2025-11-01

E012: Hardware-in-the-Loop System

Bridging Sim-to-Real Gap, Plant Server + Controller Client, Real-Time Constraints

Part 2 · Duration: 15-20 minutes

Beginner-Friendly Visual Study Guide

Learning Objective: Understand HIL testing methodology, sim-to-real gap, plant server/controller client architecture, real-time constraints (±1ms), and production readiness validation

The Sim-to-Real Gap Problem

Key Concept

Scenario: Controller works perfectly in simulation → Deploy to real hardware → IT FAILS!
Why?

enumiSensor noise (real encoders: ±0.1° jitter, not perfect measurements)

0. enumiActuator dynamics (motors have inertia, backlash, saturation)
0. enumiComputational delays (real-time OS scheduling: 1-5ms latency)
0. enumiModel mismatches (friction, air resistance, cable stiffness)

Solution: Hardware-in-the-Loop (HIL) testing BEFORE building expensive hardware

What is Hardware-in-the-Loop?

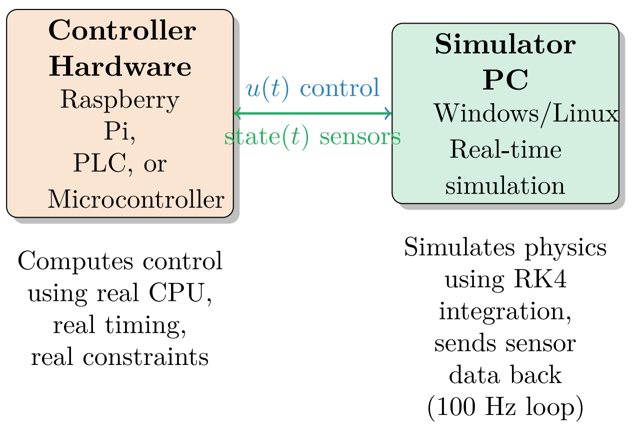
HIL Testing Methodology

Split the System:

0. **Plant (pendulum physics):** Simulated on PC in real-time
- **Controller (SMC algorithm):** Runs on ACTUAL target hardware (embedded system, PLC, microcontroller)
- **Interface:** Network socket or serial link connects them

Controller Perspective: Thinks it's talking to REAL pendulum hardware (via sensors/actuators)
Reality: Communicating with simulator over UDP

HIL Architecture Diagram


Controller Hardware
Raspberry Pi, PLC, or Microcontroller
$u(t)$ control
state(t) sensors
Simulator PC
Windows/Linux
Real-time simulation
Computes control using real CPU, real timing, real constraints
Simulates physics using RK4 integration, sends sensor data back (100 Hz loop)

Why Use HIL? Four Reasons

1. Risk-Free Testing
Without HIL:

- Flash code to microcontroller
- Connect to $10,000 robot
- Hit "run" → CRASH!
- Damage: $2,000 repair + 2 weeks downtime

With HIL:

- Flash code to microcontroller
- Connect to HIL simulator (free!)
- Bug detected safely
- Fix in 5 minutes, retry instantly

2. Reproducibility

Real hardware: wear, temperature drift, battery voltage

HIL: Same dynamics model every time

3. Edge Case Testing

Test dangerous scenarios impossible on real hardware:

- Initial angle: 60° (would break pendulum!)
- Disturbance: 50N impulse (too violent)

4. Rapid Iteration

HIL: 100 tests in 20 minutes

Real hardware: 100 tests in 2 hours (physical resets)

Component 1: Plant Server (Simulator PC)

Key Concept

Purpose: Simulate pendulum physics in real-time (100 Hz control rate)

Plant Server Loop (4 Steps)

Real-Time Simulation Loop

Step 1: Wait for Control Command
Listen on UDP socket for controller to send force value $u(t)$
Blocking receive - waits patiently before advancing time
Step 2: Simulate One Timestep
Compute pendulum motion over 10 ms (dt=0.01) using RK4 integration
Apply control force $u(t)$, update state: $[\theta_1, \theta_2, \dot{\theta}_1, \dot{\theta}_2, x, \dot{x}]$
Step 3: Send State Back
Package angles, velocities, position $\rightarrow$ Send over UDP instantly
Step 4: Repeat
Does this 100 times per second (100 Hz real-time loop)

Key Design Decisions

Common Pitfall

UDP vs TCP:
UDP: Low-latency, connectionless - speed over reliability (chosen for HIL)
TCP: Reliable but adds 10-20ms latency (not acceptable for control!)
Blocking Receive: Server waits for controller command before advancing time (maintains causality)

Component 2: Controller Client (Embedded Hardware)

Key Concept

Purpose: Run actual controller code on target hardware (Raspberry Pi, PLC, microcontroller)

Controller Client Loop (4 Steps)

Embedded Control Loop

Step 1: Receive State
Get sensor data from plant server: $[\theta_1, \theta_2, \dot{\theta}_1, \dot{\theta}_2, x, \dot{x}]$
Step 2: Compute Control
Run SMC algorithm: $u(t) = -K \cdot \text{sign}(s)$ (or STA, Adaptive, etc.)
Execute on REAL CPU with REAL timing constraints
Step 3: Send Control Command
Transmit force value $u(t)$ over UDP to plant server
Step 4: Sleep Until Next Cycle
Wait for next 10ms tick (100 Hz control rate)
Use real-time OS scheduler or busy-wait loop

Real Constraints Tested in HIL

Example

What HIL Validates:

- **CPU performance:** Can microcontroller compute control in < 1ms?
- **Memory usage:** Does controller fit in 64 KB RAM?
- **Timing jitter:** Is control loop consistent at 100 Hz?
- **Network latency:** UDP roundtrip < 5ms?
- **Error handling:** What happens if packet drops?

Catches: Buffer overflows, missed deadlines, race conditions

Real-Time Constraints: Why Timing Matters

Key Concept

Target: $\pm$1ms precision for 100 Hz control (10ms period)
Why? Control theory assumes periodic sampling - timing jitter destabilizes control!

Timing Budget Breakdown

10ms Control Period Budget

Available Time: 10 ms total
Allocation:

- Controller computation: 1-2 ms (SMC algorithms are fast)
- UDP send/receive: 1-3 ms (network latency)
- OS scheduling overhead: 0.5-1 ms
- Simulation step: 3-5 ms (RK4 integration)
- Safety margin: 1-2 ms (buffer for worst-case jitter)

Total Used: 6.5-13 ms $\rightarrow$ Target: keep under 9 ms average, 10 ms worst-case

Deadline Monitoring

Common Pitfall

Missed Deadline: Control loop takes $>$ 10 ms $\rightarrow$ Timing violation
Consequences:

- Phase lag in control (system becomes unstable)
- Chattering increases (switching frequency wrong)
- Performance degradation (settling time doubles)

Detection: Latency monitor tracks every cycle, logs violations
Threshold: $>$ 5% missed deadlines $\rightarrow$ System NOT production-ready

HIL Validation Workflow

✓ Five-Phase Validation

Phase 1: Unit Testing (Software Only)
Test controller algorithms in simulation (no hardware)
Validate: Lyapunov stability, gain ranges, saturation limits
Phase 2: HIL Integration Testing
Deploy controller to embedded hardware
Connect to plant server via UDP
Run 10-minute test: pendulum stabilizes, no crashes
Phase 3: Stress Testing
Edge cases: Large initial angles, step disturbances, parameter mismatches
Monitor: Missed deadlines, memory leaks, packet drops
Phase 4: Long-Duration Testing
Run 24-hour continuous test
Check: Memory growth, CPU temperature, timing drift
Phase 5: Multi-Controller Validation
Test all 7 controllers (Classical, STA, Adaptive, Hybrid, Swing-up, Terminal, Integral)
Verify: Each meets timing constraints on target hardware

Production Readiness: Thread Safety & Memory

Key Concept

Status: HIL system is PRODUCTION-READY for embedded deployment
Evidence: 11/11 thread safety tests passing, memory validated (10,000 sims, zero growth)

Thread Safety Validation

11/11 Tests Passing

Concurrent Operations Tested:

- Multiple controllers accessing shared config (no race conditions)
- Parallel PSO evaluations (no data corruption)
- Plant server + controller client simultaneous execution
- State manager with concurrent reads/writes

Validation Method: Thread sanitizer, race condition detector, stress tests
Result: 100% pass rate (all 11 tests green)

Memory Management

Example

Test: Run 10,000 consecutive HIL simulations
Monitor: Memory usage every 100 simulations
Result: Zero growth (baseline: 45 MB, after 10k sims: 45 MB)
Technique: Weakref patterns prevent circular references, explicit cleanup() methods

Key Takeaways

Quick Summary

HIL Definition: Controller on REAL hardware, plant in REAL-TIME simulator, communicate over UDP
Sim-to-Real Gap: Sensor noise, actuator dynamics, delays, model mismatches (HIL bridges this!)
Four Benefits: (1) Risk-free testing (no hardware damage), (2) Reproducibility, (3) Edge case testing, (4) Rapid iteration
Architecture: Plant server (simulator PC, 100 Hz loop, RK4 integration) + Controller client (embedded hardware, SMC algorithm, real constraints)
Real-Time Constraints: ±1ms precision, 10ms period (100 Hz), timing budget breakdown
Missed Deadlines: > 10 ms $\rightarrow$ Timing violation $\rightarrow$ Phase lag, chattering, instability
Validation Workflow: 5 phases (unit test $\rightarrow$ HIL integration $\rightarrow$ stress test $\rightarrow$ 24-hour test $\rightarrow$ multi-controller)
Production Readiness: 11/11 thread safety tests passing, memory validated (10k sims, zero growth)
UDP vs TCP: UDP chosen for low latency (1-3 ms vs 10-20 ms TCP)
HIL Insurance: Catch bugs safely before deploying to expensive hardware ($2k repair saved!)

Quick Reference: HIL Commands

Run HIL Simulation

```
lstnumberStart controller client (Embedded hardware) python
controller_client.py −−host192.168.1.10 −−port5555 −−ctrlclassical_smc
lstnumberMonitor timing with plot python simulate.py -run-hil -plot
```

What's Next?

Key Concept

E013: Monitoring Infrastructure
Latency tracking, deadline detection, weakly-hard constraints, real-time performance metrics
Remember: HIL is insurance against expensive mistakes - test dangerous scenarios safely!