

Emmanuel Chrisofakis¹, Andreas Junghanns², Christian Kehrer³, Anton Rink¹

¹Daimler AG, 70 372 Stuttgart

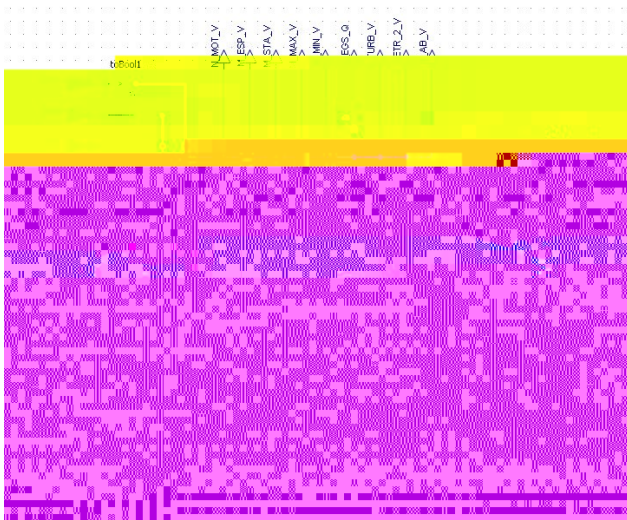
²Siemens AG, 91052 Erlangen

³Siemens AG, 01067 Dresden

emmanuel.chrisofakis@daimler.com, anton.rink@daimler.com, andreas.junghanns@siemens.com, kehrer.christian@siemens.com

We present and discuss the Modelica-based development environment currently used by Daimler to develop and train control software for passenger cars. Besides well-established vehicle models, the environment supports automotive standards such as AUTOSAR, CAN, and CANopen to integrate control software and simulated vehicles 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, in-vehicle simulation-based development environments).



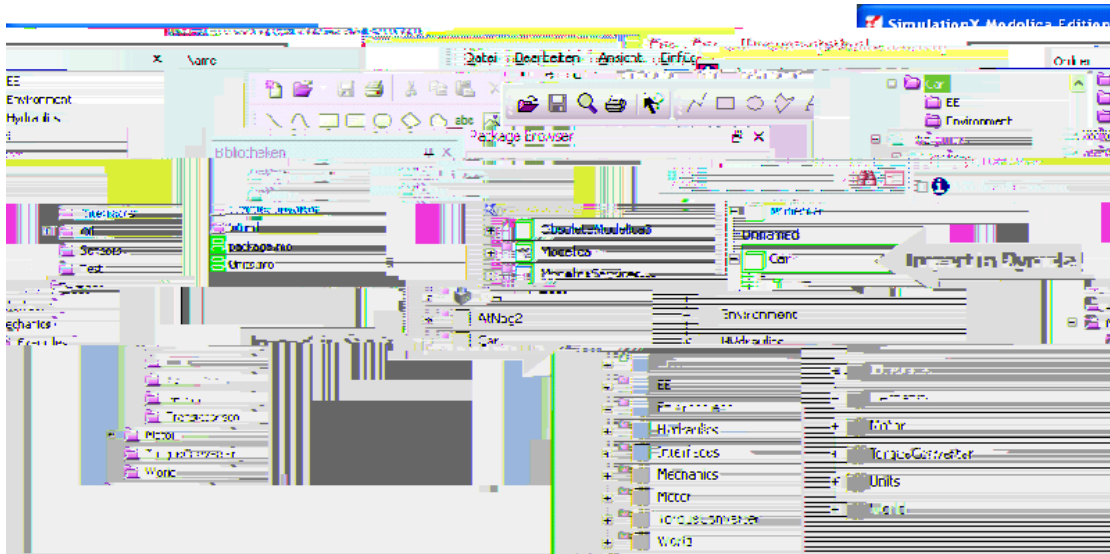
Virtualizing control strategies with plant models is standard technology today, mostly using commercial tools such as Simulink for real-time

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 scaling should

- be easy to set up and use by automotive developers who 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 defacto standards used in automotive software development to allow cost-effective use of existing information sources
- support distributed development and execution

tools or tool support 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.

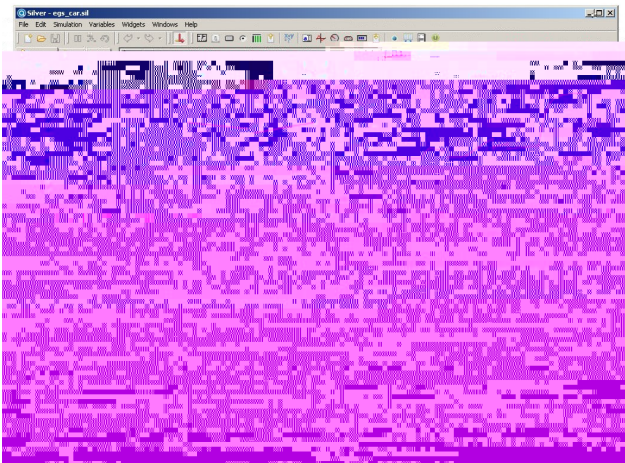
Another example is CANopen. This is a data base format used to store key information about variables and CAN parameters of automotive control software. CANopen contains the address of variables in the

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.

(adding all these standards available in the #i9 eases the task of actually getting automotiv6e &ontrol soft)ware running on a =C, and doing useful things with the resulting setup. Control software is typically de)com)posed into a number of so)called tasks. Aio e) functions implemented in C that are run '7 an R%D# Areal)time o)erating s)stem su&h as D#EK0 * an) tasks are periodically e)e)uted with a fixed rate, e)g) e)er) 10 ms) to get su&h tasks running in #i9, the user has to 'uild an ada)ter as sho)rn in :ig) , i) e) a little C)rogram that implements the #il)er module A=- and emulates the R%D# '7 &all)ing ea&h task on)e at e)er) 1) or e)er) 2nd, 3rd, 000) #i9 ma&ro ste))he #i9 tool is shi)ed with the #, # A#il)er , asis #oft)are, i) e) C sour)es that make it eas) to 'uild su&h an ada)ter '7 ada)ting tem)late ada)ter &ode) A &hea) alternati)e to)riting an ada)ter is to use the #i9 tools su)ort for * A%) 9A, ?#imulink and Realtime .orksho) AR% . B) Automotiv6e software is often de)elo)ed '7 first &re)ating a model of the &ontroller using #imulink))he

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