

# Waste Incinerator Service

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## Requirements Analysis

### Structure

Analyzing the natural language requirements text, we identified the following entities that should be modeled:

- ServiceArea
  - Home
  - BurnIn port
  - BurnOut port
  - WasteIn
  - AshOut
- OpRobot
- DDRobot
- WIS
- Incinerator
- WasteStorage
  - Scale
  - RP
  - WRP
- AshStorage
  - MonitoringDevice
  - Sonar
  - Led

### Interaction and Behavior

From the requirements, we inferred the following information that needs to be modeled:

Information	Source	Destination
activationCommand	unspecified	Incinerator
isBurning	Incinerator	unspecified
ashLevel	Sonar	unspecified
loadRP	WasteStorage	OpRobot
burnRp	OpRobot	Incinerator
loadAsh	unspecified (OpRobot    Incinerator    WIS)	unspecified (OpRobot    Incinerator    WIS)
unloadAsh	OpRobot	AshStorage

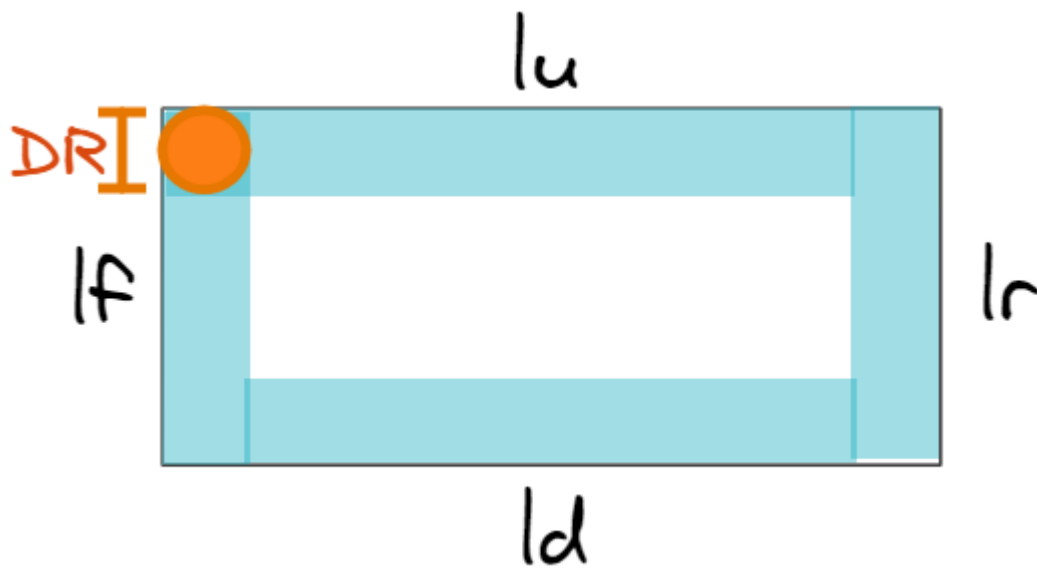
[!NOTE]

We merged the Interactions and Behavior sections because at this stage of the project, for the majority of this information, we don't know yet if it will be modeled as POJOs' methods or messages between actors.

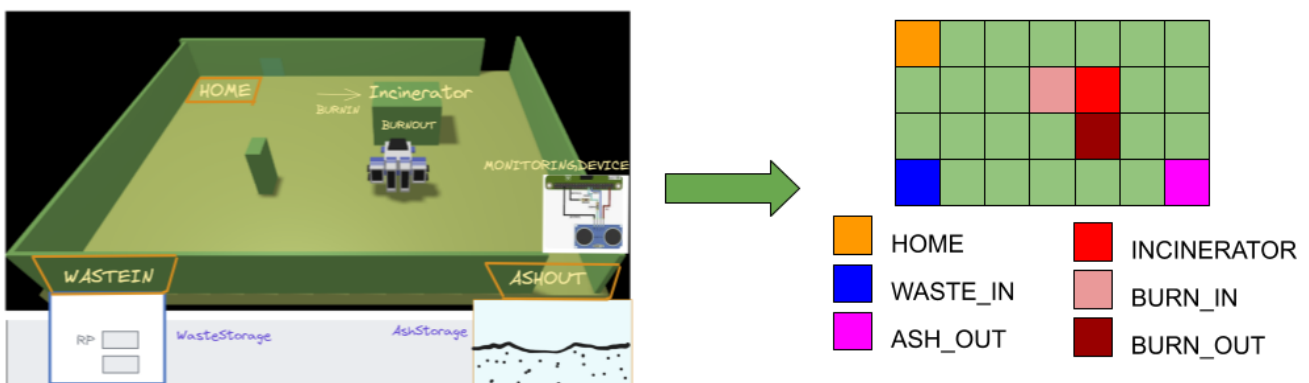
## Service Area Model

The **ServiceArea** is modeled as an Euclidean space delimited by its edges (similar to what has been done in the [BoundaryWalk](#) and [RobotCleaner](#) projects):

- The **perimeter edge** has length  $lf + ld + lr + lu$ .
- Being the ServiceArea rectangular, we have  $lf = lr$  and  $ld = lu$ .
- We define  $DR = 2R$ , where  $R$  is the radius of the DDRobot's circumscribable circle.

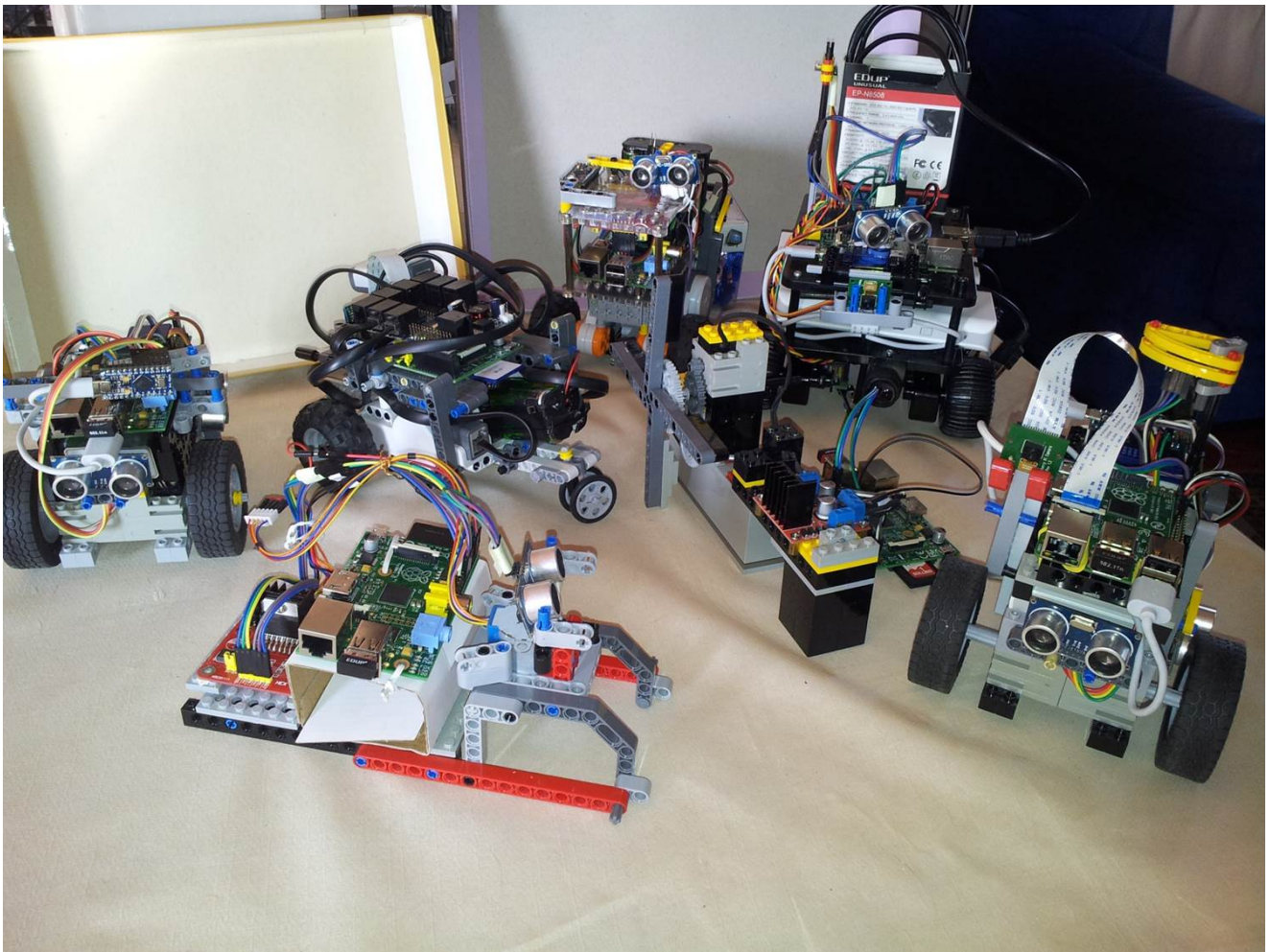


Given this model, we have that **Home**, **BurnIn**, **BurnOut**, **WasteIn**, and **AshOut** are all modeled as cells in the ServiceArea:



## DDRRobot Model

The **OpRobot**, defined in the requirements as the robot controlled by the WIS, makes use of a DDRobot (and its control software) provided by the customer. We link the [detailed definition of DDRobot](#) and its [qak control software](#).



## WIS, WasteStorage, Incinerator, and AshStorage Models

**WasteStorage**, **Incinerator**, and **AshStorage** need to exchange messages according to the requirements, so they are modeled as actors.

**Scale** can be modeled either as an actor or a POJO inside **WasteStorage**. For now, we will represent it as a POJO and **defer the discussion to a later moment**.

The same applies to the **MonitoringDevice**, **Sonar**, and **Led**, which will be modeled as POJOs inside **AshStorage** for now.

In the first prototype of the model, the **OpRobot** will contain the majority of the business logic for the realization of a 'WIS cycle' (move to waste storage, load an RP, move to incinerator, burn the RP, move to ash storage, unload ash).

However, there are **no specifications** about where to inject the business logic (injecting all business logic into **WIS** could also be an option), so we **defer this discussion to the Problem Analysis**.

**WIS** will be divided into two sub-components: a **WISStateObserver** that will act as an observer of **WasteStorage**, **AshStorage**, and **Incinerator**, checking that the constraints are satisfied, and a **WISIncineratorScheduler** that will activate the incinerator.

**This organization of WIS is not evident from the requirements; hence, it may change in future sprints.**

The following diagram illustrates the structure based on requirements:

ctx\_wis

conditions\_verified\_req conditions\_verified\_repl

