



Efficient Development of Automotive Embedded Systems by Renesas, OpenSynergy, iSYSTEM and INCHRON

Demonstrator Setup



Sensor Camera Image Processing (ASIL-B)









Central Controller

Sensor Data Fusion (ASIL-D) Body Functions (ASIL-B)





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Sensor Radar Radar Processing (ASIL-B) Crash Detection (ASIL-D)









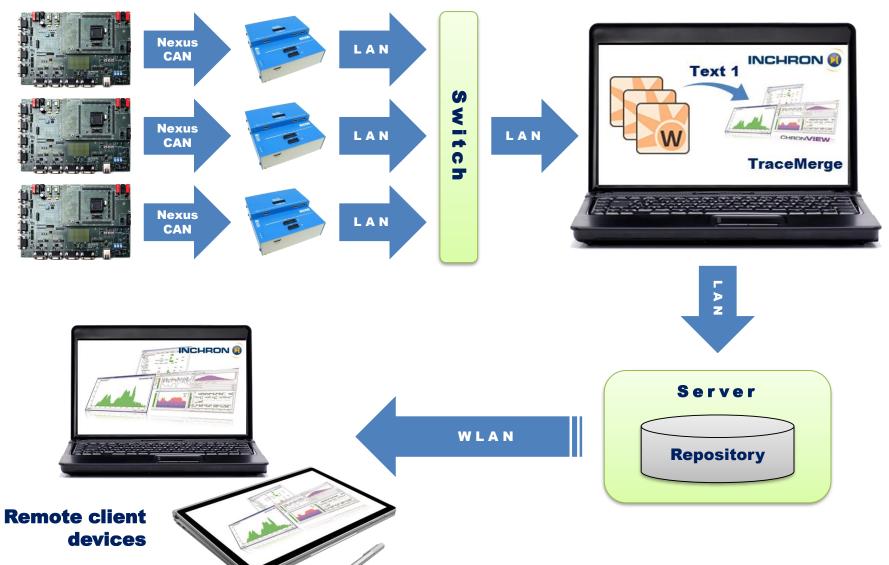




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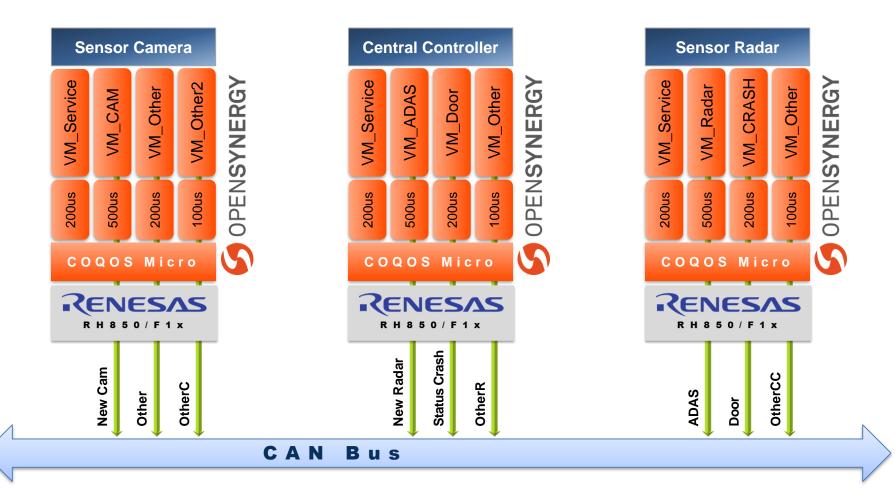
Data flow





VM and CAN Setup





Demonstrator Setup





Enhance the capabilities of your existing trace and debug tool



Reliable decisions

Function mapping
Execution order
Partitioning
Activation period
Priority
Start offset
Core affinity
Resource sharing



Intuitive trace visualization

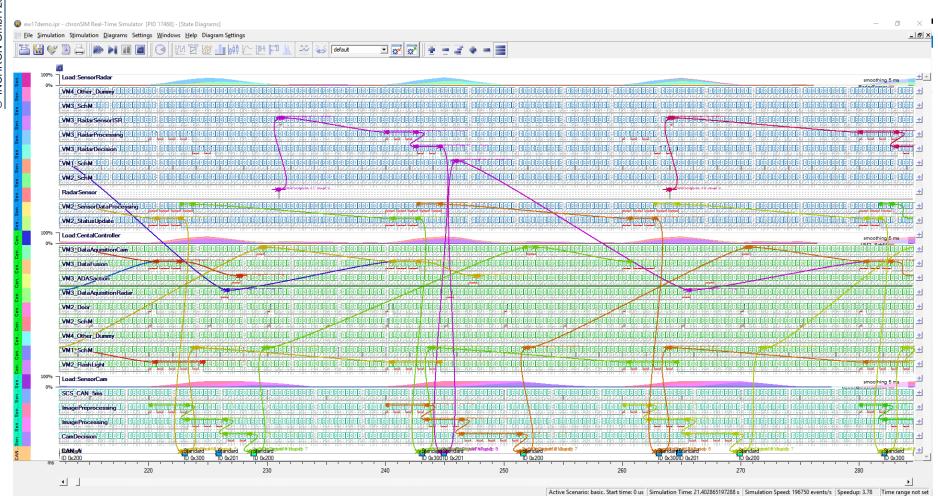
RTOS states
Function nesting
Events
Data values
Rate changes
Data flows
Stack consumption

Efficient analysis and diagnosis

CPU load
Net execution time
Response time
Jitter
End-to-end latency
Data age / loss / reuse
Blocking time

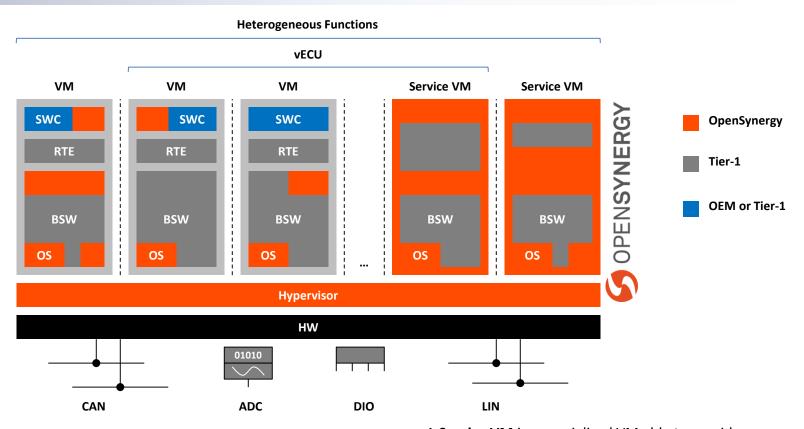
Combined Trace with Event chains





Overview COQOS Micro

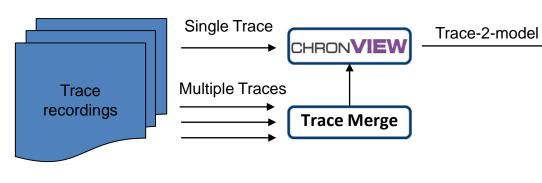




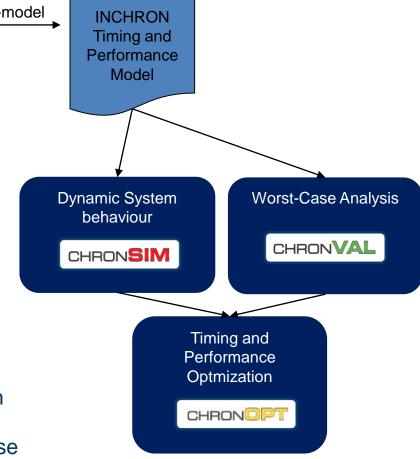
- A VM (Virtual Machine) is a software container running on top of the separation kernel. A VM consists of a single OS and user software. 3rd-party BSW, RTE and SWC may be part of a VM to provide system functions.
- The Hypervisor (separation kernel) is responsible for the scheduling of the VMs and for the software containment (freedom from interference – ISO 26262).

- A Service VM is a specialized VM able to provide basic functionality to VMs (shared access to I/O as an example) as an intra-ECU service.
- The COQOS Micro software platform supports the clustering of VMs to enable the concept of vECU.
 A vECU is able to act as a standard ECU (diagnostics as an example) at the vehicle system level.





- Enlarge test coverage
- Investigate new scenarios
- Detect performance bottlenecks
- Understand dynamic system behavior
- Follow event chains through complete system
- Visualize all information on the same time base



Measurement - Simulation - Validation



