewriter, simulation kernel, library, simulation setup, ...)
 - Reuse Java: reflection, interfaces, libraries, ...
- Kernel
 - Strict partitioning of a simulation into entities
 - Method invocations on objects marked as entities represent simulation events
 - No explicit event queue, but virtual, explicit time progress



JiST – System architecture

- Java source files are compiled with regular Java compiler
- Running JiST invokes Rewriter
 - Rewriter modifies Java bytecode to introduce simulation time semantics
- JiST invokes simulation program
 - Rewritten program interacts with simu kernel
 - Virtual time progress independent of program progress (instructions take zero virtual time)
 - Time is advanced explicitly via `JistAPI.sleep()`
 - Time synchronization between Entities on method invocation (each Entity runs at own simulation time)
- Classes may be used without underlying JiST Kernel



JiST example

```
import jist.runtime.JistAPI;

class Hello implements JistAPI.Entity {

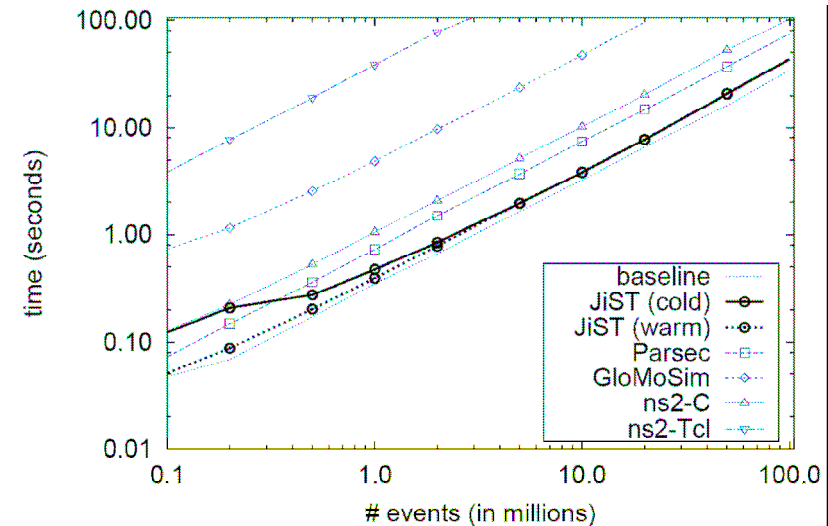
    public static void main(String[] args) {
        System.out.println("Simulation start");
        Hello h = new Hello();
        h.doSequence(3);
    }

    public void doSequence(int count) {
        while( count > 0 ) {
            JistAPI.sleep(1);
            System.out.println("Hello t="+JistAPI.getTime());
            count--;
        }
    }
}
```

```
# java jist.runtime.Main Hello
> Simulation start
> Hello t=1
> Hello t=2
> Hello t=3
```

JiST – Performance

- Event throughput
 - ~ three times faster than ns2-C
 - ns2-Tcl shows extreme performance degradation
 - JiST shows kink in the first simulation second due to JIT compiler



5×10^6 events	time (sec)	vs. baseline	vs. JiST
baseline	1.640	1.0x	0.8x
JiST	1.957	1.2x	1.0x
Parsec	3.705	2.3x	1.9x
ns2-C	5.151	3.1x	2.6x
GloMoSim	23.720	14.5x	12.1x
ns2-Tcl	160.514	97.9x	82.0x

- Memory footprint

memory	entity	event	10K nodes sim.
JiST	36 B	36 B	21 MB
GloMoSim	36 B	64 B	35 MB
ns2	544 B	36 B*	72 MB*
Parsec	28536 B	64 B	2885 MB

SWANS

- Library for MANET simulations
- SWANS is an application of JiST
- Special properties:
 - Promises to handle huge node numbers with reasonable time/memory requirements

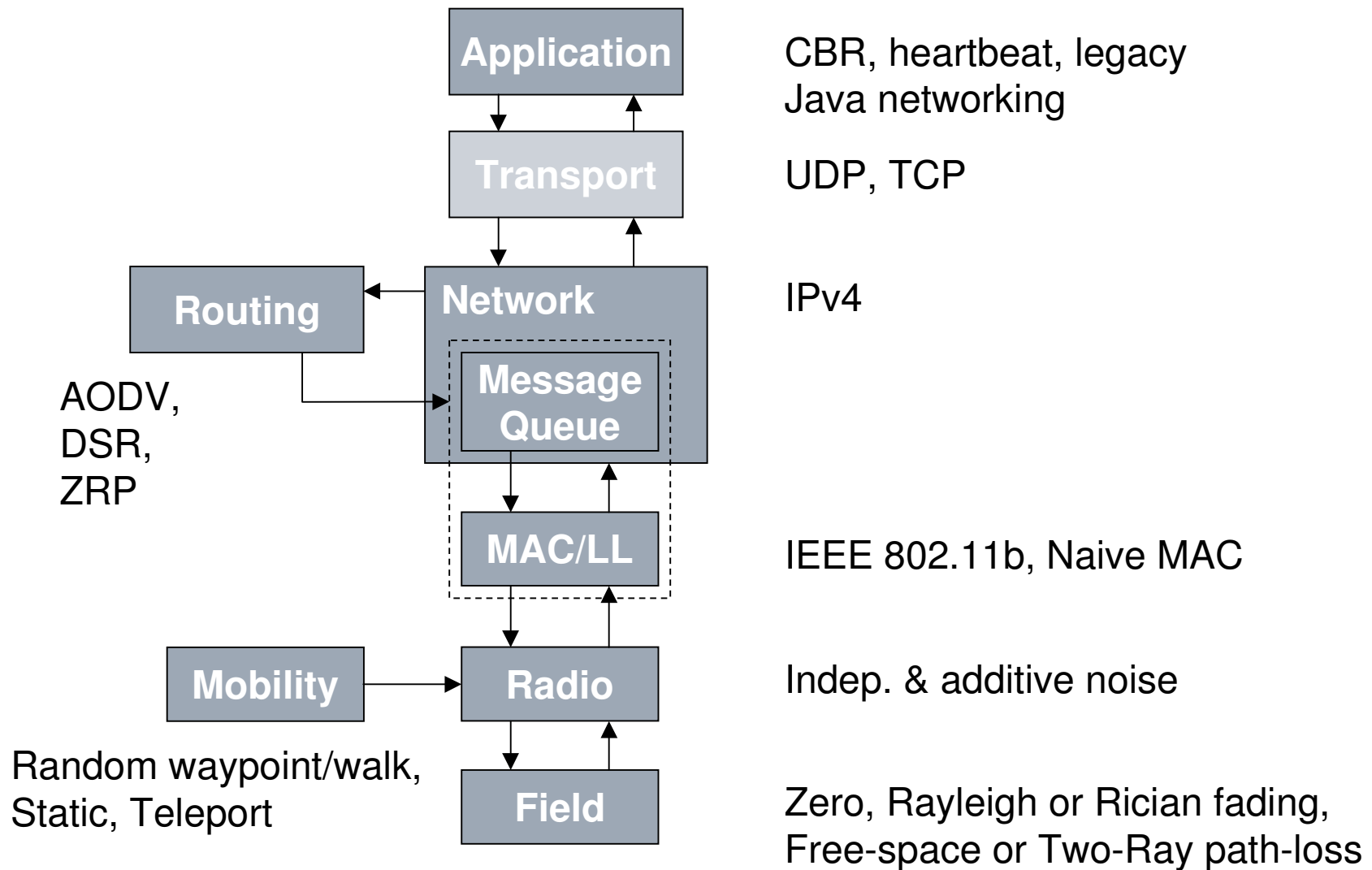
Example: Neighbor Discovery Protocol, 15 minutes

<i>t=15m</i>	ns2		GloMoSim		SWANS		SWANS-hier	
	nodes	time	memory	time	memory	time	memory	time
500	7136.3 s	58761 KB	81.6 s	5759 KB	53.5 s	700 KB	43.1 s	1101 KB
5000			6191.4 s	27570 KB	3249.6 s	4887 KB	433.0 s	5284 KB
50000						47717 KB	4377.0 s	49262 KB

Source: <http://jist.ece.cornell.edu/docs/031112-ece2.pdf>

- Efficient signal propagation by hierarchical binning
- Allows running standard Java network apps over simulated networks

SWANS overview



VANET simulations

- Node mobility model

STRAW

- Vehicle movements

- High velocities
 - Quasi one-dimensional movements on highways
 - Short encounters of oncoming traffic

- Vehicle Behavior

- Radio/Medium Access

- Decentralized medium access, bandwidth allocation
 - Realistic radio propagation in urban environments

- Routing

Currently implemented
by UULM

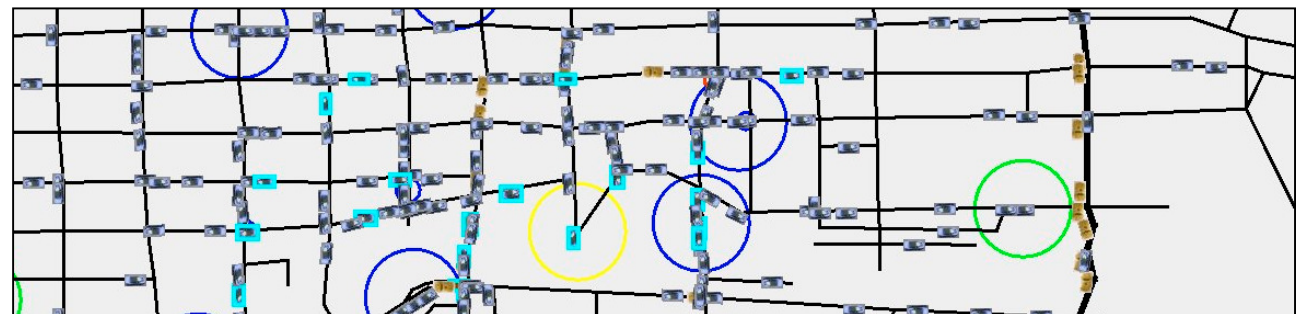
- Position-based routing particularly suitable

- Applications

- Extreme variety of application ideas
 - Other C2C projects?

STRAW Mobility Model

- By Northwestern University, Aqualab
 - <http://www.aqualab.cs.northwestern.edu/projects/STRAW/index.php>
- Written for JiST/SWANS
- Models vehicular node movements on streets
 - Structures: segments, ramps, intersections
 - Movements: acceleration, deceleration, ...
- Uses TIGER[®] street maps
 - By U.S. Census Bureau



DUCKS simulation framework

- Problem:
 - JiST/SWANS lacks tools for handling simulation parameters and output
- Solutions by DUCKS:
 - Easily define complete simulation scenarios by config files (e.g. various simulation setup parameters like field size, node number, ...)
 - Automated execution of simulations
 - Easy distribution of simulation on multiple servers
 - Structured statistics collection, storage and evaluation
- Implementation nearly finished
(still fixing some issues and extending usability)

DUCKS architecture

1 Defines complete simulation scenario

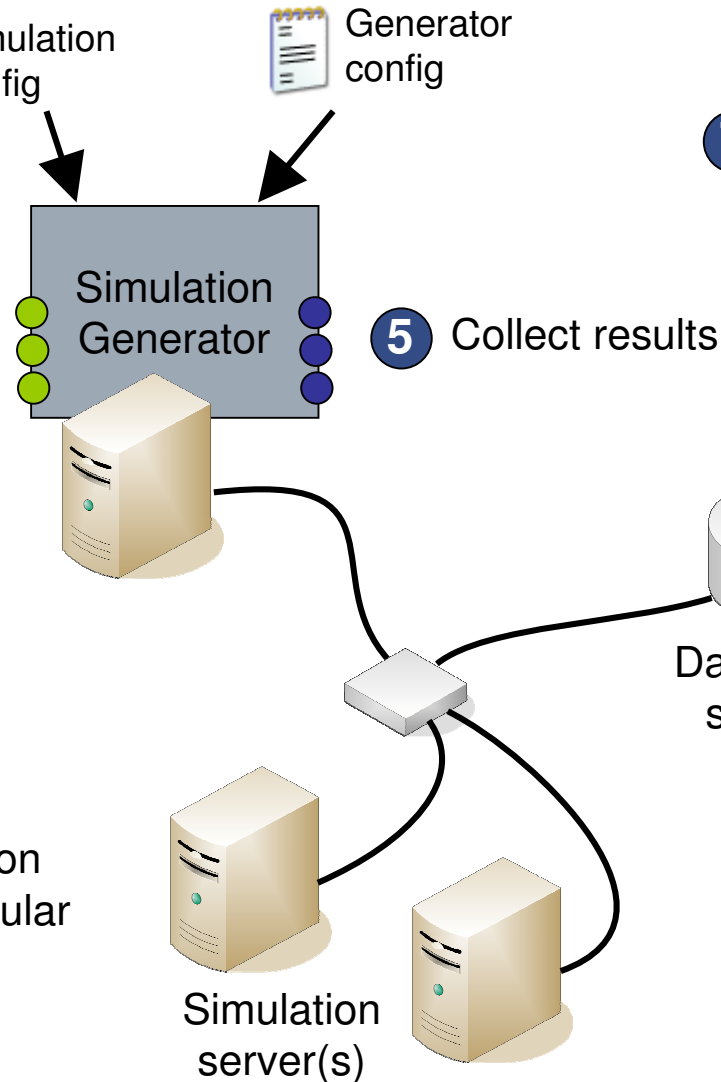
Simulation config

Generator config

2 Demultiplexes scenario to single simulations

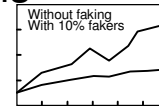
3 Distributes jobs to simulation servers

4 Distributed simulation computation on regular JiST-servers



5 Collect results

7 GUI allows to visually create graphs



6 Store results on relational database

DUCKS config file example

```
ducks.config.runs=20
```

```
ducks.general.fieldsize.x=500,1000
```

```
ducks.general.fieldsize.y=(ducks.general.fieldsize.x <-> 500,1000)
```

```
ducks.general.nodes=50-200/50,500
```

```
ducks.general.duration=120
```

```
ducks.general.waittime.start=10
```

```
ducks.general.waittime.end=(-> ducks.general.waittime.start)
```

```
ducks.mobility.movement=waypoint
```

```
ducks.mobility.waypoint.speed.min=1
```

```
ducks.mobility.waypoint.speed.max=5,20
```

```
ducks.mobility.waypoint.pausetime=(ducks.mobility.waypoint.speed.max == 5 ? 0 : 10)
```

```
ducks.mobility.waypoint.precision=100
```

```
ducks.traffic.type=cbr
```

```
ducks.traffic.cbr.rate=20
```

```
ducks.traffic.cbr.packetspercon=1
```

```
ducks.traffic.cbr.waittime=0
```

```
ducks.routing.protocol=aodv
```

```
ducks.mac.protocol=802.11
```

JiST/SWANS Pros & Cons

Pros

- Fast & scalable
- Completely Java-based approach
 - Advantages of Java (Garbage collection, type-safety, reflection, library, ...)
 - No other language needed
 - Portability of JVM
- Interesting virtual time concept
- Usage of legacy, socket-based Java applications is possible

Cons

- Maturity unproven
 - Still little attention in research community
 - Correctness of implementation
 - Minor bugs/deficiencies
 - Issues regarding platform independence
- Sparse tool support
 - No GUI modeling/output
 - No framework for automated simulation execution
 - leveraged by DUCKS

Further work

- Ongoing activities
 - Implementation of geographic routing
 - Implementation of positioning and position verification
 - DUCKS consolidation
 - Performance tests
- Planned activities
 - More realistic signal propagation models
e.g. including obstacles like buildings
 - Abstraction layer to be able to switch between
simulator and real hardware
- Scientific plans
 - Qualitative comparison of SWANS and ns-2
(e.g. regarding delivery ratio, delay, ...)
 - Use for SEVECOM protocol validation

