

SYNAPSE Neural Robotic Controller: An Evidence-Aware Architecture, Prototype Evaluation, and Integration Roadmap

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Abstract—This paper presents SYNAPSE Neural Robotic Controller, a project in a twenty-project AI infrastructure portfolio. The current repository is an active prototype with implemented behavior, automated correctness tests, and explicit boundaries around unverified hardware or production claims. We describe the system model, current implementation, goals, and evaluation method, then propose five integrations that advance the project toward reproducible system-level validation. A local audit executed 4 project tests successfully. No accelerator, deployment, or performance conclusion is inferred unless a corresponding committed benchmark or profiler artifact exists.

Index Terms—SYNAPSE, AI infrastructure, reproducibility, prototype validation, systems evaluation, hardware–software co-design

I. INTRODUCTION

SYNAPSE Neural Robotic Controller (P14) addresses a bounded problem within the portfolio’s track-04-robotics-edge track. Its declared status is *Active Prototype* [1]. The project validates its central mechanism before adding device-specific acceleration, production orchestration, or real-world hardware. This ordering matters because optimization without a trusted reference can make incorrect behavior appear successful.

The project goals are to establish deterministic behavior, encode correctness as tests, create machine-readable evidence, identify limiting resources through measurement, and integrate results with adjacent portfolio systems without losing provenance. The repository contains one paper named exactly after its singular folder: `P14-synapse-neural-robotic-controller.tex`.

II. TECHNICAL CONTEXT

Edge and robotic systems operate under resource, latency, privacy, and safety constraints. Development should progress from deterministic simulation to representative sensors, middleware, and hardware-in-the-loop validation. The portfolio benchmark standard requires environment, workload, method, metric, artifact, reproduction, and limitation fields; unknown values remain explicitly unmeasured [3].

III. SYSTEM MODEL AND ARCHITECTURE

The prototype is organized around the following domain model:

$$\bar{x}_t = \frac{1}{W} \sum_{i=0}^{W-1} x_{t-i}, \quad u_t = \text{clip}(k\bar{x}_t, -u_{max}, u_{max}) \quad (1)$$

The equation is a design and test abstraction rather than a claimed empirical law. It supports invariants and expected-value checks while later implementations replace synthetic inputs with representative workloads or devices.

The software architecture contains an input/configuration layer, a deterministic core, validation and evidence output, and a local visualization. The principal inspected source artifacts are `python/controller.py`. Unsupported real-world conditions are surfaced as limitations rather than silently simulated.

IV. DETAILED SCRIPT OPERATION AND RATIONALE

The controller generates a repeatable noisy signal, smooths it with a moving average, applies deadband and output bounds, and forces zero speed when stop is requested. Its purpose is to establish safe command semantics before biosignals, classification, middleware, or actuators are introduced.

The execution path is:

- 1) Generate deterministic noisy samples.
- 2) Smooth samples over a moving window.
- 3) Apply a deadband to suppress small unintended commands.
- 4) Scale and clip the command to the configured safety bound.
- 5) Override all motion with zero output when stop is active.

V. IMPLEMENTED PROTOTYPE

The metadata and source audit found these completed features [2]:

- Deterministic synthetic signal
- Moving-average filter
- Bounded simulated command and stop state
- Unit tests

`python3 -m unittest discover -s tests -p 'test_*.py'` completed successfully with 4 tests. The inspected test artifacts are `tests/test_controller.py`. This is evidence of local correctness for encoded cases, not production scale or hardware performance.

VI. TESTING METHODOLOGY AND OBSERVED RESULTS

Testing uses Python’s standard `unittest` discovery and exercises the public behavior of the reference implementation. The audit reran the suite from the project folder with `python3 -m unittest discover -s tests -p 'test_*.py'`. All 4 discovered tests

TABLE I
IMPLEMENTATION ARTIFACTS AND WHY THEY EXIST

Artifact	Observed responsibility	Engineering rationale
python/controller.py	moving_average, command, signal, main	Implements the inspectable, unit-tested project core.
scripts/reproduce.sh	Fixed test and demonstration entry point	Gives another developer one command for local reproduction.
PROJECT.yaml	and	Separates declared intent from evidence-backed implementation.
ANALYSIS.md		Makes outputs inspectable without upgrading simulation into a hardware claim.
streamlit_app.py		

passed. The result establishes correctness only for the encoded local cases; it does not establish accelerator correctness, real-device behavior, production reliability, or benchmark completion.

No numerical performance result is promoted by this test run. Where scripts emit JSON or JSONL, those outputs remain raw or simulation-specific until a reviewed summary includes hardware, software, workload, warm-up, repetition, correctness threshold, Git revision, and limitations.

VII. CLAIM BOUNDARIES AND RISKS

The project records these unverified or excluded claims:

- No biosignal or physical actuator is used

The main risk is confusing synthetic or modeled behavior with deployed-system behavior. Other risks include incomplete workloads, platform-dependent timing, missing failure injection, and interfaces not yet exercised across device boundaries. Performance claims require a reviewed record meeting the portfolio standard.

VIII. EVALUATION PLAN

Evaluation proceeds through correctness tests, deterministic reproduction with Git and environment metadata, repeated benchmarks reporting latency/throughput/memory/error metrics, and a named profiler capture tied to exact hardware and source revision. Success requires reference equivalence within a documented tolerance, preservation of safety and resource invariants, clear failures, and evidence reproducible from a clean environment.

IX. GOALS, MILESTONES, AND SUCCESS CRITERIA

The project goals are staged so that correctness precedes performance and integration. A goal is complete only when its proof artifact is committed or otherwise reviewable; prose or a simulated number alone is insufficient.

X. FUTURE WORK AND INTEGRATIONS

The five project-specific next steps are:

- 1) Feature windows
- 2) Classifier
- 3) Robot simulator adapter
- 4) Add calibration, confidence thresholds, watchdogs, and emergency stop enforcement.

- 5) Integrate output with P15 in simulation before hardware trials.

The early items complete declared evidence; the later items connect downstream portfolio consumers. Each integration should add tests and a reviewable artifact such as JSONL evidence, a report, profiler capture, deployment manifest, trace, or labeled data set.

XI. CONCLUSION

SYNAPSE Neural Robotic Controller is an evidence-aware active prototype: its implemented behavior and tests are real, while unbuilt hardware, deployment, and performance goals remain labeled. Completing the five integrations in dependency order will advance it from a learning artifact toward a credible portfolio component.

REFERENCES

- [1] Aaron Singh, "SYNAPSE Neural Robotic Controller PROJECT.yaml," local portfolio repository.
- [2] Aaron Singh, "SYNAPSE Neural Robotic Controller: README, ANALYSIS, source, and test artifacts," local portfolio repository.
- [3] Aaron Singh, "AI Infrastructure Portfolio Benchmark Standard," local portfolio repository.

TABLE II
AUDITED TEST MATRIX

Test artifact and case	Behavior being checked	Observed result
tests/test_controller.py:test_stop	Stop.	Pass (local)
tests/test_controller.py:test_bound	Bound.	Pass (local)
tests/test_controller.py:test_deadband	Deadband.	Pass (local)
tests/test_controller.py:test_repeatable	Repeatable.	Pass (local)

TABLE III
DECLARED STATUS VERSUS AUDITED EVIDENCE

Audit field	Finding	Evidence source
Declared status	Active Prototype	PROJECT.yaml
Evidence-backed status	Active local prototype; 4 tests passed	Source plus local unittest run
Accepted measured results	None recorded in measured_results	PROJECT.yaml
Mismatch / claim boundary	No biosignal or physical actuator is used	PROJECT.yaml and ANALYSIS.md
Next proof required	Feature windows; Classifier	Planned features

TABLE IV
PROJECT GOALS AND REQUIRED PROOF

ID	Goal	Completion evidence
G1	Feature windows	Passing tests and a reviewed source artifact
G2	Classifier	Machine-readable result with reproduction metadata
G3	Robot simulator adapter	Reference-equivalence or domain-correctness report
G4	Add window features and a classifier	Named profiler, deployment, or integration artifact
G5	Validate safe commands in a robot simulator	Dashboard/report link preserving provenance and limitations