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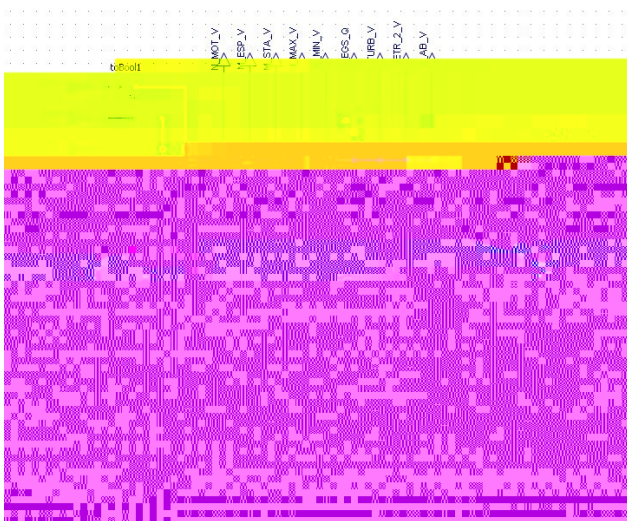
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We present and discuss the model-based development environment currently used by Daimler to develop and train control software for passenger cars. Besides well-established models, the environment supports automotive standards such as A29, CAN, and CANopen to integrate control software and simulated models on a single platform.

More and more automotive functions are implemented using software (and, there is an increasing demand to support the corresponding development process using virtual, i.e. simulation-based development environments).



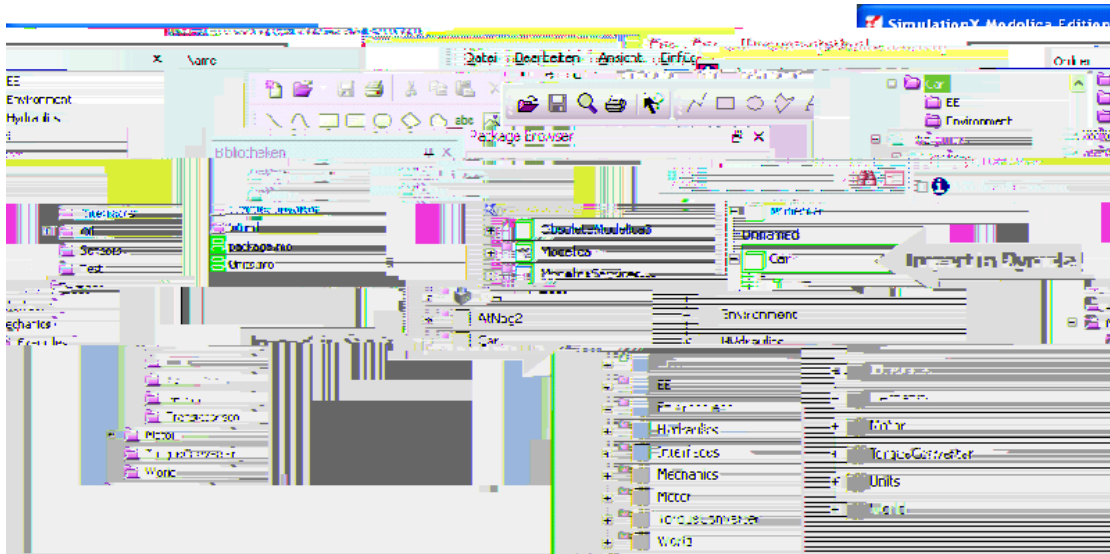
Virtualizing control strategies with plant models is standard technology today, mostly using commercial tools such as Simulink for the

development of control algorithms. This paper presents technology targeted toward the late stages in the development process, like tuning, validating and debugging the entire controller software in closed loop with simulated plant models. Virtualizing these later engineering tasks requires plant models with increasing higher quality. High-quality effects modeled and quality of calibration and near-production controller software. A percentage of the controller software is included, parameterization using production parameter sets and adaptation of the software to the plant to be used.

A toolchain supporting such virtualizing should

- be easy to use and use the automotive development tools that are usually not computer scientists
- support many of the engineering tasks usually performed with high-quality prototypes to allow for front-loading
- support short turnaround times, i.e. minimize the time between editing of control software and validation of the resulting behavior on system level to help find problems early
- provide a suitable support for standards and definitions to standards used in automotive software development to allow cost-effective use of existing information sources
- support distributed development and

tools or tool chain considerations



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ous standards and quasi-standards used for automotive software development. Developers are familiar with these standards and know how to use them. Data is available in these formats already as part of the existing tool chain and reuse is virtually free of cost. Furthermore, using these data sources in the virtual development process allows early validation of these data sources. A virtual development environment should therefore mimic, emulate, or else host support these standards. A feature examples of how the #i9 tool supports automotive standards is shown in Figure 10.

Developers typically use tools such as CANalyzer or CANape to measure signals and calibrate CAN parameters of the control software in the running car or on a test rig using standard protocols such as CAN or LIN. The #i9 environment implements this protocol when connected to a measurement tool such as CANalyzer, a #i9 simulation behaves just like a real car. Developers can therefore attach his favorite measurement tool to the #i9 to measure and calibrate using the same measurement masks, data sources and procedures they are using in a real car. Likewise, automotive developers use CAN files to store measurements. The #i9 can load and save this file format. A measured CAN file can be used to drive a #i9 simulation.

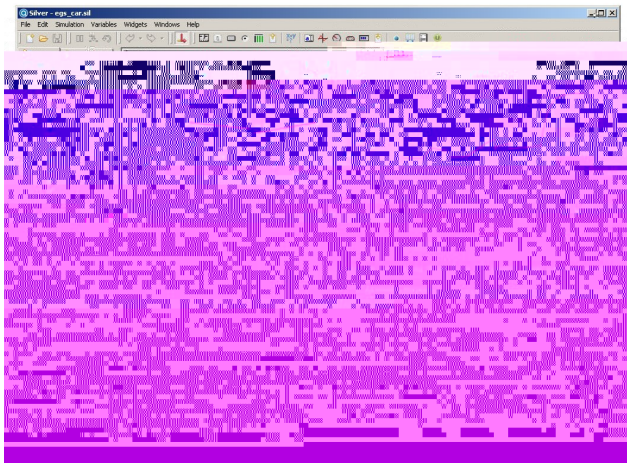
Another example is CANopen. This is a data base format used to store key information about variables and CAN parameters of automotive control software. CANopen contains the address of variables in the

ECE, its physical unit, comment and scaling information that tells how to convert the raw integer value to a physical value. The #i9 environment reads CAN files and uses the information to automate many tasks, such as scaling of the integer variables of the control software to match the physical variables of the vehicle model.

(Meeting all these standards available in the #i9 eases the task of actually getting automotivé &ontrol software running on a =C, and doing useful things with the resulting setup. Control software is typically decomposed into a number of so-called tasks. Each function implemented in C that are run within an Real-time operating system such as RTE. Many tasks are periodically executed with a fixed rate, e.g. every 10 ms. To get such tasks running in #i9, the user has to build an adapter as shown in :fig0, in a little C program that implements the #il6er module A= and emulates the RTE. Calling each task once at every 1st, 2nd, 3rd, ... #i9 macro step. The #i9 tool is shipped with the #, # #il6er, as is #oft8areB, in a C sources that make it easy to build such an adapter. An alternative adapter code. A &head alternative to writing an adapter is to use the #i9 tools support for * A%) 9A, ?#imulink and Realtime .orksho5 AR% . B0 Automotivé software is often developed first &reating a model of the &ontroller using #imulink. The

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- 0 F . 8ith the introdu&tion of the #il6er , asi& #oft)ware 5a&kage, this effort is signi)fi&ant)7 redu&ed)

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- 1 F due to &omforta'le integration of soft)ware and 6ehi&le &om5on)ents on the =C of the de)6elo5er) %his hel5s to dete&t 5ro'lems earl7)
- 1 & , e) g) 8ith *i&rosoft >isual #tudio De'ugger or \$%roni& %est . ea6er G1,2,3,"H0 :ound 5ro') lems &an 'e eCa&t)7 re5rodu&ed as often as needed)
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