

**Multi Modal Intelligent Traffic Signal System**

**Simulation Deployment – User Manual**

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(Initial Release)

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# Purpose of Document

This document is an instruction guide for deploying Multi-Modal Intelligent Traffic Signal System (MMITSS) applications in the simulation platform. The document contains the detailed configuration and usage instructions for deploying the MMITSS software components in the docker container.

# Requirements:

The following devices, software and libraries are required to be installed to deploy MMITSS applications in the simulation environment.

1. VISSIM 10 or VISSIM 2020 installed on a MS Windows (version10) computer
2. A Linux box (preferably Ubuntu 18.04) installed with docker, docker-compose, supervisor and clone mmitss repository.
3. If MMITSS path is not set already, set the MMITSS path in the .bashrc file by executing the following command:

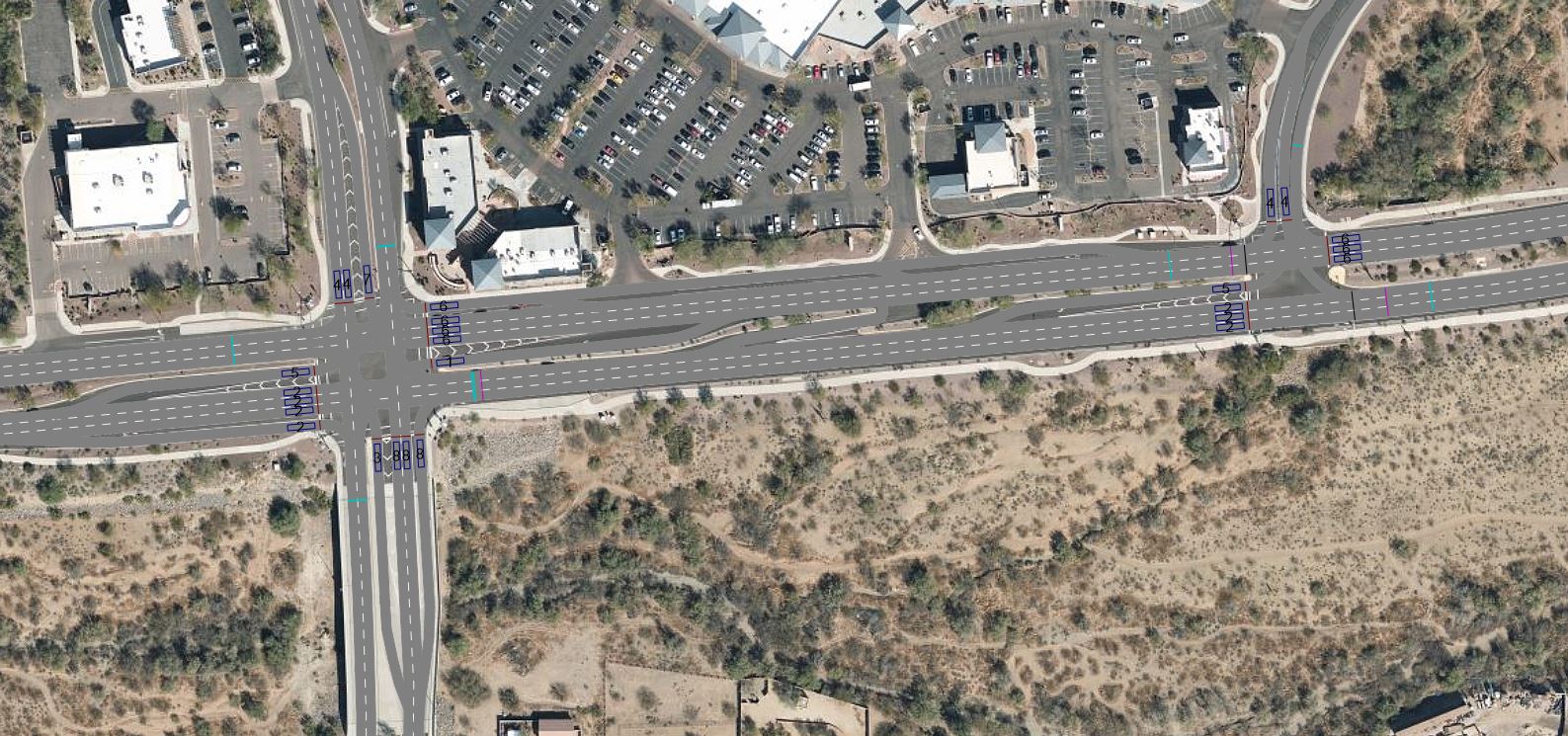
Export /MMITSS\_ROOT=<mmitss directory>

For example if mmitss is cloned on home/user directory then the command will be:

Export /MMITSS\_ROOT=/home/user

# Simulation Model

PTV VISSIM (a microscopic simulation software) is used to simulate all modes of traffic and analyses the performance of MMITSS. VISSIM can be utilized to create realistic and accurate models to test different traffic scenarios, including a variety of connected vehicle penetration rates. A sample VISSIM model of DaisyMountain & GavilanPeak and DaisyMountain &DedicationTrail intersections at Anthem, Arizona is shown in Figure 1.



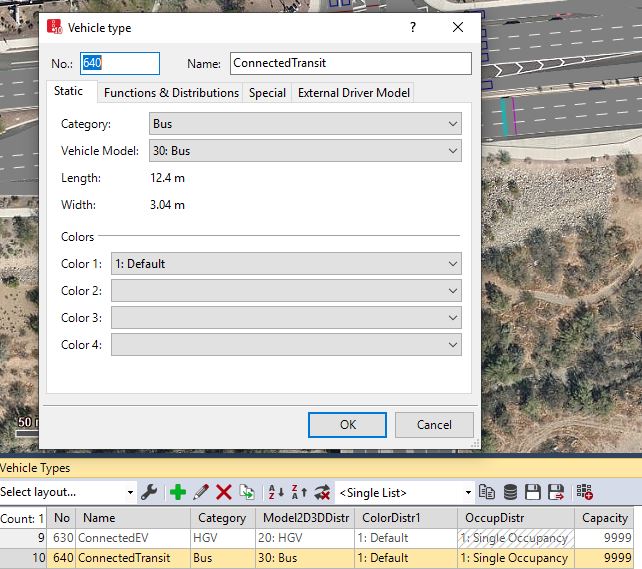
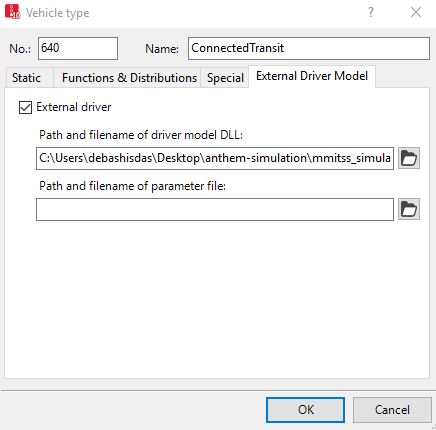
**Figure 1:** VISSIM Simulation model of Two intersections

# 

# 3.1. Configuring Connected Vehicle:

A new vehicle type (Connected vehicle) can be created using an external driver model dll. In Section 4, the method for setting up driver model dll is discussed.

1. To create a connected vehicle say Transit, a new vehicle type must be defined (Figure 2).
2. The directory of the diver model dll file has to be indicated under the External Driver Model as shown in the Figure 2.
3. The new vehicle type is required to be assigned under the “Vehicle Classes”. Go to Data->Vehicle Classes option and add the vehicle type.

**Figure 2:** Defining Connected Vehicle Type

**3.2. Signal Controller:**

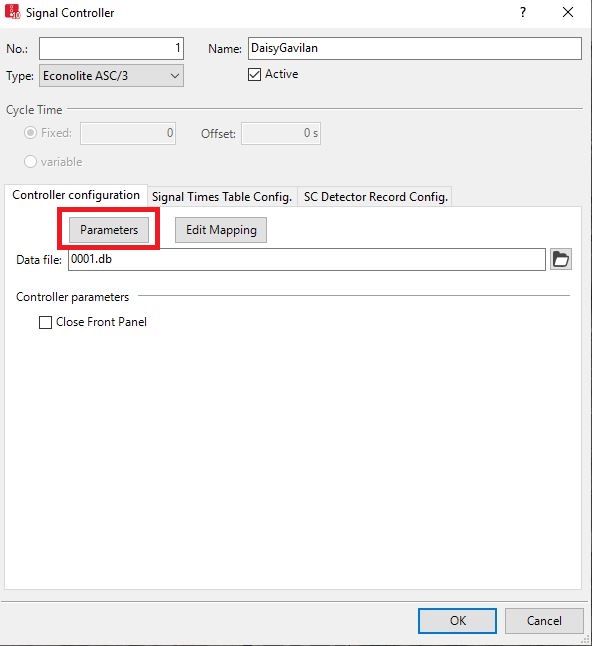
To establish communication between the MMITSS software components and a simulated software-in-the-loop (SIL) signal controller, the signal controller must be properly configured. Different agencies use different type of signal controllers. Two SIL controllers have been used with MMITSS: Econolite ASC/3 and Intelight MaxTime. The Econolite and Intelight SIL software must be obtained by the user from PTV and/or the controller vendors separately from MMITSS.

**3.2.1. Configuring Econolite ASC/3 signal controller:**

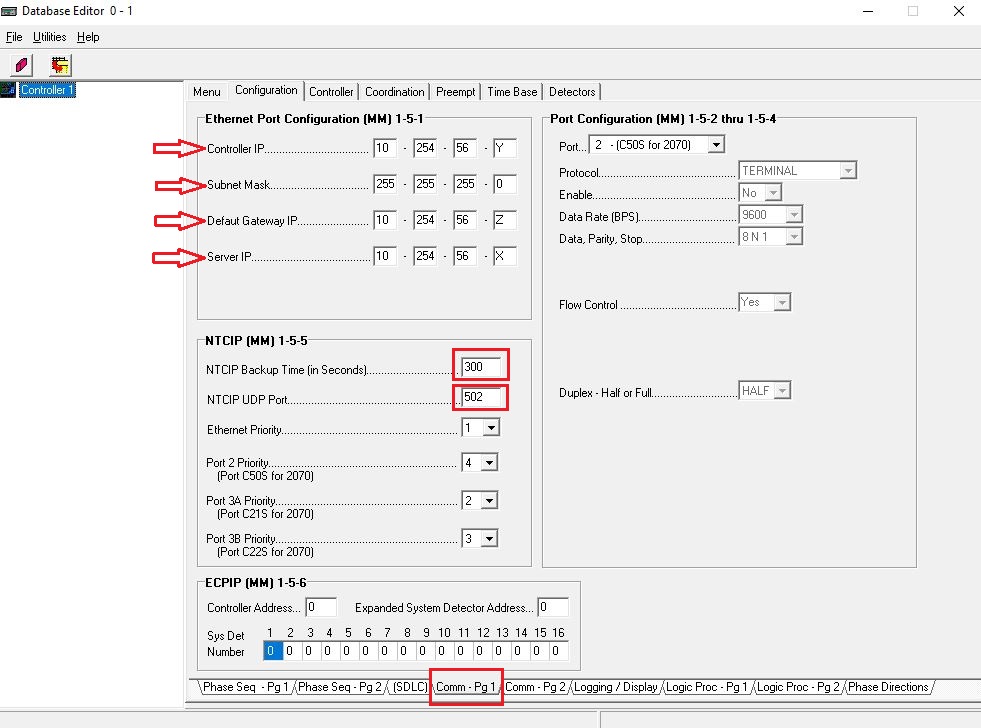
The following steps are required to configure Econolite ASC/3 signal controller:

(a) Determine the IP address of the MS Windows computer where VISSIM is installed. The Linux computer where the MMITSS Roadside Processor (MRP) container will be and the VISSIM computer must be in the same subnet. For example, if the MRP container host IP address is: 10.254.56.xx then the VISSIM computer IP address must be 10.254.56.yy, where xx and yy are determined by the user.

(b) Next define the controller IP, subnet mask, default gateway IP, server IP, NTCIP backup time and NTCIP UDP Port in the VISSIM ASC/3 controller. From the VISSIM open each signal controller and select “Parameters” option (Figure 3). Go to the Comm-Pg1 option (MM 1-4) under configuration and define the parameters (Figure 4).



**Figure 3:** Prepare to setup the parameters

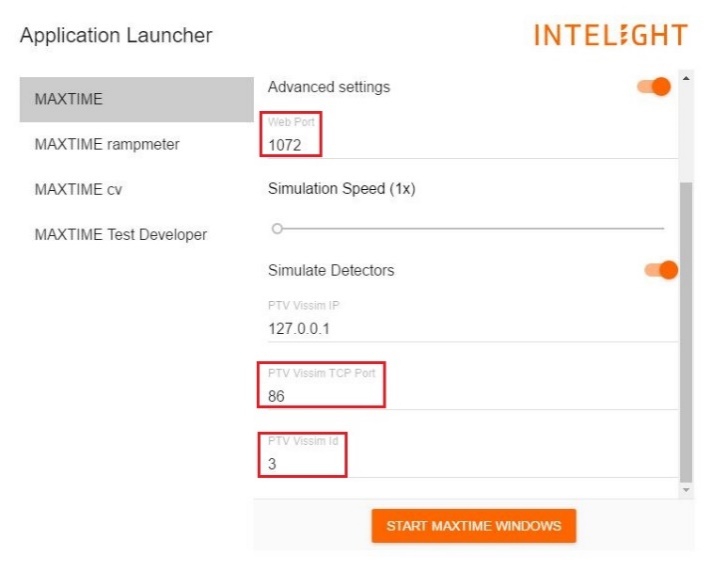
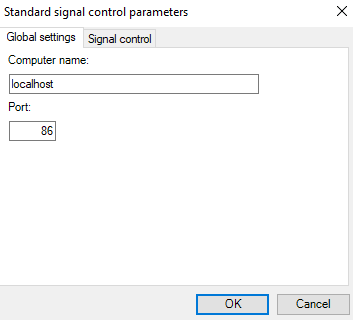


**Figure 4:** Define the parameters

**3.2.2. Configuring MaxTime signal controller:**

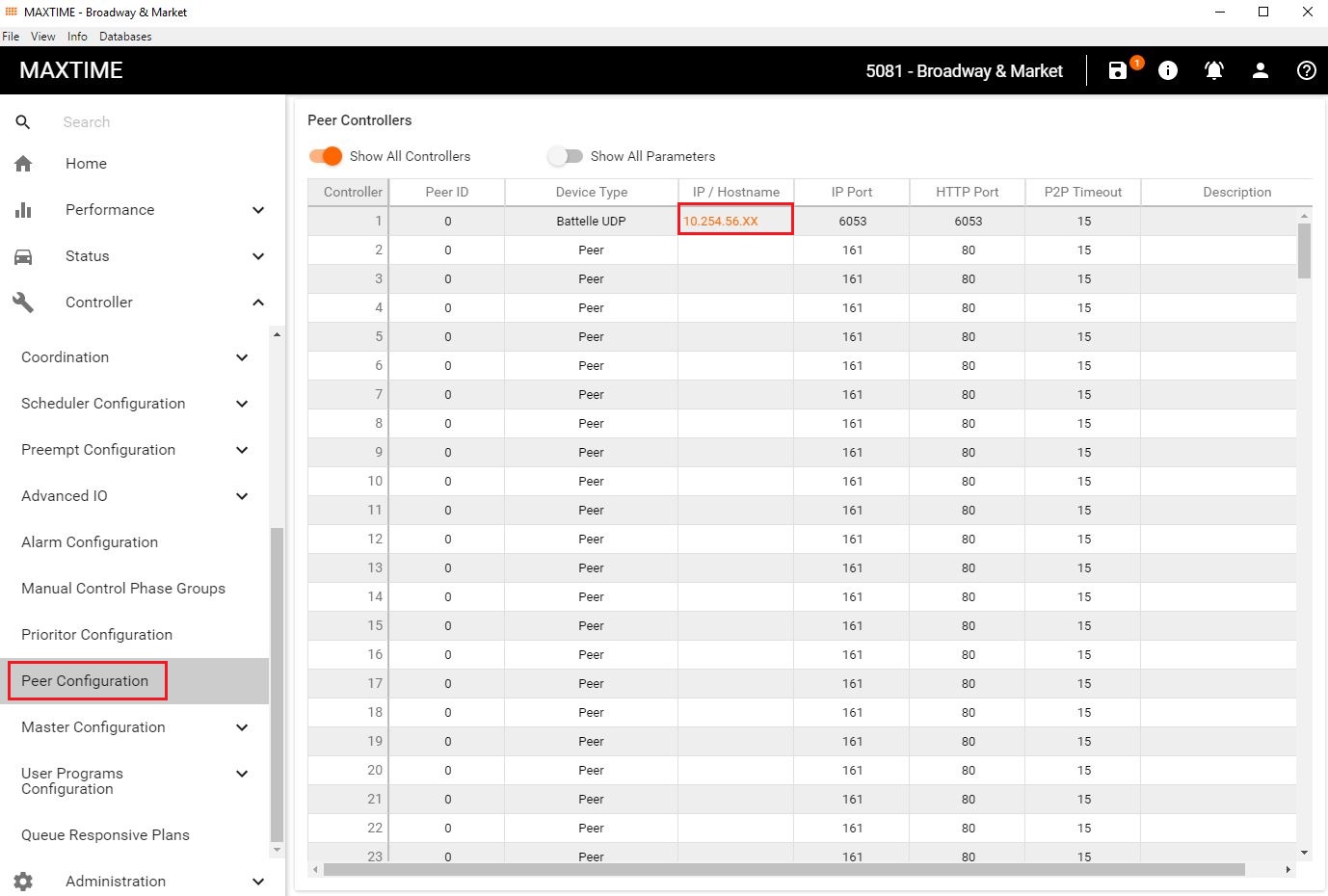
Following steps are required to configure MaxTime Signal controller:

(a) Start MaxTime by defining unique Web Port, PTV VISSIM TCP port, PTV VISSIM ID for each intersection (Figure 5). The PTV VISSIM TCP port must match the port number of the standard signal control parameters.

**Figure 5:** Starting MaxTime signal Controller

(b) The controller IP address has to define from peer configuration (Figure 6).



**Figure 6:** Defining the IP address in MaxTime Signal Controller

# VISSIM Driver Model DLL

A custom driver model has been built using the original sample driver-model provided with VISSIM distribution. Then new driver-model simulates connected vehicles that interact with MMITSS applications. Four variants of this driver-model have been built. They are as follows:

1. M\_DriverModelPassenger.dll (type = “passenger”)
2. M\_DriverModelEmergency.dll (type = “emergency”)
3. M\_DriverModelTransit.dll (type = “transit”)
4. M\_DriverModelTruck.dll (type = “truck”)

At every time instant in the VISSIM simulation, vehicles using any of above driver-models send a UDP packet containing a Basic Safety Message (BSM) like JSON formatted message containing the vehicle’s identification, type, size, current location and motion to a network node defined in the configuration file. An example of JSON string developed by the driver model is as follows:

{

"MsgType": BSM,

"BasicVehicle": {

"heading\_Degree": 359.1,

"position": {

"elevation\_Meter": 587,

"latitude\_DecimalDegree": 33.843455,

"longitude\_DecimalDegree": -112.135159

},

"secMark\_Second": 2600,

"size": {

"length\_cm": 400,

"width\_cm": 300

},

"speed\_MeterPerSecond": 12.5,

"temporaryID": 5822735,

"type": "transit"

},

}

Functionally all four driver models are identical except that the value in the *type* field in the JSON string is different for each driver-model. These driver-models have been tested in VISSIM 10 and VISSIM 2020.

To use the driver-models, a directory named “mmitss\_simulation” needs to be placed in the same directory where the “\*.inpx” file where the simulation exists. This directory is provided in the MMITSS simulation distribution package. The “mmitss\_simulation” directory contains a configuration file named “mmitss\_driver\_model\_config.json” and a subdirectory named “driver\_models” where all four prebuilt driver-models are stored. All four driver-models use the same configuration file and the relative location of the “\*.inpx” configuration file cannot be altered. The configuration file establishes the network node (called “msg\_distributor”) where the UDP packets are to be sent. In addition, the GPS coordinates of the VISSIM model origin (0,0) is set in the configuration file. This information is required to correctly transform the vehicle’s current location from the VISSIM’s local coordinate system to the GPS coordinate system (WGS-84). An example of the content of the “mmitss\_driver\_model\_config.json” is as follows:

{

"msg\_distributor\_ip": "127.0.0.1",

"msg\_distributor\_port": 5000,

"VISSIM\_origin\_position": {

"elevation\_Meter": 540.11,

"latitude" : {

"Degree" : 33.0,

"Minute" : 50.0,

"Second" : 35.4

},

"longitude" : {

"Degree" : -112.0,

"Minute" : -8.0,

"Second" : -6.1

}

}

}

The IP address and UDP port of the receiver network node are specified in the “msg-distributor-ip" and “msg-distributor-port" fields respectively. The *message-distributor* component of MMITSS simulation-tools is used to send vehicle data to the geo-located MMITSS intersections components (e.g. the MRP components).

# Simulation-Tools

To interface the simulation models with other MMITSS core components, two additional components are provided: *message-distributor* and *priority-request-generator-server*. The *message-distributor* component is responsible for receiving and distributing messages from VISSIM simulation model and other MMITSS components to the *priority-request-generator-server* component or to the appropriate intersection containers, where the *priority-request-generator-server* component is responsible for formulating the Signal Request Messages (SRMs) based on the vehicle information received from the *message-distributor* component.

## 5.1. Message-Distributor

As the name suggests, the *message-distributor* component is responsible for receiving messages from the VISSIM simulation model or other MMITSS components and distributing them to applicable configured clients. The *message-distributor* also allows the simulation to be configured for the wireless range (in Meter) of each roadside unit deployed in the corridor along with a probability of dropping message packets. These parameters are set as part of the model calibration process. The clients (IP address and UDP port) for supported messages can be configured in the configuration file of the *message-distributor*. An example of the configuration file (mmitss-message-distributor-config.json) is as follows:

{

"package\_drop\_probability": 0,

"raw\_bsm\_logging": true,

"intersections": [

{

"name": "DaisyMountain\_GavilanPeak",

"ip\_address": "xxx.xxx.xxx.xxx",

"bsm\_client\_port": 5001,

"srm\_client\_port": 20002,

"dsrc\_range\_Meter": 500,

"position": {

"latitude\_DecimalDegree": 33.842932,

"longitude\_DecimalDegree": -112.135186,

"elevation\_Meter": 539

}

},

{

"name": "DaisyMountain\_DedicationTrail",

"ip\_address": "xxx.xxx.xxx.yyy",

"bsm\_client\_port": 5001,

"srm\_client\_port": 20002,

"dsrc\_range\_Meter": 500,

"position": {

"latitude\_DecimalDegree": 33.843239,

"longitude\_DecimalDegree": -112.131541,

"elevation\_Meter": 539

}

},

],

"bsm\_clients":

{

"transit":[

{

"ip\_address": "xxx.xxx.xxx.zzz",

"port":20022

}

],

"truck":[

{

"ip\_address": "xxx.xxx.xxx.zzz",

"port":20022

}

],

"emergency":[

{

"ip\_address": "xxx.xxx.xxx.zzz",

"port":20022

}

],

"passenger":[

]

},

"map\_clients":

[

{

"ip\_address": "xxx.xxx.xxx.zzz",

"port":20022

}

],

"ssm\_clients":

[

{

"ip\_address": "xxx.xxx.xxx.zzz",

"port":20022

}

]

}

The *message-distributor* receives and distributes following messages:

1. *BSM-like information from VISSIM simulation model:*

If the *vehicle type* in the received message is either “emergency”, “transit”, or “truck”, the message is forwarded to the priority-request-generator-server component (or more clients if required). In the configuration file, the IP address xxx.xxx.xxx.zzz corresponds to the docker container (or physical machine) that hosts the *priority-request-generator-server.* In addition, regardless of the *vehicle type*, if the location described in the received message is within the wireless range (meters) of any of the configured intersections, the message is distributed to that intersection’s BSM receiving client (defined by intersection\_ip and bsm\_client\_port).

1. *SRMs from priority-request-generator-server*

The *priority-request-generator-server* sends JSON strings of formulated SRMs to the *message-distributor.* If the location of vehicle (as per the received message) is within the wireless range of any (meters) of any of configured intersections, the message is distributed to that intersection’s SRM receiving client (defined by intersection\_ip and srm\_client\_port). For MMITSS priority applications, the SRM receiving client is the *priority-request-server*.

1. *SSMs from priority-request-server of each intersection*

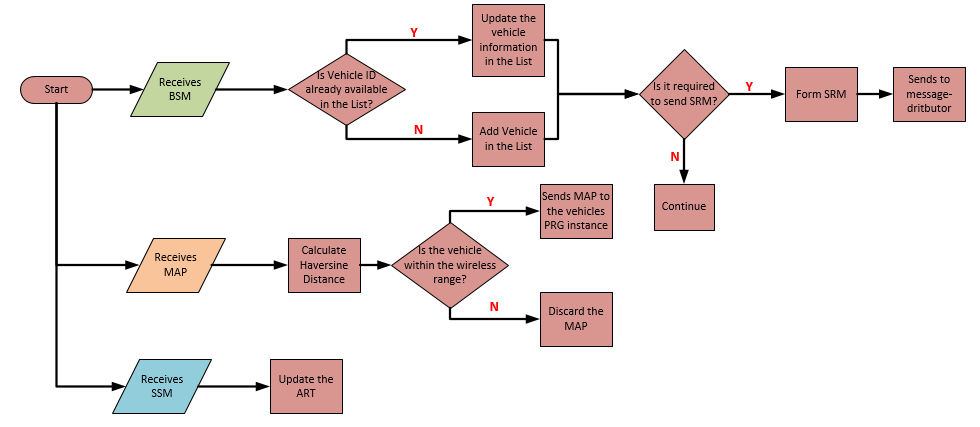
The *priority-request-server* component for each intersection generates and broadcasts a signal status message (SSM) as an acknowledgement of the receipt of SRM if it is eligible for the priority service. The *priority-request-server* for each intersection also forwards SSMs to the *message-distributor,* which then forwards these SSMs to the SSM receiving clients. For MMITSS priority applications, one SSM receiving client is the *priority-request-generator-server* component.

1. *MAPs from map-spat-broadcasters of each intersection*

The *map-spat-broadcaster* component for each intersection broadcasts MAP message at a frequency of 1 Hz. It also forwards the MAP messages to the *message-distributor*, which then forwards these MAPs to configured MAP receiving clients. For MMITSS priority applications, the MAP receiving client is the *priority-request-generator-server* component.

**5.2. Priority-Request-Generator-Server**

The *priority-request-generator-server* is responsible for simulating the priority-request-generator for each priority eligible vehicle. In a field deployment, each vehicle-side processor would have a priority-request-generator, but in simulation each priority-request-generator is an instance in the priority-request-generator-server. The priority-request-generator-server receives BSMs from the *message-distributor*. If the vehicle ID is not available in the list of active vehicles, it creates an instance of *priority-request-generator* for that vehicle ID. If the vehicle ID is already listed, it updates the vehicle information. The *priority-request-generator-server* also receives MAP messages from the *message-distributor.* It calculates the haversine distance between the map reference point and all vehicles based on their current gps coordinates. If the distance is within wireless range, it forwards the MAP messages to the instance of *priority-request-generator*. Each instance of *priority-request-generator* will generate SRM JSON string, based on the MAP and gps coordinates. *The priority-request-generator-server* sends those SRMs JSON strings to the *message-distributor*. It can also receive SSM JSON strings form the *message-distributor* and forwards it to the vehicles *priority-request-generator* instances to maintain the Active Request Table (ART).



**Figure 7:** Flow diagram of Priority-Request-Generator-Server

# Deployment – Docker Containers

To deploy MMITSS in the simulation environment, following steps can be followed:

**Step1:** Create configuration file

Twoconfigurations files are required: mmitss-phase3-master-config.json, and mmitss-data-external-clients.json, for each intersection as well as mmitss-phase3-master-config.json, mmitss-message-distributor-config.json configuration files for the simulation tools (message-distributor, priority-request-generator-server). The configuration files contain the IP addresses, UDP ports, and other configuration data which is required to establish communication between the MMITSS software components. Configuration files for each intersection need to be placed in the <intersectionName>/nojournal/bin directory. The simulation tools configuration files are required to be placed in simulation-tools/nojournal/bin directory. An example of mmitss-phase3-master-config.json is follows:

{

"HostIp": "xxx.xxx.xxx.xxx",

"SourceDsrcDeviceIp": "xxx.xxx.xxx.yyy",

"IntersectionName": "xxx",

"MapPayload":001283fe38083020315abe2149d0eecf1800a0000271c4fcbd028280",

"IntersectionID" : XXXX,

"RegionalID" : 0,

"DataCollectorIP": "xxx.xxx.xxx.xyx",

"HMIControllerIP": "xxx.xxx.xxx.yxx",

"MessageDistributorIP": " xxx.xxx.xxx.zzz ",

"PriorityRequestGeneratorServerIP": "xxx.xxx.xxx.zzz",

"VehicleType" : 6,

"Logging" : "True",

"SRMTimedOutTime" : 10.0,

"PortNumber":

{

"MessageTransceiver":

{

"MessageSender": 10003,

"MessageReceiver": 10002,

"MessageEncoder": 10003,

"MessageDecoder": 10002

},

"MessageDistributor": 5000,

"RsmDecoder": 10006,

"OBUBSMReceiver": 10005,

"HostBsmDecoder": 10005,

"TrajectoryAware": 20001,

"PriorityRequestServer": 20002,

"PrioritySolver": 20003,

"PriorityRequestGenerator": 20004,

"TrafficControllerInterface": 20005,

"TrafficControllerCurrPhaseListener": 20006,

"TrafficControllerTimingPlanSender": 20007,

"PerformanceObserver": 20008,

"HMIController": 20009,

"PrioritySolverToTCIInterface": 20010,

"SignalCoordination": 20011,

"MapSPaTBroadcaster": 6053,

"DsrcImmediateForwarder": 1516,

"PriorityRequestServer\_SendSSM": 50003,

"DataCollector": 30006,

"SnmpEngine": 20020,

"SnmpEngineInterface": 20021,

"PriorityRequestGeneratorServer": 20022

},

"psid":

{

"map": "E0000017",

"spat": "8002",

"rsm": "8003",

"srm": "E0000019",

"ssm": "E0000020",

"bsm": "20"

},

"msgId":

{

"map": "0012",

"spat": "0013",

"rsm": "0021",

"srm\_lower": "001d",

"srm\_upper": "001D",

"ssm\_lower": "001e",

"ssm\_upper": "001E",

"bsm": "0014"

},

"SignalController":

{

"IpAddress": " xxx.xxx.xxx.yyy",

"NtcipPort": 502,

"TimingPlanUpdateInterval\_sec": 60,

"NtcipBackupTime\_sec": 300,

"Vendor": "Econolite",

"TimingPlanMib": "/nojournal/bin/EconoliteMib.py",

"InactiveVehPhases":[],

"InactivePedPhases":[],

"SplitPhases":

{

"1": 6,

"3": 8,

"5": 2,

"7": 4

},

"PermissiveEnabled":

{

"1": true,

"3": true,

"5": true,

"7": true

}

}

}

1. For each intersection, *“HostIp”, “IntersectionName”, “MapPayload”, “IntersectionID”*, *signal controller* *“IpAddress”, “NtcipPort”,* and “*NtcipBackupTime\_sec”, “Vendor”, “TimingPlanMib”* are required to be specified in the mmitss-phase3-master-config.json file. The map payload can be obtained by creating an intersection map using USDOT map tool (<https://webapp.connectedvcs.com/isd/>).
2. For simulation tools, *“MessageDistributorIP”*, *“PriorityRequestGeneratorServerIP”* are required to be specified in the mmitss-phase3-master-config.jsonfile.
3. Create a log folder in the nojournal/bin directory for each intersection and simulation tools. To log the data, specify *“Logging”: “True”* in the mmitss-phase3-master-config.json file.
4. The structure of mmitss-message-distributor-config.json is discussed in the section 5.1.

**Step2:** Define the docker files

Two dockerfiles are required: 1. For MMITSS roadside software component- *“Dockerfiles”* and 2. For simulation tools- *“Dockerfile\_simulation-tools”*. The dockerfiles are required to be placed in the mmitss/bin directory. It is required to specify the docker image name (”mmitssuarizona/mmitss-base-x86:1.3”) in the dockerfile.

An example of the *Dockerfile* is as follows:

#---------------------------------------------------------------------------#

# Dockerfile to build an x86 platform image for an intersection #

#---------------------------------------------------------------------------#

FROM mmitssuarizona/mmitss-base-x86:1.3

COPY TrafficControllerInterface/x86/M\_TrafficControllerInterface /mmitss

COPY SnmpEngine/x86/M\_SnmpEngine /mmitss

COPY PriorityRequestSolver/x86/M\_PriorityRequestSolver /mmitss

COPY PriorityRequestServer/x86/M\_PriorityRequestServer /mmitss

COPY MapSpatBroadcaster/x86/M\_MapSpatBroadcaster /mmitss

COPY supervisord.conf /mmitss

CMD ["/usr/bin/supervisord"]

An example of the *Dockerfile\_simulation-tools* is as follows:

#---------------------------------------------------------------------------#

# Dockerfile to build an x86 platform image for an intersection #

#---------------------------------------------------------------------------#

FROM mmitssuarizona/mmitss-base-x86:1.3

COPY PriorityRequestGeneratorServer/x86/M\_PriorityRequestGeneratorServer /mmitss

COPY MessageDistributor/x86/M\_MessageDistributor /mmitss

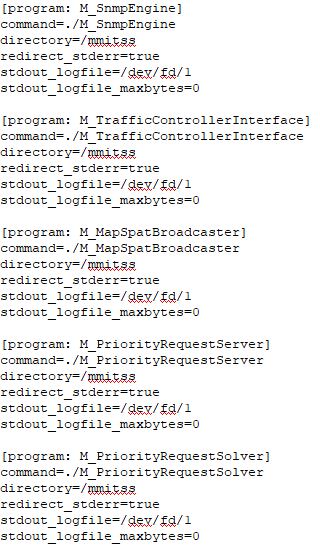
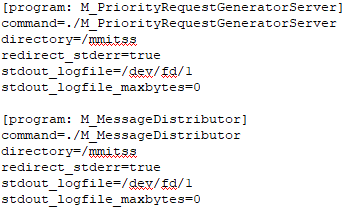
RUN mkdir -p /mmitss/map

COPY supervisord\_simulation-tools.conf /mmitss/supervisord.conf

CMD ["/usr/bin/supervisord"]

**Step 3:** Define supervisrod.conf and supervisor\_simulation-tool.conf file

To monitor the applications in the container, it is required to define two supervisord.conf files. For MMITSS roadside software components the file is named *supervisrod.conf* and for the simulation tools the file is named *supervisrod-simulation-tools.conf*. They must be placed in the same directory structure as the Dockerfile (mmitss/bin).

(a) (b)

**Figure 8:** Snapshot of supervisord.conf files for (a) intersection container (b) simulation-tools container

**Step 4:** Define docker-compose.yml file

To build and run all the software components in the docker container, docker-compose.yml file is required. The yml file must be placed in the same directory structure as Dockerfile (mmitss/bin).

1. For each MMITSS controlled intersection, *“intersection”, “container name”, “source”, and “ipv4\_address”* are required to be specified. Container name can be the same as the intersection name. The *“source”* must be the directory where the configuration files are located and the *“ipv4 address”* has to match the Host IP address which is defined in the mmitss-phase3-master-config.json file for each intersection.
2. For simulations tools, the *“dockerfile”* name has to be defined along with the *“container name”, “source”, “ipv4\_address”*. The *“container\_name”* can be “simulation-tools”, and the *“source”* must be the directory of configuration files and the *“ipv4\_address”* has to match the *message-distributor* IP address which is defined in the mmitss-phase3-master-config.json file.
3. The ethernet interface of the computer and subnet has to be defined under the network. The name of the ethernet interface which will be used to communicate with the containers can be obtained by executing following command in a terminal on the computer:

ifconfig

An example of the docker-compose.yml file for two intersections and simulation tools is as follows:

version: "3.8"

services:

daisy-gavilan:

build:

context: ./

container\_name: daisy-gavilan

volumes:

- type: bind

source: $MMITSS\_ROOT/mmitss/bin/corridors/Anthem/Daisy-Gavilan/nojournal

target: /nojournal

networks:

mmitss\_vlan:

ipv4\_address: xxx.xxx.xxx.xxx

daisy-dedication:

build:

context: ./

container\_name: daisy-dedication

volumes:

- type: bind

source: $MMITSS\_ROOT/mmitss/bin/corridors/Anthem/Daisy-Dedication/nojournal

target: /nojournal

networks:

mmitss\_vlan:

ipv4\_address: xxx.xxx.xxx.yyy

simulation-tools:

build:

context: ./

dockerfile: Dockerfile\_simulation-tools

container\_name: simulation-tools

volumes:

- type: bind

source: $MMITSS\_ROOT/mmitss/bin/corridors/simulation-tools/nojournal

target: /nojournal

networks:

mmitss\_vlan:

ipv4\_address: xxx.xxx.xxx.zzz

networks:

mmitss\_vlan:

driver: macvlan

driver\_opts:

parent: eno2

ipam:

config:

- subnet: xxx.xxx.xxx.0/24

**Step 5:** Build and run the docker container

1. Open a terminal in Linux box and change to the mmitss/scripts directory
2. Run following script to make all the software components:

mmitss\_docker\_make\_all\_for\_x86.sh

1. To build and run the docker containers go to mmitss/bin directory and execute the following command:

docker-compose up --build

Make sure the VISSIM simulation model has started.

1. To monitor the containers execute the following command:

docker-compose exec <container\_name> /bin/bash

This command will direct the console commands to the inside of the container. The following command can be executed to monitor the applications using supervisor.

supervisordctl

1. To stop all the containers, execute the following command:

docker-compose stop

To stop a specific container, execute the following command

docker-compose stop <container\_name>

1. To start all the containers the execute the following command:

docker-compose start

To start a specific container, execute the following command

docker-compose start <container\_name>

1. To take down the whole macvlan network of docker containers, execute the following command

docker-compose down

1. To bring up the whole macvlan network of docker containers, execute the following command

docker-compose up