Handbook of
Marine HIL simulator laboratory
and
Marine cybernetics laboratory

January 15, 2015

Introduction

Hva skal denne labben handle om?

Structure

Part I explains the concepts and motivations for real-time and hardware-in-the-loop (HIL) testing.

Part II describes the laboratory facilities and equipment. A general overview of hardware and software.

Part III is a user guide intended for students of the course. Step-by-step instructions for development and deployment of programs to the real-time controller are given. Lower level details, intended for laboratory assistants and customized use, are given in Part V.

Part IV holds the exercise texts for TMR4243 Marine Control Systems II.

Contents

Eirik: Skriv ordentlig om labview/XML delen av FPGA programmeringen

Nomenclature

cRIO	National Instruments compact reconfigurable input/output real-time embedded industrial controller
CSE1	Cybership Enterprise 1
HIL	Hardware-in-the-loop
MC	Marine cybernetics
RPi	Raspberry Pi single-board computer
VI	virtual instrument, a LabVIEW program

Part I

Theory

1 HIL

DNV, Hardware in the Loop Testing (HIL)

Johansen, Sørensen, Experiences with HIL Simulator Testing of Power Management Systems

Smogeli, Introduction to third- party HIL testing

Johansen, Fossen, Vik, Hardware-in-the-loop Testing of DP systems

Pivano, Experiences from seven years of DP software testing

DNV, Rules for Classification of Ships (Part 6, Ch 22)

Ambrosovskaya, Approach for Advanced Testing of DP Control System

Selvam, System Verification Helps Validate Complex Integrated Systems

A. Veksler prøveforelesning:

- Increased complexity marine vessels increases the need for testing and verification.
- A reasonably new approach to this is Hardware-In-the-Loop testing, or HIL.
- Widely used in the automotive industry
- Can be seen as something in between simulation testing and full scale testing
  - More realistic than a simulation, less realistic than a full-scale testing
  - Mathematical models of the systems that are not included as hardware.
- A real-time simulator, constructed by hardware and software, that is
  - configured for the control system under consideration
  - embedded in external hardware
  - and interfaced to the target system or component through appropriate I/O
- Advantages:
  - Another layer of independent verification
  - Allows testing emergency procedures that would be too dangerous on a real vessel
- Disadvantages:

  - Initial investment to set up a HIL simulator for a particular system. The resources could be spent on simulation testing or full scale testing.
  - Supplements, but does not replace, proper software design techniques
    * As with all software testing, it typically executes only a fraction of the control system code.

Asgeir

- HIL testing is accomplished by connecting a simulation PC in the system's communication network.
- Inputs to the equipment under test are simulated.
- The controllers respond as they would in a dynamic environment.
- Simulator responds to output from the controllers as the dynamic system would
- Software (core SW and/or configuration) errors are exposed.

1.1 Real-time computing

1.2 SIL

1.3 Model-in-the-loop

Part II

Laboratory description

2 HIL-lab

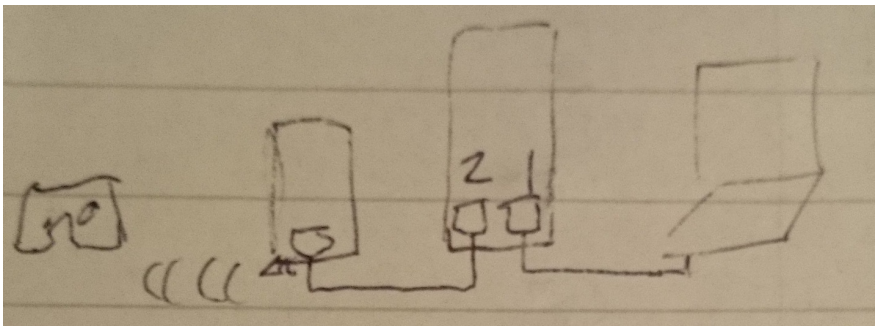

Figure 1: HIL setup

The lab consists of three equivalent setups, as illustrated in Figure 1, each including

- Sony Sixaxis wireless gamepad for PlayStation 3 (PS3)
- Raspberry Pi with Bluetooth dongle
- National Instruments (NI) cRIO-9024 compact reconfigurable input/output embedded real-time control and acquisition device
- Dell Latitude E6440 laptop

And what can we do with it

- k

Hva brukes det enkelte program-met til?

2.1 Hardware

2.1.1 cRIO-9024

The CompactRIO system's rugged hardware architecture includes I/O modules, a reconfigurable FPGA chassis, and an embedded controller. Additionally, CompactRIO is programmed with NI LabVIEW graphical programming tools and can be used in a variety of embedded control and monitoring applications. For more info vistit the producer website

Sakset fra ni.com/compactrio

2.2 Software

Only PC software, RPI and cRIO software in appendix.

MATLAB	Mathworks	Modelling
LabVIEW	National Instruments	
VeriStand	National Instruments	Interfacing, Real-time testing and simulation
NI MAX	National Instruments	Measurement & Automation Explorer: configurering av cRIO
Qualisys?		

Table 1: Software

Hva brukes det enkelte programmet til?

2.2.1 MATLAB

2.2.2 LabVIEW

LabVIEW - Real time module
National Instruments real-time technology offers reliable, deterministic performance for your time-critical applications. Use the LabVIEW Real-Time Module to develop and deploy complex real-time systems quickly and efficiently to the CompactRIO microprocessor.

2.2.3 VeriStand

2.2.4 NI MAX

2.2.5 Qualisys positioning system

The positioning system works by tracking reflectors placed on the ship with the use of high speed cameras.
Qualisys consists of three systems

- Qualisys Oqus: The cameras used to register/see the IR markers
- Qualisys Motion Capture Systems: is the system that process the data from Oqus
- Qualisys Track Manager: The userinterface to interact with Motion Capture System

2.3 Communication

.VxWorks RT targets - .out

3

3 MC-Lab

The Marine Cybernetics Laboratory is the newest test basin at the Marine Technology Centre. It is located in what was originally a storage tank for ship models made of paraffin wax.

As the name indicates, the facility is especially suited for tests of marine control systems, due to the relatively small size and advanced instrumentation package. It is also suitable for more specialised hydrodynamic tests, mainly due to the advanced towing carriage , which has capability for precise movement of models in 6 degrees of freedom.

The MCLab is operated by the Department of Marine Technology, and has been a Marie Curie EU Training Site (2002-2008). It is mainly used by Master and PhD-students, but it is also available for MARINTEK and external users.

The software in use was developed using rapid prototyping techniques and automatic code generation under Matlab/Simulink and Opal. The target PC onboard the vessel runs the QNX real-time operating system while experimental results are presented in real-time on a host PC using Labview.

Sakset rett fra nettsiden http://www.ntnu.edu/imt cybernetics-lab

3.1 CSE1 - CS Enterprise I

Figure 2: C/S Enterprise I

Control system

PWM

Digital output

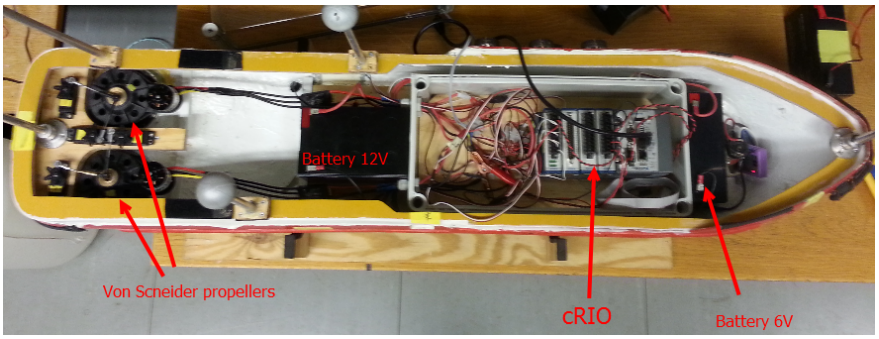

Figure 3: CSE1 - Hardware

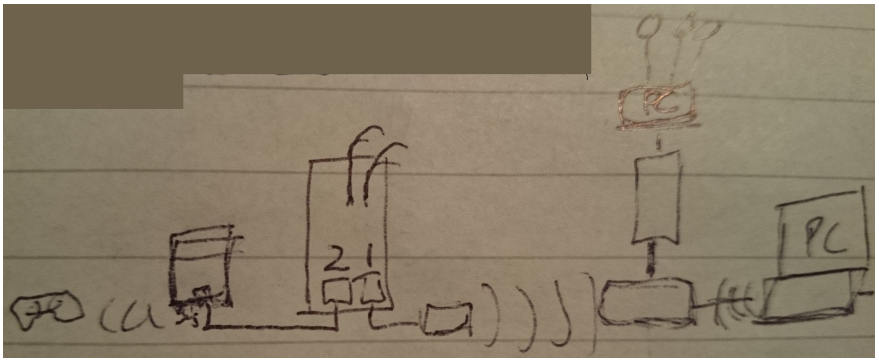

Figure 4: CSE1 setup

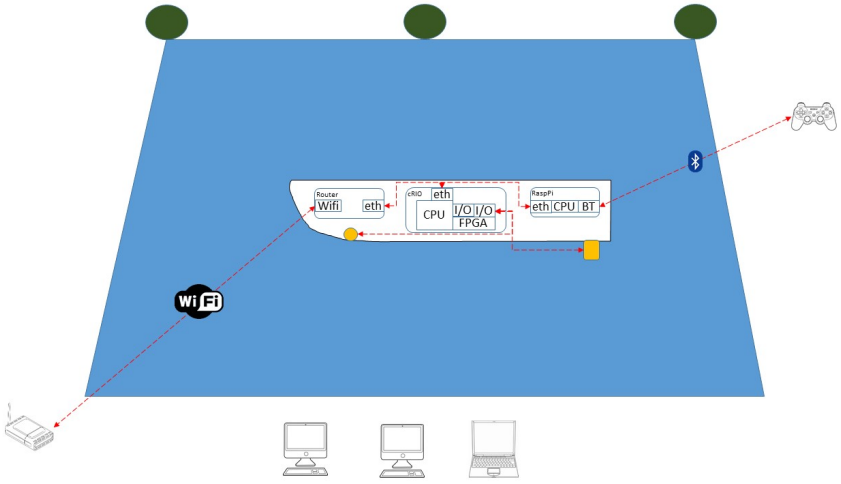

Figure 5: Towing carriage

3.2 Qualisys postitioning system

3.3 Communication

For communication with the ship, the wireless network HILlab is used

3.4 Towing carriage

Carriage : towing speed 2 m/s, 5 (6) DOFs forced motions Current generation: 0-0.15m/s

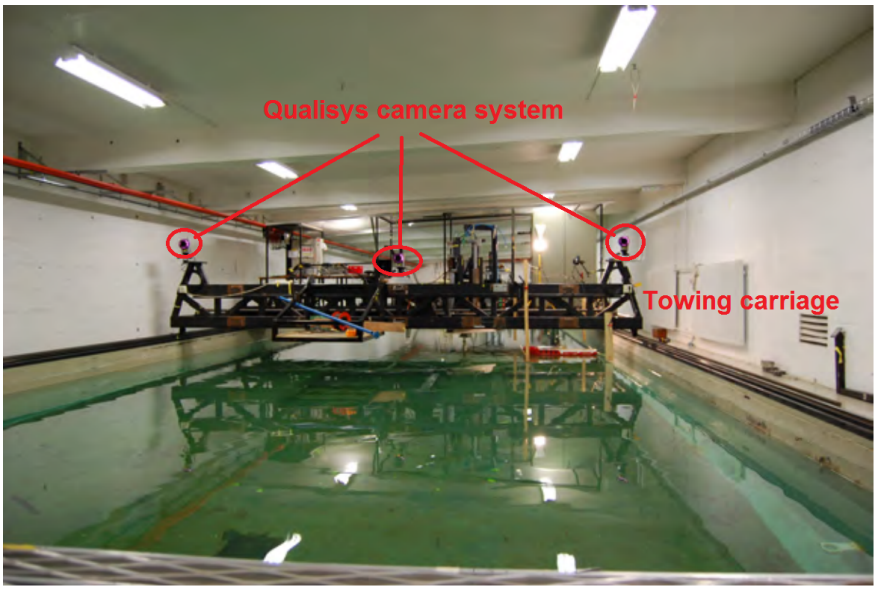

Figure 6: Towing carriage

3.5 Wave generator

The wave genertor is located at the end of the tank and is operated from its own copmuter. It has the capability to create first order Stoke waves or irregular recreate different wave spectras such as JONSWAP or PM spectras.
Significant wave height $H_s = 0.3$ [m] with period T between 0.6 [s] and 1.5 [s]

3.5.1 First order Stoke waves

First order stoke waves are regular linear waves. Very nice to do calculations with, but not so representative for real life conditions. Described by potential theory

3.5.2 Irregular waves

Part III

Laboratory user guide

4 Simulink model compilation

4.1 Modelling

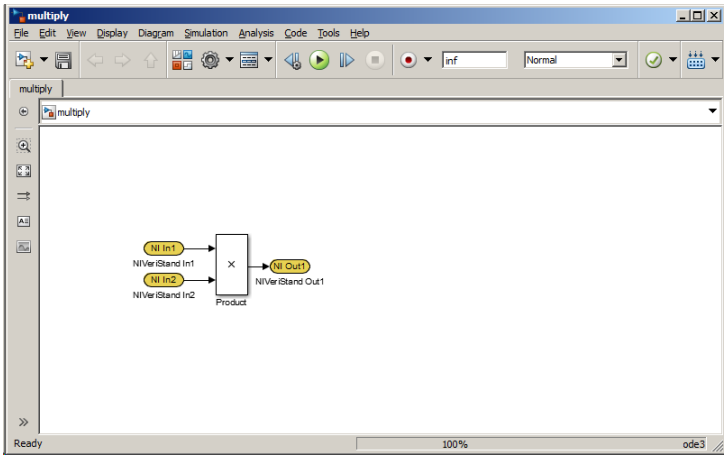

Figure 7: Simulink model for VeriStand

Simulink inports and outports located on the top-level of the simulation hierarchy in Simulink are available as inports and outports in NI VeriStand. Simulink inports and outports in submodels are available only if you place NI VeriStand inport and outport blocks in the submodel in Simulink.

The Simulink model's relevant inputs and outputs should have special VeriStand ports, as seen in yellow in Figure 7. The figure shows an example used throughout this section: two inputs are multiplied to form an output.

The special ports are available in the Simulink Library Browser under NI VeriStand Blocks, see Figure 8.

The model should be saved [model name].mdl

4.2 Model configuration

1. Open the Configuration parameters window by _____
2. Configure solver as in Figure 9.
   (a) Under "Simulation time", "Stop time" must be "inf" for infinite, since the model should not stop by itself

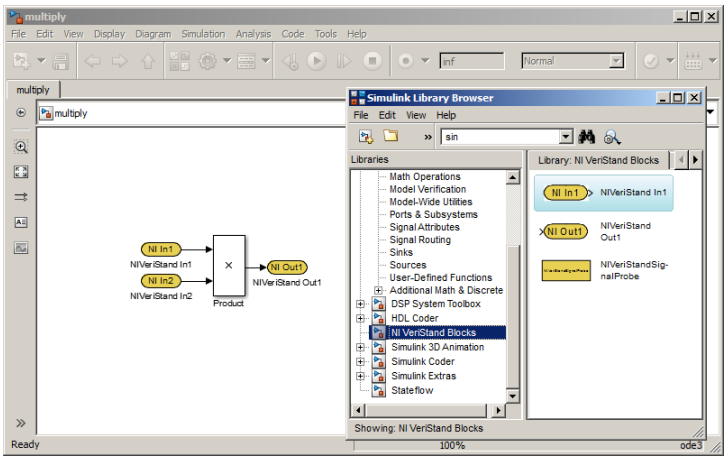

Figure 8: Simulink library

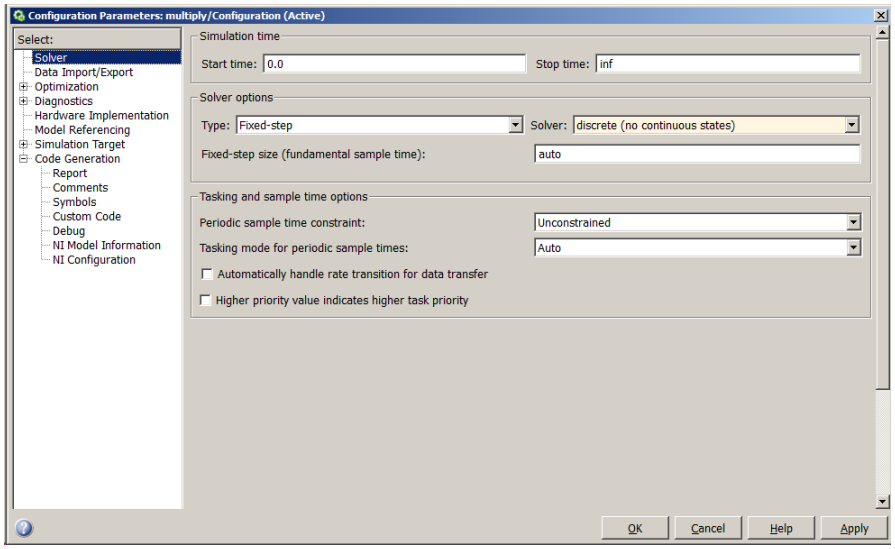

Figure 9: Simulink model configuration - solver

(b) Under “Solver options”, “Type” should be set to “Fixed-step” and “Solver” to “discrete (no continuous states)”

3. Configure target, 10

4. Make sure that the WindRiver GNU Toolchain Setup Path is correct, Figure 11

4.3 Build

Creates a build folder, named NAME_niVeriStand_VxWorks_rtw, in the MATLAB Current Folder 12, need to change to the desired directory first

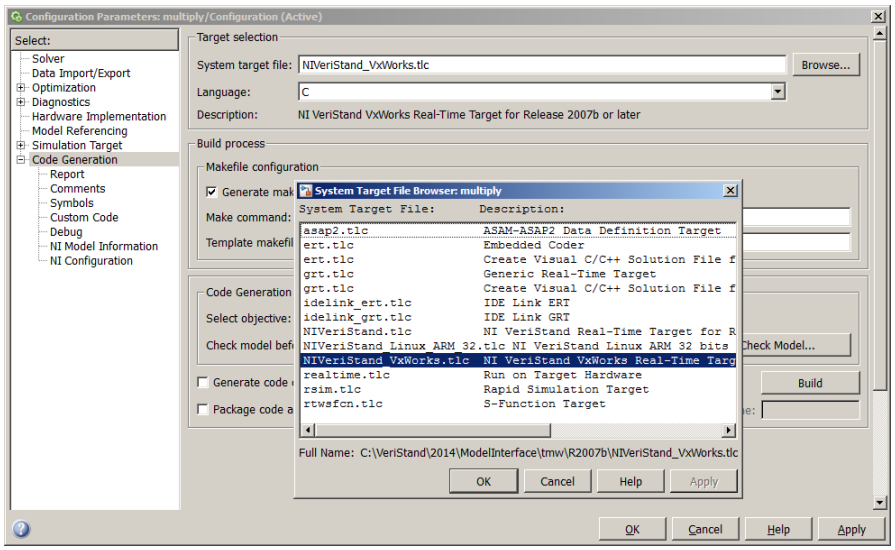

Figure 10: Simulink model configuration - target selection

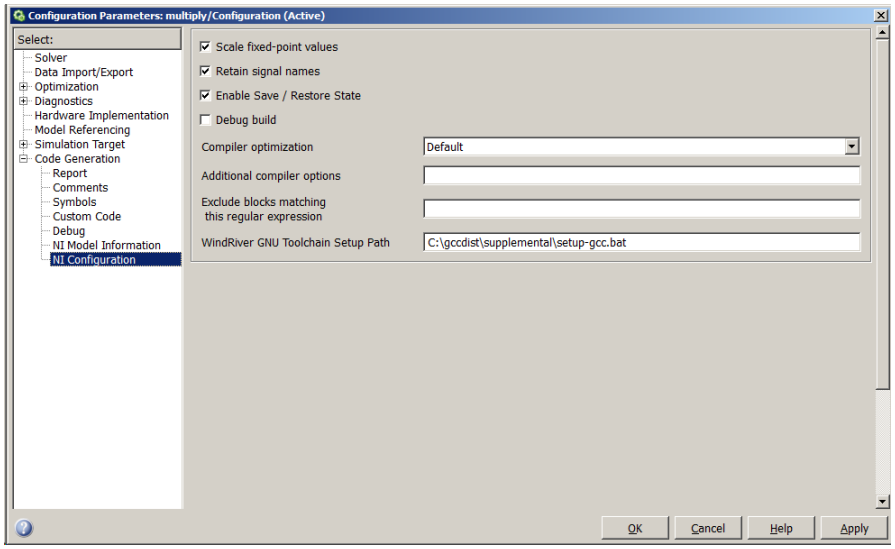

Figure 11: Simulink model configuration - NI configuration

In Simulink: Code ¿ C/C++ Code ¿ Build model or Ctrl+B or button

Model file [model name].out

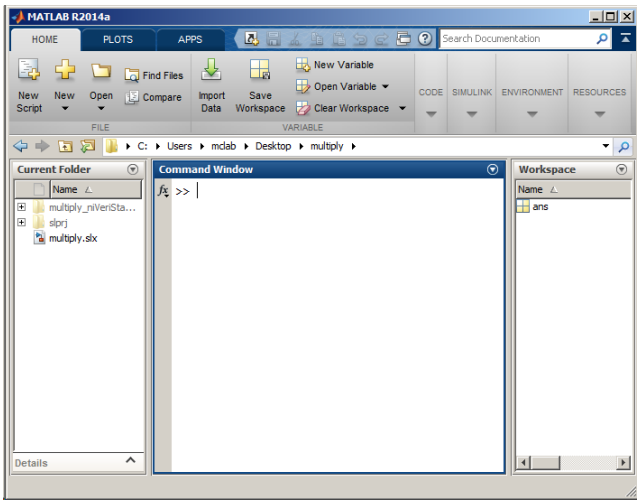

Figure 12: Matlab console

5 Model deployment

Models are deployed and interfaced through Veristand.

1. Start VeriStand 13

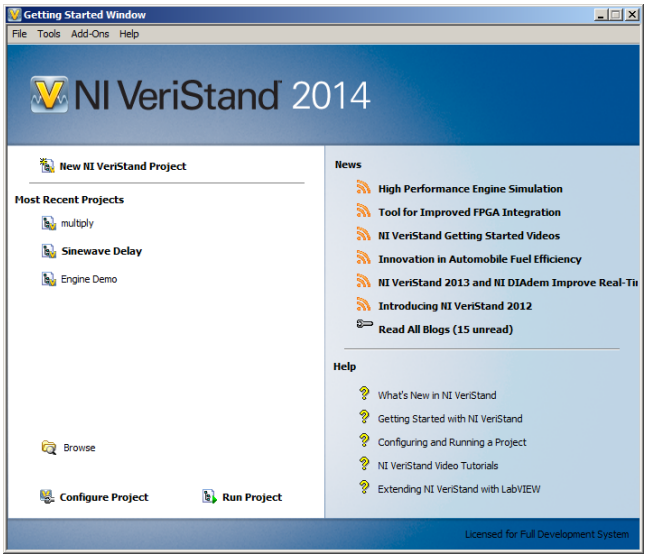

Figure 13: VeriStand

2. In the project explorer
3. In System Explorer

Veristand osv

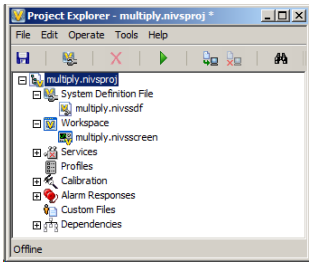

Figure 14: VeriStand Project Explorer

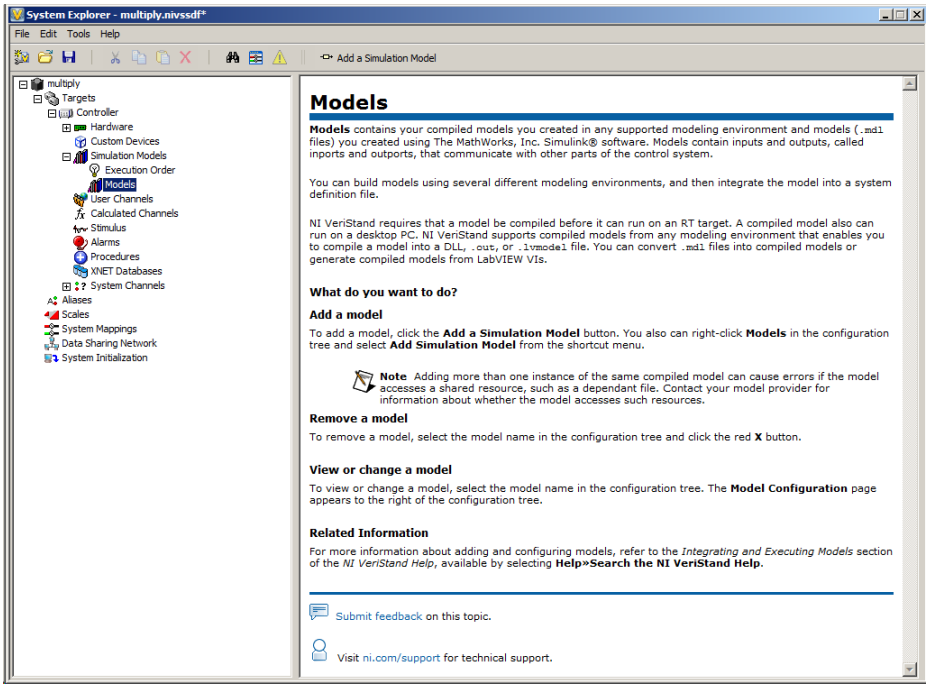

Figure 15: VeriStand - System Explorer

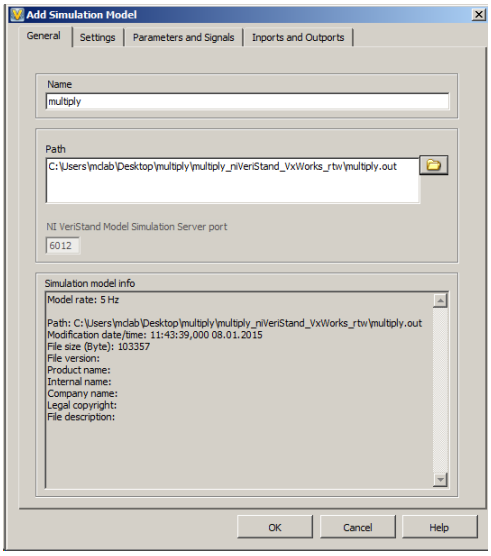

Figure 16: VeriStand - System Explorer Model

6 System interfacing

work space

6.0.1 Development for new algorithms in modules in Simulink

6.0.2 Development with structural changes in I/O or Labview UI

7 Deploying basic VI

1. Open LabVIEW
2. Create project
3. Blank project
4. In the left pane tree, right-click Project: XXX, New -¿ Targets and devices
5. Keep setting Existing target or device, Discover an existing target(s) or device(s)
6. In the tree, expand Real-Time CompactRIO, wait for search and select the cRIO
7. In the Project Explorer, drag and drop the VI to the device
8. Right-click the VI, Run

8 Running CSE1

8.1 Ship launching procedure - before sailing

8.1.1 Power connection

Batteries should be placed as in Figure 3

1. Main battery
   (a) Connect postive battery terminal ("RED-port" at portside) to wire with red isolation
   (b) Connect negative battery terminal ("BLACK-port" at starboard) to black isolation
2. Wait 5 seconds
3. Servo battery
   (a) Connect postive battery terminal ("RED-port" at portside) to wire with red isolation
   (b) Connect negative battery terminal ("BLACK-port" at starboard) to black isolation[1]

Power confirmation status lights:

1. one at bow in a purple box for indicating power to tunnel thuster
2. two close to "Main battery", one on each side for each Voith Schneider propeller

Communication confirmation:

1. The indicators on "ACT/LiNK" port 1 should light up (green) to indicate communication with "HILlab"

8.1.2 Communication test

The `ping` command-line utility is used to verify that the laptop has connection to the cRIO.

Use the command with the CSE1 cRIO IP address

```
ping 192.168.0.77
```

The result should be as in Figure 17.

- Open "Command Promt"
  - write: ping 192.168.0.77

[1] it should not matter in which order it is done, but from experience connectiong "RED-wire" before "BLACK-wire" gives a much higher probability for communication with the CompactRIO on Cybership Enterprise 1 (99-100%'ish) than connecting the "BLACK-wire" before the "RED-wire" (25%ish), and it is a habit to connect main before the servo, since main powers "CompactRIO" while servo powers "D-Link wireless bridge"

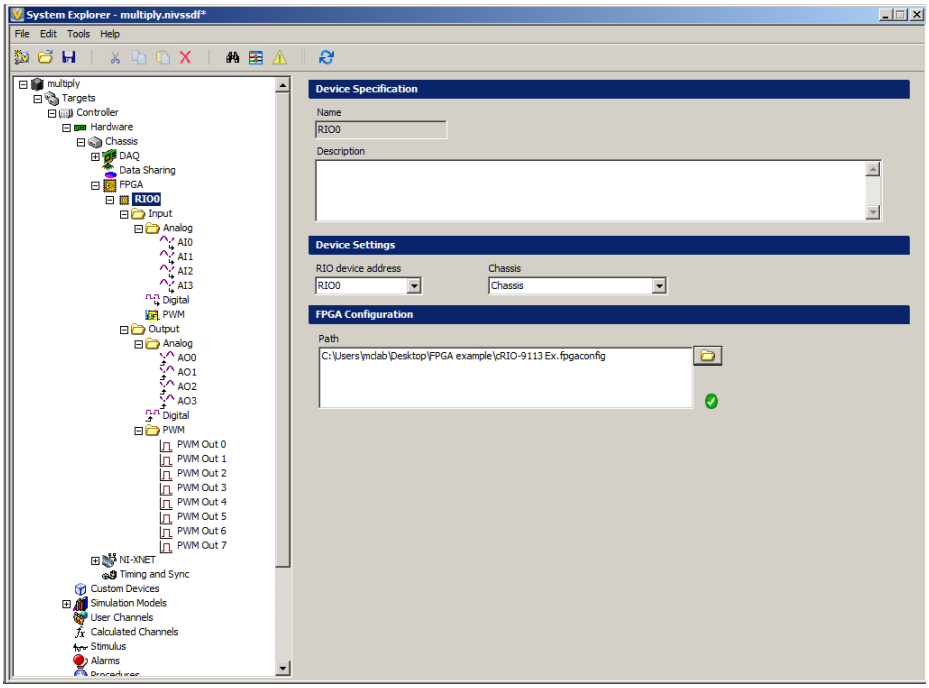

Figure 17: Ping result OPPDATER!!!

A successfull ping should return somthing like

```
C:\Documents and Settings\mcl>ping 102.168.0.77

Pinging 192.168.0.77: bytes=32 time = 5ms TTL=64
Pinging 192.168.0.77: bytes=32 time = 5ms TTL=64
Pinging 192.168.0.77: bytes=32 time = 5ms TTL=64
Pinging 192.168.0.77: bytes=32 time = 2ms TTL=64

Ping statistics for 192.168.0.77:
Packets: Sent = 4, Received = 4, Lost = 0 <0% loss>,
Approximate round trip times in milli-seconds:
Minimum =2ms, Maximum = 5ms, Average = 4ms
```

1. The most imprtant thing is that you receive packets in return, the time might vary but the important thing is that it responds to the ping.
2. If Lost = 100% meaning no repons means either "Laptop" or "CompactRIO" is unable to communicate with "HILlab".

Troubleshooting

1. Check Laptop is connected to wireless network "HILlab", if not connect to it "HILlab"
2. Check ACT/LiNK" port 1 are showing activity e.g. are lit, blinking, if

not check ethernet cable is connected to “ACT/LiNK” port 1 and to the “D-Link Wireless Bridge” if not connect to those Battery gives power to “CompactRIO” and “D-Link”, lights/indicators are lit/blinking if not check wiring

3. Check battery voltages, “Main battery” should be 10 Volt or more, maximum around 13 Volt, regular 11 to 12 Volt, low 10 Volt “Servo battery” should be in 5 Volt or more, max around 6.4 Volt, regular around 6 Volt

The PS3 controller has to be turned on when the PI is started up. And it takes about 1 minute from power up until the script is running. Nothing says that the script is supposed to start when playstation is activated

8.2 Ship docking procedure - after sailing

8.2.1 Template: DP control system

9 Troubleshooting

typiske feil

batteri

nettverk

Part IV

TMR4243 exercises and expected results

10 Pendulum lab

Adjust Simulink model for VeriStand.

Deploy

Create suitable workspace

Actuate fan manually.

Simulate to get same results as Simulink.

Export data

Try with handed out model (surprises).

11 Non-minimum phase lab

12 Estimation lab

13 The guidance lab

Part V

Equipment setup and configuration

A cRIO

A.1 Ethernet ports

A.1.1 Primary

Set fixed IP, set fixed IP on HIL-computers

A.1.2 Secondary ethernet port

Enabling the port

1. Start *NI MAX*
2. In the left pane tree, select the cRIO under *Remote Systems*
3. Open the *Network Settings* tab (located at the bottom of the window)
4. Set *Adapter Mode* to *TCP/IP Network*
5. Set *Configure IPv4 Address* to *Static*

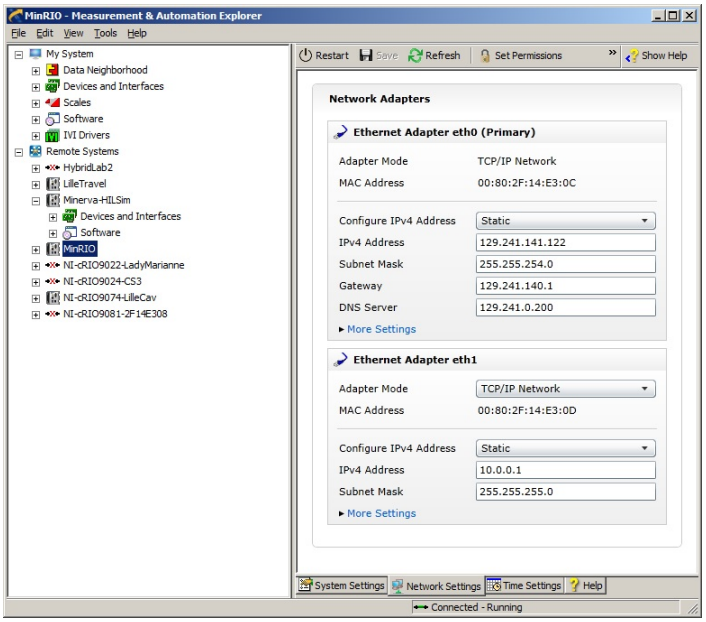

Figure 18: NI MAX - Network Settings

A.2 Install NI Veristand Engine

A.3 Installing custom device driver

In order to use a RPi to send joystick commands to the cRIO it is necessary to build a custom device driver. In our case Torgeir Wahl has built a driver, and this guide will show how to install the driver.

The first step is to copy the whole directory (folder named WL_Joystick) of the custom device driver into the correct directory on your computer:

C:\Users\Public\Documents\National Instruments\NI VeriStand 2014\Custom Devices

The directory should now contain something like Figure 19.

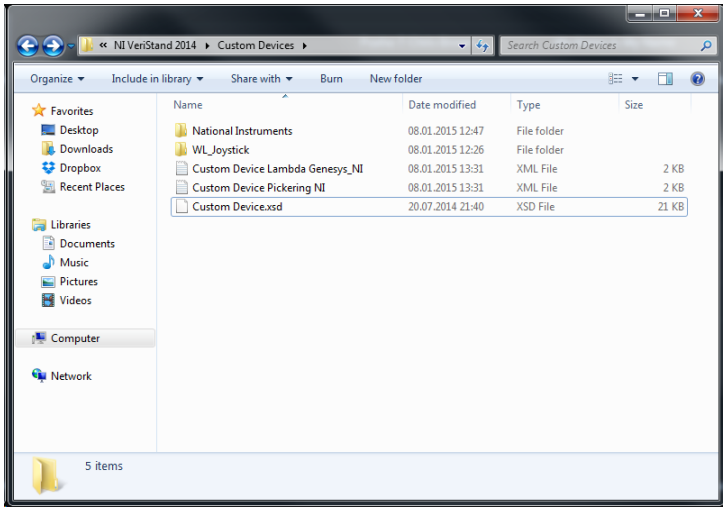

Figure 19: Custom device folder

The next step is to add custom device to your project. This is done in the system explorer, which is found as seen in Figure 20.

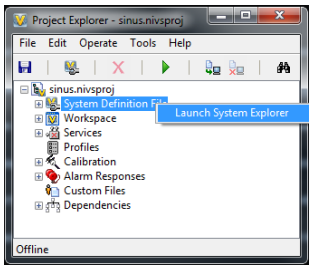

Figure 20: VeriStand launch system explorer

When in the system explorer, adding the custom device should be as simple as right clicking the custom device pane and choosing WL_Joystick, as in Figure 21. If you do not find the custom device WL_Joystick, the most likely problem is that the placement of the custom device folder from step 1 is wrong.

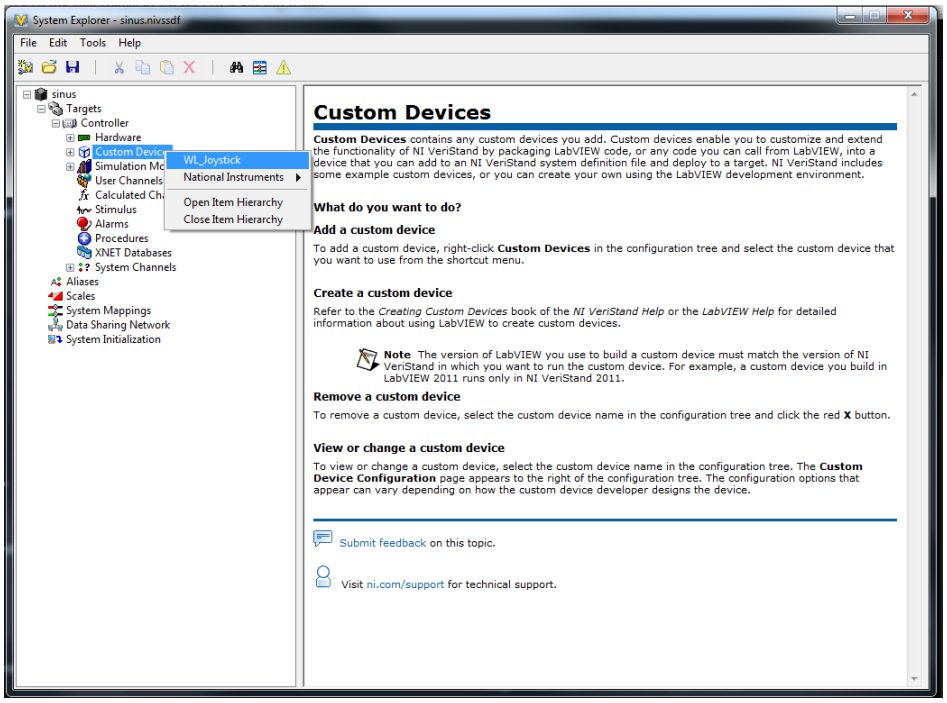

Figure 21: Custom device selection

If the installation is successful you should be able to see WL_Joystick folder under custom devices as seen in the red box in Figure 22. Here you will also see the different inputs from the custom device, in this case it is joystick axis.

To connect the joystick to the input ports of the Simulink model. You open the system configuration mappings (click the button marked by the arrow in Figure 22).

You the simply find the ports you would like to connect, mark them and click the connect button. Figure 23 a joystick output is connected to a input port on the Simulink model.

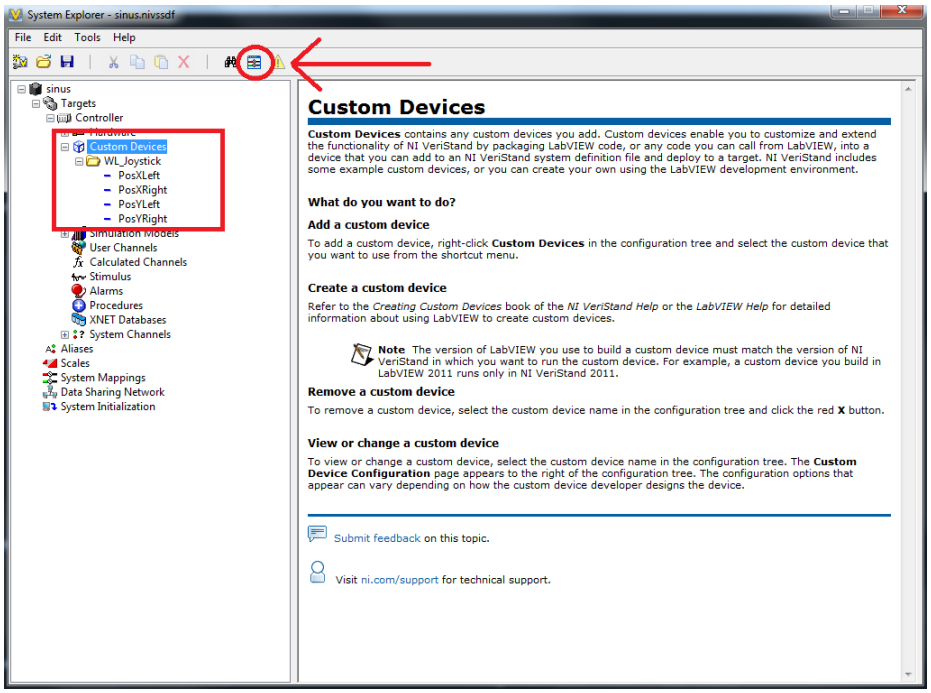

Figure 22: VeriStand

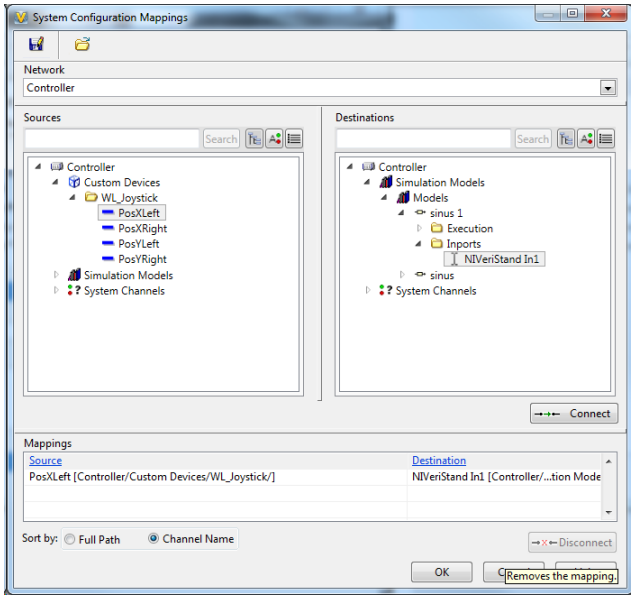

Figure 23: VeriStand System Configuration Mappings

A.4 Creating custom device driver

PWM, analog inn, analog ut

A.4.1 PWM output

VeriStand FPGA programming LabView -¿ Create project -¿ All -¿ NI VeriStand FPGA project -¿ Compact RIO -¿ Discover existing system -¿ Velge eget utstyr -¿ Vente på discovering -¿ I Project explorer *.vi (er bitfilen) *.fpgaconfig (egentlig XML) Endre på *.vi Fjerne overføldige pakker Oppdatere antall pakker i XML-filen og fjerne pakker som ikke er aktuelle, oppdatere tall på beholdte pakker. Kompiler

Kopier bit-file ut i samme mappe som *.fpgaconfig I System exlporer, FPGA -¿ Add FPGA target -¿ Finne *.fpgaconfig

A.4.2 Analog input

Eirik: FPGA-greier osv

A.5 Veristand FPGA programmering

Eirik: Skriv ordentlig om labview/XML delen av FPGA programmeringen

In order to access the analogue and digital I/O modules on our cRIO from Veristand, it is necessary to create a FPGA target in Labview with Labview and you will have to write a custom XML file.

A.5.1 Create Labview FPGA target and XML

The first step is

`https://decibel.ni.com/content/docs/DOC-13815`

A.5.2 Install in veristand

The Veristand software does not recognize the physical I/O components of the cRIO. It is necessarry to write a specific FPGA mapping for the specific setup. This results in a XML file that maps the ports.

To add this file to your Veristand project, enter the system explorer and find the FPGA pane under *targets\controller\hardware\chassis*, as seen in figure 24.

The next step is to find your XML file. In this case called cRIO-9113 Ex, it is very important that the XML file is placed on level above the FPGA bitfile folder in the directory system, as the files are really being used are the FPGA bitfiles.

The menu in should now look something like Figure 25, here you can see the analogue input signals and the digital output PWM signals. These can again be linked to other signals as seen in Figure23.

PWM

tick = FPGA clock pulse

$tickinseconds = 1/frequency = 1/40MHz = 1/(40 * 10^6) = 25 * 10^-9 = 25ns$

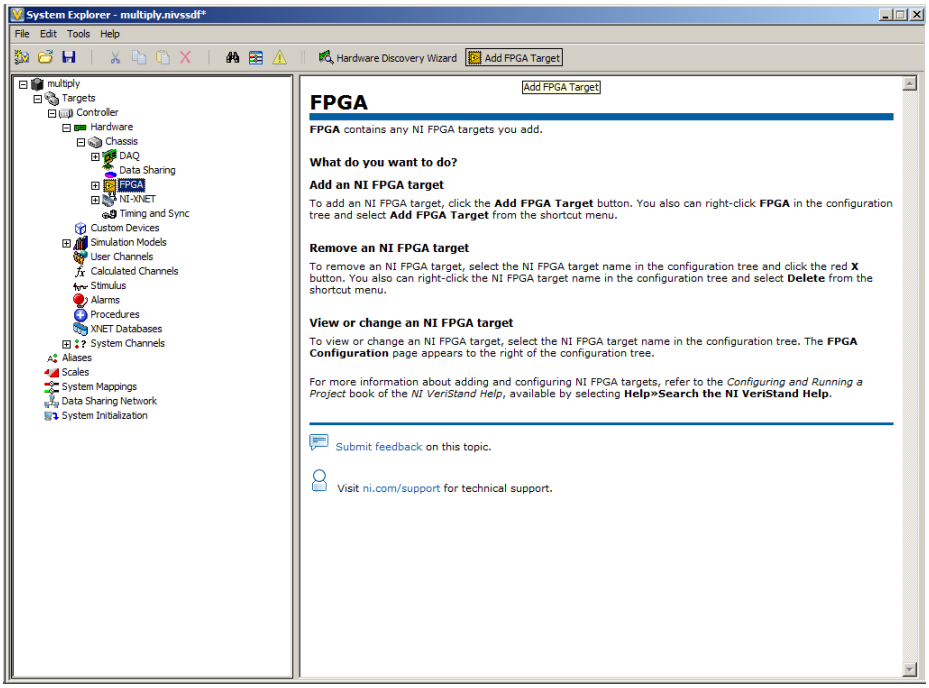

Figure 24: FPGA1

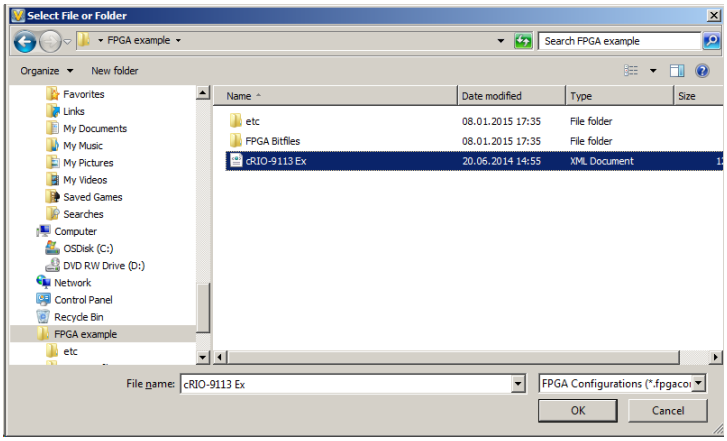

Figure 25: FPGA2

output at 50 Hz demands output every $40MHz/50Hz = (40 * 10^6)/50 = 800000tick$

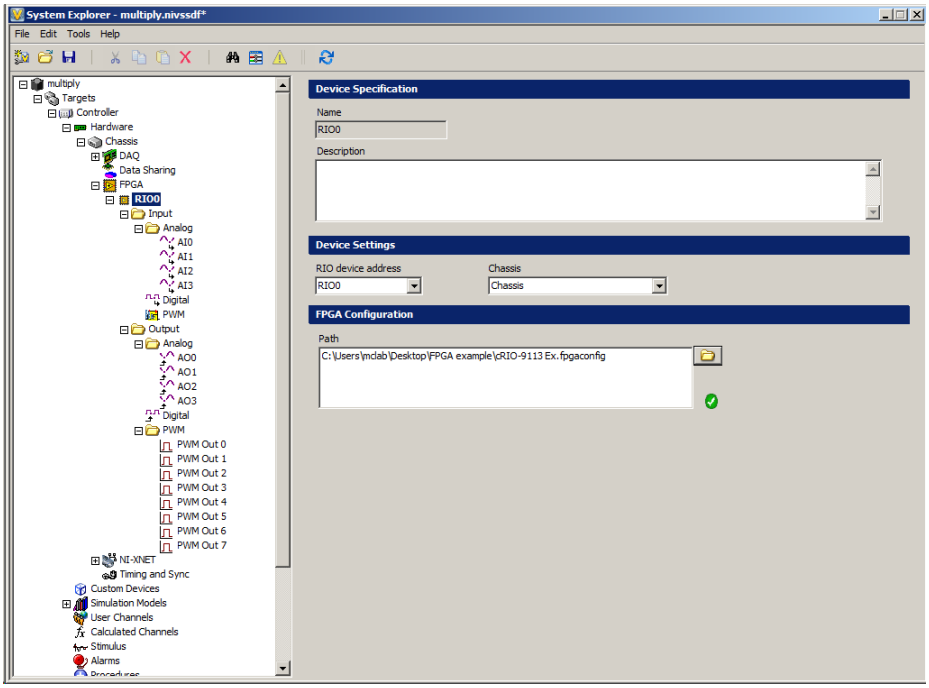

Figure 26: FPGA3

B Raspberry Pi

B.1 Raspbian installation and setup

This section describes how to install and access the Raspbian operating system on the RPi from a Windows computer. The operations are also possible from an OSX or Linux computer.

B.1.1 Download operating system and utilities

Download and extract the newest Raspbian[2] operating system (OS) image.

Necessary utilities for the setup are

- Win32 Disk Imager[3] to write the OS image to the RPi SD card
- Advanced IP scanner[4] to find the RPi address on the network
- Putty terminal emulator[5] for SSH connection
- WinSCP[6] for file transfer

[2] raspberrypi.org/downloads
[3] sourceforge.net/projects/win32diskimager
[4] by Famatech, advanced-ip-scanner.com
[5] www.chiark.greenend.org.uk/~sgtatham/putty/download.html
[6] by Martin Prikryl, winscp.net/eng/download.php

Windows	Linux, OSX
Win32 Disk Imager	dd
Advanced IP scanner	nmap
Putty	ssh
WinSCP	

Table 2: RPi installation and setup utilities

See Table B.1.1 for a list of the equivalent software for OSX and Linux.

B.1.2 Write image to SD card

Since the .iso file is raw, it needs to be written to the SD card in way that makes it bootable. Win32 Disk Imager does this.

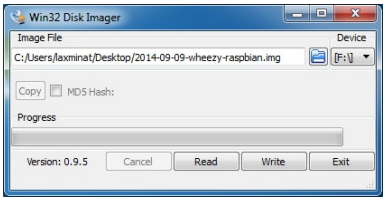

Figure 27: Disk Imager

Run the program as administrator. Select the correct image file and device, as in Figure 27. Make sure that you have slected the correct drive before you push WRITE.

Once the write is complete, insert the SD card in the RPi and boot.

B.1.3 Terminal access

RPi can be accessed through the network, i.e. without having to directly connect a monitor and keyboard.

At first boot, the RPi by default waits to be assigned an IP address by DHCP. If this address is not known, scan the network with Advanced IP Scanner. It is advicible to sort the results by manufacturer since it is fixed (*Raspberry Pi Foundation*). The name is typically *raspberrypi*. See Figure 28.

Once the IP is known, it is specified in the Putty settings, as in Figure 29, and a connection can be opened.

The default login is `pi`, and the default password `raspberry`. Figure 30 shows the terminal output on first login.

B.1.4 Finalize configuration

Enter the

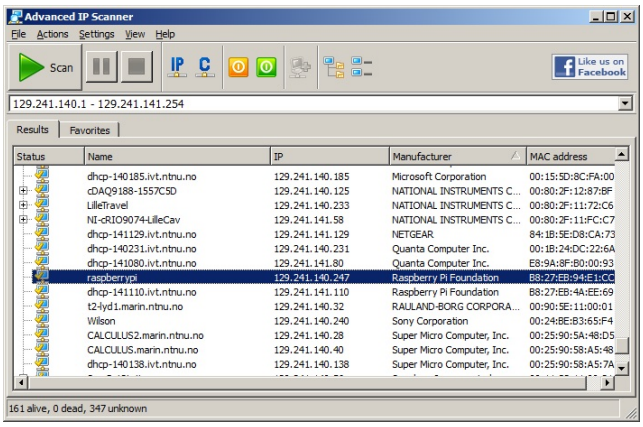

Figure 28: Advanced IP Scanner

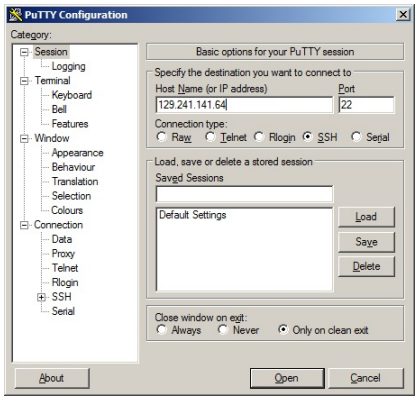

Figure 29: Putty settings

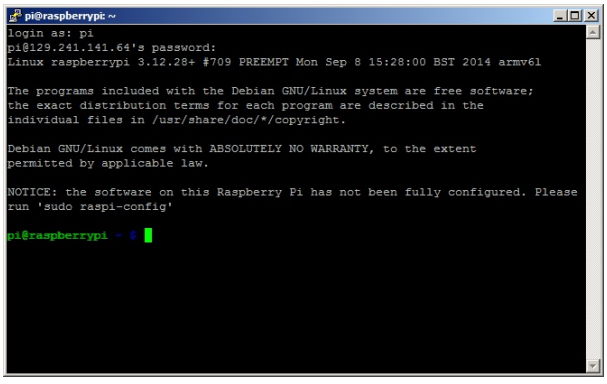

Figure 30: SSH connection

```
sudo raspi-config
```

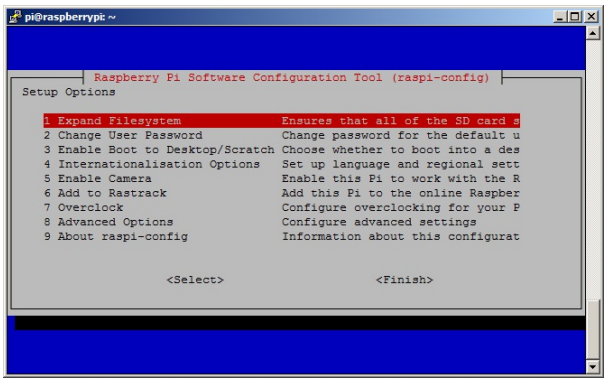

Figure 31: RPi configuration tool

command to start the RPi Software Configuration Tool, as in Figure 31. Use the menu to apply the following

1. Update configuration tool: 8 Advanced Options >A9 Update
2. Change password: 2 Change User Password
3. Expand filesystem: 1 Expand Filesystem >Finish

Reboot the system with the command

```
sudo reboot
```

Reconnect through Putty.

Finally, update the repository package lists and upgrade all packages currently installed on the RPi:

```
sudo apt-get update
sudo apt-get upgrade -y
```

This process took approximately 10 minutes on a 90 Mbps internet connection.

B.1.5 Transfer files to RPi from computer

WinSCP can be used to transfer files to the RPi. This is useful for instance when transferring code, or when the RPi is not directly connected to the internet.

B.1.6 Set fixed IP address

When the RPi is connected directly to the cRIO or computer, a fixed IP is necessary since there is no DHCP server in that network. During most of this setup, however, it is preferable to keep the default DHCP assigned IP setting.

To set a fixed IP

1. Open the network interface configuration information file for editing

   ```
   sudo nano /etc/network/interfaces
   ```

2. Alter the eth0 settings from `dhcp` to `static` and add address and netmask as

```
auto eth0
iface eth0 inet static
   address 192.168.1.22
   netmask 255.255.255.0
```

3. Save the changes by the key combination Ctrl+X.

The new IP is applied on the next reboot.

B.2 Sixaxis installation and configuration

This section describes how to install and configure the Sixaxis gamepad for Bluetooth connection to the RPi, and how to add a server for sending joystick signals to the cRIO.

B.2.1 Download and install bluetooth support

BlueZ is the official Linux Bluetooth stack. It provides support for core Bluetooth layers and protocols.

To download and install, type

```
sudo apt-get install bluez-utils bluez-compat bluez-hcidump
   libusb-dev libbluetooth-dev joystick checkinstall -y
```

The process takes a few minutes.

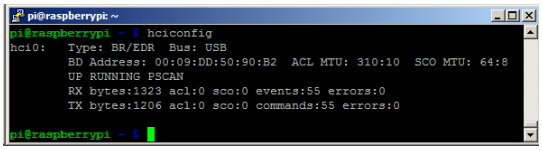

Figure 32: Bluetooth configuration tool

To confirm the installation, use the `hciconfig` command to print name and basic information about Bluetooth devices installed in the system. The output should include `UP RUNNING PSCAN`, as in Figure 32. If instead it says `DOWN`, some error har occured.

Most experienced errors were due to typos.

B.2.2 Bluetooth pairing

Sixaxis does not support the standard Bluetooth paring prcedure, instead, pairing is done over USB. The `sixpair` command-line utility[7] searches USB buses for Sixaxis devices and tells them to connect to a new Bluetooth master.

Download and compile the program by the following commands:

```
wget http://www.pabr.org/sixlinux/sixpair.c
gcc -o sixpair sixpair.c -lusb
```

Connect the Sixaxis by USB before running the paring utility

```
sudo ./sixpair
```

The output should be similar to

```
Current Bluetooth master: 00:02:72:BF:BC:8F
Setting master bd_addr to: 00:02:72:BF:BC:8F
```

[7] by Pabr Technologies, www.pabr.org

The addresses at the end of each line will only be the same if you have already paired the Sixaxis with the Bluetooth dongle. First time they will be different.

The Sixaxis USB cable may now be disconnected.

B.2.3 Joystick manager system service

`QtSixA`[8] reads the Sixaxis signals and makes them available to other programs. This program needs to run automatically whenever the RPi is booted.

To download the program, type

```
wget http://sourceforge.net/projects/qtsixa/files/QtSixA%201.5.1/QtSixA-1.5.1-src.tar.gz
```

To install, type

```
tar xfvz QtSixA-1.5.1-src.tar.gz
cd QtSixA-1.5.1/sixad
make
sudo mkdir -p /var/lib/sixad/profiles
sudo checkinstall -y
```

Update the system service list with sixad driver and reboot

```
sudo update-rc.d sixad defaults
sudo reboot
```

To test the program, turn on the Sixaxis (round PS button in the middle) and start the test program

```
sudo jstest /dev/input/js0
```

The terminal should now fill up with numbers that change as you move the analogue sticks and press the buttons on the Sixaxis.

B.2.4 Joystick signal server

A server must run to make joystick signals available over the RPi ethernet port. This should also starte whenever the RPi is booted.

Transfer the source file `jscont.c` to the RPi (see Section B.1.5), then compile:

```
g++ -o jscont jscont.c
```

To verify that the program runs correctly, turn off the previously paired Sixaxis and start the program

```
./jscont
```

The program should then wait until you turn on the Sixaxis before giving output simular to Figure 33. To exit the server use the key combination CTRL+C.

[8] the Sixaxis Joystick Manager by falkTX, qtsixa.sourceforge.net

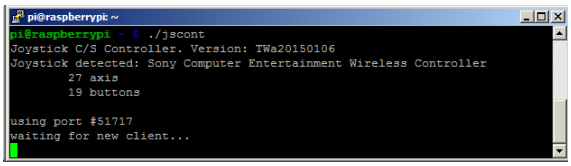

Figure 33: Joystick signal server test

Next, disable login at start-up in the bootup service description `inittab`:

1. Open the file for editing

   `sudo nano /etc/inittab`

2. Change the line that reads

   `1:2345:respawn:/sbin/getty --noclear 38400 tty1`

   by adding `--autologin pi` to get

   `1:2345:respawn:/sbin/getty --autologin pi --noclear 38400 tty1`

   Warning: Typos here may result consequences hard to correct.

3. Save the changes by the key combination Ctrl+W.

Finally, add `jscont` to the login execution file:

1. Open the file for editing

   `sudo nano /home/pi/.bashrc`

2. At the very end of the file, add

   `sudo ./jscont`

3. Save the changes by the key combination Ctrl+X.

RPi should now be sending joystick signals at start-up.

C Qualisys

calibration

Part VI

Miscellaneous

D HIL lab and MC lab device network addresses

RPi	192.168.1.22	for all
cRIO secondary ethernet	192.168.1.21	for all
cRIO primary ethernet	192.168.0.71	iimt-HILlab1-cRIO
	192.168.0.72	iimt-HILlab2-cRIO
	192.168.0.73	iimt-HILlab3-cRIO
	192.168.0.77	CSE1
Computer	192.168.0.41	iimt-HILlab1-PC
	192.168.0.42	iimt-HILlab2-PC
	192.168.0.43	iimt-HILlab3-PC
	192.168.0.	MClab
Subnet mask	255.255.255.0	for all

Table 3: IP addresses

All RPis and have the same IP address, but there is no IP conflict since the cRIO-RPi networks are separate and closed. The same goes for the cRIO secondary ethernet ports

Note: to connect the RPi directly to the computer, both need to be on the same domain and the computer IP thus needs to change to 192.168.**1**.xx.

E Personel and literature

E.1 Points of contact

Håkon Nødset Skåtun Hakon.Nodset.Skatun@km.kongsberg.com, built CSE1

Øivind Kåre Kjerstad Build CSE1

Torgeir Wahl Custom devices (Qualisys client, Sixaxis client), Sixaxis RPi server

Dinh Nam Tran oppryddingsarbeid

Andreas Orsten brukt mye, skrevet artikel om sleping av isberg

Robert Kanajus rkajanus@gmail.com brukt HIL-lab og Minerva

Eirik Valle Teaching assistant TMR4243, Sixaxis for RPi setup

Andreas Reason Dahl andreas.r.dahl@ntnu.no, Laboratory assistant TMR4243

Jostein Follestad Teaching assistant TMR4243, CS1E HIL model

Fredrik Sandved Teaching assistant TMR4243, Custom displays

E.2 Publications

2014

Andreas Orsten, Petter Norgren, Roger Skjetne, LOS guidance for towing an iceberg along a straight-line path. Proceedings of the 22nd IAHR International Symposium on ICE 2014 (IAHR-ICE 2014).

E.3 Specialization projects and master theses

2011

Håkon Nødset Skåtun Development of a DP system for CS Enterprise I with Voith Schneider thrusters. Master thesis.

2013

Nam Dinh Tran Development of a modularized control architecture for CS Enterprise I for path-following based on LOS and maneuvering theory. Specialization project.

2014

Andrea Orsten Automatic Reliability-based Control of Iceberg Towing in Open Waters. Master thesis and poster.

Nam Dinh Tran Line-Of-Sight-based maneuvering control design, implementation, and experimental testing for the model ship C/S Enterprise I. Master thesis.

F Suppliers

Laptops	Dell
cRIO	National Instruments
VSP	Thrusters were ordere at `www.cornwallmodelboats.co.uk/acatalog/voith_schottel.html`. Per 2014, availability is variable.

Table 4: Suppliers

G YouTube demonstration

`http://www.youtube.com/watch?v=MiESJsIZO04`

H To do list

- Etablere fargekoder for simulinkblokker (spesielt "ikke røre"-farge)
- Konsekvent notasjon: C/S Enterprise 1 eventuelt CSE1
- Forklaring av hva realtime betyr i HW og SW
- Troubleshooting-prosedyrer for de vanligste feilene
- Implementere "fail to zero" for når kommunikasjonen avbrytes.
- legge til IMU/gyro på båten

I Software needed

- Matlab
- Labview
- LabVIEW development system
- LabVIEW Real-Time Module
- LabVIEW FPGA Module (recommended)
- NI-RIO driver
- VeriStand