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ASPic: an Acting system based on Skill Petri net Composition

Charles Lesire\(^1\) and Franck Pommereau\(^2\)

Abstract—While developing automated planning algorithms helps in making robots more autonomous, the development of acting systems is also of major concerns. Acting systems aim at refining high-level actions into executable commands, while managing access to resources, possible failures, or any other kind of unpredictable situation from the planner point of view. Improving the trust on autonomous robots also requires to have a formal model of acting, and the capability to perform some analysis on this model. In this paper, we present ASPic, an acting system based on the modeling of robot’s skills using a specific control-flow Petri net model. The skills can then be combined using well-defined operators to build a complete plan that refines a high-level action. Some good properties are guaranteed by construction, while others can be verified on the resulting plan model. This paper also presents the application of ASPic to an area protection mission by an autonomous surface vehicle.

I. INTRODUCTION

Autonomous robotics researches bubble up. Recent works on making robots autonomous integrate advanced AI techniques, such as learning, decision theory, or automated planning. These techniques allow the robots to reason about their states and goals in order to choose the appropriate actions to execute.

However, few works deal with the way to execute correctly these actions. Managing action execution calls for refining symbolic actions into executable commands, monitoring their execution, and reacting to failures and hazards. All these features are brought together under the term Acting [1], [2]. While acting systems were an active field a couple of decades ago (especially for space exploration systems [3]), they have been a bit abandoned in favor of pure AI. Nevertheless, autonomous robots make it necessary to demonstrate the safety and reliability of autonomous acting behaviors.

In this paper, we present ASPic, an acting system that is based on the Petri net formalism. Petri nets are a natural choice to model concurrent systems as they allow to precisely represent the management of shared resources among concurrent processes, with a natural expression of conflicts, independence, causality, etc. Moreover, Petri nets form a very flexible family of formalisms which is easy to adapt to our exact needs, and they come with a wide range of analysis techniques as well as numerous tools already available. In particular, model-checking allows to formally assess dynamic properties of Petri net models in an automated way. ASPic is based on composition of elementary Petri nets, representing the basic skills of the system. Using such compositions allows first to build an executable model of a plan in a hierarchical way, and second to ensure some sound construction of the acting model.

Section II presents some works related to acting in robotics. Petri net skill models and their composition to build an action plan is presented in Sect. III. The implementation of ASPic and its application to a marine area protection is presented in Sect. IV.

II. RELATED WORKS

According to [1], Acting is the component of a deliberative architecture that has to manage: plan refinement (i.e., how to decompose a plan action down to executable commands), reaction to events (that may require plan adaptation or plan refinement adaptation), time management (when planned actions consider deadlines, durations, or time constraints), non-determinism (i.e., partial or noisy observations during the mission execution), and plan repair (when, why, how to trigger the planning component).

Historical researches on acting systems have essentially dealt with execution control, i.e., the way to refine plans into commands. Several execution frameworks used in space robotics are described in [3]. Their analysis has led to Plexil [4], a language and an executive that aggregates the features of a lot of former execution control systems. Plexil provides constructs to describe hierarchical decomposition of plans into a tree of nodes. Leaf nodes are commands sent to the physical system or read-access to system variables. The Plexil language allows to describe sequences of nodes, concurrent execution, branches and loops. However, it does not rely on a formal mathematical model, and does not support advanced features to change the refinement according to events, nor provides analysis tools.

Among the architectures for autonomy that integrate planning and acting, T-REX [5] made a step towards the formalization of the refinement process, by specifying exchanges between reactors through the manipulation of timelines. The hierarchical (and temporal) decomposition of the decision is then clearly specified through access to timelines (one timeline is writable only by one reactor). However, the implementation of the reactors is not formalized, then preventing to make some safety analysis of the overall system.

Safety and reliability analysis in acting systems requires formal models of acting. The ROS ecosystem provides some ways of specifying action refinements, through hierarchical state-machines [6], [7]. In these tools, the basic elements correspond to ROS primitives (e.g., topic listening or service calls), and the design process is very permissive. Even if some analysis may be possible on these models, it would
be interesting to restrain the possible constructs to define some patterns that preserve some properties by construction. Moreover, basic concepts are ROS-specific, that would make difficult to reuse the models and analyses in another context.

Other works used Petri nets as a formal model of robot actions. [8] models elementary actions by generalized stochastic Petri nets, with one place representing the action instance, and one place for each predicate used as a precondition or an effect of the action. The Petri net model corresponds to a PDDL-like description of actions, and predicate places are then used to causally link actions, as a task planning algorithm would do. These Petri net models are not made to describe operational behaviors: there is no specification of how to execute commands, nor composition operators allowing to describe branches, loops, or other operational constructs. Petri Net Plans [9] formalize elementary actions in terms of phases: an initial place, an execution place, and a termination place. They distinguish ordinary (deterministic) actions and sensing (Boolean) actions. They also define operators to combine actions: sequences, conditions, iterations and interruptions. However, they do not discuss formal properties or analysis of the resulting Petri net plan, and they do not manage failures as a possible action outcome.

While [9] makes an ad-hoc description of elementary actions, some common Petri net frameworks exist to model such processes, for instance workflow nets [10] (to model business processes and operations), and M-nets [11]. In this paper we use an algebra of colored Petri nets inspired from [12], [13]: on the one hand they form a variant of co-loured Petri nets [14] whose tokens carry values on which arbitrary computation can be performed; on the other hand they have an explicit control-flow that enables for composition operations like it is usual with process algebras. We borrow the classical operators of sequential composition, choice, and parallel composition as found in [13], and we adapt them to handle errors (exceptions) as in [12] but in a simpler way that is more suited to our context. We also define new operators that were not considered in the past.

III. ASPiTc

ASPiTc is an acting system based on Petri net compositions. Compositions allow to assemble elementary actions into more complex plans through consistent operators. Elementary actions are often called skills [2], as they correspond to the several capacities or behaviors that are available at the platform level. For instance, skills was the term used for the elementary behaviors of the first behavior-based architectures for autonomous navigation [15], [16].

ASPiTc formalizes skills through specific models of Petri nets using control-flow semantics. These skills can then be composed to form an action plan, through operators that manage nominal execution (sequences, concurrence), observations (through conditions evaluated at execution time), or failures (using exception management).

A. Background and basic definitions

To start with, let us recall that a multiset is a collection of unordered elements allowing repetitions. For instance \{a, a, b\} is the multiset with two a’s, one b and no other values. Multisets may be added, subtracted, compared, or multiplied by non negative integers. For instance, we have \{a, b\} + \{a\} - \{b\} = 2 \times \{a\} \leq \{a, a, a, b\}. Curly brackets around multisets my be omitted for brevity. We note by $X^*$ the set of multisets over $X$.

We consider a variant of Petri nets colored by an abstract color domain, which is both more general than a specific programming language, and simpler to define. We note by $\mathbb{D}$ the set of all the data values (e.g., integers, Boolean values True and False, regular “black token” $\bullet$, “white token” $\circ$ for errors, etc., including data structures) and assume that there is a value $\bot \notin \mathbb{D}$ corresponding to the undefined value. We note by $\mathbb{E}$ the set of all the expressions, built on the top of $\mathbb{D}$ and a set $\mathbb{V}$ of variables. Given $e \in \mathbb{E}$, we note by $\text{vars}(e) \subseteq \mathbb{V}$ the set of variables involved in $e$. We may evaluate $e$ using a binding $\beta$ that is a function $\text{vars}(e) \to \mathbb{D} \cup \{\bot\}$, and we note by $\beta(e)$ the result of evaluating $e$ with respect to $\beta$; this may be a valid value if the evaluation is possible, or $\bot$ if anything goes wrong during the evaluation (e.g., a syntax or typing error, a division by zero, etc.). For instance, for $\beta \equiv \{x \mapsto 1, y \mapsto 2\}$ we usually have $\beta(x+y) = 3$ and $\beta(y/(x-1)) = \bot$ (which actually depends on the concrete colour domain considered).

We now define our variant of colored Petri nets with control-flow, that is inspired from [12], [13] and adapted to our specific needs in this paper.

Definition 1 (control-flow Petri nets): A control-flow Petri net (CFPN) is a tuple $N \equiv (P, T, \ell, \sigma)$ such that:

- $P$ is the non-empty set of places;
- $T$, disjoint from $P$, is the non-empty set of transitions;
- $\ell$ is the labeling function such that:
  - for all $p \in P$, $\ell(p) \subseteq \mathbb{D}$ is the type of $p$, i.e., the data values it may contains,
  - for all $t \in T$, $\ell(t) \in \mathbb{E}$ is the guard of $t$, i.e., a Boolean function that serves as a condition for the firing of $t$,
  - for all $(x, y) \in (P \times T) \cup (T \times P)$, $\ell(x, y) \in \mathbb{E}^*$ is the arc from $x$ to $y$, i.e., the multiset of expressions representing the tokens carried by the arc;
- $\sigma$ is the status function such that:
  - for all $p \in P$, $\sigma(p) \in \{\text{entry, i, x, ε, }\} \cup \mathbb{D}$ where $\varepsilon$ denotes an entry place, $i$ denotes an internal place, $x$ denotes an exit place, all together forming the control-flow places, $\varepsilon$ denotes a buffer place that is not shared (private to the net), and any status in $\mathbb{D}$ denotes a buffer places to be shared with other nets,
  - for all $t \in T$, $\sigma(t) \in \mathbb{N} \cup \{\bot\}$ denotes whether $t$ is a regular transition ($\bot$) or a placeholder transition (any $n \in \mathbb{N}$ intended to be substituted by the $n$th argument of a net operation (see Sect. III-D). We assume that $\{\sigma(t) \mid t \in T\} \setminus \{\bot\}$ is an initial segment of $\mathbb{N}$, i.e., that placeholder transitions are
tokens to be consumed as specified by the input arcs (from $\beta$)

Intuitively, Petri nets are marked by tokens that are multisets $t$.

$\sigma$ be called and managed by the Acting system. Although we

remote procedure available on the robot platform, that will

correspond to one of these modules, can then be seen as a

output parameters, as well as required resources. A skill, that

the two former. The modules definition includes input and

produce tokens as specified by its arcs (and $t$)

produced tokens. We shall use in particular, for

annotation, returns the actual multiset of consumed

or produced tokens. We shall use in particular, for

Definition 2 (well-formedness): A CFPN $(P, T, \ell, \sigma)$ is

called well-formed iff:

1. For all $p \in P^e$ we have $\ell(p) = \{\bullet, \circ\}$.
2. $N$ has exactly one entry place.
3. $N$ has exactly one exit place.
4. $N$ has at most one place of each status in $\mathbb{B}$.

Black tokens • are used to represent the regular execution of the control-flow, while white tokens ¤ represent errors or exceptions.

B. Skill Petri nets

A skill represents a behavior or a capacity of a robotic system. It corresponds to commands or behaviors that can be triggered on the robot platform. These behaviors may not only deal with achievement of movements, but also with observations. Performance Level Profiles [17] is a recent work that has proposed four types of modules available at the robot platform level: Achieve, Observe, Maintain and Detect, the two last being special cases or constructs of the two former. The modules definition includes input and output parameters, as well as required resources. A skill, that corresponds to one of these modules, can then be seen as a remote procedure available on the robot platform, that will be called and managed by the Acting system. Although we used the description in [17] as a starting point for describing skills, the models described hereafter are generic enough to meet any similar representation of robots’ skills we found in the literature.

A skill Petri net (SkPN) models such a skill (see an example in Fig. 1) and is parametrized by the resources it requires in order to be executed, which may be locks (mutex on resources), inputs (the states it reads upon start-up), or outputs (the states it updates on completion). More precisely, we consider two kind of resources:

- locks from a set $L$ are resources whose access is exclusive and may be reserved or released, but that are not associated with a particular value. However, several instances of a lock may be available and several instances may be reserved or released at the same time. Locks will be modeled by buffer places marked with as many black-tokens • as the number of instances;
- states from a set $S$, disjoint from $L$, are resources associated with a value which may be read (inputs) or updated (outputs). States will me model-led by buffer places as well, whose marking is a single token in $\mathbb{I}$ representing the current value of the state.

To conveniently model resources as places, we assume that each resource is a valid buffer place status, i.e., $L \cup S \subset \mathbb{B}$.

Intuitively, a SkPN is then defined by: its control flow places, a transition $t_{start}$ that triggers the start of the skill execution, a transition $t_{stop}$ fired when the skill nominally ends, a transition $t_{except}$ fired when the skill fails, and a place $p_{exec}$ that stores the skill’s state during its execution. These nodes are surrounded with buffer places to model the resources used by the skill: when $t_{starts}$ fires, it reads the skill’s inputs and acquires its locks, then when $t_{stop}$ (or $t_{except}$) fires, it writes the skill’s outputs and releases the locks.

![Fig. 1: A Skill Petri net with $I \overset{df}{=} \{\text{call}\}$, $L \overset{df}{=} \{\text{lock} \mapsto 2\}$, and $O \overset{df}{=} \{\text{ret}\}$. Control-flow places are depicted in blue, the other places represent resources. Places’ labels are their status except for $p_{exec}$ whose name is also indicated. Some labels • on arcs are omitted as well as curly brackets around multisets. The arcs between $t_{except}$ and $ret\text{lock}$ are the same as for $t_{stop}$ as sketched in gray.](image)
Definition 3 (skill Petri nets): A skill Petri net (SkPN) is a well-formed CFPN \((P, T, \ell, \sigma)\) parametrized by \(L, I, \) and \(O\) such that:

- \(L\) is a function \(\{l_1, \ldots, l_n\} \subseteq L \rightarrow \mathbb{N}\) representing the locks required by the SkPN together with the number of instances of each;
- \(I\) is a set \(\{i_1, \ldots, i_m\} \subseteq I\) representing the inputs of the SkPN;
- \(O\) is a set \(\{o_1, \ldots, o_k\} \subseteq O\) representing the outputs of the SkPN;
- its entry, internal, and exit are respectively called \(p_e\), \(p_i\), and \(p_o\);
- there is a place \(p_{exec} \in P\) such that \(\sigma(p_{exec}) = \varepsilon\) and \(\ell(p_{exec}) = D \times ([|D|]_I \cup [|D|]_O)\), where \([|D|]_X\) denotes the set of all vectors on \(D\) indexed by \(X\);
- for each \(l \in \text{dom}(L)\) there is a place \(p_l \in P\) such that \(\ell(p_l) = \{\bullet\}\) with \(\sigma(p_l) = l \in B\) is a unique status corresponding to the resource name;
- for each \(i \in I\) there is a place \(p_i \in P\) such that \(\ell(p_i) = \mathbb{D}\) and \(\sigma(p_i) = i\);
- for each \(o \in O\) there is a place \(p_o \in P\) such that \(\ell(p_o) = \mathbb{D}\) and \(\sigma(p_o) = o\);
- \(T \equiv \{t_{\text{start}}, t_{\text{stop}}, t_{\text{except}}\}\) such that \(\ell(t) = \text{True}\) and \(\sigma(t) = \perp\) for all \(t \in T\);
- arcs as specified in Fig. 2.

C. Execution handlers

Skills are behaviors, or processes, available at the robot platform level. In order to interact with actual skills execution, the Acting system needs to manage skill handlers. SkPN must then be equipped with skill handlers in order to interact with skill execution, i.e., start skill execution, monitor success or failures, get returned values, etc.

A skill handler can be defined as a Petri net that contains an execution place \(p_{exec}\) that will be merged with the \(p_{exec}\) of the SkPN. Figure 3 shows a basic handler used to simulate the execution of skills. An handler to interact with ROS actions is presented in Sect. IV-C.

We thus define a handler net and the operation that plugs it onto a SkPN.

D. ASPiC operators

Operators are aimed at modifying or composing Petri nets from skills up to action plans. An operator is defined by a so-called operator net (noted \(N_0\) in the following definition) that is a CFPN with placeholder transitions aimed to be substituted with the operators arguments (so-called operand nets). This substitution consists in connecting the control-flow of operand nets as specified in the operator net, then merging the buffer places representing the same resources. Formally we have:

Definition 5 (SkPN operators): Take \(n > 0\) and let \(\{N_1, \ldots, N_n\}\) be \(n\) CFPN such that \(N_i \overset{df}{=} (P_i, T_i, \ell_i, \sigma_i)\). Let \(N_0 \overset{df}{=} (P_0, T_0, \ell_0, \sigma_0)\) a CFPN such that it has \(n\) placeholder transitions \(\{t_1, \ldots, t_n\}\). We note by \(e_i\) and \(x_i\) the entry and exit place of each \(N_i\) for \(0 \leq i \leq n\). We assume \(P_i \cap P_j = \emptyset\) for \(0 \leq i \neq j \leq n\). This allows to define a \(n\)-ary operation noted as \(N_0[N_1, \ldots, N_n]\) that substitutes each \(t_i\) in \(N_0\) with the corresponding \(N_i\), yielding a new CFPN that is defined in two steps. First, transitions \(t_i\)'s are substituted by nets \(N_i\)'s whose control-
flows are connected, which builds an intermediary CFPN $N \triangleq (P, T, \ell, \sigma)$ defined by:

- $P = P_0 \cup \bigcup_{1 \leq i \leq n} (P_i \setminus \{e_i, x_i\})$;
- $T = (T_0 \setminus \{t_1, \ldots, t_n\}) \cup \bigcup_{0 \leq i \leq n} T_i$;
- $\ell = \ell' \cup \bigcup_{0 \leq i \leq n} \sigma_i |_{P, T}$ and $\sigma = \sigma' \cup \bigcup_{0 \leq i \leq n} \sigma_i |_{P, T}$,

where $\ell_i |_{P, T}$ (resp. $\sigma_i |_{P, T}$) is $\ell_i$ (resp. $\sigma_i$) restricted to the domain $(P_i \cap P) \cup (T_i \cap T) \cup ((P_i \cap P) \times (T_i \cap T))$, and with $\ell'$ and $\sigma'$ defined as the smallest functions such that:

- for every $1 \leq i \leq n$, every $c \in P_0^e$, and every $t \in T_i$ such that $\ell_i(e_i, t) \leq \ell_0(c, t)$, then we have $\ell'(c, t) = \ell_i(e_i, t)$ and $\sigma'(c, t) = \sigma_0(c, t)$,

- for every $1 \leq i \leq n$, every $c \in P_0^e$, and every $t \in T_i$ such that $\ell_i(t, x_i) \leq \ell_0(t, c)$, then we have $\ell'(t, c) = \ell_i(t, x_i)$ and $\sigma'(t, c) = \sigma_0(t, c)$.

Then, the result of $N_0[N_1, \ldots, N_n]$ is defined from $N$ as follows: for every $\text{stat} \in \mathbb{B}$ we merge all the places in $\{p \in P_i \mid 0 \leq i \leq n, \sigma_i(p) = \text{stat}\}$.  

We consider specifically the operators nets depicted in Fig. 4 and we use natural notations for the operations, for instance $N_1 \odot N_2$ instead of $N_0[N_1, N_2]$, $\text{retry}(N)$ instead of $N_{\text{retry}}[N]$, or $\neg N$ instead of $N_{\neg}[N]$.  

1) **Sequential composition**: $N_1 \odot N_2$ (Fig. 4a) enforces the execution of $N_1$ followed by that of $N_2$, except if $N_1$ terminates with an error, putting $\odot$ in its exit place, in which case the execution of $N_2$ is skipped thanks to the arc on the right side.

2) **Choice**: $N_1 + N_2$ (Fig. 4b) allows to execute either $N_1$ or $N_2$, which is chosen in a non-deterministic way if both are possible.

3) **Concurrent composition**: $N_1 | N_2$ (Fig. 4c) allows to execute both $N_1$ and $N_2$ concurrently. When both are terminated, the whole composition results in a success if both nets succeeded (through transition $t_{\text{successa}}$), or a failure if at least one of the two nets has failed (through transition $t_{\text{failure}}$).

4) **If-Then-Else**: A common situation that arises when decomposing actions is to react to the successful or failed execution of a skill. In that case, one may want to execute the sequel of a nominal plan in case of success, and perform a specific action in case of failure. $\text{ite}(N_1, N_2, N_3)$ (Fig. 4d) allows to handle such a situation by executing first $N_1$, and then $N_2$ if $N_1$ succeeds, otherwise it executes $N_3$.

5) **Race composition**: The concurrent composition $N_1 | N_2$ can only terminate when both $N_1$ and $N_2$ have terminated. In some situations, one may want to execute $N_1$ and $N_2$ concurrently, and continue the plan execution as soon as one of both has finished. $N_1 \otimes N_2$ (Fig. 4e) allows this by starting both $N_1$ and $N_2$ but then, if $N_1$ terminates first, it allows the firing of $t_{\text{first,1}}$ which terminates the whole composition; then, when $N_2$ terminates, its resulting token is cleared thanks to transition $t_{\text{snd,2}}$. The situation is symmetrical if $N_2$ terminates first. Selecting between $t_{\text{first,1}}$ and $t_{\text{snd,2}}$ is ensured through the central internal place and the inhibitor arcs: when the place is marked (after $t_{\text{start}}$), only the $t_{\text{first,1}}$’s are possible and their firing consumes the token, which allows then only the $t_{\text{snd,2}}$’s.

6) **Retry**: $\text{retry}(N)$ (Fig. 4f) is another common construct related to exception management. It allows to retry the execution of $N$ in case of error, until an execution eventually succeeds.

7) **Negation**: $\neg N$ (Fig. 4g) is the negation operator that inverts the termination status of $N$ by transforming a regular token into an exception token and vice-versa. It is useful when a skill returns successfully but from a supervision point of view, this success must be considered as a failure, for instance for skills that detect abnormal situations.

![Fig. 4: ASPiC operator nets. All places are control-flow places whose status is depicted as a label. Dashed transitions are placeholder, transitions status are depicted inside the transitions, and omitted guards are True. Omitted arcs labels are • and arc status are $\sigma_\top$ except inhibitor arcs ($\odot$ shaped) whose status is $\sigma_\bot$.](image-url)
considered applications. For instance, in workflow PN [10],

in the literature, depending on the particular needs of the

likely that we have such a property because our operator nets

may not be marked by more than one token. This is desirable

reach an exit marking (i.e., a marking in which the exit

be the number of placeholder transitions in

N
i

Condition (1) holds because N respect them and N

Condition (2) and (3) hold because the composition

in several simultaneous invocations of the underlying skill.

is named cleanness and has been relaxed in [19] when buffer

soundness is defined by:

∀ M, ([p_k] ⇒ M) ⇒ (M ⇒ [p_k]) (6)

∀ M, ([p_e] ⇒ M ∧ M ≥ [p_s]) ⇒ (M = [p_s]) (7)

∀ t, ∃ M, M', [p_a] ⇒ M' ⊢ M (8)

This can be read as: (6) any reachable marking allows to

reach an exit marking (i.e., a marking in which the exit place

marking is the only marked place, and (8) every transition may

be fired following a path from the initial marking. Properties (6)

and (8) make sense for workflows but are rarely found in

general because they depend too much on the system being

modeled. For instance, (6) may be relaxed to requiring that

the only deadlocks are exit markings, but the system may

never reach them (which is usually highly desired for a

controller that is not supposed to stop). In [18], property (7)

is named cleanness and has been relaxed in [19] when buffer

places have been introduced. Indeed, such places may retain

tokens from one execution of a subnet to be used in a

further execution. This is the case in ASPiC where buffer

places model the resources of the system which are globally

available. The solution in [19] was to restrict cleanness to

the control-flow places, which can be formulated here for

any initial marking M_0 such that M_0(p_k) ∈ {{•}, {◦}} and

p ∈ P^e \ \{p_k\} ⇒ M_0(p) = ∅ as:

∀ M : M_0 ⇒ M ∧ M(p) ∉ ∅

⇒ M(p) ∈ {{•}, {◦}} ∧ (p ∈ P^e \ \{p_k\} ⇒ M(p) = ∅) (9)

In the current state of ASPiC, this property can only be

verified dynamically because operator ◦ is not clean and

allows to reach an exit marking while one of the nets is still

active (and thus has its control-flow marked).

[18], [19] also introduce another notion of well-behavior

through control-safety that states that a control-flow place

may not be marked by more than one token. This is desirable

to ensure that at any point of a system execution, each

activity cannot be activated more than once, in particular,

a skill net cannot be multiply activated which would lead

to several simultaneous invocations of the underlying skill.

Like cleanness, control-safety is guaranteed by constructions

in [18], [19] thanks to syntactical restrictions on the basic (here

SkPN) and operator nets.

Unfortunately, ◦ is not control-safe when nested into a

retry: a new instance of the still active net may be started

when the retry loops.

We thus need to find a better definition for N_0 before

to be able to provide a satisfactory notion of soundness that

would encompass cleanness and control-safety and would

be guaranteed by construction. This is left as a future work. In

the meantime, this property must be checked by computing

the state space of the Petri net. However, if ◦ is not used, it is

likely that we have such a property because our operator nets

and the SkPN basically respect the syntactical restrictions

used in [18], [19] to enforce cleanness and control-safety.

F. Properties

Specifying an acting system using Petri nets allows to

perform some analysis to verify that the plan refinement

under execution has some good properties. By enforcing a

structured way of modeling systems, ASPiC also aims at

providing some of these properties by construction.

1) Well-formedness: This property ensures that our

operations are well defined (in particular, we have the required

entry/exit places to correctly apply the substitutions of place-

holders transitions). First, we state that the result of plugin a

handler onto a SkPN is well formed; then we state that our

operations preserve well-formedness.

Proposition 1: Let N_h be a handler and N a SkPN, then

N \boxplus N_h is well-formed. □

Proof: Condition (1) holds because N is well-formed and

the internal places of N_h respect the condition. Conditions (2) and (3) hold because N respect them and N_h has no

entry nor exit place. Condition (4) holds because operation

\boxplus explicitly merges the places with the same status. ■

Proposition 2: Let N_0 be one of the operator nets from

Fig. 4 let n be the number of placeholder transitions in

N, and let N_1, . . . , N_n be n well-formed nets. Then, N \boxplus

N_0[N_1, . . . , N_n] is well-formed. □

Proof: Condition (1) holds on all the N_i’s for 0 ≤ i ≤ n

so it also holds on N whose places are all copied from the

N_i’s. Conditions (2) and (3) hold because the composition

removes the entry and exit places from the operand nets and

preserves only those from N that itself respects the condition.

Condition (3) holds because the operation explicitly merges

the places with the same status. ■

Well-formedness is also desirable because it ensures a

consistent handling of resources through condition (4): there

is only one place for each resource so that locks and states

values are uniquely represented. In particular, acquiring/releasing a lock is global on the system, and every state

has a unique value across all the system.

2) Soundness: This property can be considered as the

behavioral version of well-formedness. It guarantees that

only “good” executions can occur, i.e., that the Petri net is

well-behaved. This can be verified on the state space or

guaranteed by construction through syntactical restrictions

like those we have considered for well-formedness.

Various definitions of soundness have been considered

in the literature, depending on the particular needs of the

considered applications. For instance, in workflow PN [10],

\uboldsymbol{L} \text{ such that we have } p_l \in P \text{ with } \sigma(p_l) = l,

\text{then } M(p_l) = k_l \times \{•\} \text{ where } k_l \geq 0 \text{ is the number of }

available instances of resources } l \text{ in the system modeled;}

\text{if } p_s \in P \text{ with } \sigma(p_s) = s, \text{then } M(p_s) = \{v_s\} \text{ where } v_s \in D \text{ is the initial value }

of state } s \text{ in the system modeled;}

no other place is marked. ◯
IV. AREA PROTECTION WITH AN AUTONOMOUS SURFACE VEHICLE

A. Mission description

We consider an Autonomous Surface Vehicle (see Fig. 5) that performs an area protection mission. That ASV has to patrol within a given zone and detect intruders. On detection, the ASV may have to intercept the intruder. The ASV also avoids obstacles on its path. After an avoidance or an interception, the patrolling is resumed.

![An Autonomous Surface Vehicle controlled by ASPiC](image)

**Fig. 5: An Autonomous Surface Vehicle controlled by ASPiC**

B. ASV Skills

The ASV platform provides several skills, defined following the concepts and types described in [17], each skill being managed by a SkPN:

- **Achieve skills:**
  - \( N_{\text{traj}} \): execute a given trajectory;
  - \( N_{\text{goto}} \): move the ASV to a target pose;
  - \( N_{\text{intercept}} \): execute the interception maneuver;

- **Observe skills:**
  - \( N_{\text{comp}} \): compute a patrolling trajectory according to a given start pose, and a patrolling duration;
  - \( N_{\text{pose}} \): observe the current pose of the ASV;

- **Maintain skills:**
  - \( N_{\text{keep}} \): maintain the ASV at its current pose;

- **Detect skills:**
  - \( N_{\text{obs}} \): detect an obstacle triggering an avoidance;
  - \( N_{\text{avoid}} \): detect the end of an avoidance maneuver (the avoidance itself is automatically executed by the platform).

These skills are implemented using the MAUVE middleware [20] and provide a ROS actionlib interface in order to be manageable by ASPiC.

C. ASPiC Implementation

ASPiC has been implemented as a ROS node that receives actions to perform from a Planning node. SkPN and composition operators have been implemented in Python, using the SNAKES library [21]. To interface with the ASV platform, new handlers have been defined to manage ROS actions. The ROS handler (see Fig. 6) has a behavior that abstracts the state-machine of the ROS actionlib client. The \( p_{\text{cl}} \) place owns a ROS actionlib client object \( cl \). When the status is pending, transition \( t_{\text{activate}} \) can fire, and calls the ROS action server to execute the action. The skill status is then active. Then each time transition \( t_{\text{status}} \) is fired, the status is updated from the client object (using \( cl.st \)) and in case of termination (either succeeded or failed), the return value is retrieved using \( cl.val \).

D. Specification of ASV actions

As discussed in the introduction, ASPiC is aimed to be the acting system of a deliberative architecture. It is then supposed to be fed up with action plans coming from a Planning component.

In the ASV mission, we consider that the Planning component plans patrol actions of a given duration, intercept actions when intruders must be intercepted, and station actions in which case the ASV has to join a position and keep it. ASPiC has then to refine these actions and monitor their execution. The intercept actions are directly mapped to the execution of the interception skill through the SkPN \( N_{\text{intercept}} \). The station actions have simple decompositions combining a movement to the position to hold, and then keeping this position, as described by Eq. (10), where \( N_i \) denotes SkPN \( N_i \) combine with a ROS handler.

\[
N_{\text{goto}} \odot N_{\text{keep}}
\]

The patrol actions are more interesting as ASPiC uses a more complex decomposition, including obstacle avoidance monitoring. The expression defining the patrol action is given by Eq. (11).

\[
\text{retry}(\text{ite}(N_{\text{pose}} \odot N_{\text{comp}} \odot (N_{\text{traj}} \odot (\neg N_{\text{obs}}))), \quad N_{\text{pose}} \odot N_{\text{keep}}, \quad \neg N_{\text{avoid}})
\]

The first part of the action decomposition (first argument of \( \text{ite} \)) is a sequence of observing the current (i.e., initial) pose, computing a patrol trajectory, and concurrently executing this trajectory while detecting obstacles. In case of success (trajectory completely followed), the second part of the \( \text{ite} \) composition is executed. It consists of a sequence of observing the current (i.e., final) pose, and maintain this pose. In case of failure (i.e., an obstacle triggered an automatic avoidance, or the trajectory failed for another reason), the last part of \( \text{ite} \) is executed: ASPiC waits for the detection of
the avoidance end, then the retry operator will lead to a new patrol computation from current pose.

E. Experiments and Results

Several area protection missions have been realized with the ASV, on several areas, including obstacles and target interceptions. In total, the ASV has been under ASPiC control for 5422 seconds. In these missions, ASPiC has managed in total 17 patrol actions, 24 intercept actions, 7 station actions, and 14 obstacle avoidances that led to retry the patrol action. Figure 7 is a screenshot of the user interface showing the ASV trajectory. The mission depicted in Fig. 7 has lasted 1499 seconds, and the ASV has intercepted three targets, and performed 5 patrols.

We have computed the state space of the Petri nets obtained from (10) and (11), using the simulation handler of Fig. 8 in place of the ROS handler in order to simulate possible success or failure of each skill. Then we have checked their soundness as discussed in Sect. III-F.2:

- they terminate: an exit marking (i.e., one with the exit place marked) is always eventually reachable from the initial marking;
- they are clean: in every reachable exit marking, only the exit place is marked among the control flow places as specified by Eq. (9).

V. Conclusion

We have presented ASPiC, an acting system based on the representation of the elementary skills of a robotic system using Skill Petri nets, a Petri net model using control-flow semantics. ASPiC comes with composition operators that allow to build up action plans by using common operational constructs (sequence, concurrency, branches), managing failure cases using exception tokens. We have also presented and discussed some good properties to demonstrate on the resulting Petri net. ASPiC has been used to control an ASV performing a marine protection mission for more than 90 minutes, involving several actions to execute and several failures to manage. On this mission, we have used state space exploration to enforce the properties discussed before.

In future works, we aim at proving that the soundness property is guaranteed by construction, and we then have to correct the \( N_0 \) operation net and base our proofs on the work in [18], [19].

We would also like to define a Domain Specific Language to help users define their own compositions without having to directly manipulate Petri nets, and eventually use this language to automatically translate planner’s actions from a planning language (like PDDL) into ASPiC executable Petri nets.

References