

FSRs grouped on functional architecture component

Component	FSR
Environment perception Sensors	Failure of environment perception sensors shall not result in the generation of incorrect information on distance to the surrounding vehicles and objects.
	Incorrect information going into Environment Perception Sensors shall not cause known perception information to be incorrect as well
Actuation Sensor	A failure in Actuation Sensor shall not cause incorrect sensor information
	External interference shall not invalidate/corrupt data from actuation sensors .
Vehicle State Estimator	Corruption of signals from Sensor Abstraction to Sensor Fusion shall not interfere with the correctness of data provided to Sensor Fusion
	A failure in Sensor Fusion shall not cause incorrect interpretation of raw sensor data
	A failure in Vehicle State Estimator shall not cause the known vehicle state to be incorrect
Host Tracking	Corruption of signals from Sensor Abstraction to Sensor Fusion shall not interfere with the correctness of data provided to Sensor Fusion
	A failure in Sensor Fusion shall not cause incorrect interpretation of raw sensor data
	A failure in Host Tracking shall not cause incorrect self-tracking
Target Tracking	Corruption of signals from Sensor Abstraction to Sensor Fusion shall not interfere with the correctness of data provided to Sensor Fusion
	A failure in Sensor Fusion shall not cause incorrect interpretation of raw sensor data
	A failure in Target Tracking shall not cause it to not track a vehicle that shall be tracked
	A failure in Target Tracking shall not cause it to track a vehicle that shall not be tracked
Vehicle Control	A failure in vehicle control shall not cause generation of incorrect actuation signals
	A failure in vehicle control shall neither inhibit nor modify the input from driver to further pass on
	A failure in vehicle control shall not cause a switch to manual drive mode while in platooning mode
	A failure in Actuator Layer shall not cause control setpoints to not be properly forwarded
	A failure in Vehicle Control shall not cause the control mode (platooning or manual driving) to remain the same while it shall be changed
	A failure in Vehicle Control shall not cause lack of generation of required signals
	A failure in Vehicle Control shall not cause generation of improper control setpoints
	A failure in Vehicle Control shall not cause the lack of generation of control setpoints
	Corruption of signals from V2V to Vehicle Control shall not interfere with the correctness of data provided to Vehicle Control from V2V
V2V Communication	Failure in V2V communication shall not transmit incorrect information to or receive incorrect information from a vehicle joining or leaving a platoon.
	Corruption of signals of Actuate to V2V shall not interfere with the correctness of information at V2V
	Incorrect arrival of V2V signals at a V2V station shall not interfere with the correct of information at another V2V station
	A failure in V2V shall not cause incorrect information to be sent to other vehicles
	Incorrect information going into V2V shall not cause known information about other vehicles to be incorrect

Actuator	A failure in Actuator shall not cause incorrect propagation of control signals to hardware actuators
	Corruption of control signals from Actuator shall not interfere with the correctness of control signals at target hardware components
	Corruption of signals to Actuator shall not interfere with the correct working of actuators