

Object Store Based Simulation Interworking

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CoSMoS Project

www.cosmos-research.org

Simulation for Scientific Research

Process

Technology

Simulations

occoids

Granuloma Formation

Household Power Consumption

CoSMoS

Agile - small point solutions

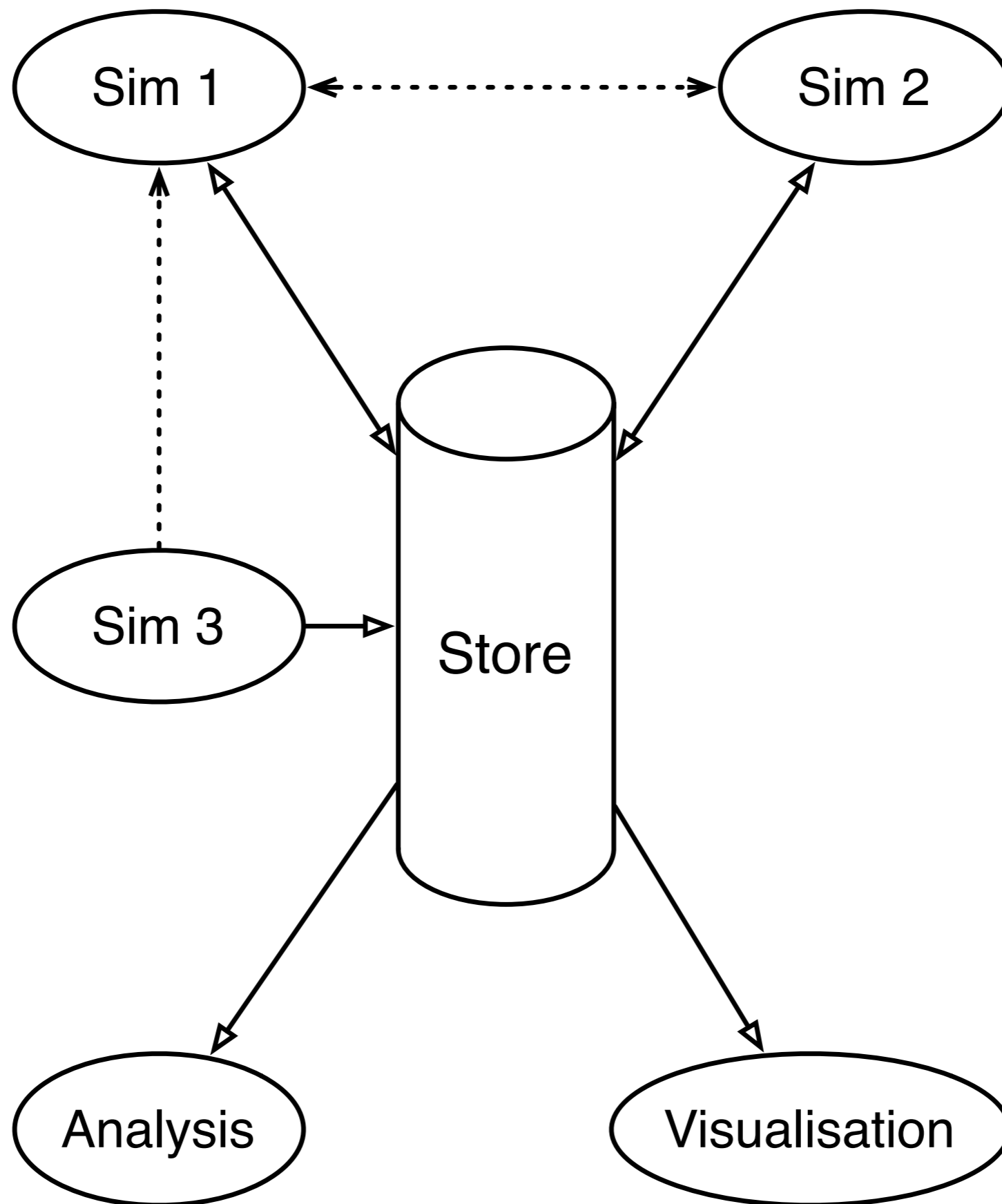
No framework

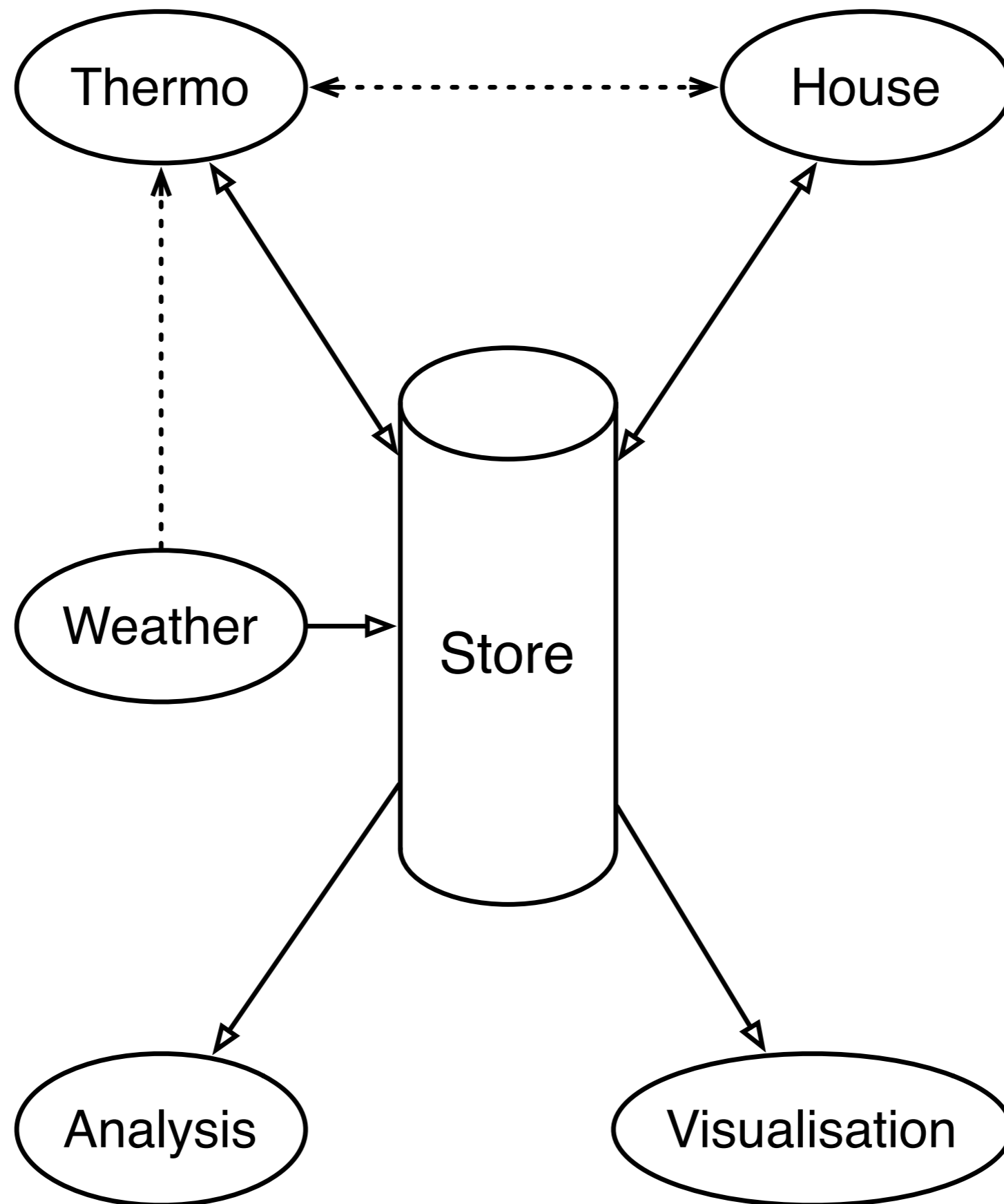
CoSMoS Driver

Integrate simulations (multi-lingual)

Connect analysis and visualisation (to simulations)

Store parameters and simulations results





Basic Protocol

create (name, start time)

delete (name)

update (name, field, value)

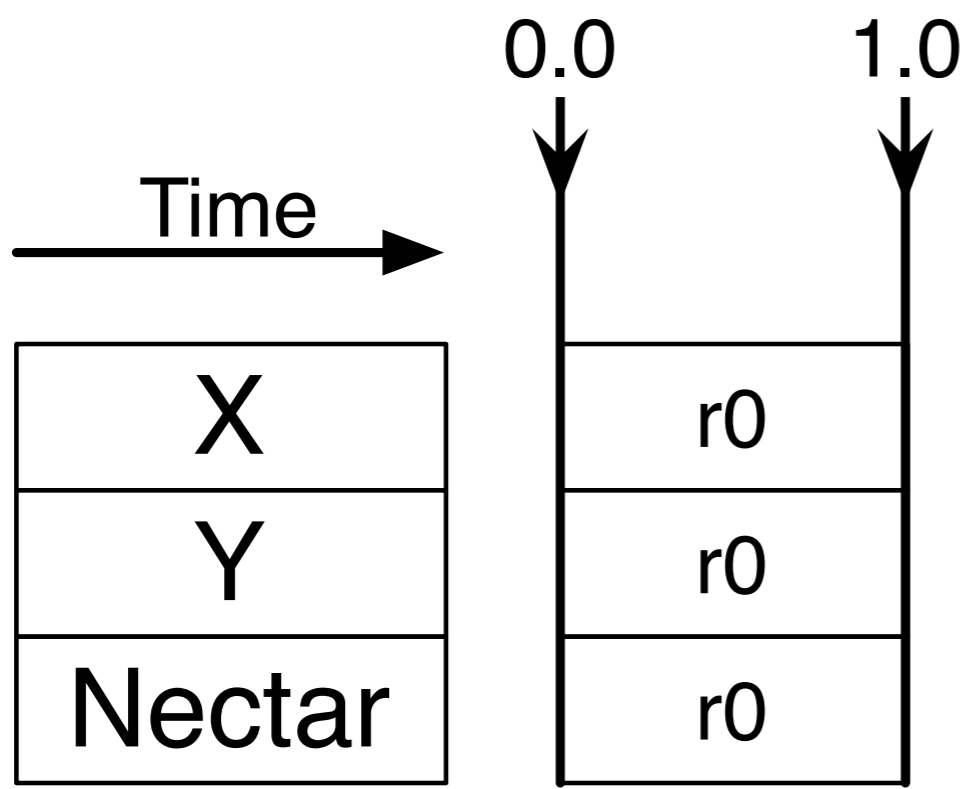
publish (name, time)

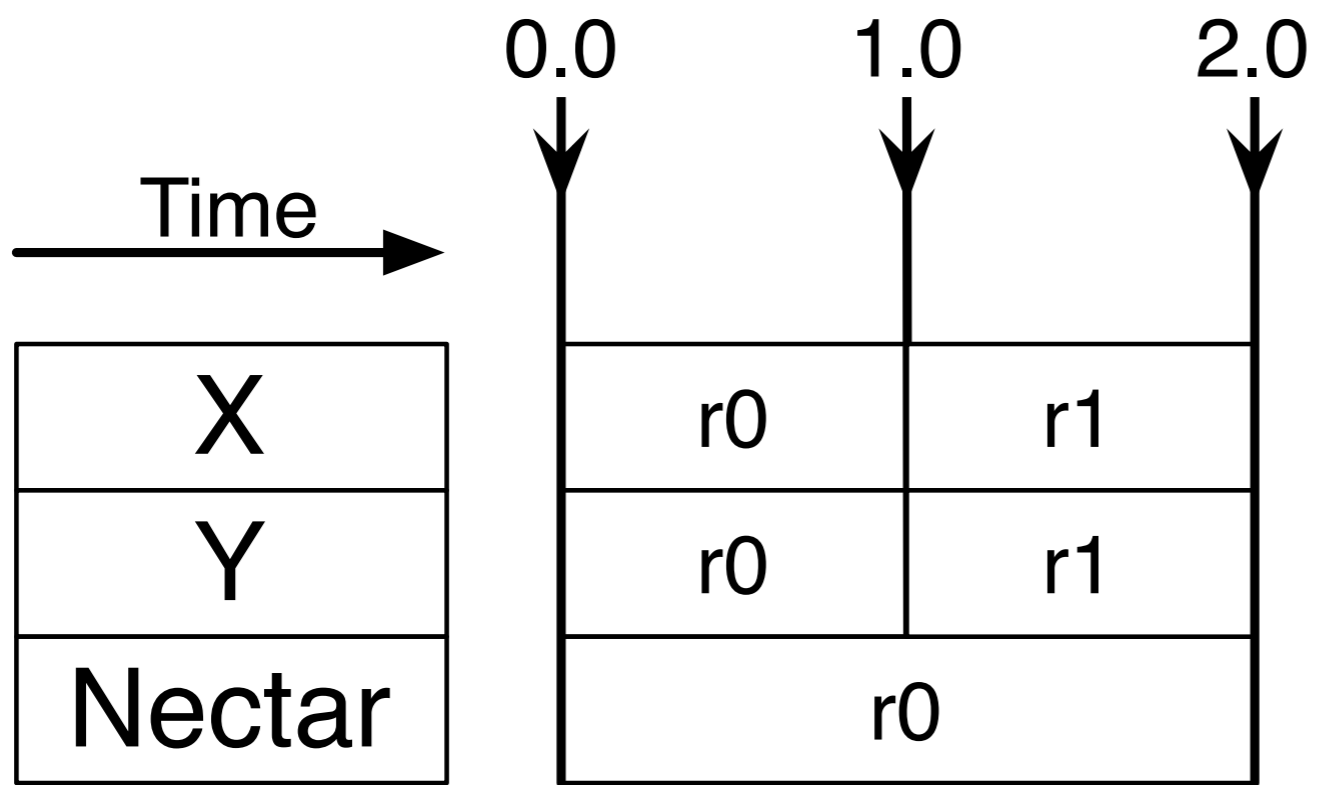
read (name, field, time)

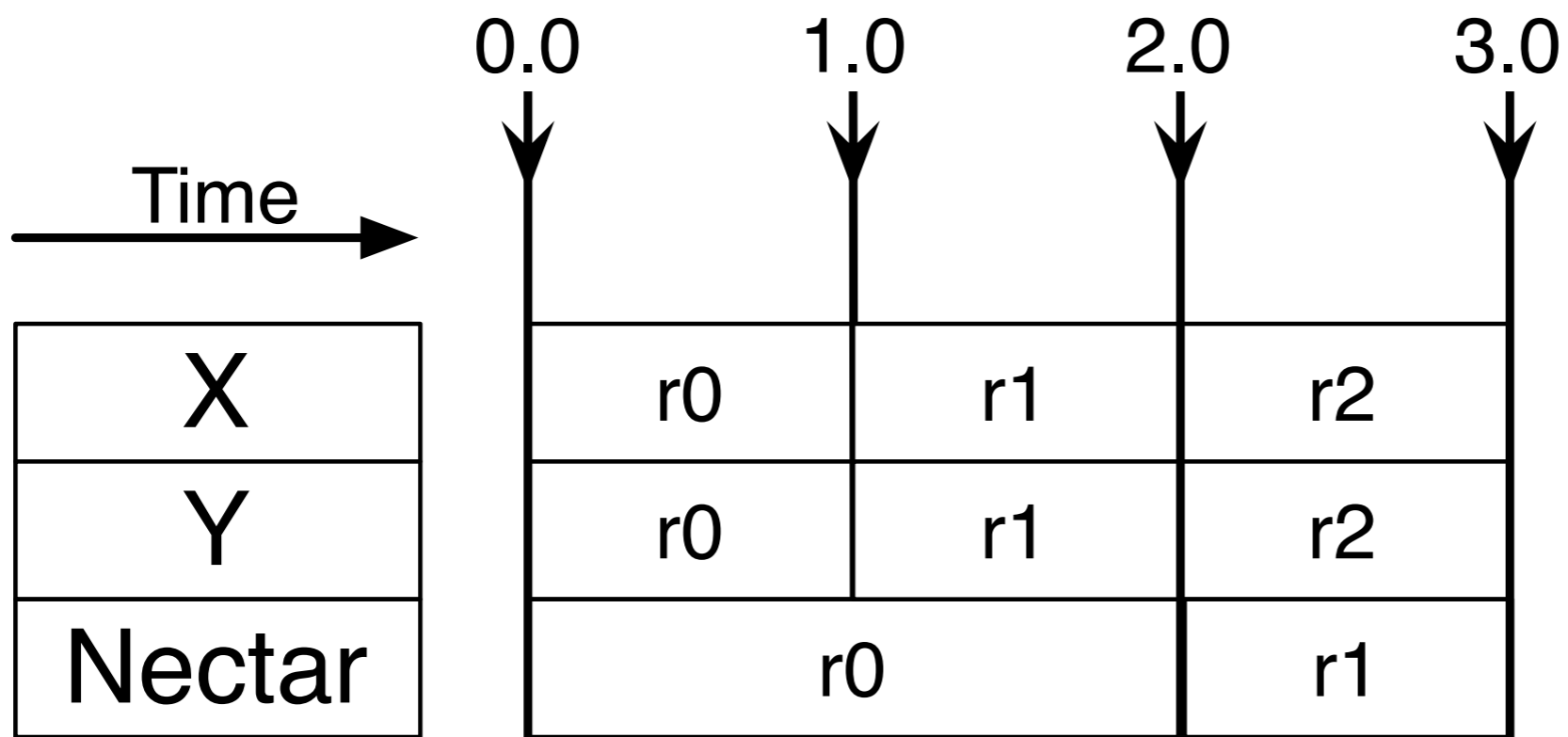
query (regular expression)

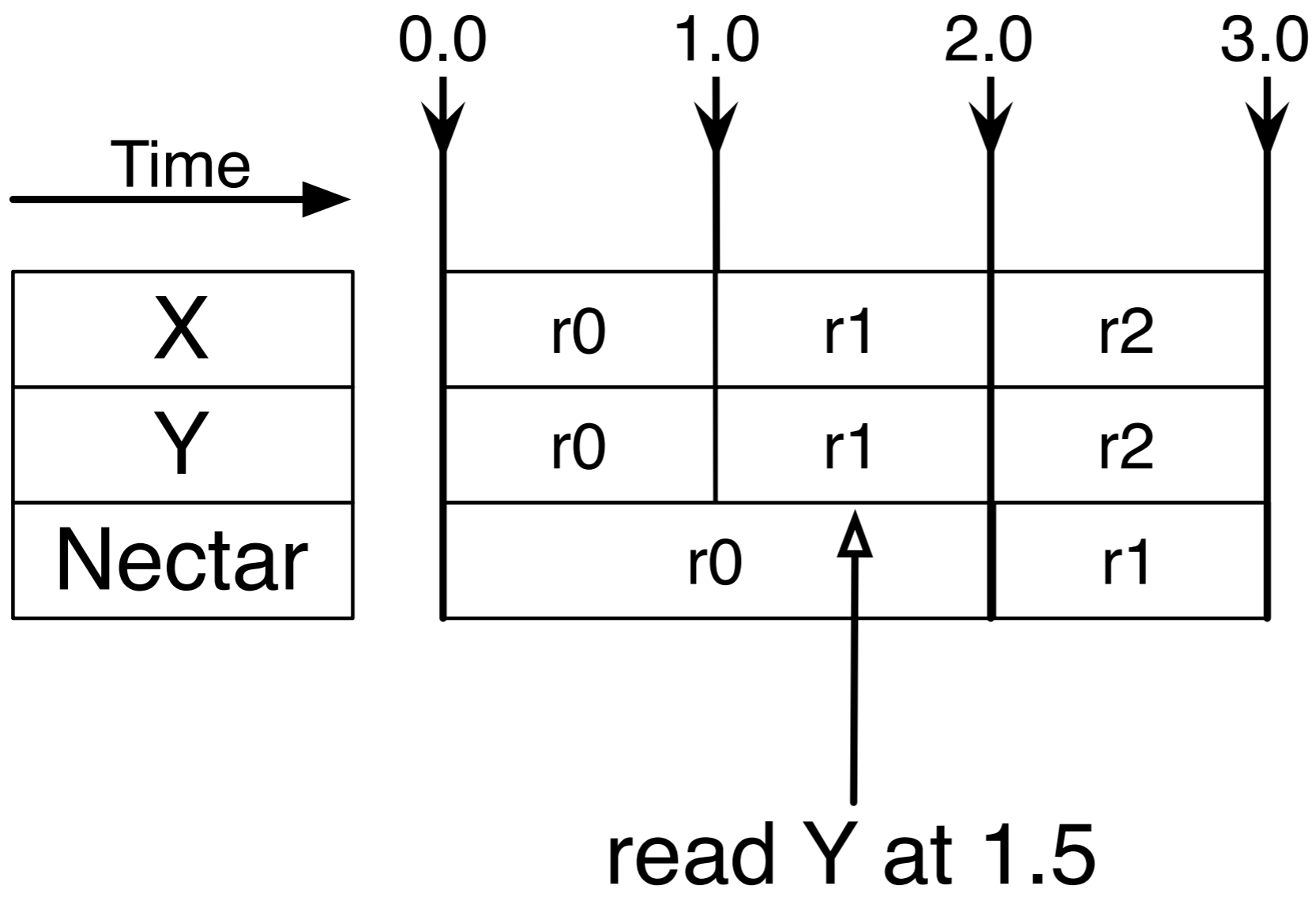
Object Timelines

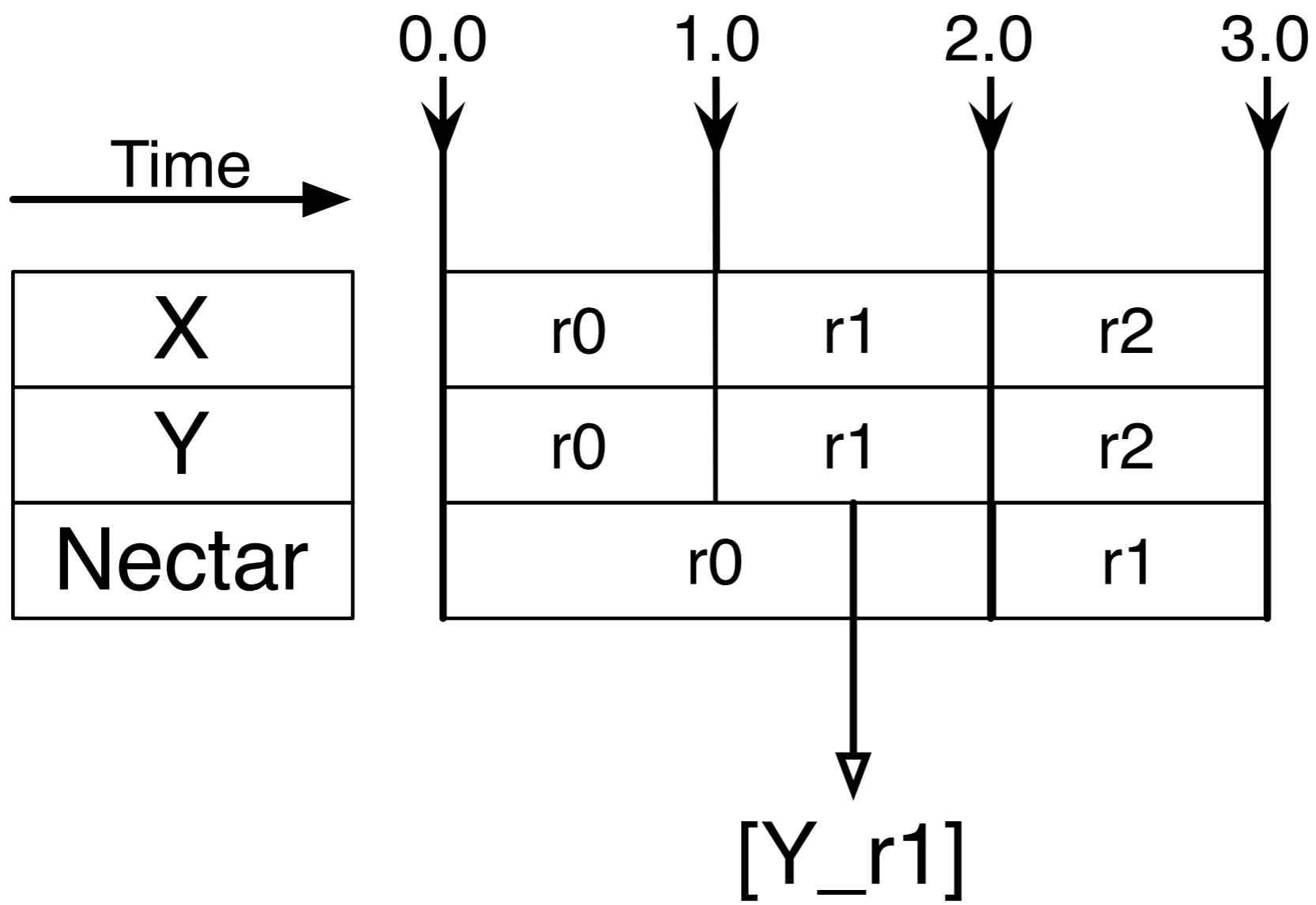
Separate simulation time steps

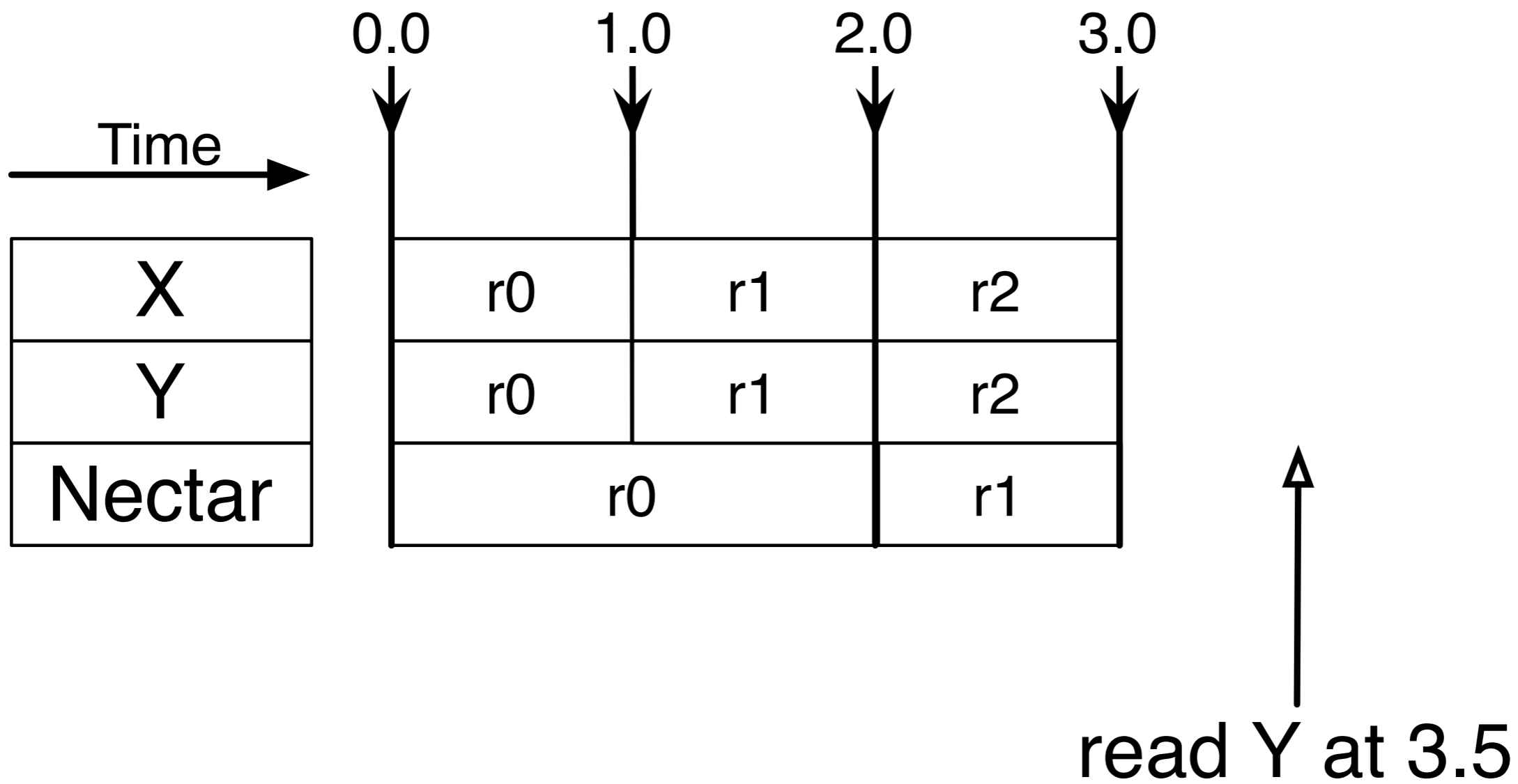


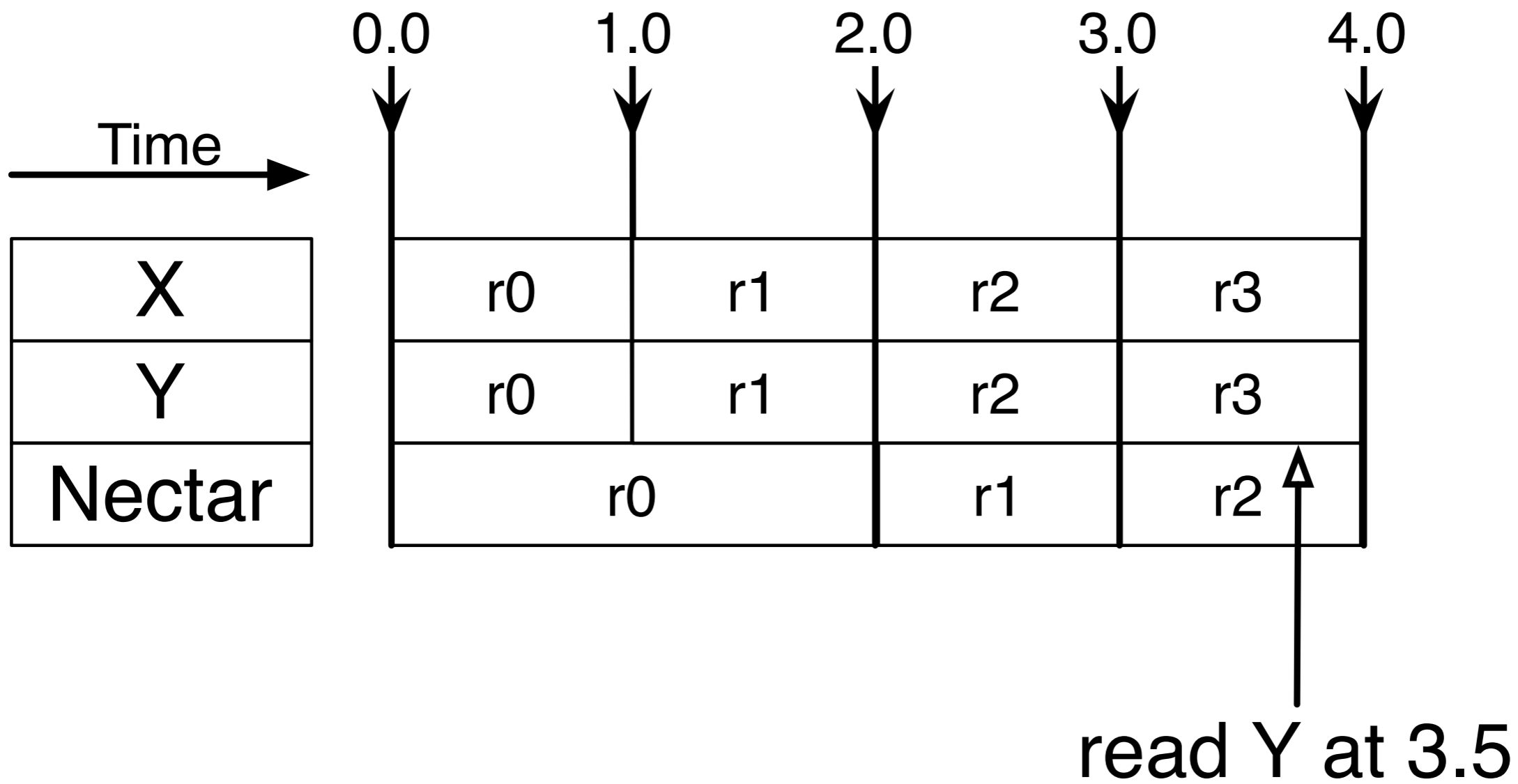


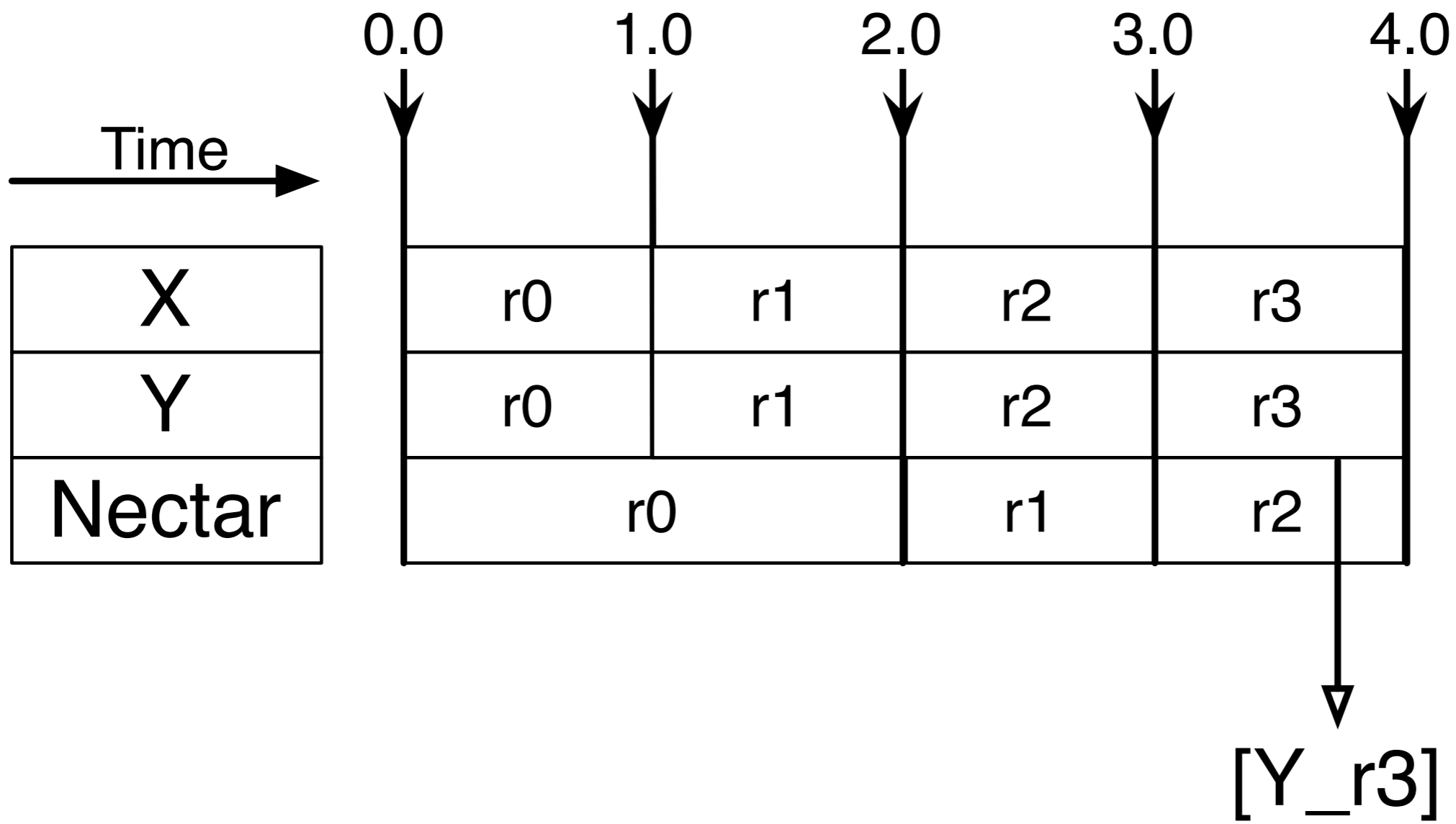


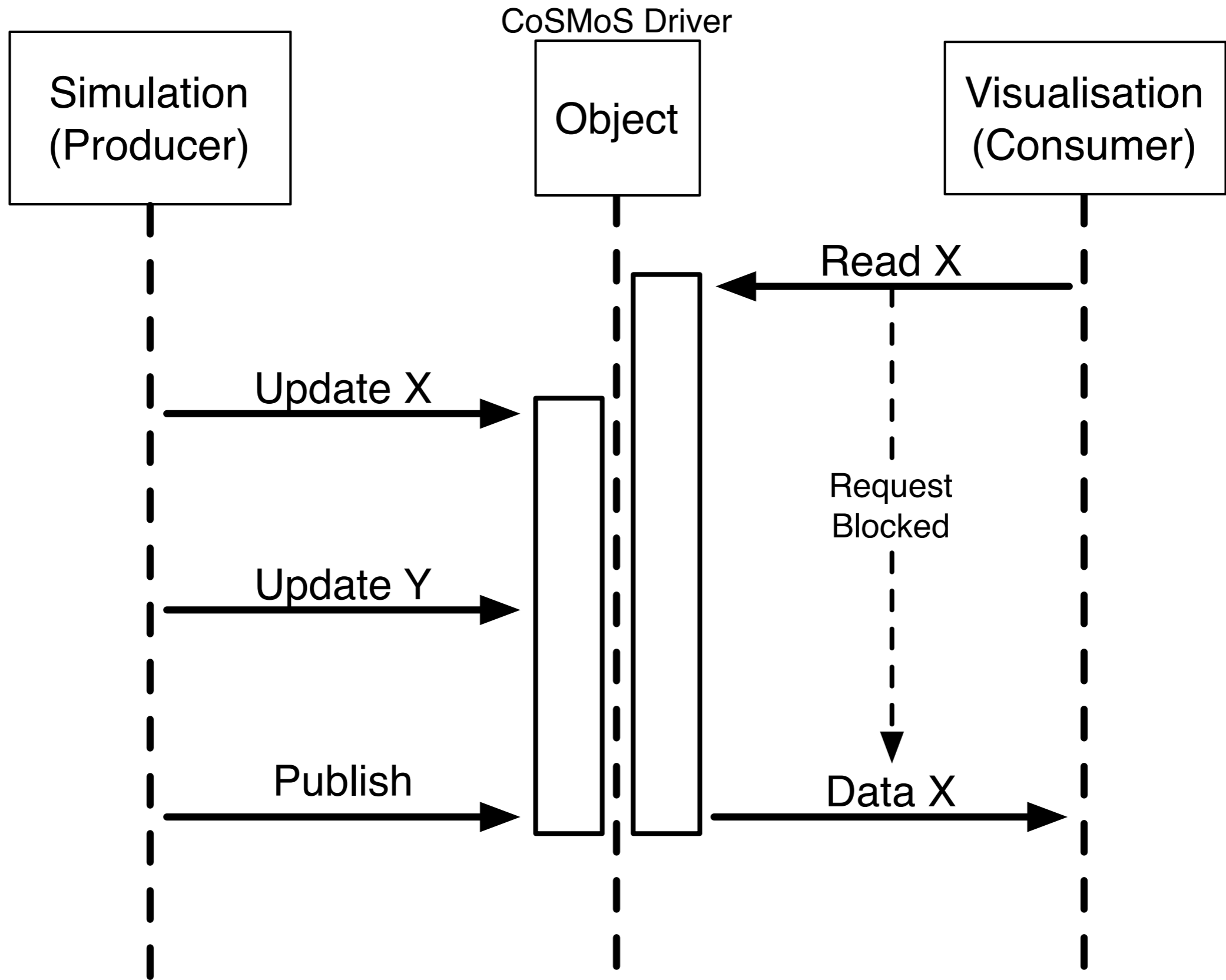












Storage and Architecture

Inspiration from web services

Client => Frontend => Database

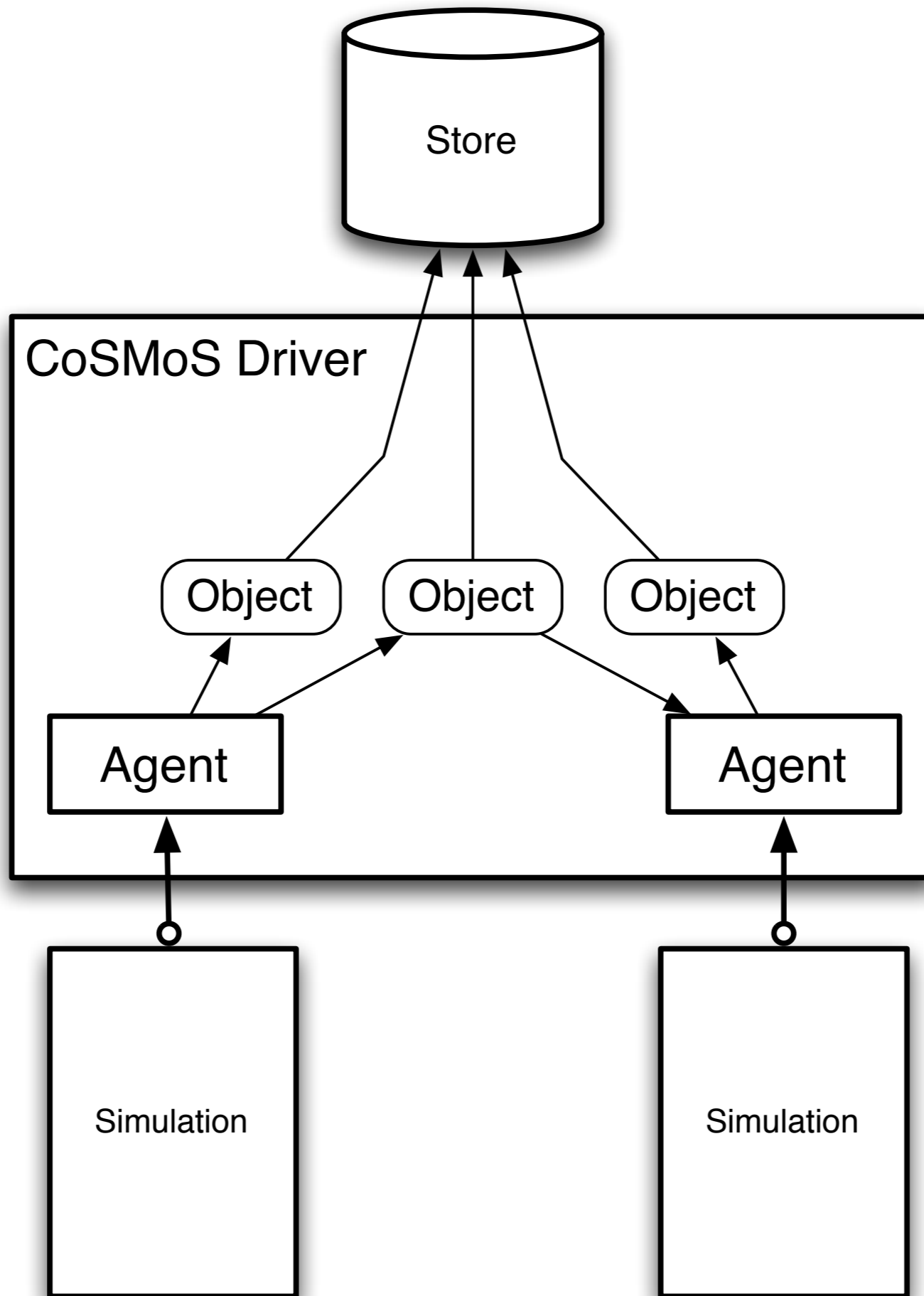
Key-Value Store

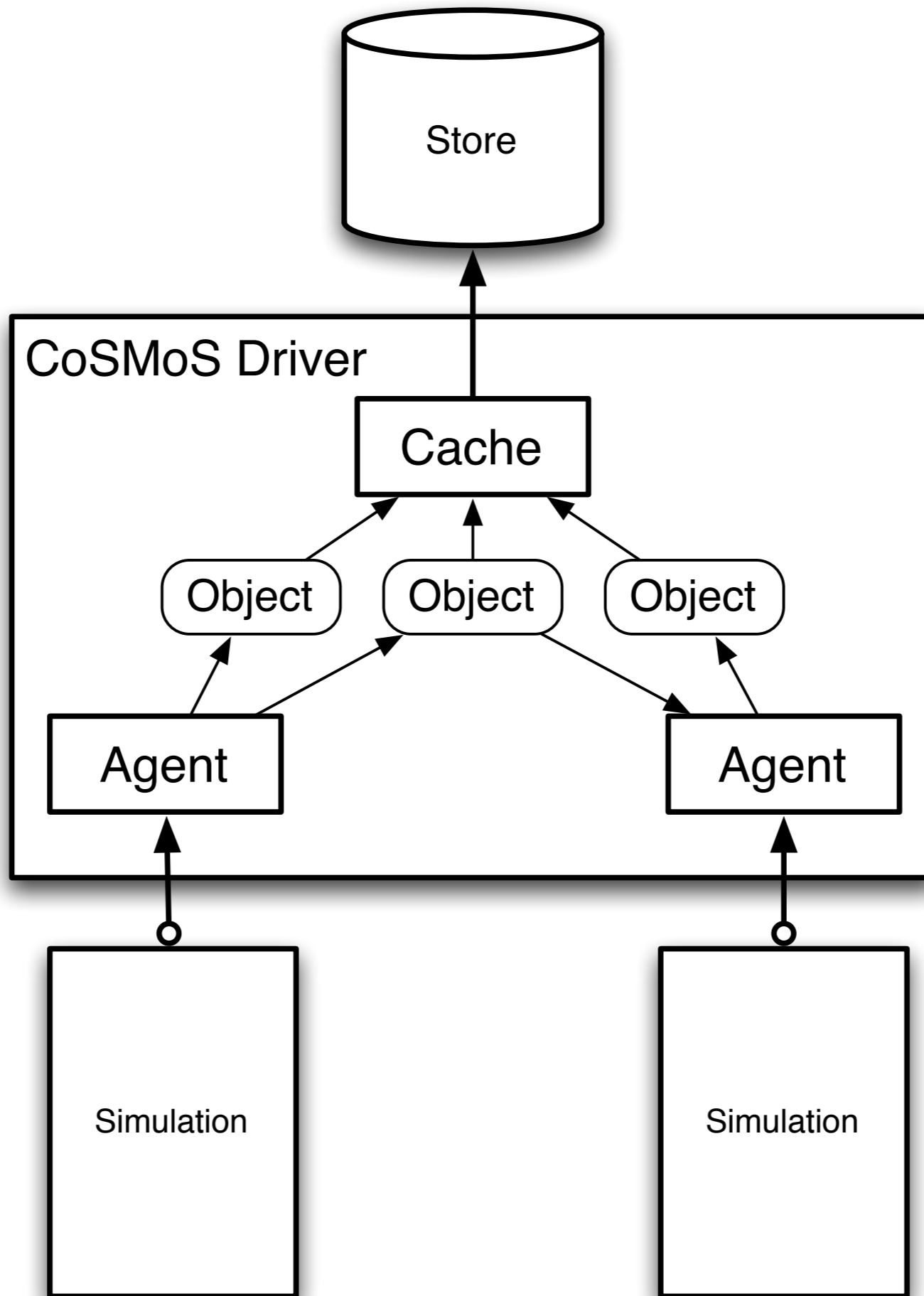
Key-Value Store

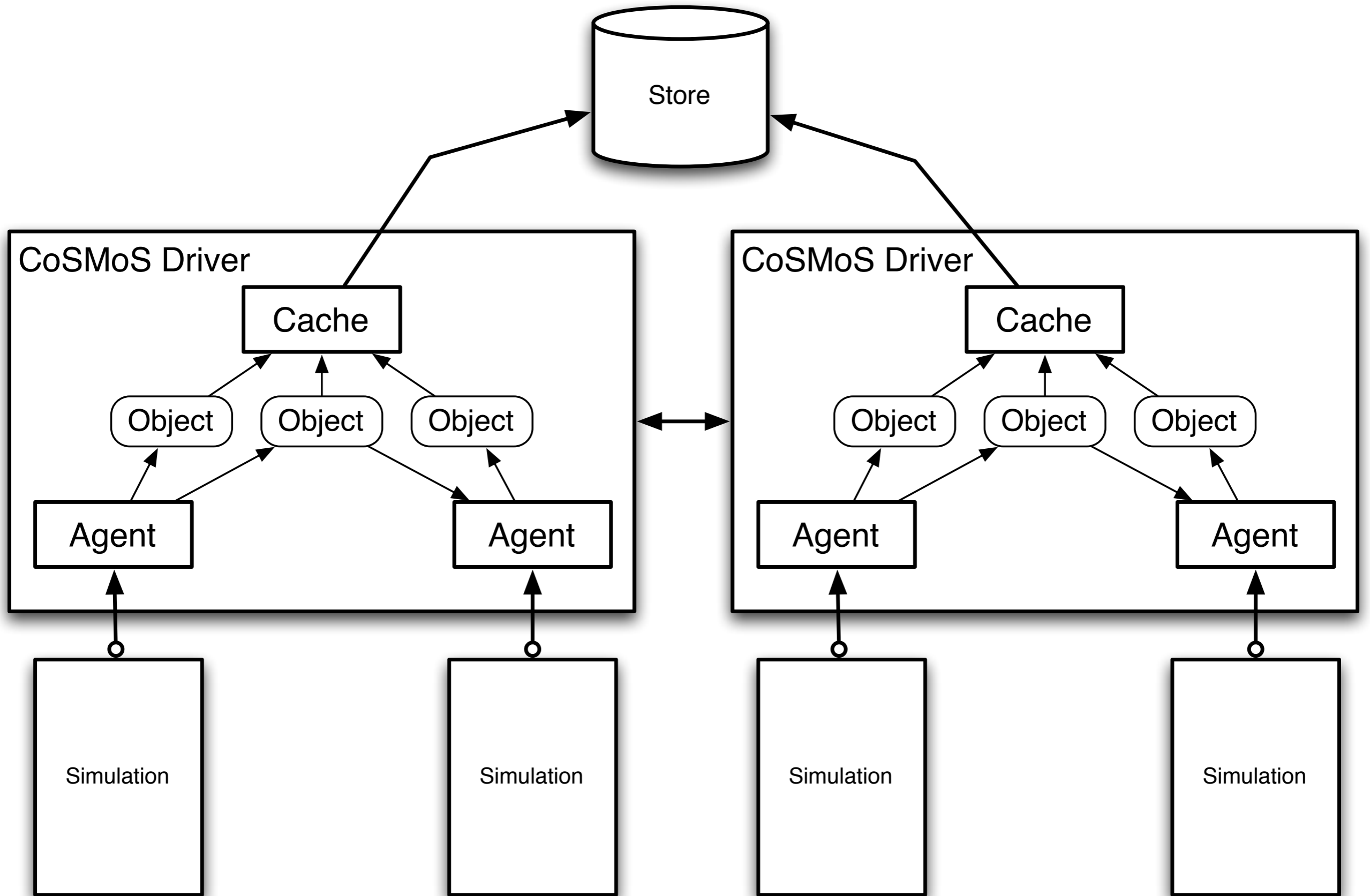
Big hash table / dictionary

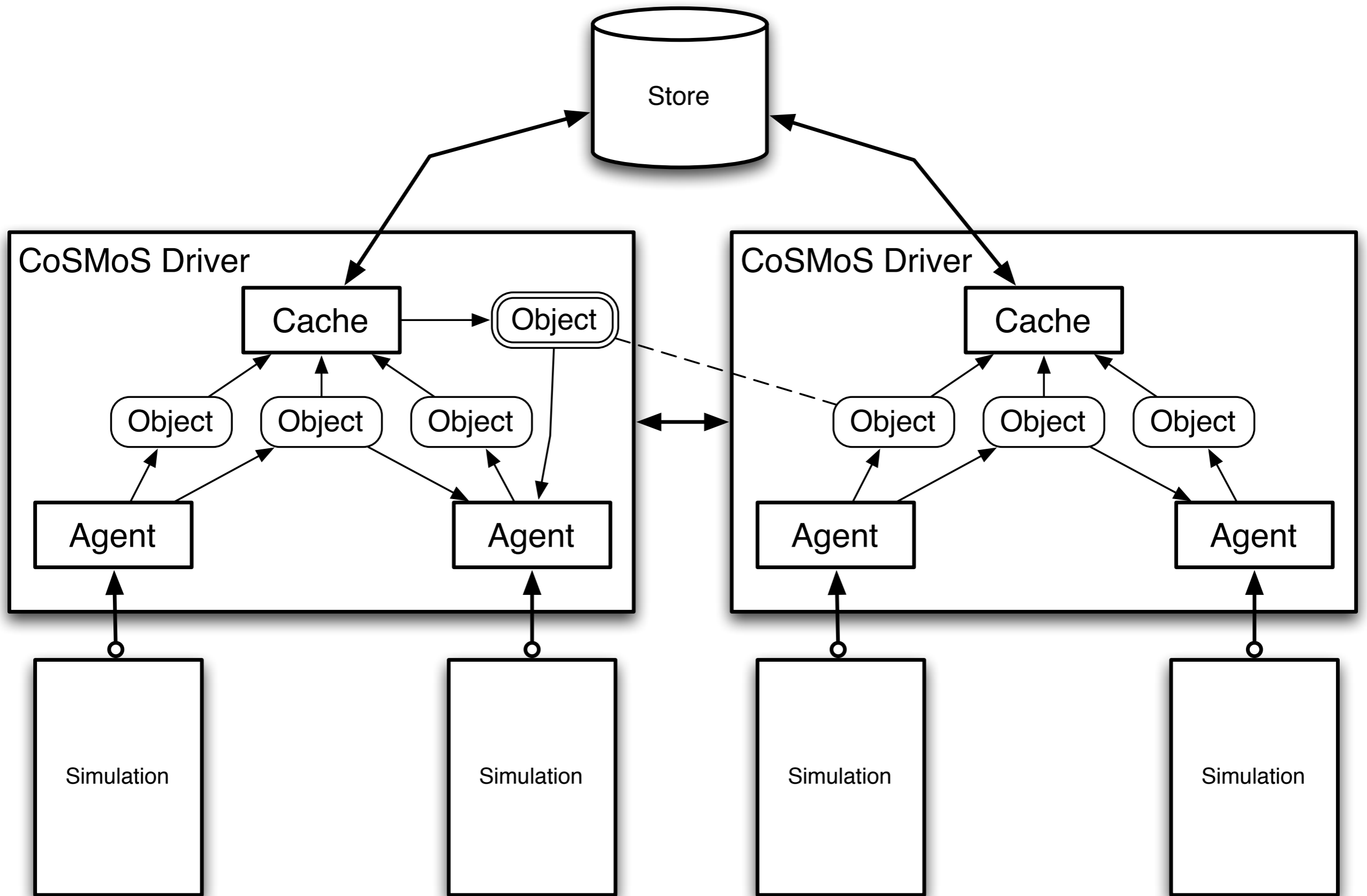
$O(1)$ access, replication, etc

Keys, e.g. obj_1:field_1:r0







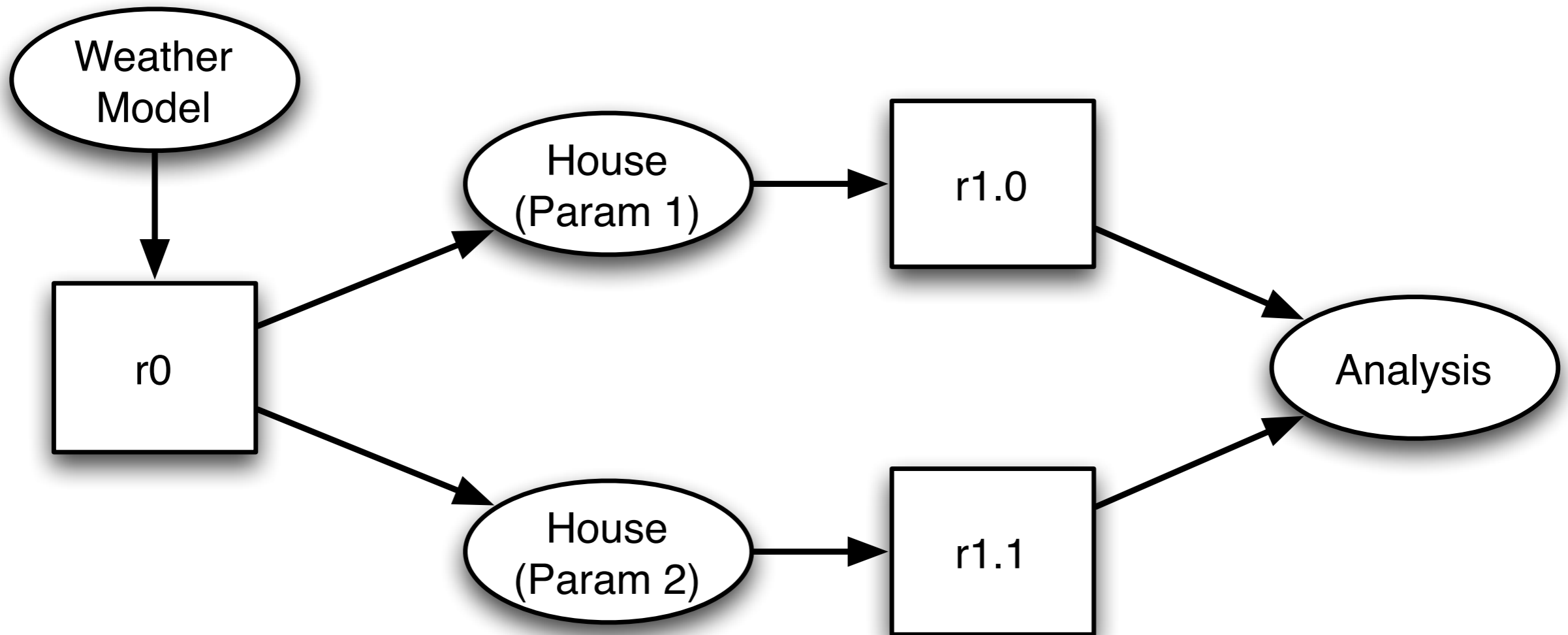


Versioning

Repeat runs based on stored data

Analysis of multiple data sets

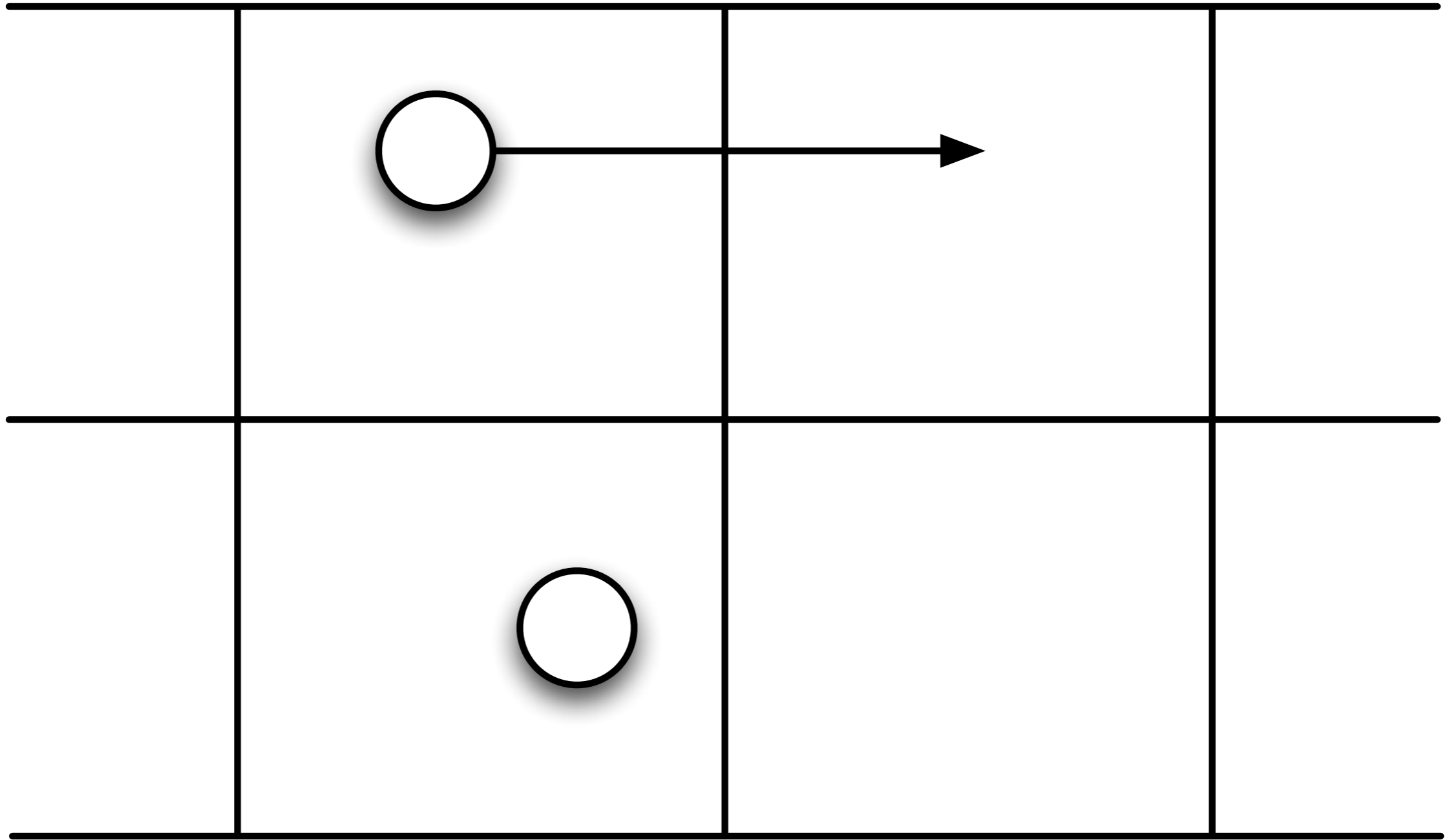
Prefix/postfix keys

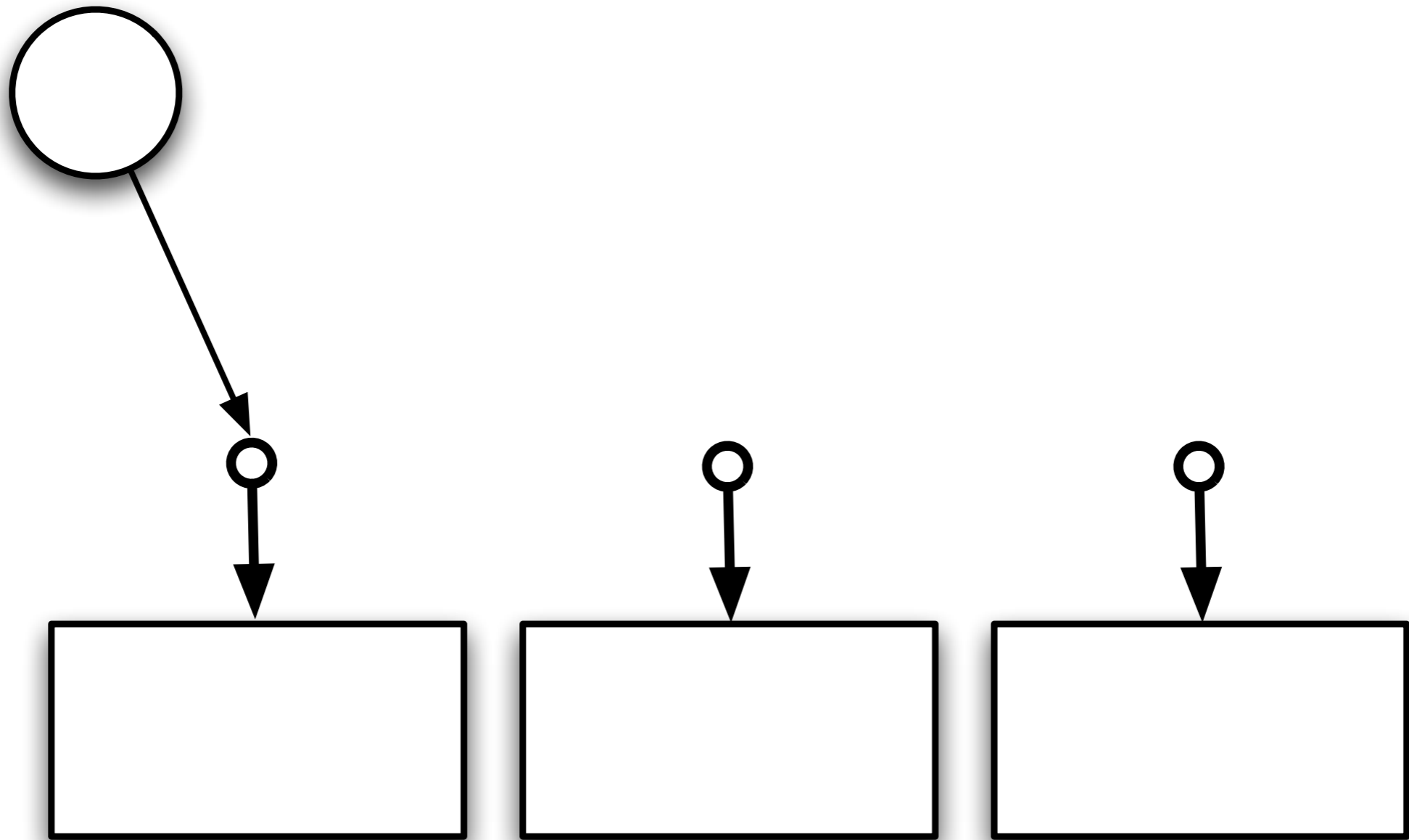


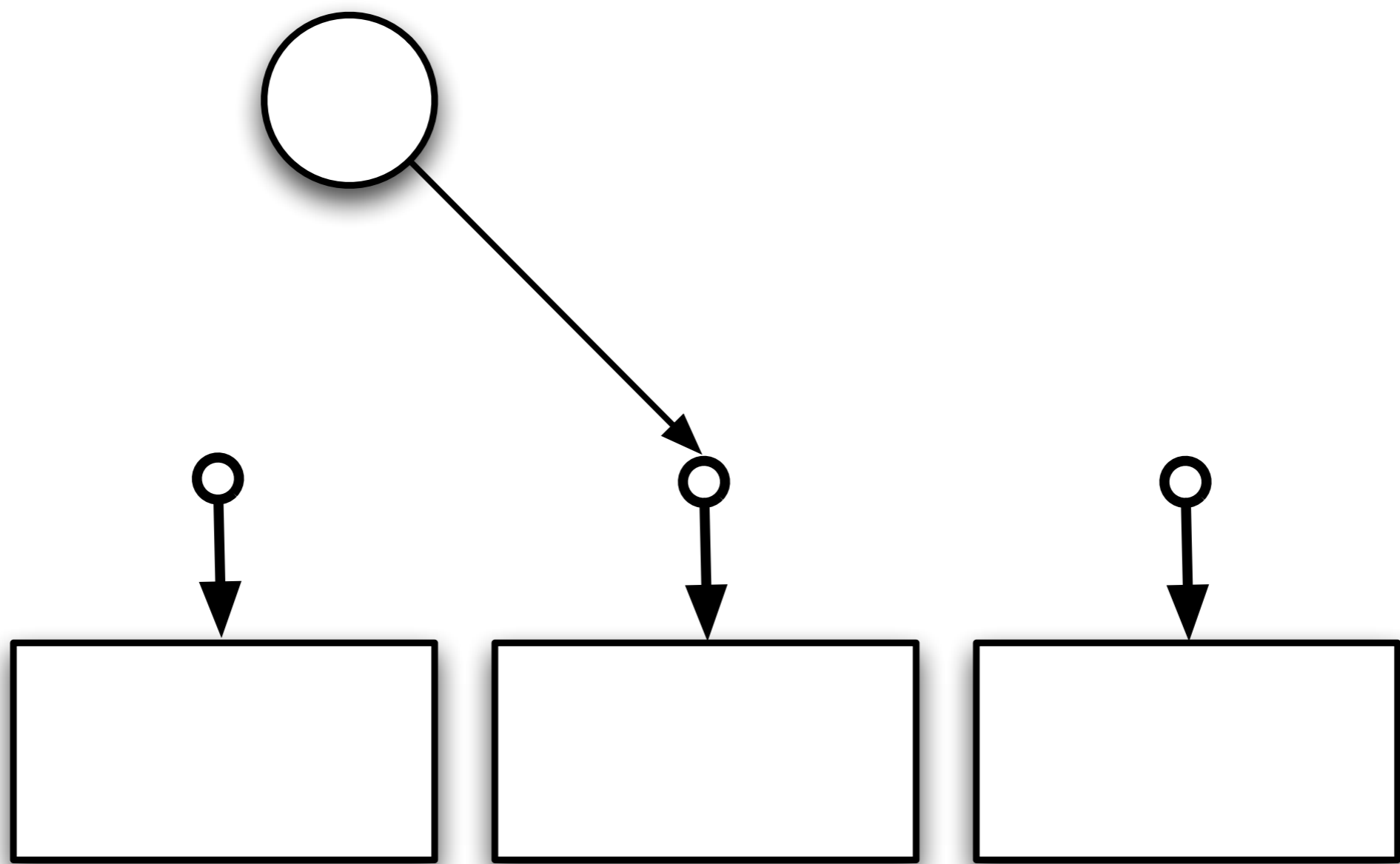
Case Study

Boids (occoids)

Flocking emergence (depending on parameters)







Retasking

Visual demo

Different dynamics: Bees

Not scientific

Modifications

Record simulations

Analyse agent movement

System Entropy

Singular Value Decomposition

$$Z = \begin{bmatrix} \overbrace{P.x_1^1 \ P.y_1^1 \ V.x_1^1 \ V.y_1^1}^{Boid_1} \ \dots \ \overbrace{P.x_1^n \ P.y_1^n \ V.x_1^n \ V.y_1^n}^{Boid_n} \\ \vdots \ \quad \quad \quad \vdots \ \quad \quad \quad \vdots \\ \overbrace{P.x_m^1 \ P.y_m^1 \ V.x_m^1 \ V.y_m^1}^{Boid_1} \ \dots \ \overbrace{P.x_m^n \ P.y_m^n \ V.x_m^n \ V.y_m^n}^{Boid_n} \end{bmatrix}$$

$$\bar{P}_{group_n} = \frac{\sum_{i \in group_n} P_t^i}{n} \wedge \bar{V}_{group_n} = \frac{\sum_{i \in group_n} V_t^i}{n}$$

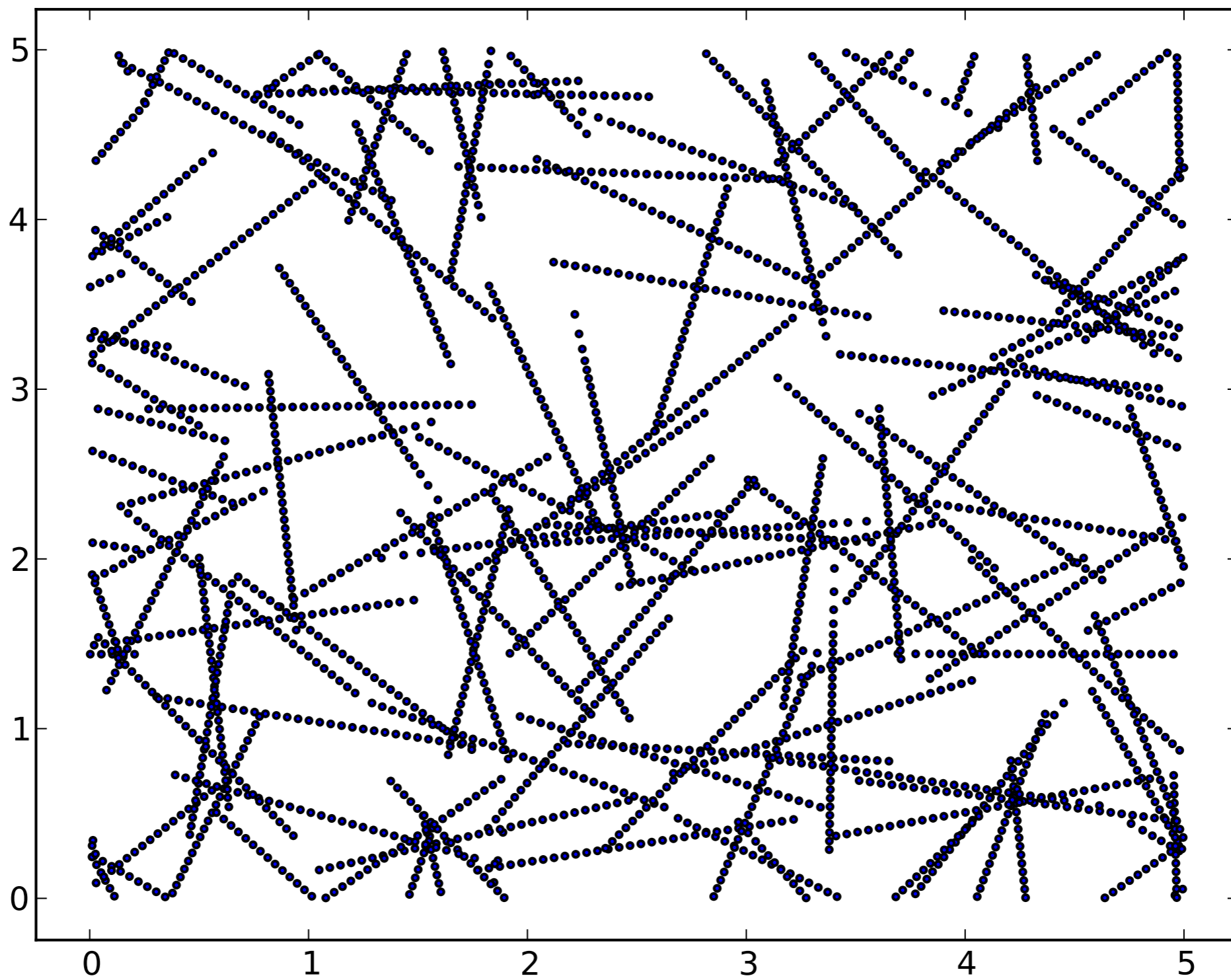
$$\forall_i Z.P_t^i \leftarrow \bar{P}_t - Z.P_t^i \wedge \forall_i Z.V_t^i \leftarrow \bar{V}_t - V.P_t^i$$

$$\Sigma_t = \text{SVD}(Z_t)$$

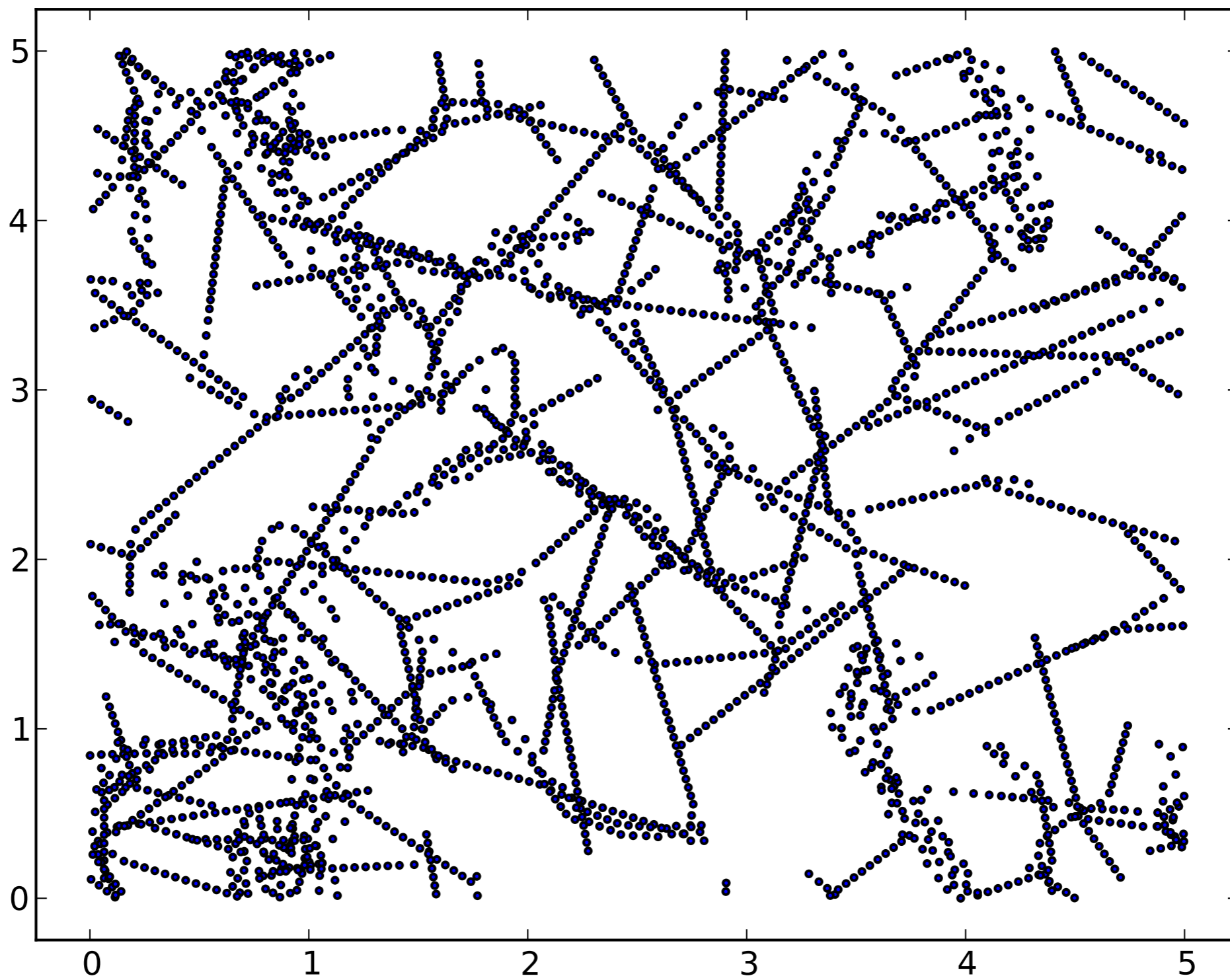
$$\Sigma'_t = \frac{\Sigma_t}{(\sum_i \sigma_{i,t})} \text{ where } \sigma_{i,t} \in \Sigma_t$$

$$S_t = - \sum_i \sigma'_{i,t} \cdot \log_2(\sigma'_{i,t})$$

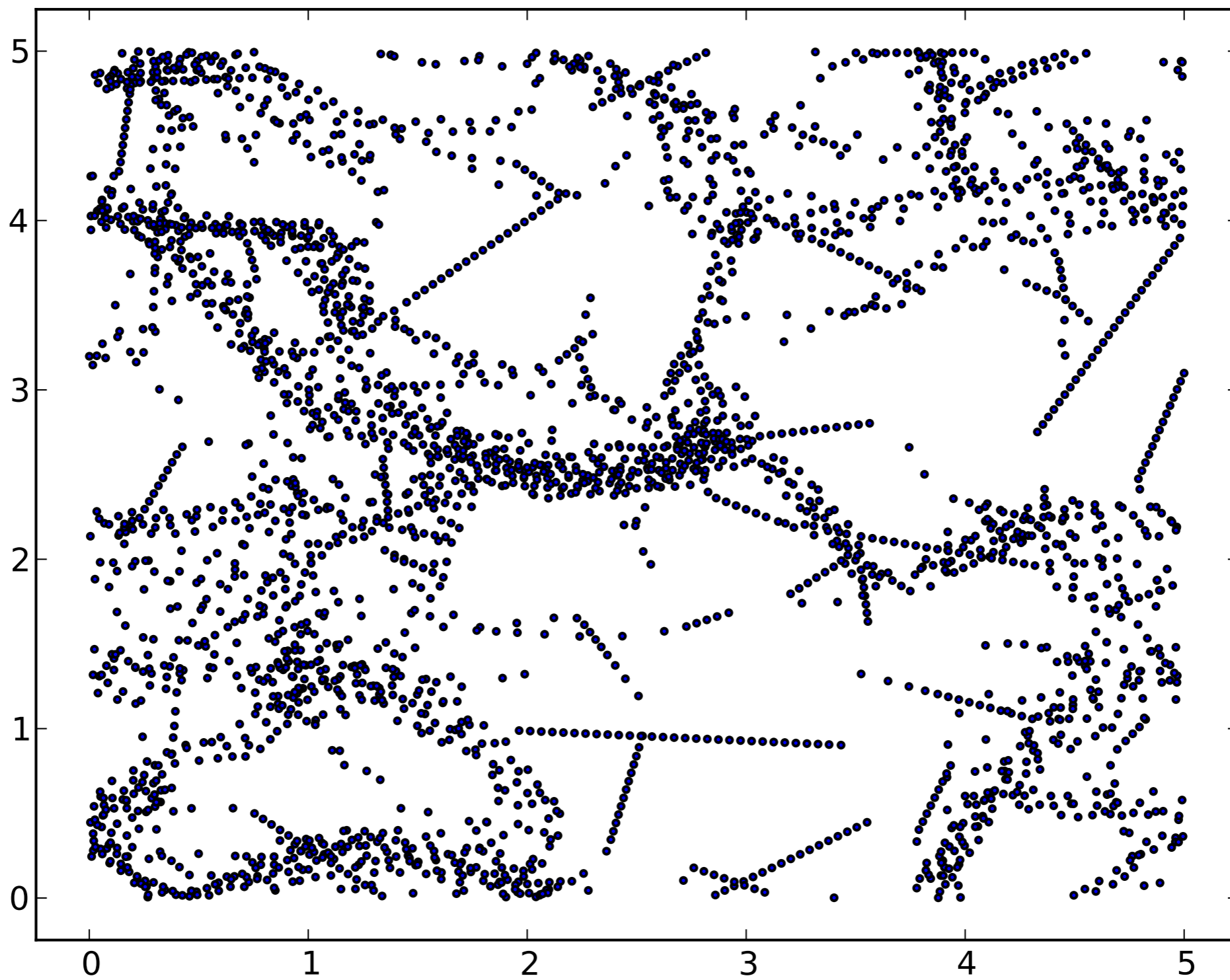
vision.radius=0.00



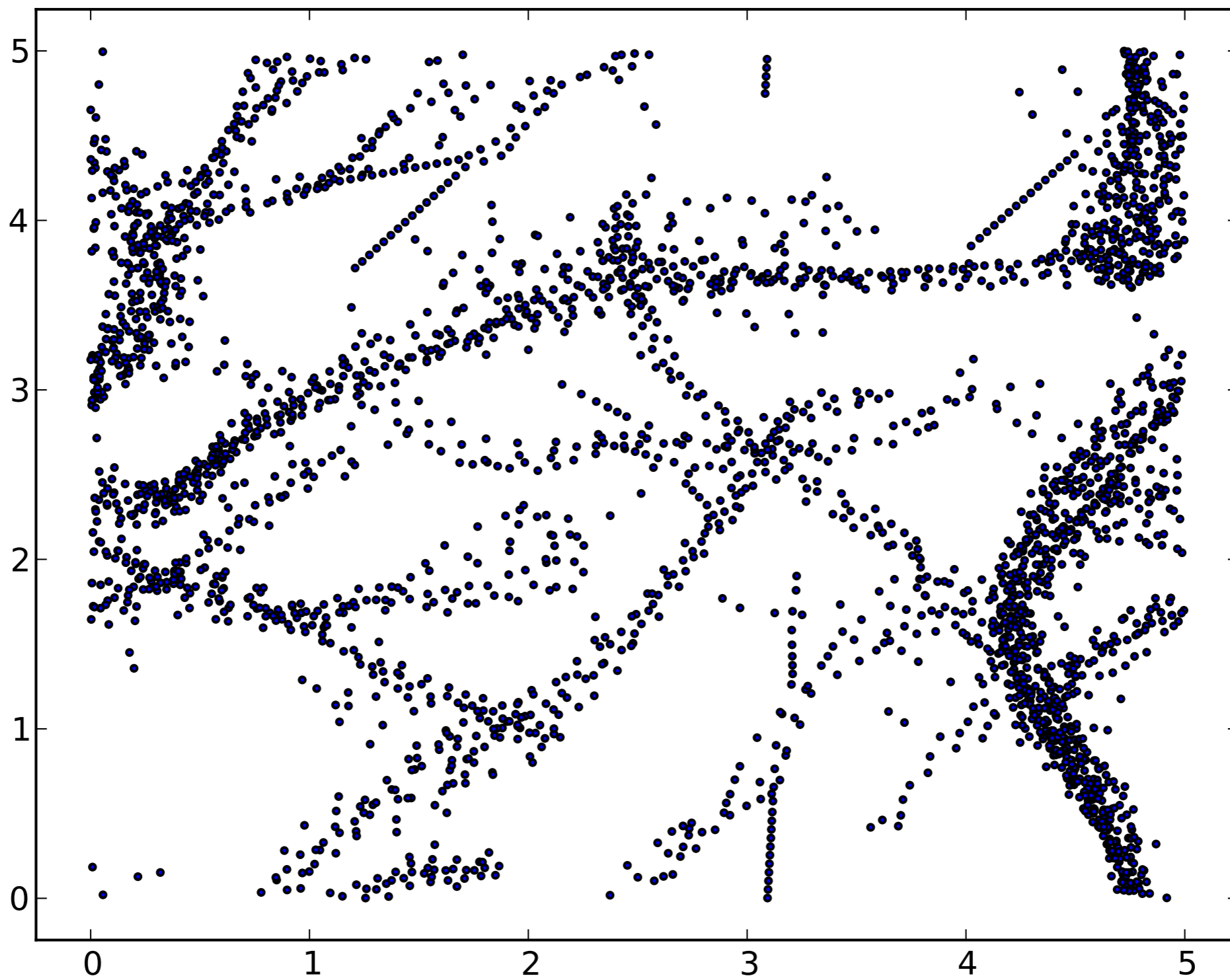
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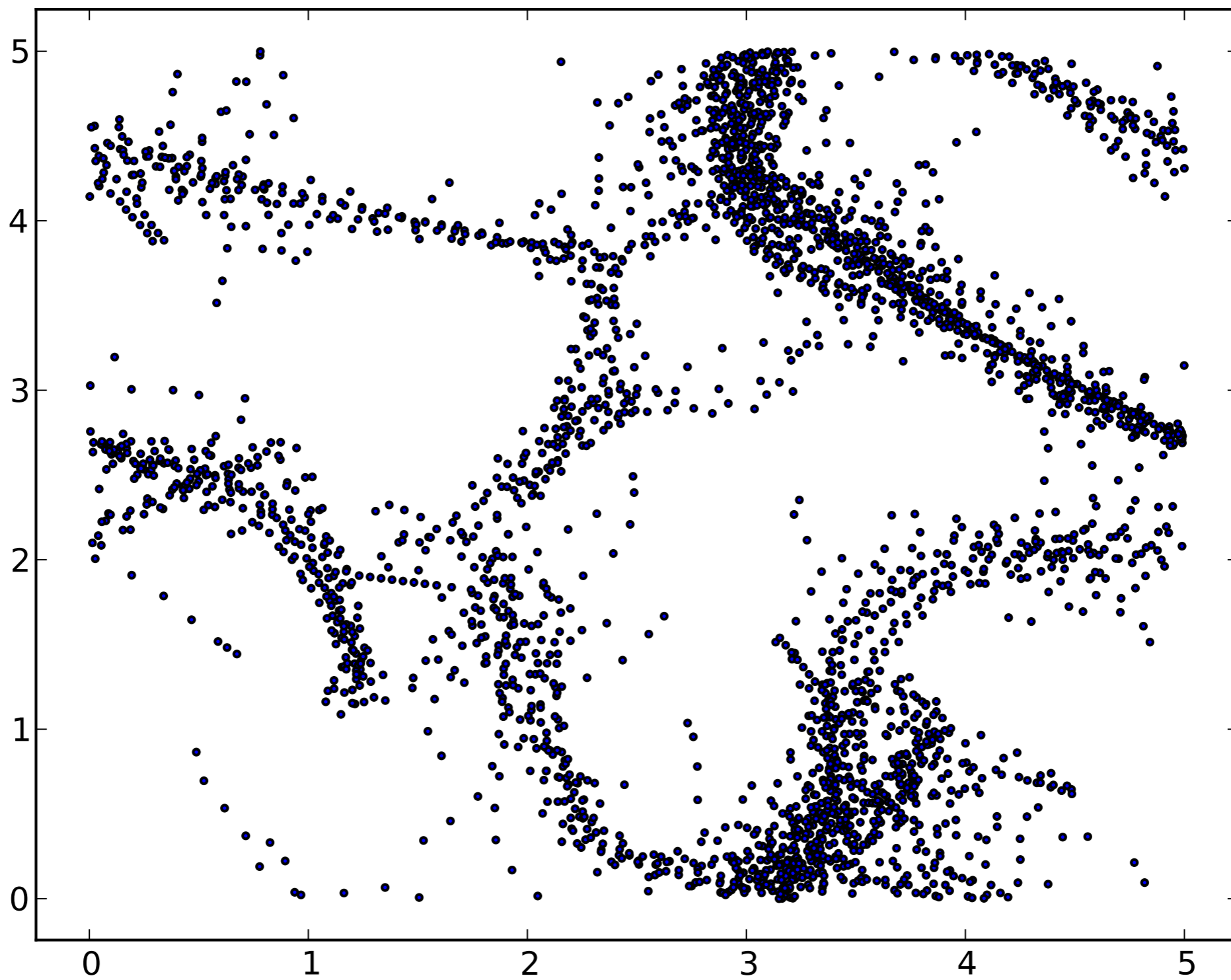
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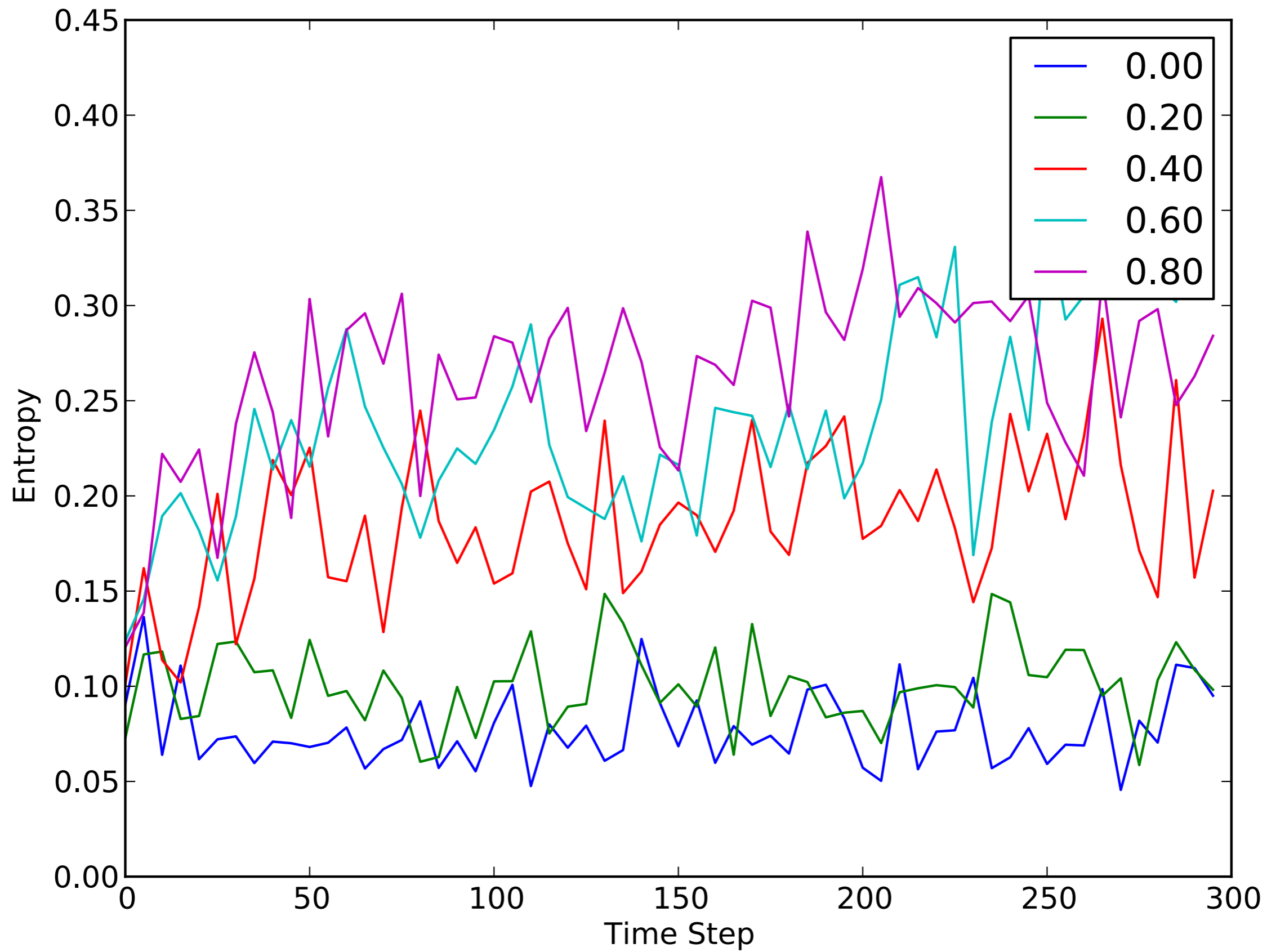


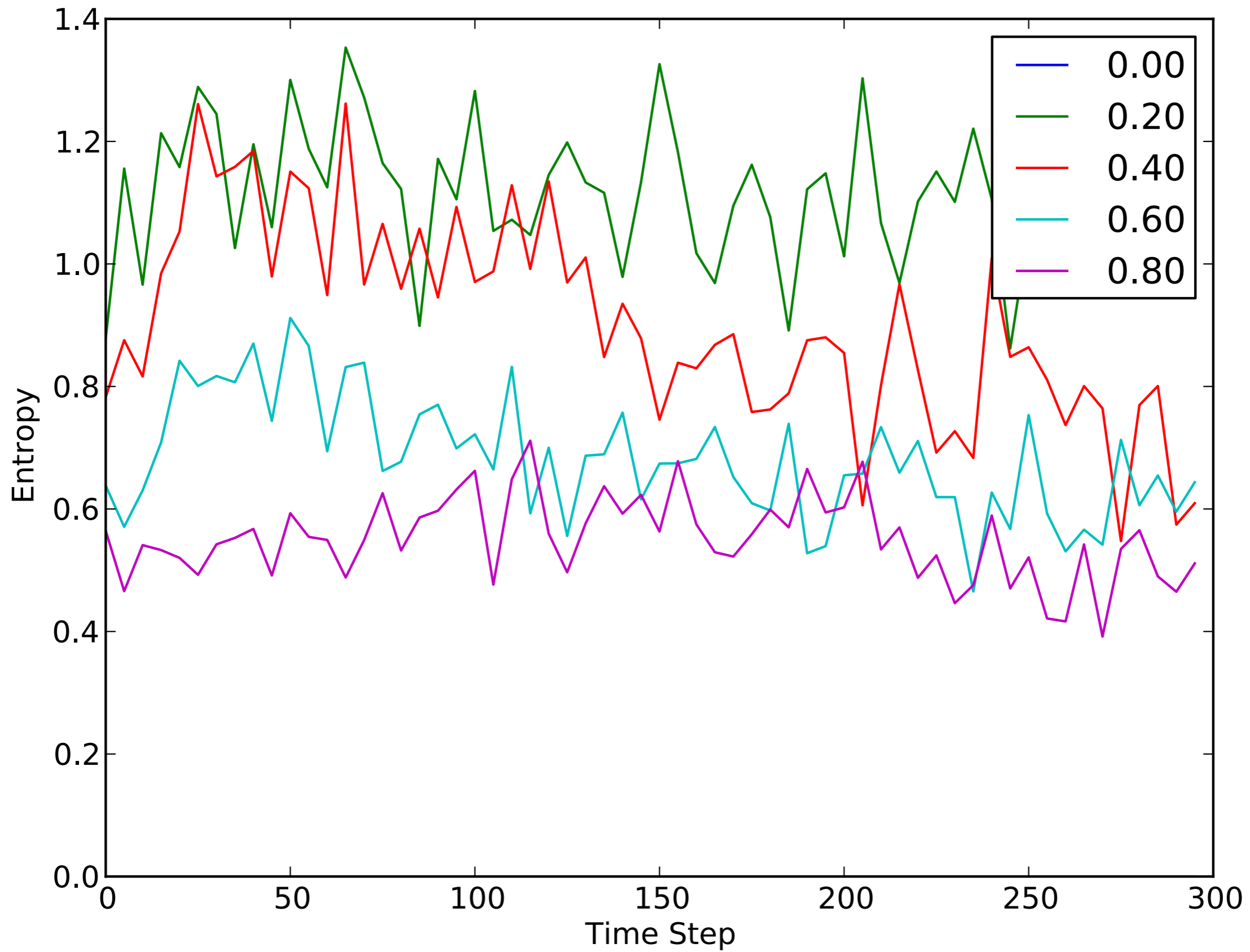
vision.radius=0.60



vision.radius=0.80







Summary

Loose coupling - synchronisation when required

On data, not explicit lock step

Coarse-grain to fine-grain support

Future Work

Performance

Time fuzziness

Questions?

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