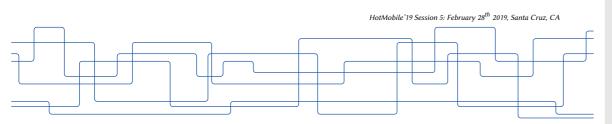


# EdgeDroid

An Experimental Approach to Benchmarking Human-in-the-Loop Applications

M. Olguín Muñoz<sup>†</sup>, J. Wang<sup>‡</sup>, M. Satyanarayanan<sup>‡</sup>and J. Gross<sup>†</sup>



#### dgeDroid

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M. Olguin Mulaz<sup>†</sup>, J. Wang<sup>†</sup>, M. Satyanarayanan <sup>†</sup> and J. Groot <sup>†</sup>

<sup>†</sup> KTH Royal Institute of Technology <sup>†</sup> Carnegle Mellon University

Heritolish P. Senire S. February 26<sup>th</sup> 201

- Name all authors
- Mention Sweden









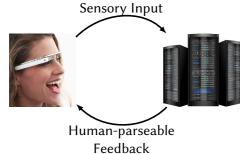
#### Introduction



- Exciting new applications which integrate with the real world and the users.
- Put the human in a feedback loop.
- High dimensional, context-aware inputs.
- High dimensional, human-parseable outputs.













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Need to understand and optimize these applications:

- ► How do they interact with each other?
- ► How do they interact with infrastructure?
- ► How do they scale?

With which methodology can we study these behaviors?



Introduction

2019-02-28

Studying Human-in-the-Loop Applications

Studying Human-in-the-Loop Applications

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- How do they scale?



- Apps are starting to proliferate.
- They are interesting for developers, users, training, live assistance, etc.
- We still don't know much.

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└─Introduction

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Costly, poor repeatability

-Introduction

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Studying Human-in-the-Loop Applications

Studying Human-in-the-Loop Applications

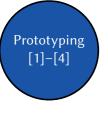
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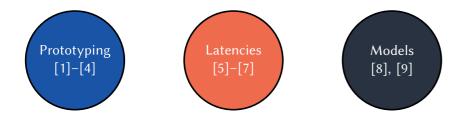
-Introduction —Background Previous & Related Work



Previous & Related Work





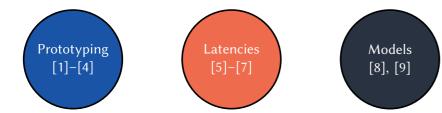


## Our Contributions

► A methodology for benchmarking human-in-the-loop applications.







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- ► EdgeDroid: A benchmarking tool-suite.

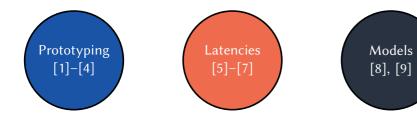




Previous & Related Work



► A methodology for benchmarking human-in-the-loop applications. EdgeDroid: A benchmarking tool-suite.



### Our Contributions

- ▶ A methodology for benchmarking human-in-the-loop applications.
- ► EdgeDroid: A benchmarking tool-suite.
- Experiments and measurements which show the effectiveness of the approach.

-Introduction 2019-02-28 -Background Previous & Related Work





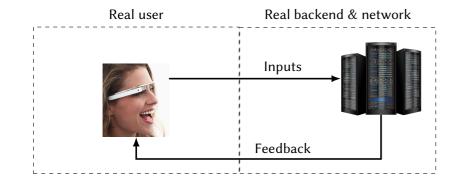


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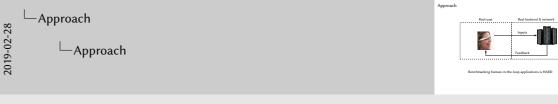
Previous & Related Work

Experiments and measurements which show the effectiveness of the approach

# Approach

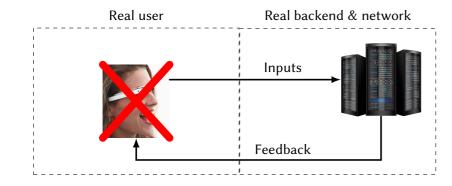


Benchmarking human-in-the-loop applications is HARD

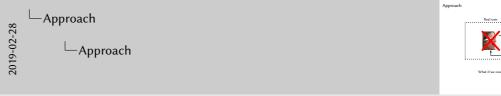


- Hard because of humans.
- Trace-based approach with a "user model" which modulates the replay of the trace.
- I will explain "user model" in the next slides using an example.

# Approach

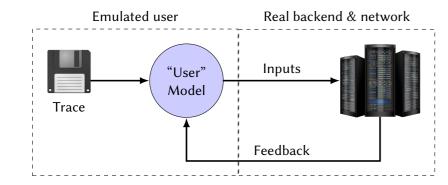


What if we could do away with the human users?



- Hard because of humans.
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# Approach



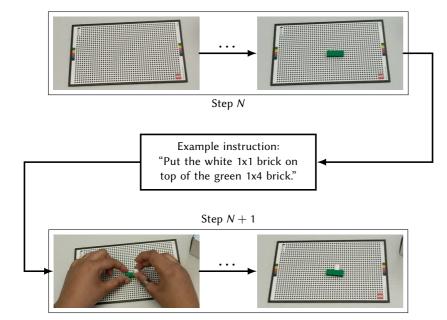
What if we could do away with the human users?

Repeatable, scalable!



- Hard because of humans.
- Trace-based approach with a "user model" which modulates the replay of the trace.
- I will explain "user model" in the next slides using an example.

# Example: Task Guidance Wearable Cognitive Assitance, LEGO [1]



-Approach

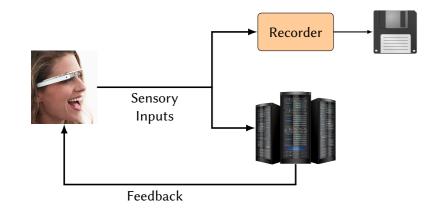
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Example: Task Guidance Wearable Cognitive
Assitance, LEGO [1]



- · Running example.
- Explain LEGO step by step. Captures video and gives feedback instructions.
- Don't say it was created at CMU.
- Usable simple example for initial implementation because of Linear model.

# Tracing





-Approach
-Tracing

Tracing

- First step in our approach is tracing.
- Trace raw inputs.
- Example: LEGO -> video frames.

# Trace Replay

# Non-trivial Challenge

- ► Changes in system responsiveness require adapting trace.
- System delays affect user behavior as well.





Trace Replay

- Merely replaying trace is not enough.
- What happens if the responsiveness of the system changes?
- Need a way to adapt the trace to system conditions.

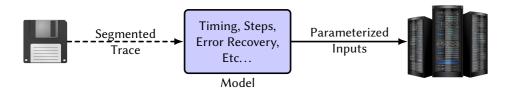
# Trace Replay

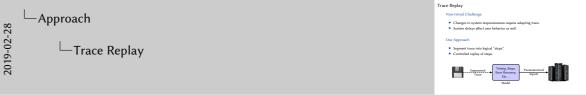
# Non-trivial Challenge

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## Our Approach

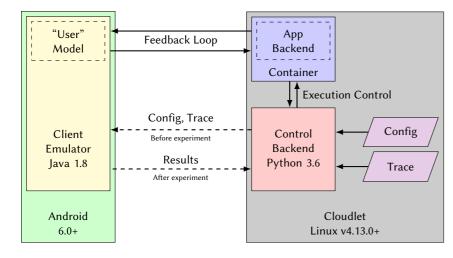
- ► Segment trace into logical "steps".
- ► Controlled replay of steps.





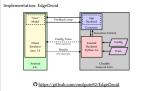
- Merely replaying trace is not enough.
- What happens if the responsiveness of the system changes?
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# Implementation: EdgeDroid



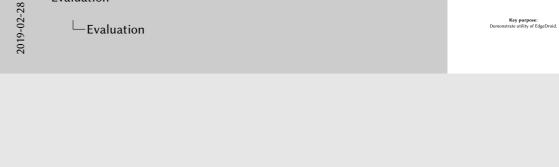
https://github.com/molguin92/EdgeDroid





- · Very short about implementation.
- Remind that we don't emulate backend or network.

# Evaluation **Key purpose:**Demonstrate utility of EdgeDroid.



Evaluation

-Evaluation

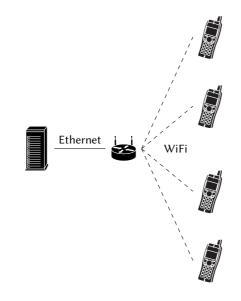
# Evaluation: Setup

# Application & Scenarios



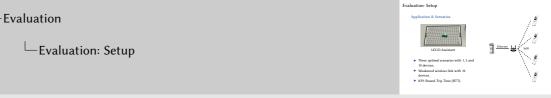
**LEGO** Assistant

- ► Three *optimal* scenarios with 1, 5 and 10 devices.
- ► Weakened wireless link with 10 devices.
- ► KPI: Round-Trip Time (RTT).



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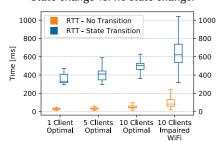
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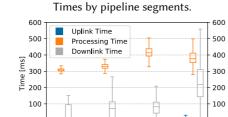


• Use example of app developer and system designer to exemplify results.

# Use Cases

#### State change vs. no state change.





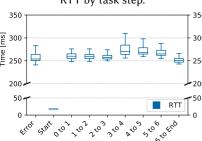
Optimal

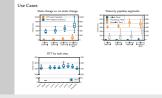
Optimal

10 Clients Optimal

Impaired

# RTT by task step.





- Use example of app developer and system designer to exemplify results.
- Important aspect is that these results are repeatable and automatically obtained.
- Did not have to train 10 users.

Evaluation

Use Cases

2019-02-28

12 / 22

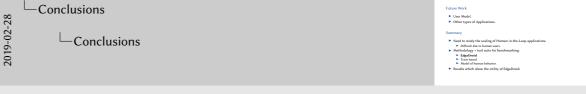
## Conclusions

#### **Future Work**

- ► User Model.
- Other types of Applications.

# Summary

- ▶ Need to study the scaling of Human-in-the-Loop applications.
  - Difficult due to human users.
- ► Methodology + tool suite for benchmarking:
  - EdgeDroid
  - ► Trace based.
  - Model of human behavior.
- Results which show the utility of EdgeDroid.



Conclusions

- Talk about future model of human behavior.
- Expand to other types of applications that are not task-based.



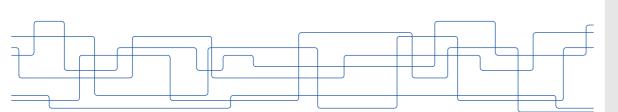
# Thank you.

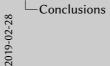
#### Contact

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KTH EECS Malvinas väg 10, 100-44 Stockholm, SWEDEN

Email: molguin@kth.se Website: https://olguin.se





Thank you.



# Requirements

- ► Generate realistic, high-dimensional, real-time inputs.
- Correctly and realistically react to feedback.
- ► KPI: Delays.

Trace of pre-recorded inputs & a model of user behavior



Requirements

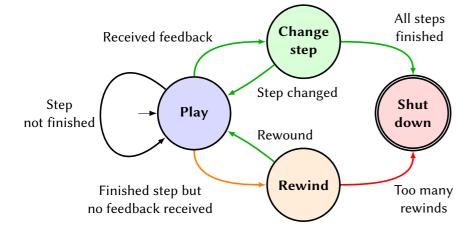


► KPI: Delays.

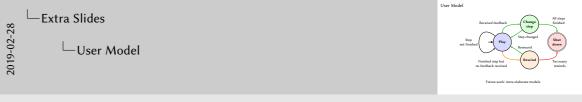
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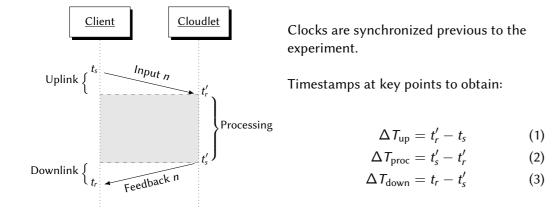
# User Model



Future work: more elaborate models.

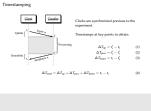


# Timestamping



 $\Delta T_{\text{total}} = \Delta T_{\text{up}} + \Delta T_{\text{proc}} + \Delta T_{\text{down}} = t_r - t_s$ 





(4)

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22 / 22