

Bachelor's Thesis

mruby Bytecode Loader

Using Bluetooth in Multi-VM Environment

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Abstract

In recent years, the productivity of embedded systems has become a problem due to their complexity and large-scale. For the purpose of improving the productivity for embedded software development, the mruby on TECS framework has been proposed that is applied mruby (Lightweight Ruby) and supports component-based development. In the current mruby on TECS, the mruby programs have to be compiled and linked every time the programs are modified because the mruby bytecodes are incorporated in the platform. Moreover, while the framework supports multi-VM, developers need to be familiar with the functions of real-time operating systems to effectively execute multiple mruby programs in concurrent or/and parallel. To improve the development efficiency, this paper proposes an mruby bytecode loader using Bluetooth as an extension of mruby on TECS. The loader executes two mruby bytecodes, mruby application bytecode and mruby library bytecode. mruby application bytecode modified frequently is sent from a host to a target device by developers. mruby library bytecode modified infrequently is preserved beforehand in an SD card at the time of the first compilation. In addition, multiple mruby programs cooperatively run in the proposed framework. In the proposed framework, RiteVM scheduler makes multitasking processing more easy-to-use than that of mruby on TECS. Synchronization of starting multiple tasks is also implemented with Eventflag. Experimental results demonstrate the advantages of the proposed framework.

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Chapter 1

Introduction

In these days, embedded systems have been required the high-quality and the high-performance. Due to this trend, the complexity of embedded systems also increases and the scale is larger. For example, IoT (Internet of Things) applications. The low production cost and the short developing period of time are also needed.

An approach of efficient software development is to use component-based techniques. CBD (Component-Based Development) is a design technique for constituting reusable components [1]. Complex and large scale software systems can be developed efficiently using component-based techniques. That is because software componentization provides high-reusability and easy verification. It also makes a system flexible in extensions and specification changes. There are TECS [2], AUTOSAR [3], and SaveCCM [4] as a typical component-based development for embedded systems

In addition, another approach of efficient software development is to develop with script languages. Most of current software are programmed in C language, and the development with C takes a high cost and more time to develop. Script languages make software engineering more efficient and shorten a development period because script languages have high-productivity from their usability. Java script, Perl, Python, Lua and Ruby are well-known as representative script languages.

Although script languages are easy to use and read, their execution time are slower than C language's. For embedded systems, the real-time properties such as worst-execution time and response time are very important factors. Therefore, it is difficult to apply the script languages to embedded systems.

mruby on TECS is a component-based framework for running script program [5]. It is integrated two technologies. One is mruby, which is a script language for embedded systems [6], [7]. The other is TECS (TOPPERS Embedded Component System), which is a component-based framework for embedded systems [2] [8]. mruby on TECS supports to effectively run mruby script language on embedded systems. mruby on TECS also makes execution time 100 times faster than that of mruby.

This paper proposes two additional features of mruby on TECS, mruby bytecode loader using Bluetooth and user-friendly multitask. mruby on TECS has several problems at present. One of the problems is that working efficiency is low because mruby on TECS only supports an SD card in the platform for LEGO MINDSTORMS EV3 [9] to load

mruby programs. In the current development process, it is annoying that the SD card should be inserted and pulled out repeatedly and the OS should be restarted. Although mruby on TECS has supported the multi-VM, developers need to call OS's function in order to execute multiple tasks. Thus, that is a big burden on developers.

This paper proposes mruby bytecode loader using Bluetooth and RiteVM scheduler for fairly executing mruby programs. To improve the development efficiency, mruby bytecode loader using Bluetooth enables developers to insert an SD card only once at the beginning and to transfer mruby application codes from a host to a target device. RiteVM scheduler enables developers to run multitasking programs more easily than mruby on TECS.

Contributions: The proposed framework gives the contribution in the following points.

1. To improve the work efficiency in software development on mruby on TECS:
mruby bytecode loader using Bluetooth helps developers develop software. Developers do not need to insert and pull out an SD card repeatedly and also to restart an OS. The loader supports the continuous loading, which saves the pairing time for Bluetooth.
2. To effectively execute multiple mruby programs in concurrent or/and parallel:
There is a problem in multitasking of the current mruby on TECS. It is that developers need to be well acquainted with the RTOS if multiple mruby programs execute in multitasking. In the proposed framework, it is easy for developers to use multitasking because RiteVM scheduler switches tasks cyclically. Synchronization of multiple tasks is also implemented.
3. To focus on the advantage of component-based developments:
The proposed framework has been developed with component-based. Component-based development gives various benefits. This paper shows the specific examples for the benefits of component-based development.

Organization: The paper is organized as follows. Section 2 introduces the basic technologies i.e. mruby, TECS and mruby on TECS. Section 3 describes the design and implementation of the proposed framework in detail. Section 4 evaluates the proposed framework, Section 5 discusses related work, and then Section 6 concludes this paper.

Chapter 2

Background

Figure 2.1 shows the system model of the proposed framework. The bytecodes are transferred from the host to the target device with Bluetooth. The RiteVMs and mruby library are assumed to be prepared in advance. Each bytecode is allocated to a RiteVM, respectively. Developers can run bytecodes transferred with Bluetooth in multitask.

This section describes mruby on TECS on which the proposed framework is based. mruby on TECS is a component-based framework for running script programs. In mruby on TECS, two technologies are integrated: mruby and TECS. To explain the system, mruby and TECS are also respectively described in this section.

2.1 mruby

mruby is the light-weight implementation of Ruby programming language complying to part of the ISO standard.

Ruby is a object-oriented script language [10]. As the main feature, Ruby is easy-to-use and easy-to-read due to its simple grammar. Ruby can run a program with fewer code lines than C language. Ruby improves the productivity of a software development owing to not only simple grammar also object-oriented functions such as classes and methods, exceptions, and garbage collection.

mruby is suitable for embedded systems because of faster execution with less amount of resources and takes over the usability and readability of Ruby. In addition, VM (Virtual Machine) mechanism is used in mruby, therefore mruby programs can run on any operating system as long as VM is implemented. RiteVM is a VM in mruby, that runs mruby programs. The RiteVM mechanism is shown in Figure 2.2. The mruby compiler translates an mruby code into a bytecode, which is an intermediate code that can be interpreted by RiteVM. The bytecodes can run on a Rite VM, and thus mruby programs can be executed on any target devices if only RiteVMs are implemented.

2.2 TECS

TECS (TOPPERS Embedded Component System) is a component system suitable for embedded systems. TECS helps decrease complexity and difficulty because the generated

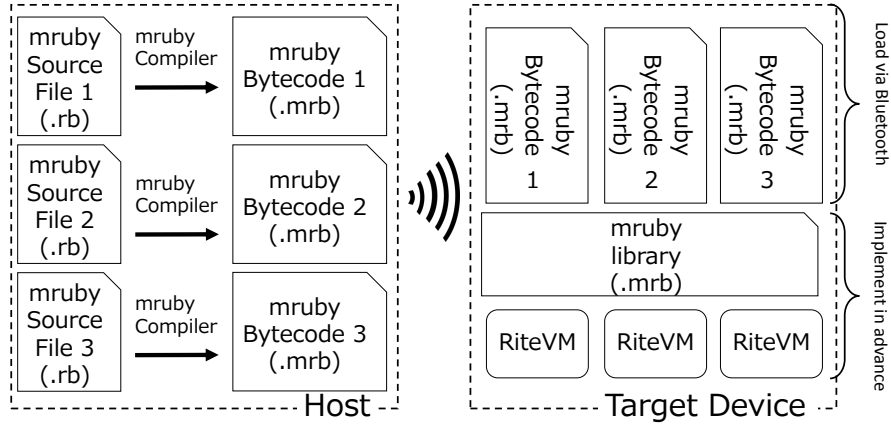


Fig. 2.1 System Model

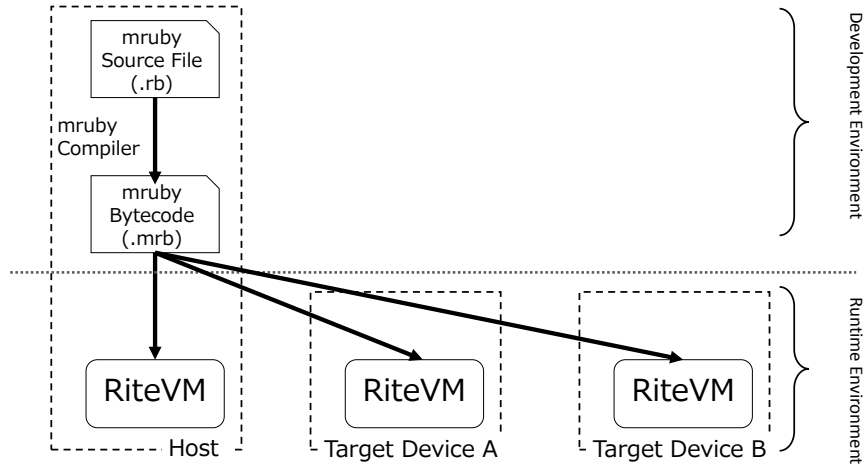


Fig. 2.2 Mechanism of mruby/RiteVM

component diagram can visualize the structure of whole software. It can also help increase productivity and reduce development duplication because a common part of software is regarded as a component.

The component deployment and composition in TECS are statically performed, which gives optimization. As a result, the overhead of execution time and memory consumption can be reduced. There are other features of TECS, implementation in C language, source level portability, fine-grained component, etc.

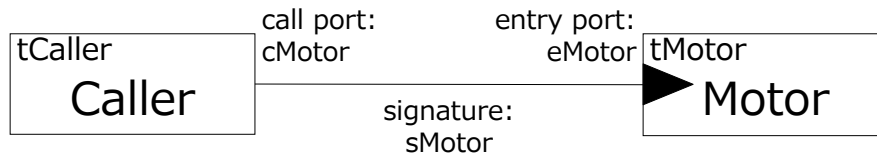


Fig. 2.3 Component Diagram

2.2.1 Component Model

Figure 2.3 shows a component diagram. A *cell* which is an instance of a component in TECS consists of *entry* ports, *call* ports, attributes and internal variables. A *entry* port is an interface to provide functions with other *cells*, and a *call* port is an interface to use functions of other *cells*. A *cell* has one or more *entry* ports and *call* ports. Functions of a *cell* are implemented in the C language.

A type of a *entry/call* port is defined by a *signature* which is a set of functions. A *signature* is the interface definition of a *cell*. The *call* port of a *cell* can be connected to the *entry* port of another *cell* with the same *signature*. A *celltype* is the definition of a *cell*. *Celltype* defines one or more *call/entry* ports, attributes and internal variables.

2.2.2 Component Description

The description of a component in TECS is divided into three parts, *signature*, *celltype*, and build description. TECS code is written in .cdl (component description language) file. The component description is mentioned with an example shown in Figure 2.3 as follow.

Signature Description

The *signature* description defines an interface of a *cell*. A *signature* name is described following the keyword *signature*. It also has the prefix “s”. In this way, a *signature* is defined such as sMotor shown in Figure 2.4. To make the definition of an interface clear, specifiers such as in and out are used in TECS. [in] and [out] represent input and output, respectively.

Celltype Description

The *celltype* description defines *entry* ports, *call* ports, attributes, and valuables of a *celltype*. An example of a *celltype* description is shown in Figure 2.5. A *celltype*

```

1 signature sMotor{
2     int32_t getCounts(void);
3     ER resetCounts(void);
4     ER setPower([in]int power);
5     ER stop([in] bool_t brake);
6     ER rotate([in] int degrees, [in] uint32_t speed_abs,
7               [in] bool_t blocking);
8     void initializePort([in]int32_t type);
9 };

```

Fig. 2.4 Signature Description

```

1 celltype tCaller{
2     call sMotor cMotor;
3 };
4 celltype tMotor{
5     entry sMotor eMotor;
6     attr{
7         int32_t attr = 100;
8     };
9     var{
10        int32_t var;
11    };
12 };

```

Fig. 2.5 Celltype Description

name following the keyword *celltype* with the prefix “t” and elements of a *celltype* is described. To define *entry* ports, a *signature* such as sMotor, and an *entry* port name such as eMotor follow the keyword *entry*. In the same way, *call* ports can be declared. Attributes and valuables follow the keyword *attr* and *var* respectively.

Build Description

The build description is used to instantiate *cells* and connect *cells*. Figure 2.6 shows an example of a build description. A *celltype* name such as tMotor, and a *cell* name such as Motor follow the keyword *cell*. To compose *cells*, a *call* port, a *signature*, a *entry* port in order are described. In this example, a *entry* port eMotor in a *cell* Motor is connected to a *call* port cMotor in a *cell* Caller.

2.3 mruby on TECS

mruby on TECS is a component-based framework for running script language. This framework uses two technologies, mruby and TECS.

```

1 cell tMotor Motor{
2 };
3 cell tCaller Caller{
4     cMotor = Motor.eMotor;
5 };

```

Fig. 2.6 Build Description

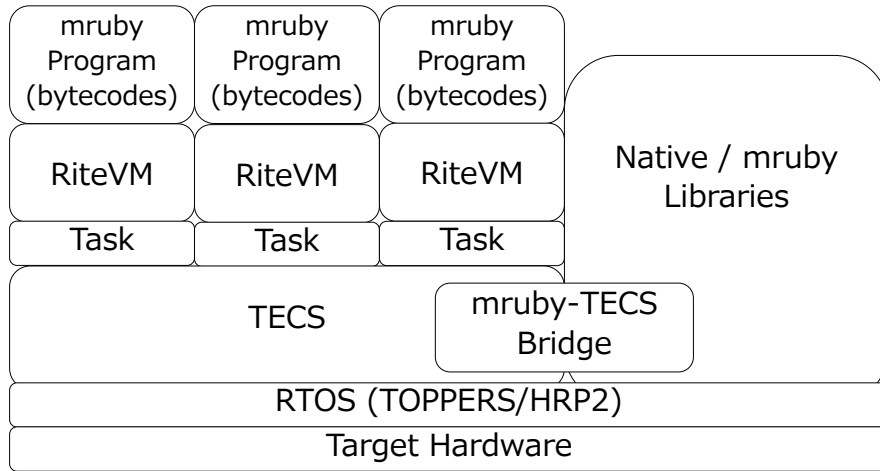


Fig. 2.7 System Model of existing mruby on TECS

2.3.1 System Model

The system model of mruby on TECS is shown in Figure 2.7. Each mruby program, which is bytecode, runs on its own RiteVM as a componentized task of an RTOS. TECS components support various embedded drivers such as motor and sensor drivers.

An mruby-TECS bridge plays a role to call a native program (e.g. C legacy code) from an mruby program. The mruby-TECS bridge provides native libraries for mruby. It also gives TECS components to receive the invocation from an mruby program. The mruby-TECS bridge is described in more detail below.

As the target RTOS, TOPPERS/HRP2 [11], [12] is used in this paper. TOPPERS/HRP2 is an RTOS based on μ ITRON [13] with memory protection. However, mruby on TECS does not depend on the RTOS because TECS supports not only TOPPERS/HRP2 but also the other RTOSs such as OSEK [14] and TOPPERS/ASP [15].



Fig. 2.8 mruby-TECS Bridge

2.3.2 mruby-TECS Bridge

There is a great difference between the execution time of mruby and C language. According to [5], mruby programs are several hundreds times slower than C programs. The execution of mruby bytecode on a RiteVM is not as efficient as that of C language. Thus it is difficult to use mruby for all of code.

The use of Ruby on embedded devices provides the benefit of productivity and maintainability due to the ease to use and read. On the other hands, it is necessary to implement parts of applications in C language in order to manipulate actuators and sensors, and also make a critical section of code run quickly.

Figure 2.8 shows an example of use of an mruby-TECS bridge for controlling a motor. The left side of BridgeMotor belongs to the mruby program. The right side of BridgeMotor belongs to TECS component.

The mruby-TECS bridge generates two things. One is a *celltype* to receive invocation from the mruby program. The other thing is an mruby class that corresponds to the TECS component specified by the developers to invoke a C function from the mruby program.

A code of an mruby-TECS bridge is generated. The generation code supports registration of classes and methods for mruby. The methods in an mruby class are defined by generation codes for an mruby-TECS bridge, such as `setPower` and `stop`. Thus, when a method is called in an mruby program, an mruby-TECS bridge calls the function defined in the TECS component such as a *Motor cell*.

Chapter 3

Design and Implementation

Figure 3.1 shows the detailed system model of the proposed framework. Each mruby application bytecode transferred from the host is received by the loader in the RiteVM. RiteVM reads the own bytecode and executes it. The mruby applications run at the same time because of synchronization processing. RiteVM scheduler switches tasks as multiple tasks can run in concurrent.

3.1 mruby Bytecode Loader Using Bluetooth

This section describes an additional feature of mruby on TECS, mruby bytecode loader using Bluetooth. In the current system, all binary data including bytecodes are saved in an SD card. Developers must insert and pull out the SD card every time the application programs are modified. The OS in the target device should be also restarted. It causes a low development efficiency to repeat that. mruby bytecode loader using Bluetooth makes the developers' burden decrease. Developers should just once carry out the work to insert the SD card and start the OS.

mruby programs are consisted of mruby application and libraries. mruby application is the main code, which developers should program. mruby libraries are the codes defining the functions for application such as Ruby classes. The mruby bytecodes including mruby application and libraries can be sent and run. However it is wasteful in terms of the size and time to send because libraries are not frequently modified. In the proposed framework, mruby applications are only sent, and mruby libraries are preserved in the SD card beforehand.

The development flow in mruby bytecode loader using Bluetooth is shown in Figure 3.2. The platform including RiteVM and mruby library is compiled and copied in the SD card at the first. In the host, the mruby application programs (.rb) are edited and compiled into the bytecodes (.mrb) by an mruby compiler. The generated bytecodes are transferred from the host to the target device with Bluetooth.

Moreover, developers can save the time of Bluetooth pairing since the loader can continuously load the bytecode.

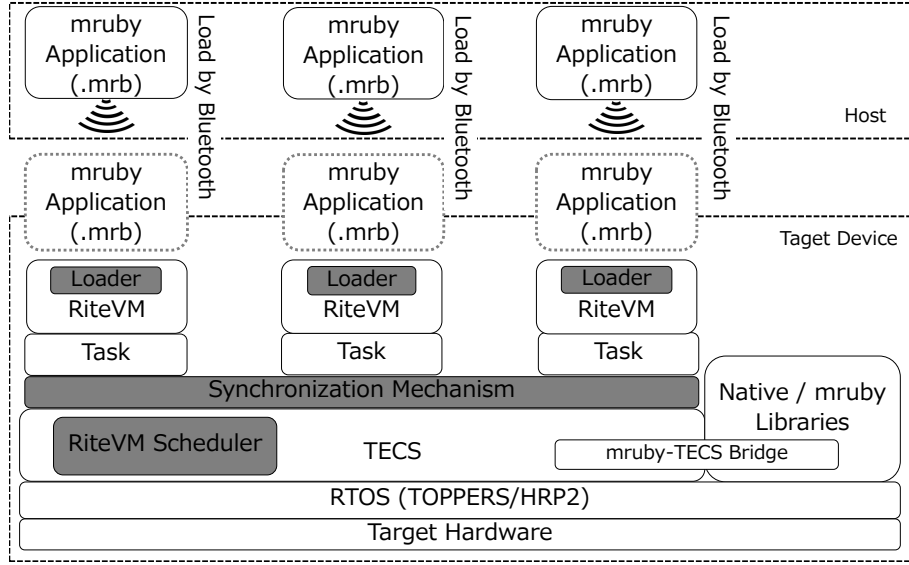


Fig. 3.1 Detailed System Model of the proposed framework

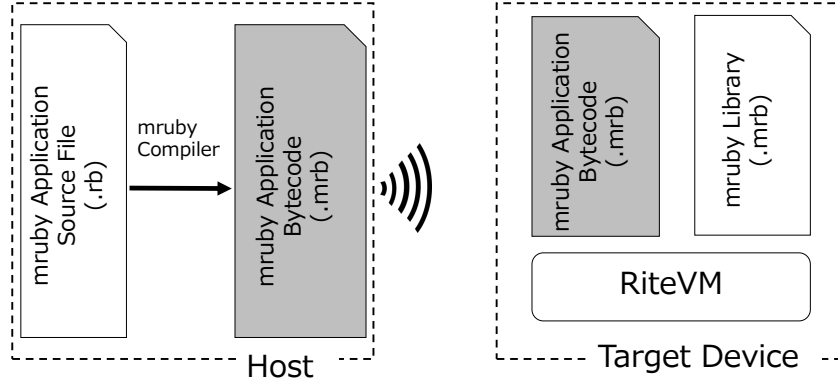


Fig. 3.2 Development Flow in mruby bytecode loader using Bluetooth

3.1.1 Component of RiteVM with mruby bytecode loader using Bluetooth

The proposed framework provides mruby bytecode loader using Bluetooth as TECS component. A component of mruby bytecode loader using Bluetooth is an extension of the RiteVM component, which is described in [5]. The component plays a role in receiving bytecodes via Bluetooth, and also manages RiteVM configuration such as automatically

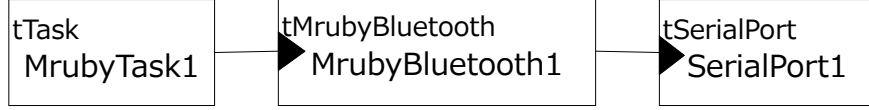


Fig. 3.3 Component Diagram of mruby bytecode loader using Bluetooth

generates the bytecode in the build description. This generated bytecode is prepared beforehand in the SD card such as mruby libraries, and different from a bytecode transferred with Bluetooth.

Figure 3.3 shows a component diagram of MrubyTask1 and MrubyBluetooth1 *cells*. The MrubyTask1 *cell* is a componentized task of the RTOS (TOPPERS/HRP2). TOPPERS/HRP2 is described in [11], [12]. The MrubyBluetooth1 is a component of RiteVM with mruby bytecode loader using Bluetooth. A bytecode in the host is transferred and received at the top of the component. In this framework, ZMODEM [16] is used as a binary transfer protocol.

Figure 3.4 shows the process of executing mruby program in a component of RiteVM with mruby bytecode loader using Bluetooth such as MrubyBluetooth1. The concrete main code of tMrubyBluetooth is shown in Figure 3.6.

First, a pointer of *mrbc_state* and *mrbc_context* are initialized. *mrbc_state* is a set of states and global variables used in mruby.

Second, RiteVM reads the bytecode of mruby libraries. mruby libraries are a set of Ruby classes such as motor class and sensor class. For example, motor class defines methods to rotate and stop a motor. The tMrubyBluetooth *cell* has two attributes as shown in Figure 3.5: *mrubyFile* and *irep*. The *mrubyFile* indicates the program files of mruby libraries. *[omit]* is only used for the TECS generator, thus the attribute, *mrubyFile*, does not consume memory. The *irep* is the pointer of the array stored the bytecode of mruby libraries. In short, the bytecode of mruby libraries is stored as an attribute of the component when compiling for the first time.

Third, RiteVM reads the bytecode of the mruby application transferred with Bluetooth. The mruby application bytecode is stored in an array of type `uint8_t`, which is the same as type `char`. The array is different from that of holding the mruby library bytecode. Two bytecodes are read separately in the RiteVM.

Finally, the mruby task runs. When the mruby application is modified, only the bytecode of the modified application should be transferred. mruby libraries need not be touched because libraries are not normally changed.

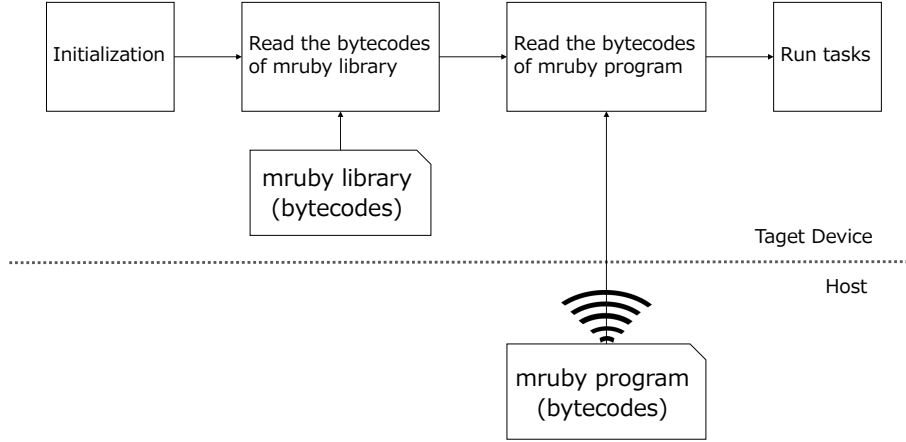


Fig. 3.4 Control Flow of mruby bytecode loader using Bluetooth

```

1 celltype tMrubyBluetooth{
2     entry sTaskBody eMrubyBody;
3     attr{
4         [omit]char_t *mrubyFile;
5         char_t *irep=C_EXP("&$cell_global$_irep");
6         % uint8_t irepApp[COUNT_STK_T(TMAX_APP_BINARY_SIZE)]
7         % __attribute__((nocommon));
8     };
9 };

```

Fig. 3.5 Celltype Description for mruby bytecode loader using Bluetooth

3.2 Multitask

This section describes implementation of multitasking in the proposed framework. mruby on TECS has supported multitasking. However, multitask processing in mruby on TECS requires the knowledge of the RTOS (TOPPERS/HRP2) for developers.

One of approaches for multitasking is co-routine. Co-routine is a cooperative thread, and scheduled by developers with the functions such as *resume* and *yield*. (Ruby co-routine is defined in class Fiber [17]) Co-routine is a non-preemptive multitasking, and does not receive the OS's support because developers have to switch tasks manually. Co-routine can not take advantage of multi core processing.

Besides, as another method, *delay*, a service call of μ ITRON, can be used for multitasking. This service call delays the execution of the own task for the time of the argument. In the approach of *delay* function, developers have to schedule as the same as co-routine.

In the proposed framework, as an approach for multitask processing, RiteVM scheduler is implemented. The RiteVM scheduler is a fair scheduler and runs multiple tasks equally.

```

1 void
2 eMrubyBody_main(CELLIDX idx)
3 {
4     /* Declaration variables */
5     mrb_state *mrb;
6     mrbc_context *c;
7     /* New interpreter instance */
8     mrb = mrb_open();
9     // Omit: error check for mrb_state
10    /* New mruby context */
11    c = mrbc_context_new(mrb);
12    // Omit: initialization of mruby-TECS bridge
13    /* Receive the bytecode via Bluetooth */
14    bluetooth_loader( App_bytecode );
15    /* Load mruby library bytecode and run */
16    mrb_load_irep_cxt(mrb, ATTR_irep, c);
17    /* Load mruby application bytecode and run */
18    mrb_load_irep_cxt(mrb, App_bytecode, c);
19    if (mrb->exc) {
20        /* Failure to execute */
21        mrb_p(mrb, mrb_obj_value(mrb->exc));
22        exit(0);
23    }
24    /* Free mruby context */
25    mrbc_context_free(mrb, c);
26    /* Free interpreter instance */
27    mrb_close(mrb);
28 }

```

Fig. 3.6 Main code for mruby bytecode loader using Bluetooth

3.2.1 RiteVM Scheduler

The RiteVM scheduler is a cyclic handler, and calls *rotateReadyQueue*, a service call of μ ITRON to switch tasks with the same priority. In other words, the RiteVM scheduler calls *rotateReadyQueue* cyclically. *rotateReadyQueue* is described as follows.

The case is assumed that there are two tasks with the same priority, and both tasks are in an infinite loop. In the current system, when one task is executed first, another task would not be executed. That is because the task with first execution runs in the loop.

When *rotateReadyQueue* is called, tasks with the same priority are switched as shown in Figure 3.7. The argument of *rotateReadyQueue* is the priority.

The *rotateReadyQueue* can be performed if the number of tasks is more than two. For example, three tasks are in the order: task 1, 2, and 3. In this case, the order is rotated, task 2, 3 and, 1, when the *rotateReadyQueue* is called.

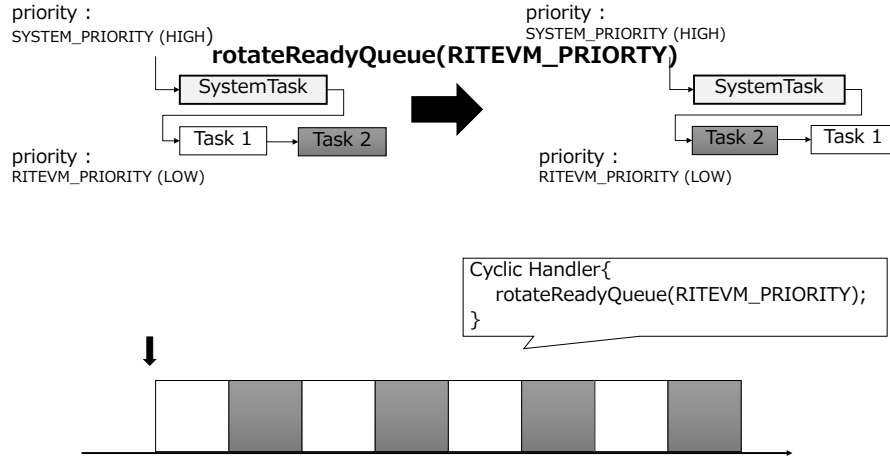


Fig. 3.7 rotateReadyQueue

3.2.2 Component of RiteVM Scheduler

Figure 3.8 shows a component diagram of the cyclic handler. The components of cyclic handler consist of two components: *CyclicHandler* and *CyclicMain*. *CyclicHandler cell* configures the cyclic handler based on μ ITRON. Cyclic handlers based on μ ITRON are described in detail [13]. The cyclic handler has five arguments: ID, attribute, cyclic time, cyclic phase and access pattern. *CyclicHandler cell* has these arguments as attributes of the *cell*. *CyclicMain cell* is a component to perform the processing body of a cyclic handler. *rotateReadyQueue* is implemented as the body. Figure 3.9 shows *tCyclicMain celltype*, which has a *call* port, an *entry* port and an attribute. The *call* port is connected with the *entry* port of the Kernel *cell* (*tkernel.eiKernel*) to call functions of the kernel. The attribute is used as an arguments of *rotateReadyQueue*.

Figure 3.10 shows a build description that corresponds to the component diagram shown in Figure 3.8. In the part of *CyclicHandler cell*, configurations of a cyclic handler is described such as attribute, cyclicTime and cyclicPhase. In this case, the cyclic handler is executed when it is generated because the attribute is *TA_STA* that represents the cyclic handler is in an operational state after the creation. The cyclic handler is executed every one msec. In another part, the priority of *CyclicMain cell* is described. *RITEVM_PRIORITY* defines the priority of mruby tasks. In the main of *CyclicMain*, *rotateReadyQueue* is implemented and the priority is passed as the argument.



Fig. 3.8 Component Diagram of Cyclic Handler

```

1 celltype tCyclicHandler {
2     [inline] entry sCyclic eCyclic;
3     call siHandlerBody ciBody;
4     attr {
5         [omit] ATR attribute = C_EXP("TA_NULL");
6         [omit] RELTIM cyclicTime;
7         [omit] RELTIM cyclicPhase = 0;
8     };
9 };
10 celltype tCyclicMain{
11     require tKernel.eiKernel;
12     entry siHandlerBody eiBody;
13     attr {
14         PRI priority;
15     };
16 };
  
```

Fig. 3.9 Celltype Description of Cyclic Handler

3.2.3 Synchronization of Multiple RiteVM Tasks

In the proposed framework, RiteVMs read mruby bytecodes, and then execute the applications. Eventflag, one of synchronous processing, is applied to synchronize the starting of multiple mruby applications. Each task sets the flag pattern such as 0x01 (01) and 0x02 (10), and then waits the flag pattern, 0x3 (11), with AND. This process can also apply to the case of the more tasks. For example, in the case of the four RiteVM tasks, each task sets the flag pattern such as 0x01 (0001), 0x02 (0010), 0x04 (0100) and 0x08 (1000), and then waits 0x0f (1111) with AND as shown in Figure 3.11 (A).

3.3 Benefits of Component-Based Development

This section describes the design using the benefits of component-based development.

In the framework, RiteVM, RiteVM scheduler, and Eventflag are implemented as com-

```

1 cell tCyclicHandler CyclicHandler{
2     ciBody = CyclicMain.eiBody;
3     attribute = C_EXP("TA_STA");
4     cyclicTime = 1;
5     cyclicPhase = 1;
6 };
7 cell tCyclicMain CyclicMain{
8     priority =
9         C_EXP("RITEVM_PRIORITY");
10 };

```

Fig. 3.10 Build Description of Cyclic Handler

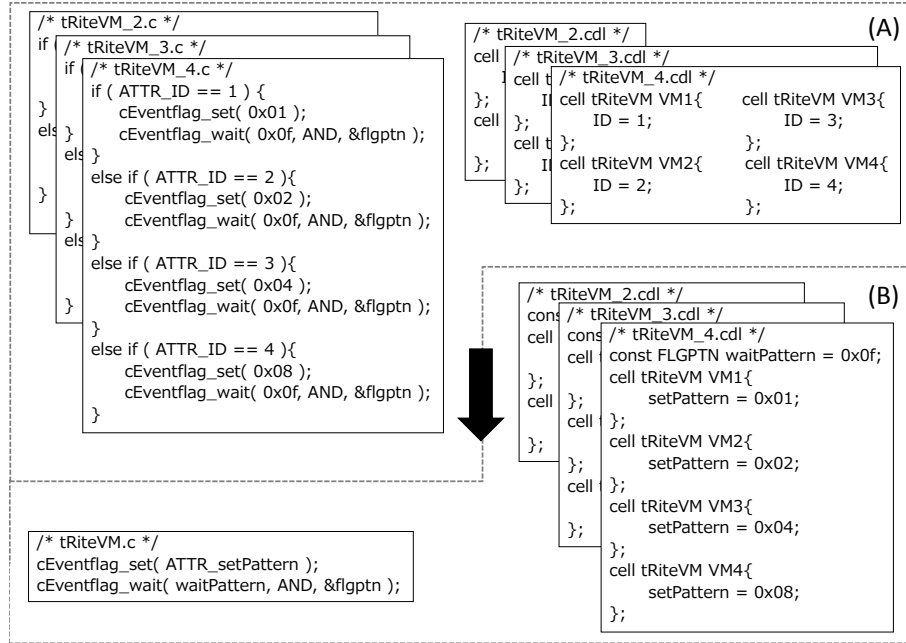


Fig. 3.11 The design for Eventflag using TECS

ponents. Therefore, developers can easily add or remove these components and also reuse them. For example, if developers do not need the cyclic handler, the .cdl files shown as Figures 3.9 and 3.10 should be commented out such as `//import(<tCyclicHandler.cdl>);`.

In addition, the code size can decrease by developing with component-based. In the proposed framework, the advantage is applied in the Eventflag component. The set pattern and wait pattern are defined as attributes of the component as shown in Figure 3.11 (B). This design such as `cEventflag_set(ATTR_setPattern)` enables the program without “if” statements and reuses the identical .c file. Developers do not need to modify the .c file because the .cdl files are prepared in accordance with the number of RiteVMs. In addition, the components of Eventflag are built with *[optional]* in TECS. *[optional]* means that the codes are run only when the call port is connected. The .c file does not be rewritten even if developers do not use Eventflag.

Chapter 4

Experimental Evaluation

This section mentions experimental results and their consideration. To analyze the advantages of the proposed framework, the evaluations are performed as follows.

- Size and time for transferred mruby bytecodes
- Execution time with singletasking, co-routine, and multitasking
- Overhead for cyclic time
- Code size using the benefit of CBD

These evaluations are performed in order to indicate that mruby bytecode loader improves the work efficiency, and that the proposed multitask processing effectively executes compared with singletasking or co-routine, and also the overhead of the cyclic period. This paper demonstrates the proposed system on a LEGO MINDSTORMS EV3 (300MHz ARM9-based Sitara AM1808 system-on-a-chip) compiled with gcc 4.9.3 -O2 and mruby version 1.2.0.

The size, load process time, and compilation time for mruby application and mruby application including library is shown in Table 4.1. The bytecode of mruby application is smaller and faster than that of including mruby libraries in all terms. In the proposed framework, developers send only mruby application and prepare mruby library in advance. Therefore, the design can send the bytecode faster. In addition, the design can save the time to insert an SD card to restart an OS. These advantages lead improvement of the work efficiency.

The comparison of the application execution time with singletasking, co-routine, and multitasking is shown in Figure 4.1. The 100,000 times loop program is used as mruby application for evaluation of execution time. In detail, the singletask program loops 100,000 times, and the multitask and co-routine programs loop 50,000 times in each task. In Figure 4.1, the cyclic time of the cyclic handler for multitasking is one msec. Multitasking's execution time is about the same as singletasking's while co-routine takes more time than them to execute an mruby application. This result shows the proposed design is superior to co-routine in terms of execution time. Switching tasks' overhead is also evaluated, that is about three μ sec on average. The number of switching tasks is from 500 to 600 because singletasking process in Figure 4.1 takes about 540 msec. Therefore, the overhead of multitasking is 0.5 % or less, and multitasking can be used without the

Table 4.1 Comparison of the size and load process time between an mruby application including mruby libraries and not

	App&Lib	App	App&Lib / App
Bytecode Size	14,044 bytes	199 bytes	
Load Process Time	305.081 msec	7.774 msec	
Compilation Time			

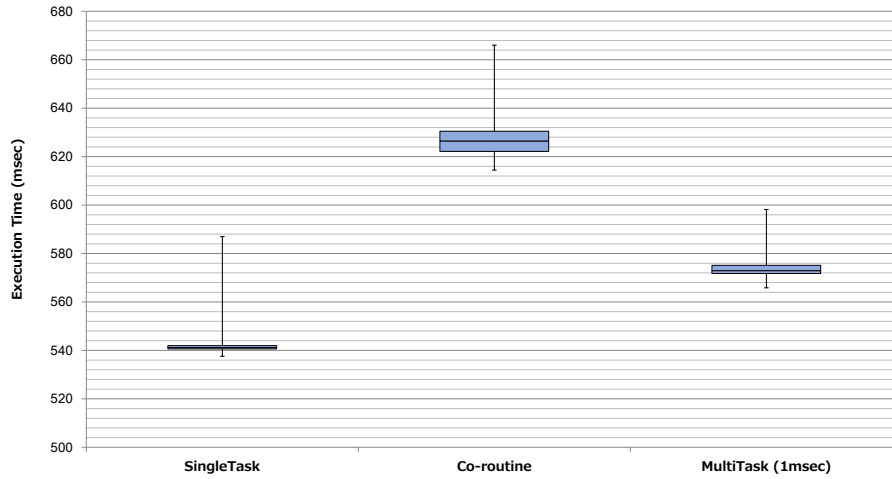


Fig. 4.1 Comparison of the application execution time with singletask, co-routine, and multitask

overhead.

Figure 4.2 shows the execution time of multitasking with the cyclic handler. A lower limit of the cyclic time is one msec due to the specification of TOPPERS/HRP2, the used RTOS. More than 10 msec do not be evaluated in this paper because it is thought the larger cyclic time influences applications. Each execution time of cyclic period is the same as the others. That is because the overhead of switching tasks (about 3 μ sec) is small in comparison with the execution time. The smaller cyclic time is better in multitasking due to concurrent and/or parallel processing.

CodeSize

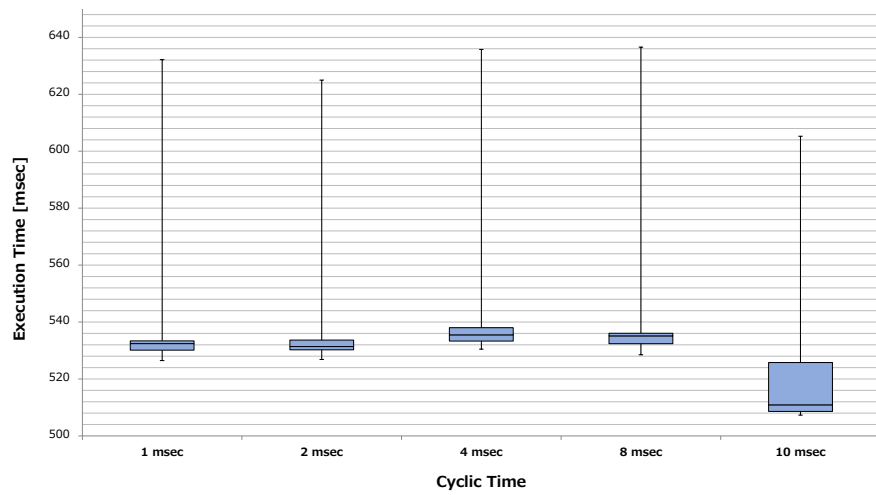


Fig. 4.2 Comparison of the overhead for each cyclic period of calling rotateReadyQueue

Chapter 5

Related Work

The open-source run-time systems for scripting languages have been proposed such as follow: python-on-a-chip [18], the Owl system [19], eLua [20], mruby [6], [7], and mruby on TECS [5].

python-on-a-chip (p14p) is a Python run-time system that uses a reduced Python VM called PyMite. The VM runs a significant subset of Python language with few resources on a microcontroller. p14p can run multiple stackless green threads.

The Owl system is an embedded Python run-time system. The Owl is a complete system for ARM Cortex-M3 microcontrollers. The Owl toolchain produces relocatable memory images, that are directly runnable on the microcontroller, from Python code objects. The interpreter of the Owl system is the same as that of python-on-a-chip.

eLua offers the full implementation of Lua programming language to the embedded systems. Lua is one of the most popular script languages for embedded systems [21], [22]. Lua supports co-routine, referred to collaborative multitasking. A co-routine in Lua is used as an independently executed thread. A co-routine can just suspend and resume multiple routines. Thus, a Lua co-routine is not like multitasks in multitask systems.

mruby, the lightweight implementation of the Ruby language, has been proposed for embedded systems. mruby programs can run on a RiteVM, which is the VM for mruby and reads the mruby bytecode. mruby has supported co-routine, but not supported multitasking for RTOSs.

mruby on TECS is a component-based framework for running mruby programs. The programs on mruby on TECS can execute about 100 times faster than the mruby programs. Software can be also developed with component base by mruby on TECS. Although multitasking has been supported in the current mruby on TECS, developers need to be familiar with functions of an RTOS to use multitasking. The co-routine is supported as same as mruby.

Table 5.1 shows a comparison between the proposed framework and previous work.

Table 5.1 Comparison of the proposed and previous work

	Bluetooth Loader	C Function	Call Function	Legacy Code of Embedded System	VM Management	VM Scheduler	Synchronization of Application	Co-routine
python-on-a-chip [18]			✓					✓
Owl system [19]			✓	Partially				✓
eLua [20]			✓	Partially				✓
mruby [6]			✓	✓	✓	△		✓
mruby on TECS [5]			✓	✓	✓	✓	✓	✓
Proposed framework	✓							✓

Chapter 6

Conclusion

This paper has presented the mruby bytecode loader using Bluetooth in multi-VM on mruby on TECS. The proposed framework provides developers the efficient development without disconnecting an SD card and restarting an OS. Furthermore, RiteVM scheduler makes multitasking more easily than the current mruby on TECS. In the evaluation, experimental results of the mruby bytecode loader and proposed multitasking show their advantages. mruby bytecode loader using Bluetooth can improve the work efficiency. RiteVM scheduler has the effectiveness in terms of execution time and ease of use compared with singletasking and co-routine because of the low overhead.

The proposed framework is developed in component-base by TECS. The facilities such as the RiteVM, the RiteVM scheduler, and the Eventflag are implemented as components. Developers can easily add or remove the facilities as necessary, and also reuse them. Component-based development can increase productivity and decrease complexity.

In the future, the mruby bytecode loader using Bluetooth will be supported to handle multiple bytecodes and run the application in multi-VM. Moreover, the .cdl files for RiteVM and mruby-TECS bridge are generated automatically using a plugin, and developers can send a bytecode with ZMODEM protocol on the command line.

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