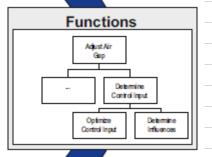
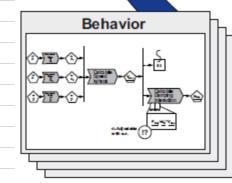
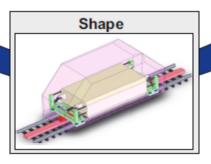
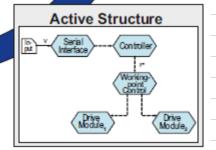


System of Coherent Partial Models









		Downston out list								
		Requriement list								
No	Requriement descrip	tion	Type (D/W)							
	Geometry									
1	-		_							
1.1	 	owing trucks should be not more than 3 meters.	D							
1.2		ch truck should be not less than 30cm.	W							
1.3		uck should be less than 15m	D							
1.4		ould be more than 10 tonns	W							
1.5	 	k should be able to make a trip on a distance at least 1500km.	W							
1.6	Size of trucks:	Ī								
1.6.1		lenght not more than 20m	W							
1.6.2	-	width not more than 2.5 meters	D							
1.6.3			D D							
1.7	height not more than 3.5 m The length of a platoon should be limited to 7 vehicles									
2	Communications									
2.1	All trucks should be a	ble to broadcast and recieve platooning information through V2V	D							
2.2	The system in the ego truck shall broadcast its actual and intended acceleration via V2V to enable following vehicles to detect emergency braking events.									
	The ego truck shall be informed in case of emergency braking events of the preceding trucks in the platoon. Therefore at least the requested and actual acceleration value of the preceding platoon									
2.3	1:	d and to be compared with a defined acceleration threshold value.	D							
		ble to use folowing protocols and standards for communication: Wifi,								
2.4	Bluetooth, LoRaWAN	EnOcean	W							
2.5	All vehicles should be	provided with secure communication channel according to the X.509 standard	D							
2.6	Communication laten	cy should be less than 10ms	D							
2.7	Each platoon should a	assign roles to trucks in time less than 1 minute	W							
		engages from the platoon, the former first follower truck becomes the leader	_							
2.8	truck		D							
2.9	-	ct and broadcast a cut-in when detected.	D							
3	Safety		D							
3.1	Emergency brake distance should be not more than 20m when the speed is not higher than 60 kmph									
3.2	In case of failure of ADAS the drive control should be assigned to the driver in less than 2 seconds									
3.3										
2.4	The system shall keep a time gap to the preceding truck such that it can avoid collision if the									
3.4	preceding truck is braking to standstill with its maximum deceleration capacity.									
3.5	The system shall com m/s ²	municate the ego vehicle maximum brake deceleration capacity, if unknown: 8	l w							
3.6		er keep a closer time gap than 0.8 s to the preceding truck in the platoon.	D							
	-		W							
3.7	The speed limit for pi	atoon should be 100 kmph	VV							

The system shall be able to inform the preceding truck that it cannot reach the intended time gap, i. e. the gap is too large, by communicating a desired maximum speed request. The system shall be able to inform the preceding truck about its performance limitations by communicating a desired maximum acceleration request and a desired maximum speed request. During platoon formation the truck shall detect preceding truck and measure the position of these with a longitudinal accuracy of 0.4m, a range of 200m and an opening angle of +/- 4° with an azimuth accuracy of 0.1° The system shall not brake with a deceleration that is higher (stronger braking) than the maximum brake deceleration capacity communicated to the other platoon vehicles. Diver satisfaction 4.1 Cabin size 4.1.1 the height should be not less than 1.8m What is the length should be not less than 2m What is the length should be not less than 2m What is the width should be not less than 2m What is the vehicle Max speed should be not less than 2m What is the vehicle should be equipped with an embedded refrigirator What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places The vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2 sleep places What is the vehicle should have at least 2					
3.9 communicating a desired maximum acceleration request and a desired maximum speed request. During platoon formation the truck shall detect preceding truck and measure the position of these with a longitudinal accuracy of 0.4m, a range of 200m and an opening angle of +/- 4° with an azimuth accuracy of 0.1° The system shall not brake with a deceleration that is higher (stronger braking) than the maximum brake deceleration capacity communicated to the other platoon vehicles. D Driver satisfaction 4.1 Cabin size 4.1.1 the height should be not less than 1.8m W H.1.2 the lenght should be not less than 2m W H.1.3 the width should be not less than 2m W H.2 Vehicle Max speed should be not less than 2m W H.3 The vehicle should be equipped with an embedded refrigirator W H.4 The vehicle should have at least 2 sleep places W H.5 The vehicle should have customization of drive controls W H.6 The vehicle should have customization of drive controls W H.8 Minimize sensitivity to the sidewind S System interaction The driver in a platoon should be able to recognize that the ego-truck has a platoon feature D The driver in a platoon shall be informed about platooning system failures and their causes D The driver in a platoon shall be informed about platooning system failures and their causes	3.8			D	
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3.11 brake deceleration capacity communicated to the other platoon vehicles. 4 Driver satisfaction 4.1 Cabin size 4.1.1 the height should be not less than 1.8m 4.1.2 the lenght should be not less than 2m 4.1.3 the width should be not less than 2m 4.2 Vehicle Max speed should be not less than 90kmph 4.3 The vehicle should be equipped with an embedded refrigirator 4.4 The vehicle should have at least 2 sleep places 4.5 The vehicle should have easy access to the emergency mechanisms and exits 4.6 The vehicle should have customization of drive controls 4.7 The system shall not brake more than needed to keep the selected time gap to the preceding truck 4.8 Minimize sensitivity to the sidewind 5 System interaction 5.1 The driver in a platoon should be able to recognize that the ego-truck has a platoon feature D The driver in a platoon can activate the platoon mode at any time. The system determines if and when parameters are met to start the search for other platoon trucks D South of the platoon driving as Leader, Follower D The driver in a platoon shall be informed his role in the platoon driving as Leader, Follower D The driver in a platoon shall be informed about platooning system failures and their causes	3.10	with a longitudinal ac	curacy of 0.4m, a range of 200m and an opening angle of +/- 4° with an	D	
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4.1.3 the width should be not less than 2m W 4.2 Vehicle Max speed should be not less than 90kmph W 4.3 The vehicle should be equipped with an embedded refrigirator W 4.4 The vehicle should have at least 2 sleep places W 4.5 The vehicle should have easy access to the emergency mechanisms and exits D 4.6 The vehicle should have customization of drive controls W 4.7 The system shall not brake more than needed to keep the selected time gap to the preceding truck W 4.8 Minimize sensitivity to the sidewind W 5 System interaction 5.1 The driver in a platoon should be able to recognize that the ego-truck has a platoon feature D The driver in a platoon can activate the platoon mode at any time. The system determines if and when parameters are met to start the search for other platoon trucks D 5.3 The driver in a platoon shall be informed his role in the platoon driving as Leader, Follower D 5.4 The driver in a platoon shall be informed about platooning system failures and their causes D	4.1.2		the lenght should be not less than 2m	W	No.
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4.7 The system shall not brake more than needed to keep the selected time gap to the preceding truck 4.8 Minimize sensitivity to the sidewind 5 System interaction 5.1 The driver in a platoon should be able to recognize that the ego-truck has a platoon feature The driver in a platoon can activate the platoon mode at any time. The system determines if and when parameters are met to start the search for other platoon trucks 5.3 The driver in a platoon shall be informed his role in the platoon driving as Leader, Follower 5.4 The driver in a platoon shall be informed about platooning system failures and their causes D	4.5	The vehicle should ha	D		
4.8 Minimize sensitivity to the sidewind 5 System interaction 5.1 The driver in a platoon should be able to recognize that the ego-truck has a platoon feature The driver in a platoon can activate the platoon mode at any time. The system determines if and s.2 when parameters are met to start the search for other platoon trucks D 5.3 The driver in a platoon shall be informed his role in the platoon driving as Leader, Follower D The driver in a platoon shall be informed about platooning system failures and their causes D	4.6	The vehicle should ha	ve customization of drive controls	W	
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5.4 The driver in a platoon shall be informed about platooning system failures and their causes D	5.2		· · · · · · · · · · · · · · · · · · ·	D	
	5.3	The driver in a platoo	n shall be informed his role in the platoon driving as Leader, Follower	D	No No
5.5 The driver in the platoon shall be warned in case of an Emergency brake situation.	5.4	The driver in a platoo	n shall be informed about platooning system failures and their causes	D	
	5.5	The driver in the plate	oon shall be warned in case of an Emergency brake situation.	D	

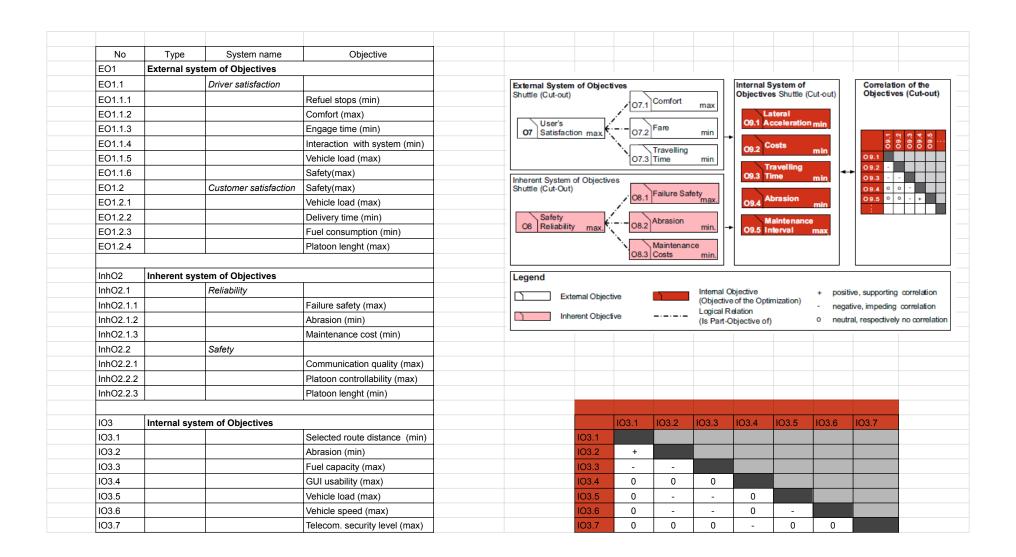
	Requirements list	
No.	Requirement description	D/W
1	Geometry	
1.9	Entrance should be possible from both sides.	D
1.10	Optimal aerodynamics for single and convoi drive modes.	D
1.11	Modular construction.	D
2	Kinematics	D
2.1	The vehicle has a steering system.	D
7	Safety	
7.9	Provide emergency mechanisms and exits.	D
7.10	Minimize sensitivity to the side wind.	W

No	Name	Subclass								
	Provide mobility for trucks carrying goods	Provide autonomous movement capability								
			Provide ACC capabilities							
				Maintain a chosen velocity and dis	stance betwe	en a vehicle	and the vehic	le ahead		
				Avoid obstacles						
				Automatically brake or accelerate						
			Provide Lane keeping capabilities							
				Detect Lanes						
				Maintain and control distance to la	anes					
			Provide Navigation system capabilities							
			Provide Blind spot monitoring capabilities							
				Detect and notify if any obstacles	come close t	to the vehicl	e.			
			Provide Crosswind stabilization							
			FTOVIGE CLOSSWING STADIIIZATION	Distribute the wheel load in relation	n to the valo	oits and dire	ation of the or	anuind		
		Provide platooning capability		Distribute the wheel load in relation	on to the velo	city and dire	cuon or the cr	osswiriu		
		Provide piatooning capability	Draviding platean formation						Provide mobility for	
			Providing platoon formation						trucks carrying goods	
			Disenanging from platoon							
			Engaging to platoon							, ,
			Enable platoon braking mode		Г	Provide			Provide platooning Provide capability commun	Provide system secure interaction with loations driver
			Enable platoon driving mode			autonomous movement capability				
			Enable platoon searching mode						Enable platoon En	Provide n
									driving mode	ortween trucks Selection: No or Autonom
		Provide secure communications			Provide ACC Processing Records Provide ACC Processing Records Provide Records Provide Records Provide ACC Provide	rovide Lane mo	Blind spot Provide Navigatio		Providing platoon Dr.	ocrypt messages Provides G
			Encrypt messages between trucks	L.	Capazines (Capazines	cap	abilities system capabilitie	stabilization		Provides wa
			Decrypt messages between trucks	Man Man	iantain speed and		Detect and notify if	Distribute the wheel	Engaging to platoon	Provide and displayment information information
			Provide communication according to local	standards and regulations	distance gap	➤ Detect Lanes	⇒any obstacles come close to the vehicle.	load in relation to the velocity and direction of the crosswind		standards and regulations
		Provide system interaction with driver			Avoid obstacles	Maintain and control distance to lanes			Disensing from platoon	
			Provide mode selection: Manual or Autono	omous	Automatically brake	Somme Willies			Enable platoon searching mode	
			Provides GUI for interaction		or accelerate				L	
									Enable platoon braking mode	

Name		Logical group	Туре	Connection's name	Connection type	Connected to the No	
		main group	System element		Information flow		RailCab
ACC M	lodule	acc group	System element		Information flow		
Brake c	control system	break group	System element		Information flow		energy spring and tilt
Brake c	control system	break group	System element		Information flow		management module
Hydraul	ilic actuator	break group	System element		Information flow		power F _{holding}
GPS re	eceiver	Communication	System element		Information flow		/ noong
on-boar	rd computer (Of	Communication	System element		Information flow		track- guidance module
Leading	g truck		environmental eleme	nt			•
					energy flow		F _{steering} hydraulic- undercarriage
Brake c	control system	break group	System element		energy flow		axis actuator frame
Hydraul	ilic actuator	break group	System element		energy flow		F holding displacement
Brakes		break group	System element		energy flow		↑ ¹ holding
Wheels	3	break group	System element		energy flow		wheels ddy-current information-
							distance sensor distance processing
							flange-rail information
					material flow		\\\.\.\.\.\.\.\.\.\.\.\.\.\.\.\.
Precipit	tations on road		environmental eleme	nt	material flow		F _{RailCab} ; informations ▼ (data requests, track data etc.)
Wheels	3	break group	System element		material flow		track track
							section
							control
					measurement inform	nations	Legend
							environment information flow r logical
Speedo	ometer	break group	System element		measurement inform	nations	element — energy flow group
Wheels	3	break group	System element		measurement inform	nations	system — material flow O> measurement informations
GPS an	ntenna	Communication	System element		measurement inform	nations	— element informations
GPS re	eceiver	Communication	System element		measurement inforn	nations	
			environmental eleme	nt			

	Screenshots from Carla					
	difefrent views: frond, side, 3d					

		we can use sequence diagram and state machine digram
		behavior specification by activities and/or states
		and/or states
		51 (8)



No	Object	Connection name	Connection type Connected to	
1	Folowing truck	Control signals	information flow Leading truck	
	Leading truck	•		
	Driver	Manual control->, platoon system's conditions<-,	energy, information	
	Environment	impact from nature	material	user
	Lane markup	car positioning	infrmation	Legend
	Cargo	F cargo	energy,	environment
	Service Company	technical data	information	destination de
	Folowing truck	abrasion	energy	Fearn
				cargo — information flow
				— energy flow — material flow
				disturbance relation
				Usul bance relation
				rain, snow, wind etc.
				informations
				(data requests,
				abrasion FRaiCab, track data etc.)
				set error
				rain, snow, wind etc. track track-section
				environment rain, show, wind etc. section contol
				Section Conto

No	Scenario name	Date	Code	Description	Solution	References	
	1						
		in the google	e docs document				A Application Scenario Drive onto next track section Drive onto next track section Drive onto next track section
							Description of the partial development task AS12: When the RailCab is
							driving on a track section, it is at some point notified that it approaches the end of the track section. Then, the RailCab must obtain the information, whether it
							may enter the next track section, from the corresponding section control. This information must be available to the RailCab before the RailCab reaches the
							point of the last safe brake. This point precedes the point of no return, beyond which it cannot be guaranteed that braking will safely stop the Rail Cab before it
							enters the next track section.
							Principle solution for AS12: The RailCab, when reaching the end of the
							track section, sends a request to enter the next track section to the section control responsible for the next track section. Then the section
							control replies, stating whether entering the track section is currently allowed or not. The reply is sent in time for the RailCab to receive it
							before it reaches the point of the last safe brake.
							current track next track section control section control
							RailCab 🦈 🌘
							NaliCab Page 1
							approaching end last safe point of next track section
							of track section brake no return reached
							Reference to Application Scenario Specific Cut-out of - Requirements
							- Requirements - Environment - Active Structure
							- Active Structure

id	License Number	Destination	Distance	Platoon Destination	Platoon Number	Max Platoon Size	Platoon Size	Assigned role
1	1	Dortmund	400	Dortmund	1	1	1	searching
	2	Dortmund	400	Dortmund	1	2	2	searching
	3	Dortmund	400	Dortmund	1	3	3	searching
3	3	Dortmund	400					Lead
2	5	Dortmund	400	Dortmund	1	2	1	Follower
		Dortmund	100	Hamburg	1	2	2	Searching
		Dantas	400	Dardmannd	4	0	4	F -U
4				Dortmund	1	2		Follower
5		Dortmund		Dortmund	1	3		Follower
6		Dortmund		Dortmund	1	3		Follower
7	7	Dortmund	400	Dortmund	1	3	3	searching
		Dortmund	400	Dortmund	1	2	3	Follower
		Dortmund	400	Dortmund				Lead
4	4							
5	5	Dortmund	100	Hamburg	1	2	1	Searching
6	6	Dortmund	100	Hamburg	1	2	3	Searching
7	7	Dortmund	100	Hamburg	1	2	3	Searching
8	8							

Assigned_Role	Assigned_Role_Id Route_Destination	Distance	Platoon_Destination	Platoon_Destination_Id	Platoon_Number	Max_Platoon_Size	Platoon_Size	Distance_to_platoon	Weather_condition	Truck_load	Truck_load_limit	Timeout
Searching	0 Dortmund	400	Dortmund	1	1	1	1	200	1	20	20	0
Searching	0 Dortmund	400	Dortmund	1	1	2	2	100	1	10	20	0
Searching	0 Dortmund	400	Dortmund	1	1	3	3	100	1	20	20	0
Lead	1 Dortmund	400	0	0	0	0	0	0	1	10	20	0
Follower	2 Dortmund	400	Dortmund	1	1	2	1	2	1	20	20	0
Searching	0 Dortmund	100	Hamburg	2	1	2	2	500	1	10	20	0
Follower	2 Dortmund	400	Dortmund	1	1	2	1	50	1	20	20	0
Follower	2 Dortmund	400	Dortmund	1	1	3	1	10	1	10	20	0
Follower	2 Dortmund	400	Dortmund	1	1	3	2	2	1	15	20	0
Searching	0 Dortmund	400	Dortmund	1	1	3	3	40	1	10	20	0
Follower	2 Dortmund	400	Dortmund	1	1	2	3	2	1	10	20	0
Lead	1 Dortmund	400	Dortmund	1	0	0	0	4	1	12	20	0
Searching	0 Dortmund	100	Hamburg	2	1	2	1	40	1	14	20	0
Searching	0 Dortmund	100	Hamburg	2	1	2	3	20	1	10	20	0
Searching	0 Dortmund	100	Hamburg	2	1	2	3	30	1	20	20	0
Searching	0 Dortmund	10	Duisburg	3	1	5	2	12	2	10	20	0
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	10	20	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	10	10	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	10	15	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	10	20	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	15	20	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	20	20	1
Lead	1 Dortmund	10	Duisburg	3	1	5	2	12	2	15	20	1

Assigned_Role_Id	Route_Destination_		Platoon_Destination_Id	Platoon_Number	Max_Platoon_Size	Platoon_Size		Weather_condition	Truck_load	Truck_load_limit	Timeout
0	1			1	1	1	200	1	20	20	0
0	1	400	1	1	2	2	100	1	10	20	0
0	1	400	1	1	3	3	100	1	20	20	0
1	1	400	0	0	0	0	0	1	10		0
2	1	400	1	1	2	1	2	1	20		0
0	1	100	2	1	2	2	500	1	10	20	0
2	1	400	1	1	2	1	50	1	20	20	0
2	1	400	1	1	3	1	10	1	10	20	0
2	1	400	1	1	3	2	2	1	15	20	0
0	1	400	1	1	3	3	40	1	10	20	0
2	1	400	1	1	2	3	2	1	10	20	0
1	1	400	1	0	0	0	4	1	12	20	0
0	1	100	2	1	2	1	40	1	14	20	0
0	1	100	2	1	2	3	20	1	10	20	0
0	1	100	2	1	2	3	30	1	20	20	0
0	1	10	3	1	5	2	12	2	10	20	0
1	1	10	3	1	5	2	12	2	10	20	1
1	1	10	3	1	5	2	12	2	10	10	1
1	1	10	3	1	5	2	12	2	10	15	1
1	1	10	3	1	5	2	12	2	10	20	1
1	1	10	3	1	5	2	12	2	15	20	1
1	1	10	3	1	5	2	12	2	20	20	1
1	1	10	3	1	5	2	12	2	15	20	1
0	1	10	3	1	5	2	12	2	10	20	0
0	1	10	3	1	5	2	12	2	10	10	0
0	1	10	3	1	5	2	12	2	10	15	0
0	1	10	3	1	5	2	12	2	10	20	0
0	1	10	3	1	5	2	12	2	15	20	0
0	1	10	3	1	5	2	12	2	20	20	0
0	1	10	3	1	5	2	12	2	15	20	0
1	1	10	1	1	5	2	12	2	20	10	1
1	1	10	1	1	5	2	12	2	15	10	1
1	1	10	1	1	5	2	22	2	20	10	1

License Number	Destination	Platoon Destination		Platoon Size	Assigned role
1	Dortmund	Dortmund	1	0	Lead
2	Dortmund	Dortmund	2	1	Follower
3	Dortmund	Dortmund	1	1	Searching
4	Dortmund	Dortmund	2	2	Searching
5	Dortmund	Dortmund	3	3	Searching
6	Dortmund	Hamburg	2	1	Searching
7	Dortmund	Dortmund	2	3	Searching

License Number	Destination	Platoon Destination		Platoon Size	Assigned role
2	Dortmund	Dortmund	2	1	Follower
3	Dortmund	Dortmund	1	1	Searching
2	Dortmund	Dortmund	2	1	Follower
1	Dortmund				Lead
4	Dortmund	Dortmund	2	2	Searching

License Number		Platoon Destination			Assigned role
7	Dortmund	Dortmund	2	1	Follower

License Number		Platoon Destination			
8	Dortmund	Dortmund	2	2	2

			Assigned role		Assigned role
		Platoon Max Size			
	Assigned role		Platoon Destination		
		Assigned role		Assigned role	
				Assigned	1
	Tr			role	
1	Platoon Max Size	Platoon Destination		Lead	
2	Platoon Destination	Destination	Platoon Size	Following	
3	Destination	Platoon Max Size		Following	

Assigned Assigned Platoon Assigned role Size role

		Tree		Assigned role
1	Platoon Max Size	Platoon Destination		Lead
2	Platoon Destination	Destination	Platoon Size	Following
3	Destination	Platoon Max Size		Following

Assig	ned role
Following	Lead
2	1
	•

Final Prediction
Following

Final Prediction	
Following	Ī

License Number	Final Prediction
5	Searching
6	Following

License Number	Platoon Max Size
5	Searching
6	Following
6	Following

nse nber		Platoon Destination			Assigned role
5	Dortmund	Dortmund	3	3	Searching
6	Dortmund	Hamburg	2	1	Searching
ŝ	Dortmund	Hamburg	2	1	Searching

License Number	Destination	Platoon Destination		Platoon Size	Assigned role
1	Dortmund	Dortmund	1	0	Lead
2	Dortmund	Dortmund	2	1	Follower
3	Dortmund	Dortmund	1	1	Searching
4	Dortmund	Dortmund	2	2	Searching
5	Dortmund	Dortmund	3	3	Searching
6	Dortmund	Hamburg	2	1	Searching
7	Dortmund	Dortmund	?	3	Searching

License Number	Destination	Platoon Destination	Platoon Max Size	Platoon Size	Assigned role
1	Dortmund	Dortmund	1	0	Lead
2	Dortmund	Dortmund	2	1	Follower
3	Dortmund	Dortmund	1	1	Searching
4	Dortmund	Dortmund	2	2	Searching
5	Dortmund	Dortmund	3	3	Searching
6	Dortmund	Hamburg	2	1	Searching
7	Dortmund	Dortmund	2	3	Searching

Proximity Matrix

	<u> </u>								
	1	2	3	4	5	6	7		
1		2	1	1	1	1	1		
2	2		1	2	1	1	5		
3	1	1		1	1	1	1		
4	1	2	1		1	1	0		
5	1	1	1	1		3	0		
6	1	1	1	1	3		0		
7	1	5	1	0	0	0			

Proximity Matrix

1	2	3	4	5	6	7

1		1				
2	1		1			1
3						
4		1				
5					1	
6				1		
7		1				

License Number		Platoon Destination			Assigned role
5	Dortmund	Dortmund	3	3	Searching
6	Dortmund	Hamburg	2	1	Searching

Weighted proximity Matrix

	1	2	3	4	5	6	7
1		0.3	0.1	0.1	0.1	0.1	0.1
2	0.3		0.1	0.3	0.1	0.1	8.0
3	0.1	0.1		0.1	0.1	0.1	0.1
4	0.1	0.3	0.2		0.1	0.1	0
5	0.1	0.1	0.1	0.1		0.5	0
6	0.1	0.1	0.1	0.1	0.5		0
7	0.1	8.0	0.1	0	0	0	

License Number		Platoon Destination			Assigned role
8	Dortmund	Dortmund	?	3	?

License Number		Platoon Destination			Assigned role
8	Dortmund	Dortmund	?	3	Searching

License Number Destination	Platoon Destination			Assigned role
8 Dortmund	Dortmund	?	3	Following

License Number	Destination	Platoon Destination			Assigned role
8	Dortmund	Dortmund	?	3	Lead