

# Modeling Principles and Modeling Foundations

Composition and Separation of Roles in a Robotics Ecosystem

RobMoSys - Composable Models and Software for Robotics Systems: Towards an EU Digital Industrial Platform for Robotics

Second RobMoSys Brokerage Day, Frankfurt  
August, 24th 2017



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# What is the aim of RobMoSys?



**RobMoSys**

## Composable Models and Software for Robotics Systems: Towards an EU Digital Industrial Platform for Robotics

- **RobMoSys** envisions an integrated approach built on top of the current code-centric robotic platforms, by applying model-driven methods and tools.
- **RobMoSys** will enable the management of the interfaces between different robotics-related domains in an efficient and systematic way according to each system's needs.
- **RobMoSys** aims to establish Quality-of-Service properties, enabling a composition-oriented approach while preserving modularity.
- **RobMoSys** will drive the non-competitive part of building a professional quality ecosystem by encouraging the community involvement.
- **RobMoSys** will elaborate many of the common robot functionalities based on broad involvement of the community via two Open Calls.

***Better models, as the basis for better tools and better software, which then allow to build better robotic systems***

*The project is open for constructive suggestions from the community, as long as "platform", "composability" and "model-tool-code" are first-class citizens of those suggestions*



# What is the aim of RobMoSys? Commercial User Stories...



**RobMoSys**

Reduction of development time



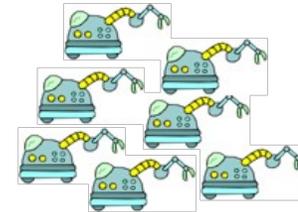
Reduced development costs



Shorter time to market



Larger production volumes possible



Certifyable systems



Predictable safety



Systems become more easily re-usable



Commoditisation of base components

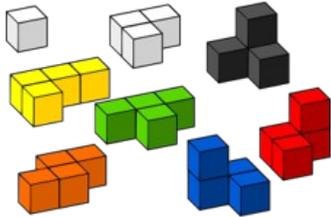


# What is the aim of RobMoSys? Technical User Stories...



RobMoSys

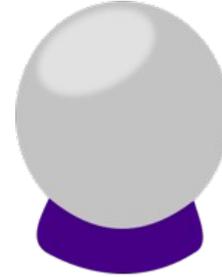
Composable components



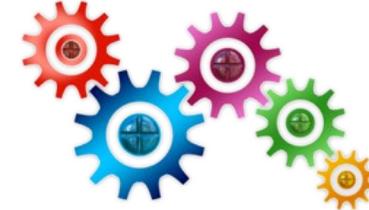
Traceable properties



Predictable properties



Reliable quality of service



Certifiable systems



Replaceable components



Re-usable



Commoditisation of base components



# Composition, Composability, Compositionality

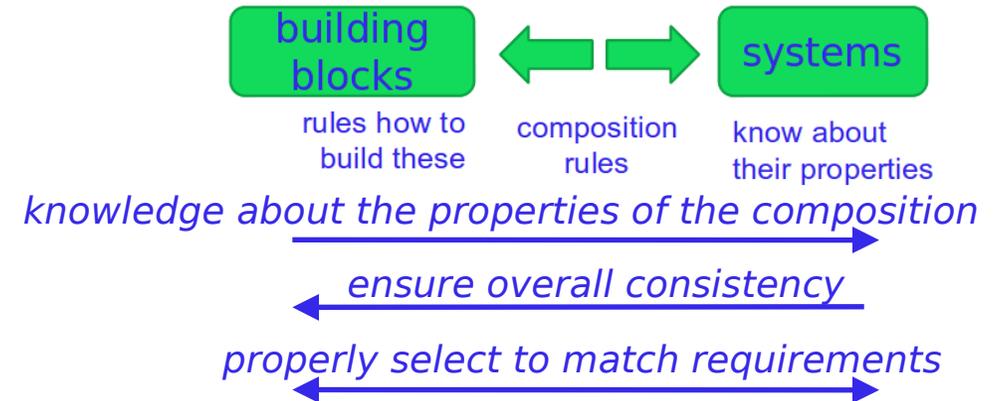
- **composability** is the ability to combine and recombine *as-is building blocks* into different systems for different purposes. It requires that properties of sub-systems are invariant („remain satisfied“) under composition.
- splittability is the „inverse“ relationship of composability.
- **compositionality** requires that the behavior of a system is predictable from its sub-systems and that of the composition „glue“.
- **system composition (activity)**: the activity of putting together a set of existing building blocks to match system needs with a focus on flexible (re-)combination.
- **system integration (activity)**: the activity that requires effort to combine components, requiring modifications or additional actions to make them work with others.



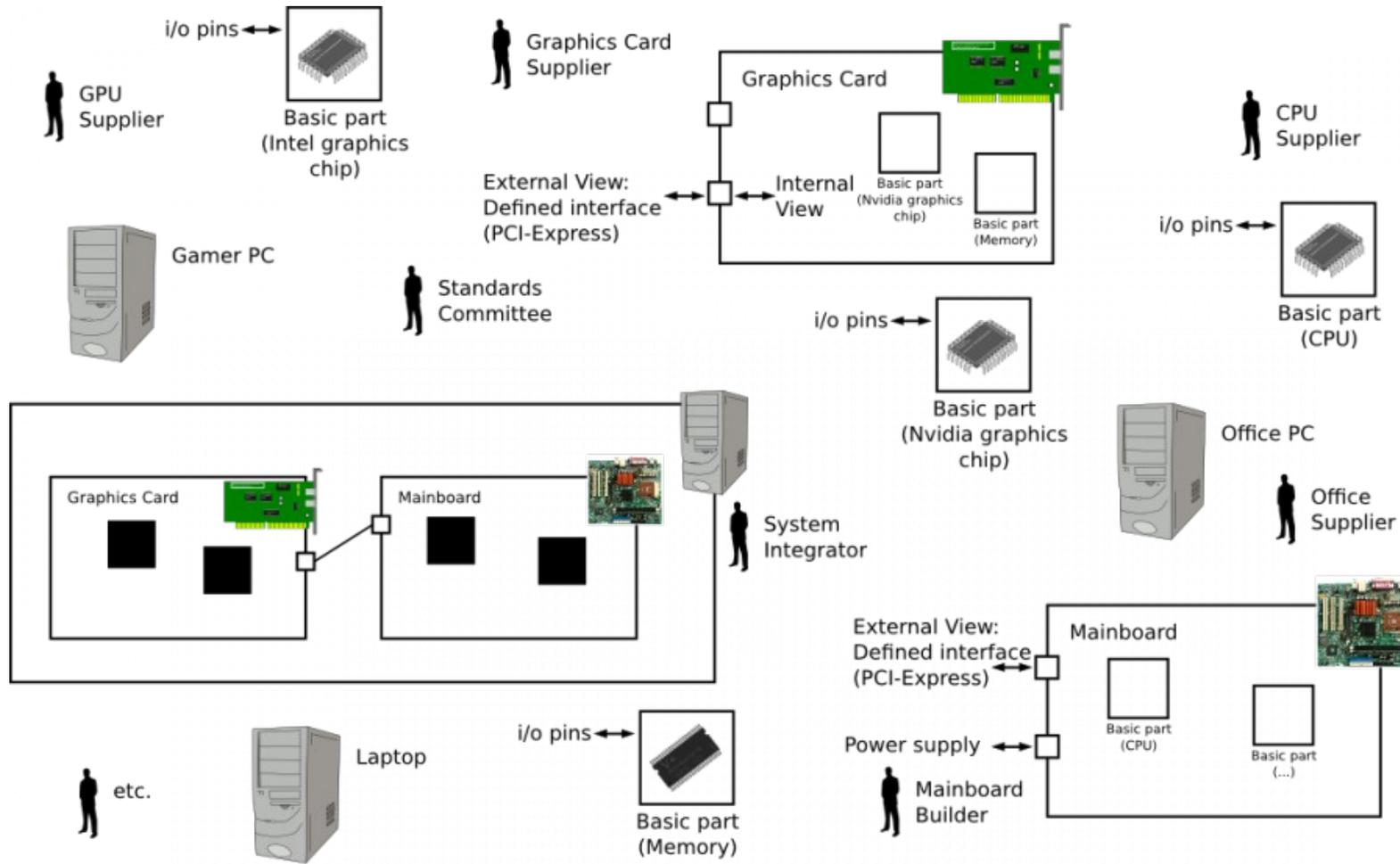
# System Composition in an Ecosystem

- RobMoSys adopts a **composition-oriented** approach to **system integration** that manages, maintains and assures **system-level properties**, while preserving **modularity** and independence of **existing robotics platforms** and code bases, yet can build on top of them.
- Towards an open and sustainable European robotics software **ecosystem** based on models and supporting **separation of roles**
- Apply **model-driven** techniques
- Manage **non-functional properties**
- From integration-centric to **composition-oriented** approaches
- Composition is about the **management** of the **interfaces** between different **roles** (participants in an ecosystem) in an efficient and systematic way.
- Composition is about guiding the roles via **superordinate composition-structures**.
- Composition is about explicating and managing **properties**.
- Composition is about the right **levels of abstraction and views** for roles.

*We operationalize architectural patterns and composition such that properties of system-of-systems become known in order to build trust in the system under development.*



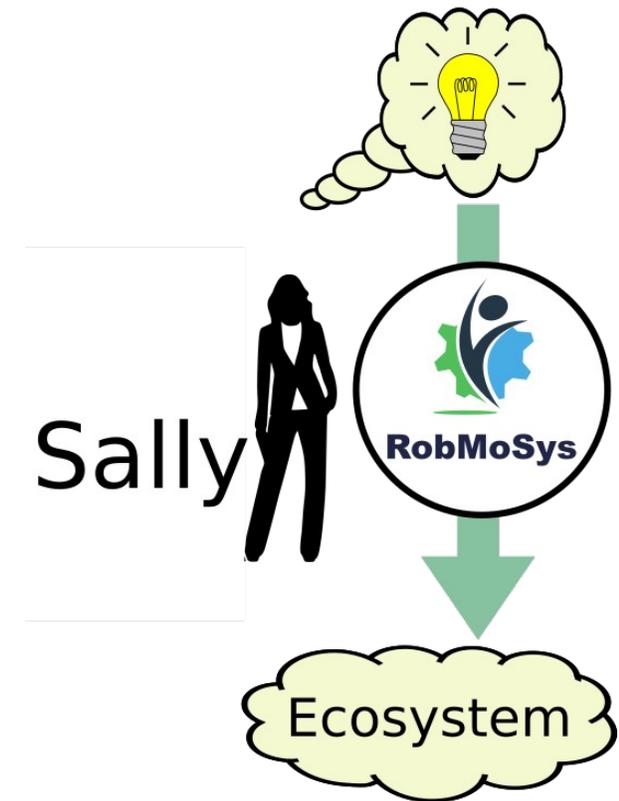
# Ecosystem, Separation of Roles, Composition: PC analogy



- building blocks with data sheets
- different stakeholders in different roles
- composition instead of integration

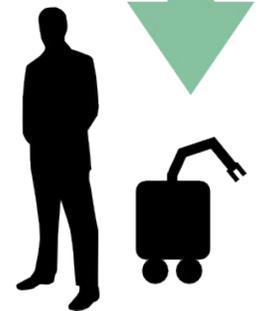
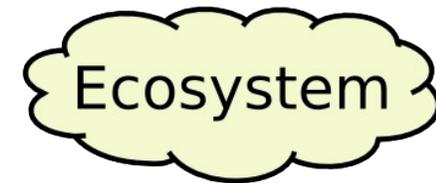
# Ecosystem Participant “Sally”

- Imagine you have **developed software** to localize a robot in the environment and you are interested in **making it available** in robotics.
- You are
  - a **SME**, specialized in a certain domain
  - e.g. a **component supplier** for robot navigation
- You want to
  - express your offer with pivotal features such that others can find your component (yellow pages)
  - ensure that others can use your component (composability+compositionality)
  - explicate non-functional properties of your component and define its variation points



# Ecosystem Participant “Max”

- Imagine you as an integrator are willing to develop an application which **needs a localization** module and you are interested in **integrating the third-party localization** software on your intralogistics mobile platform.
- You are
  - a **SME** that wants to **access robotics technology** and that wants to **build a robot** application
- You want
  - to **select components** from the market matching your expressed needs
  - your application to be **correct by construction**: you expect that building blocks seamlessly fit together
  - to view components as **grey-boxes** and use them “**as-is**”: adjust only at explicated variation points within modeled boundaries, do not modify source code



Max

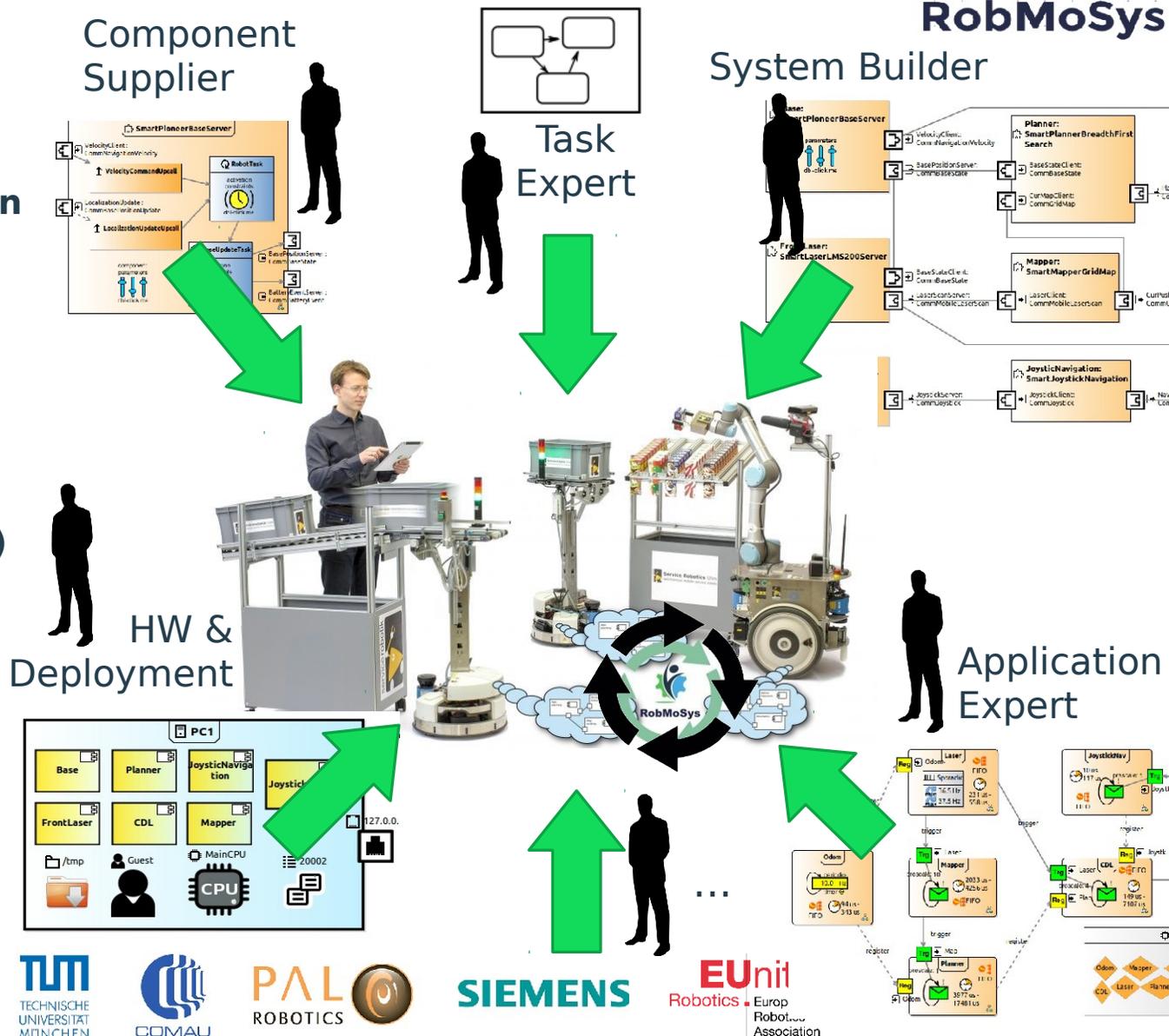


# Ecosystem, Separation of Roles, Composition



**RobMoSys**

- RobMoSys enables the composition of robotics applications with managed, assured and maintained system-level properties via model-driven techniques
- RobMoSys enables **communication of design intent, analysis of system design** before it is being built and **understanding of design change impacts**
- RobMoSys enables systems **correct by construction**
- RobMoSys supports management (design, assurance, traceability) of **(extra-functional) system properties** (e.g. resources, safety, QoS, accuracy, adequateness, etc.) in all development phases and at run-time:
  - deliver goods in time
  - trade-off energy consumption, speed, safety, etc.



# Technical User Stories and Benefits

See Wiki!



RobMoSys

- Composable commodities for robot navigation with traceable and assured properties
- Description of building blocks via model-based data sheets
- Replacement of components and again matching all the attached constraints (requirements, system, building blocks)
- Composition of components and managing all the dependencies, e.g. mounting a camera on a manipulator
- Quality of Service and management of resource shares
- Determinism when you change the processing platform, e.g. keep cause-effect-chains valid
- Free from hidden interference when you add further components to a system
- Management of non-functional properties and tool-supported trade-off
- Manage gap between design time assumptions and run time situation via e.g. sanity checks
- System analysis tools for what-if questions, trade-off analysis etc.
- Task modeling for task-oriented robot programming
- Safety and shift from fail-safe to safe-operational (not just “the following things cannot happen” but “the system only behaves like that”)
- ...



# RobMoSys: Roles and Views

The participants in the ecosystem take one or several **roles** to use and supply building blocks, e.g.

- Behavior Developer
- Component Supplier
- Function Developer
- Performance Designer
- Safety Engineer
- Service Designer
- System Architect
- System Builder

Each role uses dedicated **views** to work on models, the modeling twin and the building block, e.g.

- Communication Pattern View
- Component Development View
- Execution Container View
- Service Design View
- System Configuration View
- Performance View
- Deployment View
- Service Architecture View
- Service Fullfilment View

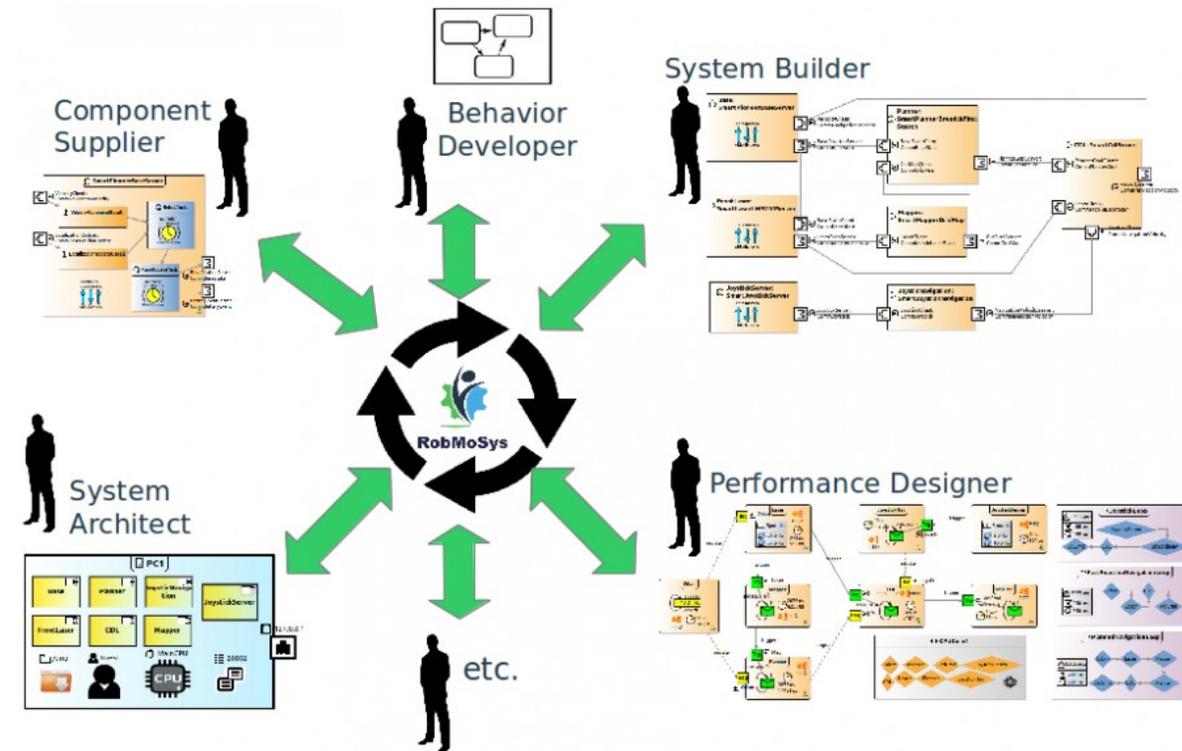
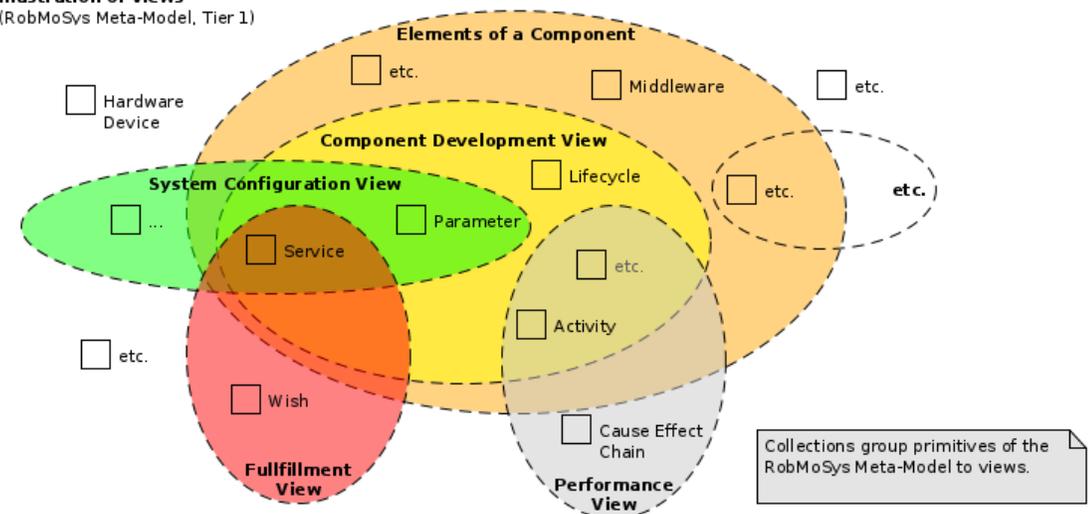


Illustration of views  
(RobMoSys Meta-Model, Tier 1)

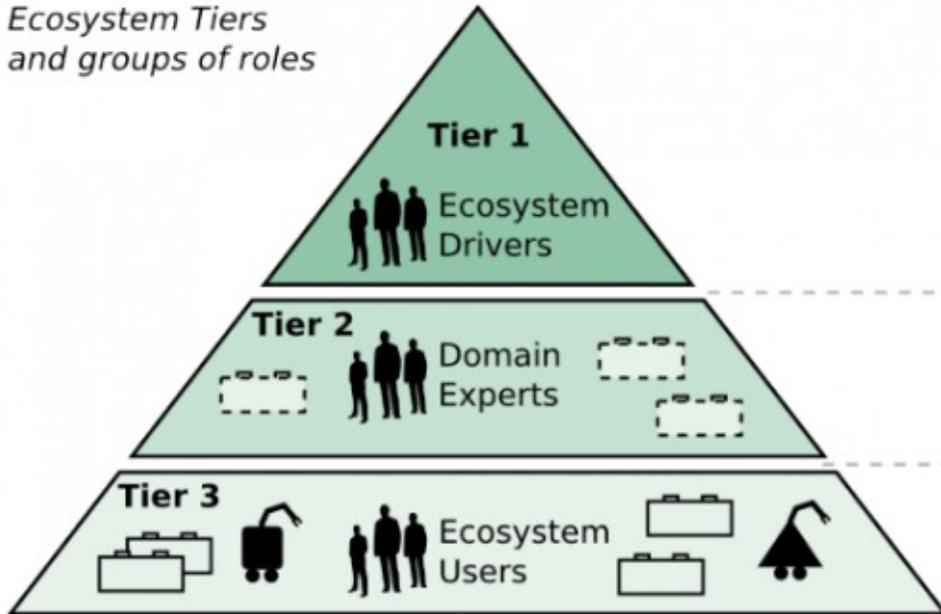


# RobMoSys Ecosystem Organization



RobMoSys

RobMoSys  
Ecosystem Tiers  
and groups of roles



Examples  
of the PC Analogy:



e.g. Semiconductor standards, computer architecture, USB, PCIe, modern use of ethernet, etc.

e.g. laptop PC, desktop PC, industry PC, ATX, ITX, Mini-ITX, VGA, HDMI, SATA, IDE, CPU socket, GPU socket, etc.

e.g. graphics card, CPU, TPM, Memory, power supply, etc.

**Examples of Robotics:**

**e.g. robotics architectural patterns and robotics composition structures (service-oriented software component model, robotics task models etc.)**

**e.g. Flexible Navigation Stack, Active Object Recognition, Motion Stack, Perception Stack etc.**

**e.g. robotics software components (Motion Planning, SLAM, Object Recognition), robotics functional libraries (MRPT, OpenCV, PCL), applications (Pilots, Logistics Fleet, Production Cell, Healthcare Servicerobot), etc.**



# Abstraction Levels and Concerns



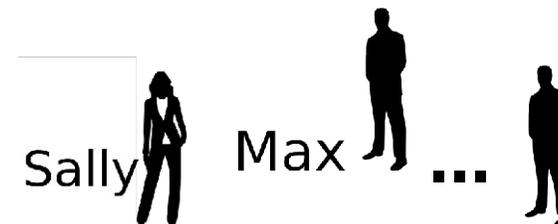
RobMoSys

		Concerns				
		Computation	Communication	Coordination	Configuration	
Levels	Mission	<i>serve as butler</i>				
	Task	<i>deliver coffee</i>				
	Skill	<i>grasp object with constraint</i>				
	Service	<i>move manipulator</i>				
	Function	<i>IK solver</i>	does	structures		translate into parameters
	Execution Container	<i>activity</i>	provides resources	provides resources	prov. Access to scheduler	
	Operating System / Middleware	<i>pthread, socket</i>	realizes	realizes		receives
	Hardware	<i>manipulator, laser scanner, CPU</i>	does	does	receives	receives

*cross-cutting concern (e.g. extra-functional property)*

## The Challenge:

- Adhere to separation of concerns while at the same time, package different concerns into structures such that these fit the views of the different roles.
- Manage interfaces between different roles and between different levels of abstractions
- Freedom of Choice versus Freedom from Choice

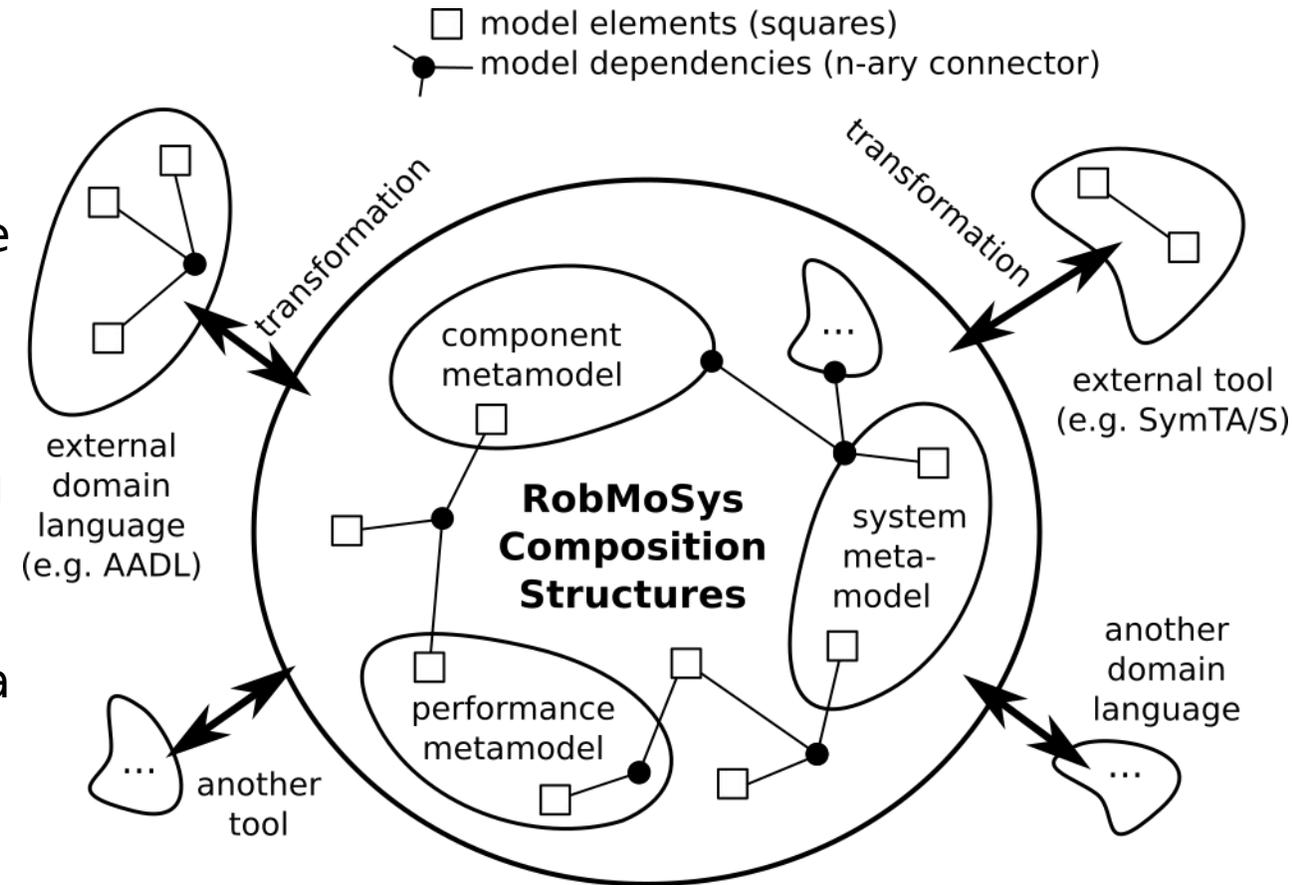


# How to build models for different parts and different aspects of a robotic system?



RobMoSys

- be able to correctly **compose models**
- be at least as detailed as needed for a certain level of confidence into the properties of the outcome (by simulation, by testing, by reasoning, ...)
- cannot be done easily as long as you do not adopt to a notion of Meta-Models
- Meta-Models allow to **transform** in a consistent way **between models** including constraints, tolerances etc.

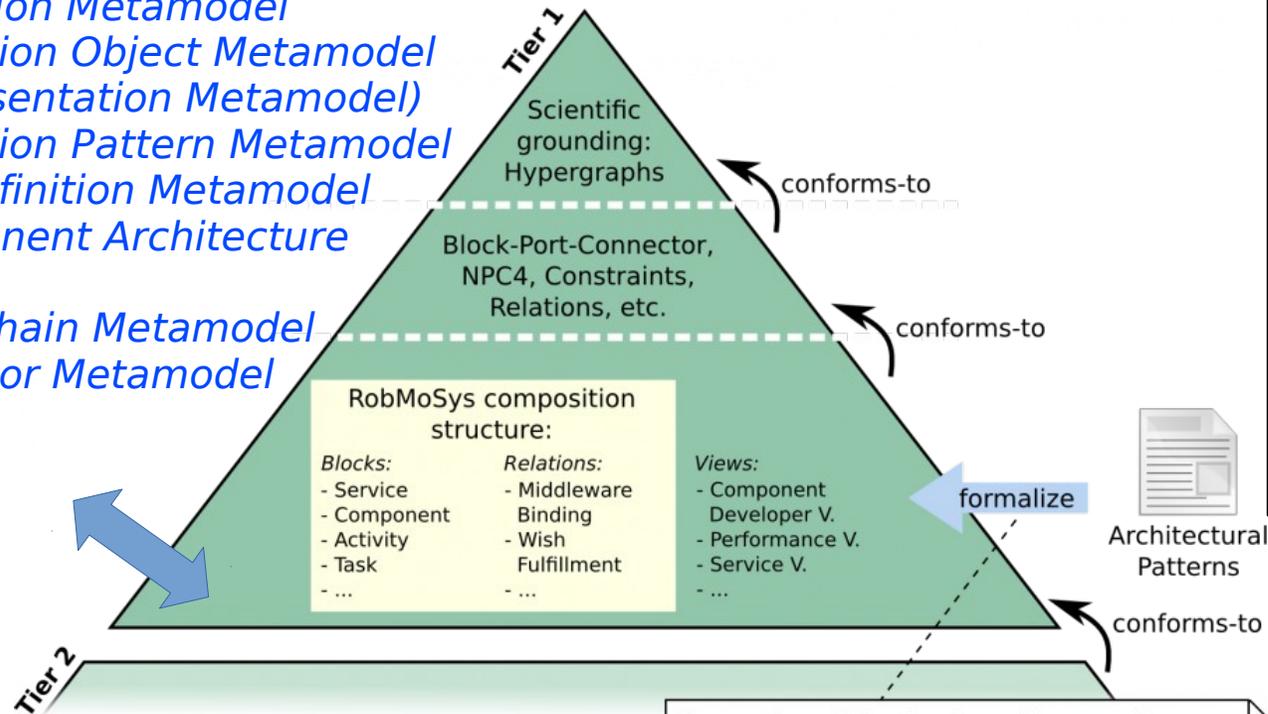




# Tier 1: Modeling Foundations

Tier 1 provides the **general structures for composition**. Three levels can be distinguished:

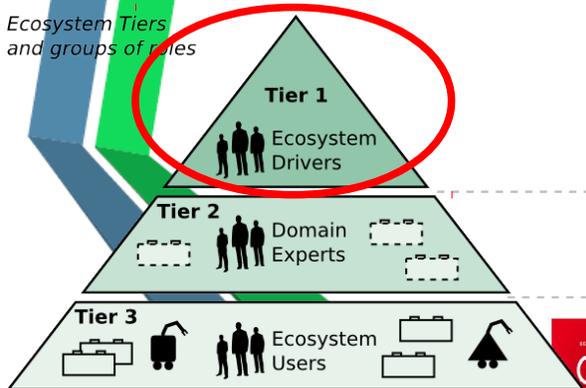
- *Service-Definition Metamodel*
  - *Communication Object Metamodel (Data Representation Metamodel)*
  - *Communication Pattern Metamodel*
- *Component Definition Metamodel*
- *System Component Architecture Metamodel*
- *Cause-Effect-Chain Metamodel*
- *Robotic Behavior Metamodel*
- ...



**Architectural Patterns:**

- levels / concerns
- composability
- separation of roles

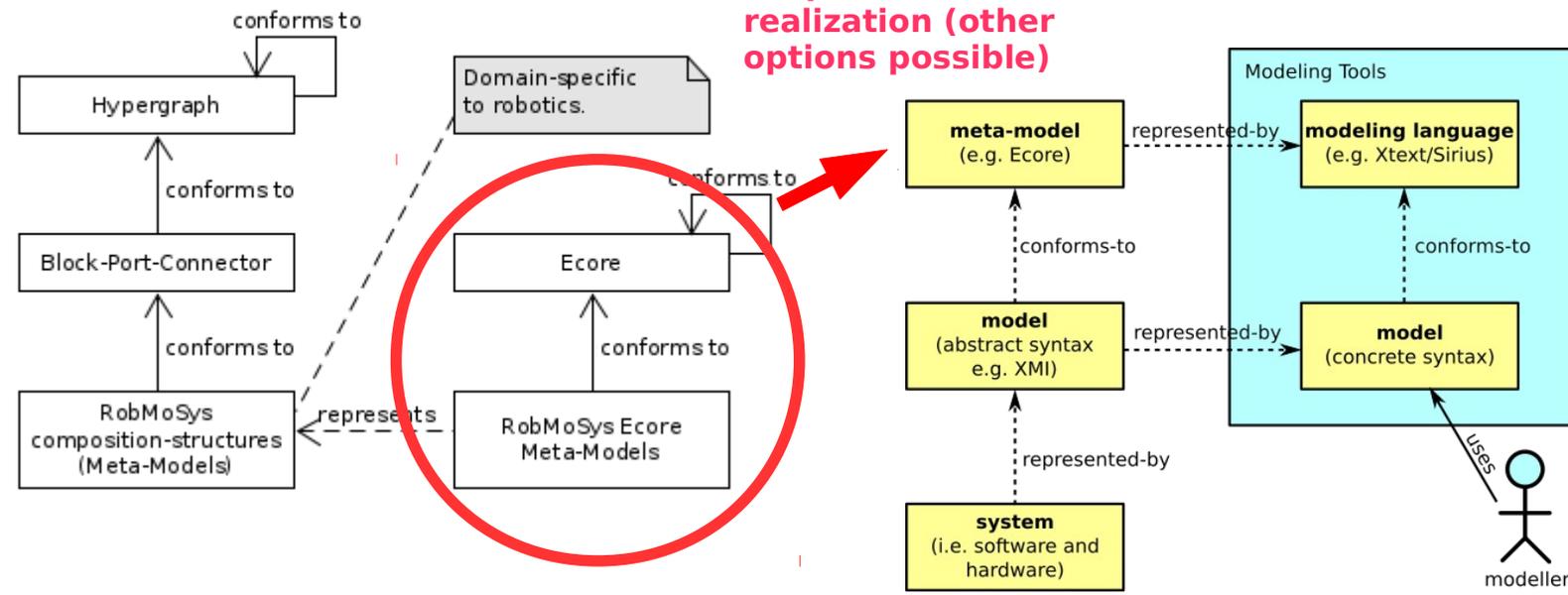
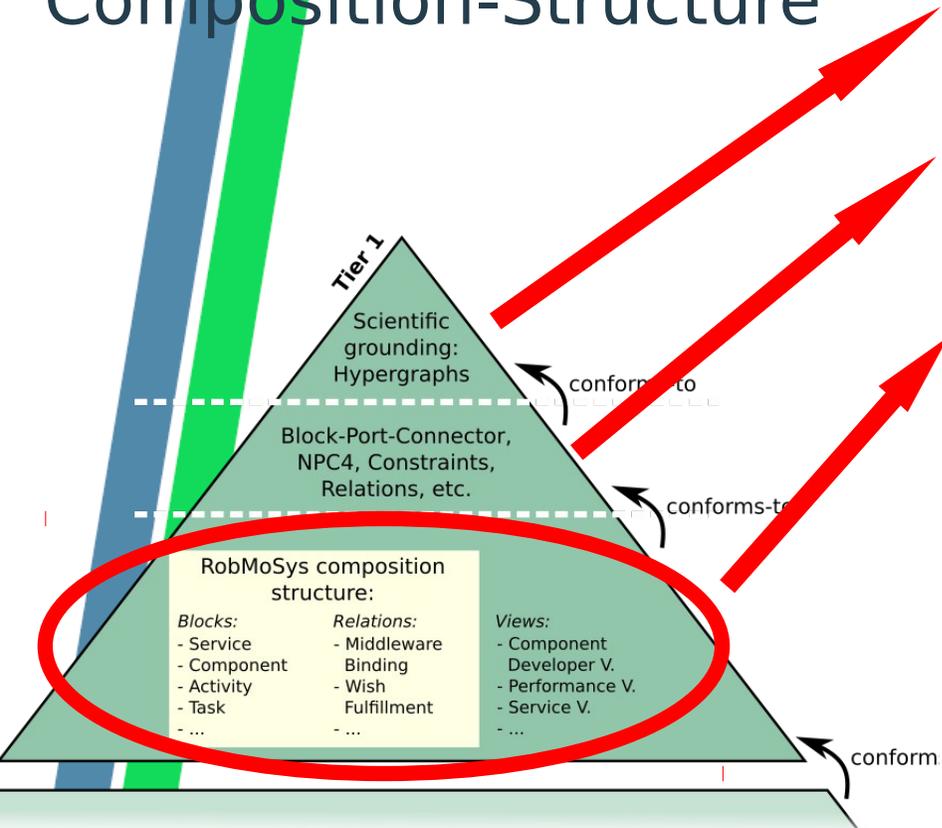
		Concerns			
		Computation	Communication	Coordination	Configuration
Mission					
Task					
Skill					
Service					
Function					
Execution Container					
Operating System / Middleware					
Hardware					



Human translates best practices and lessons learned as described in architectural patterns into formal models using the RobMoSys Block-Port-Connector meta-models to result in the RobMoSys composition-structure.



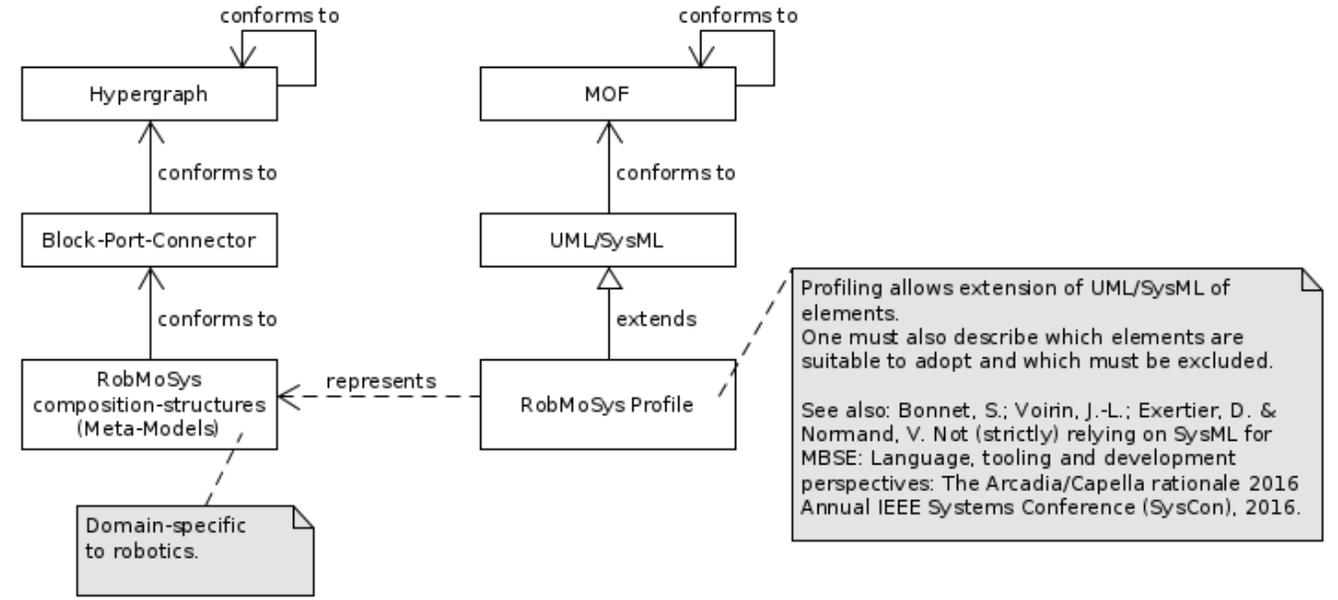
# Realization of RobMoSys Composition-Structure



Eclipse Ecore based realization (other options possible)

## Alternative 1

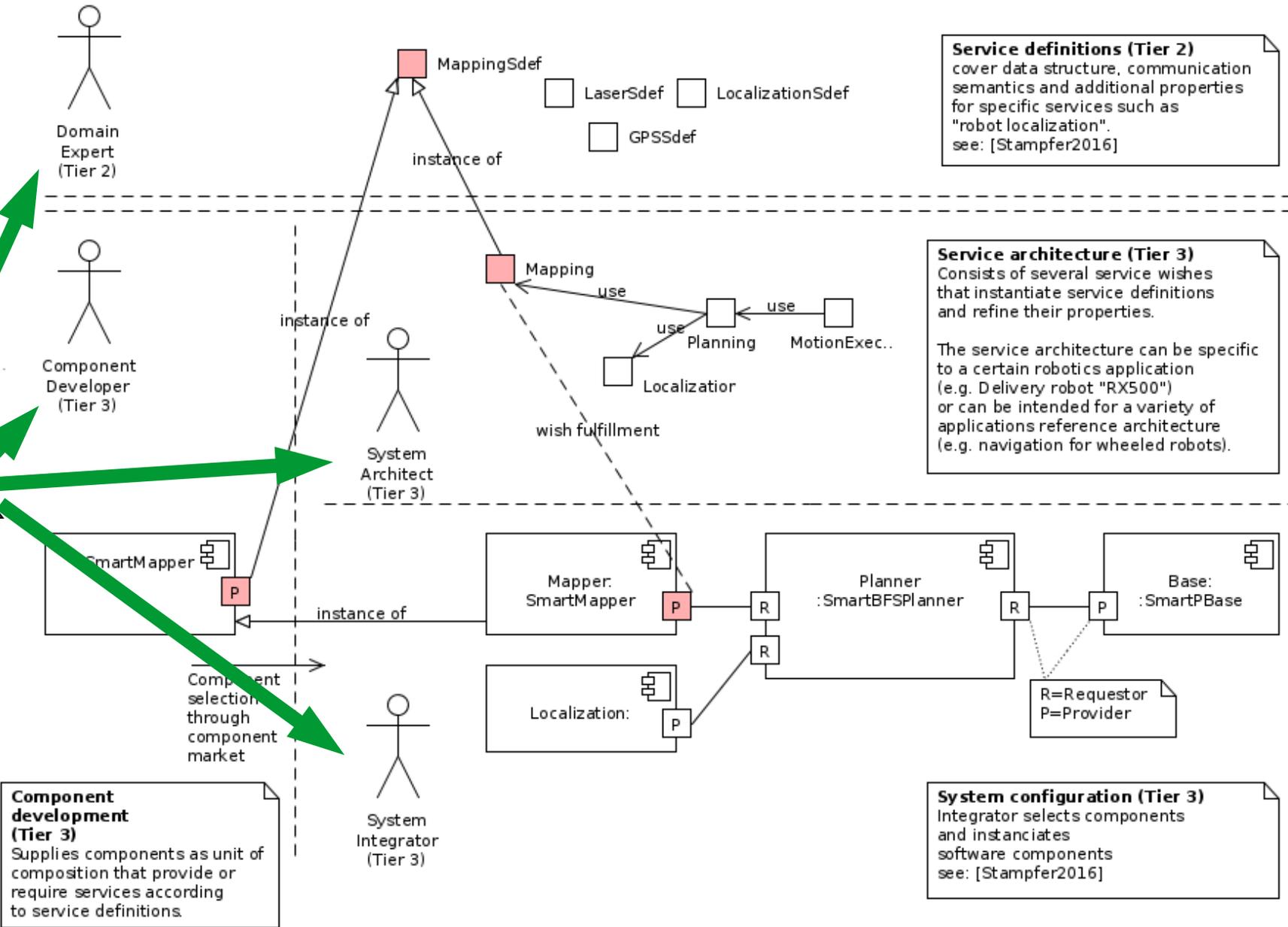
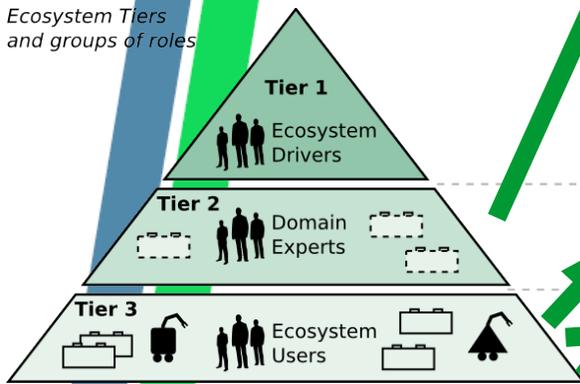
## Alternative 2



# Service-Based Composition Workflow

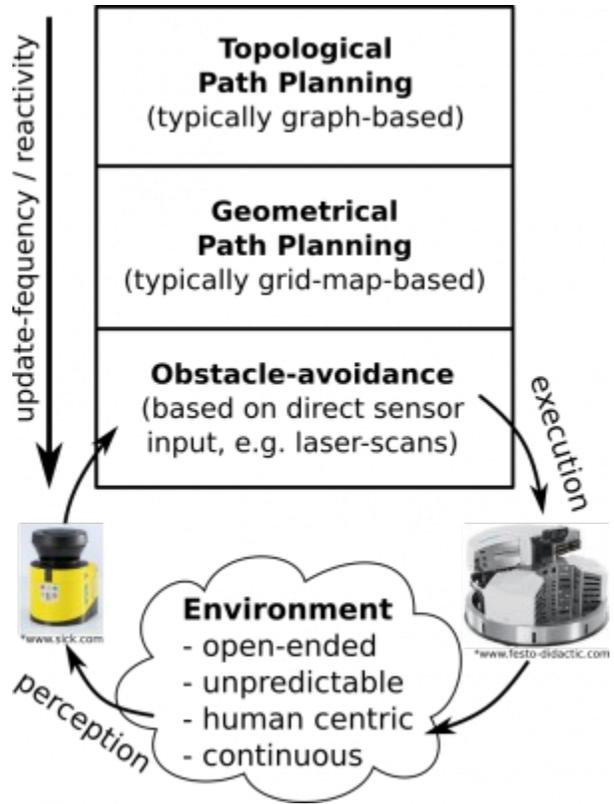
**Tier 2: Service Definition**  
**Tier 3: Service Realization / Usage**

Ecosystem Tiers and groups of roles

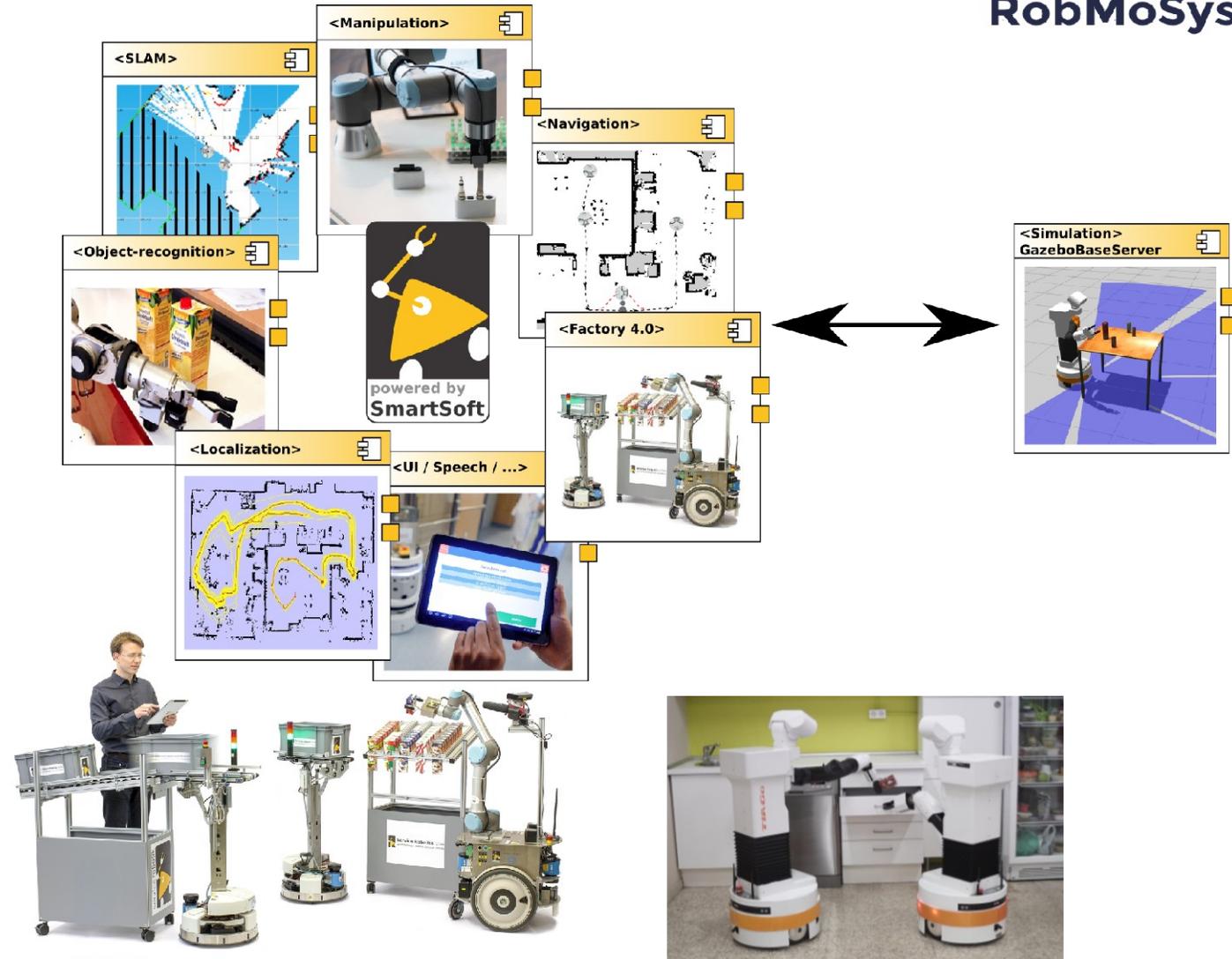


# Tier 2: Example of Domain Models

- Flexible Navigation Stack
- Active Object Recognition
- Motion Stack
- Perception Stack
- ...



# Tier 3: Existing Building Blocks and Scenarios





**RobMoSys**

# Pilots

Pilot 1: Goods Transport in a Company  
Intralogistics Industry 4.0 Robot Fleet (HSU)

Pilot 2: Mobile Manipulation for manufacturing applications on a product line  
Flexible Assembly Cell (Siemens)

Pilot 3: Mobile manipulation for assistive robotics in a domestic environment or in care institutions  
Assistive Mobile Manipulation (PAL)

Pilot 4: Modular Educational Robot (COMAU)

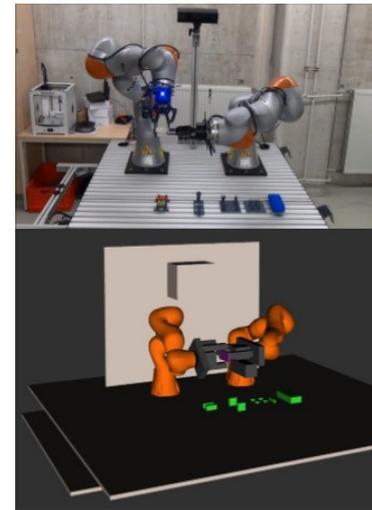
Pilot 5: Human Robot Collaboration for Assembly (CEA)  
and further pilots

*the project is open for constructive suggestions from the community for further pilots, as long as "platform", "composability" and "model-tool-code" are first-class citizens of those suggestions*

## Pilot 1



## Pilot 2



## Pilot 3



[www.robmosys.eu/wiki](http://www.robmosys.eu/wiki)