Appendix
Data-driven Mutation Testing: LuxSpace Case Study

This Appendix describe the procedures adopted to execute data-driven mutation testing on the LuxSpace case study system. Section 1 provide a detailed overview of the case study and the function targeted by data-driven mutation testing. Section 2 describes the fault models defined for the case study. Section 3 describes the integration of mutation probes into ADCS_IF_SW.

1. Overview of the case study

In the case of LXS, data-driven mutation testing is applied to assess the quality of the test cases that exercise the ADCS software interface of the ESAIL system (hereafter, ADCS_IF_SW). In ESAIL, the ADCS_IF_SW is used to manage and collect data from hardware devices (e.g., sensors). Detailed specifications for the ADCS interface appear in the document *ESAIL-LXS-ICD-P-0184 ADCS IF SW External ICD.*

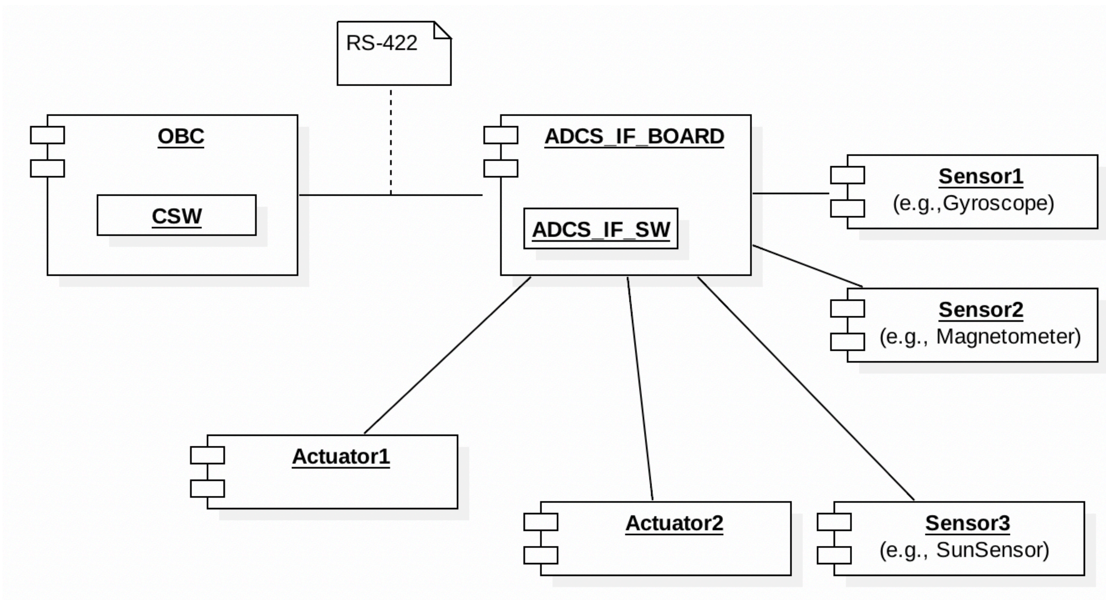

Figure 1: OBC-ADCS integration in ESAIL

Figure 1 provides an overview of the integration between ESAIL OBC and the ADCS board. ESAIL CSW (central software) runs on an onboard controller (OBC) with a Leon 3 microprocessor. The OBC is connected to ADCS interface boards (ADCS_IF_BOARD) through RS-422. The ADCS_IF_BOARD runs its own controller (ADCS_IF_SW). Each board processes data received from sensors and controls actuators. The ADCS_IF_SW is the target of data-driven mutation testing and is the software layer where mutation probes are installed.

The ADCS_IF_SW implements functions used by the OBC to send data to devices (i.e., set their configuration) and functions that send devices data to the OBC. Since the functions that send data to the devices are typically tested with hardware in the loop, in the context of FAQAS, we will apply data-driven mutation testing only to verify the functions used by the ADCS to send data to the OBC.

The function of the ADCS_IF_SW that manages the communication between the ADCS and the OBC, i.e., *ObcRecvBlockCb*. The function is implemented in file *AdcsIf.c*.

The implementation of function *ObcRecvBlockCb* is shown in Section 1.1. It mainly consists of a switch command (line 138) that generates a response for the OBC after invoking a *data generation method* selected according to the request received on the data link. For example, Line 146 invokes method *GetIfStatus*, which prepares a response packet containing the information about the ADCS status.

Each *data generation method* receive as input an object of type *std::vector* (i.e., the object *newBlock)* that will be used to store the data to be sent to the OBC. The vector *newBlock* acts as a buffer; it contains elements of type *UInt8*, the length of the vector matches the size of the response message indicated in *ESAIL-LXS-ICD-P-0184 (one element per byte).* Table 1 reports, for each feature targeted by data-driven mutation testing, the page in *ESAIL-LXS-ICD-P-0184 that describes the data format, the* ADCS_IF_SW function that fill the content of message, and the size of the response message (i.e., the length of *std::vector*).

Table 2:Features targeted by data-driven mutation testing and message size

ADCS Feature	Page	ADCS_IF_SW function	Message size (bytes)
ADCS IF Status	19	GetIfStatus	6
ADCS IF HK	22	GetIfHk	37
GYTM - Gyroscope TM	34	GetGyroTm	21
MMTX - Magnetometer TX	41	GetMgtmTm	2
Sun Sensor TM	42	GetSsTm	48
SSTP - Sun Sensor Temperature	45	GetSsTemp	12
Reaction Wheel TX	50	GetRwTm	2
SpaceCraft HK	60	GetIfScHk	18
Magnetorquer Set PWM RSP	57	GetMgtqTm	39

Each invocation of a *data generation method* generates a response (i.e., the vector *newBlock*) that may either contain the desired result or an error code. The response generated in the first case is referred to as *nominal response message*, the response generated in the second case is an *error response message*. The reponse message is sent to the OBC through the invocation of function SendResponse (Lines 298 and 312). When an error code is generated, the data generation method returns *CR_Failure*. The response code is read by function *ObcRecvBlockCb* to determine if it is necessary to trim the buffer before sending back to OBC; this behaviour is handled by the parameter *true* passed to SendResponse (Line 312).

1.1 Function ObcRecvBlockCb

```cpp
// --OPENING ELEMENT--AdcsIf::ObcRecvBlockCb--
/// Function that is called when a block of data is received from the data link layer.
/// @param block The received data block.
void AdcsIf::ObcRecvBlockCb(const std::vector<Smp::UInt8>& block)
{
    // MARKER: OPERATION BODY: START
    Trace(4, "Received command: 0x%s", OhbCommon::ByteUtils::BinToHex(block));

    if(!CheckRxEnabled())
    {
        return;
    }

    std::vector<Smp::UInt8> newBlock(block);

    Smp::UInt8 cmdId = block[0];
    Smp::UInt8 subcmdId = block[1];

    if(forcedResponse && (forcedResponseCmdId == cmdId || forcedResponseCmdId < 0)
       && (forcedResponseSubcmdId == subcmdId || forcedResponseSubcmdId < 0))
    {
        newBlock.resize(2);

        if(forcedResponseErrorCode >= 0)
        {
            // Generate forced error response
            Trace(2, "Generating forced response message with error code 0x%02X", forcedResponseErrorCode);
            newBlock.push_back(forcedResponseErrorCode);
            SendResponse(newBlock, true);
        }
        else
        {
            // Generate forced valid response
            Trace(2, "Generating forced response message with data 0x%s", forcedResponseData.c_str());
            for(unsigned int i = 0; i < forcedResponseData.length(); i += 2)
            {
                std::string byteString = forcedResponseData.substr(i, 2);
                newBlock.push_back(strtol(byteString.c_str(), NULL, 16));
            }
            SendResponse(newBlock, false);
        }
        return;
    }

    bool processed = true;
    CommandResult cr = CR_Failure;

    if(Status->ADRD || ((cmdId == 1) && (subcmdId < 3)))
    {
        switch(cmdId)
        {
        case 1:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetIfStatus(newBlock);
            }
            break;
            case 1:
            {
                cr = GetIfHk(newBlock);
            }
            break;
            case 2:
            {
                cr = SetIfPower(newBlock);
            }
            break;
            case 3:
            {
                cr = SetUnitStatus(newBlock);
            }
            break;
            case 4:
            {
                cr = SetConfiguration(newBlock);
            }
            break;
            case 5:
            {
                cr = LclRetrigger(newBlock);
            }
            break;
```

```
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        case 4:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetGyroTm(newBlock);
            }
            break;
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        case 5:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetMgtmTm(newBlock);
            }
            break;
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        case 6:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetSsTm(newBlock);
            }
            break;
            case 1:
            {
                cr = GetSsTemp(newBlock);
            }
            break;
```

```
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        case 7:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetRwTm(newBlock);
            }
            break;
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        case 8:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = SetMgtqPwm(newBlock);
                if(cr == CR_Success)
                {
                    if(newBlock[2] == 0x55)
                    {
                        // Bypass Magnetometer response
                        newBlock.resize(2);
                        cr = GetMgtqTm(newBlock);
                    }
                    else
                    {
                        cr = BuildMgtmDataRequestCmd(newBlock);
                        cr = GetMgtmTm(newBlock);
                    }
                }
            }
            break;
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
```

```
        case 9:
        {
            switch(subcmdId)
            {
            case 0:
            {
                cr = GetIfScHk(newBlock);
            }
            break;
            default:
                Log(Smp::Services::LMK_Warning, "Sub-command %u not implemented", subcmdId);
                processed = false;
            }
        }
        break;
        default:
            Log(Smp::Services::LMK_Warning, "Command %u not implemented", cmdId);
            processed = false;
        }
    }
    switch(cr)
    {
    case CR_Success:
    {
        SendResponse(newBlock, false);
    }
    break;
    case CR_InProgress:
    {
        Trace(5, "Operation in progress");
    }
    break;
    case CR_Failure:
    {
        if(!processed)
        {
            newBlock.push_back(0x56);
        }
        SendResponse(newBlock, true);
    }
    break;
    default:
        Log(Smp::Services::LMK_Error, "Command result %u not supported", cr);
    }
    // MARKER: OPERATION BODY: END
}
// --CLOSING ELEMENT--AdcsIf::ObcRecvBlockCb--
```

2. Fault Model

In the case of ADCS_IF_SW we have defined a total of 18 fault models, two for each feature listed in Table 1. For each feature, one fault model captures the fault that might affect a nominal response message, one fault model captures the faults that might affect an error response message.

In the following sections we describe the fault models by providing for each byte of the response message (column *Byte*), the relevant bits (column *Bit*), a description of the information that is supposed to be transmitted by the byte (column *Description*), the type of data written on the byte (column *Type*), the fault classes that might affect the byte (column *Fault class*). We do not report the span of the item since it can be deducted from the table; indeed, descriptions that span over multiple rows correspond to data types that, to be loaded, require the readin of multiple data items. For each fault class, we indicate the value of the parameters required to configure the corresponding mutation operator (see Table 2.1 of D2). The label NONE indicates that we are not interested into performing data-driven mutation testing for that specific byte. Columns Byte, Bit, and Description match the columns of corresponding tables in *ESAIL-LXS-ICD-P-0184.*

2.1 ADCS IF Status

Byte	Bit	Description	Type	Fault class
1	2..0	Reset Source Provides information about last reset. The bit is cleared after the first read of the status 0 = No reset 1 = Power-on Reset 2 = External Reset (released by JTAG adapter) 3 = Watchdog Reset 4 = Brown-out Reset 5 = JTAG AVR Reset (logic reset by JTAG) 6 = Not used 7 = Not used	BIN	BF(MIN=3;MAX=3) BF(MIN=4;MAX=4) BF(MIN=5;MAX=7)
	3	ADCS IF ready This bit is set when ADCS is ready to read/write to units. In the boot of the ADCS IF shall be a time to initialize all modules and units. After initialization of the ADCS IF, modules and units, shall go to a ready state. While ADCS IF is not ready, the available commands are: • ASST • ASHK • ASCT		

	4	OBC communication error This bit is set if a communication error between OBC and ADCS IF occurred in the last command. The bit is cleared after the first reading of the status 0 = No error 1 = Communication error		
	7..5	Unit communication error This bit is set if a communication error between ADCS IF and ADCS unit occurred. The bit is cleared after the first read of the status 0 = No error 1 = Communication error		
2	7..0	Unit in error Provides a list of units in error. 0 = No error 1 = Unit error Each bit is assigned to one unit: Bit 0 = Gyroscope unit Bit 1 = Reaction Wheel Bit 2 = Magnetorquer Bit 3 = Magnetometer Bit 4 = Sun Sensor	BIN	BF(MIN=0;MAX=4)
3	7..0	Watchdog Reset Counter Watchdog Reset counter value. Increment in every watchdog reset. Value is stored in non-volatile memory To clear watchdog reset counter, shall be used the ASCF command.	INT	None: ESAIL OBC does not deal with anomalous values of reset counters. Thus we do not expect ESAIL test suite to fail in case of a high reset counter..
4	7..0	Overall Reset Counter Overall reset counter value. Increment in every device reset. Value is stored in non-volatile memory To clear overall reset counter, shall be used the ASCF command.	INT	None: same as above.
5	1..0	Gyroscope enable Enable/Disable status of nominal or redundant bus transceiver. 0 = Disabled both transceivers 1 = Enabled nominal transceiver only 2 = Enabled redundant transceiver only	BIN	BF(MIN=0;MAX=2) BF(MIN=2;MAX=4) BF(MIN=5;MAX=7)

		3 = not existing (reserved for future needs)		
	4..2	Reaction Wheel enable Enabled/Disabled status of bus transceiver. 0 = Disabled transceiver 1 = Enabled transceiver 7..2 = not existing (reserved for future needs)		
	7..5	3 axis Magnetorquer enable General Enable/Disable status of the Magnetorquer Driver for all three axis. 0 = Disabled 1 = Enabled Bit assignement: Bit 0 = Enabled/Disabled Driver Bit 1 = 0 not used (reserved for future needs) Bit 2 = 0 not used (reserved for future needs)		
6	1..0	Magnetometer enable Enable/Disable status of nominal or redundant bus transceiver. 0 = Disabled both transceivers 1 = Enabled nominal transceiver only 2 = Enabled redundant transceiver only 3 = not existing (reserved for future needs)	BIN	BF(MIN=0;MAX=1) BF(MIN=2;MAX=7)
	7..2	Sun Sensor board ADC enable Enabled/Disabled Sun Sensor board ADC, see Note 3) 0 = Disabled 1 = Enabled Each bit is assigned to one ADC: Bit 0 = Enabled/Disabled ADC2 Bit 1 = Enabled/Disabled ADC3 Bit 2 = Enabled/Disabled ADC4 Bit 3 = Enabled/Disabled ADC5 Bit 4 = Enabled/Disabled ADC6 Bit 5 = Enabled/Disabled ADC7		

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	HEX	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x55)

				IV(VALUE=0x57) IV(VALUE=0x58) IV(VALUE=0x59) IV(VALUE=0x5A) IV(VALUE=0x5B) IV(VALUE=0x5C)

2.2 ASHK - ADCS IF HK

Byte	Bit	Description	Type	Fault class
1	7..0	VCC1N	Double?	VAT(T=XX;D=XX)
2	7..0	OBC Nominal transceiver circuit voltage		
3	7..0	VCC1R		VAT(T=XX;D=XX)
4	7..0	OBC Redundant transceiver circuit voltage		
5	7..0	VCC2		
6	7..0	Gyroscope transceiver/UART circuit voltage		VAT(T=XX;D=XX)
7	7..0	VCC3		
8	7..0	Magnetometer transceiver/UART circuit voltage		VAT(T=XX;D=XX)
9	7..0	VCC4		
10	7..0	Reaction Wheel transceiver/UART circuit voltage		VAT(T=XX;D=XX)
11	7..0	VCCa		
12	7..0	Internal power supply (5.5V), measured with ADC0		VAT(T=XX;D=XX)
13	7..0	VCCb		
14	7..0	Internal power supply (5.5V), measured with ADC1		VAT(T=XX;D=XX)
15	7..0	VBUS		VAT(T=XX;D=XX)
16	7..0	Unit input bus voltage		
17	7..0	VCC5		VAT(T=XX;D=XX)
18	7..0	Supply voltage for ADC2, ADC3, ADC4 and VCCB1. Sun-sensor PCB		
19	7..0	VCC6		
20	7..0	Supply voltage for ADC5, ADC6, ADC7 and VCCB2. Sun-sensor PCB		VAT(T=XX;D=XX)
21	7..0	VCC5_IN		
22	7..0	LDO input voltage for ADC2, ADC3, ADC4 and VCCB1. Sun-sensor PCB		VAT(T=XX;D=XX)
23	7..0	VCC6_IN		
24	7..0	LDO input voltage for ADC5, ADC6, ADC7 and VCCB2. Sun-sensor PCB		VAT(T=XX;D=XX)
25	7..0	VCC_SW1 SSB internal switched power supply, measured by ADC3		VAT(T=XX;D=XX)
26	7..0	Remark: the voltage VCC_SW is measured 2 times with two different ADC. This allows to compare the results and conclude for a drift in the ADC's.		
27	7..0	VCC_SW2		VAT(T=XX;D=XX)

28	7..0	SSB internal switched power supply, measured by ADC6 Remark: the voltage VCC_SW is measured 2 times with two different ADC. This allows to compare the results and conclude for a drift in the ADC's.		NONE
29	7..0	T_PCB_TEMP1 Main Board PCB Temperature, sensor 1 Temperature of VCC DC/DC regulator. Remark: 1/2 is measured on the same place, it's to compare the values to discover a measurement failure		VOR(MIN=XX; MAX=XX;D=XX)
30	7..0			
31	7..0	T_PCB_TEMP2 Main Board PCB Temperature, sensor 2 Temperature of VCC DC/DC regulator. Remark: 1/2 is measured on the same place, it's to compare the values to discover a measurement failure		VOR(MIN=XX; MAX=XX;D=XX)
32	7..0			
33	7..0	T_PCB_TEMP3a Sun Sensor Board PCB Temperature, sensor 3a. Temperature of VCC5 LDO regulator. Remark: 3a/b is measured on the same place, it's to compare the values to discover a measurement failure		VOR(MIN=XX; MAX=XX;D=XX)
34	7..0			
35	7..0	T_PCB_TEMP3b Sun Sensor Board PCB Temperature, sensor 3b. Temperature of VCC5 LDO regulator. Remark: 3a/b is measured on the same place, it's to compare the values to discover a measurement failure		VOR(MIN=XX; MAX=XX;D=XX)
36	7..0			
37	7..0	T_PCB_TEMP4 Sun Sensor Board PCB Temperature, sensor 4. Temperature of VCC6 LDO regulator.		VOR(MIN=XX; MAX=XX;D=XX)

Byte	**Bit**	**Description**	**Type**	**Fault class**
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	HEX	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x55) IV(VALUE=0x57) IV(VALUE=0x58) IV(VALUE=0x59) IV(VALUE=0x5A) IV(VALUE=0x5B) IV(VALUE=0x5C)

2.3 GYTM - Gyroscope TM

Byte	**Bit**	**Description**	**Type**	**Fault class**
1	7..0	Unit identifier Identification of the unit that addresses the message 0 = Nominal 1 = Redundant	Int	BF(MIN=0,MAX=0)
21..2	7..0	Gyroscope Telemetry All telemetry data from Gyroscope. Message is the same sent from Gyroscope unit without adding/removing data	HEX	NONE?

Byte	Bit	Description		
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x56)

2.4 MMTX - Magnetometer TX

Byte	Bit	Description	Type	Fault class
1	7..0	Unit identifier Identification of the unit that addresses the message 0 = Nominal 1 = Redundant	BIN	BF(MIN=0;MAX=0)
2	7..0	Self Test Result 0 = no error 1 = error detected during TX self test 2-255 = reserved	BIN	BF(MIN=0;MAX=0;STATE=0) BF(MIN=1;MAX=7), it simulates reporting a failure for another unit.

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	HEX	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x56) IV(VALUE=0x5D)

2.5 Sun Sensor TM

Byte	Bit	Description	Type	Fault class
1	7..0	Photodiode Q1 current ADC #3	Double?	VAT(T=XX;D=XX)
2	7..0			
3	7..0	Photodiode Q2 current ADC #3		
4	7..0			
5	7..0	Photodiode Q3 current ADC #3		
6	7..0			
7	7..0	Photodiode Q4 current ADC #3		
8	7..0			
9	7..0	Photodiode Q1 current ADC #2		
10	7..0			
11	7..0	Photodiode Q2 current ADC #2		
12	7..0			
13	7..0	Photodiode Q3 current ADC #2		
14	7..0			
15	7..0	Photodiode Q4 current ADC #2		
16	7..0			
17	7..0	Photodiode Q1 current ADC #6		
18	7..0			
19	7..0	Photodiode Q2 current ADC #6		
20	7..0			
21	7..0	Photodiode Q3 current ADC #6		
22	7..0			
23	7..0	Photodiode Q4 current ADC #6		
24	7..0			
25	7..0	Photodiode Q1 current ADC #5		
26	7..0			
27	7..0	Photodiode Q2 current ADC #5		
28	7..0			
29	7..0	Photodiode Q3 current ADC #5		
30	7..0			
31	7..0	Photodiode Q4 current ADC #5		
32	7..0			
33	7..0	Photodiode Q1 current ADC #4		
34	7..0			
35	7..0			

36	7..0	Photodiode Q2 current ADC #4		
37	7..0	Photodiode Q3 current ADC #4		
38	7..0			
39	7..0	Photodiode Q4 current ADC #4		
40	7..0			
41	7..0	Photodiode Q1 current ADC #7		
42	7..0			
43	7..0	Photodiode Q2 current ADC #7		
44	7..0			
45	7..0	Photodiode Q3 current ADC #7		
46	7..0			
47	7..0	Photodiode Q4 current ADC #7		
48	7..0			

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x51) IV(VALUE=0x54) IV(VALUE=0x56)

2.6 SSTP - Sun Sensor Temperature

Byte	Bit	Description	Type	Fault class
1	7..0	Temperature reading from ADC #3	Double?	VOR(MIN=?;MAX=?;D=?)
2	7..0			
3	7..0	Temperature reading from ADC #2		
4	7..0			
5	7..0	Temperature reading from ADC #6		
6	7..0			
7	7..0	Temperature reading from ADC #5		
8	7..0			
9	7..0	Temperature reading from ADC #4		
10	7..0			
11	7..0	Temperature reading from ADC #7		
12	7..0			

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x51) IV(VALUE=0x54) IV(VALUE=0x56)

2.7 Reaction Wheel TX

Byte	Bit	Description	Type	Fault class
1	7..0	Unit identifier Identification of the unit that addresses the message 0 = Nominal 1 = Redundant	BIN	BF(MIN=0,MAX=0)
2	7..0	Self Test Result 0 = no error 1 = error detected during TX self test 2-255 = reserved	BIN	BF(MIN=0,MAX=0)

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x56) IV(VALUE=0x5D)

2.8 SpaceCraft HK

Byte	**Bit**	**Description**	**Type**	**Fault class**
1	7..0	TMTC_SW1 Identifies the switching position of the TMTC switch 1: the voltage is ~1.1V for position A and 2.2V for position B. 0V or 3.3V will indicate a short or an interruption.	?Double	VAT(T=3.3;D=0) VBT(T=0;D=0)
2	7..0			
3	7..0	TMTC_SW2 Identifies the switching position of the TMTC switch 2: the voltage is ~1.1V for position A and 2.2V for position B. 0V or 3.3V will indicate a short or an interruption.		
4	7..0			
5	7..0	SC_TEMP1 Temperature SC-TEMP1 of a sensor in the S/C structure	?	VOR(MIN=x;MAX=X; D=X)
6	7..0			
7	7..0	SC_TEMP2 Temperature SC-TEMP2 of a sensor in the S/C structure		
8	7..0			
9	7..0	SC_TEMP3 Temperature SC-TEMP3 of a sensor in the S/C structure		
10	7..0			
11	7..0	SC_TEMP4 Temperature SC-TEMP4 of a sensor in the S/C structure		
12	7..0			
13	7..0	SC_TEMP5 Temperature SC-TEMP5 of a sensor in the S/C structure		
14	7..0			
15	7..0	SC_TEMP6 Temperature SC-TEMP6 of a sensor in the S/C structure		
16	7..0			
17	7..0	SC_TEMP7 Temperature SC-TEMP7 of a sensor in the S/C structure		
18	7..0			

Byte	Bit	Description		
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x56)

2.9 Magnetorquer Set PWM RSP

Byte	Bit	Description	Type	Fault class
1	7..0	Unit identifier Magnetometer Identification of the Magnetometer unit that addresses the message 0 = Nominal 1 = Redundant		BF(MIN=0;MAX=0)
2	7..0	Magnetometer Data request reply Byte1 Sync(LSB) (Note 1)		?
3	7..0	Magnetometer Data request reply Byte2 Sync(MSB) (Note 1)		
4	7..0	Magnetometer Data request reply Byte3 RAdr (Note 1)		
5	7..0	Magnetometer Data request reply Byte4 Sadr (Note 1)		
6	7..0	Magnetometer Data request reply Byte5 ReplyMsg (Note 1)		
7	7..0	Magnetometer Data request reply Byte6 Bx Low (Note 1)		
8	7..0	Magnetometer Data request reply Byte7 Bx Middle		
9	7..0	Magnetometer Data request reply Byte8 CS error + Average + pos Clip X + neg Clip X + BX High (Note 1)		
10	7..0	Magnetometer Data request reply Byte9 By Low (Note 1)		
11	7..0	Magnetometer Data request reply Byte10 By Middle (Note 1)		
12	7..0	Magnetometer Data request reply Byte11 spare + pos Clip Y + neg Clip Y + BY High (Note 1)		
13	7..0	Magnetometer Data request reply Byte12 Bz Low (Note 1)		
14	7..0	Magnetometer Data request reply Byte13 Bz Middle (Note 1)		
15	7..0	Magnetometer Data request reply Byte14 spare + pos Clip Z + neg Clip Z + BZ High (Note 1)		
16	7..0	Magnetometer Data request reply Byte15 CS (Note 1)		
17	7..0	Magnetorquer nX Current - on Current MTXA_N when powered		
18	7..0			
19	7..0	Magnetorquer nX Current - off Current MTXA_N when unpowered		
20	7..0			
21	7..0	Magnetorquer pX Current - on		

22	7..0	Current MTXA_P when powered		
23	7..0	Magnetorquer pX Current - off Current MTXA_P when unpowered		
24	7..0			
25	7..0	Magnetorquer nY Current - on Current MTYA_N when powered		
26	7..0			
27	7..0	Magnetorquer nY Current - off Current MTYA_N when unpowered		
28	7..0			
29	7..0	Magnetorquer pY Current - on Current MTYA_P when powered		
30	7..0			
31	7..0	Magnetorquer pY Current - off Current MTYA_P when unpowered		
32	7..0			
33	7..0	Magnetorquer nZ Current - on Current MTZA_N when powered		
34	7..0			
35	7..0	Magnetorquer nZ Current - off Current MTZA_N when unpowered		
36	7..0			
37	7..0	Magnetorquer pZ Current - on Current MTZA_P when powered		
38	7..0			
39	7..0	Magnetorquer pZ Current - off Current MTZA_P when unpowered		

Byte	Bit	Description	Type	Fault class
1	7..0	Error type The possible errors are described in the **Error! Reference source not found.**.	Hex	IV(VALUE=0x51) IV(VALUE=0x52) IV(VALUE=0x53) IV(VALUE=0x54) IV(VALUE=0x56) IV(VALUE=0x5D) IV(VALUE=0x5E)

3. Mutation Probes

Mutation probes are manually integrated into the source code of function *ObcRecvBlockCb*. Figure 2 shows an example of how we integrate mutation probes. All the probes are integrated following the same pattern; more precisely, for each data generation function we manually insert two invocations to the FAQAS mutation probe API, one to perform mutation of the nominal response message (Line 154, in Figure 2) the other one to mutate an error response message (Line 149). The choice of the data model to pass to the FAQAS mutation probe API is based on the value of *cr*, the variable that captures the return status of the specific data generation function invoked (function *GetIfHk* in Figure 2).

The function _FAQAS_mutate takes as input the fault model to be used to drive the mutation. Fault models are automatically generated from template files matching to the tables reported in Section 2.

```
144:        case 0:
145:        {
146:          cr = GetIfStatus(newBlock);
147:          if ( cr == CR_Failure ){
148:                FaultModel *dm = _FAQAS_GetIfStatus_FM_Error ()
149:                _FAQAS_mutate( newBlock, dm );
150:                _FAQAS_delete_DM( dm )
151:          } else {
152:                FaultModel *dm = _FAQAS_GetIfStatus_FM ()
153:                _FAQAS_mutate( newBlock, dm);
154:                _FAQAS_delete_DM( dm )
155:          }
156:        }
```

Figure 2: Mutation probe for GetIfStatus