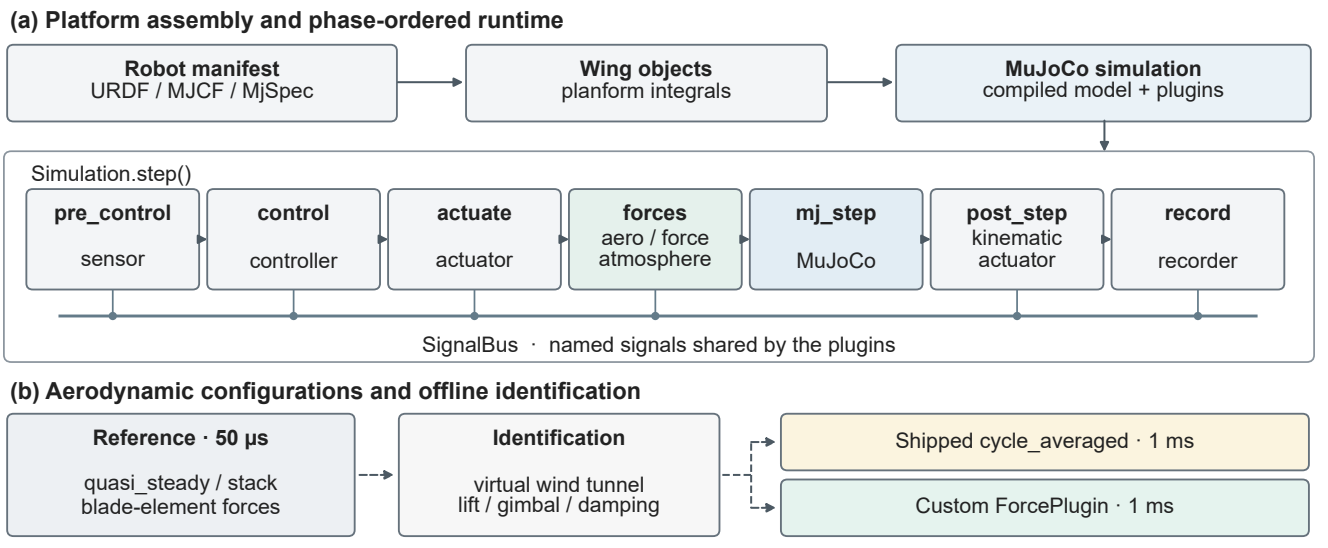

(a) Platform assembly and phase-ordered runtime
Robot manifest
URDF / MJCF / MjSpec
Wing objects
planform integrals
MuJoCo simulation
compiled model + plugins
Simulation.step()
pre_control
sensor
control
controller
actuate
actuator
forces
aero / force
atmosphere
mj_step
MuJoCo
post_step
kinematic
actuator
record
recorder
SignalBus · named signals shared by the plugins
(b) Aerodynamic configurations and offline identification
Reference · 50 µs
quasi_steady / stack
blade-element forces
Identification
virtual wind tunnel
lift / gimbal / damping
Shipped cycle_averaged · 1 ms
Custom ForcePlugin · 1 ms