

Contents

1	Introduction	1
1.1	Motivation	2
1.2	Hypothesis	4
1.3	Objectives	6
2	State of the Art	9
2.1	Execution Support Arquitectures	10
2.2	Service Providers and Intelligent Devices	12
2.3	Robot Mission and Behaviors	15
2.4	Environment Formalization and Interaction	18
2.5	Conclusions	24
3	Framework	25
3.1	Control Kernel Middleware	27
3.1.1	Control Kernel Concept	27
3.1.1.1	Light nodes and Tiny Control Kernel Middleware	29
3.1.1.2	Service nodes and Full Control Kernel Middleware	30
3.1.2	Middleware General Features	30
3.1.2.1	Sensory Perception Service	30
3.1.2.2	Control Service	31
3.1.2.3	Actuation Service	31
3.1.2.4	Monitoring and Alarms System	31
3.1.2.5	Resource Management	32
3.1.2.6	Code Delegation	32

CONTENTS

3.1.2.7	Controller Switching	32
3.1.2.8	Scheduling and Flexible Tasking	32
3.1.2.9	Networking	33
3.1.2.10	Data Management	33
3.1.3	Distributed Embedded Control Kernel	33
3.1.3.1	Underlying Topology	34
3.1.3.2	Virtualized and Partitioned Nodes	34
3.1.4	Control Kernel Multi-Peer	35
3.1.4.1	Peer Connexion	36
3.1.4.2	Peer Discovery	37
3.1.4.3	Message Types	37
3.1.4.4	Listeners	38
3.1.5	Middleware Configuration	39
3.1.5.1	Configuration Model	39
3.1.5.2	Configuration Files	40
3.1.5.3	Graphic Configuration Interface	41
3.1.6	CKM: Capabilities and Applications	42
3.2	Smart Devices	44
3.2.1	Smart Devices: A Control Kernel Middleware Implementation	45
3.2.2	Process architecture: Smart Plugin Topology	45
3.2.3	Data path mechanisms	46
3.3	Conclusions	48
4	Smart Resources	49
4.1	Smart Resources: Distributed Service Providers	51
4.2	Task Configuring Model: Adaptive Execution Mechanisms	54
4.2.1	Quality-based model and SPT configuration selection	54
4.2.1.1	Quality measures: Quality of Service and Endpoint Quality of Context Metadata	54
4.2.1.2	Quality policies and measure evaluation	55
4.2.1.3	System Scenarios	56
4.2.1.4	Quality-based Scenario Selection	57

4.2.1.5	TCM for Smart Resource Scenario Selection . . .	59
4.3	Communication API: Services Management	60
4.4	Smart Resources for Robotic	61
4.4.1	ROS integration: ROS MultiPeer Architecture	62
4.5	Conclusions	65
5	Robot Behavior and Mission Architecture	67
5.1	Individual Behavior	69
5.1.1	Behavior integrated services	69
5.1.2	Behavior execution and Service Composition	70
5.2	Mission	73
5.3	Mission Group Coordination	75
5.4	Validation Mechanism	77
5.5	Conclusions	80
6	Environment Model, Reconstruction and Interaction	81
6.1	Environment Model Formalization	83
6.1.1	Environment Object	83
6.1.1.1	Object Topology	83
6.1.1.2	Object Semantics	84
6.1.2	Global Map	85
6.1.3	Environment Management Enhancements	85
6.2	Robot Localization	89
6.2.1	Localization Algorithm	91
6.3	Sensor Service and feature analysis	95
6.3.1	Sensor services access and feature analysis	95
6.3.2	Classification matching	98
6.3.3	High-level fusion: Environment Knowledge Generation	99
6.3.4	Fusion Algorithm	100
6.4	Heterogeneous Robot Interaction Cooperation	101
6.5	Conclusions	103

CONTENTS

7 Experiments and Results	105
7.1 Experiment Framework	107
7.2 Smart Resource Quality Adaptation Test	112
7.3 Behaviour and Mission Design	116
7.3.1 Individual Robot Mission Design	116
7.3.2 Robot Cooperation Experiments	119
7.4 Environment Model, Reconstruction and Interaction	122
7.4.1 Environment Model	122
7.4.2 Object Interaction	127
7.5 Mission Execution and Validation	129
7.5.1 Individual Robot Mission Execution	129
7.5.2 Group Mission Execution	131
7.6 Conclusions	134
8 Conclusions	135
8.1 Developments and Achievements	137
8.2 Future Work	140
Appendices	143
A Projects and Publications	145
Nomenclature	155
List of Figures	159
List of Tables	165
Bibliography	167