

# Scoop Methodology : Modeling, Simulation And Analysis For Cooperative Systems

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**Abstract**—In this paper, we present our methodology proposal for cooperative remote systems modeling. Its aim is to develop models of existing or planned cooperative systems. These models are used to specify systems or to create dynamic working simulations. Comparative performances are deduced from the latter. The associated meta-model proposal is based, among other things, on the use of multi-agent systems, Petri nets and stochastic Petri nets. After having described the whole methodology concepts, we show a set of general results extracted from simulations.

**Keywords :** Cooperation, Cooperative systems, Multi-agent, Petri nets, Simulation, Evaluation

## I. INTRODUCTION

Cooperation is a complex activity known since the beginning of humanity. It allows other activities that would not have been possible without cooperation. It is then known as an efficiency factor for many activities.

At present, the industrial world is becoming more and more enhanced and developed by the use of new technologies. Cooperative systems take advantage of this situation. New technologies of communication, mobile terminals and data access modes, for instance, improve cooperation capabilities. But, the other side of the coin is that the complexity of the distributed system which is the support for cooperation is added to the complexity of cooperation activity.

It is then difficult to quantify the profit generated by the use of one technology or another, or the use of a particular organisation in a given cooperative system. There is a clear need for an efficient cooperative system meta-model.

This paper presents our methodology, based on a meta-model of cooperative remote systems which aim is to develop models of existing or planned cooperative systems. These models are used to specify systems or to create dynamic working simulations. Comparative performances are derived from the latter using our criteria.

Several research projects have been conducted in computer and information sciences (computer-supported

cooperative work, group decision support systems, knowledge engineering, human-computer interaction, distributed artificial intelligence and multi-agent systems, etc.) and in social sciences (organisational and management sciences, sociology, psychology, ergonomics, linguistics, etc.). After defining general cooperation concepts found in the literature, we propose a synthesis of existing work in cooperation modeling and cooperative systems modeling. Cooperation used in multi-agent systems is also described in this part of the paper.

Our methodology is then described step by step. The associated meta-model is also presented in this part. We describe more particularly our hypothesis, formal specification of system components, structural modeling meta-model, interaction Petri nets modeling methodology, knowledge and behaviour modeling tools that lead to the multi-agent system design.

The last part shows the results obtained using stochastic Petri nets and multi-agent simulations.

## II. MODELS, COOPERATION AND COOPERATIVE SYSTEMS

### A. Definitions

Cooperation is a complex human activity. The studied literature gives us different definitions revolving around cooperation :

- Cooperation requires communication, with a view to exchange information, inform the other of its intentions, interpret and understand the partner interactions, especially for current and future actions [1].
- A system is considered as a cooperative one when it considers all situations and interaction formalisms between partners. It needs to define objectives and goals to be reached by the group, to break down and allocate tasks so as to reduce conflicts, disagreements and redundancy as much as possible, and to execute

tasks with synchronisation and convergence of goals to be reached [2].

- When cooperation occurs, we can distinguish three very distinct conceptual universes [1] : the data world, the users world (which has access and operates data world components), and the organisation world (which structures the previous two).
- Another classification is based on functional group definitions. Three functional groups are defined : production space (designating results from a group activity), coordination space and communication space [3].

### B. Cooperation models

Cooperation models have been proposed using different viewpoints : activity, communications and interaction among others.

A cooperation activity model is proposed in [1]. It is based on oriented graphs representing cooperative interactions. As a formal cooperation model, it is interesting; however, it does not allow dynamic working simulations of cooperative systems. It could better be used in cooperation mode analysis on an existing simulation.

Collective cooperative behaviours are studied in [4] [5]. In this work, six primitive collective behaviours for cooperation are defined : equivalence, transfer, specialisation, redundancy, complementarity and concurrency. This study could also be used to detect specific cooperation behaviours in an existing simulation, and then draw conclusions on its efficiency.

### C. Cooperative systems modeling

The border between cooperation models and cooperative systems modeling is difficult to determine. Cooperation models are often used in cooperative systems modeling. However, several points of view are considered in cooperation system modeling (decision-making process, problem to solve modeling, physical system modeling...).

For example, researches reported in [6] and [7] shows a Petri net modeling based on processes and activities. The system is modelled in view of activities so Petri nets represent states like decision, evaluation, negotiation... Cooperative process is known and follows a specific pattern of decision making. Colored Petri nets used in this work allow information transport and information modification on tokens. In this sense, transitions are fired only when two people generate the same type of tokens (or proposition).

### D. Multi-agent systems and cooperation representation

Cooperation in multi-agent systems is an important concept. As a rule, agents interact with each other in multi-agent systems. They have the ability to communicate. They can understand the will of other agents and adapt their own behaviour to improve collective results [8] [9].

Many multi-agent systems represent existing systems composed of intelligent entities. Cooperation appears when the system is dynamically working using simulation tools. Cooperation is not explicitly represented but appears from simulation.

The principle is to represent each entity of the existing system as an agent having its own behaviour and knowledge. These agents have communication abilities and may react specifically to external constraints (environment changes, orders from another agent...).

## III. SCOOP : A COMPLETE METHODOLOGY FOR COOPERATIVE SYSTEMS MODELING

The lack of a global cooperative systems modeling approach leads us to the proposal of a complete methodology that allows us to draw models of different cooperative systems aspects. We will first describe the used hypothesis. Then, we will describe the Scoop methodology step by step, linking each step with his meta-model proposal.

### A. Hypothesis

In this part, we describe our modeling hypothesis, which define the limits of our representation. The whole Scoop methodology is based on our cooperative systems definition.

We defined in [10] and [11] cooperation in a cooperative system as a complex mechanism involving the following <sup>1</sup>:

- *Knowledge possessed by members,*
- *Specific behaviour of the members.* Human behaviour, during cooperation represents an important part of cooperation activity. Existing multi-agent work allows behaviour specification for each individual [8]. By extension, we can define individual behaviour and observe resulting collective behaviour by simulation.
- *A certain organisation of the member group.* Organisation of cooperating groups has been studied considerably by different authors. This research is often oriented towards group management algorithms or protocol development [3], [12], [13].
- *Communication means between members* [14]. This concerns shared data access and communication between human beings. Concerning shared data, several problems are dealt with in the literature such as data heterogeneity, shared data modes or data availability. The same can be said for communication with regards to heterogeneity and defining communication tools [13]. Much of this work has been reused to integrate multimedia flows in cooperative applications [15].

Thus, the following five categories have to be represented :

- *Cooperating member behaviour:*  
This category implies the modeling of the individual behaviours. It includes social behaviour and member

<sup>1</sup>In this definition, a member can be a person or equipment

reasoning. Behaviours have an influence on group organisation, on fluctuations in communication and on access to shared data. Modeling behaviour includes modeling roles and goals.

- **Knowledge of cooperating members:**  
Knowledge of a cooperating member is of different types : knowledge of his capacities (*skills*), knowledge of his *environment* (including his knowledge and vision of the problem and his knowledge of cooperation rules) and knowledge of his *role and goals*.
- **Organisation of the cooperating member group:**  
The cooperating member group is organised on several levels : *geographical organisation*, *hierarchical organisation* and *legal organisation*. Organisation intervenes in shared data management mode, and on communication and shared data access authorisations. The static and dynamic aspect of organisation has to be considered.
- **Interactions between group members:**  
These interactions can be of several types : *synchronous or asynchronous*. It may involve two or more people : *diffusion to several people*, *conference*, or *peer to peer conversations* (we suppose that the communication media is exclusive for this kind of communication). Mutual exclusion and network channel availability constraints have to be represented.
- **Shared data usable by participants:**  
On shared data, we have mutual exclusion constraints preventing several people from modifying the same data at the same time. We also find constraints on network channel availability. Access to shared data may be of 3 types : visualisation, object adding, object modifying or deleting (which represent the same constraints).

### B. Scoop methodology

The Scoop<sup>2</sup> methodology presents 4 main phases (see figure 1). These 4 phases are linked to the software engineering classification [16].

#### a) Formal specification of system components

The first step of Scoop methodology is the formal specification of system components. It uses this set :

$$SCOOP_{name\_of\_the\_system} = \{P, S, G, H, L\} \quad (1)$$

Where :

- *P* is the list of human members of the system
- *S* is the list of equipment members of the system
- *G* is the list of geographical places used in the system
- *H* is the number of hierarchical levels used in the system
- *L* is the level of legal rules used in the system (0 is a system without any rules and 100 is a system where every action is ruled)

<sup>2</sup>Acronym for : Cooperative systems Simulation

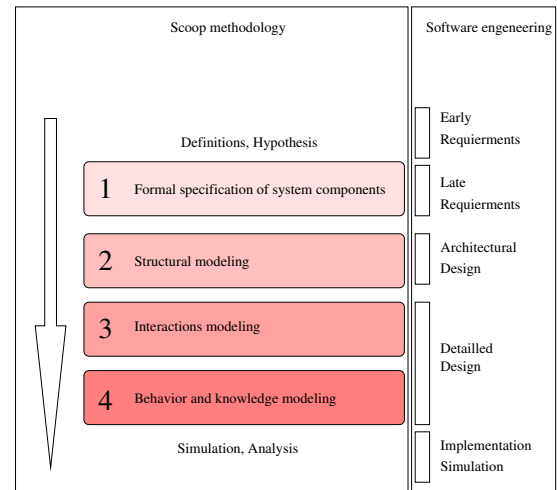


Figure 1. The 4 main phases of Scoop methodology

Each human member (*P*) is described by another set :

$$P_i = \{Beh, Know, G, H, Ch\} \quad (2)$$

Where :

- *Beh* is the class describing the behaviour of the member
- *Know* is the class describing the knowledge of the member
- *G* is the geographical place where the member is (taken from the previous list)
- *H* is the hierarchical place of the member (taken from the previous list)
- *Ch* is the work load level of the member

Each equipment member (*S*) is described by a couple :

$$S_i = \{App, G\} \quad (3)$$

Where :

- *App* is the class describing the working mode of the member
- *G* is the geographical place where the member is (taken from the previous list) located.

This specification allows describing cooperative systems at a high level. However, a graphical representation of the cooperative system would help a lot at the specification time. This point is covered by the next step of the Scoop methodology.

#### b) Structural modeling

The second point of Scoop methodology is the fact that it helps designer to draw structural models of the system. These models are easy to read and their graphical aspect simplify comprehension of the system.

The structural modeling we propose is based on a concrete nomenclature of members and interactions. This

nomenclature is described according to the different aspects previously identified.

Human members are represented using a square containing basic information of the  $P_i$  set. Equipment members are represented using a circle containing the basic information of the  $S_i$  couple.

Interactions are represented using 2 specific nomenclatures. The communication nomenclature (see figure 2) and the shared data access nomenclature (see figure 3).

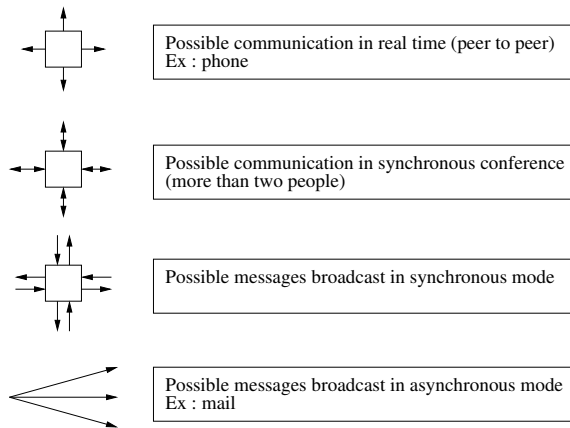


Figure 2. Representation of the communication possibilities

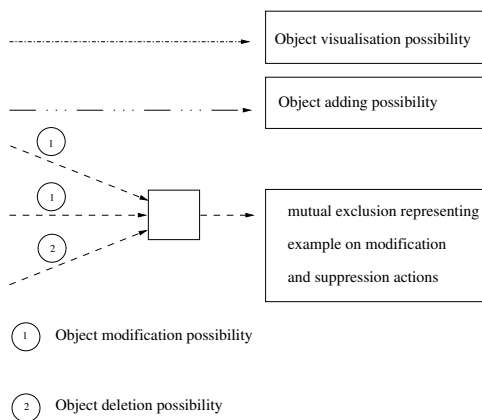


Figure 3. Representation of data access possibilities

In both interaction nomenclatures, the square symbol means that mutual exclusion is required for this type of interaction. The number of arrows is related to the number of members involved in the interaction.

It is necessary to draw several structural models to represent dynamic aspects. For instance, the initial state and the cooperative state of the system may be represented.

Figure 4 shows an example of the structural model for a cooperative e-maintenance system (the prototype of the e-maintenance system we developed in the European PROTEUS project [17], [18]). This model is developed in cooperative state of the system.

This structural model shows a synchronous peer to peer communication possibility (requiring mutual exclusion) between 3 members (electrician, machinist and

maintenance manager). It also shows shared data access possibilities for the access to the web camera control or e-documentation reading.

The second step of Scoop methodology helps describe the global structure of the system. It is very useful for specification. However, we cannot verify or simulate anything with this representation. That is why we developed associated Petri nets for the interactions.

### c) Interaction modeling

Each element of the interaction nomenclatures (figures 2 and 3) is then linked to a sub-method, allowing the creation of Petri nets representing interaction operating mode. Mutual exclusion is then represented. The sub-method uses number of members linked to the interaction mean, and the type of interaction mean. Conference and synchronous broadcast interaction means are similar cases in our basis hypothesis. They are modelled using the same Petri net.

We developed two different methods that allow to create either colored Petri nets or standard Petri nets for each interaction mode. However, standard Petri net representation is the one we used to extract results from stochastic simulation.

Using these methods, we built a set of 10 standard interaction models which may be used in most interaction cases (see figure 12). General results derived from these latter are presented in the part IV. In this part, we will only present synchronous peer to peer interaction modeling methodology for standard Petri nets design.

Our methodology allows the inventory of states and transitions to be drawn in the Petri net. In a first step, we show how to create members models with “internal states” and “internal changing states transitions”. This represents the “behaviour” of each member. In a second step we create the “communication states” and the transitions leading to a communication state.

For a number  $m$  of members connected to the communication system, the standard Petri net model for a member is composed of  $2 + m - 1$  states (see figure 5). The first two states are always present : state “available” and state “does not want to be disturbed”. Then, a member may also want to interact with any member linked to the interaction mean except himself. That is why we have  $m - 1$  in the second part of the equation.

The initial state marking is composed of one token in the state “available”. We used the following hypothesis to simplify the representation : a member cannot reach a state “wants to communicate with a member x” from a state “wants to communicate with a member y”. He must first come back to the state “available”. In consequence, the number of Petri nets “internal changing states transition” ( $T_i$ ) is limited to :

$$card(T_i) = 2 * ((2 + m - 1) - 1) \quad (4)$$

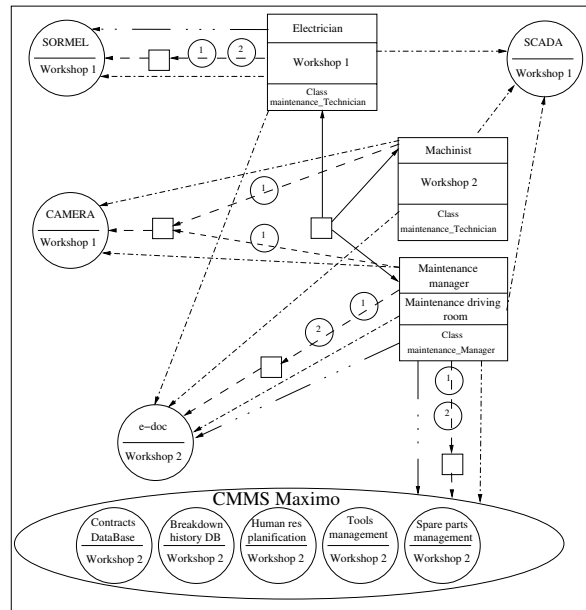


Figure 4. Example of structural model

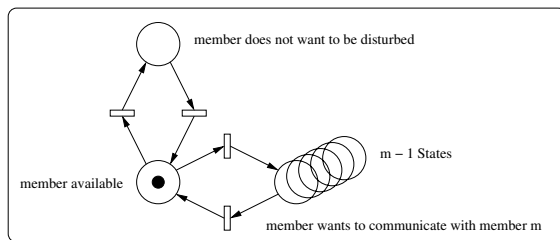


Figure 5. Generic model for a member in a synchronous peer to peer interaction system.

instead of :

$$card(T_i) = 2 * \sum_{j=0}^{2+m-1} (j) \quad (5)$$

There is as many communication states ( $E_c$ ) as there is peer to peer possible communication :

$$card(E_c) = \sum_{i=1}^m (m - i) \quad (6)$$

For example : 3 members = 3 different sets of 2 members. 4 members = 6 different set of 2 members. 5 members = 10 different sets of 2 members...

In a peer to peer communication system (like phone), there is 3 ways to get a communication state between 2 members (x and y) :

- member x wants to interact with member y and member y is available
- member y wants to interact with member x and member x is available
- member x wants to interact with member y and member y wants to interact with member x

For this reason, there will exist 3 transitions for each communicating state. The number of transitions leading to a communication state ( $T_c$ ) will be :

$$card(T_c) = 3 * \sum_{i=1}^m (m - i) \quad (7)$$

If we apply this method in the previously presented structural model (figure 4), the interaction operating mode between electrician, machinist and maintenance manager is detailed by the petri net shown on figure 6.

Petri nets created are used to verify livingness properties, to find deadlocks and conflicts in the interaction. We also developed an analysis based on stochastic simulations of these Petri nets (results are presented in section IV).

However, interaction study is just a part of cooperation aspects in cooperative systems. Human cognitive aspects have to be represented. To study this particular point, we choose to create a multi-agent simulator of cooperative systems.

#### d) Knowledge and behaviour modeling

We propose to define each member of cooperation as an agent. Multi-agent systems allow us to propose a good representation of human entities because of their artificial intelligence abilities. Multi-agent systems require knowledge and behaviour inherent to members. That is why we use behaviour and knowledge description formalisms.

We used a simple XML formalism based on a DTD that allowing us to describe simple knowledge classified in the 3 identified parts (see part III-A) : skills, environment and role and goals. This concept may be extended and more specific tags defined.

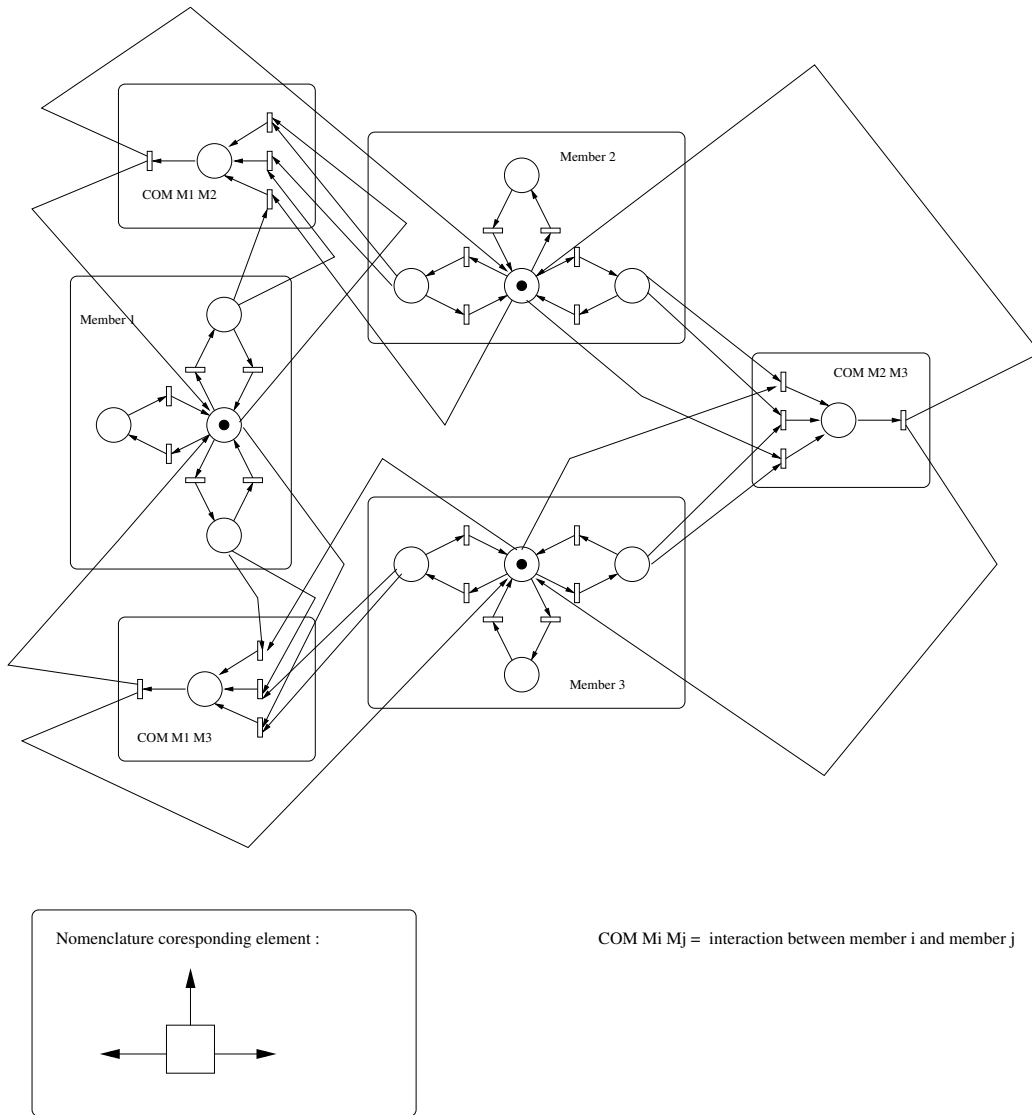


Figure 6. Interaction operating mode for 3 members interacting in peer to peer synchronous mode (ex : phone)

We defined a DTD (figure 7) which structures the knowledge of members in previously cited categories. This work helps future agent implementation.

```

<!DOCTYPE knowledge [
<!ELEMENT Environnement knowledge (name,
geographical position, hierarchical position,
known equipement members, known human members,
cooperation rules)>
<!ELEMENT Skills (...)>
<!ELEMENT Goals (...)>
]>
    
```

Figure 7. First level elements for each XML knowledge description file

Goals are organised in a priority order using another DTD (see figure 8)

It is rather easy to integrate human will or desire into agents. Each agent has a goal, and in a well-managed

```

DTD_XML.goals

<!DOCTYPE goals [
<!ELEMENT primary (secondary)>
<!ELEMENT secondary (tertiary)>
<!ELEMENT tertiary (#PCDATA)>
]>
    
```

Figure 8. Generic XML syntax for member goal description

cooperative system, these goals converge to a common goal. Agents may behave in cooperation because of their communication abilities and their initiating capacity [8]. We used an existing behaviour formalism, well suited to describe agents : PLOOM-UNITY. This one allows behaviour description with notions of goals and role.

UNITY [19] is an object typed formalism which allows agent description. We used PLOOM [20] to extend UNITY. In particular, we can use inheritance and functions in PLOOM UNITY formalism. This was not possible with UNITY formalism.

The figure 9 shows the general class syntax in PLOOM-UNITY formalism.

Figure 10 shows our generic class for the definition of a “human agent”.

Using basic knowledge and behaviour previously defined, we developed a standard multi-agent simulator using JAVA with MADKit library<sup>3</sup>. This simulator allows analysis of human aspects in cooperative systems.

#### IV. GENERAL ANALYSIS

Based on our modeling methodology proposal, we developed a general analysis of cooperative systems in two main parts :

- Interaction analysis based on Petri nets
- Cognitive human aspects based on multi-agent simulator

##### A. Interactions

We studied 8 typical interaction models shown on figure 12. These models have been chosen for their ability to answer the basic needs of cooperative systems. Indeed, few interaction systems involve more than 4 people. We have created the associated Petri nets for each of these 8 models.

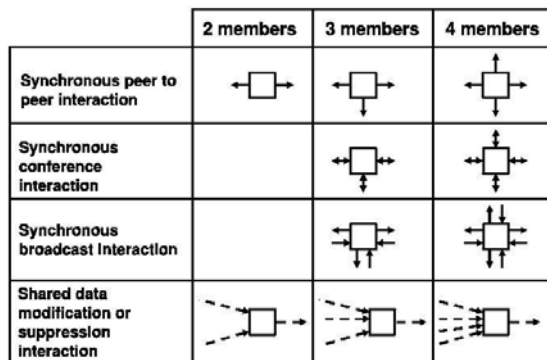


Figure 12. Standard interaction models chosen for study

We formally analysed these 8 Petri nets models, proving that there is no deadlock. The 8 models are live. Structural conflicts that may be detected draw our attention to the points to be managed. For instance, a conflict may appear when 2 members want to access the data at the exact same time. In this case, an algorithm or a human manager would have to choose the member which would be allowed to access data using some criteria. This underline aspects to be managed while interaction is running.

<sup>3</sup>[www.madkit.org](http://www.madkit.org)

We realised a set of experiments, using stochastic parameters on these Petri nets. We realised these experiments with STPNPlay<sup>4</sup>. We present in this paper the results we obtained when using different interaction durations (from 1 to 10 time units, considered as minutes to obtain readable results), for the following communication means :

- Synchronous peer to peer interaction (ex : phone)
- Synchronous conference and synchronous broadcast (same modeling)
- Shared data modification or suppression (same modeling)

We studied the effect of this duration variation :

- on the mean number of interaction (figure 13),
- on the mean number of interaction generated by a member (figure 14),
- on the mean interaction time in the system (figure 15),
- on the mean interaction time generated by a member (figure 16),
- on the mean cooperative activity time of a member in the system (figure 17),
- on the cooperative system efficiency. This criterion is defined as the time the user takes to use the system without obtaining any interaction. It is a “lost time criterion” which is better when it goes lower (figure 18). It is a mixed criterion that uses other criteria as a basis.

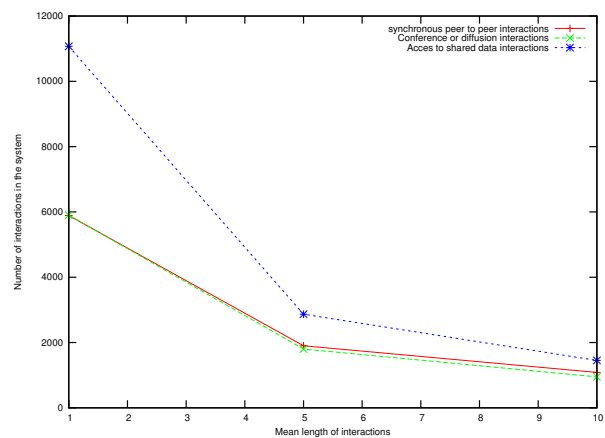


Figure 13. Effect of interaction duration variation on the mean number of interactions

For each kind of interaction system, the mean number of interactions gets lower when the mean interaction duration gets higher (figure 13). It is normal to observe this. Longer interactions leads to fewer interactions. The system will be more solicited when interaction mean duration is short. The same phenomenon appears on figure 14, which represents the evolution of the mean number of interaction generated by a member.

<sup>4</sup><http://dce.felk.cvut.cz/capekj/StpnPlay/>

```

Class ;Class namei
Sub class from ;mother classi
Fields
< fieldi >:< fieldtypei > ;method – definitioni;
End;Class namei
    
```

Figure 9. General class syntax in PLOOM-UNITY

```

Class human
Declare :
name : String // Agent name
belief : XML_DTD // agent environment knowledge, XML_DTD // agent skills
desire : XML_DTD // agent goals
End Class
    
```

Figure 10. Generic class for “human” agent

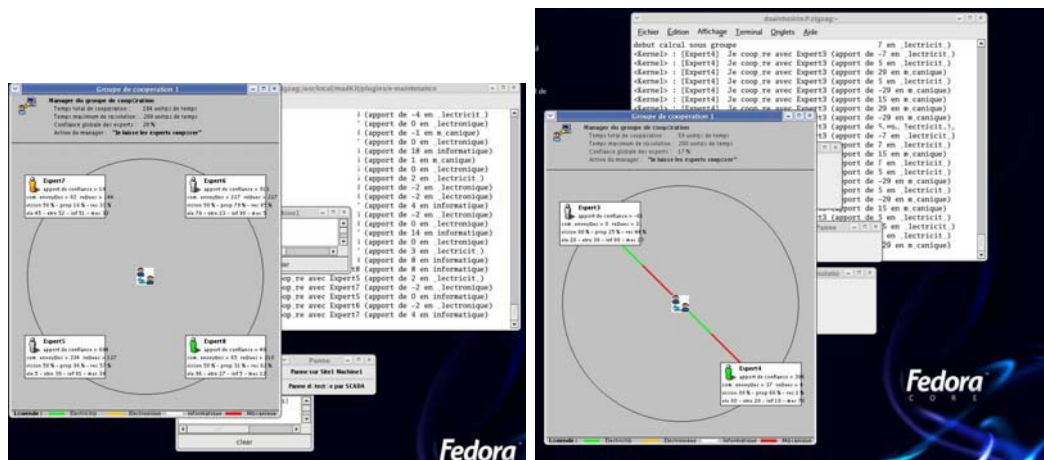


Figure 11. Screen capture during the simulation. The cooperative systems multi-agent simulator.

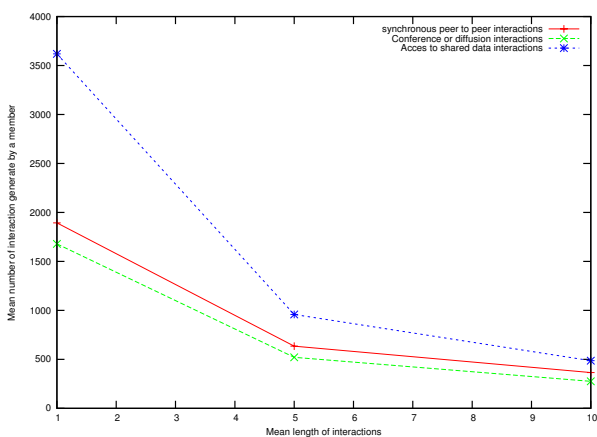


Figure 14. Effect of interaction duration variation on the mean number of interaction generated by a member

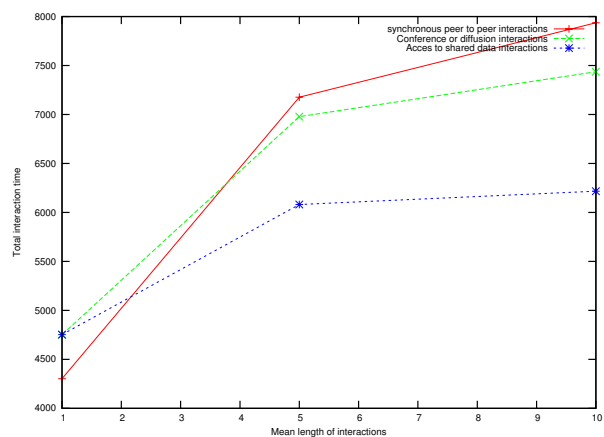


Figure 15. Effect of interaction duration variation on the mean total interaction time in the system

Figure 15 shows that total interaction time in the system grows when interaction mean duration is getting higher. Cooperating members lost less time to find a member to speak with in a situation where mean interaction duration is high. To rise the mean interaction duration is useful to unload the system and generate a bigger total interaction time.

The shared data modification or suppression interaction mode does not get any best results after using a 5 minutes mean length for interactions. That is because it begins to saturate. There is no parallelism in this interaction mean (just one shared object that members want to access).

These results are confirmed by the results shown on figure 16. Saturation of the modification or suppression

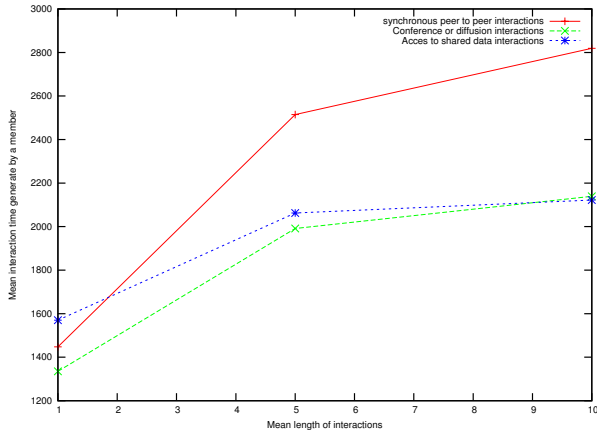


Figure 16. Effect of interaction duration variation on the mean interaction time generated by a member

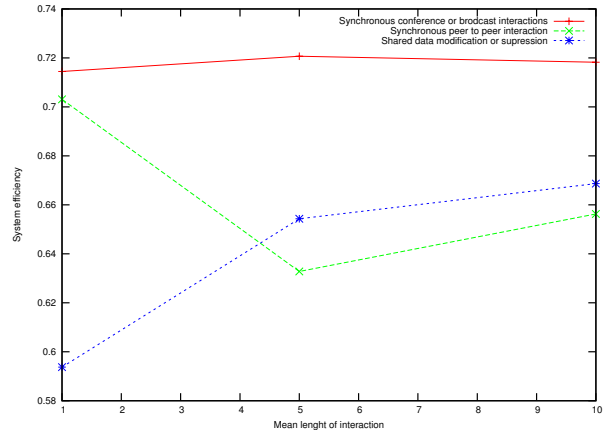


Figure 18. Effect of interaction duration variation on cooperative system efficiency

interaction system is even more visible.

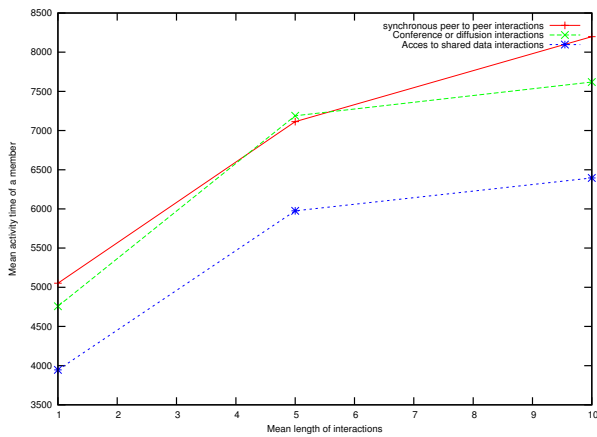


Figure 17. Effect of interaction duration variation on the mean cooperative activity time of a member in the system

Figure 17 shows the evolution of mean cooperative activity time of a member in the system. It gets higher when mean interaction duration is growing. However, going up to 5 minutes of mean interaction length is not very useful for increasing cooperative activity time.

On the figure 18. Our modeling shows synchronous conference or broadcast systems efficiency is not much affected by the mean duration of interaction. At the opposite, a shared data modification or deletion system is losing its efficiency when mean interaction duration is growing. In a last point, the results of synchronous peer to peer interaction systems shows that a short interaction duration (1 minute) gives bad results, a long interaction duration (10 minutes) gives bad results, whereas an intermediate interaction duration (5 minutes) gives the best results.

B. Cognitive human aspects

Cognitive human aspects have been studied throughout our cooperative system multi-agent simulator. We studied

several parameters as the multi-agent simulation is rather versatile : number of members that constitute the cooperating group, number of available members to constitute the cooperating group, vision quality of the cooperating members, type of members behaviour, members knowledge, type of management group algorithm...

Criteria we used to present results are :

- The mean time to solve a problem,
- The mean number of exchanged messages,
- The percentage of messages that get lower the group trust in its solution.

Results of this study shows that the number of available members to constitute the cooperating group is a very important parameter compared to the number of members that constitute the cooperating group which influence not much on the cooperation quality (see figures 19 and 20). This is caused by the “knowledge availability” provided by a great number of available members.

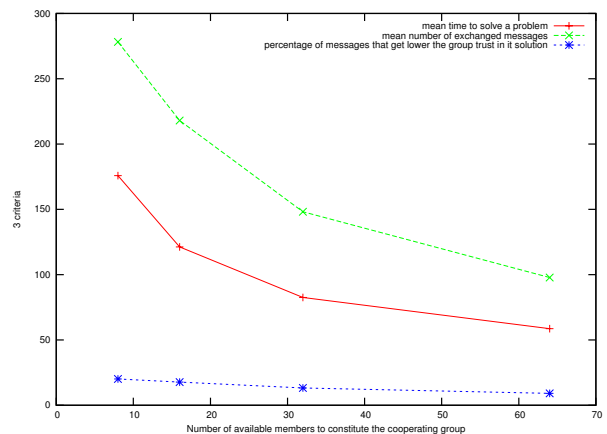


Figure 19. number of available members to constitute the cooperating group effect on the 3 criteria

V. CONCLUSION AND PROSPECTS

This paper proposes a general methodology and a meta-model which allows us to specify and to define

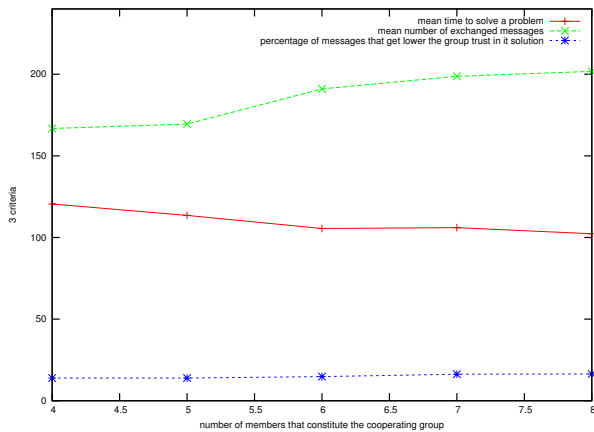


Figure 20. number of members that constitute the cooperating group effect on the 3 criteria

cooperative remote systems.

After having presented the existing work both in cooperation and cooperative systems, we developed our own analysis of cooperative systems, leading us to the description of a meta-model.

This meta-model is based on a concrete and unified nomenclature of people and systems and also of their communication and resource access possibilities. It can therefore be used to draw the structure of a given system with a flexible level of description.

For each communication and resource access possibility type, we represent mutual exclusion for connexion by Petri nets. Communication and shared data access deadlock or starvation are then detected on Petri nets without simulation.

XML knowledge file definition and PLOOM - UNITY behaviour specification contribute to implementing a dynamic working simulation using multi-agent architecture. Multi-agents have been chosen for their ability to represent human behaviour, integrating role, belief and desire among other features.

Based on Petri nets and multi-agent simulator, we propose two ways for analysing cooperative systems :

- The first uses stochastic Petri nets to represent individual behaviour with probabilistic rules of transition.
- The second method of analysis is to compute a multi-agent system using the meta-model specifications. This method is more realistic because of the artificial intelligence aspect.

In a new project, XML knowledge representation will allow us to develop an ontology for agent communication and data requests. ACL (Agent Communication Language) research will assist us in this task. We then hope to be able to draw qualitative results based on the semantic content of messages exchanged by agents.

A semi-automatic generation of models would be an important step forward. It would simplify the computer model creation of existing or planned cooperative systems.

Representation of the different cooperating members' mobility is an important contribution to new cooperative system modeling. Our meta-model will have to take mobility representation into account by adding mobility behaviour and position knowledge.

Finally, adaptive agents could be used in our representation to improve simulation realism by allowing agents to acquire new abilities.

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