EXCEEDS THE LIMIT!!!
Since it exceeds the maximum number of model elements to be processed, the visualization result may be incomplete.

ElectricVehicleDefinitions

«part def» E_Vehicle
attributes
color
currentBatteryLife:>ISQThermodynamics::energy
mass:>ISQBase::mass
maxBatteryLife:>ISQThermodynamics::energy
maxMass:>ISQBase::mass
requiredBatteryPower:>ISQThermodynamics::energy

«part def» Transmission
attributes
mass:>ISQBase::mass

«part def» AxleAssembly

@Mechanical Components

«part def» Lugbolt
attributes
mass:>ISQBase::mass
tighteningTorque:>ISQMechanics::torque

«part def» Battery
attributes
capacity:>ISQThermodynamics::energy
mass:>ISQBase::mass

@Electric Components

@Sensor Definitions

«port def» DriveIF
parameters
in driveTorque:>ISQMechanics::torque
attributes
ConnectionLag:>ISQBase::duration

«port def» BatteryHubIF
parameters
out wattage:>ISQElectromagnetism::electricPower
attributes
ConnectionLag:>ISQBase::duration

@Module Definitions

«interface def» ComputedPowerSupply

«interface def» motorMovement

«interface def» SensorHandle

«interface def» Forward

«interface def» ActAuto

«interface def» ActManual

«interface def» ActRemote

«interface def» controlMotor

@INTERFACE DEFINITIONS

@Electric Vehicle Initial Draft.

@PART DEFINITIONS

@Modules are used to ensure added functionality, like 5G, etc that are not sensors, but provide better computation ability.

@Defining the Autopilot Module

@PORT DEFINITIONS

«part def» Axle
attributes
mass:>ISQBase::mass

«part def» Motor
attributes
mass:>ISQBase::mass
rating:>ISQMechanics::power

«part def» RemoteDrivingModule
attributes
Lag

«interface def» Mounting
doc
The definition of the interface for mounting a Wheel to an Axle.

«part def» Wheel
attributes
mass:>ISQBase::mass

«port» leftMountingPoint: AxleMountIF

«port» rightMountingPoint: AxleMountIF

«port» MotorHub: MotorHubIF

«part» sensors: Sensor

«part» c5g: connection_5G

«part» cb: connection_bluetooth

«part» cw: connection_wifi

«part» ui: UI

«part» cpu: CPU

«part» controller: Controller

«part» remote: RemoteDevices

«port» axleMount: AxleMountIF
parameters
inout *transferredTorque:>ISQMechanics::torque

«part def» AutonomousDrivingModule
attributes
sensorTypes

«part def» DriverDrivingModule
attributes
Lag

«port def» AxleMountIF
parameters
inout transferredTorque:>ISQMechanics::torque

«port def» MotorHubIF
parameters
inout wattage:>ISQElectromagnetism::electricPower
attributes
ConnectionLag:>ISQBase::duration

«part def» connection_5G

«part def» connection_bluetooth

«part def» connection_wifi

«part» module: Module

«part» ui: UI

«part» gpu: GPU

«part» cpu: CPU

«part» ui: UI

«part» controller: Controller

«part» gps: GPS

«part» cpu: CPU

«part» controller: Controller

«part» human: HumanDrivingDevices

«part def» RemoteDevices

«port» hub: WheelHubIF
parameters
in *appliedTorque:>ISQMechanics::torque

«port» hub: WheelHubIF

«part def» Camera
attributes
fieldOfView
frequency:>ISQSpaceTime::frequency
pixelation
rating:>ISQMechanics::power

«part def» Lidar
attributes
beamDivergence
multiEchoCepacity
rating:>ISQMechanics::power
sourceType
wavelength:>ISQBase::length

«part» sensors: Sensor

«part def» Radar
attributes
antennaSize
freq:>ISQSpaceTime::frequency
rating:>ISQMechanics::power
transmitterPower:>rating

«part def» Speedometer
attributes
frequency:>ISQSpaceTime::frequency
rating:>ISQMechanics::power
tireDiameter

«part def» Microphone
attributes
frequency:>ISQSpaceTime::frequency
rating:>ISQMechanics::power

«part def» Module
attributes
BUS_type
SecurityProtocol
count
input

«part def» UI
attributes
rating:>ISQMechanics::power

«part def» GPS
attributes
accuracy
antenna
augmentationAlgorithms
range
rating:>ISQMechanics::power
satelliteCount

«part def» GPU
attributes
ProcessorClockRate
ProcessorComputePotential

«part def» CPU
attributes
ProcessorClockRate
ProcessorComputePotential

«part def» Controller
attributes
AcceleratorValue
BrakeValue
Mode
TurnAngle

«part def» HumanDrivingDevices

«part def» Sensor
attributes
mass:>ISQBase::mass
output:>ISQElectromagnetism::voltage

«port» communication: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» output: ComputeCommunicationIF

«port» read: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» communication: ComputeCommunicationIF

«port» read: ComputeWithVariableIF

«port» write: ComputeWithVariableIF

«port» processor
attributes
computationSpeed
memory
rating:>ISQMechanics::power

«port» communication: ComputeCommunicationIF

«port» read: ComputeWithVariableIF

«port» inputCommunication: ComputeCommunicationIF

«port» write: ComputeWithVariableIF

«port» human: ManualControlIF

«port» remote: RemoteControlIF

«port» manualcontrol: ManualControlIF

«port» remotecontrol: RemoteControlIF

«port» input: SensorReadIF

«port def» SensorReadIF
parameters
out voltage:>ISQElectromagnetism::voltage
attributes
ConnectionLag:>ISQBase::duration
count
outType

«port def» ComputeCommunicationIF
parameters
inout data
inout dataRate
inout dataType
attributes
ConnectionLag:>ISQBase::duration

«port def» ComputeWithVariableIF
parameters
inout voltage:>ISQElectromagnetism::voltage
attributes
ConnectionLag:>ISQBase::duration

«port def» ManualControlIF
parameters
inout accelerator:>ISQMechanics::force
inout brake:>ISQMechanics::force
inout turn:>SI::degree
attributes
ConnectionLag:>ISQBase::duration

«port def» RemoteControlIF
parameters
out accelerator:>ISQMechanics::force
out brake:>ISQMechanics::force
out signalStrength:>ISQMechanics::power
out turn:>SI::degree
attributes
ConnectionLag:>ISQBase::duration

«port def» WheelHubIF
parameters
in appliedTorque:>ISQMechanics::torque