

Test Specification Report

CoDeAs Team 2

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Table of Contents

1. controllerTest	2
1.1. No Charge	2
1.1.1. Scenario 10	2
1.2. Dead	5
1.2.1. Scenario9	5
1.3. Combined	9
1.3.1. Scenario 1	9
1.3.2. Scenario2	11
1.3.3. Scenario3	14
1.3.4. Scenario4	16
1.4. Regenerative Braking	18
1.4.1. Scenario5	18
1.4.2. Scenario6	20
1.4.3. Scenario7	22
1.4.4. Scenario8	25
1.5. Electrical Drive	27
1.5.1. Scenario11	27

1. controllerTest

Test File Options

Close open figures	true
Store MATLAB figures	false
Generate report	false

1.1. No Charge

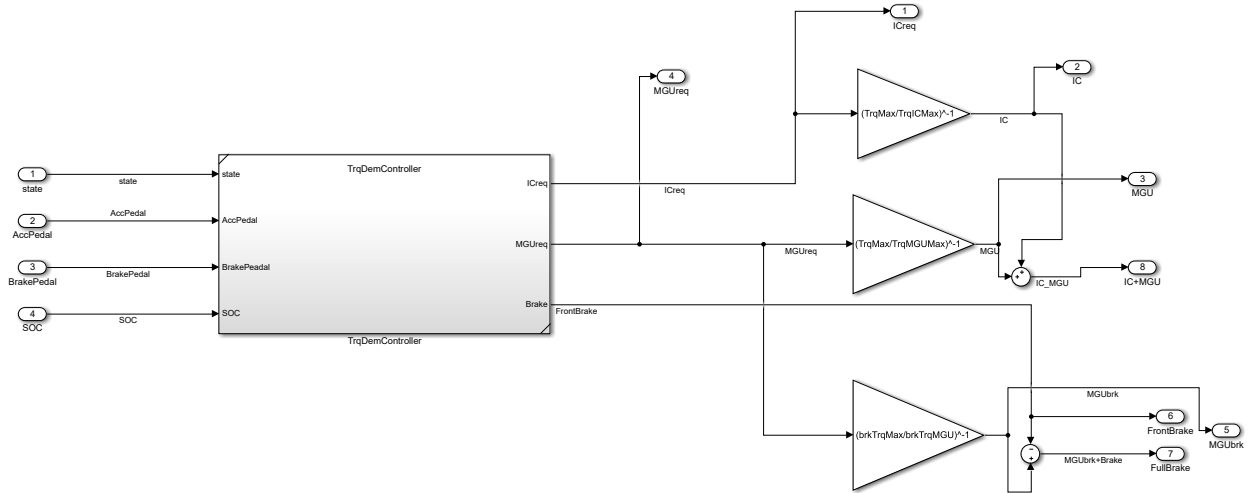
1.1.1. Scenario 10

Test Details

Description	State = no charge AccPedal = exponential growth and decay over time BrakePedal = 0 SOC = between 0 and 0.1
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs10.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs10.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			

Name	Source	Port Index	Plot Index
• ICreq	controllerModel/TrqDemController	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Logical and Temporal Assessments

Assessments

Enabled	Name	Definition	Requirements
True	Assessment1	At any point of time, ICreq <= AccPedal ICreq <= 1 must be true	

Symbols

Symbol	Scope	Metadata	
ICreq	Signal	Name	ICreq
		Path	controllerModel/TrqDemController
		Port Index	1
		Field/Element	
AccPedal	Signal		
		Name	AccPedal

Symbol	Scope	Metadata	
		Path	controllerModel/AccPedal
		Port Index	1
		Field/Element	

1.2. Dead

Test Details

Description	Dead case suite of tests
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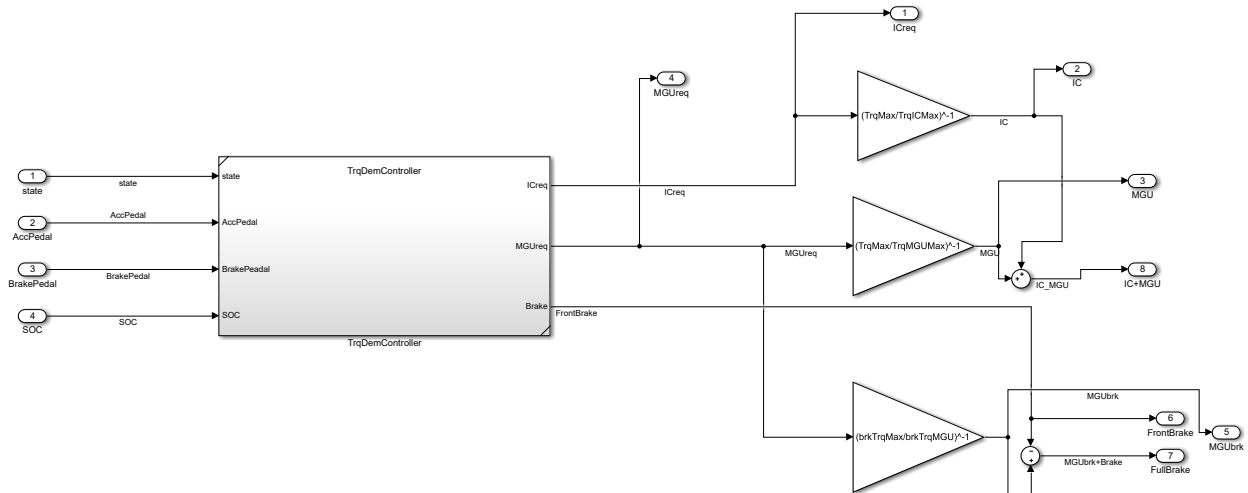
1.2.1. Scenario9

Test Details

Description	<p>Scenario 9:</p> <p>State = dead</p> <p>AccPedal = exp growth and decay</p> <p>BrakePedal = 0</p> <p>SOC = from 0.1 to 0</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs9.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs9.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			

Name	Source	Port Index	Plot Index
• ICreq	controllerModel/TrqDemController	1	
• MGUreq	controllerModel/TrqDemController	2	
• IC_MGU	controllerModel/Sum	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Dead_baseline.mat (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• IC_MGU (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• ICreq (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
• MGUreq (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• ICreq (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• IC (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• MGU (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• MGUreq (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• MGUbrk (Active)	9.99 9999 9999 9999	9.99 9999 9999 9999	0	0

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
	95e-07	95e-07		
• FrontBrake (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0
• MGUbrk+Brake (Active)	9.99 9999 9999 9999 95e-07	9.99 9999 9999 9999 95e-07	0	0

1.3. Combined

Test Details

Description	Combined case suite of tests
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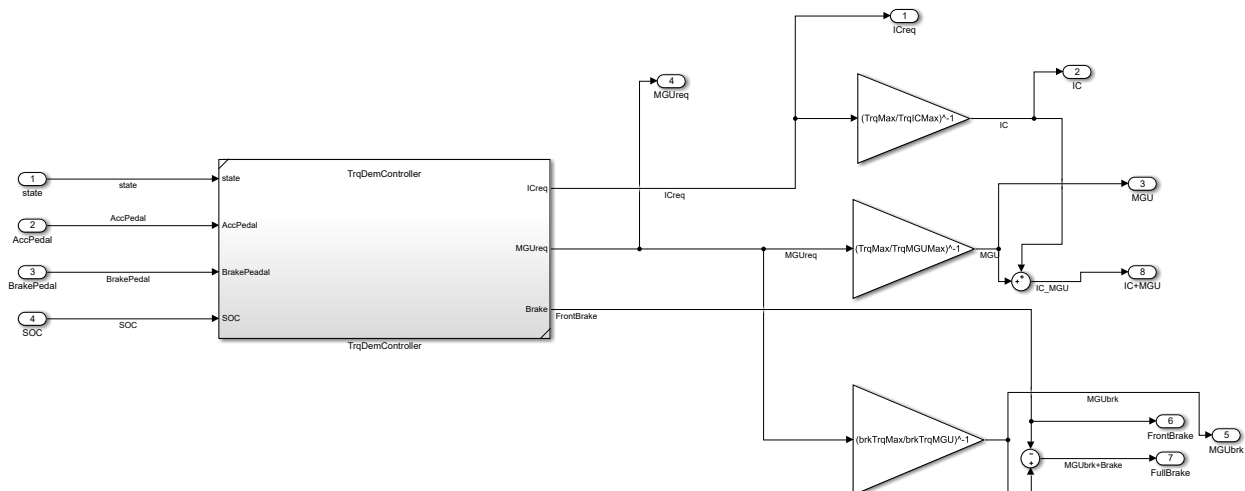
1.3.1. Scenario 1

Test Details

Description	<p>Scenario 1:</p> <p>State = combined</p> <p>AccPedal = pulse signal of amplitude 0.5, width 0.5 and period 10 seconds</p> <p>BrakePedal = 0</p>
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A horizontal bar chart showing a single bar with a value of 50%. The bar is light blue and is positioned against a white background. The text 'SOC = 50%' is displayed to the right of the bar.

Model Name: controllerModel



Simulation Mode	Model Settings
Releases	Current

Name	File Path	Status
controllerInputs1.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs1.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• IC_MGU	controllerModel/Sum	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Combined_Baseline1.mat (Active)	1.00 0000 0000 0000 01e- 05	0	0.001	0.001
• IC_MGU (Active)	1.00 0000 0000 0000 01e- 05	0.00 1	0.001	0.001

1.3.2. Scenario2

Test Details

Description	Scenario 2:
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1. controllerTest

State = combined

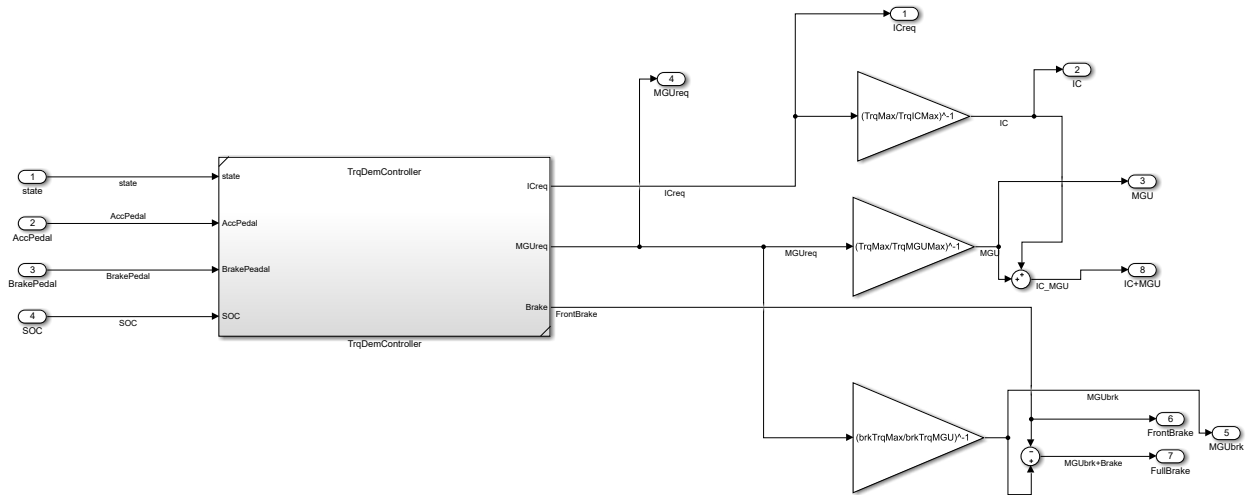
AccPedal = pulse signal of amplitude 0.1, width 0.5 and period 10 seconds

BrakePedal = 0

SOC = 50%

System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs2.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-	Successfully mapped inputs.

Name	File Path	Status
	controller\Test\ControllerTest\testScenarios\controllerInputs2.mat	

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• IC_MGU	controllerModel/Sum	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
------------------------	--------------------------------

Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Combined_Baseline2.mat (Active)	1.0000000001e-05	0	0.001	0.001
• IC_MGU (Active)	1.0000000001e-05	0	0.001	0.001

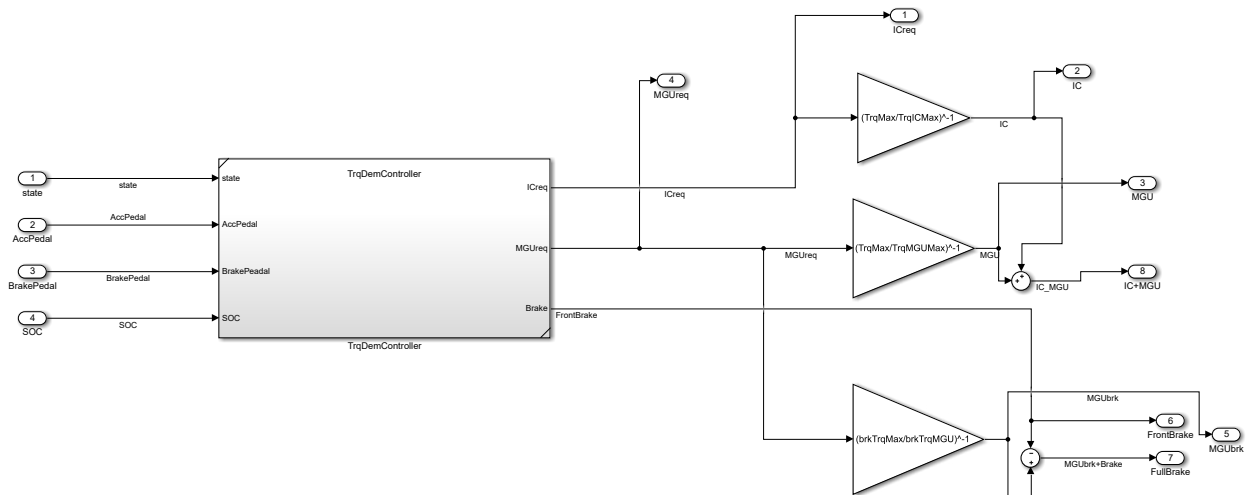
1.3.3. Scenario3

Test Details

Description	<p>Scenario 3:</p> <p>State = combined</p> <p>AccPedal = pulse signal of amplitude 0.9, width 0.5 and period 10 seconds</p> <p>BrakePedal = 0</p> <p>SOC = 50%</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs3.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs3.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• IC_MGU	controllerModel/Sum	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
------------------------	--------------------------------

Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Combined_Baseline3.mat (Active)	1.0000000001e-05	0	0.001	0.001
• IC_MGU (Active)	1.0000000000000000	0	0.001	0.001

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
	01e-05			

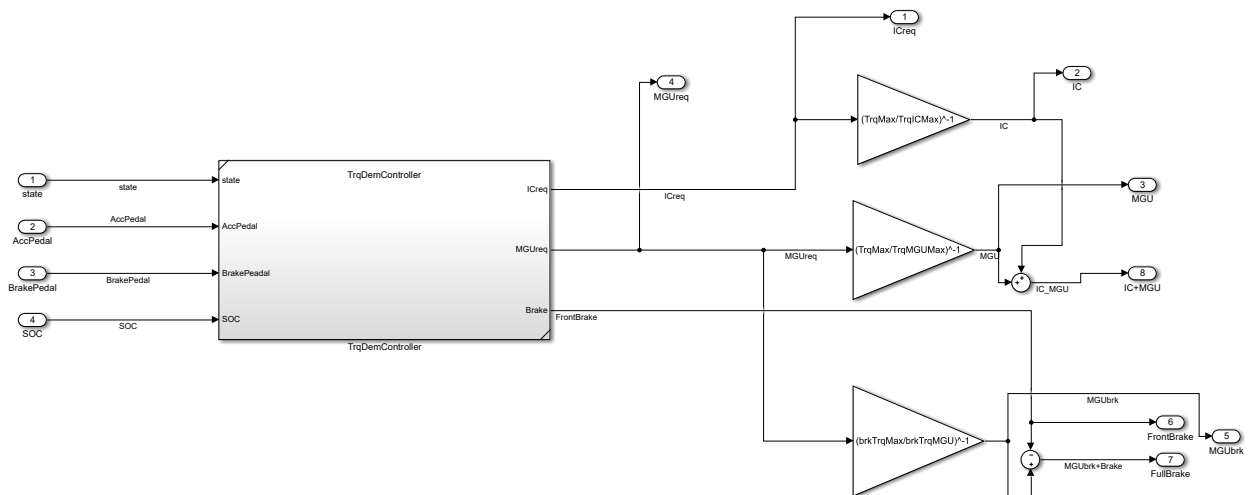
1.3.4. Scenario4

Test Details

Description	<p>Scenario 4:</p> <p>State = combined</p> <p>AccPedal = exponential growth and decay over time</p> <p>BrakePedal = 0</p> <p>SOC = 50%</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs4.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs4.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• IC_MGU	controllerModel/Sum	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
------------------------	--------------------------------

Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Combined_Baseline4.mat (Active)	1.00 0000 0000 0000	0	0.001	0.001

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
	01e-05			
<ul style="list-style-type: none"> IC_MGU (Active) 	1.0000000001e-05	0	0.001	0.001

1.4. Regenerative Braking

Test Details

Description	Regenerative Braking case suite of tests
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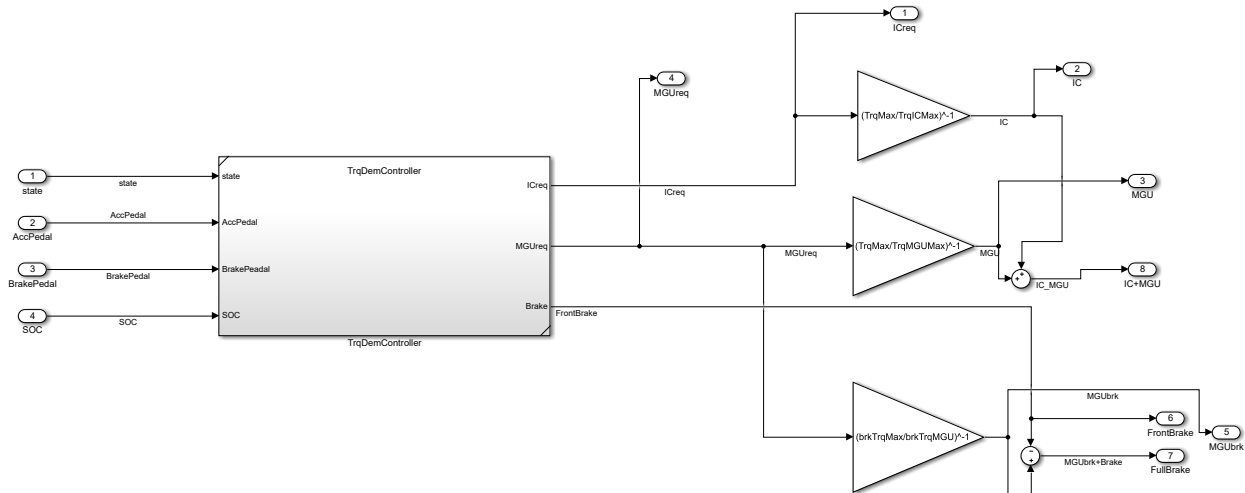
1.4.1. Scenario5

Test Details

Description	<p>Scenario 5:</p> <p>State = regenerative braking</p> <p>AccPedal = 0</p> <p>BrakePedal = pulse signal of amplitude 0.5, width 0.5 and period 10 seconds.</p> <p>SOC = 50%</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs5.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs5.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			

Name	Source	Port Index	Plot Index
• MGUbrk+Brake	controllerModel/Sum1	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Regen_Baseline1.mat (Active)	1.0000000001e-05	0	0.001	0.001
• MGUbrk+Brake (Active)	1.0000000001e-05	0	0.001	0.001

1.4.2. Scenario6

Test Details

Description	<p>Scenario 6:</p> <p>State = regenerative braking</p> <p>AccPedal = 0</p>
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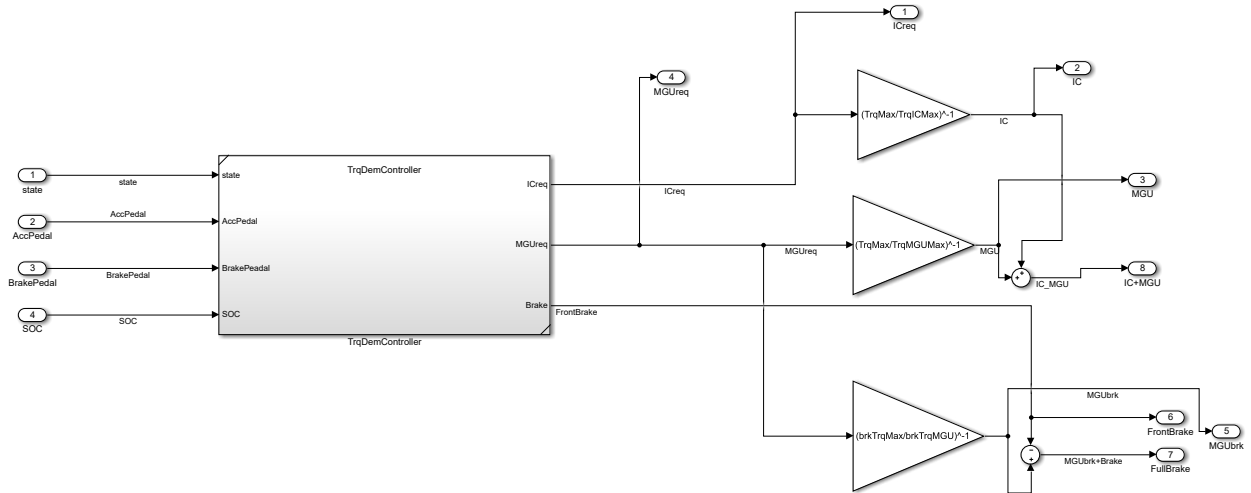
1. controllerTest

BrakePedal = pulse signal of amplitude 0.1, width 0.5 and period 10 seconds.

SOC = 50%

System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs6.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs6.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• MGUbrk+Brake	controllerModel/Sum1	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Regen_Baseline2.mat (Active)	1.00 0000 0000 0000 01e- 05	0	0.001	0.001
• MGUbrk+Brake (Active)	1.00 0000 0000 0000 01e- 05	0	0.001	0.001

1.4.3. Scenario7

Test Details

Description	Scenario 7:
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1. controllerTest

State = regenerative braking

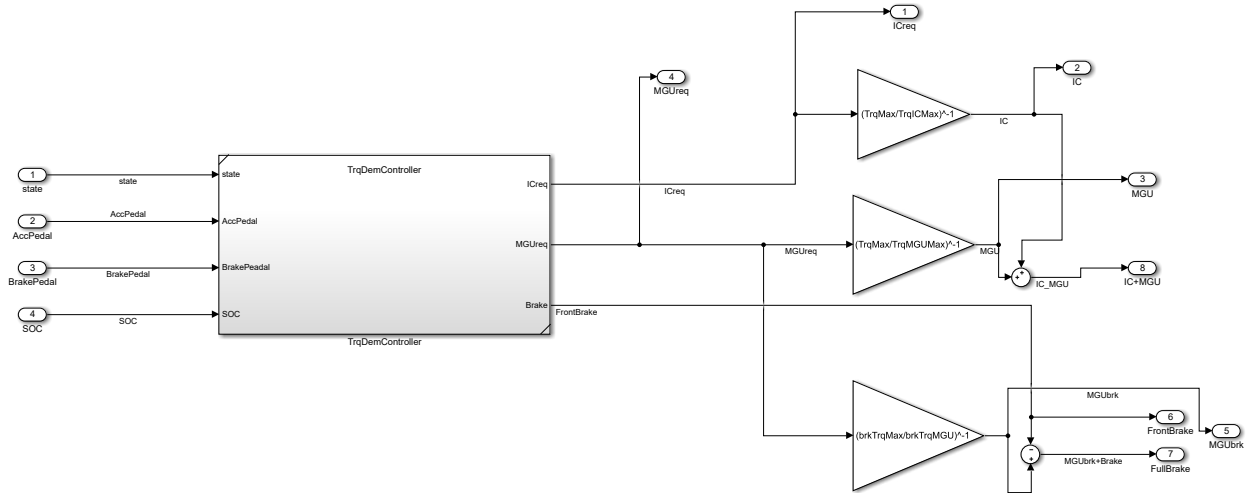
AccPedal = 0

BrakePedal = pulse signal of amplitude 0.9, width 0.5 and period 10 seconds.

SOC = 100%

System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs7.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-	Successfully mapped inputs.

Name	File Path	Status
	controller\Test\ControllerTest\testScenarios\controllerInputs7.mat	

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• MGUbrk+Brake	controllerModel/Sum1	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Regen_Baseline3.mat (Active)	1.0000000001e-05	0	0.001	0.001
• MGUbrk+Brake (Active)	1.0000000001e-05	0	0.001	0.001

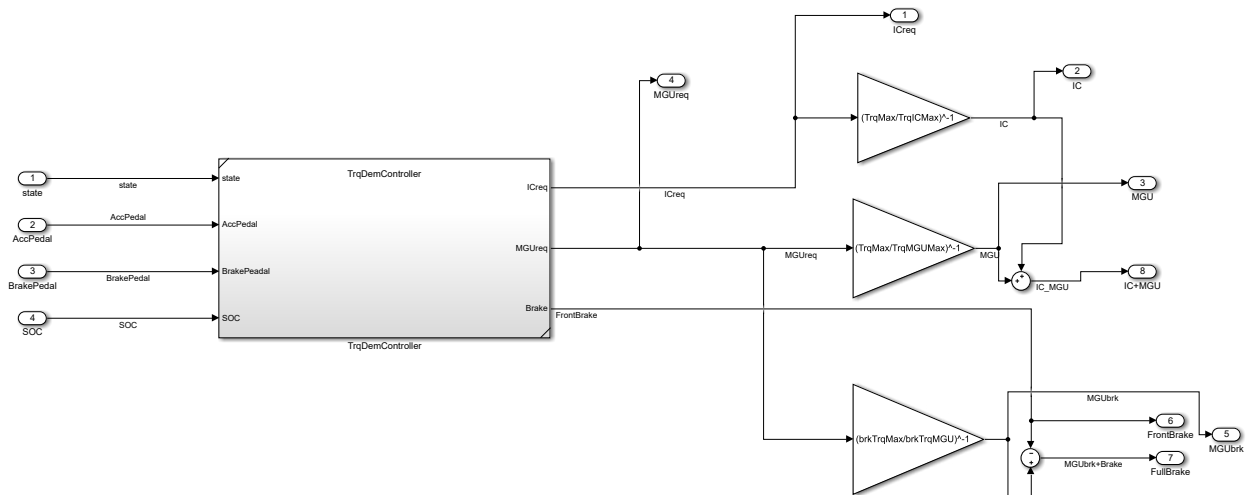
1.4.4. Scenario8

Test Details

Description	<p>Scenario 8:</p> <p>State = regenerative braking</p> <p>AccPedal = 0</p> <p>BrakePedal = exponential growth and decay over time</p> <p>SOC = 50%</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs8.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs8.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			
• MGUbrk+Brake	controllerModel/Sum1	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Baseline Criteria

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
Regen_Baseline4.mat (Active)	1.0000000001e-05	0	0.001	0.001
• MGUbrk+Brake (Active)	1.0000000000000000	0	0.001	0.001

Signal Name	Abs Tol	Rel Tol	Leading Tol	Lagging Tol
	01e-05			

1.5. Electrical Drive

Test Details

Description	Electrical Drive case suite of tests
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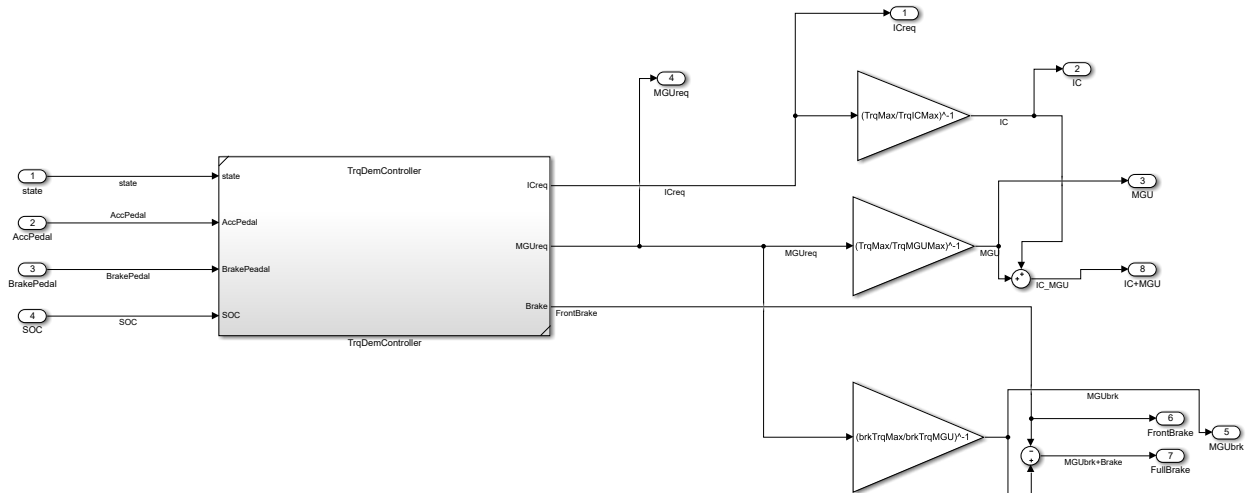
1.5.1. Scenario11

Test Details

Description	<p>Scenario 11:</p> <p>state = electrical drive</p> <p>AccPedal = exponential growth and decay</p> <p>BrakePedal = 0</p> <p>SOC = from 70% to 15%</p>
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System Under Test

Model Name: controllerModel



Simulation Settings Overrides

Simulation Mode	Model Settings
Releases	Current

External Inputs

Name	File Path	Status
controllerInputs11.mat (Active)	C:\Users\mordi\Desktop\Materiale Università\Compliance\hybrid-controller\Hybrid-controller\Test\ControllerTest\testScenarios\controllerInputs11.mat	Successfully mapped inputs.

Logged Signals

Name	Source	Port Index	Plot Index
Signal Set 1			

Name	Source	Port Index	Plot Index
• MGUreq	controllerModel/TrqDemController	2	
• ICreq	controllerModel/TrqDemController	1	
• MGUbrk+Brake	controllerModel/Sum1	1	
• SOC	controllerModel/SOC	1	

Configuration Settings Overrides

Configuration settings	Do not override model settings
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Logical and Temporal Assessments

Assessments

Enabled	Name	Definition	Requirements
True	Assessment1	At any point of time, SOC >= 15 & Brake-Pedal == 0 & (MGUreq <= AccPedal MGUreq <= 1) must be true	

Symbols

Symbol	Scope	Metadata	
SOC	Signal		
		Name	SOC
		Path	controllerModel/SOC

Symbol	Scope	Metadata								
		<table><tr><td>Port Index</td><td>1</td></tr><tr><td>Field/Element</td><td></td></tr></table>	Port Index	1	Field/Element					
Port Index	1									
Field/Element										
BrakePedal	Signal	<table><tr><td>Name</td><td>BrakePedal</td></tr><tr><td>Path</td><td>controllerModel/BrakePedal</td></tr><tr><td>Port Index</td><td>1</td></tr><tr><td>Field/Element</td><td></td></tr></table>	Name	BrakePedal	Path	controllerModel/BrakePedal	Port Index	1	Field/Element	
Name	BrakePedal									
Path	controllerModel/BrakePedal									
Port Index	1									
Field/Element										
MGUreq	Signal	<table><tr><td>Name</td><td>MGUreq</td></tr><tr><td>Path</td><td>controllerModel/TrqDemController</td></tr><tr><td>Port Index</td><td>2</td></tr><tr><td>Field/Element</td><td></td></tr></table>	Name	MGUreq	Path	controllerModel/TrqDemController	Port Index	2	Field/Element	
Name	MGUreq									
Path	controllerModel/TrqDemController									
Port Index	2									
Field/Element										
AccPedal	Signal	<table><tr><td>Name</td><td>AccPedal</td></tr><tr><td>Path</td><td>controllerModel/AccPedal</td></tr></table>	Name	AccPedal	Path	controllerModel/AccPedal				
Name	AccPedal									
Path	controllerModel/AccPedal									

Symbol	Scope	Metadata	
		Port Index	1
		Field/Element	