

IOCOM library

Automation and IoT - connecting IO boards to control computer over TCP/IP or serial port.

21.9.2019/Pekka Lehtikoski

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1. Introduction

190527, updated 1.9.2019/pekka

The IOCOM library implements communication between a control computer and IO devices over TCP network or full duplex serial communication wire. The library supports scalable range of functionality. Minimum configuration supports only serial communication on plain metal, while some applications may require multi-threading and secured communication over Internet.

Micro-controllers can be used as plain metal, or equipped with Arduino derived libraries, FreeRTOS (currently testing), possibly RT-Thread (under consideration), LWIP for networking, and TLS library. The IOCOM is not bound tightly to any underlying system, so it can be ported basically to any environment with sufficient resources for the task. Still, using configuration which has been implemented and tested makes things much easier.

The same code runs on Windows and Linux. Linux on should cover Raspberry PI and similar devices. We are considering MAC and Android testing as well.

Communication security is becoming paramount in IoT and Manufacturing environments. Thus TLS integration, strong encryption and device identification are essential part of the project.

1.1 Design goals and miscellaneous ideas

180812, updated 1.9.2019/pekka

The IOCOM library connects IO devices to control computer in a heterogeneous network environment. The same library code run on computers and micro controllers.

- Connect distributed IO devices to controller
- Make it simple, reliable and fast.
- Open source, free to use also as part of commercial code.
- No compromises. Only one simple way to the specific job.
- Reference implementation and documented protocol to connect the devices.
- Code can be ported to any system with standard C compiler and sufficient resources.
- Data is seen as memory blocks. Memory blocks are plain byte arrays.
- Memory blocks are transferred to one direction only.
- Application never locks up. If communication doesn't keep up with changes by application, frames are dropped.
- Preserve order of changes and data transfer synchronization, so that application will know that whole memory block is up to date.
- Low small transaction latency. Typical goal is around 1 milliseconds, depending on hardware.
- High through output in bigger transactions.
- Large address space size. Typically 32k bytes for 8/16 bit micro-controllers and 2GB for 32/64 bit systems. Practical maximum memory block size is set by available system memory.
- Point to point connection over TCP socket or full duplex serial communication.
- Low overhead. Small message headers, transfer only changes, compress transferred data.
- Secure TLS connections and device identification when needed.
- RTOS multi-threading support, when needed.

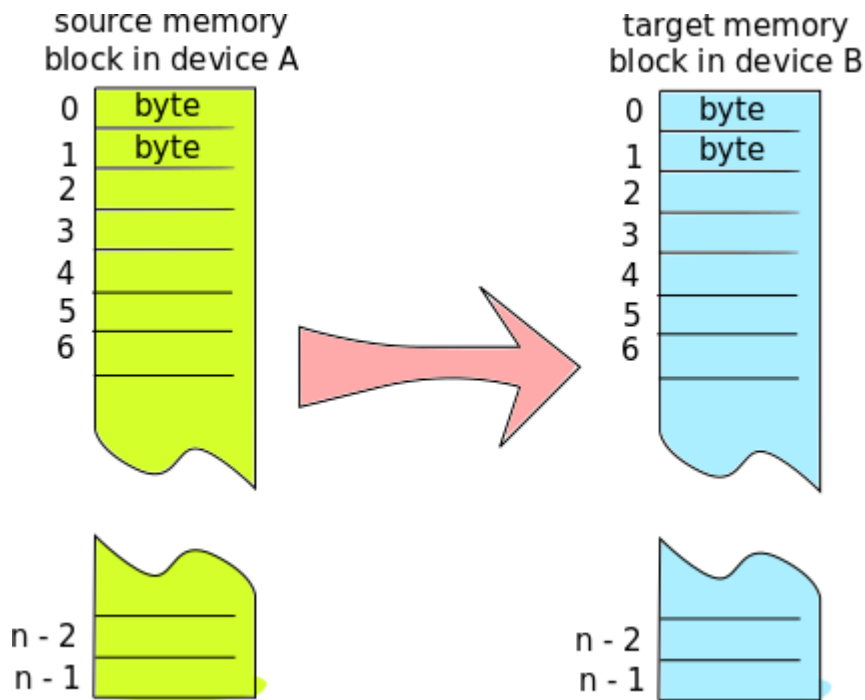
1.2 Memory blocks

180727, updated 22.6.2019/pekka

Communication is based on memory blocks. Device A stores data to be transferred into memory block.

Communication maintains identical copy of the memory block in device B. Separate memory blocks are necessary to implement two directional communication.

A memory block is byte array which is copied from a device to another. Under the hood this is quite a bit more complex, since only changes are transferred over communication, there is compression and synchronization, but user of this library should not need to care about this. There can be multiple recipients of one memory block. There are iocom API functions for allocating, reading and writing memory blocks, and for data transfer synchronization.



A memory block in device A is copied to identical memory block in device B. If the memory blocks have different size, the extra data is ignored.

Communication between two devices typically involves several memory blocks, for example IO board blocks could be "binary inputs", "analog inputs" and "binary outputs". When deciding how to divide data into memory blocks, consider also synchronization and how often input data changes. If some data changes quickly and some is static, these should be in different groups. Data which need to be synchronized (transferred in specific order), like "my data array" and "data array ready" bit, need to be in the same memory block.

A memory block is presented by `iocMemoryBlock` structure. The structure stores pointers to buffers, flags and state information. A memory block structure is initialized or allocated by:

```
iocMemoryBlock *ioc_initialize_memory_block(  
    iocMemoryBlock *mblk,  
    iocRoot *root,  
    iocMemoryBlockParams *prm);
```

The root object is root of iocom instance's object hierarchy. It kind of binds memory blocks, connections and source/target buffers together. The root object must be initialized before it can be used, and releasing root object will free all resources allocated within the root.

If `mblk` argument is `OS_NULL`, the function allocates memory for the memory block structure. Otherwise it initializes a memory block in application allocated memory.

Once a memory block is no longer needed, it should be released by calling `ioc_release_memory_block` function. If the memory block was allocated by the `ioc_initialize_memory_block` function, the allocated memory is released by this function.

```
void ioc_release_memory_block(  
    iocMemoryBlock *mblk);
```

1.3 Access memory block content

190622, updated 23.6.2019/pekka

Memory block content is the actual data to be transferred. It is accessed using functions, which change the content and cause changes to be propagated.

1.3.1 Writing data to be transferred

The `ioc_write` is the generic function to set data to be transferred.

```
void ioc_write(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_uchar *buf,  
    int n);
```

There are simple functions to set one typed value. These set 8 bit integer value (1 bytes), 16 bit integer value (2 bytes), 32 bit integer value (4 bytes), 64 bit integer value (8 bytes) and 32 bit floating point value (4 bytes). These functions take care that values are stored least significant byte first order within memory block, regardless of processor architecture. These functions convert longer (or same length) integer type, so we do not need to care whether value is signed or unsigned.

```
void ioc_set8(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_int value);  
  
void ioc_set16(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_int value);  
  
void ioc_set32(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_int value);  
  
void ioc_set64(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_int64 value);  
  
void ioc_setfloat(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_float value);
```

1.3.2 Writing string

String is written by `ioc_write()` function:

```
void ioc_setstring(
    iocMemoryBlock *mblk,
    int addr,
    const os_char *str,
    int n);
```

For example:

```
ioc_clear(mblk, addr, "teststrings", 10);
```

The example above writes always 10 bytes to wipe out any previous value. Resulting string in memory block has maximum nine characters followed by at least one '\0' character. Strings should be UTF-8 encoded and always terminated with '\0' character.

1.3.3 Writing arrays

Writing arrays element at a time is somewhat waste of processor time and if IOC_AUTO_SEND flag is set, generates extra data transfers. Use functions to write typed arrays into memory block:

```
void ioc_setarray16(
    iocMemoryBlock *mblk,
    int addr,
    os_short *arr,
    int n);
```

```
void ioc_setarray32(
    iocMemoryBlock *mblk,
    int addr,
    os_int *array,
    int n);
```

```
void ioc_setfloatarray(
    iocMemoryBlock *mblk,
    int addr,
    os_float *array,
    int n);
```

Here n is number of array elements, not number of bytes. You may notice that array functions for bytes and for 64 bit integers are missing. For simple byte data this is because the function would be the same as ioc_write(). Reason for missing 64 bit array function is that I cannot imagine where it would be needed (can be added if someone really needs it).

1.3.4 Clearing range in memory block

The ioc_clear() function sets range of bytes starting from address given as argument to zero. This is preferred way to clear memory block data.

```
void ioc_clear(
    iocMemoryBlock *mblk,
    int addr,
    int n);
```

1.3.5 Propagating writes to transfers

Propagating changes is done by ioc_send() function. This function is called automatically if IOC_AUTO_SEND flag was given when the memory block was initialized. Similarly received data is propagated by ioc_receive() function, and flag to call it automatically is IOC_AUTO_RECEIVE.

1.3.6 Reading received data

Similarly to writing to outgoing memory block, we can read incoming memory block. Data can also be read from outgoing memory block, but never write to incoming memory block. Generic read function is as:

```
void ioc_read(  
    iocMemoryBlock *mblk,  
    int addr,  
    os_uchar *buf,  
    int n);
```

The read functions for simple values are:

```
os_int ioc_get8(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_int ioc_get8u(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_int ioc_get16(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_int ioc_get16u(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_int ioc_get32(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_int64 ioc_get64(  
    iocMemoryBlock *mblk,  
    int addr);  
  
os_float ioc_getfloat(  
    iocMemoryBlock *mblk,  
    int addr);  
  
void ioc_getstring(  
    iocMemoryBlock *mblk,  
    int addr,  
    const os_char *str,  
    int n);
```

When reading, we may convert to longer integer type, thus sign conversion matters. Thus there are unsigned version of `ioc_get8u`, `ioc_get16u` and `ioc_get32u`. 64 bit integers are assumed to be always signed.

1.3.7 Reading arrays

Same as for writing, data can be read as arrays. Here `n` is number of elements, not number of bytes.

```
void ioc_getarray16(  
    iocMemoryBlock *mblk,  
    int addr,  
    const os_short *arr,  
    int n);  
  
void ioc_getarray32(  
    iocMemoryBlock *mblk,  
    int addr,
```

```

    const os_int *array,
    int n);

void ioc_getfloatarray(
    iocMemoryBlock *mblock,
    int addr,
    const os_float *array,
    int n);

```

1.3.8 Detecting received data using callback function

Using callback function to react to received data is usually much more efficient than polling for changes. Application implemented callback function could be something like:

```

static void iocontroller_callback(
    struct iocMemoryBlock *mblock,
    int start_addr,
    int end_addr,
    os_ushort flags,
    void *context)
{
    /* Echo 2 bytes at address 2 back to IO board address 11. This happens
       practically immediately.
    */
    if (end_addr >= 2 && start_addr < 2 + 2)
    {
        os_int command_echo = ioc_get16(mblock, 2);
        ioc_set16(c->outputs, 11, command_echo);
    }
}

```

Use `ioc_add_callback` to set the callback function:

```
ioc_add_callback(mblock, iocontroller_callback, OS_NULL);
```

There are few things to be aware of when using callbacks:

- Callback must return almost immediately, it cannot have long processing and even debug prints slow down communication significantly. If callback needs to initiate longer process, trigger an event or set a flag from the callback function.
- In multithread operation, the callback function can be called by other thread than which runs the sequence. Typically thread running the communication.

1.3.9 About thread safety

If multithreading support is enabled for eosal and iocom when compiling, memory block access is thread safe. These functions can be called from multiple threads.

1.4 Devices, memory blocks and connections

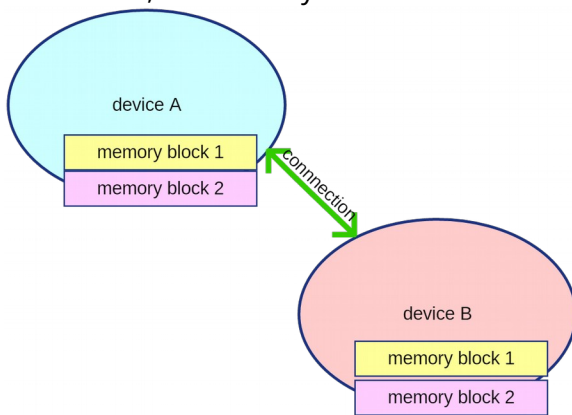
190502, updated 21.6.2019/pekka

A device holds multiple memory blocks, at minimum one for receiving data and another for sending data. There can be also memory blocks for IO device structure information (metadata), for programming flash, etc. Basic communication doesn't really care what memory block is for.

1.4.1 Connecting two devices together

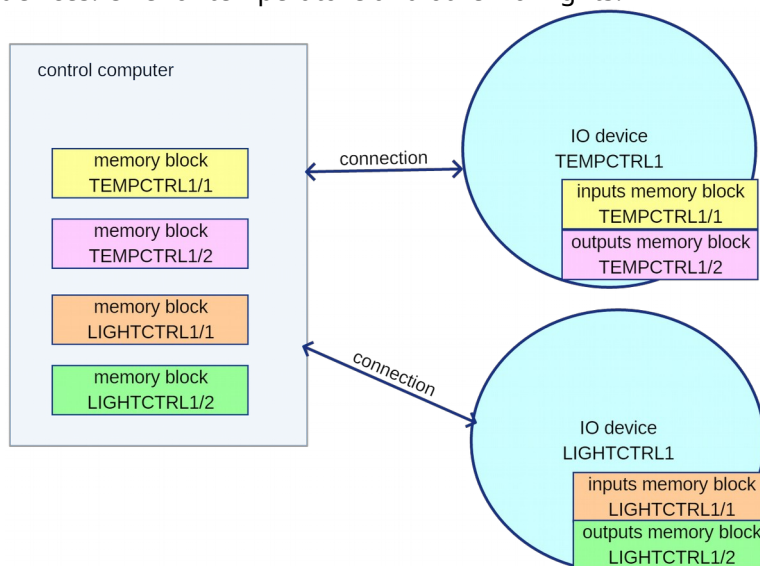
A simple example is connecting device A and device B. Both devices "know" that they have memory blocks 1 and 2, and these memory blocks are constructed by `ioc_initialize_memory_block()` calls at both ends. Once connection is

established, the memory blocks which have same number will be transferring data.



1.4.2 Connecting multiple IO devices to control computer

Usually we need to add some more complexity. For example we have one control computer, which controls two IO devices: One for temperature and other for lights.



Here the memory blocks are also created before establishing the connections between the control PC and the IO devices. Difference is that here in addition to memory block number we give memory blocks also device name and device number. To transfer data between two memory block all three must match.

1.4.3 Device name and number

Device name and device number make an device identifier which is unique within a control system. Device name describes IO board functionality, so two devices with name "LIGHTCTRL" are assumed identical. The device name must be a short string (max 12 characters) with only upper case characters 'A' - 'Z'. Since one control system may have multiple same kind of IO devices, these are separated by device number. Usually 1 if first device... The device name is typically hard coded in device software and device number (if needed) either set by jumpers or stored in EEPROM.

1.4.4 Who connects and who listens for connections?

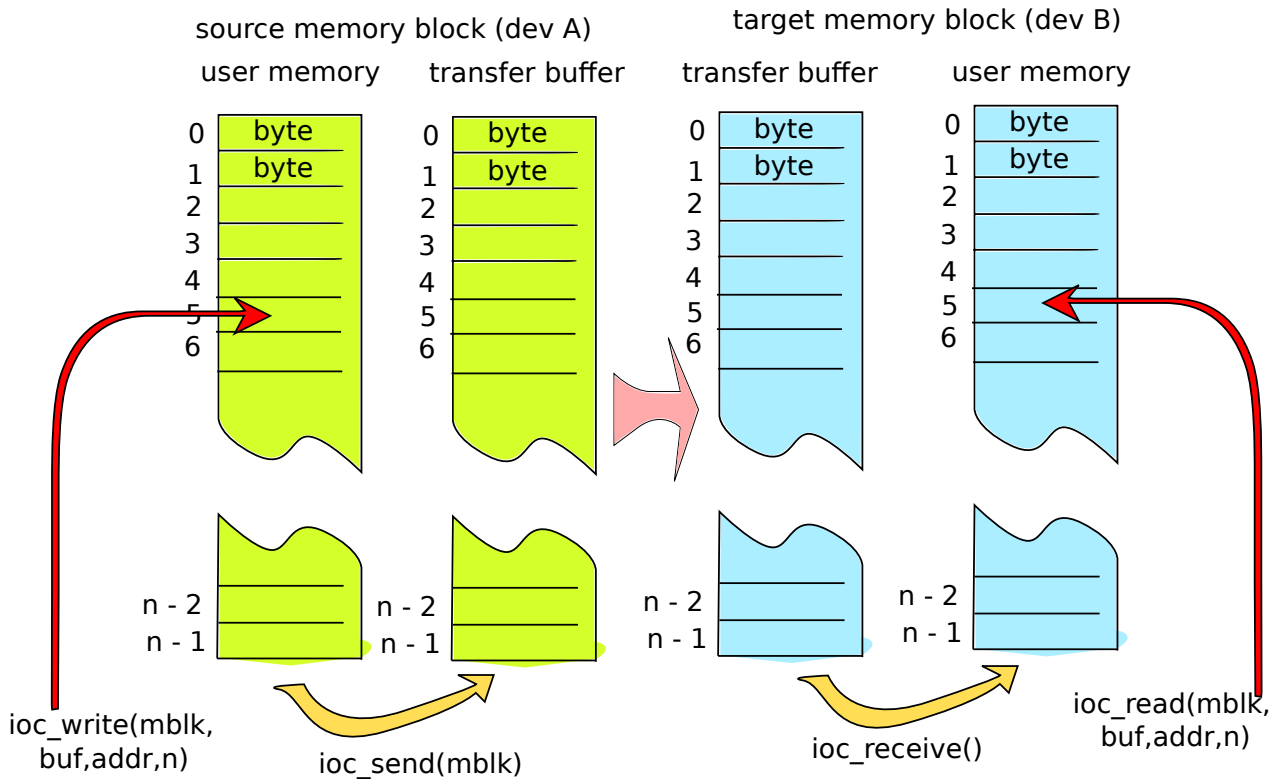
It doesn't really matter which end listens for socket connection, or if connection is through serial port. It works just the same. One good choice in own subnet is to assume that IO board "knows" IP address of the control computer and connects to it with TCP socket. The "known" address could be calculated from device's IP address and subnet mask, for 255.255.255.0 network this could be said "first three numbers are same as in my own IP address, and the fourth number is always 253". If in addition DHCP is used to get IO device's network configuration, this would

work like plug and play without using UDP broadcasts/multicasts. This approach works also well with planned future TLS connection.

1.5 Data synchronization

190502, updated 20.6.2019/pekka

The synchronization logic preserves time order of changes. Consequent changes are received in same order as they were set or in same snapshot. Never in reverse order.



Transfer buffer drawn above here is simplified, implementation detail like real record keeping, buffering and transfer format are not discussed here.

Memory block content is accessed from application code using `ioc_write()` and `ioc_read()` functions, or simple `ioc_set*()` and `ioc_get*()` functions. Target buffer is read only and source buffer is read/write. On source side, the `ioc_send()` function copies source memory block to be transferred (or at least modified part of it). If there no space in transfer buffer, an ongoing transfer, the function does nothing. If there are no modifications, the function may do nothing. We can say that `ioc_send()` records (or may record) a snapshot of user memory for transfer. On target end, the `ioc_receive` function copies data from transfer buffer to user memory. The copied data is last complete transferred snapshot.

Note about `IOC_AUTO_SEND` mode: If this flag is given to source memory buffer, `ioc_send()` is called every time `ioc_write()` is called. Similarly `IOC_AUTO_RECEIVE` causes `ioc_receive()` to be called every time `ioc_read()` is called. This is not really unefficient, and can be recommended at least to get started.

1.6 MODBUS comparison

190901, updated 1.9.2019/pekka

The library is an alternative to MODBUS protocol for point to point communication. Since the MODBUS is well known, it is easy to get the general idea by listing the main differences between the protocols:

- The IOCOM is event based, while MODBUS uses polling. This means that data is transferred when it changes, not when it is queried.
- Data transfers are synchronized in way that it guarantees that other end of communication receives changes in same order the changes are made.
- IOCOM uses compression, flow control, etc and aims for performance. This makes it more complex than MODBUS. While most MODBUS users write their own protocol implementation, I do not expect this to work well with IOCOM. I recommend using reference implementation, at least as starting point, unless there is need to port the protocol to Python, Java, etc.

- IOCOM requires full duplex serial communication (at least logically), half duplex will not do. It cannot do “one master – multiple slaves” serial communication, every device needs it's own serial wire. If those features are important, then use MODBUS. It was designed specifically for that scenario and does it well.
- When needed, IOCOM handles secure TLS connections natively. MODBUS is channeled through SSH to provide secure connection. SSH is typically too heavy for micro controllers, while many more powerful ones can use TLS.

2. Using the library

190502, updated 16.7.2019/pekka

I think the best way to get started using the library is to try it out: Glance through introduction chapter in this document. Check it out from GIT repository. Compile it under Linux or Windows and run/look through the code examples.

2.1 IOCOM in GitHub

180728, updated 18.5.2019/pekka

The library code is stored in:

<https://github.com/pekkalehtikoski/iocom.git>

The IOCOM library relies on the operating system abstraction layer:

<https://github.com/pekkalehtikoski/eosal.git>

Email:

pekka.lehtikoski@gmail.com

2.2 Micro-controller and Arduino build notes

190608, updated 27.6.2019/pekka

Even this is called Arduino build, the code will not run on UNO, etc. It is simply too heavy and intended for 32 bit micro controllers. I recommend using 32 bit ARM architecture micro-controllers, and my personal favorites of those which I am testing with are STM32F429 Nucleo and Teensy 3.6.

- Teensy 3.6 has really good performance and format that it can be plugged directly into my own PCB. But has two big minuses: lack of debugging support and incomplete LWIP library port.
- STM32F429 Nucleo on the other hand shines where Teensy lacks, but it comes short as development board which doesn't physically integrate with own electronics nicely. In addition Nucleo cannot be legally reused "as is" as part of commercial project: You have to draw your own PCB and put the STM chip on it. This is something I cannot do at home, but need to order from China.

2.2.1 Building Arduino libraries

An Arduino library is compressed package of source code, not collection of compiled object files. To build eosal (operating system abstraction layer) library.

```
cd /coderoot/eosal/build/arduino-library
mkdir tmp
cd tmp
cmake ..
make
```

Library (or in Arduino's case .zip file) eosal-master.zip will be created in /coderoot/lib/arduino directory. Remove tmp directory. Then same for iocom library.

```
cd /coderoot/iocom/build/arduino-library
mkdir tmp
cd tmp
cmake ..
```

make

The iocom-master.zip should appear in the same /coderooot/lib/arduino directory.

NOTE: WRITE ABOUT PACKAGES NEEDED. ARDUINO IDE, STMDUINO, TEENSYDUINO VERSIONS. USING TEENSYDUINO SOCKET LIBRARY FOR STM32/WIZ5500. MODIFICATION TO SOCKET LIBRARY. SETTING SERIAL COMMUNICATION TX AND RX TO 256 BYTES.

2.2.2 Bringing the libraries into Arduino IDE

- Delete old version of arduino libraries in use. For example I need to delete eosal-master and iocom-master directories within /home/pekka/Arduino/libraries directory.
- Open an Arduino sketch in Arduino IDE, for example 4_arduinoioioboard.ino in /coderooot/iocom/examples/4_arduinoioioboard directory.
- Select [Sketch][Include Library][Add .ZIP Library] from Arduino IDE menu and browse to /coderooot/lib/arduino director, select eosal-master.zip and click Ok to bring it in.
- Do the same for the iocom-master.zip.

2.3 Atollic True Studio notes

190714, updated 15.7.2019/pekka

Atollic True Studio is professional eclipse based development environment primarily for STM32 micro-controllers. The IDE is similar to Keil or even QT or Visual Studio, and debugging works very nicely. In addition to IDE, there is Cube. Cube makes assigning micro-controller pins and timing easy (much much easier than reading thick reference manuals and doing it by hand). It generates code to initialize the micro-controller, which can then be used in True Studio project.

Advice: If you are new to programming micro-controllers, starting out cold with building the iocom library with True Studio will be hard. Better to start either with True Studio examples, or even better with STM32duino examples. Way from hello world "blink led", proceeding step at a time, is likely to yield results faster than time than trying to take it all in with single bite.

2.3.1 What is great about Atollic True Studio and Cube

- Cube is excellent tool for assigning micro-controller pins and timing.
- True Studio IDE has excellent debugging trough IDE. Notice that Nucleo boards come with integrated ST-link USB connector, or if you have board without one, a \$6 "ST-Link V2 Mini STM8 STM32 Emulator Downloader" from Amazon works well (connects USB to micro-controller pins).
- Nice professional look and feel. Full functionality without any licensing fees. Experienced IDE users familiar with Eclipse, Kail, QTCreator, Visual Studio, etc. feel quickly at home.
- Integration of LWIP and FreeRTOS to Cube.
- Great ready support and examples for ST Microelectronics ARM32 products.
- Good, although not trouble free, system to keep developers up to date.

2.3.2 What is not so great

- Wants to integrate Cube generated code with application and hardware.
- This easily leads to bloated, non reusable application projects. Extra work is needed to keep IO device application code portable, to separate it from Cube generated files, and to avoid duplicating same Cube and C source files.
- Low abstraction level, chip specific implementations are often needed. For instance Ethernet requires separate implementations for Wiznet and for LWIP, and micro controller chip specific serial port driver code and flash programming. HAL provides some level of portability, but not much. When comparing

STMduino/Teensyduino which has APIs for these (others but for flash): This approach allows developer great control of detail, but also consumes lot of time and requires expertise to get the reliability.

- Much steeper learning curve than STM32duino or TeensyDuino.
- Dependency on Cube versions. Cube and True Studio version updates have caused, and are likely to cause future headaches.
- Cube support for other manufacturers than ST microelectronics practically null. True Studio can still be used for generic ARM builds and should work for debugging.

2.3.3 Static libraries and settings

- Static libraries like iocom, eosal and w5500 have True Studio project in build/atollic folder. This will build the static library in build/atollic/Debug, etc, folder.
- Compiler defines E_OS_metal and STM32L476xx (or other) are set for static libraries. The E_OS_metal indicates that we are compiling for "bare metal" or close to it, anyhow to system without typical operating system (we may still use HAL/CMSIS and FreeRTOS). The STM32L476xx sets micro-controller type. This is needed by HAL.
- Include directories coderoot/eosal, coderoot/iocom allow build with eosal and iocom headers.
- Include directory coderoot/eosal/libraries/WIZnetIOlibrary/Ethernet allows build with WizNET w5500 IO library.
- Include directories related to HAL and CMSIS and come with STM32 Cube. Once support for a specific micro-controller family, lets say STM32F4, is installed within Cube, full copy HAL and CMSIS appears in user's home repository ~/STM32Cube/Repository/STM32Cube_FW_L4_V1.13.0.

2.4 Windows build notes

190610, updated 27.6.2019/pekka

So far only used build system for Windows has been Visual Studio 2019. There are many other tools the build for Windows: It should be possible to use CMAKE files also on Windows and build with MinGW/Qtcreator, other Visual Studio version, etc, but these are likely to require minor tinkering with build setup and possibly with code.

2.4.1 Build folder organization and .sln files

Each library and example project directory contains subdirectory named build/vs2019. The <projectname>.sln solution file and the <projectname>.vcxproj is project file. All the other files and folders within vs2019 folder are temporary intermediate build and user setting files. For libraries, the solution file contains only reference library's project file. For example projects, the solution file, in addition to example's project file, lists all library projects needed to build the example. To build, open the solution file .sln in Visual Studio 2019, select if you want 32/64 bit compilation and debug/release build.

2.4.2 Microsoft Visual Studio 2019 pitfalls (27.6.2019)

I have used Visual Studio 2019 for Windows development, mostly because it is new. As previous Microsoft libraries, it has nice debugging. Anyhow to me it does have a few surprising disappointments, since Visual Studio 2015 did not have these illnesses:

1. By default it comes with "automatic code formatting" enabled. This will totally mess up your code readability, and is unsustainable for projects with lot of code, long code life time, multiple environments or multiple developers. This must be disabled before using, instructions from Google.
2. Rebuild when using multiple copies of Visual Studio simultaneously to debug multiple executables at same time doesn't work. If these are based on same libraries, something is always locked in other copy of visual Studio by other and prevents the build. It looks like someone has reported problem that door hinges sometimes give a sound, so Microsoft solved the problem by nailing whole door shut. Workaround to debug two executables is to use 64 bit build for other and 32 bit build for the other.

3. Debugging doesn't always work if network connection is not up to Microsoft "specs" (what ever those are). In practice this means that all works when at home, but when traveling I often need to turn off Wifi networking. Otherwise debugging doesn't start, but Visual studio just locks up.

2.5 Linux build notes

190611, updated 16.7.2019/pekka

Build is cmake based, so anything which can work with it should do just fine. The cmake is like preprocessor for make files. One writes build instructions in cmake syntax in CmakeLists.txt file, and cmake will generate the make files for actual build system to use. It can generate many different ones. You can as well build with cmake from command line, or use Eclipse, other IDE, etc. QTCreator is an exception, it can use CmakeLists.txt directly. The cmake version should not make much difference, the projects here do not use the new cmake features.

2.5.1 QT creator is good

I have used QT creator 4.0.1, QT 5.6 and cmake for Linux builds. To build a project, start QT creator and open CmakeLists.txt file from project's root folder. QT creator is easy to set up and use, and works well. I appreciate easy debugging and it pointing out the build errors.

2.6 Using vmware virtual machines for development

190828, updated 28.8.2019/pekka

There are good reasons to use virtual machines in product development. Ready development environment with all tools, settings and repositories can be copied from a developer to another. These can be prepared separately for different operating systems, micro controllers or development tool sets. It is easy to get started or get a tested reference to compare to when setting up your own development environment. These things are great, but there are downsides. USB devices like JTAG/ST-link and serial ports need to be mapped to virtual machine. To test a micro controller communication with PC code, network needs to be mapped, etc. Virtual machines are large files, often tens of gigabytes. Copying these over Internet can be problematic and one needs considerable amount of fast reliable hard disc space to store these. High RAM requirements may also be a problem on low end computers.

I have found vmware to be better for this purpose than virtual box. The vmware workstation-player can be downloaded from vmware's web site. It is free for non commercial hobbyist use, but license needs to be bought to use it for work. At the time of writing this, the license price is around \$150 USD.

2.6.1 Using USB devices from virtual machine

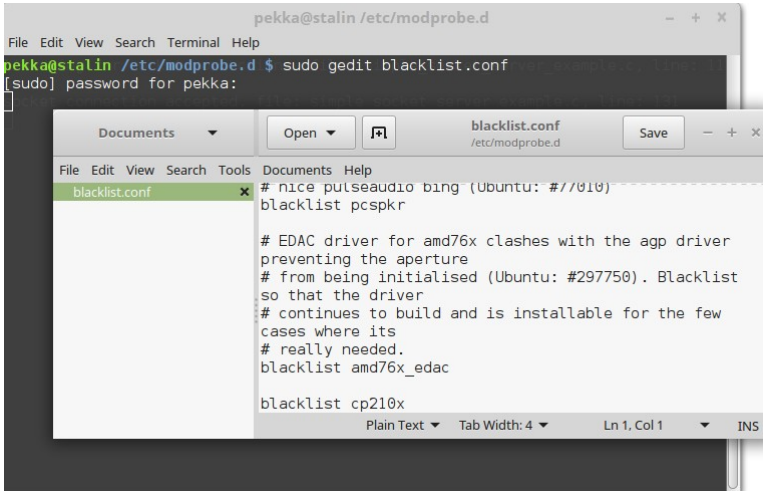
ST-Link, JTAG and serial ports are nowadays typically USB devices for the development computer. To use these from a virtual machine, these need to be connected to the virtual machine, not to the host computer's operating system.

Virtual machines run typically Linux operating system. Windows is more problematic because license would need to be bought separately for each copy of virtual machine and this makes it impractical to use windows virtual machines for sharing development environments.

In Linux, the development tools run mostly on local user accounts, and serial ports require root privileges by default. To allow anyone to use /dev/ttyUSB0, etc:


```
john@john-PC: /dev$ sudo chmod a+r /dev/ttyUSB0
john@john-PC: /dev$
```

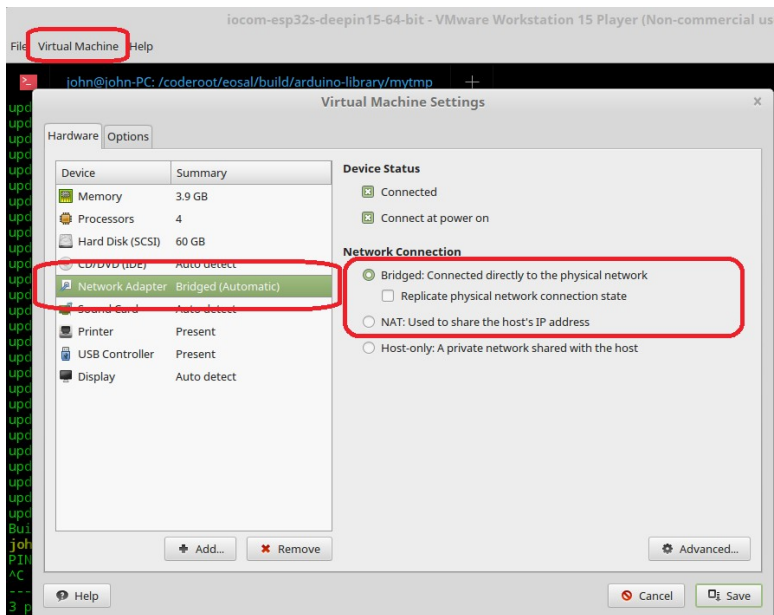
If host computer is also Linux, sometimes it is necessary manually to black list a driver in host operating system to prevent it being loaded. In picture below I have disabled serial port driver cp210xx from the host operating system.



2.6.2 Network considerations

There are basically there ways to approach this.

- Add second network using USB device directly to virtual machine. Map the USB Ethernet or Wi-Fi adapter into virtual machine and just configure it these. Use that network for testing the micro controllers.
- The host's network (either wired or wireless) can also be used to test the devices. If a micro controller is server and software within the virtual machine is client, not much configuration is needed NAT can be used. NAT means that virtual machine shares host's IP address. NAT is especially nice if you use VPN on host computer to connect to corporate network, the virtual machine can share this connection.
- If working other way around where the device is client and it needs to connect to software in virtual machine, set up virtual machine network as "bridged". This means that the virtual machine will appear as completely separate computer from the host computer. Then the virtual machine should pick up network from DHCP, or in none available configure the virtual machine network manually.



3. Implementing IO device

The IO device is often micro controller based. I think ARM32 architecture is best choice. Development tools are good, programming is easy, chips range from very cheap to powerful. Having only one architecture to support is great, saves time and money, and a lot. Developers can use same code in different products and need only to learn one assembler, set of development tools etc.

My personal favorite is STM32 chips, because STM has put much effort on development boards (Nucleo/Discovery), development tools, examples and ready libraries. Atollic True Studio with Cube is free and good and easy. STMDuino is alternative which keeps code simpler than Atollic. Good choice if you have Arduino background, just debugging is more cumbersome and using Cube for pin configuration is not as straight forward.

Big choice is whether to write code in single thread mode directly on metal, or to use RTOS, etc, to get multi threading. Both have advantages. Generally if your team of programmers are solid with concurrent programming and know pitfalls of it, RTOS is probably the right choice. On the other hand, if there is lack of knowledge/experience, use of RTOS is likely to result in boards which crash and burn at random. Direct metal is also the choice, if resources in micro controller are limited. IOCOM library can be used in both these configurations, single thread metal is supported and multi-thread support comes naturally since we run same code on PC.

3.1 Using the library in IO board

190421, updated 30.5.2019/pekka

An IO board communication is typical use for the IOCOM library. I usually power IO boards by ARM32 micro controller. Resources are limited and reliability is the key requirement. Typical choices are:

- We do prefer single threaded model over multi threaded. A programming which crashes the micro controller, locks up the network or shifts timing is far more likely to pass through testing unnoticed in multi threaded programming than in single threaded.
- We stay away from heap based memory allocation, since memory leak or fragmentation could cause reliability problems over long run. Rather memory is allocated globally, from stack or from application managed memory pool.

3.1.1 API for an IO board

The `ioc_ioboard.c` collects IOCOM functionality needed by an IO board into simple to use API calls.

3.1.2 Single thread - IO board software organization

If IO board code runs on bare metal, it is single thread mode: typical initialization and main loop organization is used. Main loop must never pause. The IOCOM can also be used in multi threaded with RTOS, etc. See ? for information.

3.1.3 Mapping the memory blocks to inputs and outputs

Unless there is significant benefit in bit packing, it is easiest to use 1 digital input or output = 1 byte in memory block. Support for bit packing digital inputs and outputs adds some complexity. In most cases, there is too small performance benefit compared to added complexity.

3.1.4 State machines

In single thread mode we can never call `sleep()` etc. State machines are simple way to generate code which will execute a timed sequence or loop without pausing the IO board's main loop.

3.2 Communication status

1890529, updated 29.5.2019/pekka

Communication status refers to general communication information and settings. For example number of connections (sockets, etc) connected to a memory block. In future this could indicate which input data is selected in redundant communication, etc. Communication status may include also settings.

From application's view communication status appears the same as data memory and is accessed using the same `ioc_read()`, `ioc_get16()`, `ioc_write()`, `ioc_set16()`, etc. functions. For data memory, the address is positive or zero, status memory addresses are negative.

| <i>address</i> | <i>nro bytes</i> | <i>description</i> |
|--|------------------|--|
| <code>IOC_NRO_CONNECTED_STREAMS</code> | 2 | Number of connected streams at this moment. |
| <code>IOC_CONNECTION_DROP_COUNT</code> | 4 | How many times socket connection has been dropped. |

For example `IOC_NRO_CONNECTED_STREAMS` is defined as address -2 and has two bytes, thus less significant byte is in address -2 and more significant byte in address -1.

3.2.1 Example, print communication status without callbacks

The example function below: Every time a socket connects or disconnects to this "IO board", this function prints number of connected sockets and how many times a socket has been dropped (global count).

```
static int
    prev_nro_connections,
    prev_drop_count;

static void ioboard_show_communication_status(void)
{
    int
        nro_connections,
        drop_count;

    char
        nbuf[32];

    nro_connections = ioc_get16(&ioboard_fc, IOC_NRO_CONNECTED_STREAMS);
    drop_count = ioc_get32(&ioboard_fc, IOC_CONNECTION_DROP_COUNT);
    if (nro_connections != prev_nro_connections ||
        drop_count != prev_drop_count)
    {
        osal_console_write("nro connections = ");
        osal_int_to_string(nbuf, sizeof(nbuf), nro_connections);
        osal_console_write(nbuf);
        osal_console_write(", drop count = ");
        osal_int_to_string(nbuf, sizeof(nbuf), drop_count);
        osal_console_write(nbuf);
        osal_console_write("\n");

        prev_nro_connections = nro_connections;
        prev_drop_count = drop_count;
    }
}
```

3.2.2 Example, get communication status from callback

The `iocontroller_callback()` example function is called when changed data is received from connection or when connection status changes. Here we are interested in case when connections status, number of connected sockets, etc. or connection drop count changes. We check by callback start and end addressed if either of the two has changed.

```

static volatile int
    nro_connections,
    drop_count;

static void iocontroller_callback(
    struct iocMemoryBlock *mblk,
    int start_addr,
    int end_addr,
    os_ushort flags,
    void *context)
{
    if (end_addr >= IOC_NRO_CONNECTED_STREAMS && start_addr < IOC_NRO_CONNECTED_STREAMS + 2)
    {
        nro_connections = ioc_get16(mblk, IOC_NRO_CONNECTED_STREAMS);
    }

    if (end_addr >= IOC_CONNECTION_DROP_COUNT && start_addr < IOC_CONNECTION_DROP_COUNT + 4)
    {
        drop_count = ioc_get32(mblk, IOC_CONNECTION_DROP_COUNT);
    }
}

```

No heavy processing or printing data should be placed in callback. The callback should return quickly, the communication must be able to process all data it receives. Thus here we just copy the status into global variables.

3.3 Publish static IO device information

190708, updated 8.7.2019/pekka

There are scenarios, where hard coding memory block map in both ends is not the best thing. For example if we wish user interface to display the state of any unknown IO board, or to use names for inputs/outputs, etc, instead of addresses within memory block. This map for example state that "HEATER_POWER" is a 4 byte floating point number at address 121 within memory block "OUT".

Here, we work at low abstraction level, thus we do not yet define what this information is nor how it is formatted. For now it is enough that this is "const static char mydevice_info[] = x....", basically statically allocated block of memory whose contents do not change, or at least changes are not synchronized.

Recommendation is that device information would start with the name of the device information format as '\n' terminated string. This could be used by controller to check what format the device information is.

To set up a static memory block, we allocate space for it statically. For micro-controllers it is beneficial to use "const static" C declaration, so that no RAM copy of the static information is needed, it can be used directly from flash.

3.3.1 Publish device information using ioboard.c API

If the we use ioboard.c API to set up the, we store device information pointer and size in parameter structure before calling ioboard_start_communication:

```

const static os_uchar mydevice_info[]
    = "di-1\n"
      "HEAT_POWER,OUT,121,float\n"
      "TEMPERATURE,IN,18,float\n";

ioboardParams prm;
os_memclear(&prm, sizeof(prm));
...
prm.device_info = mydevice_info;
prm.device_info_sz = sizeof(mydevice_info);

```

Here is some very basic device information as text example. Since plain text takes kind of a lot of space, this is not optimal way to present device information. It is beneficial to compress device information as much as possible, since it is usually transferred every time when a connection is established.

The static memory pool needs to be slightly larger, by `sizeof(iocMemoryBlock) + IOBOARD_MAX_CONNECTIONS * sizeof(iocSourceBuffer)` bytes. We need space for memory block structure and source buffer structure for each connection. We do not need to allocate memory for memory block data nor for source buffer content, since this will be IOC_STATIC memory block.

```
static os_uchar
ioboard_pool[IOBOARD_POOL_SIZE(IOBOARD_CTRL_CON,
    IOBOARD_MAX_CONNECTIONS,
    IOBOARD_TC_BLOCK_SZ, IOBOARD_FC_BLOCK_SZ)
    + sizeof(iocMemoryBlock)
    + IOBOARD_MAX_CONNECTIONS * sizeof(iocSourceBuffer)];
```

3.3.2 Or call basic ICOM functions to set up

When a device information memory block is allocated, it needs pointer to and size of static data. Flag IOC_STATIC will tell that the buffer is static and source synchronization buffering is not needed.

```
os_memclear(&blockprm, sizeof(blockprm));
blockprm.mblk_nr = IOC_DEVICE_INFO_MBLK;
blockprm.mblk_name = "INFO";
blockprm.buf = (os_uchar*)prm->device_info;
blockprm.nbytes = prm->device_info_sz;
blockprm.flags = IOC_SOURCE|IOC_STATIC;
ioc_initialize_memory_block(OS_NULL, &ioboard_communication, &blockprm);
```

3.3.3 Dynamic access to device information in control computer

This is code in control computer's end. A "root callback" function can be set at startup. It gets called when a new memory block is created (among other things).

```
osal_socket_initialize();
ioc_initialize_root(&root);
ioc_set_root_callback(&root, root_callback, OS_NULL);
```

Creating dynamic memory blocks is enabled by IOC_DYNAMIC_MBLKS flag in either `ioc_listen()` or `ioc_connect()` call.

```
ep = ioc_initialize_end_point(OS_NULL, &root);
os_memclear(&epprm, sizeof(epprm));
epprm.flags = IOC_SOCKET|IOC_CREATE_THREAD|IOC_DYNAMIC_MBLKS;
ioc_listen(ep, &epprm);
```

Thus application's `root_callback()` function gets called with IOC_NEW_DYNAMIC_MBLK event, once connection is established and memory block information is received from the IO device.

```
static void root_callback(
    struct iocRoot *root,
    struct iocConnection *con,
    struct iocMemoryBlock *mblk,
    iocRootCallbackEvent event,
    void *context)
{
    os_char text[128], mblk_name[IOC_NAME_SZ];

    switch (event)
    {
        case IOC_NEW_DYNAMIC_MBLK:
            ioc_get_memory_block_param(mblk, IOC_MBLK_NAME,
                mblk_name, sizeof(mblk_name));

            os_strncpy(text, "Memory block ", sizeof(text));
            os_strncat(text, mblk_name, sizeof(text));
            os_strncat(text, " dynamically allocated\n", sizeof(text));
```

```

        osal_console_write(text);

        if (!os_strcmp(mblk_name, "INFO"))
        {
            ioc_add_callback(mblk, info_callback, OS_NULL);
            ioc_set_flag(mblk, IOC_AUTO_RECEIVE, OS_TRUE);
        }
        break;

    default:
        break;
}
}

```

This function again checks if this is device information memory block "INFO". If so it adds info_callback for the memory block and enables IOC_AUTO_RECEIVE to read data instead of explicit ioc_receive() call. Info callback will be called when device information data has been transferred. This example just prints the device information (string assumed).

```

static void info_callback(
    struct iocMemoryBlock *mblk,
    int start_addr,
    int end_addr,
    os_ushort flags,
    void *context)
{
    os_char buf[128];

    if (end_addr >= 0)
    {
        ioc_getstring(mblk, 0, buf, sizeof(buf));
        osal_console_write(buf);
        osal_console_write("\n");
    }
}

```

4. Classes

190502, updated 19.5.2019/pekka

The IOCOM library is an object oriented design written in plain C.

- The root object is starting point for communication object hierarchy. If it is deleted, all resources allocated by the library are released. Memory blocks store incoming or outgoing data. The application accesses data by reading and writing these memory blocks.
- A connection object represent connection from this process to another process. A connection object corresponds to a socket, etc.
- Transfer buffers are the bridge between the memory blocks and connection objects. These take care about buffering what should be sent, what is being received and about synchronization.

4.1 Root object

180727, updated 18.5.2019/pekka

An iocRoot object is the root of communication object hierarchy, and must be initialized before using any other iocom functions. It holds first and last object pointers for memory block list, connection list, etc.

If the library is compiled to support multi-threading, the root object holds also the mutex to synchronize access to communication object hierarchy.

An application can have multiple root objects to keep communication. This is useful when using multi-threading in client, to make sure that separate socket connects, etc work independently without delays caused by the other.

The `ioc_initialize_root()` function initializes the root object. The root object can always be allocated global variable. In this case pointer to memory to be initialized is given as argument and return value is the same pointer. If dynamic memory allocation is supported, and the root argument is `OS_NULL`, the root object is allocated by the function.

```
void ioc_initialize_root(  
    iocRoot *root);
```

The `ioc_release_root()` function releases resources allocated for the root object. Memory allocated for the root object is freed, if it was allocated by `ioc_initialize_root()`.

```
void ioc_release_root(  
    iocRoot *root);
```

Lock functions are used to lock object hierarchy for the root so it can be accessed only by one thread at the time. Once the `ioc_lock()` is called by one threads, other threads are paused when they `ioc_lock()`, until the first thread calls `ioc_unlock()`.

```
void ioc_lock(  
    iocRoot *root);
```

```
void ioc_unlock(  
    iocRoot *root);
```

If the multi-threading support is not enabled for the build, these lock/unlock functions are replaced by empty macros, which do nothing.

4.2 Memory blocks

190502, updated 19.5.2019/pekka

A memory block is byte array which is copied from a device to another.

A memory block in device A is copied to identical memory block in device B. If the memory blocks have different size, the extra data is ignored.

Communication between two devices typically involves several memory blocks, for example IO board blocks could be "binary inputs", "analog inputs" and "binary outputs". When deciding how to divide data into memory blocks, consider also synchronization and how often input data changes. If some data changes quickly and some is static, these should be in different groups. Data which need to be synchronized (transferred in specific order), like "my data array" and "data array ready" bit, need to be in the same memory block.

A memory block is presented by `iocMemoryBlock` structure. The structure stores pointers to buffers, flags and state information. A memory block structure is initialized by:

```
iocMemoryBlock *ioc_initialize_memory_block(  
    iocMemoryBlock *mblk,  
    iocRoot *root,  
    int mblk_nr,  
    os_uchar *buf,  
    int nbytes,  
    int flags);
```

If `mblk` argument is `OS_NULL`, the function allocates memory for the memory block structure. Otherwise it initializes a memory block in application allocated memory block structure. Memory block data size is `nbytes`. Data buffer `buf` is optional and can be `OS_NULL` (buffer allocated by this function). If `buf` pointer is given, it must be pointer to `nbytes` of memory. Memory block identifier number `mblk_nr` identifies which memory block this is, for example `IOC_INPUT_MBLK`. If application gives either `mblk` or `buf` as argument, these must stay in memory until `ioc_release_memory_block` is called.

Once a memory block is no longer needed, it should be released by calling `ioc_release_memory_block` function. If the memory block and/or the buffer were allocated by `ioc_initialize_memory_block` function, the allocated memory is released by this function.

```
void ioc_release_memory_block(  
    iocMemoryBlock *mblk);
```

4.3 Connection objects

180727, updated 18.5.2019/pekka

A connection object represents logical connection between two devices. Both ends of communication have a connection object dedicated for that link, serialized data is transferred from a connection object to another.

```
ioc_initialize_connection(iocConnection *con, iocRoot *root);  
ioc_release_connection(iocConnection *con);  
ioc_attach_memory_block(iocConnection *con, iocMemoryBlock *mblk, iocTransferBuffer *tbuf);  
ioc_detach_memory_block(iocConnection *con, iocMemoryBlock *mblk);
```

```
ioc_connect(iocConnection *con, char *constr, flags)  
ioc_listen(iocConnection *con, flags)  
ioc_accept(iocConnection *con, flags)
```

```
ioc_disconnect(iocConnection *con)
ioc_run(iocConnection *con);
```

4.4 Transfer buffers

180727, updated 18.5.2019/pekka

Transfer buffer binds a memory block and connection object together. It buffers changes to be sent through the connection.

```
ioc_initialize_source_buffer(iocSourceBuffer *sbuf, con, mblk);
ioc_remove_source_buffer(iocSourceBuffer *sbuf);
```

5. The IOCOM library implementation

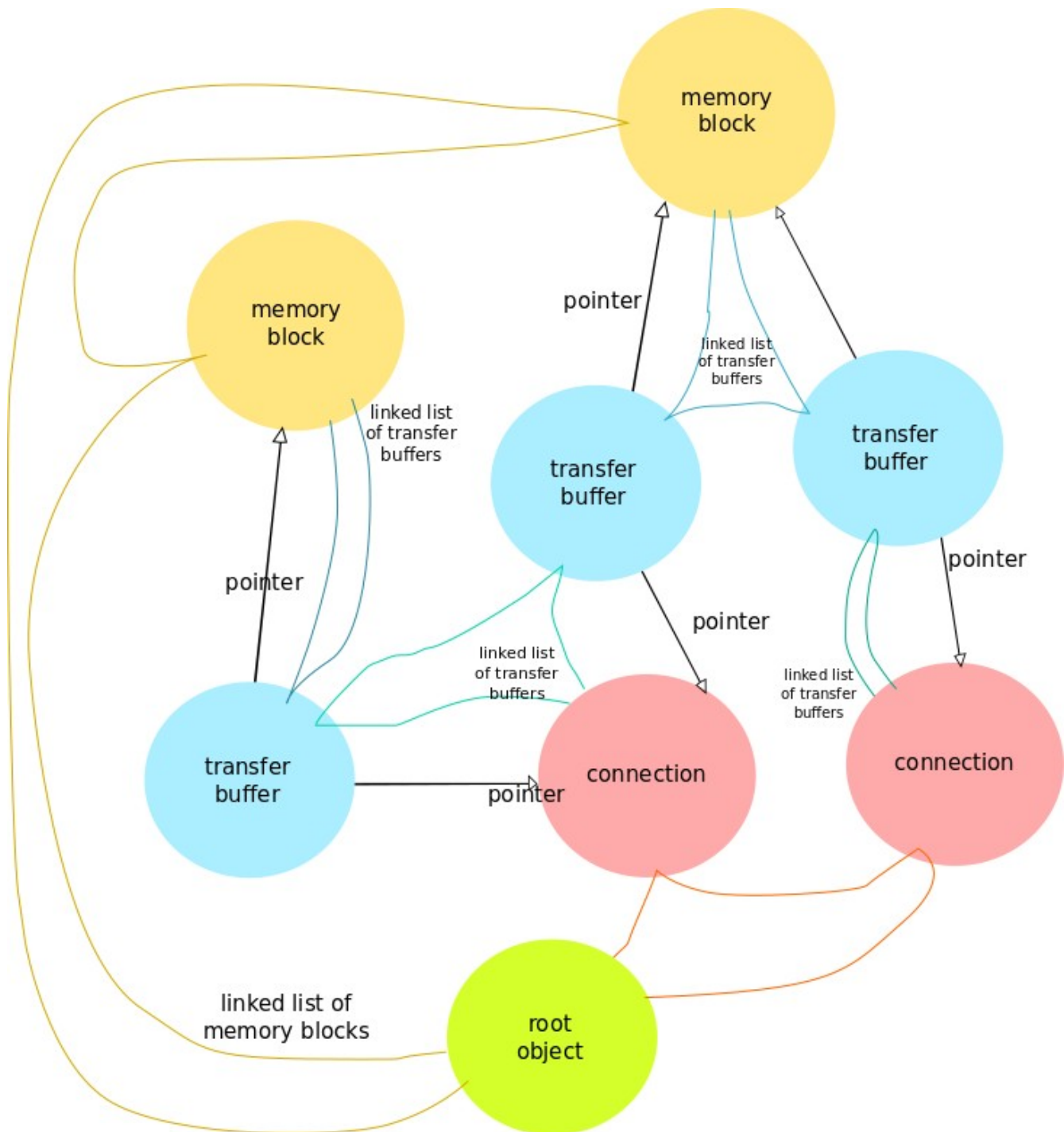
190502, updated 19.5.2019/pekka

The library functionality can be broken into separate concepts. Discussing one topic at a time is more understandable than trying to explain functionality as a single blob. In real code it is these concepts overlap, one .c file rarely corresponds with one topic.

5.1 Object interconnections

180727, updated 18.5.2019/pekka

Linked lists are used to bind communication objects together to form communication hierarchy.

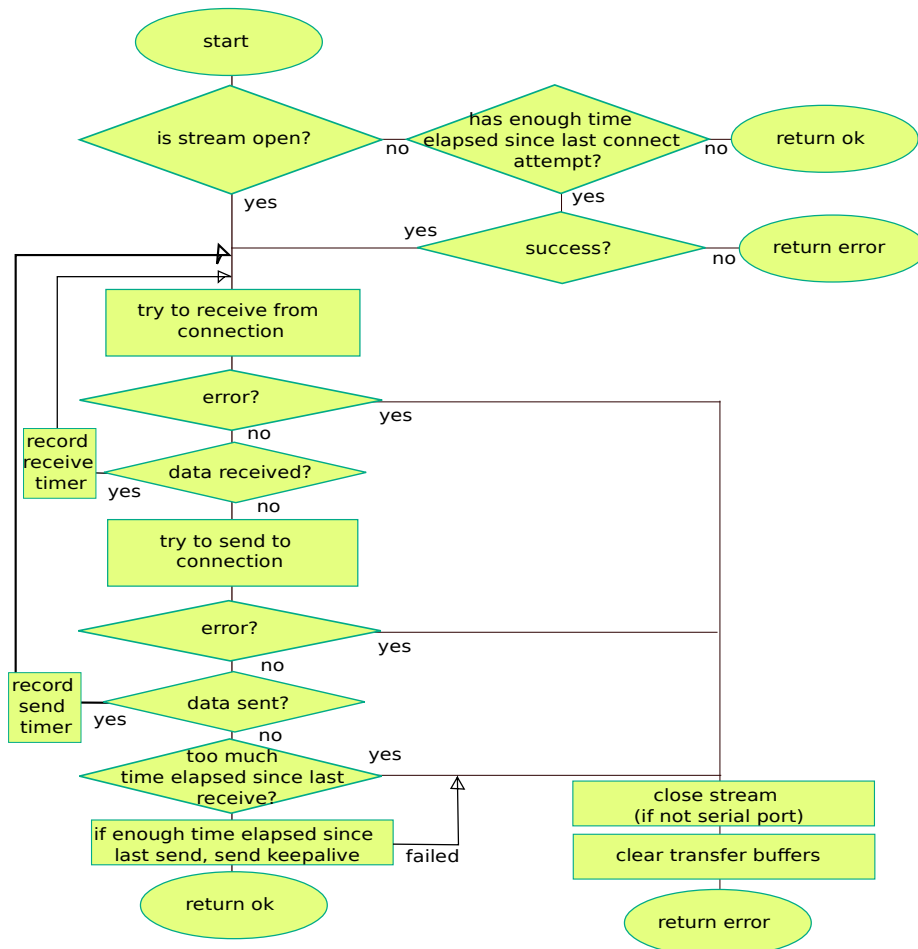


The root maintains list of initialized memory blocks and list of initialized connections. Similarly list of attached transfer buffers is maintained for connections and memory blocks. Object is detached from object hierarchy and all linked lists by calling remove function (like `ioc_remove_memory_block()`). Transfer buffer structure holds pointers to both memory block and connection it is attached to. In addition (not shown in picture) that every communication object holds pointer to root object.

5.2 Run - keep the connection alive

190502, updated 7.7.2019/pekka

The `ioc_connection_run()` function keeps the connection the connection alive. This is single thread function which must be called repeatedly. Similar, but more efficient, implementation exists for multi threaded environments mode using `select()` instead of polling for new data.

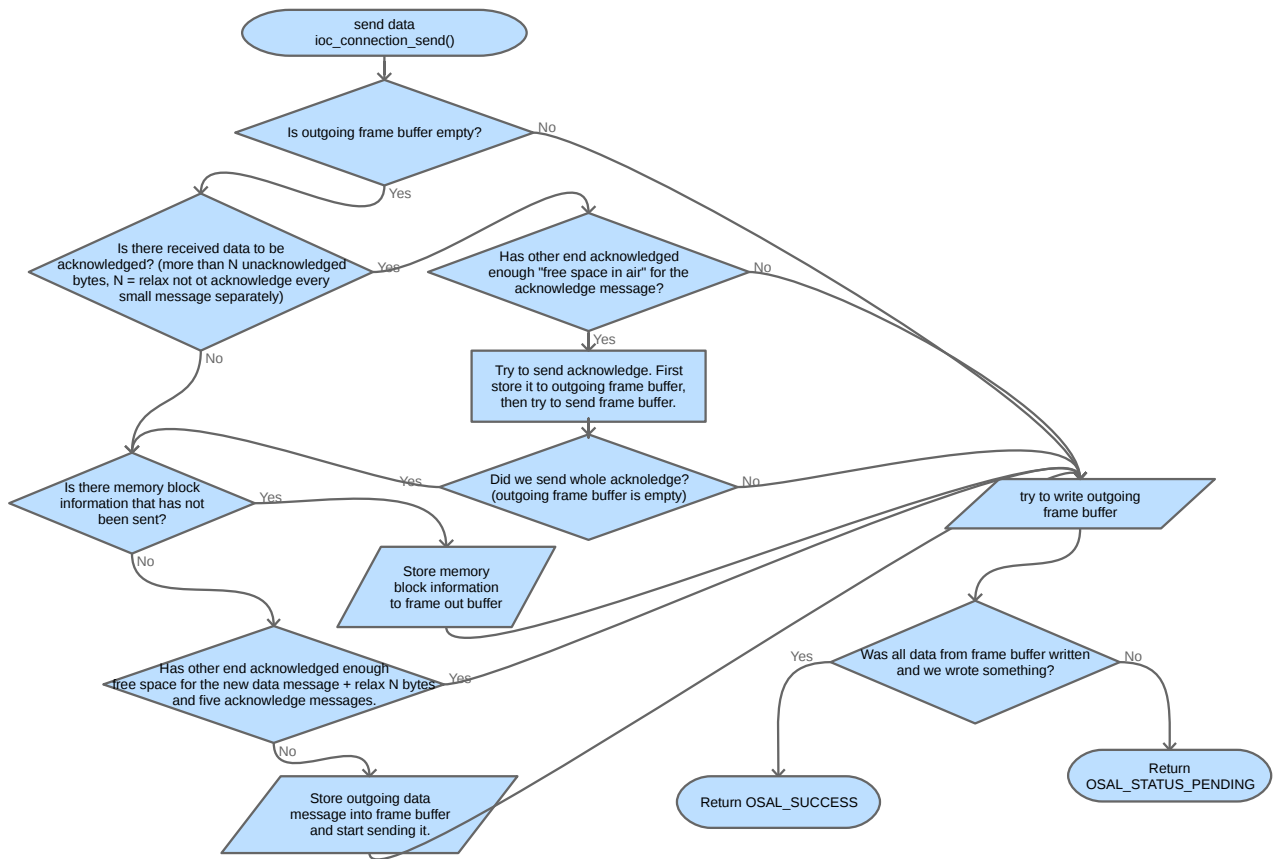


This function calls `ioc_connection_send()` and `ioc_connection()` receive functions to send/receive data.

5.3 Sending data

190502, updated 7.7.2019/pekka

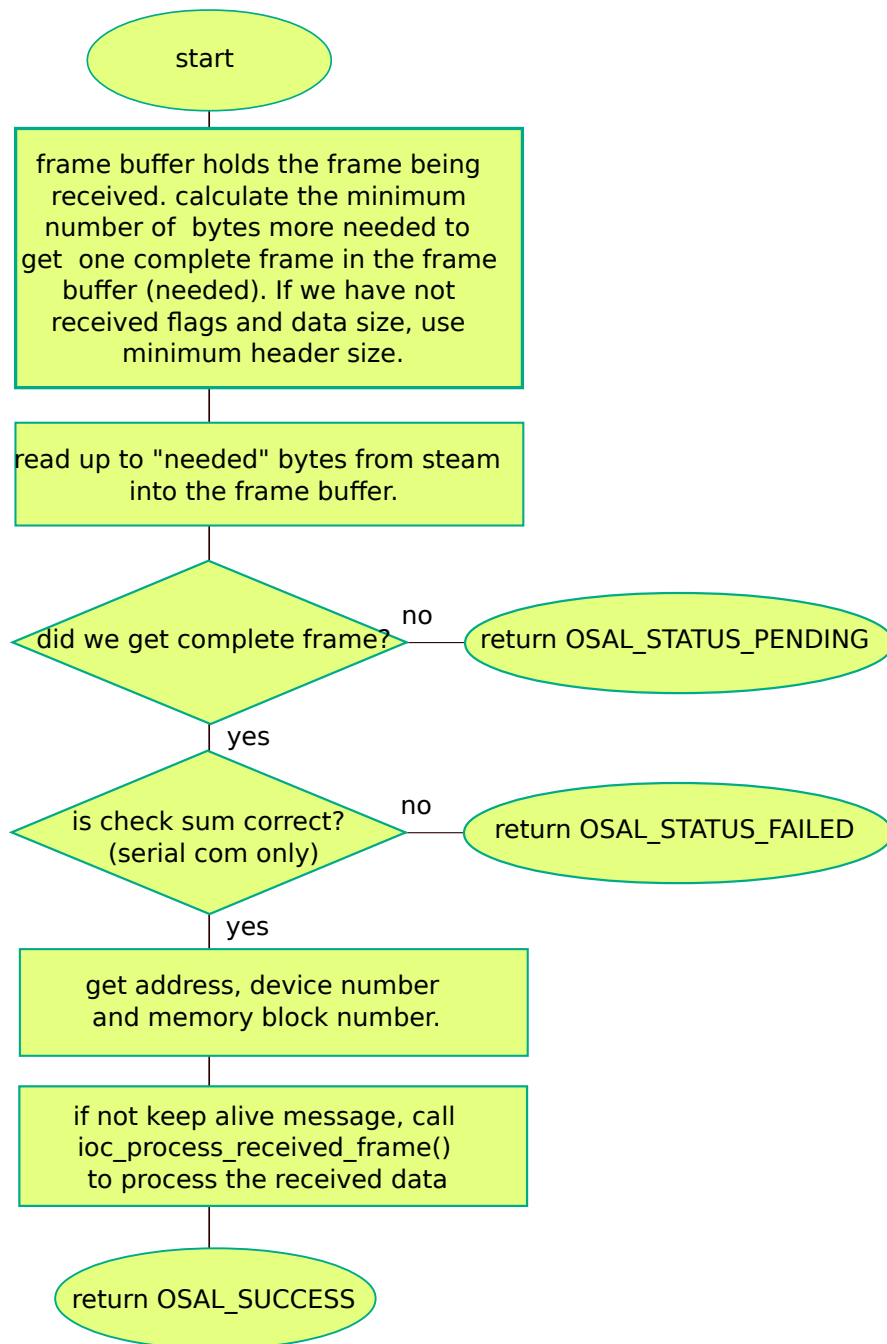
The `ioc_connection_send()` function flow chart: The function takes care about flow control, sending memory block information and memory block data. Memory block data is moved from source synchronization buffer to frame out buffer, this step includes division of data into frames, compression, etc.



5.4 Receiving data

190502, updated 2.5.2019/pekka

The ioc_connection_receive() function flow chart.



5.5 More about flow control

180910, updated 10.9.2018/pekka

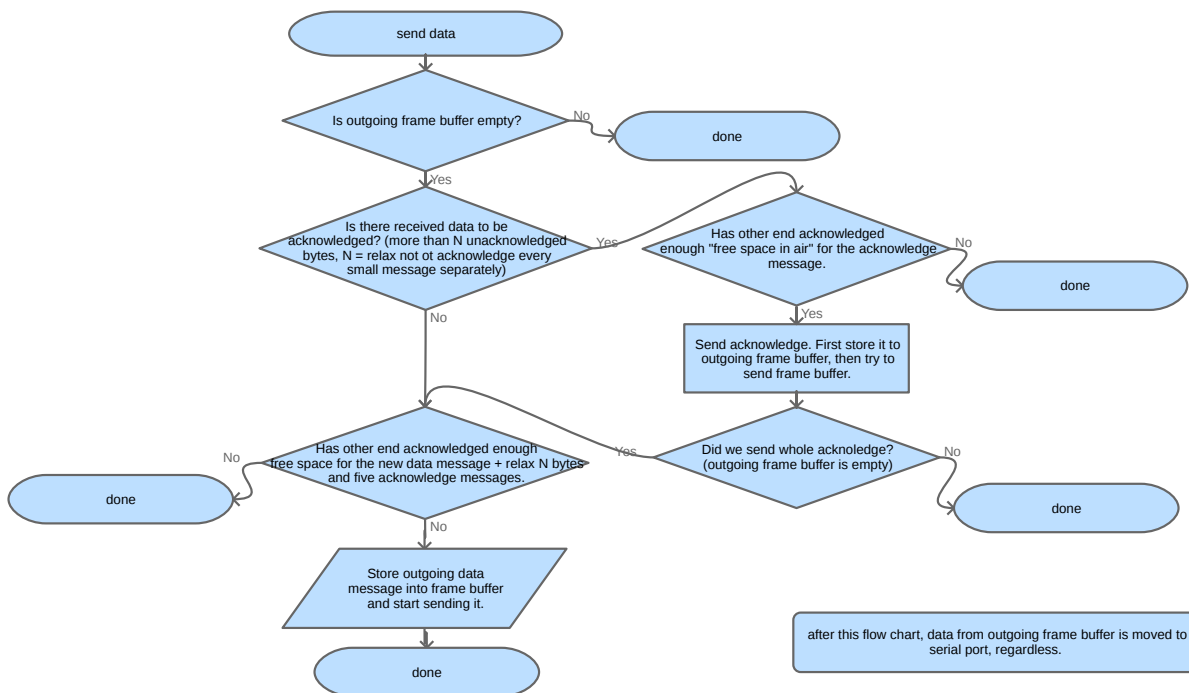
The flow control is used to stop transmitting before serial communication buffers overflow or socket communication buffers collect so much data that communication starts to lag.

Basic idea is simple. A end of connection calculates number of bytes it has sent. The other end calculates number

of bytes it has received and sends this number back as an acknowledgement message (= keep alive message, the two are the same). So sender can know how many bytes it has sent out, but may not have yet been processed by the other end: Subtract last received RBYTES from number of bytes sent out.

This is done using 16 bit unsigned integers. Since we subtract these from each others, we simply ignore overflow. This works as long as maximum allowed lag is below 65536 bytes. We call the maximum lag parameter MAX_IN_AIR.

Serial receive buffer (256 bytes, 255 effective) is able to hold at least two data frames of IOC_SERIAL_FRAME_SZ (96) bytes, plus we allow IOC_SERIAL_UNACKNOLEDGED_LIMIT (40) bytes for unacknowledged data, and reserve some space of the buffer to be used only for acknowledgements. Since our minimum acknowledgement is 40 bytes, we acknowledge minimum 200 bytes with five acknowledgement messages, which is more than enough to keep communication up at any load conditions.



Buffers for socket communication are typically large compared to serial communication, and bigger MAX_IN_AIR values can be used. Since sockets do never lose data and can, especially over Internet, have significant latency, large values would be beneficial. On the other hand embedded systems may have limited socket buffers. Thus conservative MAX_IN_AIR value 2000 bytes is for now used for sockets, but may be changed in further testing.

Preventing possibility of dead lock: Common problem with acknowledge based flow control is that if both ends simultaneously have sent out the maximum number of bytes "in air", but not yet received reply that these have been processed, so both ends halt sending at same time. This has been resolved by reserving space for 5 acknowledgement messages and setting minimum acknowledgement size as 40 bytes.

5.6 Memory block information

190624, updated 24.6.2019/pekka

Each memory block must inform all connected devices about it's existence. This is needed so that memory blocks in different devices can be bound, resized or dynamically created. Following information is maintained for a memory block.

| device name | Device number | Memory block number | Memory block id | Memory bloc name | Memory block size/bytes | Flags (includes direction) |
|-------------|---------------|---------------------|-----------------|------------------|-------------------------|----------------------------|
| TEMPCTRL | 1 | 1 | 1 | INPUTS | 128 | 0 |

This information is static type. Let's say, even if memory block is automatically resized, the information here reflects original set values.

When connection is established, memory block information is sent for every existing memory block is sent to new connection. If new memory is added, block information is sent trough every connection.

I connection contains pointer to memory block, whose information is to be sent. When new connection is established, this pointer is set to first memory block. When information about the pointed memory block has been sent trough the connection, pointer is moved to next memory block. When all are ready, pointer becomes zero.

When new memory block if added, we set the pointer within connection object to point it (unless not null, which means that the connection is already working on transferring memory block data).

Thus control computer end is responsible of subscribing data it wants, and informing what data it will send. This generates source and target buffer objects also in device end.

5.7 Data compression

180728, updated 18.5.2019/pekka

Over lossless connection we have to pass only initial state and later on just changes. To compress the only changes we keep record of previous data sent in transfer buffer.

$$\text{delta}[i] = \text{data}[i] - \text{prev_data}[i]$$

This is done just with 8 bit integers, overflow ignored. Typically most of diff[i] values are zeroes, since in most cases much of data does not change. So we use zero-run compression:

1. Repeat while we have data left. Interrupt with -1 if compressed data is as long or longer than original data.
2. Count how many nonzero bytes there are starting from current byte p. Count up to maximum 255 bytes. Do not interrupt count to one stand alone zero
3. Write number of nonzero bytes.
4. Write nonzero bytes.
5. Calculate number of zero by
6. Count how many zero bytes there are starting from current byte p. Count up to maximum 255 bytes.
7. Write number of zero bytes.


```

int ioc_compress(
    os_uchar *srcbuf,
    int *start_addr,
    int end_addr,
    os_uchar *dst,
    int dst_sz)
{
    os_uchar
        *dst_start,
        *dst_end,
        *p,
        *start;

    int
        bytes,
        count,
        dst_count,
        max_count;

    dst_start = dst;
    dst_end = dst + dst_sz;

    p = &srcbuf[*start_addr];
    bytes = end_addr - *start_addr + 1;

    while (bytes > 0)
    {
        start = p;
        count = 0;
        max_count = bytes;
        if (max_count > 255) max_count = 255;
        while ((p[0] || p[count < max_count-1 ? 1 : 0]) && count < max_count)
        {
            count++;
            p++;
        }
        bytes -= count;

        if (dst + count >= dst_end)
        {
            p = start;
            break;
        }

        *(dst++) = count;
        while (count-- > 0) *(dst++) = *(start++);
        if (bytes == 0) break;

        start = p;
        count = 0;
        max_count = bytes;
        if (max_count > 255) max_count = 255;
        while (*p == 0 && count < max_count)
        {
            count++;
            p++;
        }
        bytes -= count;

        if (dst >= dst_end)
        {
            p = start;
            break;
        }
        *(dst++) = count;
    }

    count = p - &srcbuf[*start_addr];
    *start_addr = p - srcbuf;
    dst_count = dst - dst_start;

    return dst_count < count ? dst_count : -1;
}

```

}

The outgoing message will contain “delta encoding” and “zero run compression” bits in header. If compression result would be as long or longer than data in uncompressed format, compression is not done. The delta encoding is not done at least for the first snapshot to send. Data received should use these bits to detect if data is delta encoded or compressed to read it.

5.8 Uncompress data

This is simpler to implement than compression:

1. Start from first source byte to process.
2. Quit if we have processed all source data.
3. Get next source byte in n . It is count of real data bytes.
4. Move n data bytes from source to destination.
5. Quit if we have processed all source data.
6. Get next source byte in n . It is count of zero bytes.
7. Write n zero bytes to destination
8. Back to step 2.

In addition we must check that we do not overflow destination buffer, in case our source data is erroneous. Undoing delta encoding is also simple. We add received delta values to previous values.

$$\text{data}[i] = \text{data}[i] + \text{delta}[i]$$

This is again done just with 8 bit integers, overflow ignored.

5.9 Data transfer framing

180728, updated 22.6.2019/pekka

Serial frame.

| name/address | bytes | type | use |
|--------------|-------|-------------------|---|
| FRAME_NR/0 | 1 | uchar | Frame count. Every time new frame is sent, this number is incremented, value 0 if used to indicate the first frame and skipped from that point on. Used to check for missing or duplicated frames, first frame, etc. Value 255 is used as ACKNOWLEDGE/KEEP ALIVE. Also values greater than 220 are reserved for control characters. |
| CHECKSUM/1 | 2 | ushort | Checksum. 16 bit CRC. Used to verify frame integrity. |
| FLAGS/3 | 1 | uchar | Flags: IOC_DELTA_ENCODED, IOC_COMPRESSED, IOC_ADDR_HAS_TWO_BYTES, IOC_ADDR_HAS_FOUR_BYTES, IOC_MBLK_HAS_TWO_BYTES, IOC_SYNC_COMPLETE |
| BYTES/4 | 1 | uchar | Data size, bytes. Compressed or uncompressed. Data size zero indicates special message. In this case start address is parameter for special message. |
| MBLK/5 | 1/2 | uchar/ushort | Memory block identifier. |
| ADDR/6-7 | 1/2/4 | uchar/ushort/uint | Start address within memory block. Or for special messages like keep alive or request to bind, this is 32 bit value containing both special message and argument for it. |
| DATA/7-11 | ? | uchar[] | Data. Can be delta encoded and/or compressed. |

Socket frame.

| name/address | bytes | type | use |
|--------------|-------|------|-----|
|--------------|-------|------|-----|

contains check sum, which must match to rest of frame content. First frame has FRAME_NR zero. From then on frame number is incremented until IOC_MAX_FRAME_NR, after IOC_MAX_FRAME_NR frame number jumps to 1 (number 0 is never repeated). In code the frame number is maintained in "frame_nr" for both outgoing and incoming data.

If error is detected, a the connection swiches back to "initiate connection" mode. This starts either BY CONNECT or DISCONNECT character. Thus the connection is dropped off and reinitialized. All key frames are retransmitted. This is somewhat time consuming and the connection will pause for a period. This way of handling errors is well suited for serial links which do not normally have errors, like adequately designed wired serial connections. It is not well suited when communication breaks are frequent, for blue tooth, etc.

If no other data is sent, a connected connection sends periodic "keep alive" message to keep other end of connection that all is still working. If no keep alive no other data is received for a period, connection is terminated and moves back to "connection initialization state". So silent line and communication errors are treated exactly the same way.

5.10.2 Check sums

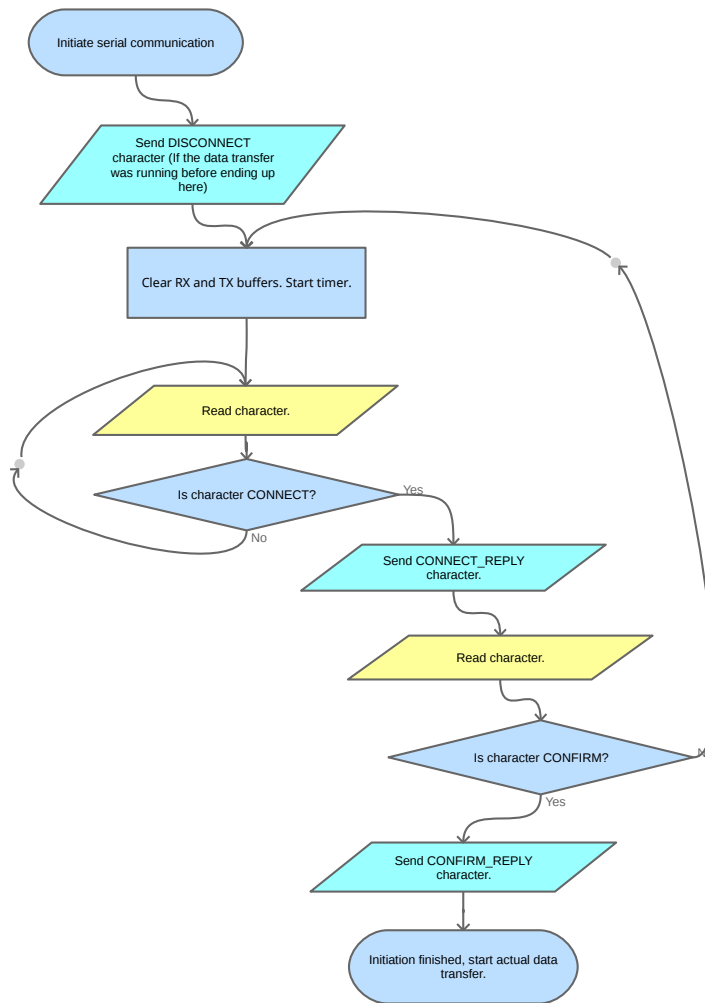
The check sum is calculated from whole transmitted frame, including header. The two bytes used to store the check sum are zeros when the check sum is calculated. Used algorithm is Modbus CRC-16. See ioc_checksum.c for details.

5.10.3 Establishing connection - client

When client end of connection is in disconnected mode, it periodically sends "CONNECT" character to serial line. Once server end receives the "CONNECT" character, it sends "CONNECT_REPLY" character back... Serial communication connect state machine for client end:

5.10.4 Establishing connection - server

When disconnected, the server end listens for "CONNECT" character from client and initiation goes on from there. Serial communication connect state machine for the server end:



5.10.5 Timing

Timing is defined in milliseconds regardless of connection speed. Reasoning for this is that we use relatively long timeouts which can be easily timed using typical OS time slice. Notice that timeouts effect to communication speed/latency only when there are transmission errors in serial line.

- There may not be long pauses within a message frame. Maximum allowed pause between two characters is 100ms. If there is longer pause than 100 ms, receiver will decide connection is broken and clear receive buffer and restart establishing connection.
- There must be at least 200ms pause between "connect" messages sent by client.

5.10.6 Testing serial communication

It is useful to test new IO device software in PC without actual hardware. Serial communication of a simulated IO device can be tested either in linux or Windows. In Linux one can use socat to create virtual serial ports connected together. For example

- `sudo apt-get install socat`
- `sudo socat PTY,link=/dev/ttyS30 PTY,link=/dev/ttyS31`
- `cd /dev/pts`
- `sudo chmod 0666 2`
- `sudo chmod 0666 3`

Would install socat and create and connect ports "ttyS30" and "ttyS31" together. Initially this gives only root access

to the simulated ports. The /dev/ttyS30 and /dev/ttyS31 are links to /dev/pts/2 and /dev/pts/3 (in my test, for you these may be different).

- `cd /dev`
- `ls -la ttyS3*`
- output: `lrwxrwxrwx 1 root root 10 Jun 3 14:02 ttyS30 -> /dev/pts/2`
- output: `lrwxrwxrwx 1 root root 10 Jun 3 14:02 ttyS31 -> /dev/pts/3`
- `cd /dev/pts`
- `ls -la`
- `sudo chmod 0666 2`
- `sudo chmod 0666 3`

I have used com0com on Windows. It works nicely, if one gets it set up. But setting it to run on Windows 10 is a hassle. It needs to load unsigned device driver(s).

5.11 Multi-threading and thread safety

180727, updated 18.5.2019/pekka

If multi-threading is enabled for the library, the function calls are reentrant and can be called from different threads.

The define below controls whether multi-threading support is enabled, set either 1 or 0. There are system specific defaults for this, but this can be overridden by setting compiler define.

```
#define OSAL_MULTITHREAD_SUPPORT 1
```

5.12 Operating system abstraction layer

180727, updated 7.7.2019/pekka

The IOCOM library needs separate operating system abstraction layer, called eosal library. The eosal wraps operating system and hardware dependent functionality as function call interface. This interface is similar for all platforms: Purpose of the operating system abstraction is to separate platform dependent code from the bulk of the library. Thus the IOCOM library can run on multiple platforms, like Windows, Linux and several micro-controllers, and be ported to new systems.

5.13 Memory allocation

180727, updated 18.5.2019/pekka

Heap based dynamic memory allocation is used by default in systems that support it. Anyhow using heap based memory allocation is not recommended for micro controllers or other systems with limited memory resources, even if it was supported. I recommend to set up dedicated memory pool in micro controller environments. It can be set up also for linux/windows, which is useful when developing code to run in micro controllers in PC environment.

The OSAL_DYNAMIC_MEMORY_ALLOCATION define (OS abstraction layer, eosal library) is set depending if dynamic memory allocation is supported for the system, either 1 or 0. This usually follows system specific defaults, but this can be overridden by setting the compiler define.

The IOCOM library has its own functions for memory allocation, `ioc_malloc()` and `ioc_free()`. By default these map directly to corresponding eosal library memory allocation functions.

The trick is here: A static memory buffer can be as memory pool for the ioal library. Function `ioc_set_memory_pool()` stores buffer pointer within the `iocRoot` structure.

If pool is set:

- The pool is dedicated to one iocRoot structure.
- All memory needed by the iocom library is allocated from the pool.
- No dynamic memory allocation is used.
- Necessary pool size can be calculated precisely from maximum number of connections, number of registers, etc, communication detail.
- No fragmentation can occur, blocks are never split.

6. Licensing, etc

190502, updated 27.6.2019/pekka

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6.1 MIT license

190625, updated 27.6.2019/pekka

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190627, updated 27.6.2019/pekka

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