



**MOTIUS**  
WE R&D.

# Omniverse for Automation Simulation

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November 18, 2025 12:05 (fbf23f7)



# Omniverse for Automation Simulation

 Automotive

 Robotics

 Synthetic Data

Our automotive customer needed to automate the movement of cars coming off the production line to various stations in the factory.

Differential Drive



Omnidirectional Drive



Ackermann Steering

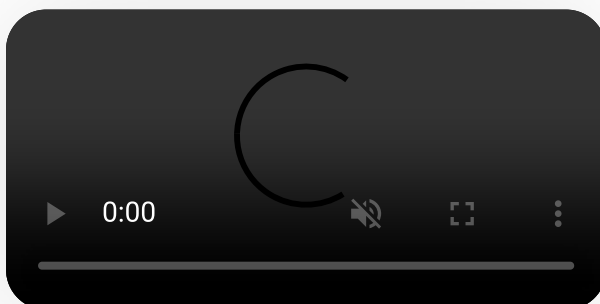


Various robots and even tele-operation solutions exist, but exploring them all with pilot projects would have taken too long, been too costly and it would have disrupted the production line.

Simpler scenario calculations did not answer the really important questions:

1. **How many robots** do we need to cover all shifts and all stations?
2. How do the robots behave in a realistic environment, including **limited space**, limited battery life, and other traffic?
3. How can we **adapt our factory layout** to optimize the flow of robots and cars? How does this change the number and type of robots we need?

## Approach



We built a simulation environment in NVIDIA's Isaac Sim to answer these questions, and to simulate the behavior of different types of autonomous mobile robots (AMRs) in a factory setting.

Using the library of open source robot models for ROS and synthetic data generation capabilities of Omniverse, the Motius team put together realistic simulations of each robot

## Software Architecture

Next to Isaac Sim, we needed a central fleet manager to realistically control the robots. The scenarios also needed to be controlled and monitored.

### Isaac Sim Environment

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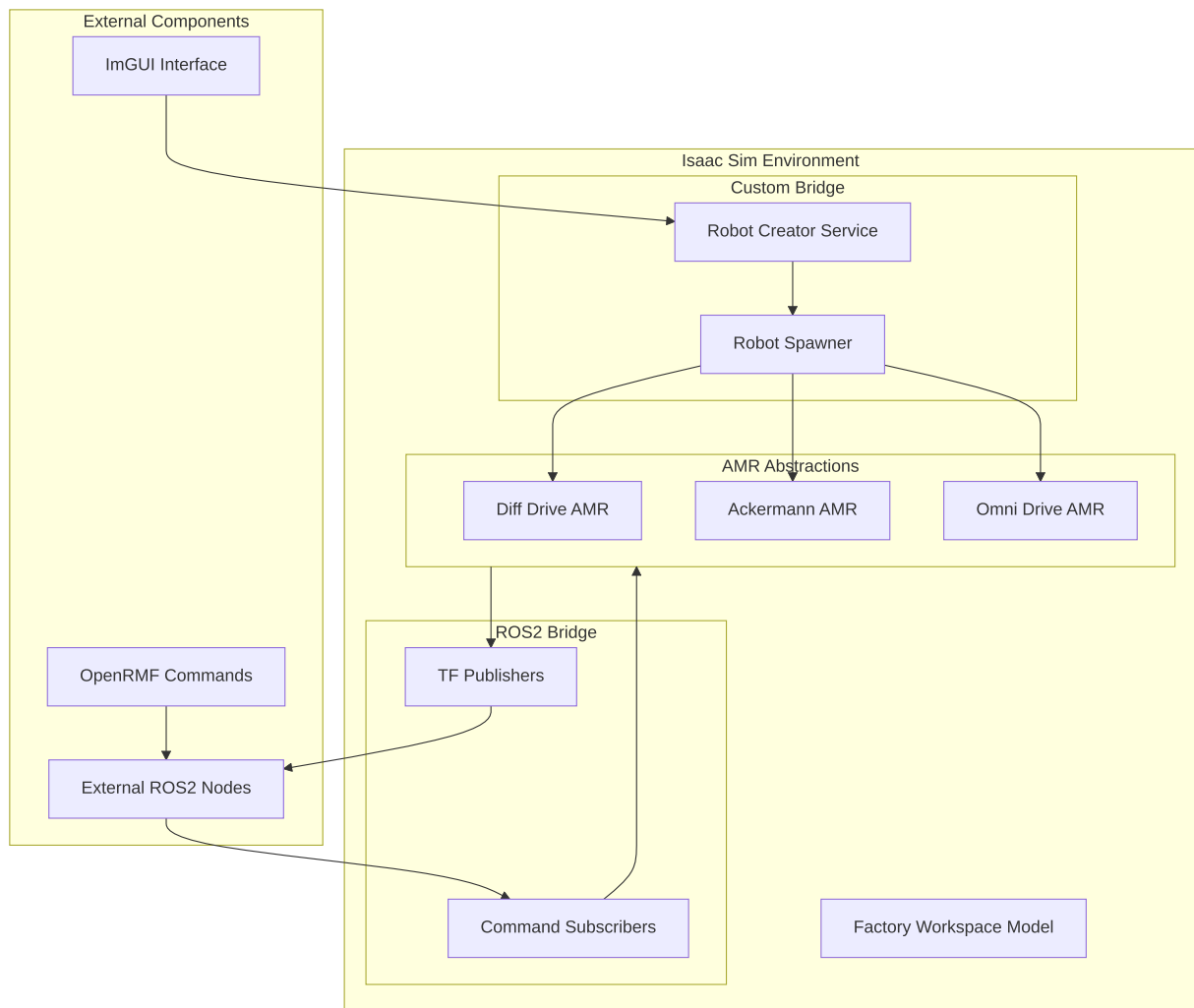
The simulation environment is built using NVIDIA's Isaac Sim, which provides a realistic physics engine and rendering capabilities for simulating autonomous mobile robots (AMRs) in a factory setting.

### Integration Points

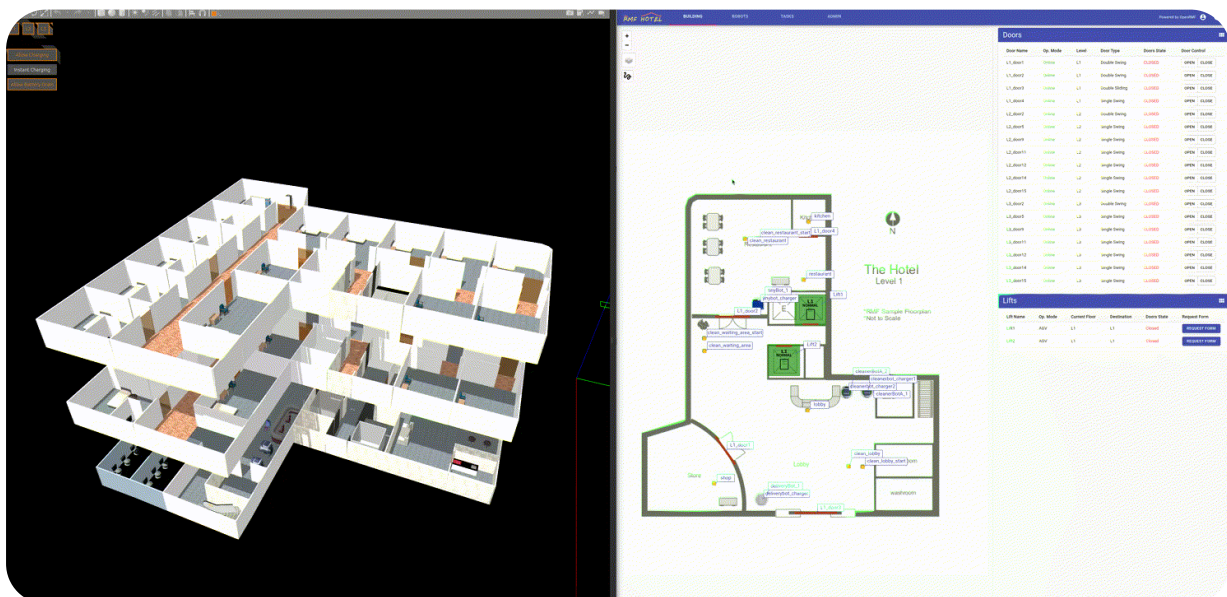
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OpenRMF integrates with the simulation environment to send commands, create robots dynamically, and provide real-time feedback on robot poses.

Finally, results of the simulation (robot types, number, performance, etc.) needed to be logged and analyzed.



## OpenRMF



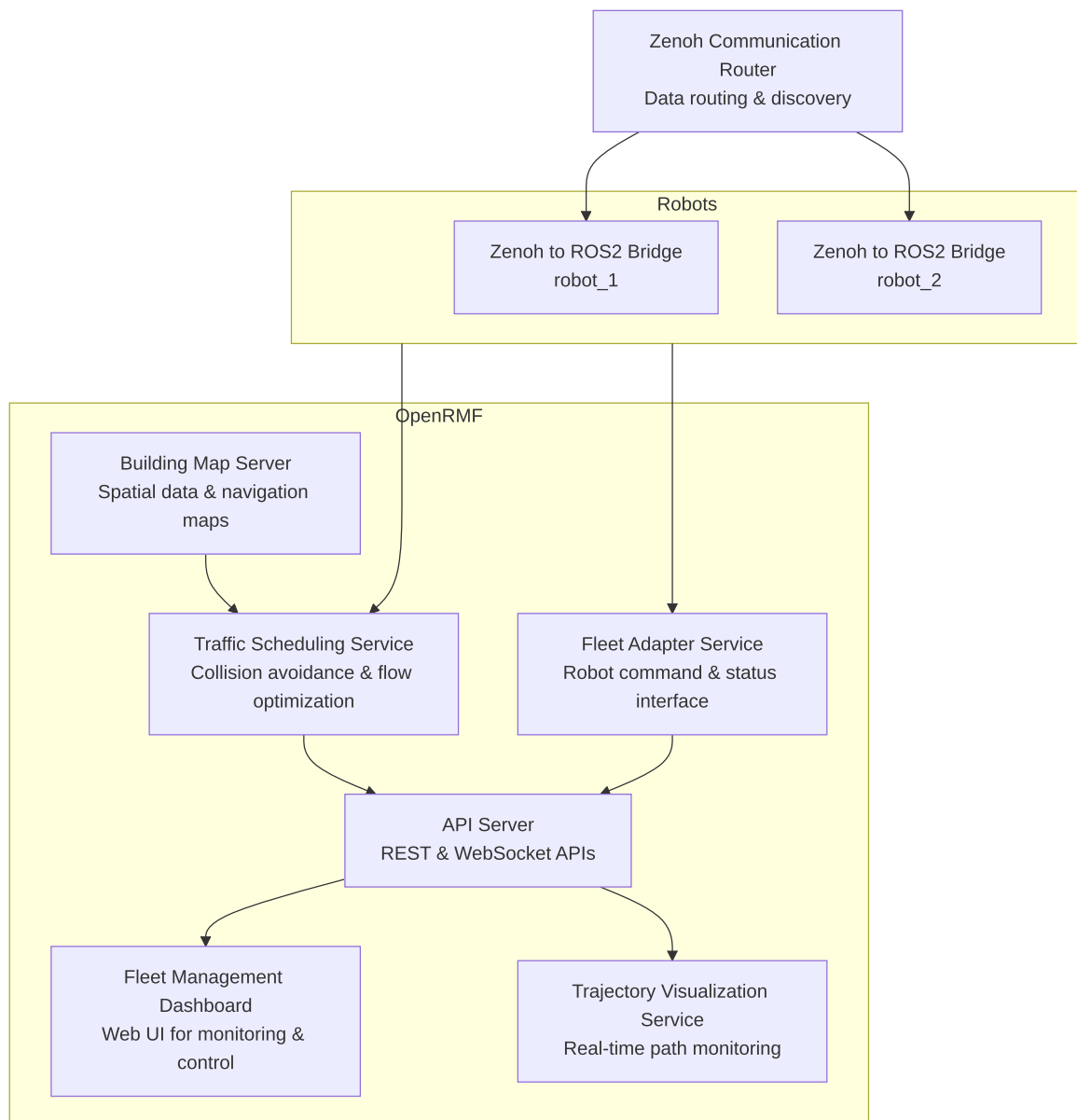
*Demo video of Open RMF in a multi-story office building*

OpenRMF is used as a fleet management system and central map server:

- ☑ Each robot gets its own Zenoh bridge for isolated control
- ☑ Traffic Management prevents AMRs from crashing into each other using the building map and tracks where each robot is going
- ☑ Web dashboard lets operators the status of the robot and task execution
- ☑ We built tools to import maps and define zones of interest



## OpenRMF Architecture



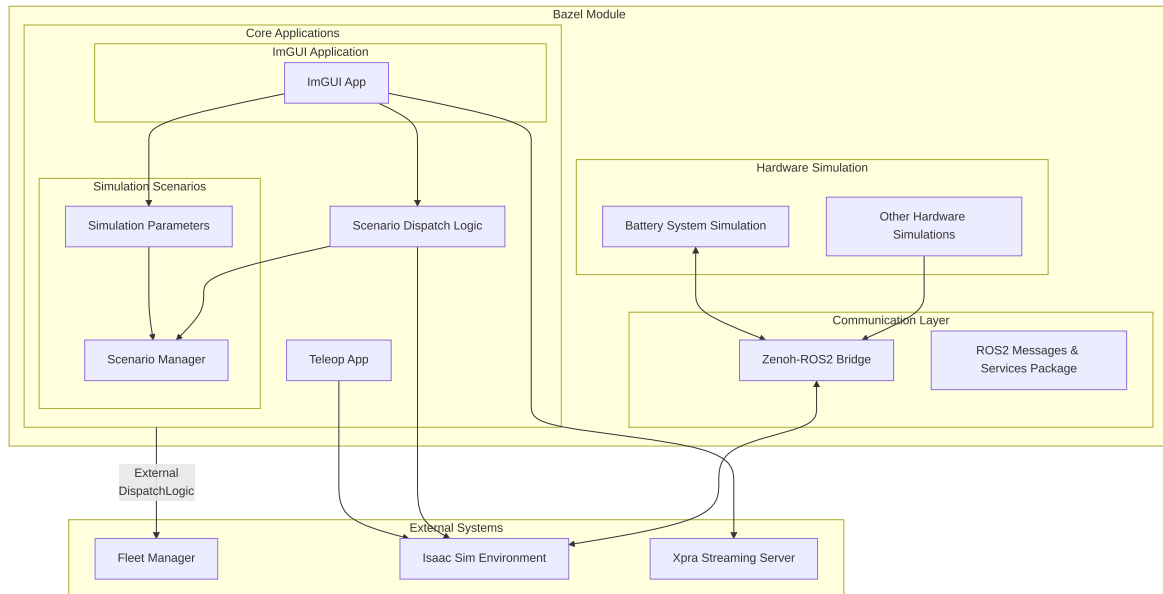
## Development Workflow



Our simulation runs in a **Kubernetes** cluster, allowing us to develop and test scenarios locally or in the cloud.

 **Bazel** is used to manage dependencies and build the simulation environment, ensuring a consistent and reproducible development workflow.

## Structure in Bazel



## Deployment

Our simulation runs in Kubernetes, both locally for engineering, and in a cloud environment for executing long-running scenarios.

The cloud deployment comes with external systems that allow remote access, tracking KPIs of the scenarios, and tracing simulation execution.

## Application at UNTHA

For UNTHA's industrial shredding machines, IsaacSim could  UNTHA Logo significantly speed up development of new machine vision systems that detect anomalies in the shredding process, or in the shredded material.

- ✓ Simulate automation scenarios with new camera systems, at 80% accuracy in only 20% of the time it would take to pilot them
- ✓ Test real software components in a physics-based simulation environment
- ✓ Easily give your IT & OT engineers access to this environment to verify their own changes