

# VisibleSim Manual

Julien Bourgeois, Benot Piranda, Thadeu Knychala Tucci, Andr Naz

April 23, 2015

# Contents

<b>1</b>	<b>Introduction</b>	<b>3</b>
<b>2</b>	<b>Installation</b>	<b>3</b>
<b>3</b>	<b>User applications in VisibleSim</b>	<b>3</b>
3.1	Examples of applications . . . . .	3
3.2	Implementing a new application . . . . .	3
3.3	Running an application . . . . .	3
3.3.1	C++ application . . . . .	3
3.3.2	Meld application . . . . .	3
3.3.3	Command line arguments . . . . .	3
<b>4</b>	<b>Embedded debugger</b>	<b>3</b>
<b>5</b>	<b>Local clock Simulation</b>	<b>3</b>
5.1	Programming API . . . . .	3
5.2	Clock model . . . . .	3
5.2.1	BlinkyBlocks . . . . .	3
5.2.2	Systematic model for clocks . . . . .	3
5.2.3	Experimental values . . . . .	4
5.3	Clock simulation in DES . . . . .	4

## 1 Introduction

VisibleSim is a general discrete event simulator (DES) for modular robot systems.

## 2 Installation

## 3 User applications in VisibleSim

### 3.1 Examples of applications

### 3.2 Implementing a new application

### 3.3 Running an application

#### 3.3.1 C++ application

#### 3.3.2 Meld application

#### 3.3.3 Command line arguments

## 4 Embedded debugger

## 5 Local clock Simulation

VisibleSim supports local clock simulation. We present here the programming API and the clock model. The model

### 5.1 Programming API

### 5.2 Clock model

#### 5.2.1 BlinkyBlocks

#### 5.2.2 Systematic model for clocks

[1] proposes a general model for oscillators:

$$x(t) = x_0 + y_0 t + \frac{1}{2} D t^2 + \epsilon(t) \quad (1)$$

where  $t$  is the simulation time (real-time),  $x(t)$  is the local time,  $x_0$  is the time offset,  $y_0$  is the frequency offset,  $D$  is the frequency drift and  $\epsilon(t)$  is the random noise.  $\epsilon(t)$  is not deterministic. [2] assume that  $\epsilon(t)$  follows a Gaussian distribution  $\mathcal{N}(0, \sigma^2)$ .

### 5.2.3 Experimental values

Compensate communication delays. At most 2-hops.

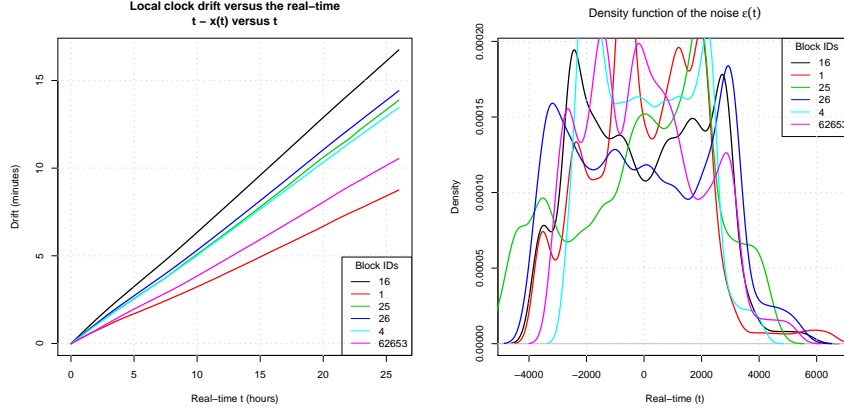


Figure 1: Local clock drift ( $t - x(t)$ ) and noise ( $\epsilon(t)$ ) distribution.

Parameter	Min	Mean	Max	Standard-deviation
$D$	1.613992e-11	-1.179717e-11	-7.991859e-12	3.060884e-12
$y_0$	0.9896537	0.9922277	0.9949096	0.001851285
$x_0$	-5984.141	-3532.051	-785.9812	1921.629
Residual standard error	1688.103	2080.197	2423.646	294.832

Figure 2: Parameters

### 5.3 Clock simulation in DES

[3] explains how to enhance DES with efficient local clock simulation.

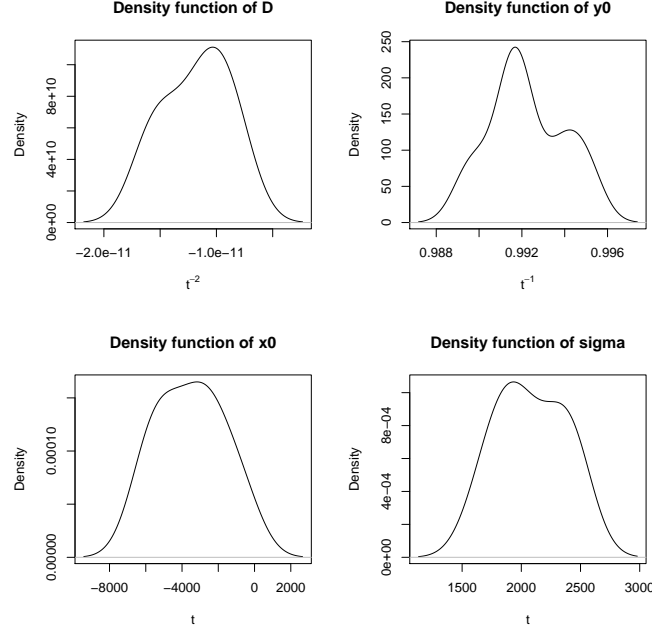


Figure 3: Parameter distributions.

## References

- [1] David W Allan. Time and frequency(time-domain) characterization, estimation, and prediction of precision clocks and oscillators. *IEEE transactions on ultrasonics, ferroelectrics, and frequency control*, 34(6):647–654, 1987.
- [2] Liangping Ma, Hua Zhu, Gayathri Nallamothu, Bo Ryu, and Heidi Howard. Understanding linear regression for wireless sensor network time synchronization. In *Proceedings of the 2007 International Conference on Wireless Networks, June 25-28, 2007, Las Vegas, Nevada, USA*, pages 325–328, 2007.
- [3] Felix Ring, Anetta Nagy, Georg Gaderer, and Patrick Loschmidt. Clock synchronization simulation for wireless sensor networks. In *Sensors, 2010 IEEE*, pages 2022–2026. IEEE, 2010.