

ENVIRONMENT FOR DESIGNING AND SIMULATING CONTROL NETWORKS AT DIGITAL HOME

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Keywords: Simulation, control network design, automation, digital home.

Abstract: A design and simulation environment for control network is presented. Control network design could be complex task because many technologies are involved. Each network technology uses its own design and configuration software. Also, it is necessary realize network installation in order to validate its correct operation. This situation introduces high temporal and economical costs in the network life cycle. Simulation design methodology as a task allows detect errors prematurely. System validations are made to a high level of abstraction. This paper proposes a design and simulation environment of digital home control network. It is based on a design independent from technology and postpone the technology choice and incorporates a simulation task that allows simulate the network.

1 INTRODUCTION

In this paper a digital home control networks design environment is proposed. The set of technologies that make the applications viable are diverse: X10 (Fuster and Azorín, 2005), KNX/EIB (Haenselmann et al., 2007), LonWorks (Ming et al., 2007), CAN (Jung et al., 2005), for example. It turns out complex to integrate them in a common system. However, sometimes system requirements need to communicate them in order to provide higher services. Discovery protocols facilitate devices connection and the services negotiation like: Universal Plug and Play (UPnP) (Rhee et al., 2004), Jini Network Technology, Open Service Gateway initiative (OSGi) (Kawamura and Maeomichi, 2004). In spite of standardization attempt, the integration is complex. As example, tools used by technologies considered as automation networks standard are: European Installation Bus Tool Software (ETS) for Konnex (KNX), and LonMaker Integration Tool (LonMaker) for Lonworks. Both tools have the same purpose, but they have different design methodology. Moreover these tools do not allow realizing simulations. A consequence is that the correct functioning will not be verified until the system will be implemented. These facts introduce high temporal and economical costs. Simulation

brings advantages in the design of control installation. It allows detect errors prematurely in the design phase (Denning et al., 1989). Therefore simulation is seen as a test case (Norton and Suppe, 2001), where checks are made to a higher level of abstraction. There are some control network simulators like DOMOSIM (Bravo et al., 2006) and VISIR (González et al. 2001) that are orientated to teaching methodology of facilities design. These tools present negative aspects like: are oriented to one technology or are not valid for professional environment.

The proposal gathered in this paper is to provide an environment to provide control network architectures in the digital home. The objective is that these architectures can be valid for any technology. We are going to pay special attention to network simulation task.

2 MODELING CONTROL SYSTEMS

The technologies and methods used for modelling home automated systems are based on the use of very low level technologies (Muñoz et al., 2004). The great diversity of control technologies causes

that the system creation, following bottom-up methodologies turns out to be a complex task.

The top-down methodologies are characterized essentially abstract. They require that design network is conceived before any consideration imposed by the technologies. A model based on Model Driven Architecture (MDA) (Mellor et al., 2004) and Services Oriented Architectures (SOA) (Newcomer and Lomow, 2005) is proposed. It consists in three layers called: functional, structural and technological. Each layer is defined by the corresponding question:

What features I want to offer (functional). The design will provide features, and will be composed by a set of services.

How should behave services (structural). How relate them to provide the features.

What technologies will implement the system (technological). The implementation technology will be chosen among the available technologies.

Functional is the most abstraction layer. It describes installation features. It avoids thinking about how to do this and technology implementation. In this layer, the control installation, CI , is defined by a set of services, Si , (1). Services, Si , need to satisfy a set of tasks, ti (2).

$$CI = \{S_1, S_2, \dots, S_n\} \quad (1)$$

$$S_i = \{t_{i1}, t_{i2}, \dots, t_{in}\} \quad (2)$$

The next level of abstraction is called structural. It is focuses on the structure and generic devices behaviour. Since the structural layer, the control installation, CI , is composed of a set of generic resources, Rs , and a wide range of connections, C , which are established between resources (3).

$$\begin{aligned} CI &= CI(Rs, C) / \\ Rs &= \{Rs_1, Rs_2, \dots, Rs_n\}, \\ C &= \{C_1, C_2, \dots, C_q\} \end{aligned} \quad (3)$$

A resource represents the entity that provides some tasks, tij . Resources are represented as a series of tasks, tij , offered to other entities (4).

$$Rs_i = Rs_i \{t_{i1}, t_{i2}, \dots, t_{im}\} \quad (4)$$

Connections are seen as associations between two resources, Rsi and Rso (5).

$$C_i = C_i(Rs_i, Rs_o) \quad (5)$$

Lower abstraction layer is technological. It is an instance of structural layer using a specific technology. Resources are defined by the set of tasks, Ti , and by set of characteristics, CAi , (6).

$$\begin{aligned} R_i &= R_i(T_i, CA_i) / \\ CA_i &= \{ca_{i1}, ca_{i2}, \dots, ca_{ip}\} \end{aligned} \quad (6)$$

In order to design specific system implantation is necessary to make the transition from the functional to structural and finally, to technological. To achieve the first transition, the services should have all their tasks matched with some of the tasks that provide the resources of the technological layer. Therefore should there some task, txy , belong to any resource, Rsx , which is equivalent to the task, tij , required for service Si . This must be met for all tasks, tij , required by the service, Si (7).

$$\begin{aligned} \exists t_{xy} \in Rs_x / \\ t_{xy} \equiv t_{ij}, \forall t_{ij} \in S_i, Rs_x \in Rs \end{aligned} \quad (7)$$

Structural technological transition needs to match generic resources Rs , with technological resources Ri . Therefore all tasks, txy , from all generic resources, Rsx , should be matched with task, tij , from technological resources Ri . This matching must be among equivalent tasks, (8).

$$\begin{aligned} \forall Rs_x \in Rs, \exists Ri \in R / \\ t_{xy} \equiv t_{ji}, \forall t_{xy} \in Rs_x, t_{ji} \in Ri \end{aligned} \quad (8)$$

3 TRASGU: DESIGN ENVIRONMENT

Trasgu is a design environment based on the previously model defined. The installation is designed from a higher level of abstraction and the specific implementation aspects are chosen in last steps. It provides robustness design and reduction of development time, because transitions from the highest abstraction level to the lowest are progressive and simple.

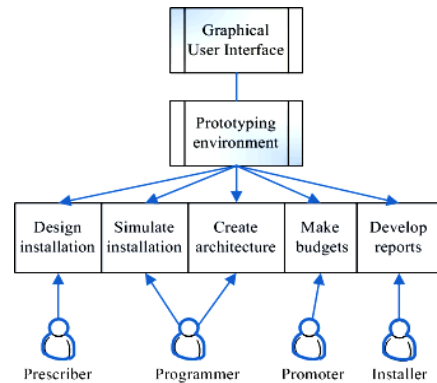


Figure 1: Environment features and their possible users.

Environment provides the following features: designing a control installation independently any technology; perform simulations to verify and validate that our design meets users specifications; create architecture in agreement to the chosen technology for implementation; making budgets with each technology; develop different types of reports. These features will be used by their respective actors who are involved in a control installation: designers, integrators, property developers, engineer... (See figure 1).

The installation design is the first task. First of all, services (2) should be added then input and output resources (4) should be added and connected with their corresponding services.

Network design is simulated in order to guarantee that design satisfies specification. This simulation will be explained in next points. The architecture creation task allows architecture generation that will implement the design in a real installation. This architecture is based on a middleware (Valdivieso et al., 2007) (Fuster et al., 2005) that provides communication among different control technologies. The budget creation task generates budgets from the technological design. The reports development task allows generate some types of reports: wired connections, devices situation, etc.

4 SIMULATION

The environment is designed to perform simulations from different abstraction levels. Simulations are from functional layer (1), (2), structural layer (3), (4) and (5) and technological layer (6). The functional simulation is responsible for simulating the behaviour of generic control network. With this validation the generic device configuration and connections can be ensured. The structural simulation includes the functional, but adds new features, like the real resources position and installation regulation. The technological simulation determines the real behaviour that the implemented control network provides.

Simulation calculations are realized by an external module that has been developed in Matlab / Simulink. The communication between the simulation calculations module and environment has been done through a Java library called jMatLink (Müller and Waller, 1999). It is responsible for sending commands to Matlab. A library called jSCA has been developed. It is responsible for encapsulating Matlab commands for facilitate the

communication. The jSCA features are implemented as methods which allow: create Matlab instances; create, configure, and remove blocks in Simulink; configure parameters simulation, and obtain the simulation results. This library is a level above jMatLink. The environment calls jSCA library and this library calls jMatlink library.

Prototyping Environment	jSCA	jMatlink	Matlab Engine	Simulink
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Figure 2: Architecture that achieves communication among Java application and Simulink.

The architecture that achieves the communication among Java application and Simulink is showed at figure 2. The first layer is the own Trasgu that communicates with jSCA library in order to use jMatlink library that allows communication with matlab engine. It is daemon that is listening matlab commands thrown by jMatlink and uses own Simulink library for simulate.

4.1 Implementation

The environment has been implemented in Java and uses an information system implemented in XML. These XML files reflect information of the resources that can be used in the installation and the information about the current network. This information is reflected from abstraction layers defined at the model.

Environment presents distinct areas. Services that the user can add to the network are at the top of the window. Generic resources are on the left side of the window and can be used in the design. Building plant is on the centre. Services and resources can be added to this area. Services (2) define their behaviour based on inputs from input resources (4) and provide outputs to output resources (4). These functions are logical, arithmetical and comparison operators. This specification is done in a form that contains inputs, output and operators that allows interconnect them. Figure 3 shows control network designed at environment.

Simulation requires a parallel model from the functional layer in Simulink. This model is equivalent to the XML files defined in the information system used by the environment. Each resource defined in the environment is corresponded by another defined in Simulink library created for control network simulation. The Simulink model consists in a block set formed by input blocks, output blocks, input-output blocks, and connections in order to establish a logic circuit. For this purpose

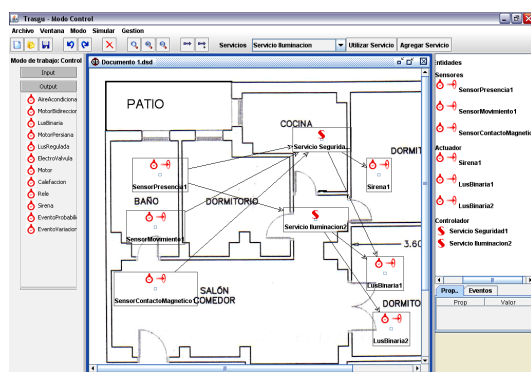


Figure 3: Network designed at environment.

there are two block types: discrete and continuous. The discrete blocks are for digital devices, and continuous are for analogic devices.

The simulation starts creating an equivalent control network in Simulink. The corresponding network blocks must be added to create the mdl file. Parameters of each block are configured and connections among blocks are created. The last step is to add probability or schedules events for activate sensors. Finally the mdl file is created and Simulink executes the simulation and the environment reads values from all Simulink network blocks and represents them at environment.

5 CONCLUSIONS

This paper presents a design and simulation environment of control networks in digital home. The objective is to facilitate the tasks of designing and validating control networks. A top-down methodology is proposed, where technology implementation choice is left to the end phase of designing process. The environment kernel is the control network model around different abstraction layers: functional, structural and technological.

Simulation is presented as a new phase in methodology of design control network. It reduces costs and helps us to design effective and efficient control networks.

The future work is aimed to deepening in aspects of results generalization: new models for structural and technological layers, simulation of technological layer and interactive simulation module.

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