

Tutorial 3 — Using SysML

Overview

This tutorial will show you how to:

- 1. Add a new FMU in a SysML model
- 2. Generate a new multi-model configuration
- 3. Associate an FMU with a multi-model configuration
- 4. Execute a co-simulation using the new multi-model configuration

Requirements

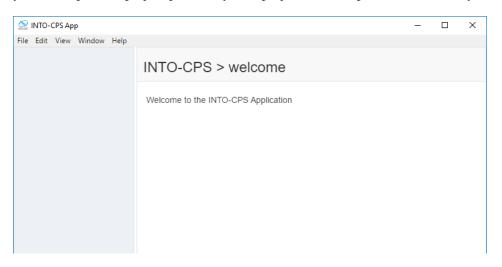
This tutorial requires the following tools from the INTO-CPS tool chain to be installed:

- INTO-CPS Application
- COE (Co-simulation Orchestration Engine) accessible through the INTO-CPS App Download Manager
- Modelio accessible through the INTO-CPS App Download Manager
 - If you use linux please make sure your installation meets the dependencies listed in: https://www.modelio.org/downloads-links/requirements.html
 - For debian based distributions the following command may be usefull:
 dpkg-query -l libatk1.0-0 libc6 libcairo2 libgtk-3-0 libglib2.0-0 libwebkitgtk-1.0-0 libxtst6 libstdc++6

You may have been provided with tools on a USB drive at your training session. Otherwise follow Tutorial 0 with the guidelines to install the INTO-CPS Application. Tools can be downloaded from there through *Window* > *Show Download Manager* to your *into-cps-projects* install downloads directory. Please ask if you are unsure.

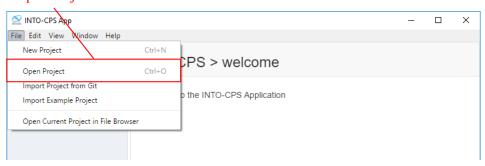
1 Opening a Project

Step 1. Launch the *INTO-CPS Application*. On first loading, it will look like the screenshot below. If you have opened a project previously, that project will be opened automatically.

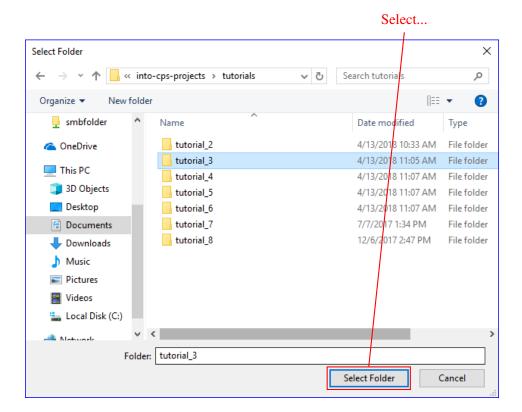


Step 2. To open a project, select *File > Open Project*.

Open Project



Step 3. Set the *Project root path* to the location of *Tutorials/tutorials_3*. You can browse using the *Select Folder* button.



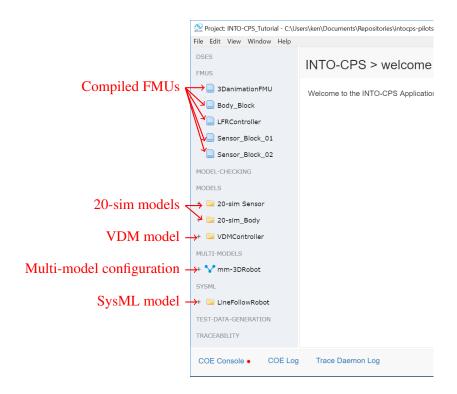
Step 4. Once the project is opened, you will see that project browser on the left of the INTO-CPS Application window is now populated. The entries in the project browser correspond to folders and files in the *Tutorials/tutorials_3* folder. These are:

FMUs Compiled FMUs (with file extension .fmu) that are used in co-simulation.

Models Source models used to generate the FMUs. The icon of each entry shows which tool created the model. In this case Overture and 20-sim.

Multi-models Used to configure co-simulations, including which FMUs are used and other co-simulation settings.

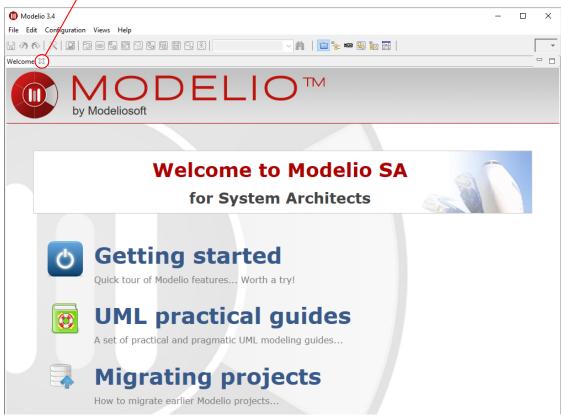
SysML Architectural models that are used to create model and multi-model descriptions.



2 Edit Architecture

- Step 5. In case *Modelio* does not install automatically after download you need to navigate to the into-cps-projects/install_downloads directory, and run the modelio executable.
- Step 6. Launch *Modelio*. On first loading, you may have to close the *Welcome* screen (you can bring it back with *Help > Welcome* if you need)

Close Welcome screen

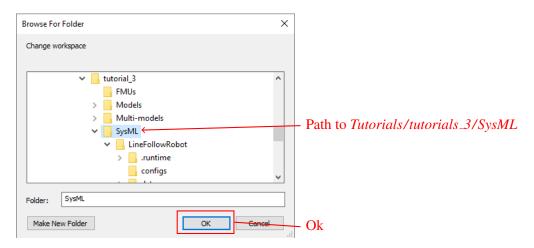


Step 7. A workspace must be chosen, select *File > Switch Workspace*.

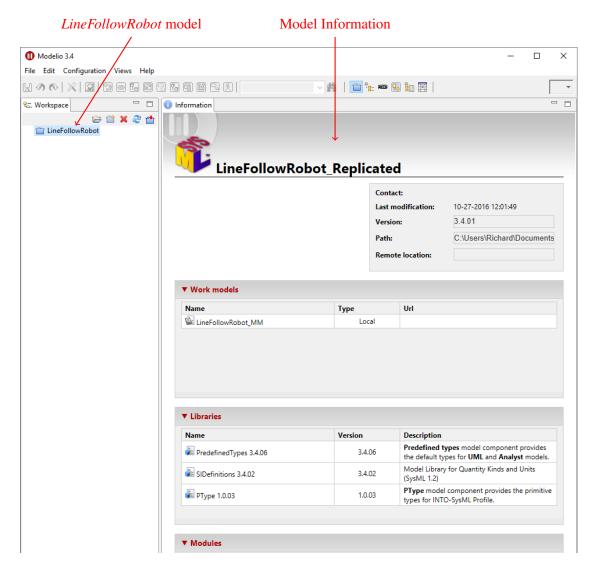
Switch Workspace



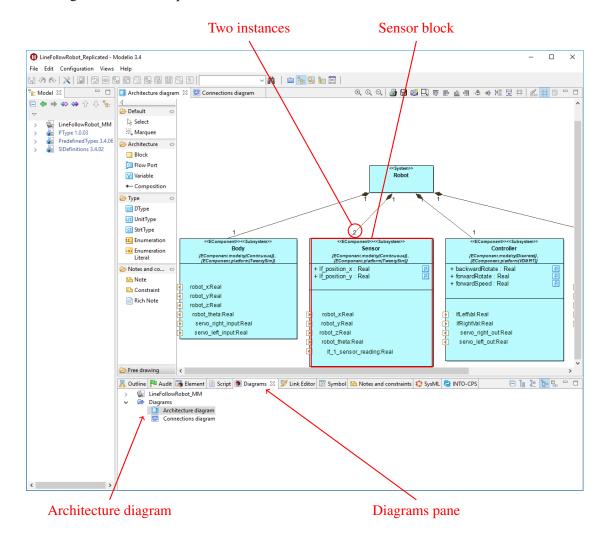
Step 8. Set the Workspace to the location of Tutorials/tutorials_3/SysML and click Ok.



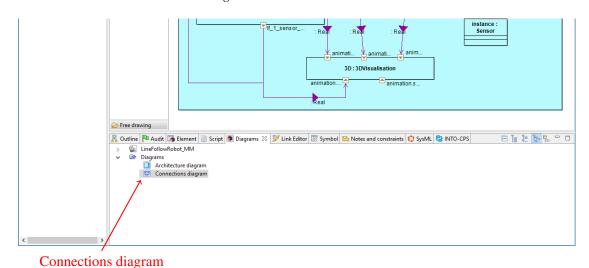
Step 9. Left-click on the *LineFollowRobot* model once on the left to see details of the model. Double-click the *LineFollowRobot* model to open the model.



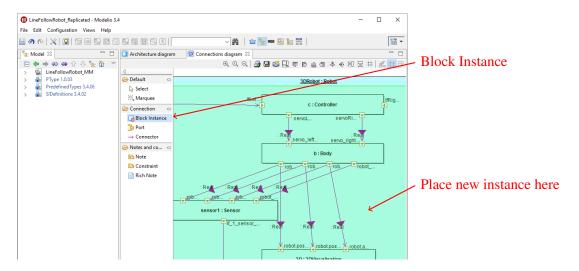
Step 10. In the *Diagrams* pane, expand the *Diagrams* folder and double click the *Architecture Diagram*. The diagram below will open. Notice there are two instances of the Sensor model.



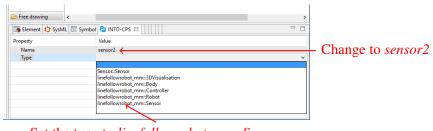
Step 11. Double click the Connections Diagram



Step 12. To add a new Sensor, select *Block Instance* from the palette menu and add the new instance to the 3DRobot – simply click inside the 3DRobot, as indicated below.

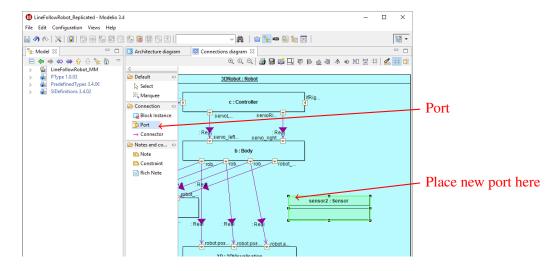


Step 13. In the *INTO-CPS* panel, change the name of the new instance to 'sensor2' and set the type to be 'linefollowrobot_mm::Sensor'.

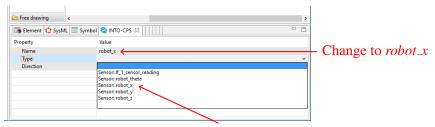


Set the type to linefollowrobot_mm::Sensor

Step 14. The next step is to add ports to the sensor instance. Select *Port* from the palette menu and add the new port to the sensor2.



Step 15. Select the new port and in the *INTO-CPS* panel change the name to 'robot_x' and type to be 'Sensor::robot_x'.



Set the type to *Sensor::robot_x*

Step 16. Repeat steps 14 and 15 to add four more ports:

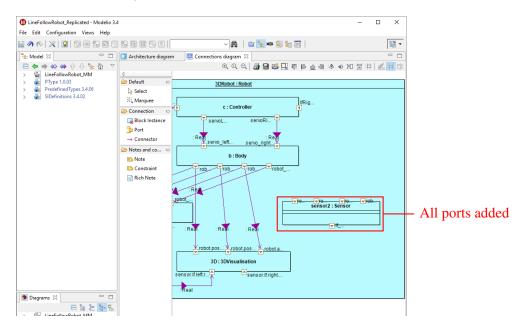
• Name: 'robot_y'; Type: 'Sensor::robot_y'.

• Name: 'robot_z'; Type: 'Sensor::robot_z'.

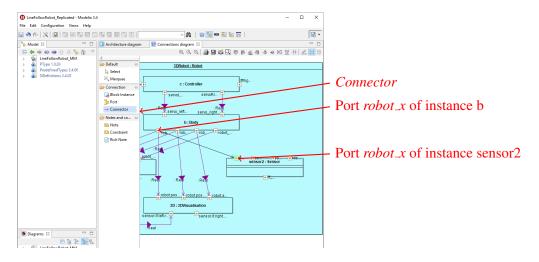
• Name: 'robot_theta'; Type: 'Sensor::robot_theta'.

• Name: 'lf_1_sensor_reading'; Type: 'Sensor::lf_1_sensor_reading'.

The connections diagram should look like that below:



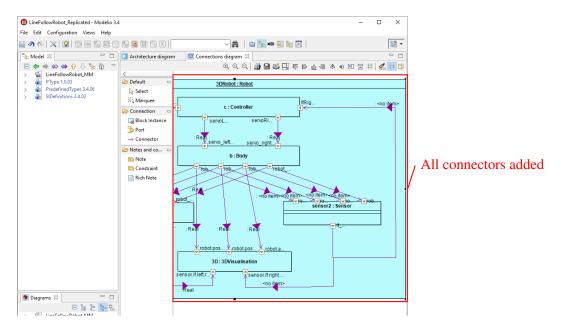
Step 17. The next step is to add connections between the different models of the robot. Select *Connector* from the palette menu and connect the *robot_x* port of the *body* component to the *robot_x* port of the new *sensor2* component



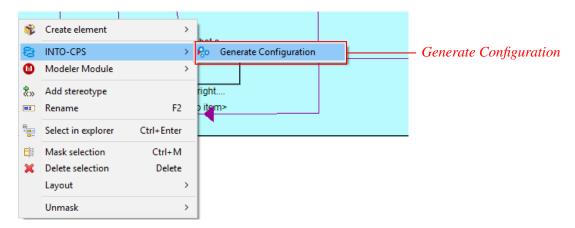
Step 18. Repeat step 17 to add five more connectors:

- 'body.robot_y' to 'sensor2.robot_y'.
- 'body.robot_z' to 'sensor2.robot_z'.
- 'body.robot_theta' to 'sensor2.robot_theta'.
- 'sensor2.lf_1_sensor_reading' to 'controller.lfRightVal'.
- 'sensor2.lf_1_sensor_reading' to '3D.animation.sensor.lf.right'.

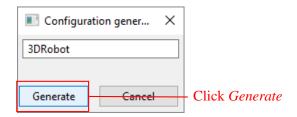
The connections diagram should look like that below:



Step 19. To export this new configuration, right click on the 3DRobot instance and select *INTO-CPS* > *Generate Configuration. If nothing happens, closing and re-opening Modelio often helps.*



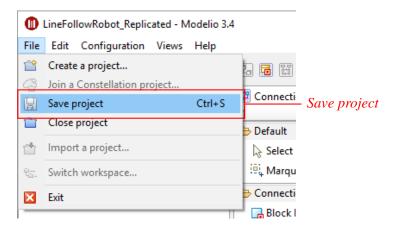
Step 20. Click *Generate*. If this seems to be unresponsive, then click *Cancel*, save the model, close and reopen *Modelio* and try again.



Step 21. Click OK.



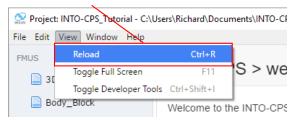
Step 22. Finally, save the SysML model.



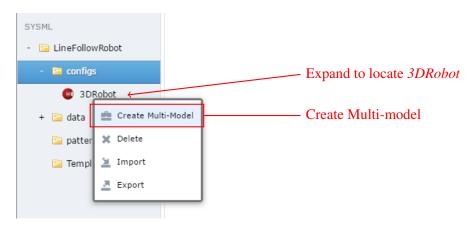
3 Configuring a Multi-model

Step 23. Return to the *INTO-CPS Application* and reload the view by selecting *View > Reload*.

Click Reload



Step 24. In the SysML entry of the project browser, expand the *LineFollowRobot* and then *config* folders. There should be a *3DRobot* icon (as in the Figure below). Right click on *3DRobot*, select *Create Multi-Model*. You can just accept the default name in the prompt that appears.

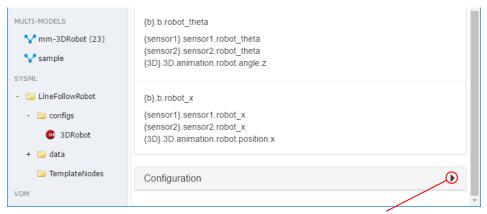


Step 25. A new multi-model configuration has been created and is shown in the multi-model entry of the project browser. Double-click on the new multi-model to open it.

Double-click to open

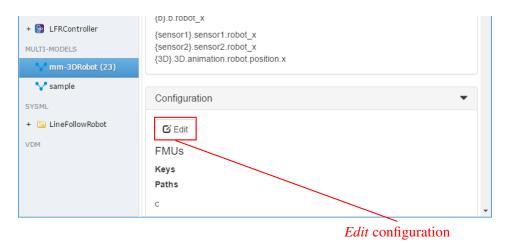


Step 26. We need to associate FMUs with this multi-model and set its parameters. Expand the *Configu- ration* section of the multi-model by clicking on the triangle.

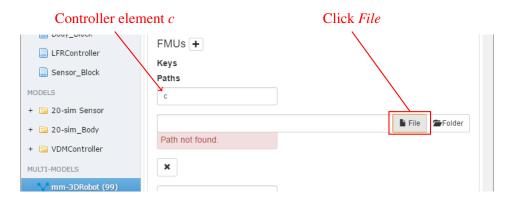


Expand Configuration

Step 27. Scroll down and click Edit.

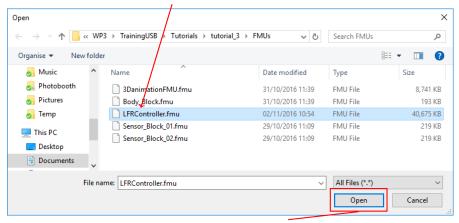


Step 28. In the FMUs section, next to the Controller element c, click the File button.



Step 29. A file browser window will open and show five FMUs (if the file browser does not show the FMUs, navigate to *tutorials_3/FMUs*). Select *LFRController.fmu* and click *Open*.

1. Locate and select LFRController.fmu



2. Click Open

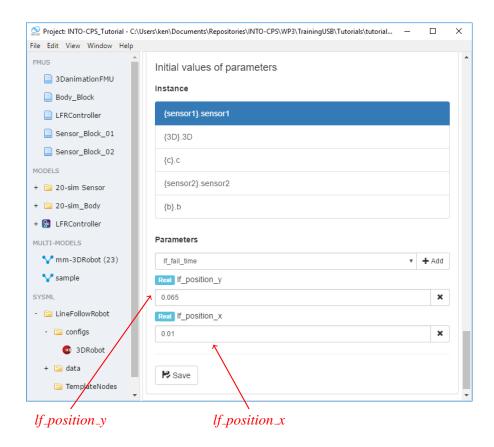
Step 30. The LFRController has been added. Repeat this for the remaining elements:

• b : Body_Block.fmu

3D: 3DanimationFMU.fmu
sensor1: Sensor_Block_01.fmu
sensor2: Sensor_Block_02.fmu

Users\ken\Documents\Repositories\INTO-CPS\WP3\TrainingUSB\Tutorials\tutorial... — LFRController.fmu File Folder × Body Block.fmu File Folder All FMUs added × Sensor_Block_02.fmu File Folder × 3DanimationFMU.fmu **l** File **/** Folder sensor1 File Folder Sensor Block 01.fmu

- Step 31. Next the sensor positions must be defined. Scroll down to the *Initial values of parameters section*, and click {sensor1}.sensor1. In the Parameters section, enter the following values:
 - $lf_position_y = 0.065$
 - $lf_position_x = 0.01$



Step 32. Repeat the previous step for the second sensor – {sensor2}.sensor2 with the following values:

- $lf_position_x = -0.01$
- $lf_{-position_{-y}} = 0.065$

Step 33. Save the Configuration.



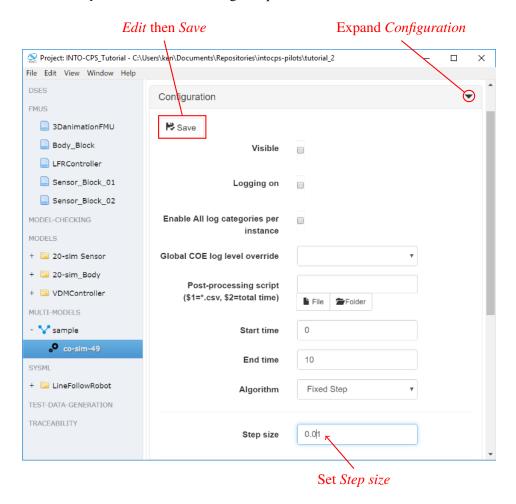
Save configuration

Step 34. The multi-model configuration is complete. Right-click on the multi-model configuration and select *Create Co-simulation Configuration*.



Create Co-Simulation Configuration

Step 35. Set the *Step size* to 0.01. Don't forget to press *Edit* then *Save*.

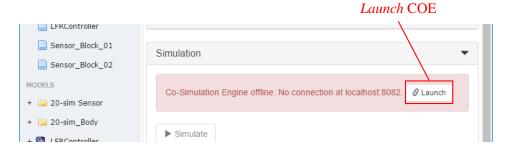


Step 36. Check *lf_1_sensor_reading* from {*sensor1*}.*sensor1* and {*sensor2*}.*sensor2* to see the sensor values appear in the *Live Plotting Configuration*.

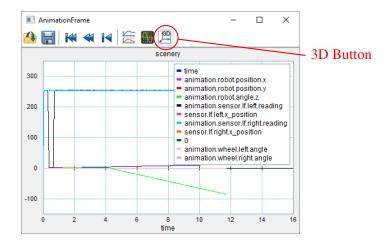


4 Running a Co-simulation

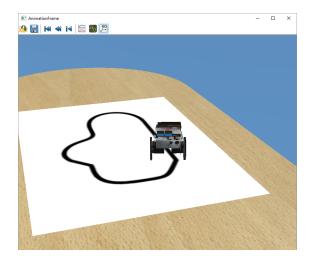
Step 37. Launch the COE if necessary (see *Tutorial 1 — First Co-simulation* for a reminder if needed).



Step 38. When the COE is running (see *Tutorial 1* for more details if you need a reminder), click the *Simulate* button. After a few seconds, a Java window called *Animation Frame* will appear like the one below. It shows a plot of variables from the co-simulation. You can click the *3D* button to see the 3D visualisation of the robot.



Step 39. A 3D model of the line following robot will appear. This view may be changed by clicking and dragging the mouse (note this is currently quite sensitive, so don't make quick movements). When the simulation has finished, this window will close. If everything went well, the robot should follow the line.



5 Additional Exercises

When this tutorial is complete, either move onto Tutorial 4, or try to answer the following questions:

- 1. Is there a relation between this tutorial and tutorial 2?
- 2. What are the advantages on using SysML and its accompanying tool Modelio?