



OPC UA DT DATA MODELING AND CODE GENERATION USING PAPYRUS

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CLUSE, 29/03/2022

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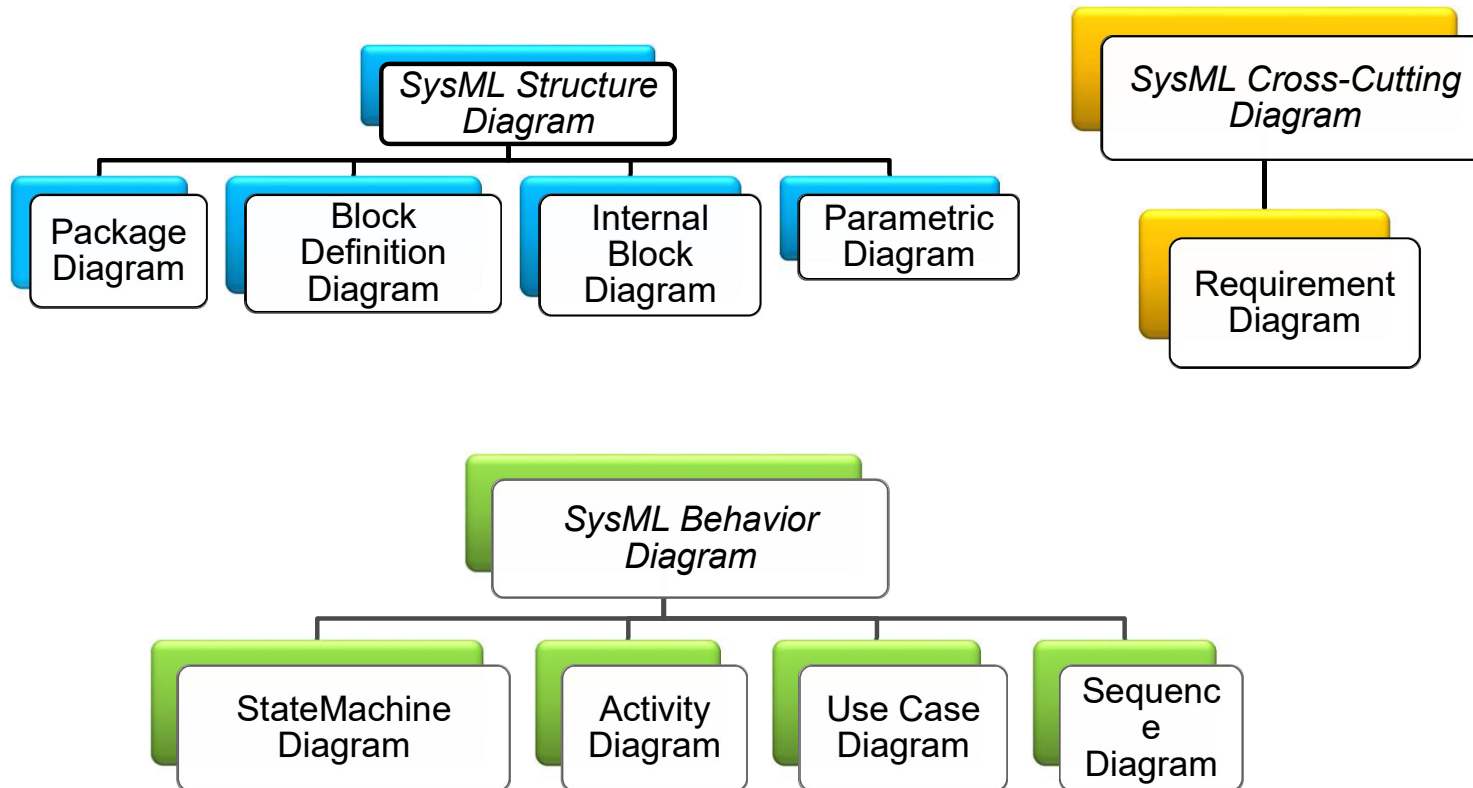


1. Introduction
2. OPC-UA Model Driven Tool Chain Architecture
3. Robotic Cell SysML Model
4. QVTo Transformation from SysML to OPC UA
 1. Transformation of Blocks
 2. Transformation of Motion Devices
5. Demo

- There Is No Industrie 4.0 without OPC UA[1]
 - Need for OPC UA CS for specific semantics description
 - Need for model driven tools for fastening the deployment of Industry 4.0 compliant systems
- Choice of SysML as a modelling language and Model2Model transformation for automating the deployment of OPC-UA Information models

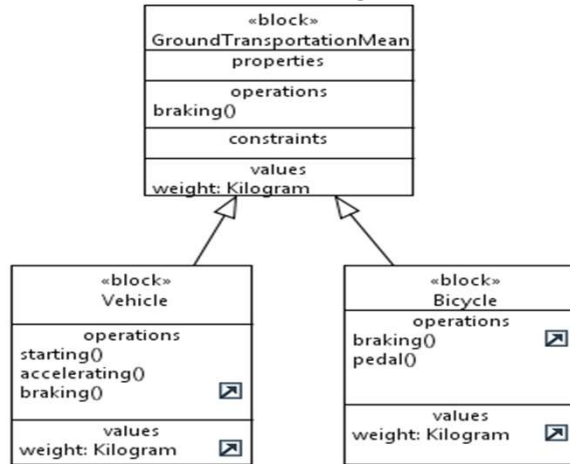
[1] Industry 4.0 and OPC UA: <https://opconnect.opcfoundation.org/2017/06/there-is-no-industrie-4-0-without-opc-ua/>

SysML DIAGRAMS

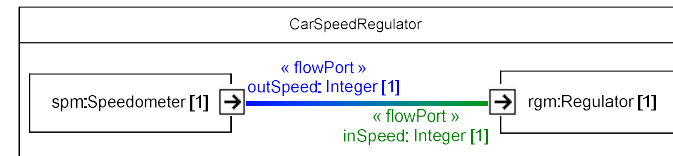


Multiple dedicated viewpoints

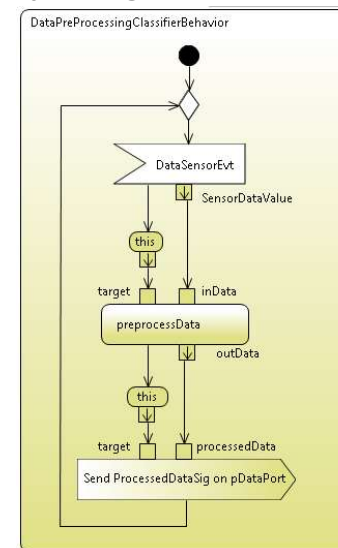
Block Definition Diagram



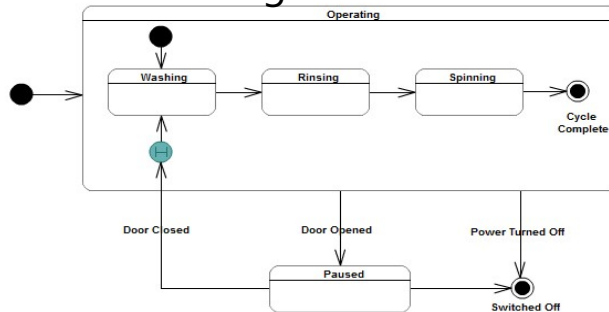
Internal Block Diagram



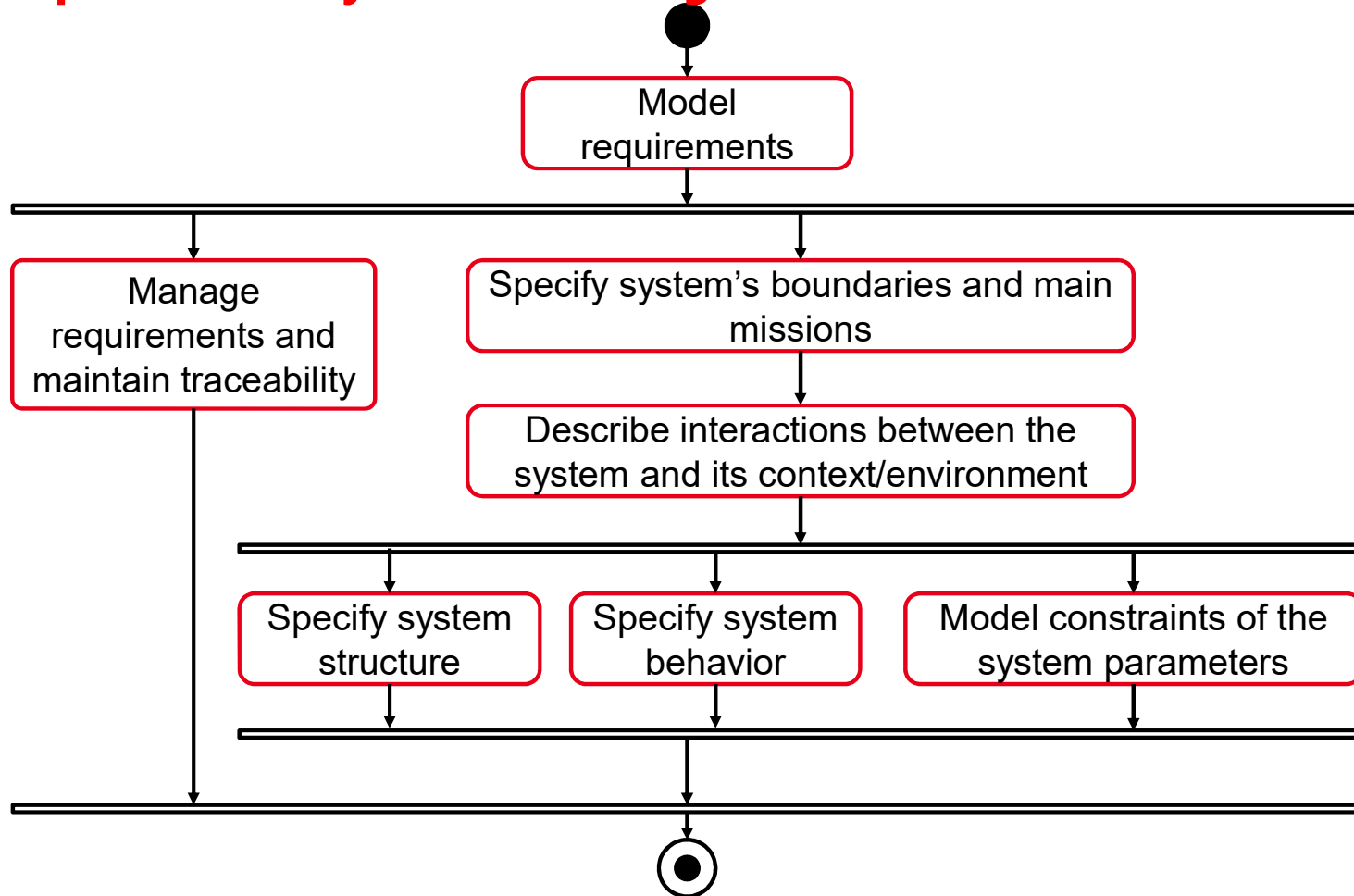
Activity Diagram



Statemachine Diagram



A process for system modeling



SysML for robotic cells modelling

1. Specification:

Use Case diagrams, Requirements diagrams

2. Functional Design:

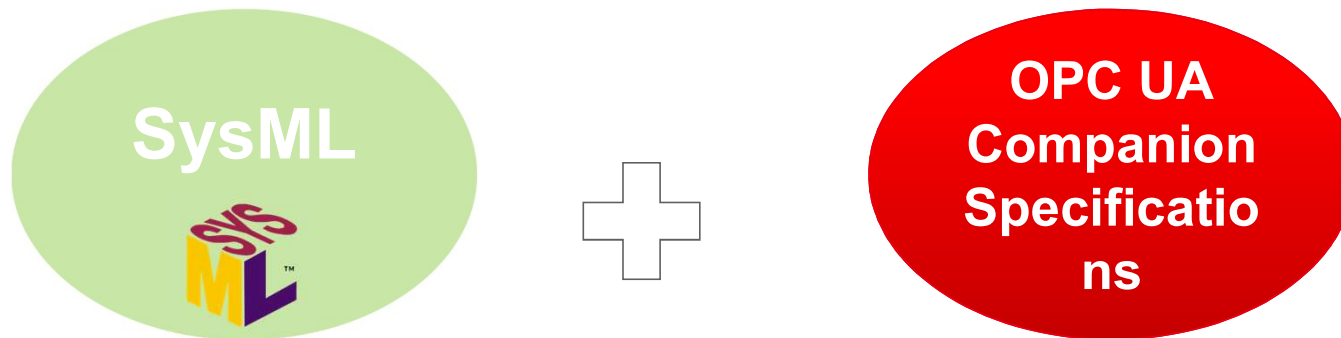
Structure: BDD, IBD

Behavior: State Machine diagrams, activity diagrams, sequence diagrams

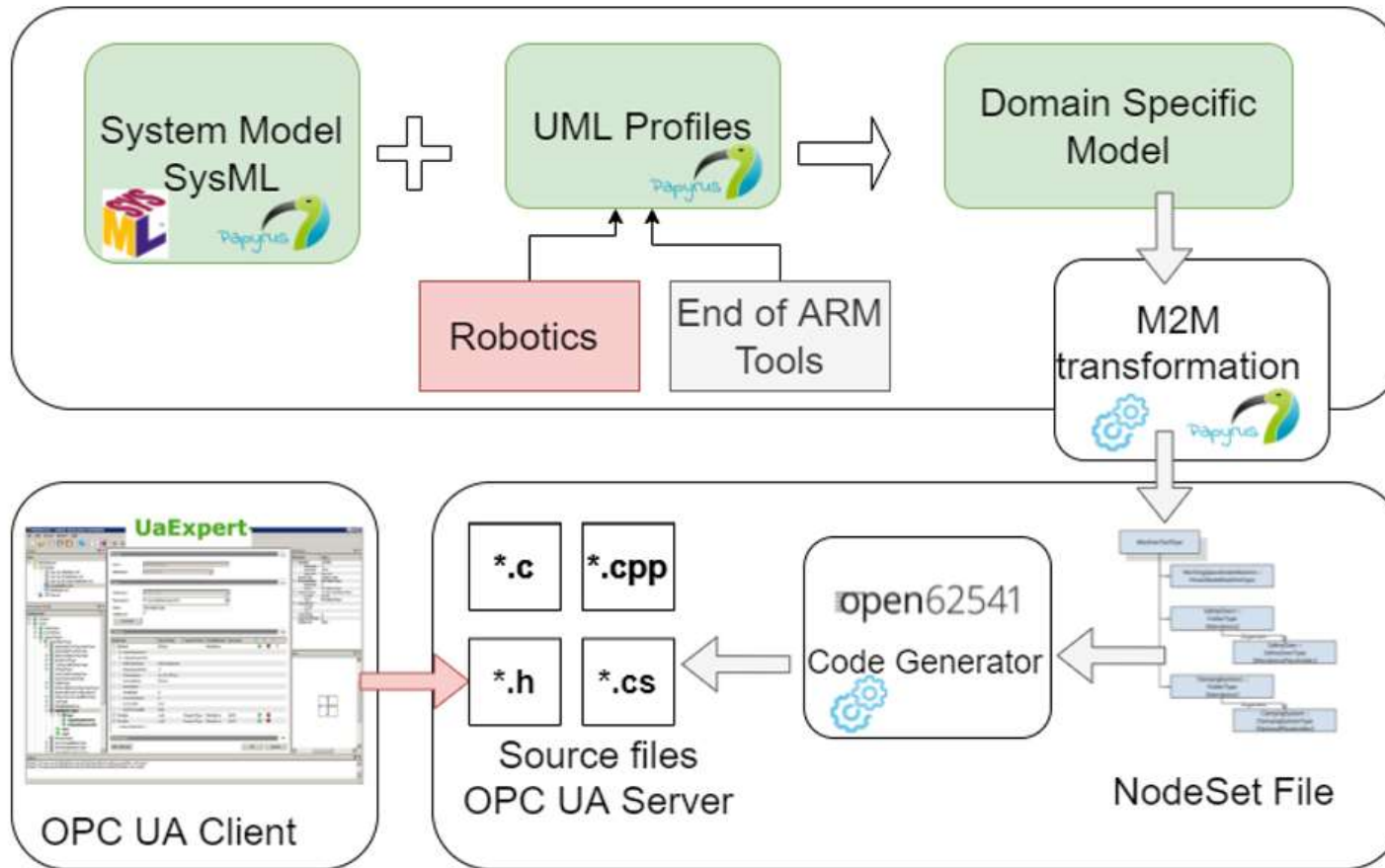
Extending SysML with Robotics Information Models

SysML Blocks are generic and do not contain meta data specific to robotic systems

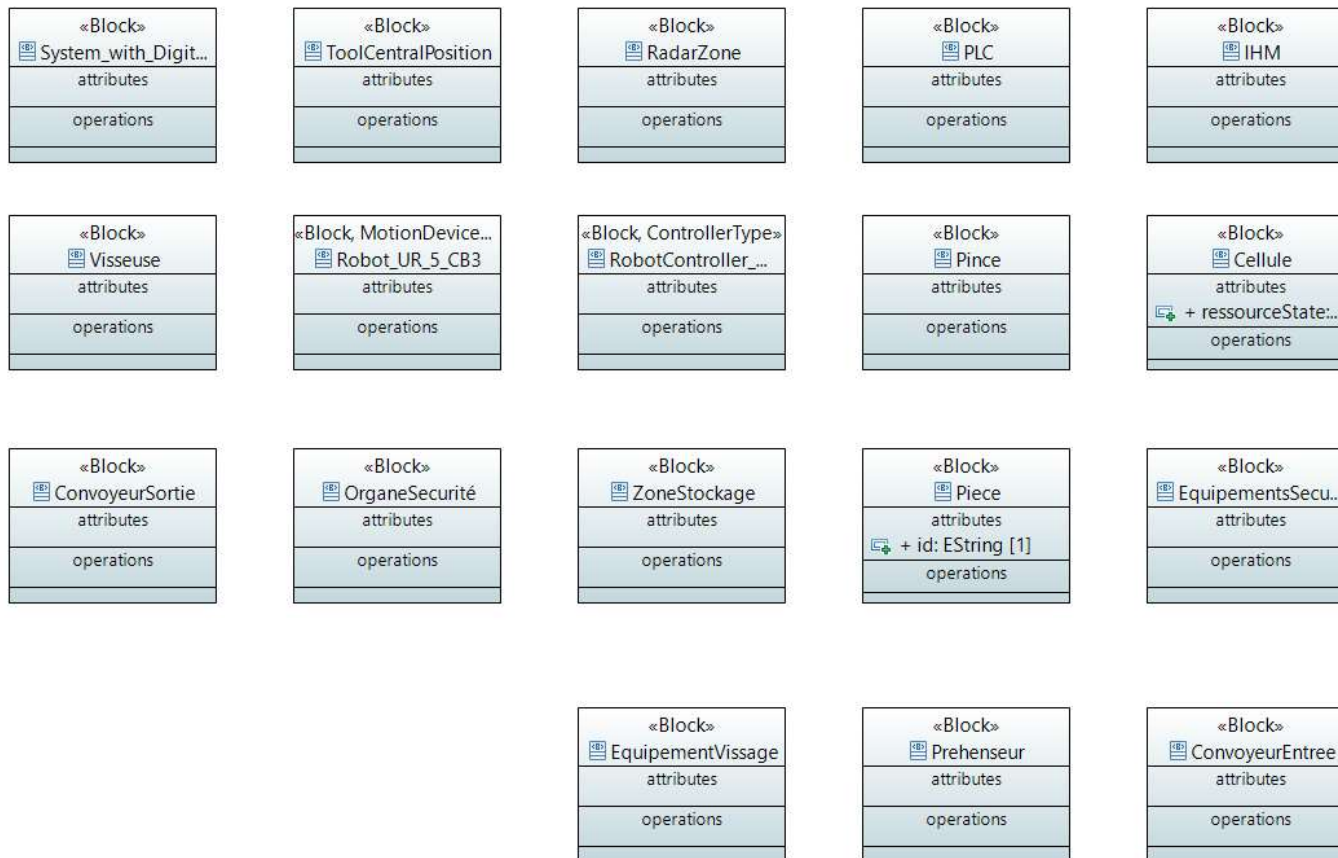
→ Extension of SysML by adding **OPC-UA Companion Specifications** as UML Profiles



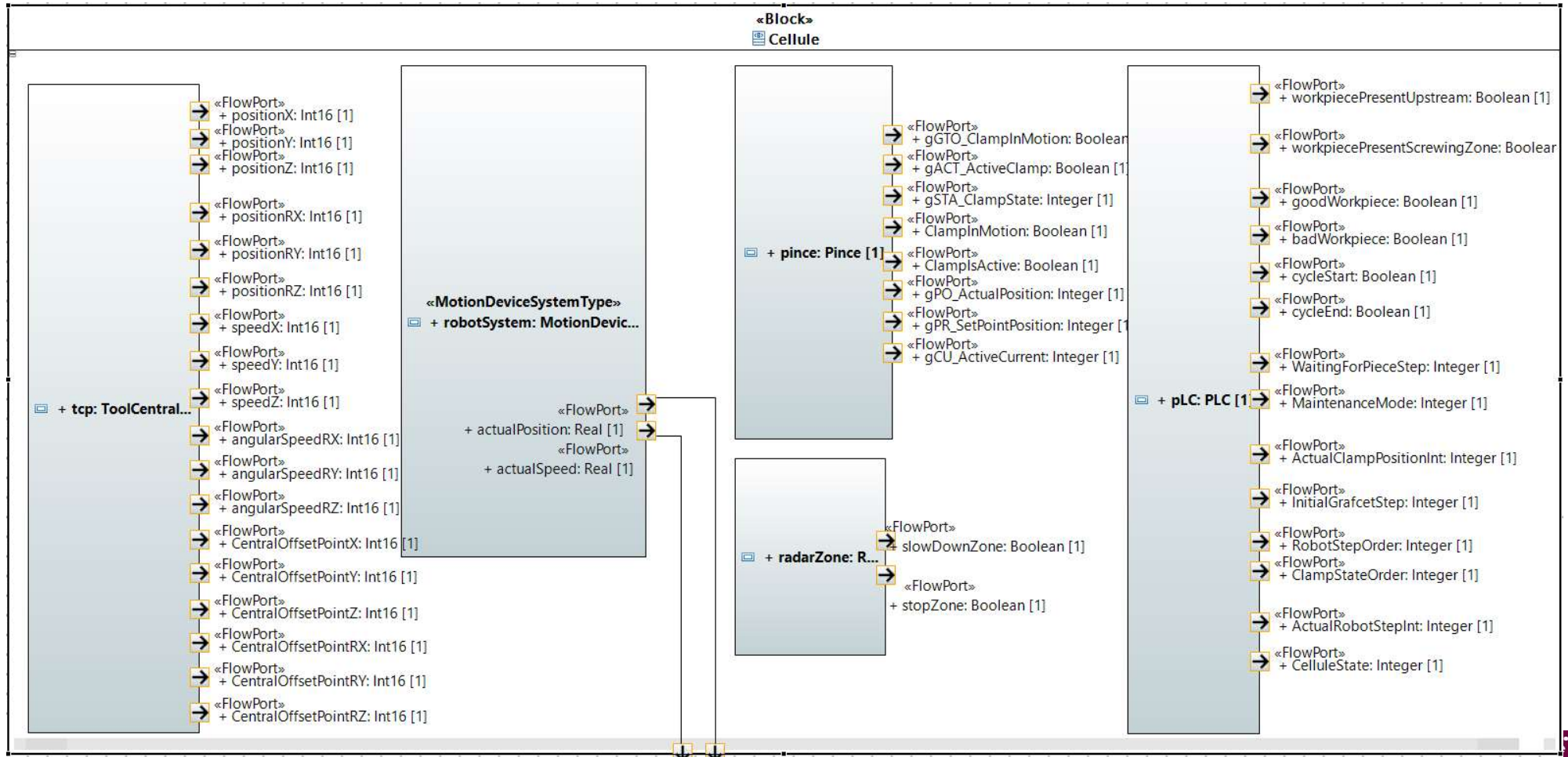
MODEL DRIVEN TOOL-CHAIN ARCHITECTURE



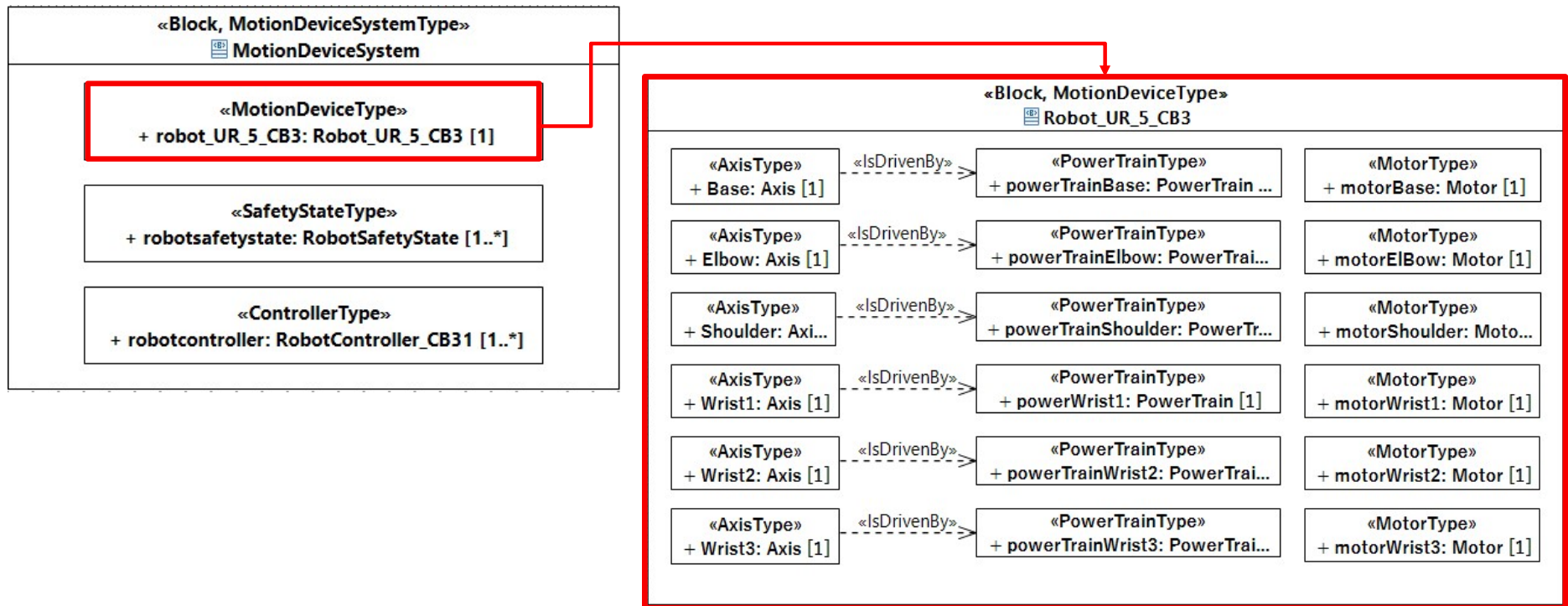
ROBOTIC CELL SYSML MODEL : BDD

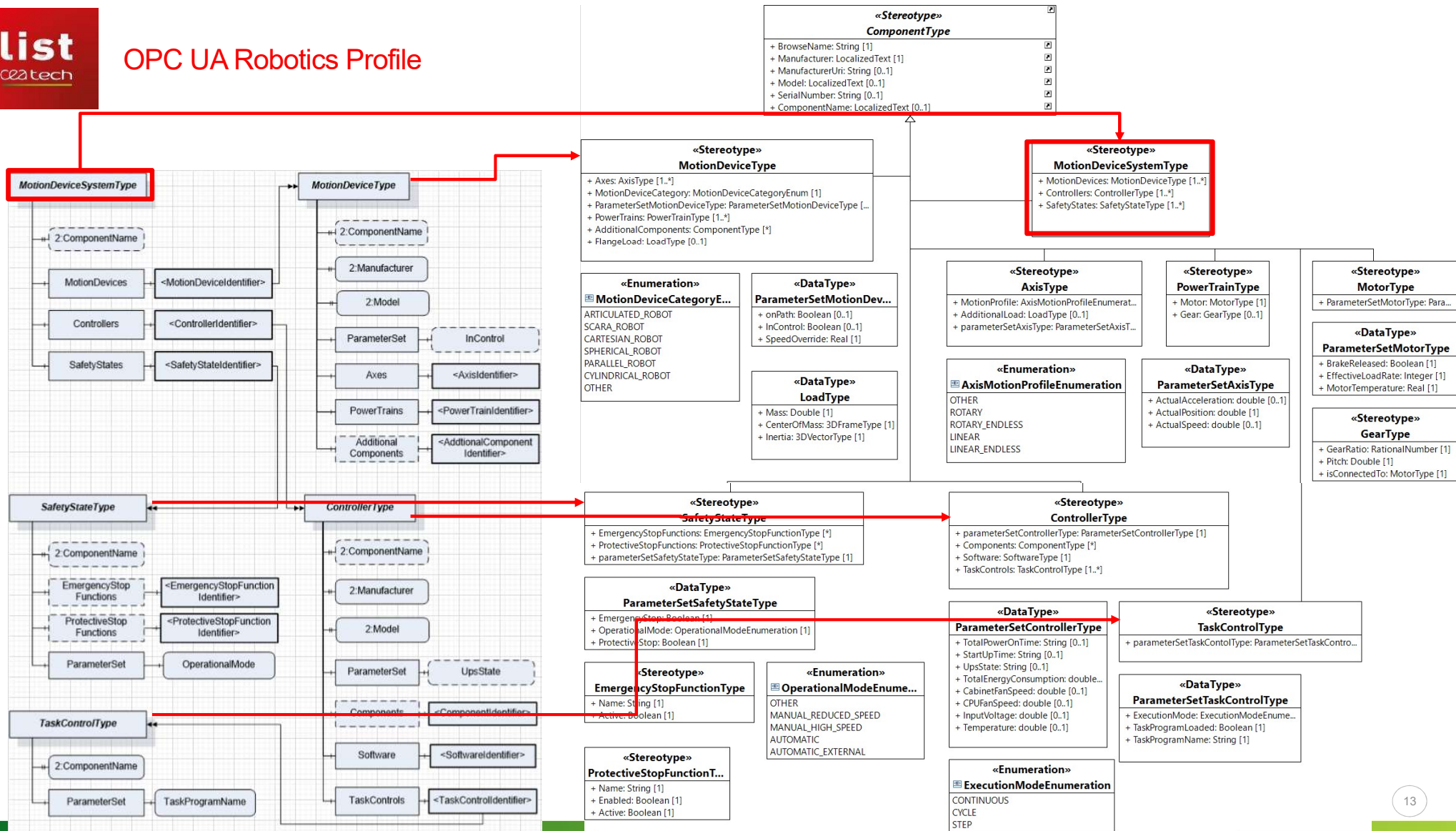


ROBOTIC CELL SYSML MODEL : IBD

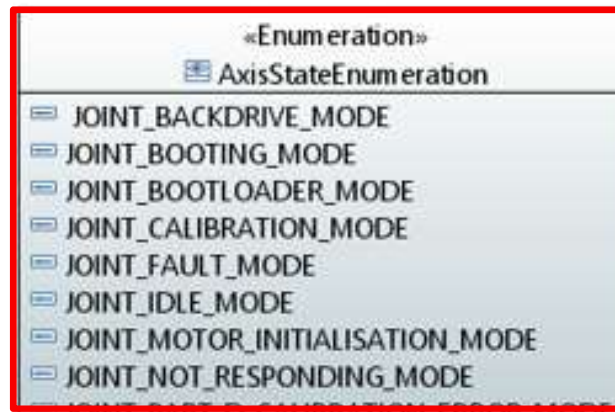
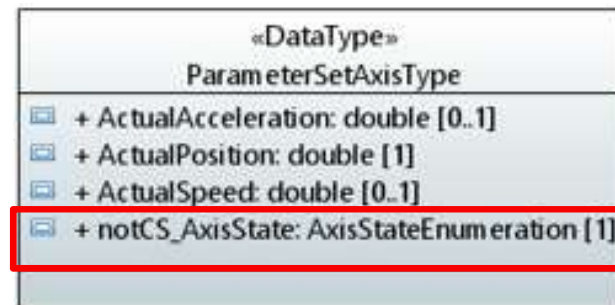
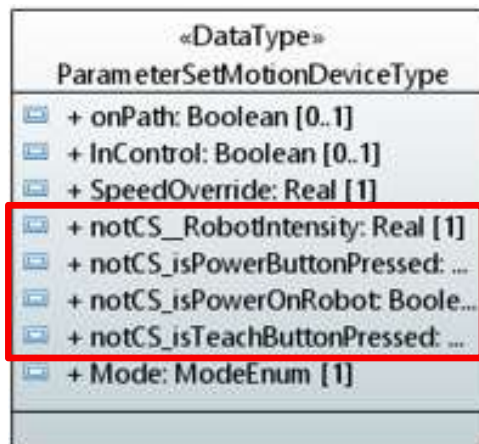


Motion Device System Model

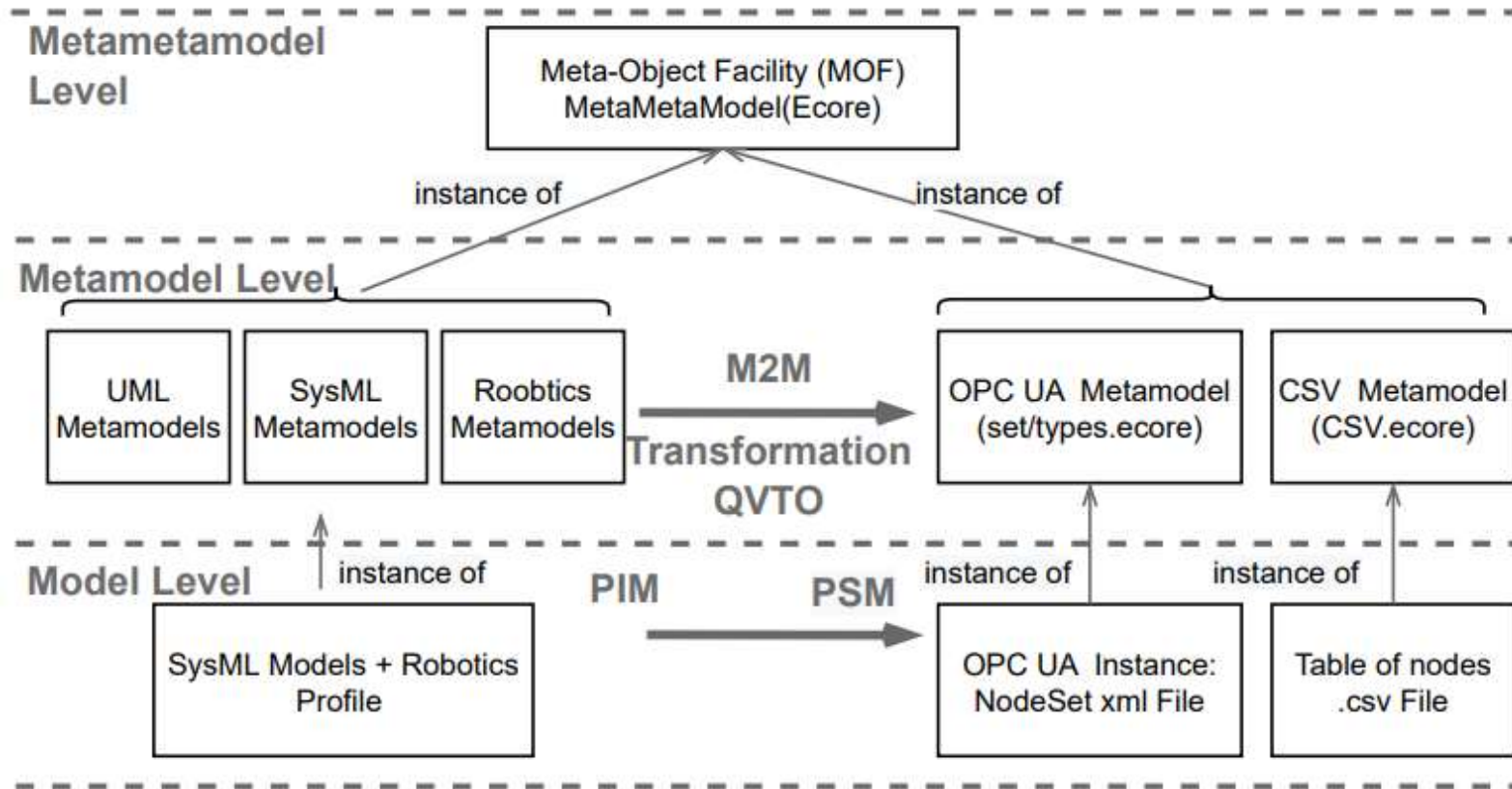




Add non existing information to the CS Robotics Profile



QVTo Transformation



Transformation of Blocks

«Block»
Pince

→ «FlowPort»
+ gACT_ActiveClamp: Boolean [1]
→ «FlowPort»
+ gGTO_ClampInMotion: Boolean [1]
→ «FlowPort»
+ gSTA_ClampState: Integer [1]
→ «FlowPort»
+ gFLT_Fault: Integer [1]
→ «FlowPort»
+ ClampInMotion: Boolean [1]
→ «FlowPort»
+ ClampsActive: Boolean [1]
→ «FlowPort»
+ gPR_SetPointPosition: Integer [1]
→ «FlowPort»
+ gPO_ActualPosition: Integer [1]
→ + gCU_ActiveCurrent: Integer [1]
«FlowPort»
→ «FlowPort»
+ byte0: Integer [1]
→ «FlowPort»
+ pinceStateEnum: PINCE_STATE [1]
→ «FlowPort»
+ pinceStateEnumInt: Integer [1]

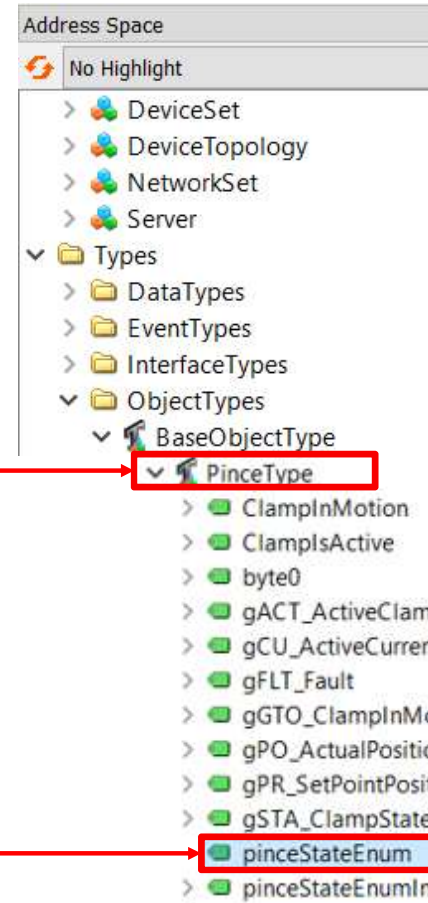
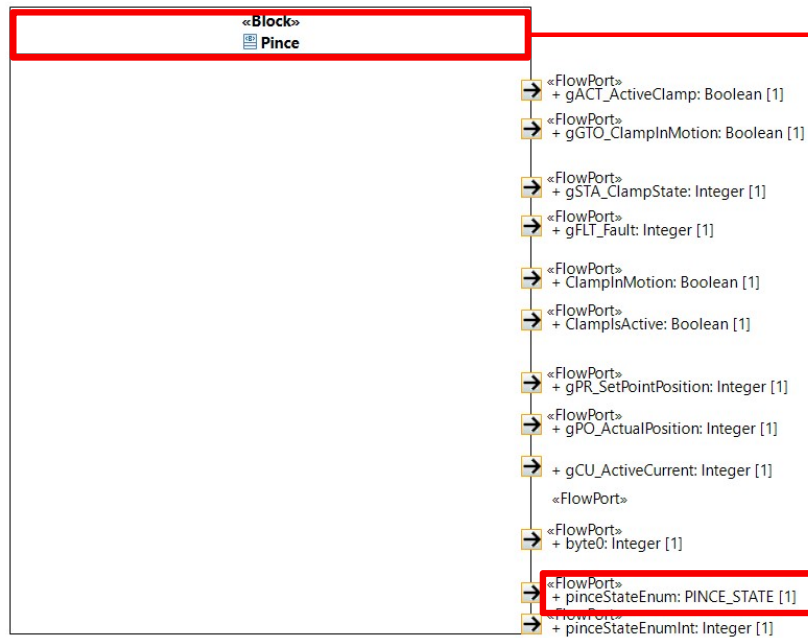
New UAObjectType

```
<UAObjectType BrowseName="PinceType" NodeId="ns=1;i=1000">
  <DisplayName>PinceType</DisplayName>
  <References>
    <Reference IsForward="false" ReferenceType="HasSubtype">BaseObjectType</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1001</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1002</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1003</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1004</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1005</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1006</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1007</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1008</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1009</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1010</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1011</Reference>
    <Reference ReferenceType="HasComponent">ns=1;i=1012</Reference>
  </References>
</UAObjectType>
```

```
<UAVariable BrowseName="gPR_SetPointPosition" NodeId="ns=1;i=1003" ParentNodeId="ns=1;i=1000" DataType="Int32">
  <DisplayName>gPR_SetPointPosition</DisplayName>
  <References>
    <Reference ReferenceType="HasTypeDefinition">BaseDataVariableType</Reference>
    <Reference ReferenceType="HasModellingRule">ModellingRule_Mandatory</Reference>
    <Reference IsForward="false" ReferenceType="HasComponent">ns=1;i=1000</Reference>
  </References>
</UAVariable>
```


Transformation of Blocks

UA Expert

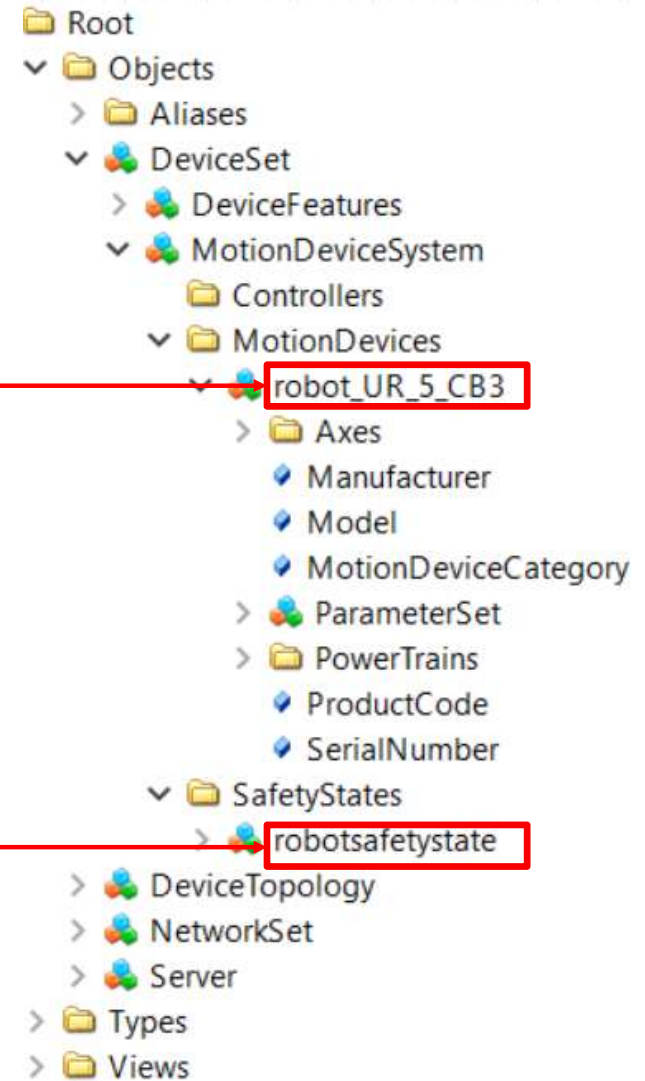
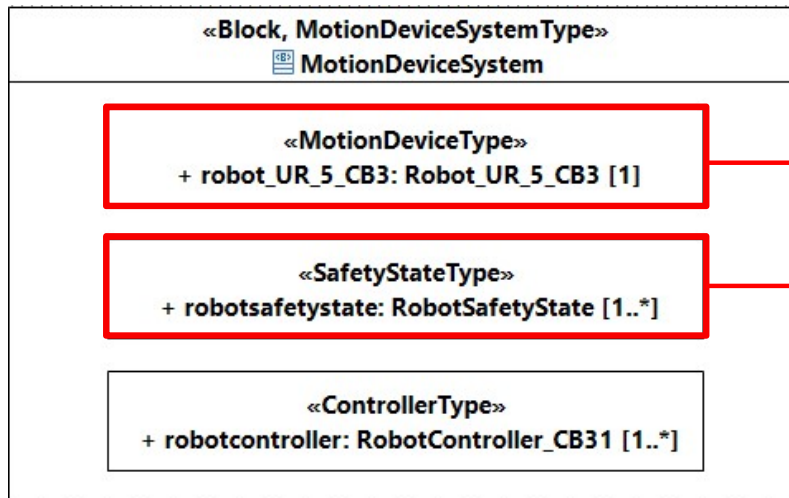


New UAObjectType

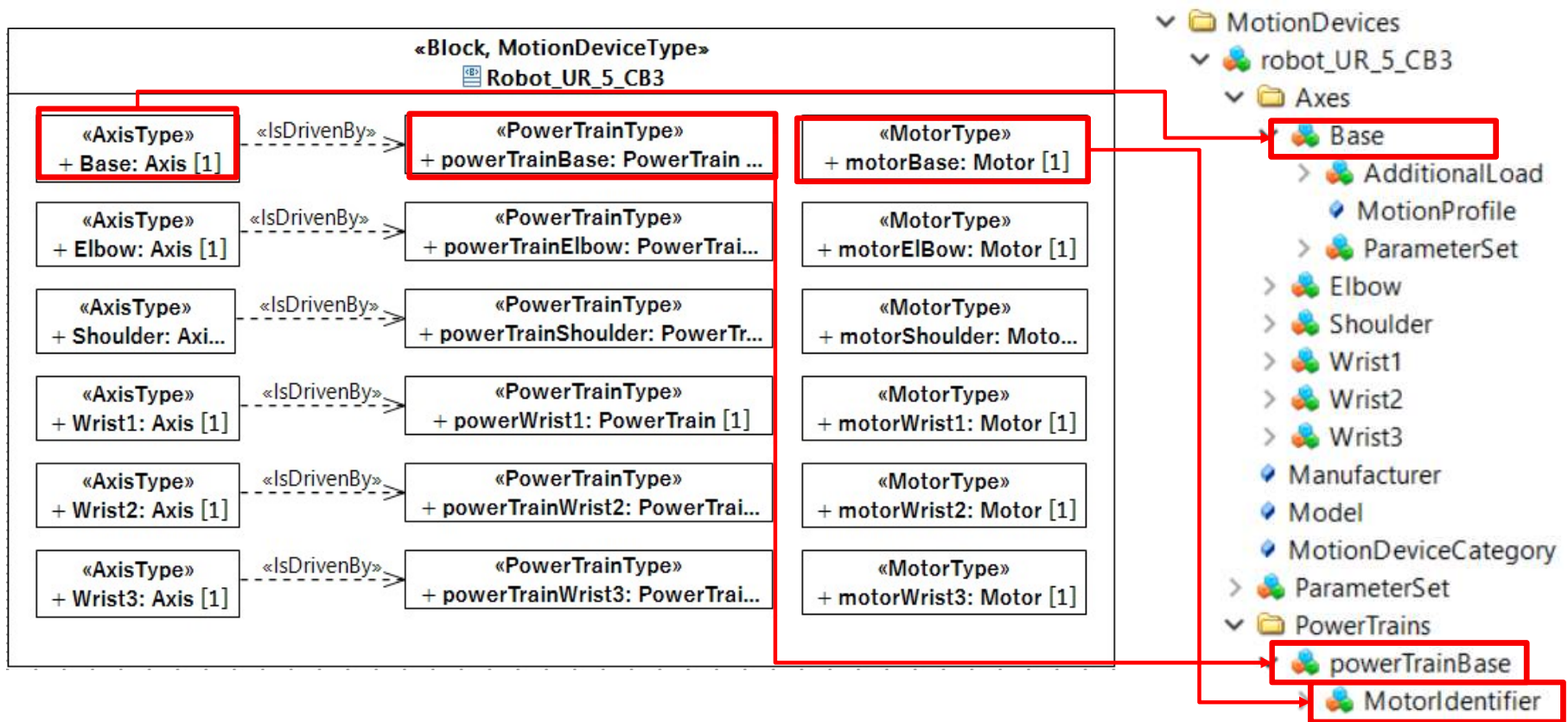
New UAVariableType

Data Access View				
#	Server	Node Id	Display Name	Value
1	open62541-...	NS4 Numer...	pinceStateE...	0 (RESET_LIBERATION)
				0 (RESET_LIBERATION)
				1 (ACTIVATION_FINISHED)
				2 (ACTIVE_NON_USED)
				3 (ACTIVATION_RUNNING)

Transformation of MotionDeviceSystemType instance



Modelling and Transformation of the MotionDeviceType instance



runtime-New_configuration - OPC_UA_DT_Experiment/OPC_UA_DT_Experiment.di - Eclipse Platform

File Edit Project management Navigate Search Papyrus Project Run Window Help

Package ... Project E... x JUnit

> doc [uml-to-opcua master]

OPCUA_test

> opc-ua-dt [opc-ua-dt master]

> Modeling [opc-ua-dt master]

> Documentation

OPC_UA_DT_Experiment [opc-ua-dt master]

OPC_UA_DT_Experiment

ArchitectureFonctionnelle.png

casUtilisation.png

cell_with_DT.png

Cellule_IBD.png

MotionDeviceSystem_IBD.png

MotionDeviceSystemObject24_0'

MotionDeviceType_IBD.png

Motor_IBD.png

OPC_UA_DT_Experiment2.xml

Model Explorer x

ArchitectureOrganique

> «Block, AxisType» Axis

> «Block, ControllerType» RobotCon

> «Block, GearType» Gear

> «Block, MotionDeviceSystemType»

> «ControllerType» robotcontrolk

> «FlowPort» actualPosition : Real

> «FlowPort» actualSpeed : Real

> «FlowPort» rACT : Boolean

> «FlowPort» rARD : Boolean

1 item selected

Type tags, projects, or working set names to mat

1 item selected

«Block»

CentralPosition

attributes

operations

«Block»

RadarZone

attributes

operations

«Block»

PLC

attributes

operations

«Enumeration»

ACTUAL_ROBOT_S...

STANDBY_POSITI...

«Block»

Visseuse

attributes

operations

«Block, MotionDevice...

Robot_UR_5_CB3

attributes

operations

«Block, ControllerType»

RobotController_...

attributes

operations

«Block»

Pince

attributes

operations

«Block»

Cellule

attributes

+ ressourceState...

operations

«Block»

ConvoyeurSortie

attributes

operations

«Block»

OrganeSecurité

attributes

operations

«Block»

ZoneStockage

attributes

operations

«Block»

Piece

attributes

+ id: EString [1]

operations

«Block»

EquipementsSecu...

attributes

operations

«Block»

Gateway

attributes

operations

«Block»

IHM

attributes

operations

«Block»

EquipementVissage

attributes

operations

«Block»

Prehenseur

attributes

operations

«Block»

ConvoyeurEntree

attributes

operations

Palette

General Annotations

Abstraction

Comment

Constraint

General Structure

Containment Link

Model

Package

Viewpoint

Conform

Expose

Stakeholder

Blocks

AbstractDefinition

Actor

Association (Directed)

Ports and Flows

FlowPort

FlowProperty

FullPort

Constraints

Constraint

ConstraintBlock

Parameter

Welcome System_IBD Cellule_IBD RobotSystem_IBD IBD_Robot_UR5_CB3 BlocOrganiques x Robot_BDD Pince_IBD ArchitectureFonctionnelle

Properties x Problems Javadoc Declaration Search Console Git Repositories Call Hierarchy Debug Model Validation Metamodel Explorer Synchronize

1 item selected

Resource Property Value

CodeMix

Tapez ici pour effectuer une recherche

09:05 23/03/2022

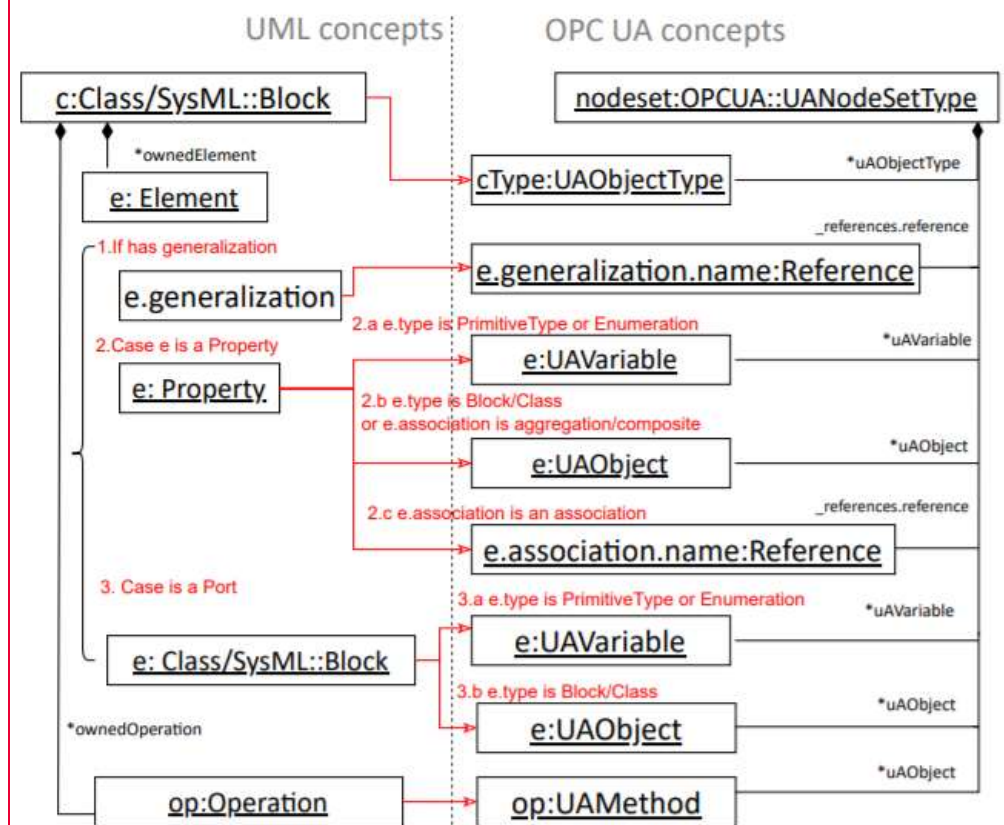
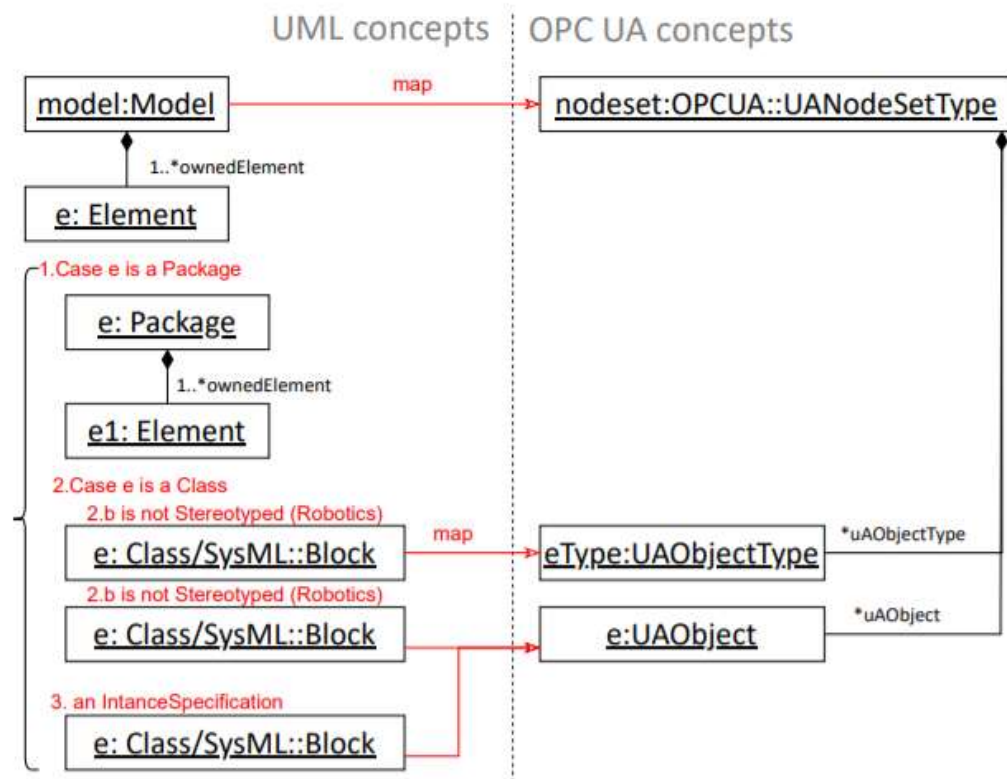
Future Work

- Take into consideration other Companion Specification (PLC, End Of Arms Tools...)
- Generation of Companion Specification from SysML Models
- Automatically deploy the OPC-UA clients (3D DT) from the SysML model

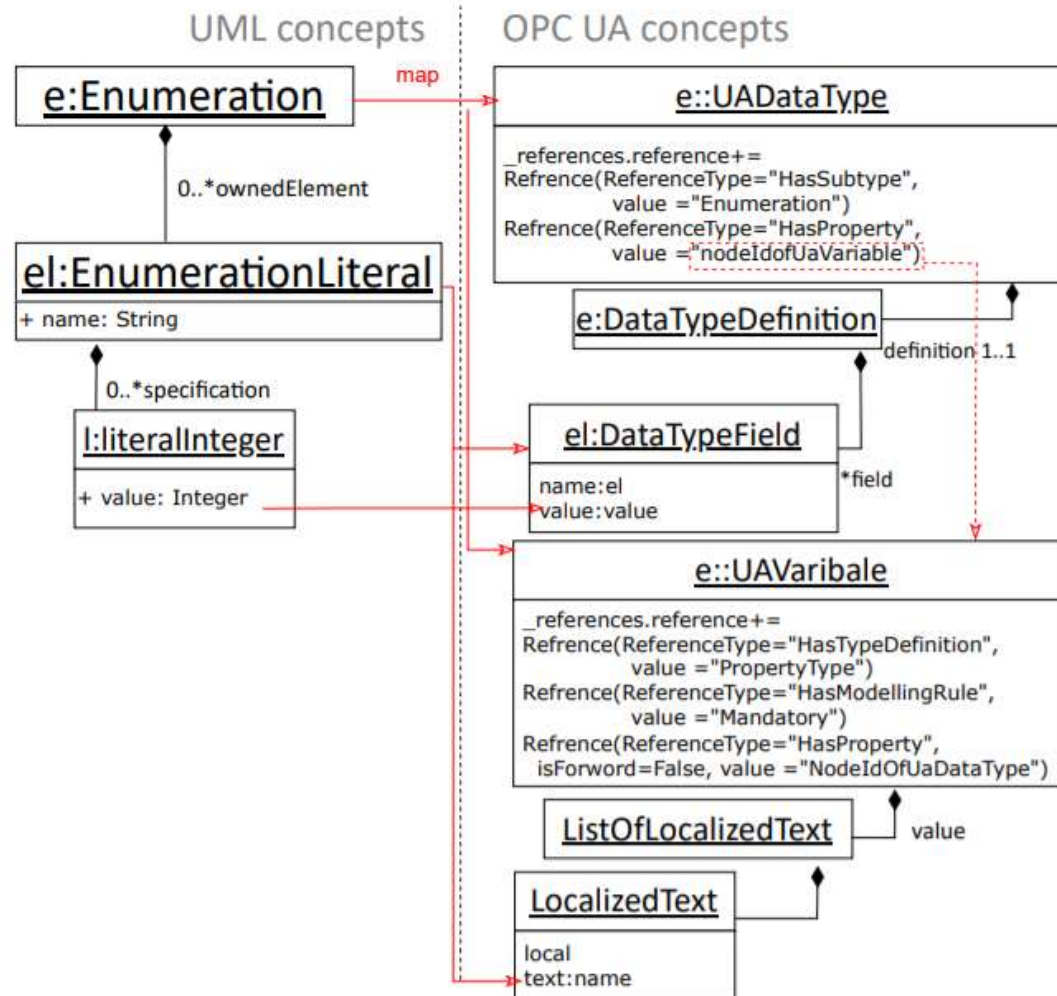
Questions



Transformation rules 1



Transformation rules 2



Cell Model

