

# Real-Time Monitoring and Remote Guidance of Mobile Robots Using Multimodal Digital Twins

Trung Kien La

*Dept. of Comp. Science & Engineering* *Dept. of Comp. Science & Engineering* *Dept. of Comp. Science & Engineering*  
*Frankfurt University of Applied Sciences* *Frankfurt University of Applied Sciences* *Frankfurt University of Applied Sciences*  
Frankfurt a.M., Germany  
trung.la@stud.fra-uas.de

René Harmann

Frankfurt a.M., Germany  
rene.harmann@fb2.fra-uas.de

Eric Guiffo Kaigom

Frankfurt a.M., Germany  
kaigom@fb2.fra-uas.de

**Abstract**—Although digital twins have been playing a pivotal role in the management of the lifecycle of physical robotic systems of systems, they have hardly been employed to guide mobile robots in real-time. In fact, the guidance of such systems requires functionalities, including the perception of targeted locations and avoidance of collisions, that build upon spatial information beyond internal robot states usually acquired using proprioceptive sensors. In this case, exteroceptive sensors help meet this demand. Nevertheless, such sensors have received little attention thus far in the development of digital twins. On the other hand, the completion of various spatial objectives, such as reverse motions, might require the awareness of the historical internal state of the distant robot. For instance, the current energy budget is likely to constrain the reachability of the initial state after a while, even when spatially and kinematically feasible. We therefore embrace these challenges with a multi-modal approach to provide and employ digital twin of mobile robots. We collect data about the internal state and camera-captured neighborhood of the robot in real-time. The robot operator is thereby provided with a multi-dimensional state and perception view that characterizes the robot, elevates situational awareness, and facilitates decision support. We then develop a versatile graphical interface that helps monitor and steer mobile robots. Since the bidirectional approach is intuitive and user friendly, even novices can remotely guide a mobile robot with multi-modal situational awareness. We show the versatility and effectiveness of our approach in use case scenarios in practice.

**Index Terms**—Robotics, Multimodal Data, Digital Twins, Industry 4.0, Industry 5.0, Society 5.0, Human-Mobile Robot-Interaction, Systems of Systems

## I. INTRODUCTION

The Robot Operating System (ROS) is one of the most popular pieces of robot middleware when it comes to creating a basis for robots and creating robot applications [1]. Nevertheless, it is a challenge for people with little or no knowledge of robot software to familiarize themselves with this software. Especially people who are dependent on the help of robots should have intuitive access to these robots. With this in mind, a web application was developed that is as platform-independent as possible. This web application enables users to monitor and control the robot located in the local network. Furthermore, relevant data such as the battery status and the temperatures of the motors are visualised. The application can also be accessed by any device with web browser support. The robot we use is the Husky Unmanned Ground Vehicle (UGV)



Fig. 1. Picture of the Husky UGV by Clearpath

from Clearpath, which is a medium-sized mobile robotics platform as shown in Fig. 1. With a maximum payload of 75 kg, other robots, peripherals and tools, for example, can be transported or mounted on it [2].

## II. STATE OF THE ART

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### A. Maintaining the Integrity of the Specifications

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## III. IMPLEMENTATION AND DESIGN

The system architecture of the web application can be divided into a backend and a frontend, whereby various tools and frameworks are used.

#### A. Backend

The web application is a Flask application. Flask is a micro web framework that is characterized by providing the core features to create a python web based application. Therefore, Flask is very flexible and also highly extensible [4].

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- standard
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#### B. Frontend

#### C. Equations

#### D. $\LaTeX$ -Specific Advice

#### E. Some Common Mistakes

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