

MPC-L - Test Specification Report

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1. MPC_L Setup

Test Details

Releases	Current (2019b)
Description	This test is aimed to try to find a feasible and stable configuration for the MPC when it comes to slow s-speed scenarios

Parameter Sets

Workspace Variable	Override Value	Source	Model Elements
Parameter Set 1			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none">• Dynamic_obstacle_avoidance_L/Subsystem/• Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function• Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1• Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2• Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			m/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	10	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 2			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem-

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> m/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 5 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
▪ p	8	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 3			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 0 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	10	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 4 (Active)			

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
▪ Ts	0.005	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	10	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 5			
▪ Ts	0.02	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	10	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 6			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<p>em/Calculating deviation from reference/To Workspace2</p> <ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 0 0]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	10	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 7			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			m/Subsystem/MATLAB Function
▪ WOV	[30 30 0 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	8	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 8			
▪ Ts	0.005	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem-

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> m/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
▪ p	8	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 9			
▪ Ts	0.005	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[10 10 10 10]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	8	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 10			

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	15	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 11			
▪ Ts	0.005	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/To Workspace2 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 8 30]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	15	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector
Parameter Set 12			
▪ Ts	0.01	base workspace	<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/ Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/MATLAB Function Dynamic_obstacle_avoidance_L/Subsystem/Calculating deviation from reference/Sampling/CounterFree-Running1 Dynamic_obstacle_avoidance_L/Subsystem/

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<p>em/Calculating deviation from reference/To Workspace2</p> <ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace1 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace4 Dynamic_obstacle_avoidance_L/Subsystem/Data to Workspace/To Workspace5 Dynamic_obstacle_avoidance_L/Subsystem/Dynamic Model/C_r Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/Constant5 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/MATLAB Function1 Dynamic_obstacle_avoidance_L/Subsystem/Obstacle detector/To Workspace Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/ Dynamic_obstacle_avoidance_L/Subsystem/Plant generator/Plant Model Generator

1. MPC_L Setup

Workspace Variable	Override Value	Source	Model Elements
			<ul style="list-style-type: none"> Dynamic_obstacle_avoidance_L/Subsystem/Sample map/CounterFree-Running Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/MATLAB Function
▪ WOV	[30 30 0 0]	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Subsystem/Adaptive MPC Controller/Constant
▪ p	15	base workspace	Dynamic_obstacle_avoidance_L/Subsystem/Sample map/Selector

Iterations

Name	Details						
Iteration1	<table> <tr> <th>Parameter Name</th><th>Value</th></tr> <tr> <td>External Inputs</td><td>Parameter Set 1</td></tr> <tr> <td>Parameter Set</td><td>Parameter Set 4</td></tr> </table>	Parameter Name	Value	External Inputs	Parameter Set 1	Parameter Set	Parameter Set 4
Parameter Name	Value						
External Inputs	Parameter Set 1						
Parameter Set	Parameter Set 4						
Iteration2	<table> <tr> <th>Parameter Name</th><th>Value</th></tr> <tr> <td>External Inputs</td><td>Parameter Set 2</td></tr> <tr> <td>Parameter Set</td><td>Parameter Set 4</td></tr> </table>	Parameter Name	Value	External Inputs	Parameter Set 2	Parameter Set	Parameter Set 4
Parameter Name	Value						
External Inputs	Parameter Set 2						
Parameter Set	Parameter Set 4						

1. MPC_L Setup

Name	Details	
Iteration3		
	Parameter Name	Value
	External Inputs	Parameter Set 3
	Parameter Set	Parameter Set 4
Iteration4		
	Parameter Name	Value
	External Inputs	Parameter Set 4
	Parameter Set	Parameter Set 4
Iteration5		
	Parameter Name	Value
	External Inputs	Parameter Set 5
	Parameter Set	Parameter Set 4
Iteration6		
	Parameter Name	Value
	External Inputs	Parameter Set 6
	Parameter Set	Parameter Set 4
Iteration7		
	Parameter Name	Value
	External Inputs	Parameter Set 7

1. MPC_L Setup

Name	Details	
	Parameter Name	Value
	Parameter Set	Parameter Set 4
Iteration8	Parameter Name	Value
	External Inputs	Parameter Set 8
	Parameter Set	Parameter Set 4
Iteration9	Parameter Name	Value
	External Inputs	Parameter Set 9
	Parameter Set	Parameter Set 4
Iteration10	Parameter Name	Value
	External Inputs	Parameter Set 10
	Parameter Set	Parameter Set 4
Iteration11	Parameter Name	Value
	External Inputs	Parameter Set 11
	Parameter Set	Parameter Set 4

1. MPC_L Setup

Name	Details	
Iteration12		
	Parameter Name	Value
	External Inputs	Parameter Set 12
	Parameter Set	Parameter Set 4