Towards system development processes for robotic applications

Anonymous Author(s)

ABSTRACT

The number of robotic applications that are being developed is increasing exponentially both in industry and academia. However, those applications do not have common system development process, what leads to the necessity of starting projects from scratch for most of the robot developers. Thus, developing an application of robotics is always a time consuming task.

In this PhD project, we aim to produce a set of processes and architectural models and methods to be used by developers in order to improve reusability and modularity in robotic applications and also reducing the time wasting tasks. In order to validate our results we make use of a set of service robots that will be employed for different case studies.

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1 INTRODUCTION

Service robots are invading human lives. They are increasingly used in environments such as houses, airports, hospitals, and offices for performing navigation, transportation, and manipulation tasks. The World Robotic Survey [5] estimated 35 million indoor service robots to be sold by 2018, accumulating a sales value of $12 billion since 2015. The global sales of household and personal robots is expected to grow by 23.5% per year [9]. This increase is accompanied with huge progress in robot technology, especially in image processing, planning, control, and collaboration. Software engineering is key to sustaining this new technology.

A robot typically performs specialized tasks; however, some tasks are highly complex and require a team of robots, whose capabilities (e.g., perception, manipulation, and actuation) are coordinated and supervised. Such teams also need to adapt to changes, such as of the environment, of the desired tasks, or of the robot (e.g., hardware failures). These demands drive the complexity of robot control software relying on appropriate software architectures. To tackle this complexity, we need to rethink design processes [7] by properly managing system integration and raising the abstraction levels, addressing qualities like evolvability [8], configurability [4], scalability, power consumption, and dependability.

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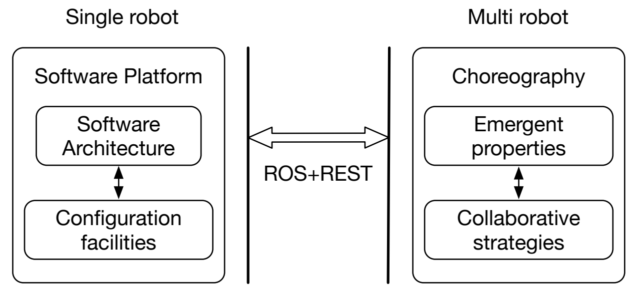

Figure 1: Overview of this PhD project.

The PhD project presented in this paper is involved in the Co4Robots [1] European project. Being part of this project allow us not only to formulate but also to validate our research questions in real-world scenarios.

Figure 1 depicts an overview of the work being developed for this project. There is an evident difference between two different approaches in robotic practices, that is when the robotic application puts to work an unique robot or a team of them. This division also splits the research schedule of this project in terms of time, as explained in the following. The “Single robot" subdivision of the overview represents the work already achieved and work in progress to be achieved in the near future. This subdivision contains the block of the *Software Architecture*, which is at the same time contained in the *Software Platform* block. The last mentioned block represents an additional layer for integrating the tools developed by researchers. Our platform must also be able to be customized by means of *configuration facilities*, which provide the required tools for configuring the basic platform both at design and run-time.

On the other hand, the future work that will be tackled once the single robot contents are already addresses is group in the subdivision of “Multi robot". The main expected outcome of this subdivision is to perform the choreography of a deployed team of potentially heterogeneous robots. In order to do so, issues as *Emergent properties* [2, 3] and selecting the most suitable *Collaborative strategy* Sergio ►*needed citation*◄ must be addressed.

Research Questions. In this project we divide robot applications between single-robot and multi-robot approaches. For this reason, we state the following research questions:

- RQ1 Which are the software engineering practices for single and multi-robotic systems?
- RQ2 Which are the applicable strategies to manage an heterogeneous robotic application?

Contributions. Our contributions are listed in the following:

(1) Definition of a software architecture able to support a robotic team
(2) Validation of the architecture in a real-world scenario

(3) Implementation of a software platform where all the algorithms and tools developed can be plugged in
(4) Definition of configuration mechanisms to enable *start-up configuration* and *run-time configuration*
(5) Integration of an approach based on ROS+REST for the internal communication between robots
(6) Development of the algorithms in charge of perform the choreography, based on:
    (a) Response to emergent properties
    (b) Selection of collaborative strategies

Organization. In Section ??, we introduce different works with a similar scope and position our research. Section 2 describes the research approach of the current work. Then, the next sections present the current state of our work in Section 3, future work and planned directions in Section 4 and it concludes with Section ?? with final remarks.

2 RESEARCH APPROACH

In this project we are working from the academic point of view research-wise but we are also working closely with the industry. As stated before, the work developed for this PhD project is embedded in the Co4Robots European project. The main goal of this project is to deploy a robotic application in a “domestic" environment such as hospitals, hotels, airports, etc. These robotic applications must be able to accomplish complex missions with a systematic, real-time, decentralized methodology. Furthermore, a robotic application could be composed by a team of potentially heterogeneous robots. The aforementioned environments will be considered as dynamic and will also count with the presence of human beings. For this reason, the robots must have integrated a set of perceptual capabilities that enables them to localize themselves and estimate the state of their highly dynamic environment in the presence of strong interactions and in a collaborative manner. Robots must not only interact between them, but also with human beings.

In order to validate the code and artifacts developed for Co4Robots, the committee defined a set of study cases for the project proposal. Our framework builds upon various cases of base interactions between agent pairs of different types. The considered inter-agent interactions are:

Case A physical guidance by a human for the transportation of an object carried by a robot;
Case B collaborative grasping and manipulation of an object by two agents;
Case C collaborating mobile platform and stationary manipulator to facilitate loading and unloading tasks onto the mobile platform; and
Case D information exchange between a human giving orders and a robotic agent.

On the other hand, it is important to decouple the research made just for the project and the one intended for the whole PhD. While the single-robot part can be more driven by the Co4Robots goal, the second part is expected to reach far beyond results than the intended for the project. For example, the multi-robot choreography for Co4Robots is limited by its study cases to two robots. However, for our own research we plan to manage a team of them acting under some defined collaborative strategies and adapting to emergent properties.

3 CURRENT STATUS

Currently, our main focus lays on the RQ1, learning, defining and differencing between software engineering practices regarding single-robot and multi-robot systems. Our software architecture, Self-adaptive dEcentralised Robotic Architecture (SERA) is already defined. As its name indicates, it supports a real-time decentralized robot coordination to accomplish missions with teams of robots. Furthermore, it is self-adaptive, responding to different changes by computing new strategies to achieve the desired goals. SERA was already tested during an Integration Meeting of the project, where it demonstrate that can support the performance of a robot achieving different complex missions —i.e. collaborative transportation with an human being, autonomous driving in a dynamic environment.

The aforementioned architecture is three layers architecture that is strongly influenced by the well-known work of Kramer and Magee [6]. It has the same structure, but, as depicted in Figure 2, we also added a new item that works as a central station. It is important to remark that the aim of our project is to build a system that can be easily used by not technical users, so we had to define a way for them to command the missions to the robotic team. The central station is just used during design-time in order to allocate a graphical interface to be used by a final user.

On the other hand, SERA follows the component-based style, so the main robotic functionalities are encapsulated in different modules or "components". All this components are developed abstracting the communication capabilities since we rely on the interfaces defined in the architecture. It not only significantly reduces the complexity of the code but also triggers the modularity of our system making possible exchanging the components that conform our architecture.

Since the components of our architecture are exchangeable our next short-term goal is to define configuration facilities that can be applied to our system depicted in the architecture. It will allow to our applications to support two thing:

(1) Being customizable at design-time, so we can configure its components based on the requirements of our context (i.e. hardware installed in each robot, environment where they will be deployed, etc.)
(2) To self-adapt or self-configure at run time, so each robot can apply changes in its configuration based on emergent events of the environment or failures of their system.

In order to do so we will implement pluginlib [1], a package that uses the ROS build infrastructure and provides tools for writing and dynamically loading plugins.

Finally, in order to communicate each robot with its teammates we implemented an approach based on ROS+REST. So, using a suitable component that works as an interface we are able to send messages in form of services between robots. In this way, each robot has an instance of ROS running in their own local environment so we can deploy a whole team of robots avoiding a central master node and the problems related with this approach (i.e. bottleneck

[1] http://wiki.ros.org/pluginlib

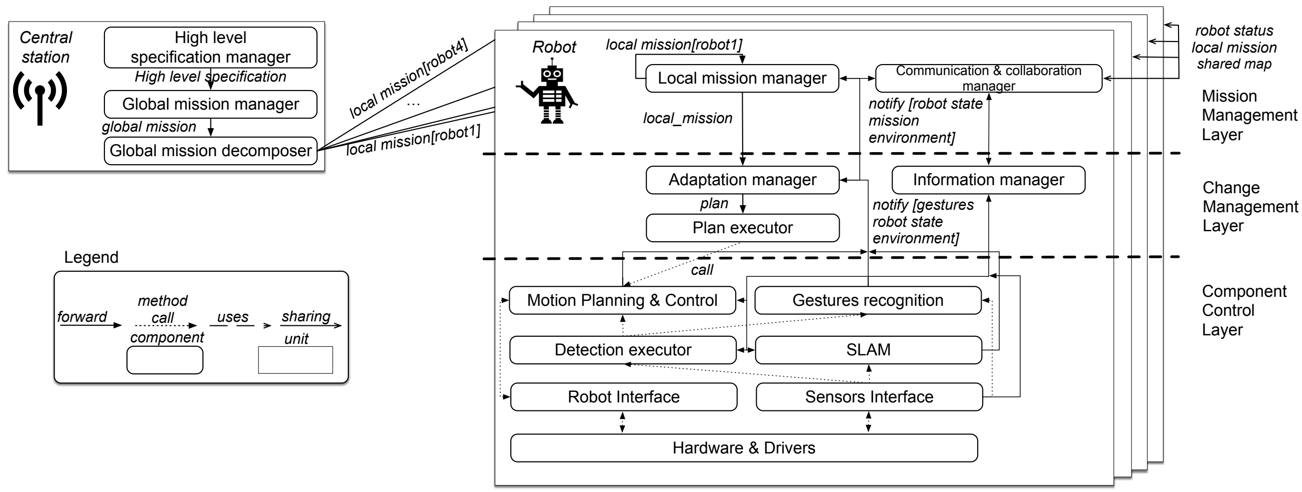

Figure 2: Software architecture.

issues, less robustness facing failures of a node, etc.), specially working with the ROS middleware.

4 FUTURE WORK AND DIRECTIONS

As stated before, we plan to split the work related with this PhD project in two parts: (1) the first part, focused in the single-robot approach; (2) and the second part, focused in the multi-robot approach.

Therefore, our future work will be focused in trying to find an answer to the RQ2. In order to achieve it, a detailed study of the current state of the art of features involved with multi-robot choreography such as emergent properties or collaborative strategies must be performed.

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