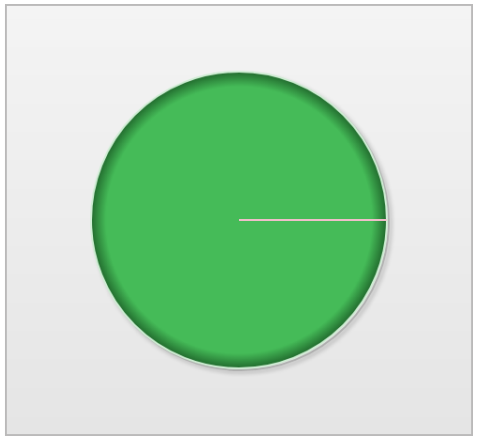
Snapshot 3 Summary

Project: Autonomous Driving Car

By Humayra Rashid, 5/10/2025 10:34 PM

Run: Test Run 5/10/2025, Snapshot 3



10 Passed

100% set to Passed

0 Blocked

0% set to Blocked

0 Retest

0% set to Retest

0 Failed

0% set to Failed

100%
passed

0 / 10 untested (0%).

This section focuses on validating the core algorithmic components of the autonomous driving system, specifically the Processing Module (PM) and the Response Module (RM). These tests are designed to ensure accurate interpretation of sensor input, consistent decision-making, and timely generation of control commands. Functional correctness and performance efficiency are key priorities in this phase.

Tests in this section evaluate the logic pipeline from image preprocessing to output command generation, both in isolation and in integration with sensor and motor subsystems.

Focus Areas:

Image preprocessing and edge detection accuracy

Obstacle and path recognition

Decision logic consistency across scenarios

Created On	5/10/2025
Completed	No

Activity

5/5/2025 – 5/10/2025:

10 Passed

59% set to Passed

1 Blocked

6% set to Blocked

2 Retest

12% set to Retest

4 Failed

24% set to Failed

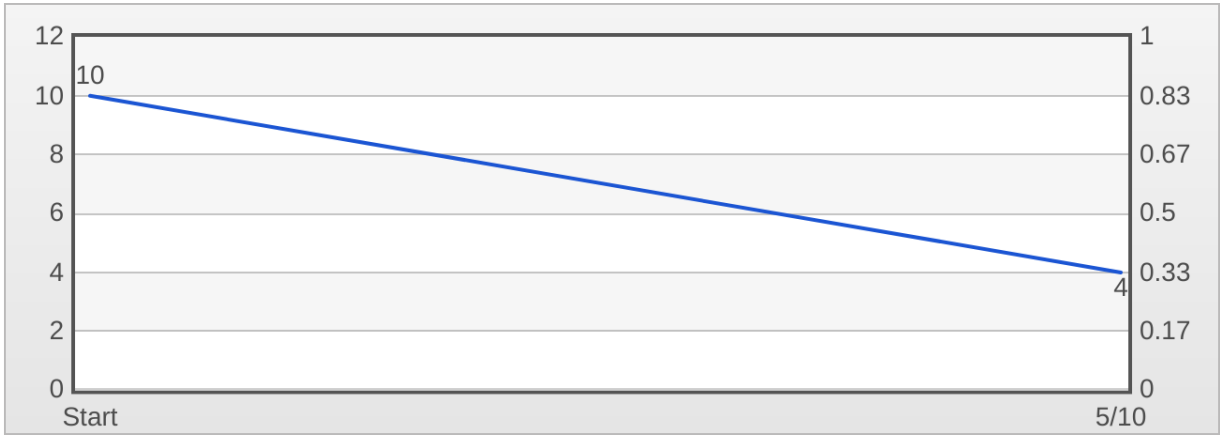
Saturday, May 10, 2025

Passed	Time-to-response validation under peak system load	Tested by Henry X.
Assigned	Time-to-response validation under peak system load	Assigned to Henry X.
Passed	PM-RM response under partial image corruption	Tested by Henry X.
Failed	PM-RM response under partial image corruption	Tested by Henry X.
Assigned	PM-RM response under partial image corruption	Assigned to Daniel G.
Passed	RM handles conflicting sensor data gracefully	Tested by Henry X.

Retest	RM handles conflicting sensor data gracefully	Marked by Henry X.
Assigned	RM handles conflicting sensor data gracefully	Assigned to Rodrigo V.
Passed	PM identifies lane markings under varying road textures	Tested by Henry X.
Failed	PM identifies lane markings under varying road textures	Tested by Henry X.
Assigned	PM identifies lane markings under varying road textures	Assigned to Humayra R.
Passed	Real time detection of moving obstacles	Tested by Henry X.
Retest	Real time detection of moving obstacles	Marked by Henry X.
Assigned	Real time detection of moving obstacles	Assigned to Rodrigo V.
Passed	End-to-end decision loop (sim)	Tested by Henry X.
Failed	End-to-end decision loop (sim)	Tested by Henry X.
Assigned	End-to-end decision loop (sim)	Assigned to Henry X.
Passed	RM generates valid response	Tested by Henry X.
Assigned	RM generates valid response	Assigned to Humayra R.
Passed	PM filters irrelevant data	Tested by Henry X.
Assigned	PM filters irrelevant data	Assigned to Daniel G.
Passed	PM processes live image input	Tested by Henry X.

Blocked	PM processes live image input	Marked by Henry X.
Assigned	PM processes live image input	Assigned to Rodrigo V.
Passed	Image edge detection under low visibility	Tested by Henry X.
Failed	Image edge detection under low visibility	Tested by Henry X.
Assigned	Image edge detection under low visibility	Assigned to Humayra R.
Untested	Image edge detection under low visibility	
Untested	Real time detection of moving obstacles	
Untested	End-to-end decision loop (sim)	
Untested	RM generates valid response	
Untested	PM filters irrelevant data	
Untested	PM processes live image input	

Progress



Since 5/10/2025:

Remaining Tests

100% of tests completed.

Remaining Effort

Forecast not available.

Ideal Progress

Forecast not available.

Forecasts & Estimates

Based on the current activity and forecasts, the projected completion date for the test run(s) is:

Unknown

Forecast not possible

The test run(s) were started **21 hours ago** (5/10/2025).

Completed:100%(10/10)
Elapsed:0h 0m
Tests / day: 10
Hours / day:n/a

Metric	By Estimate	By Forecast
Completed	0h 0m	n/a
To-do	0h 0m	n/a
Total	0h 0m	n/a

Tests & Results

Snapshot 3 (10)

This section focuses on validating the core algorithmic components of the autonomous driving system, specifically the Processing Module (PM) and the Response Module (RM). These tests are designed to ensure accurate interpretation of sensor input, consistent decision-making, and timely generation of control commands. Functional correctness and performance efficiency are key priorities in this phase.

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Focus Areas:

Image preprocessing and edge detection accuracy

Obstacle and path recognition

Decision logic consistency across scenarios

Response time for generating steering/throttle commands

Integration between PM and RM

ID	Title	Status
T46	PM processes live image input	Passed
T47	PM filters irrelevant data	Passed
T48	RM generates valid response	Passed

T49	End-to-end decision loop (sim)	Passed
T50	Real time detection of moving obstacles	Passed
T51	Image edge detection under low visibility	Passed
T60	PM identifies lane markings under varying road textures	Passed
T61	RM handles conflicting sensor data gracefully	Passed
T62	PM-RM response under partial image corruption	Passed
T63	Time-to-response validation under peak system load	Passed