ETAS VECU-BUILDER V1.8

User Guide

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VECU-BUILDER V1.8 I User Guide R11 EN I10.2024

Contents

1 Introduction

In this chapter you can find information about the intended use, the addressed target group and information about safety and privacy related topics.

1.1 Intended use

The product is designed to create a virtual ECU for microcontrollers using existing ECU source code or precompiled binaries. This virtual ECU is intended for simulation, debugging, and pre-calibration of ECU software in a computer-based virtual simulation environmenIn general, virtual ECUs may not be real-time capable. If you use a virtual ECU to control physical devices, the system may react unexpectedly. Take suitable precautions to ensure safe operation.

ETAS GmbH cannot be made liable for damage which is caused by incorrect use and not adhering to the safety information. Adhere to the ETAS Safety Advice (see `documentation` folder).

1.2 Target group

This product is intended for skilled and qualified personnel in development of auto-motive ECU software (e.g., function developer, application engineer, ECU soft-ware integrator, systems engineer or calibration engineer) at OEMs, tier-1 or tier-2 suppliers in the auto-motive industry. Technical knowledge in control unit engineering is a prerequisite. In addition, programming knowledge in C/C++ is required. AUTOSAR Classic knowledge is helpful.

1.3 Data protection

If the product contains functions that process personal data, legal requirements of data protection and data privacy laws shall be complied with by the customer. As the data controller, the customer usually designs subsequent processing. Therefore, he must check if the protective measures are sufficient.

1.4 Data and information security

To securely handle data in the context of this product, see the next sections about data and storage locations as well as technical and organizational measures.

1.4.1 Data and storage locations

The following sections give information about data and their respective storage locations for various use cases.

License Management

When using the ETAS License Manager in combination with user-based licenses that are managed on the FNP license server within the customer's network, the following data are stored for license management purposes:

Data

- Communication data: IP address
- User data: User ID

Storage location

- FNP license server log files on the customer network

When using the ETAS License Manager in combination with host-based licenses that are provided as FNE machine-based licenses, the following data are stored for license management purposes:

Data

- Activation data: Activation ID
  - Used only for license activation, but not continuously during license usage

Storage location

- FNE trusted storage

  Windows:
  `C:\ProgramData\ETAS\FlexNet\fne\license\ts`

  Linux:
  `/usr/share/ETAS/LiMa/fne/license/ts/`

1.4.2 Technical and organizational measures

We recommend that your IT department takes appropriate technical and organizational measures, such as classic theft protection and access protection to hardware and software.

2 About VECU-BUILDER

VECU-BUILDER is a tool for building virtual ECUs (vECUs) for simulation, debugging, and pre-calibration of ECU software within a computer-based virtual simulation environment.

VECU-BUILDER supports the generation of Level-1, Level-2, and Level-3 vECUs in accordance with the Prostep Definition of vECUs.Level-4 vECUs, i.e., HEX files for a specific target, are not supported.

VECU-BUILDER is built on Python and CMake. It can take inputs in the form of C/C++ source codes or binaries, such as object files or shared libraries containing symbol information. Unlike AUTOSAR Classic, the configuration of a vECU is performed in a single YAML file (`vEcuConf.yaml`). The properties are configured within this text-based file, which is used to define the supported features of the vECU, such as an XCP slave or initial data as part of simulated NVRAM.

VECU-BUILDER wraps the binaries of the vECU into an FMU. These FMUs can be integrated into any FMI-compliant simulation master.

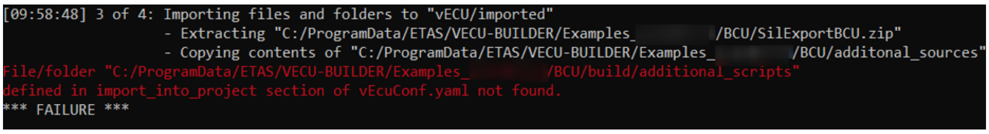
2.1 VECU-BUILDER on YouTube

You can access a playlist on YouTube that features VECU-BUILDER and its functionalities. To open the playlist, click the image below.

2.2 Warning and error messages

VECU-BUILDER may encounter situations in which an error or a warning message is displayed.

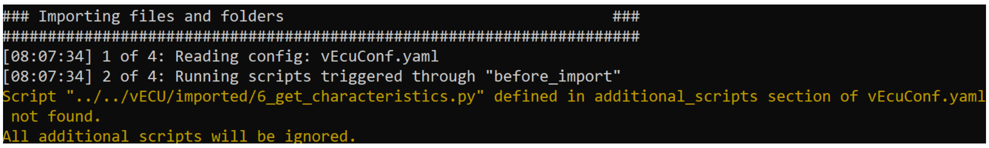
Errors are printed in red and indicate a severe issue which prevents the build from succeeding.



```
[09:58:48] 3 of 4: Importing files and folders to "vECU/imported"
                   - Extracting "C:/ProgramData/ETAS/VECU-BUILDER/Examples_[redacted]/BCU/SilExportBCU.zip"
                   - Copying contents of "C:/ProgramData/ETAS/VECU-BUILDER/Examples_[redacted]/BCU/additonal_sources"
File/folder "C:/ProgramData/ETAS/VECU-BUILDER/Examples_[redacted]/BCU/build/additional_scripts"
defined in import_into_project section of vEcuConf.yaml not found.
*** FAILURE ***
```

Fig. 2-1: Error message

Warnings are printed in yellow and are meant to draw the attention to a certain issue during the build. The issue is not as severe as an error and thus the build continues.



```
### Importing files and folders                                      ###
######################################################################
[08:07:34] 1 of 4: Reading config: vEcuConf.yaml
[08:07:34] 2 of 4: Running scripts triggered through "before_import"
Script "../../vECU/imported/6_get_characteristics.py" defined in additional_scripts section of vEcuConf.yaml
 not found.
All additional scripts will be ignored.
```

Fig. 2-2: Warning message

2.3 Basics

The basic principle is to keep the data lean in a simple and smart way. The concept is the simplification of the ECU software stack and the ARXML file. The A2L file is patched by removing all hardware dependencies and updating memory addresses of all inputs, outputs, measurements, and characteristics. The software stack layers are represented by C and H files. These files are reflected in the `imported` folder (`vECU\imported`) in the vECU build process.

The result is a stand alone FMU:

- The FMU contains the model description (e.g. its variables) as XML file.
- The FMU contains the access to calibration and measurement variables via patched A2L file .
- The FMU contains an executable model as DLL/SO file.

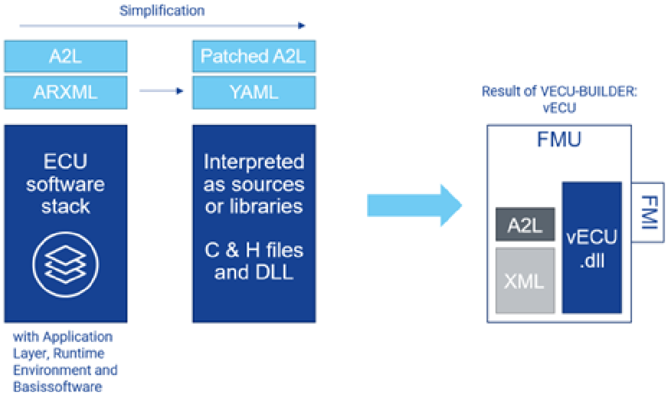

Simplification
A2L
ARXML
Patched A2L
YAML
ECU software stack
with Application Layer, Runtime Environment and Basissoftware
Interpreted as sources or libraries
C & H files and DLL
Result of VECU-BUILDER: vECU
FMU
A2L
XML
vECU .dll
FMI

Fig. 2-3: Basic concept and result of VECU-BUILDER

2.4 Virtual ECU

A vECU is a virtualized ECU which can be used as a real ECU. With the vECU you can test the ECU software and execute the software functionality without hardware. This gives you the possibility to test the communication between the ECUs before prototypes or hardware is available. The vECU contains the code, the parameters and the XCP slave as an alternative path to the HEX code.

2.5 vECU creation process workflow

The whole workflow is an iterative process to get to the final configuration of the YAML file. The listed points provide a rough overview of the workflow. Section A and F take place outside of VECU-BUILDER.

A. Prepare sources
   - Fix directives that refer to header files in code
   - Generate a script collecting the files you need from the various locations you found

B. Compile sources, incompatible sources must be removed
   - Generate new workspace
   - Copy sources into workspace
   - Build
   - Check error messages
   - Remove or patch code

C. Link sources and create stubs
   - Solve link errors with empty stubs

D. Define Inputs and Outputs (I/O) to make the vECU runnable
   - Use symbol information to generate I/O
   - Manually patch the sources of virtual devices
   - Use the C notation of the variables (e.g., `sensor.*`)

E. Create task model to run the tasks
   - Use text format to define task model

F. Operate for first time, apply SiL specific code changes
   - Debug code
   - Fill some stub functions with code or apply SiL specific code changes

After completing the first iteration of an vECU it can be used to perform further steps outside of VECU-BUILDER:

- Integration of the vECU with plant models and execution in a Co-Simulation environment
- Running and testing the vECU in an experimental environment
- Measuring and calibrating the vECU
- Debugging using a source code editor

2.6 Functional Mock-up Interface (FMI)

The Functional Mock-up Interface (FMI) is a free specification that outlines a container and interface for exchanging dynamic simulation models. VECU-BUILDER supports Co-simulation (CS). The FMU is provided with its own solver in Co-simulation.

For more information about FMI,see FMI standard.

Fig. 2-4 shows the general steps for Co-Simulation in FMI versions 2 and 3.

Steps 4-6 are repeated until `fmi2Terminate` or `fmi3Terminate` function is called.

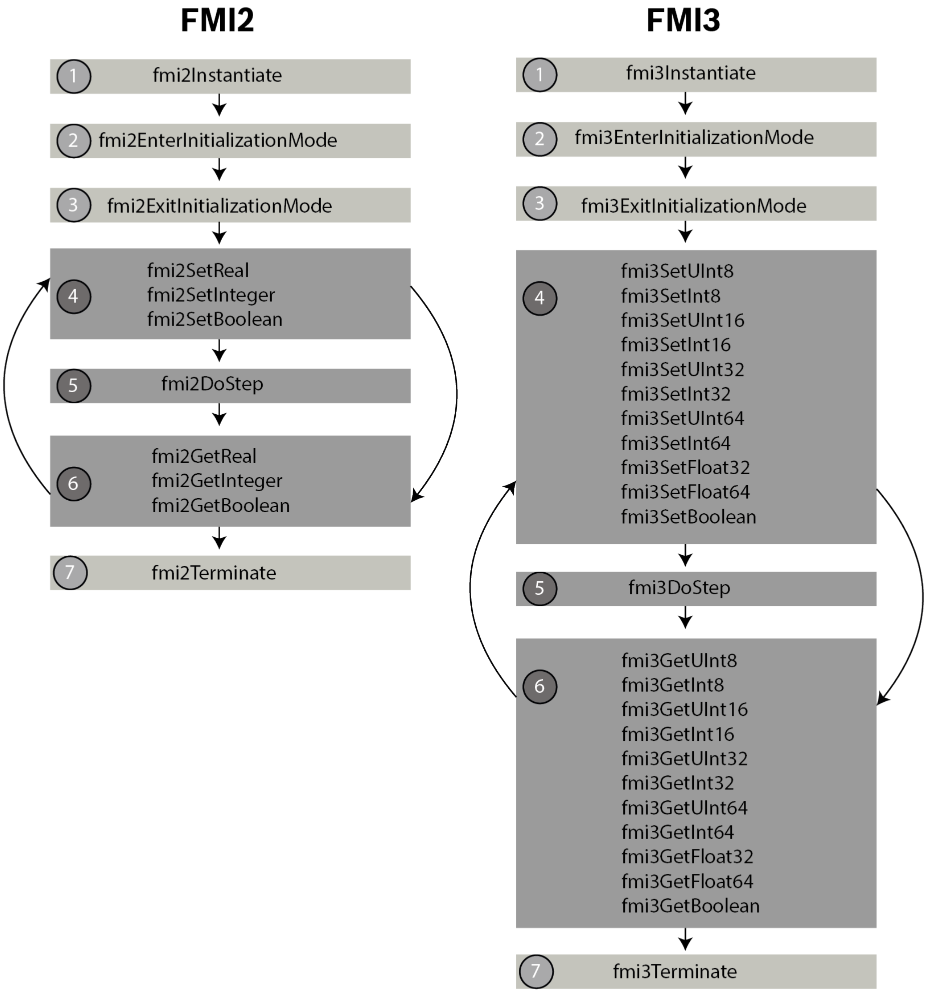


Fig. 2-4: General steps for Co-Simulation

VECU-BUILDER supports FMI2 and FMI3 by a plug-in concept. For more information about plug-in concept, see Template for plug-in V1 (FMI2) and Template for plug-in V2 (FMI3).

3 Installation

This chapter provides information for preparing and performing the installation and for licensing the software. The installation can be fulfilled for the following operating systems:

- Windows 10
- Ubuntu 22.04 LTS
- Ubuntu 22.04 on WSL for Windows

3.1 Hardware requirements

The following Hardware Requirements need to be met:

Processor	min. 2 GHz 3 GHz Dual-Core or higher recommended
Memory	min. 8 GB RAM 32 GB RAM recommended
Free Disk Space	5 GB (not including the size for application data) >100 GB recommended

3.2 Preparation

Prior to installing, ensure that your computer meets the hardware and software requirements. Ensure that you have the appropriate user rights based on your operating system and network connection.

> **Note**
>
> If you lack appropriate user rights, contact your system administrator.

3.3 Installation content

You can download the installation content from ETAS license and download portal. Log in using your email address, download the installation content, and then proceed with the installation.

The installation content includes information about the open-source software attributions, important information such as Safety Advice or the User Guide as well as the executable installation files.

> **Note**
>
> If the download files or download link are not available, contact technical support for assistance.

3.4 Licensing

A valid license is required to use the software. You can obtain a license in one of the following ways:

- from your tool coordinator
- via the self-service portal on the ETAS website at www.etas.com/support/licensing
- via the ETAS License Manager

To activate the license, you must enter the Activation ID that you received from ETAS during the ordering process.

For more information about ETAS license management, see the ETAS License Management FAQ or the ETAS License Manager help.

To open the ETAS License Manager help

The ETAS License Manager is available on your computer after the installation of any ETAS software.

1. From the Windows Start menu, select **E** > **ETAS** > **ETAS License Manager**.

   or

   Under Linux, use `LiMaQt.sh`, which you can find at the following location: `./usr/share/ETAS/LiMa/x32/bin/`.

   The ETAS License Manager opens.
2. Click in the ETAS License Manager window and press F1.

   The ETAS License Manager help opens.

VECU-BUILDER performs the following checks:

- Check of the product license when building FMUs.
- Check of the run time license during run time of the vECU.
- Check of the GO license during build time. If it is valid, it will prevent all license checks during run time.

3.5 Installation on Windows 10

3.5.1 Software requirements for Windows 10

The following Software Requirements need to be met:

Required Software	ETAS License Manager CMake (version ≥3.15)
Recommended Software	Notepad++
Optional Software	Visual Studio 2015, 2017, 2019, 2022 Visual Studio Code Python

3.5.2 Manual installation of VECU-BUILDER

1. Navigate to the directory where the installation file is located and execute the `VECU_BUILDER_installer_1.8.0.exe` file.

⇨ The Setup Wizard opens.

2. Click **Next**.

⇨ The Safety Advice window opens.

3. Read the Safety Advice carefully, then select "I read and accept the Safety Advice".

4. Click **Next**.

⇨ The Installation Path window opens.

5. Accept the default path (click **Next**) or click **Browse** to select a custom location.

⇨ The Ready to Install window opens.

6. Click **Install**.

⇨ The installation is performed, its progress is shown via a progress bar.

7. Click **Next**.

⇨ The Third-party Software window opens.

8. Install CMake (required) and Notepad++ (recommended).

   See the links below in the installation dialog:

   CMake (version 3.15 or higher)

   Notepad++

9. Click **Next**.

⇨ The Completing VECU-BUILDER Setup window opens.

10. Optional:To open the documentation folder ,activate the Open VECU-BUILDER documentation checkbox.

11. Click **Finish**.

⇨ The installation is completed, and you can use VECU-BUILDER.

3.5.3 Silent installation of VECU-BUILDER

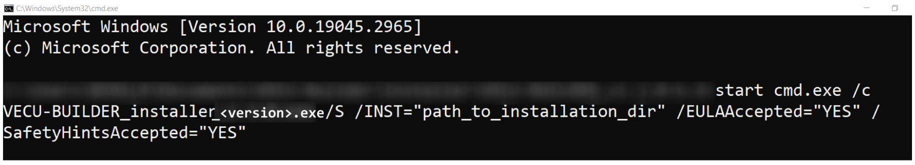
You can also use silent installation in addition to manual installation. The installation process varies based on whether you use the Command Prompt or the PowerShell.

Silent installation using command prompt

1. Open the command prompt.
2. Navigate to the directory where the installer (`VECU-BUILDER_installer_1.8.0.exe`) is located.
3. Install VECU-BUILDER using the following command:

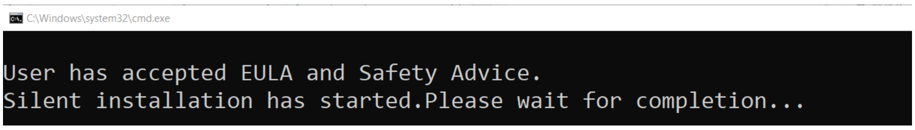
   ```
   start cmd.exe /c VECU-BUILDER_installer_1.8.0.exe /S
   /INST="path_to_installation_dir" /EULAAccepted="YES"
   /SafetyHintsAccepted="YES"
   ```

   where `path_to_installation_dir` contains a path to a directory where the software is to be installed.



```
Microsoft Windows [Version 10.0.19045.2965]
(c) Microsoft Corporation. All rights reserved.

[redacted] start cmd.exe /c
VECU-BUILDER_installer<version>.exe/S /INST="path_to_installation_dir" /EULAAccepted="YES" /
SafetyHintsAccepted="YES"
```

⇨ A new command prompt window opens and installation starts.



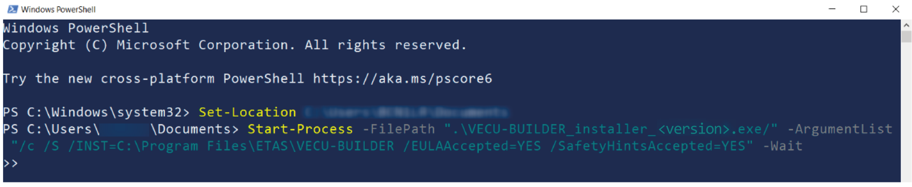
```
User has accepted EULA and Safety Advice.
Silent installation has started.Please wait for completion...
```

Silent installation using PowerShell

1. Open the PowerShell.
2. Navigate to the directory where the installer (`VECU-BUILDER_installer_1.8.0.exe`) is located.
3. Install VECU-BUILDER using the following command:

   ```
   Start-Process -FilePath".\VECU-BUILDER_installer_1.8.0.exe/" -ArgumentList "/c /S /INST= path_to_installation_dir /EULAAccepted=YES /SafetyHintsAccepted=YES" -Wait
   ```

   where `path_to_installation_dir` contains a path to a directory where the software is to be installed.

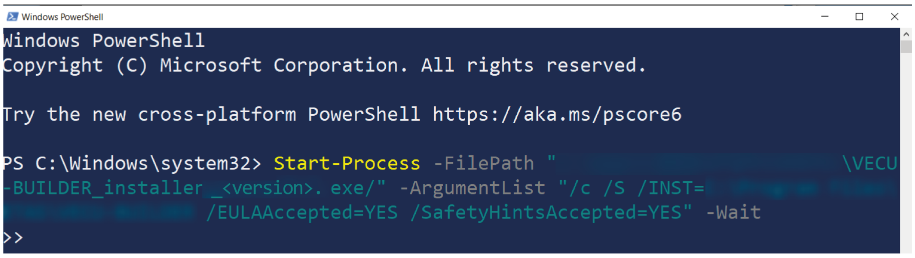
   ```
   Windows PowerShell
   Copyright (C) Microsoft Corporation. All rights reserved.

   Try the new cross-platform PowerShell https://aka.ms/pscore6

   PS C:\Windows\system32> Set-Location [redacted]
   PS C:\Users\[redacted]\Documents> Start-Process -FilePath ".\VECU-BUILDER_installer_<version>.exe/" -ArgumentList
    "/c /S /INST=C:\Program Files\ETAS\VECU-BUILDER /EULAAccepted=YES /SafetyHintsAccepted=YES" -Wait
   >>
   ```

Or

Install VECU-BUILDER using the following command:

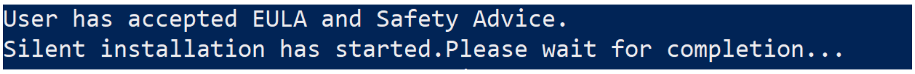
```
Start-Process -FilePath " path_to \VECU-BUILDER_installer_1.8.0.exe/" -ArgumentList "/c /S /INST= path_to_installation_dir /EULAAccepted=YES /SafetyHintsAccepted=YES" -Wait
```

where `path_to` contains the path where the installer (`VECU-BUILDER_installer_1.8.0.exe`) is located and `path_to_installation_dir` contains a path to a directory where the software is to be installed.



```
Windows PowerShell
Copyright (C) Microsoft Corporation. All rights reserved.

Try the new cross-platform PowerShell https://aka.ms/pscore6

PS C:\Windows\system32> Start-Process -FilePath "[redacted]\VECU
-BUILDER_installer_<version>.exe/" -ArgumentList "/c /S /INST=[redacted]
[redacted] /EULAAccepted=YES /SafetyHintsAccepted=YES" -Wait
>>
```

➩ Installation starts.



```
User has accepted EULA and Safety Advice.
Silent installation has started.Please wait for completion...
```

3.5.4 Uninstalling VECU-BUILDER on Windows 10

1. Open the location where you installed VECU-BUILDER.

   If you used the default installation location, you can find it under `C:/Program Files/ETAS/VECU-BUILDER`
2. Execute the `uninstall.exe` with double-click.

3.6 Installation on Ubuntu 22.04 LTS

3.6.1 Software requirements for Ubuntu 22.04 LTS

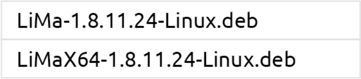
The following Software Requirements need to be met:

Required Software	ETAS License Manager cmake build-essential gcc-multilib g++-multilib libssl-dev:i386 linux-libc-dev:i386 xterm
Optional Software	Visual Studio Code Python nano

3.6.2 Installing License Manager (LiMa) on Ubuntu 22.04 LTS

Prior to installing VECU-BUILDER, you need to manually install the ETAS License Manager (LiMa).

The installation debian packages for LiMa are delivered next to the VECU-BUILDER installation debian package.



LiMa-1.8.11.24-Linux.deb

LiMaX64-1.8.11.24-Linux.deb

Fig. 3-1: LiMa installation debian packages

1. Navigate to the directory where the LiMa debian Package files are located.
2. Install LiMa using the following command:

   ```
   sudo apt install ./LiMa-1.8.11.24-Linux.deb
   ```

3. Install LiMaX64 unsing the following command:

   ```
   sudo apt install ./LiMaX64-1.8.11.24-Linux.deb
   ```

⇨ LiMa and all its components are installed.

3.6.3 Opening ETAS License Manager on Ubuntu 22.04 LTS

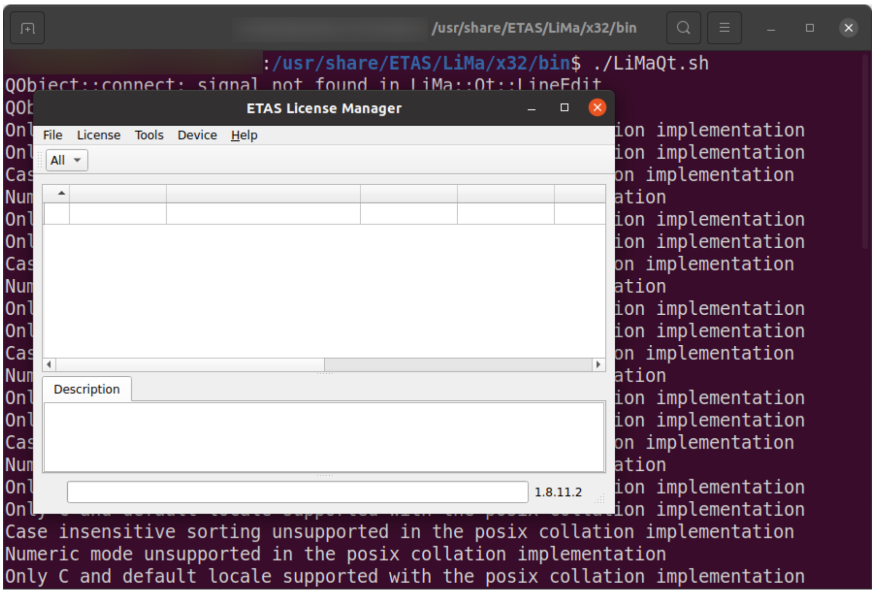
1. Navigate to the following direction:

   `/usr/share/ETAS/LiMa/x32/bin`

2. Open a new terminal.
3. Enter the following command:

   `./LiMaQt.sh`

➩ LiMa was opened.



```
[redacted]:/usr/share/ETAS/LiMa/x32/bin$ ./LiMaQt.sh
QObject::connect: signal not found in LiMa::Qt::LineEdit
QOb
Onl                                                         ion implementation
Onl                                                         ion implementation
Cas                                                         on implementation
Nun                                                         ation
Onl                                                         ion implementation
Onl                                                         ion implementation
Cas                                                         on implementation
Nun                                                         ation
Onl                                                         ion implementation
Onl                                                         ion implementation
Cas                                                         on implementation
Nun                                                         ation
Onl                                                         ion implementation
Onl                                                         ion implementation
Cas                                                         on implementation
Nun                                                         ation
Onl                                                         ion implementation
Only C and default locale supported with the posix collation implementation
Case insensitive sorting unsupported in the posix collation implementation
Numeric mode unsupported in the posix collation implementation
Only C and default locale supported with the posix collation implementation
```

3.6.4 Activating the LiMa license

There are several possibilities to activate the license. For more information about ETAS license management, see the ETAS License Management FAQ or the ETAS License Manager help.

3.6.5 Installing VECU-BUILDER on Ubuntu 22.04 LTS

1. Navigate to the directory where the Debian Software Package file `(VECU-BUILDER_installer_1.8.0.deb)` is located.
2. Open a new terminal.
3. Install VECU-BUILDER using the following command:

```
sudo apt install ./VECU-BUILDER_installer_1.8.0.deb
```

> **Note**
>
> VECU-BUILDER has dependencies on other software. The dependent software packages will be installed during the installation. An Internet connection is required to install the dependent software packages.

4. Accept the installation of dependent packages.

⇨ The packages are selected and unpacked.

5. Accept the Safety Advice.

⇨ The VECU-BUILDER package deployment is completed.

6. Log out and log in to enable environment variables to be set.

3.6.6 Uninstalling VECU-BUILDER on Ubuntu 22.04 LTS

1. Open a new terminal.
2. Uninstall VECU-BUILDER using the following command:

```
sudo apt remove vecu-builder
```

⇨ You are asked if you want to continue uninstalling.

3. To continue uninstalling, enter <Y> and press <ENTER>.

⇨ The VECU-BUILDER package is removed.

3.7 Installation on Ubuntu 22.04 LTS for WSL

It is possible to create a Linux-vECU from a Windows host. To be able to create a Linux-vECU from a Windows host, the following prerequisites must be met:

- WSL is installed on Windows.
- Ubuntu 22.04 LTS is installed on WSL.
- LiMa is installed on WSL.
- VECU-BUILDER is installed on WSL.

3.7.1 Software requirements for Ubuntu 22.04 LTS on WSL

The following Software Requirements need to be met:

Required Software	ETAS License Manager cmake build-essential gcc-multilib g++-multilib libssl-dev:i386 linux-libc-dev:i386 gnome-terminal (for dialog mode softwares)
Optional Software	Visual Studio Code (for debugging, installed on Windows computer host) Python nano gdb (for debugging)

3.7.2 Installing WSL on Windows

To install WSL on Windows, see Install WSL command.

3.7.3 Installing Ubuntu 22.04 LTS on WSL

1. Open PowerShell.
2. Check what distributions are available online in PowerShell using the following command:

```
wsl --list --online
```

3. Install Ubuntu 22.04 LTS on WSL using the following command:

```
wsl --install -d ubuntu-22.04
```

⇨ Ubuntu 22.04 LTS is installed.

3.7.4 Installing dependent software packages

In order to install VECU-BUILDER you need to install dependent software packages.

Note

The installation of dependent software packages requires unrestricted internet access. If your computer is not permitted to connect to the official package repositories, the `sudo apt` commands will fail. For further information, contact your system administrator.

Note

Downloading dependencies or installing VECU-BUILDER only runs in WSL1, working with VECU-BUILDER only runs in WSL2. Ensure that the WSL version aligns with the specific action. If necessary, you need to change the version.

— For WSL1:

- wsl --set-version Ubuntu-22.04 1

— For WSL2:

- wsl --set-version Ubuntu-22.04 2

1. In PowerShell, check the WSL Ubuntu version using the following command:

   ```
   wsl -l -v
   ```

   If it is not 1, set the version to 1, using the following command:

   ```
   wsl --set-version Ubuntu-22.04 1
   ```

2. Open Ubuntu 22.04 LTS command line interface.
3. Install the `i386` architecture using the following command:

   ```
   sudo dpkg --add-architecture i386
   ```

4. Install `libc6-i386` using the following command:

   ```
   sudo apt install -y libc6-i386
   ```

5. Install `lsb` using the following command:

   ```
   sudo apt install -y lsb
   ```

6. Run a package update using the following command:

   ```
   sudo apt update
   ```

7. Run a package upgrade using the following command:

   ```
   sudo apt upgrade
   ```

8. Install `gnome-terminal` using the following command:

   ```
   sudo apt install gnome-terminal
   ```

You need `gnome-terminal` for debugging, ETAS License Manager (LiMa) and the Dialog mode.)

9. Install `gdb` using the following command:

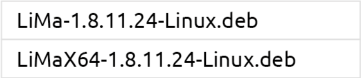
   ```
   sudo apt install gdb
   ```

   You need `gdb` for debugging.

3.7.5 Installing License Manager (LiMa) on Ubuntu 22.04 LTS for WSL

Prior to installing VECU-BUILDER, you need to manually install the ETAS License Manager (LiMa).

The installation debian packages for LiMa are delivered next to the VECU-BUILDER installation debian package.



LiMa-1.8.11.24-Linux.deb

LiMaX64-1.8.11.24-Linux.deb

Fig. 3-2: LiMa installation debian packages

1. In order to install LiMa copy the required installation debian packages for LiMa to user home on Ubuntu.
2. Open Ubuntu 22.04 LTS command line interface.
3. Install LiMa using the following command:

   ```
   sudo apt install ./LiMa-1.8.11.24-Linux.deb
   ```

4. Install LiMaX64 using the following command:

   ```
   sudo apt install ./LiMaX64-1.8.11.24-Linux.deb
   ```

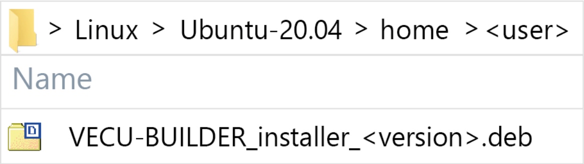
⇨ LiMa and all its components are installed.

3.7.6 Installing VECU-BUILDER on Ubuntu 22.04 LTS for WSL

Note

The installation of VECU-BUILDER only works if you have unrestricted access to the internet. The `sudo apt` commands will fail if your computer is not allowed to connect your Linux to the official package repositories. In this case, ask your IT department for help.

1. In order to install VECU-BUILDER copy VECU-BUILDER_installer_1.8.0.deb to user home on Ubuntu.



> Linux > Ubuntu-20.04 > home > <user>

Name

VECU-BUILDER_installer_<version>.deb

2. Install VECU-BUILDER using the following command:

```
sudo apt install ./VECU-BUILDER_installer_1.8.0.deb
```

Note

VECU-BUILDER has dependencies on other software. The dependent software packages will be installed during the installation. An Internet connection is required to install the dependent software packages.

3. Close and restart Ubuntu 22.04 LTS.

To create a workspace using WSL Ubuntu 22.04 LTS, see Ubuntu 22.04 LTS Command Line Interface.

3.7.6.1 Opening ETAS License Manager on Ubuntu 22.04 LTS for WSL

Prerequisites:

- Ensure to have the latest Ubuntu 22.04 LTS version and all related packages installed.
- Ensure to have XTerm (Ubuntu-22.04) installed.
- Ensure to have UXTerm (Ubuntu-22.04) installed.

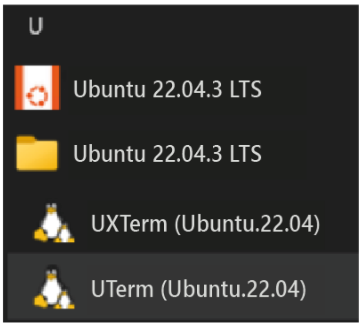


Fig. 3-3: UXTerm and XTerm for Ubuntu 22.04 LTS

For more information about running Linux GUI apps on the Windows Subsystem for Linux see Run Linux GUI apps on the Windows Subsystem for Linux.

1. Open PowerShell.

   Set WSL Ubuntu 22.04 LTS version to 2 using the following command:

   ```
   wsl --set-version Ubuntu-22.04 2
   ```

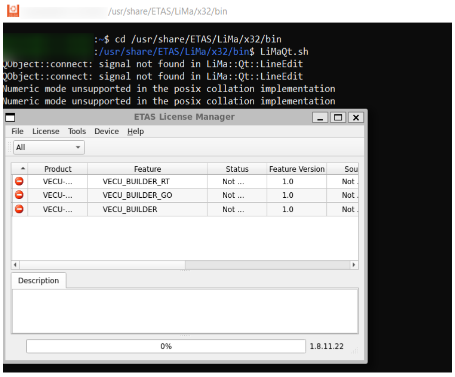
2. Open Ubuntu 22.04 LTS and change directory using the following command:

   ```
   cd /usr/share/ETAS/LiMa/x32/bin
   ```

3. Open `LiMaQt.sh` using the following command:

   ```
   LiMaQt.sh
   ```

➩ LiMa was opened.



[redacted] /usr/share/ETAS/LiMa/x32/bin

```
[redacted]:~$ cd /usr/share/ETAS/LiMa/x32/bin
[redacted]:/usr/share/ETAS/LiMa/x32/bin$ LiMaQt.sh
QObject::connect: signal not found in LiMa::Qt::LineEdit
QObject::connect: signal not found in LiMa::Qt::LineEdit
Numeric mode unsupported in the posix collation implementation
Numeric mode unsupported in the posix collation implementation
```

ETAS License Manager

	Product	Feature	Status	Feature Version	Sou
⛔	VECU-...	VECU_BUILDER_RT	Not ...	1.0	Not .
⛔	VECU-...	VECU_BUILDER_GO	Not ...	1.0	Not .
⛔	VECU-...	VECU_BUILDER	Not ...	1.0	Not .

3.7.7 Activating the LiMa license

There are several possibilities to activate the license. For more information about ETAS license management, see the ETAS License Management FAQ or the ETAS License Manager help.

3.7.8 Uninstalling VECU-BUILDER on Ubuntu 22.04 LTS for WSL

1. Open Ubuntu 22.04 LTS command line interface.
2. To uninstall, execute the following command:

   ```
   sudo apt remove vecu-builder
   ```

➩ You are asked if you want to continue uninstalling.

3. To continue uninstalling, enter <Y> and press <ENTER>.

➩ The VECU-BUILDER package is removed.

3.8 Installed files and folders

VECU-BUILDER software

The default installation location is

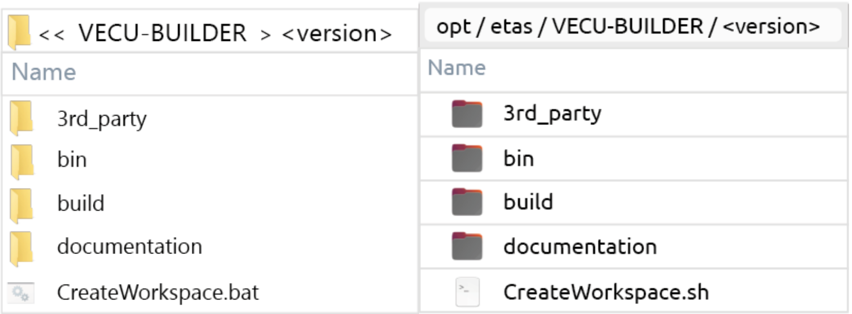
`C:/Program Files/ETAS/VECU-BUILDER/1.8.0` on **Windows**

or

`/opt/etas/VECU-BUILDER/1.8.0` on **Ubuntu 22.04 LTS** and **Ubuntu 22.04 LTS on WSL**.

It is recommended not to alter the installation location.

An environment variable of `VECUBUILDER_HOME` points to this folder.



<< VECU-BUILDER > <version>

Name
3rd_party
bin
build
documentation
CreateWorkspace.bat

opt / etas / VECU-BUILDER / <version>

Name
3rd_party
bin
build
documentation
CreateWorkspace.sh

Fig. 3-4: Installation content (left: Windows, right: Ubuntu 22.04 LTS)

This folder contains multiple subfolders and a one command/shell script:

- `3rd_party`: Contains the third party software of fmusim and MinGW.
- `bin`: Contains library and execution files for the build process. These files are important for the build and must not be altered.
- `build`: Contains templates, resources, and scripts for the build process. These files are important for the build and must not be altered.
- `documentation`: Contains the VECU-BUILDER User Guide, the OSS Attribution and the ETAS Safety Advice documents.
- `CreateWorkspace.bat`/ `CreateWorkspace.sh`: Creates a new workspace. After executing, you will be guided through the process step by step.

VECU-BUILDER examples/templates

You can find ready-to-use examples and templates in the following location:

`C:/ProgramData/ETAS/VECU-BUILDER/Examples_1.8.0` on **Windows**

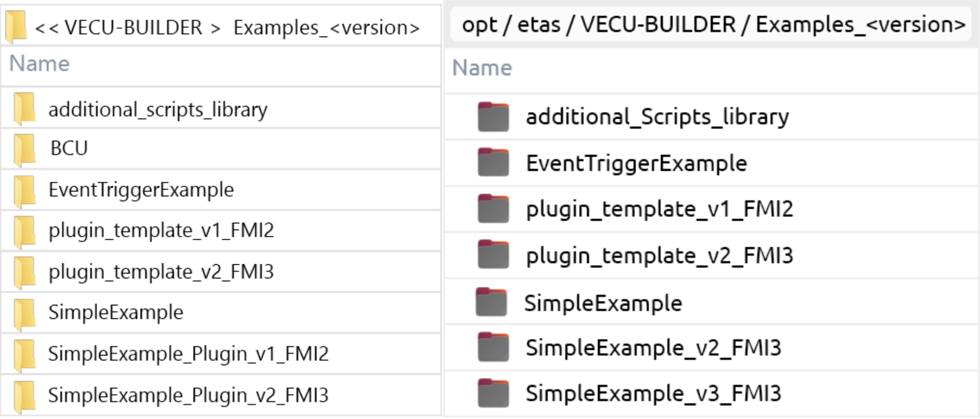
or

`/opt/etas/VECU-BUILDER/Examples_1.8.0` on **Ubuntu 22.04 LTS** and **Ubuntu 22.04 LTS on WSL**.

An environment variable of `VECUBUILDER_EXAMPLES` points to this folder.

The following examples and templates are delivered along with the software:

- additional_scrpts_library
  BCU (Body Control Unit) - only for Windows
- EventTriggerExample
- plugin_template_v1_FMI2
- plugin_template_v2_FMI3
- SimpleExample
- SimpleExample_Plugin_v1_FMI2
- SimpleExample_Plugin_v2_FMI3



<< VECU-BUILDER > Examples_<version>

Name

additional_scripts_library
BCU
EventTriggerExample
plugin_template_v1_FMI2
plugin_template_v2_FMI3
SimpleExample
SimpleExample_Plugin_v1_FMI2
SimpleExample_Plugin_v2_FMI3

opt / etas / VECU-BUILDER / Examples_<version>

Name

additional_Scripts_library
EventTriggerExample
plugin_template_v1_FMI2
plugin_template_v2_FMI3
SimpleExample
SimpleExample_v2_FMI3
SimpleExample_v3_FMI3

Fig. 3-5: Delivered examples/templates (left: Windows, right: Ubuntu 22.04 LTS)

VECU-BUILDER workspaces

The default folder is recommended as the location for all your workspaces, where you can create a dedicated subfolder for each workspace.

The default folder is created during the installation process under

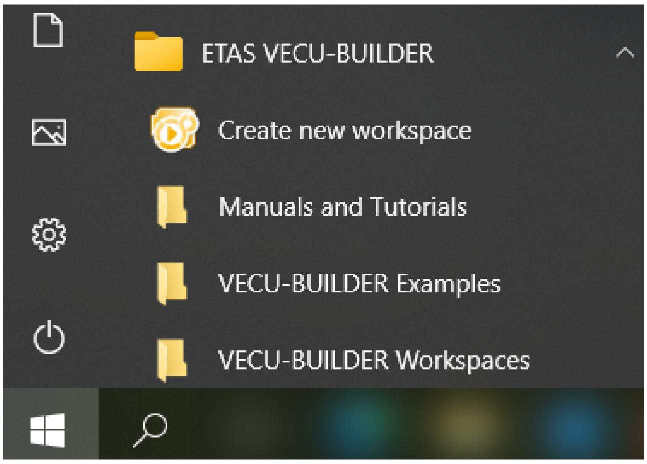
`C:/Users/Public/Documents/VECU-BUILDER_Workspaces` on **Windows**

or

`/opt/etas/VECU-BUILDER_Workspaces` on **Ubuntu 22.04 LTS** and **Ubuntu 22.04 LTS on WSL**.

Access to artefacts in Windows

You can access all artefacts in Windows via their respective Start Menu entries.



ETAS VECU-BUILDER

Create new workspace

Manuals and Tutorials

VECU-BUILDER Examples

VECU-BUILDER Workspaces

Fig. 3-6: Start Menu entries

4 VECU-BUILDER without admin credentials

You can use VECU-BUILDER without Admin credentials. If you lack admin credentials, you can use VECU-BUILDER as a portable version without needing an installation.

4.1 Use of portable version without admin credentials on Windows

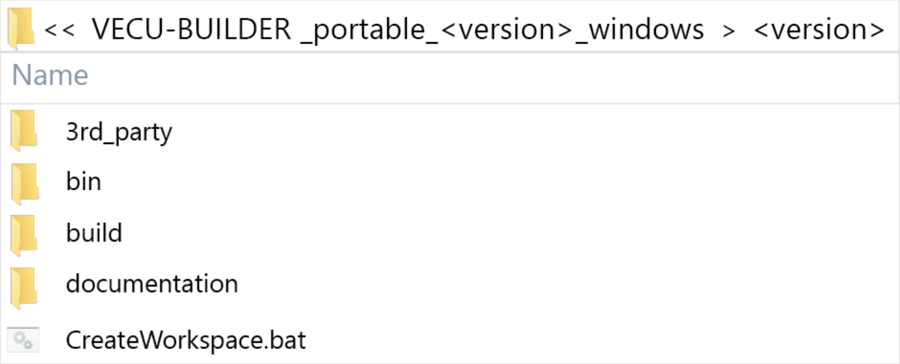
Prerequisites:

- Ensure that ETAS License Manager (LiMa) is installed and a valid license is available.

To use VECU-BUILDER portable version:

1. Extract `VECU-BUILDER_portable_1.8.0_windows.zip` to some folder, such as `C:/PortableTools/`.
2. Open a new command prompt.
3. Set environment variables using the following commands:
   - `SET VECUBUILDER_EXAMPLES=<C:/PortableTools/>/VECU-BUILDER_portable_1.8.0_windows\$LOCALAPPDATA\ETAS\VECU-BUILDER\EXAMPLES_1.8.0`
   - `SET VECUBUILDER_HOME=<C:/PortableTools/>VECU-BUILDER_portable_1.8.0_windows\1.8.0`
4. Log off and log in again.

⇨ You can now create a new workspace using `CreateWorkspace.bat` under `VECU-BUILDER_portable_1.8.0_windows\1.8.0`.



For more information about Working with VECU-BUILDER and VECU-BUILDER Examples/Templates, see VECU-BUILDER software, VECU-BUILDER examples/templatesWorking with VECU-BUILDER and Exploring the examples/templates.

4.2 Use of portable version without admin credentials on Ubuntu 22.04 LTS

Prerequisites:

- Ensure that License Manager (LiMa)is installed and a valid license is available.
- To install LiMa on Ubuntu 22.04 LTS, see Installing License Manager (LiMa) on Ubuntu 22.04 LTS.

To use VECU-BUILDER portable version:

1. Navigate to the directory where the Debian Software Package file `VECU-BUILDER_installer_1.8.0.deb` is located.
2. Extract the directory to some folder, such as `/home/<your user>/PortableTools`.

   To extract the portable version, use the following command:

   ```
   dpkg-deb -R ./VECU-BUILDER_installer_1.8.0.deb /home/<your user>/PortableTools
   ```
3. Navigate to the following path:

   ```
   /etc/profile.d
   ```
4. Create a shellscript file named `vecubuilder-conf.sh`.
5. Enter the following content into the shellscript file:

   ```
   #!/bin/bash
   export VECUBUILDER_HOME=/home/<your user>/PortableTools/opt/etas/VECU-BUILDER/1.8.0/
   ```
6. Log out and log in again.
7. Copy the content of `/home/<your user>/PortableTools>/usr` to any location in the home(~) folder.

Note

You can find SW and examples under `/home/<your user>/PortableTools/opt/etas/VECU-BUILDER/`.

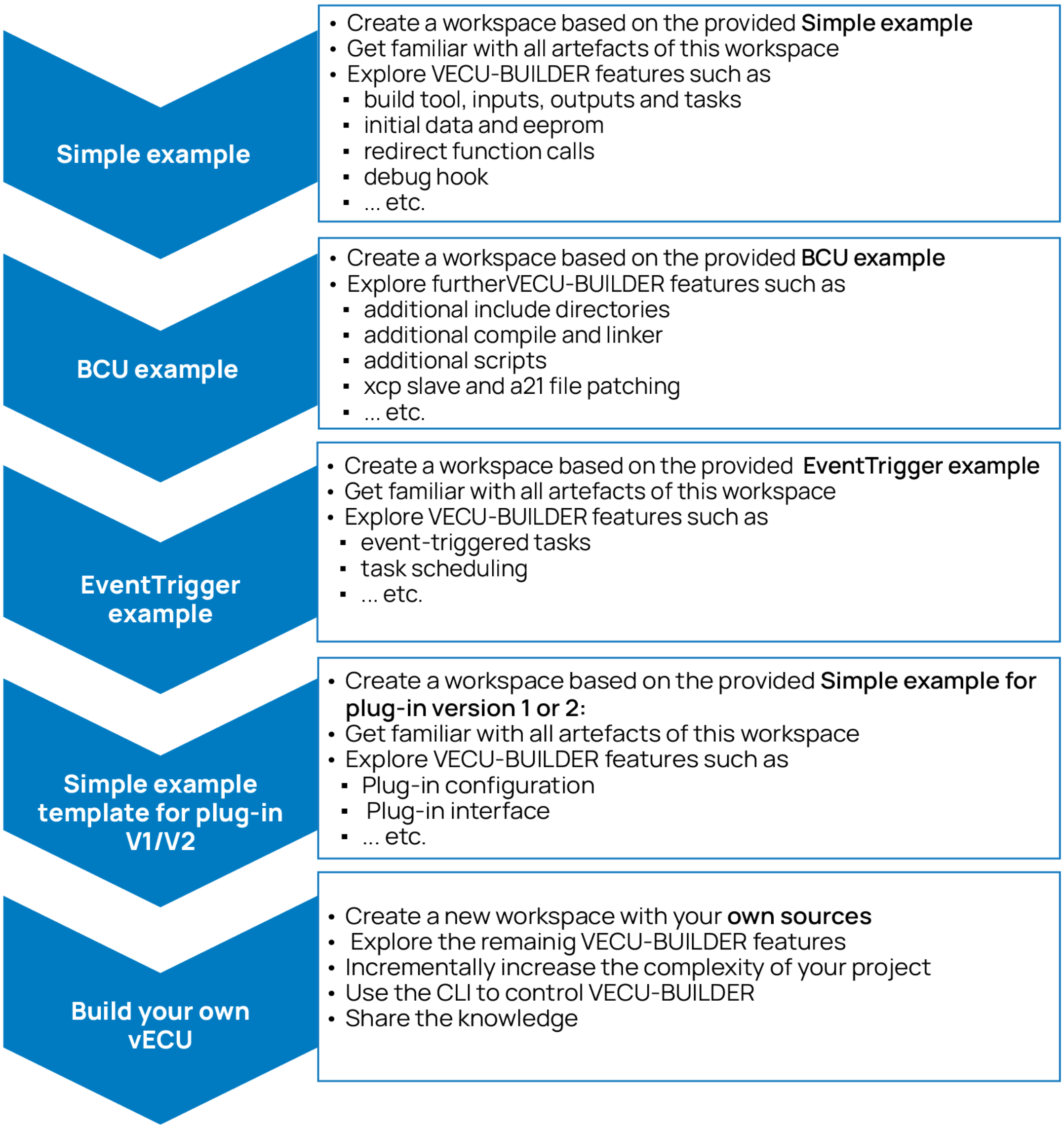
⇨ You can now create a new workspace.

For more information about Working with VECU-BUILDER and VECU-BUILDER Examples/Templates, see VECU-BUILDER software, VECU-BUILDER examples/templates, Working with VECU-BUILDER and Exploring the examples/templates.

5 Working with VECU-BUILDER

The steps outlined in the upcoming chapters guide you in creating your first vECU based on the Simple example. This provides an ideal starting point for your journey into virtualization.

To become familiar with working in VECU-BUILDER, follow the path below:



Simple example

- Create a workspace based on the provided **Simple example**
- Get familiar with all artefacts of this workspace
- Explore VECU-BUILDER features such as
  - build tool, inputs, outputs and tasks
  - initial data and eeprom
  - redirect function calls
  - debug hook
  - ... etc.

BCU example

- Create a workspace based on the provided **BCU example**
- Explore furtherVECU-BUILDER features such as
  - additional include directories
  - additional compile and linker
  - additional scripts
  - xcp slave and a21 file patching
  - ... etc.

EventTrigger example

- Create a workspace based on the provided **EventTrigger example**
- Get familiar with all artefacts of this workspace
- Explore VECU-BUILDER features such as
  - event-triggered tasks
  - task scheduling
  - ... etc.

Simple example template for plug-in V1/V2

- Create a workspace based on the provided **Simple example for plug-in version 1 or 2:**
- Get familiar with all artefacts of this workspace
- Explore VECU-BUILDER features such as
  - Plug-in configuration
  - Plug-in interface
  - ... etc.

Build your own vECU

- Create a new workspace with your **own sources**
- Explore the remainig VECU-BUILDER features
- Incrementally increase the complexity of your project
- Use the CLI to control VECU-BUILDER
- Share the knowledge

Fig. 5-1: Learning path

This section guides you through the process of creating a vECU in four distinct stages. Each stage can be triggered individually, and you can choose to continue with the next one.

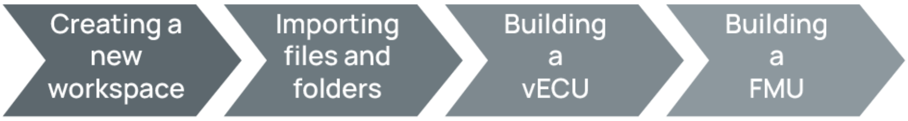


Fig. 5-2: VECU-BUILDER stages

5.1 Creating a new workspace

The very first step, required at the beginning of every project, is to create a workspace.

> **Note**
>
> Workspaces are designed for parallel use.
>
> A single workspace cannot be used for tasks running in parallel.

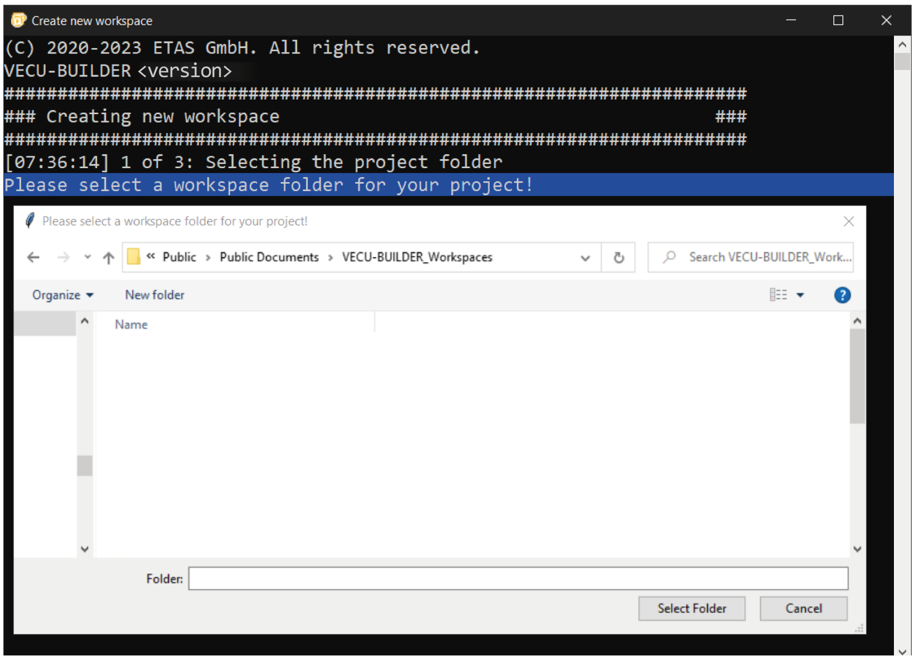
To create a workspace using Command Line Interface (CLI) and Ubuntu 22.04 LTS CLI, see Controlling VECU-BUILDER.

5.1.1 Creating a workspace on Windows

1. Launch Create new workspace from the Start Menu.

⇨ A console window opens providing details on the overall process, various stages it goes through and their individual steps.

⇨ In the first step of Create new workspace you will be asked to select a folder where your workspace will be saved.



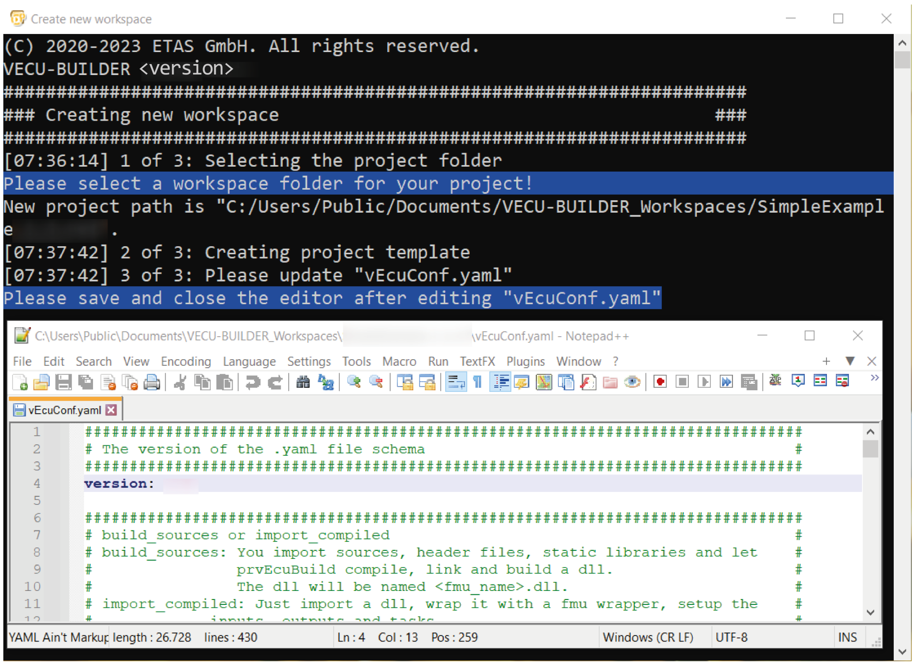
```
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Creating new workspace                                         ###
######################################################################
[07:36:14] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
```

Create new workspace
Please select a workspace folder for your project!
« Public › Public Documents › VECU-BUILDER_Workspaces
Search VECU-BUILDER_Work...
Organize
New folder
Name
Folder:
Select Folder
Cancel

2. Navigate to the default location of your workspaces `C:/Users/Public/Documents\VECU-BUILDER_Workspaces` and select an existing folder or create a new one.

➯ The `vEcuConf.yaml` configuration file opens in Notepad++.

➯ Per default, this is the configuration file of the Simple example.



```
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Creating new workspace                                         ###
######################################################################
[07:36:14] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
New project path is "C:/Users/Public/Documents/VECU-BUILDER_Workspaces/SimpleExampl
e[redacted].
[07:37:42] 2 of 3: Creating project template
[07:37:42] 3 of 3: Please update "vEcuConf.yaml"
Please save and close the editor after editing "vEcuConf.yaml"
```

C:\Users\Public\Documents\VECU-BUILDER_Workspaces\[redacted]\vEcuConf.yaml - Notepad++
File Edit Search View Encoding Language Settings Tools Macro Run TextFX Plugins Window ?
vEcuConf.yaml

```
################################################################################
# The version of the .yaml file schema                                        #
################################################################################
version: [redacted]

################################################################################
# build_sources or import_compiled                                            #
# build_sources: You import sources, header files, static libraries and let   #
#                prvEcuBuild compile, link and build a dll.                   #
#                The dll will be named <fmu_name>.dll.                        #
# import_compiled: Just import a dll, wrap it with a fmu wrapper, setup the   #
#              inputs, outputs and tasks.                                     #
```

YAML Ain't Markup length : 26.728 lines : 430 Ln : 4 Col : 13 Pos : 259 Windows (CR LF) UTF-8 INS

3. Keep the configuration file as is and close the Notepad ++ software.

➯ Your new workspace is now created.

The process will automatically continue with the next stage.

5.1.2 Creating a workspace on Ubuntu 22.04 LTS

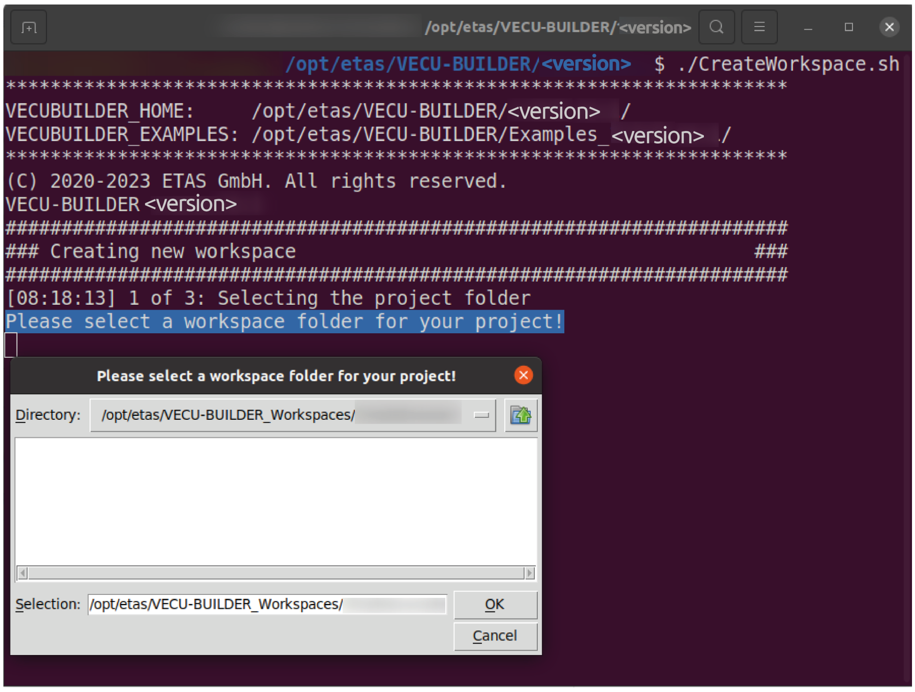
> **Note**
>
> In Ubuntu 22.04 LTS LTS the folder, that should be used as workspace, needs to exist before the workspace creation is proceeded.

1. Navigate to the folder, where the `CreateWorkspace.sh` is located.

   The default path is `opt/etas/VECU-BUILDER/1.8.0`.
2. Open a new terminal. VECU-BUILDER will use the editor found under `/usr/bin/editor`.
3. Enter `./CreateWorkspace.sh`.

⇨ In the first step of Create new workspace you will be asked to select a folder where your workspace will be saved.

4. Navigate to the default location of your workspaces `/opt/etas/VECU-BUILDER_Workspaces` and select an existing folder.



```
/opt/etas/VECU-BUILDER/<version>  $ ./CreateWorkspace.sh
**********************************************************************
VECUBUILDER_HOME:     /opt/etas/VECU-BUILDER/<version>  /
VECUBUILDER_EXAMPLES: /opt/etas/VECU-BUILDER/Examples_<version> /
**********************************************************************
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Creating new workspace                                         ###
######################################################################
[08:18:13] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
```

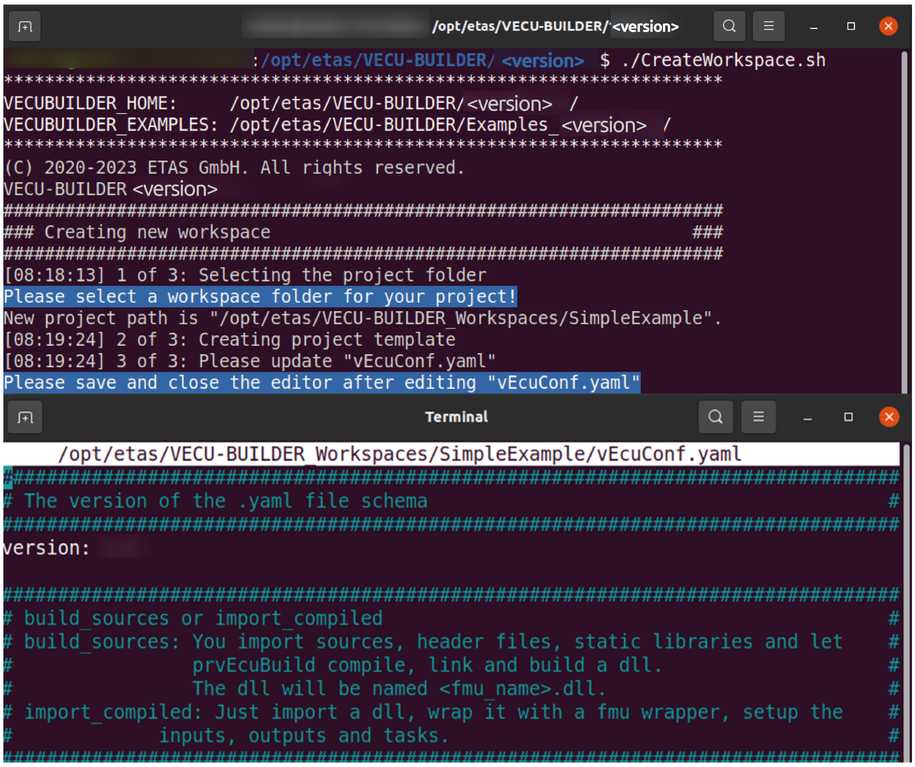
Please select a workspace folder for your project!

Directory: /opt/etas/VECU-BUILDER_Workspaces/

Selection: /opt/etas/VECU-BUILDER_Workspaces/

⇨ The `vEcuConf.yaml` configuration file opens.

⇨ Per default, this is the configuration file of the Simple example.



```
[redacted]:/opt/etas/VECU-BUILDER/ <version>  $ ./CreateWorkspace.sh
***********************************************************************
VECUBUILDER_HOME:     /opt/etas/VECU-BUILDER/<version>  /
VECUBUILDER_EXAMPLES: /opt/etas/VECU-BUILDER/Examples_<version>  /
***********************************************************************
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
#######################################################################
### Creating new workspace                                          ###
#######################################################################
[08:18:13] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
New project path is "/opt/etas/VECU-BUILDER_Workspaces/SimpleExample".
[08:19:24] 2 of 3: Creating project template
[08:19:24] 3 of 3: Please update "vEcuConf.yaml"
Please save and close the editor after editing "vEcuConf.yaml"
```

```
     /opt/etas/VECU-BUILDER_Workspaces/SimpleExample/vEcuConf.yaml
###############################################################################
# The version of the .yaml file schema                                        #
###############################################################################
version: [redacted]

###############################################################################
# build_sources or import_compiled                                            #
# build_sources: You import sources, header files, static libraries and let   #
#                prvEcuBuild compile, link and build a dll.                   #
#                The dll will be named <fmu_name>.dll.                        #
# import_compiled: Just import a dll, wrap it with a fmu wrapper, setup the   #
#             inputs, outputs and tasks.                                      #
###############################################################################
```

5. Keep the configuration file as is and close it.

⇨ Your new workspace is now created.

The process will automatically continue with the next stage.

5.2 Importing files and folders

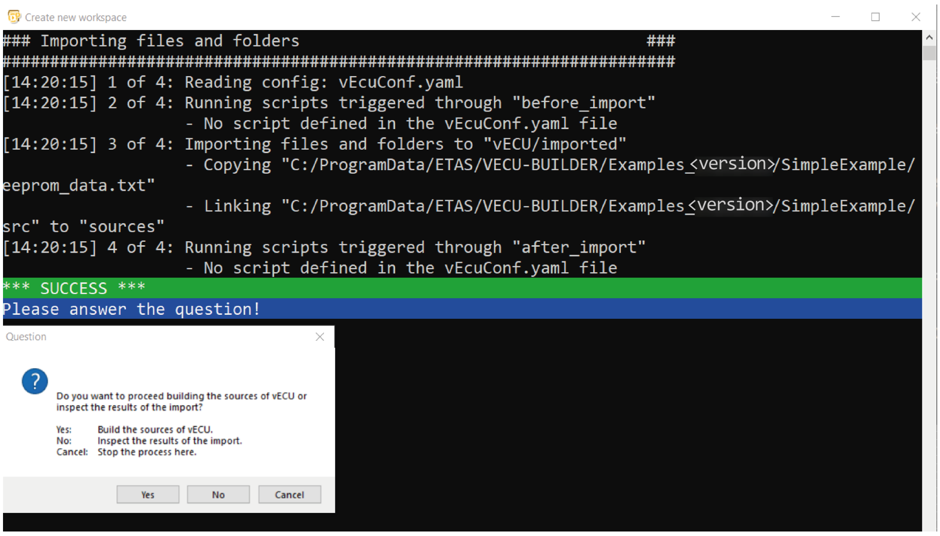
During this stage, the sources defined in your `vEcuConf.yaml` file are copied into `vEcu/imported` folder in your workspace.

> **Note**
>
> During the import stage, files and folders get copied into the workspace. For reasons of portability, it is recommended to create workspaces that are self-contained.

After successful completion of the previous stage Creating a new workspace you were forwarded to the next stage (Importing files and folders) and the process continues.

If you work in an already existing workspace, you can trigger this stage by running `1_Import.bat` on **Windows** or `1_Import.sh` on **Ubuntu 22.04 LTS**.

After successful completion of this stage, a dialog opens. It asks whether you want to continue with the next stage Building the vECU or inspect the results of this stage.

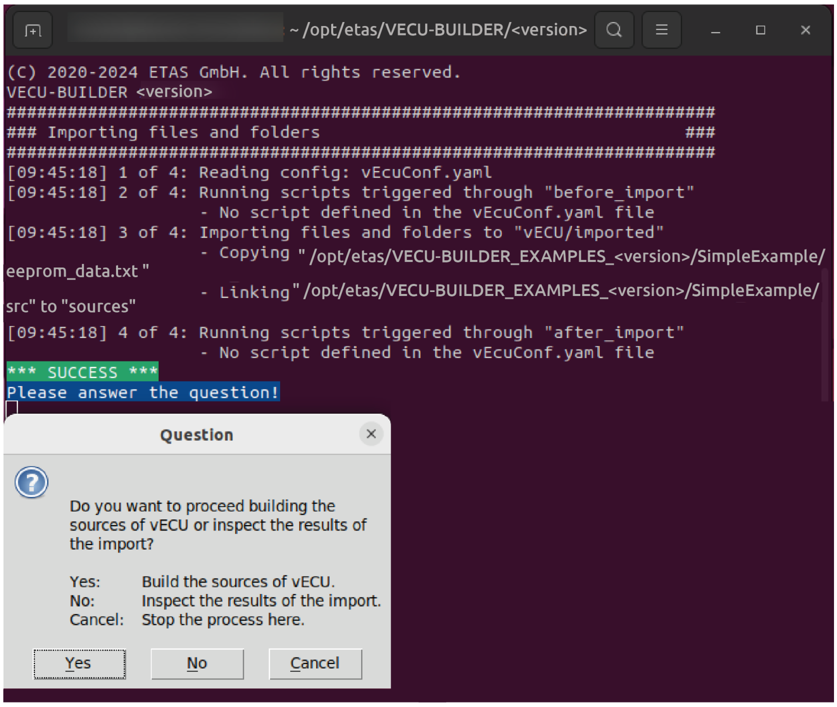


```
### Importing files and folders                                      ###
######################################################################
[14:20:15] 1 of 4: Reading config: vEcuConf.yaml
[14:20:15] 2 of 4: Running scripts triggered through "before_import"
                   - No script defined in the vEcuConf.yaml file
[14:20:15] 3 of 4: Importing files and folders to "vECU/imported"
                   - Copying "C:/ProgramData/ETAS/VECU-BUILDER/Examples_<version>/SimpleExample/
eeprom_data.txt"
                   - Linking "C:/ProgramData/ETAS/VECU-BUILDER/Examples_<version>/SimpleExample/
src" to "sources"
[14:20:15] 4 of 4: Running scripts triggered through "after_import"
                   - No script defined in the vEcuConf.yaml file
*** SUCCESS ***
Please answer the question!
```

Do you want to proceed building the sources of vECU or inspect the results of the import?

Yes: Build the sources of vECU.
No: Inspect the results of the import.
Cancel: Stop the process here.

Fig. 5-3: Proceed with vECU Build dialog or inspect the results (Windows)



[redacted] ~ /opt/etas/VECU-BUILDER/<version>

```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Importing files and folders                                    ###
######################################################################
[09:45:18] 1 of 4: Reading config: vEcuConf.yaml
[09:45:18] 2 of 4: Running scripts triggered through "before_import"
                   - No script defined in the vEcuConf.yaml file
[09:45:18] 3 of 4: Importing files and folders to "vECU/imported"
                   - Copying " /opt/etas/VECU-BUILDER_EXAMPLES_<version>/SimpleExample/
eeprom_data.txt "
                   - Linking" /opt/etas/VECU-BUILDER_EXAMPLES_<version>/SimpleExample/
src" to "sources"
[09:45:18] 4 of 4: Running scripts triggered through "after_import"
                   - No script defined in the vEcuConf.yaml file
*** SUCCESS ***
Please answer the question!
```

Question

Do you want to proceed building the sources of vECU or inspect the results of the import?

Yes: Build the sources of vECU.
No: Inspect the results of the import.
Cancel: Stop the process here.

Fig. 5-4: Proceed with vECU Build dialog or inspect the results (Ubuntu 22.04 LTS)

1. Click **Yes**.

⇨ Your new workspace is now created.

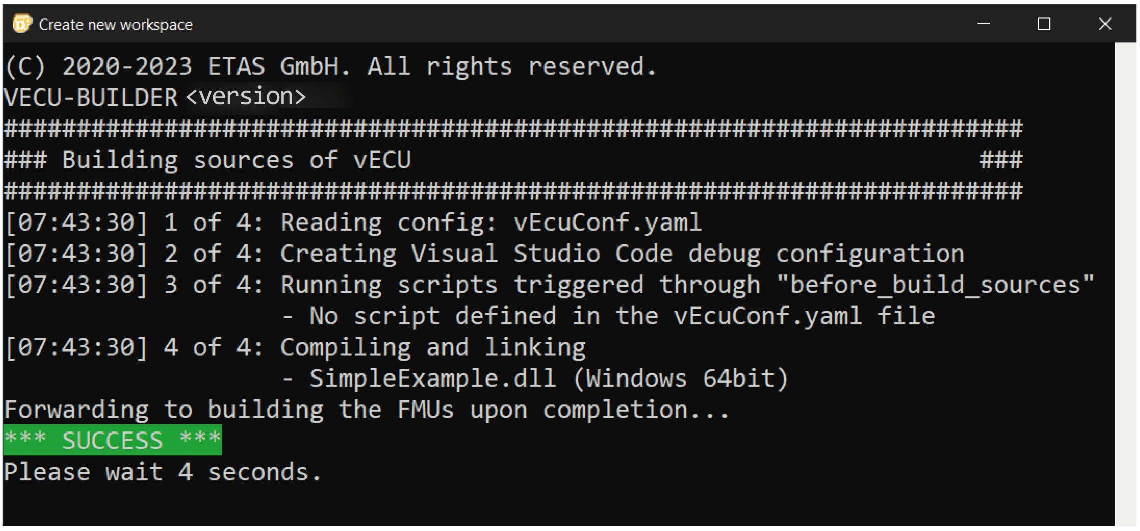
The process will continue with the next stage.

5.3 Building the vECU

During this stage, the sources imported into your workspace are compiled. Also they are linked into a DLL/SO file forming the core functionality of your future vECU.

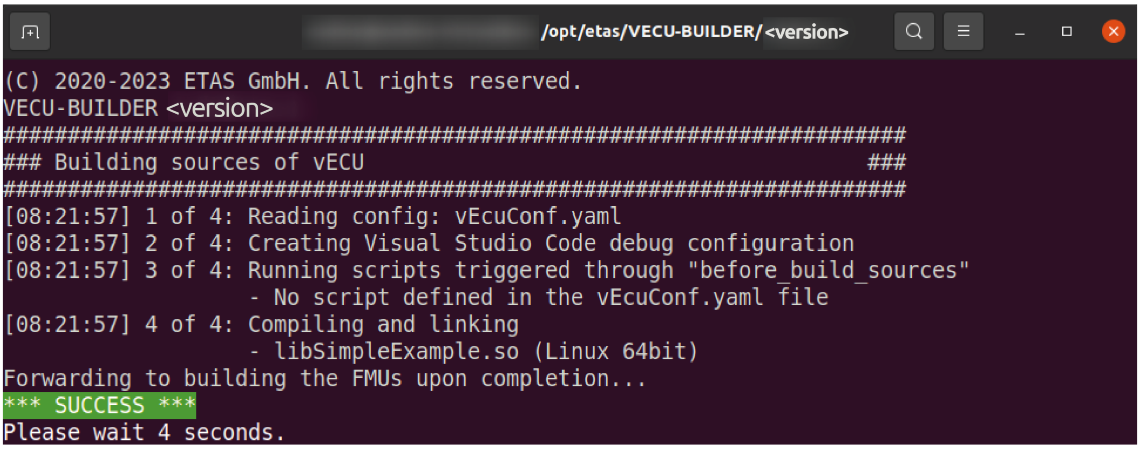
After successful completion of the previous stage Importing files and folders and selecting to proceed with the build of the vECU you are forwarded to the next stage (Building the FMU) and the process continues.

If you work in an already existing workspace, you can trigger this stage by running `2_Build.bat` on **Windows** or `2_Build.sh` on **Ubuntu 22.04 LTS**.



```
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Building sources of vECU                                       ###
######################################################################
[07:43:30] 1 of 4: Reading config: vEcuConf.yaml
[07:43:30] 2 of 4: Creating Visual Studio Code debug configuration
[07:43:30] 3 of 4: Running scripts triggered through "before_build_sources"
                   - No script defined in the vEcuConf.yaml file
[07:43:30] 4 of 4: Compiling and linking
                   - SimpleExample.dll (Windows 64bit)
Forwarding to building the FMUs upon completion...
*** SUCCESS ***
Please wait 4 seconds.
```

Fig. 5-5: Building vECU completed (Windows)



```
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Building sources of vECU                                       ###
######################################################################
[08:21:57] 1 of 4: Reading config: vEcuConf.yaml
[08:21:57] 2 of 4: Creating Visual Studio Code debug configuration
[08:21:57] 3 of 4: Running scripts triggered through "before_build_sources"
                   - No script defined in the vEcuConf.yaml file
[08:21:57] 4 of 4: Compiling and linking
                   - libSimpleExample.so (Linux 64bit)
Forwarding to building the FMUs upon completion...
*** SUCCESS ***
Please wait 4 seconds.
```

Fig. 5-6: Building vECU completed (Ubuntu 22.04 LTS)

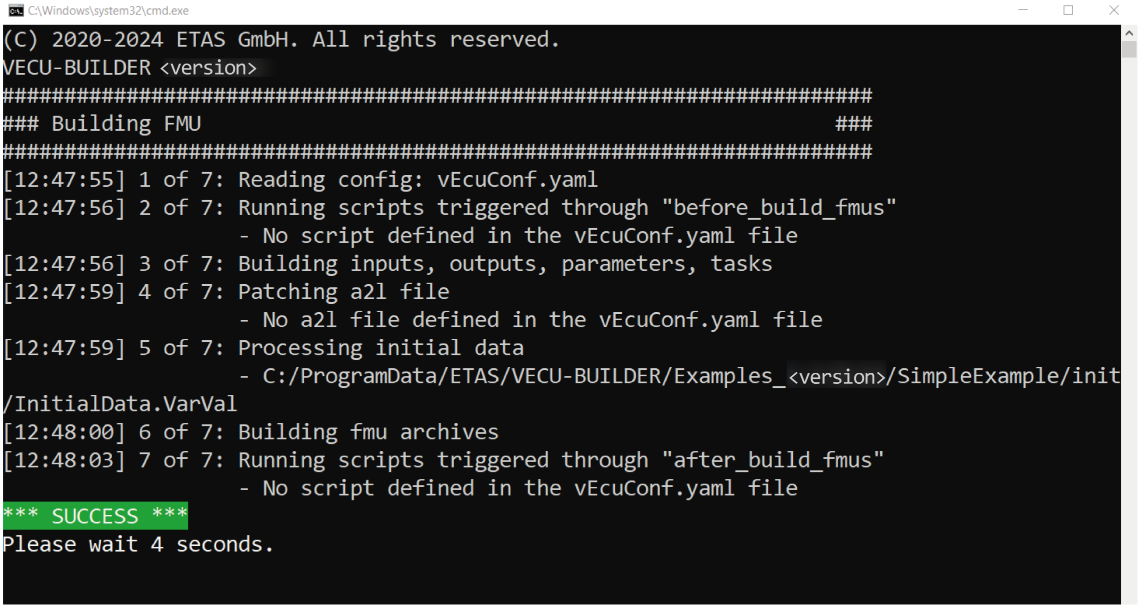
The process will automatically continue with the next stage.

If the process will not automatically continue with the next stage and error messages are displayed, see Building sources failed for more information.

5.4 Building the FMU

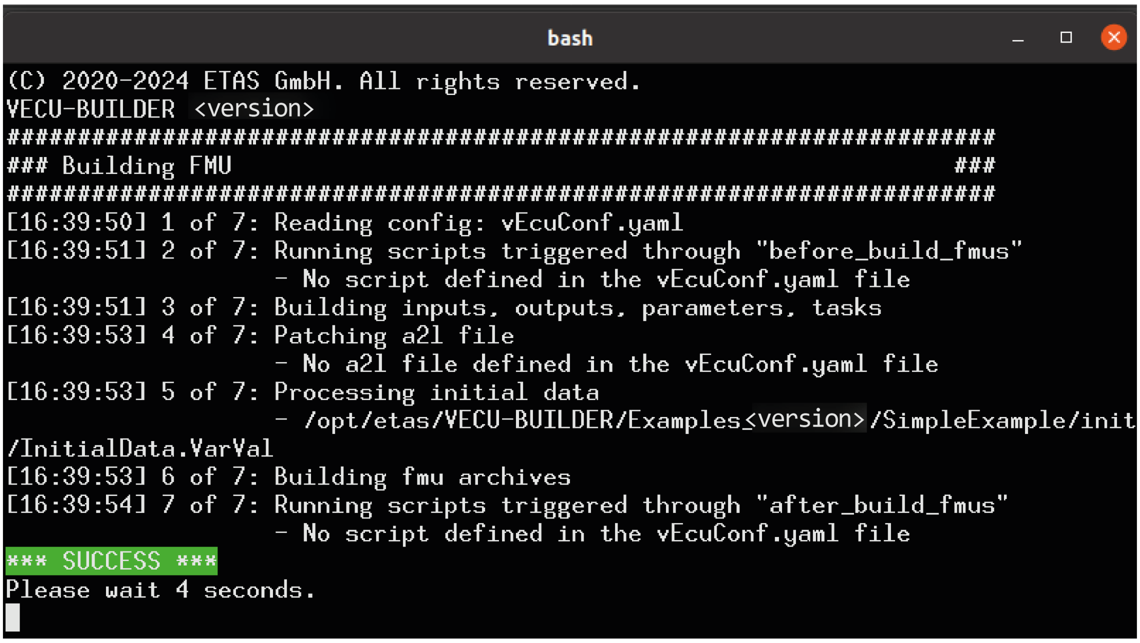
During this stage, the DLL/SO file created in the previous stage will be wrapped into an FMU container representing your vECU.

After successful completion of the previous stage Building the vECU and selecting to proceed with the build of the vECU you were forwarded to the next stage (Building the FMU) where the process completes.



```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
#######################################################################
### Building FMU                                                    ###
#######################################################################
[12:47:55] 1 of 7: Reading config: vEcuConf.yaml
[12:47:56] 2 of 7: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[12:47:56] 3 of 7: Building inputs, outputs, parameters, tasks
[12:47:59] 4 of 7: Patching a2l file
                   - No a2l file defined in the vEcuConf.yaml file
[12:47:59] 5 of 7: Processing initial data
                   - C:/ProgramData/ETAS/VECU-BUILDER/Examples_<version>/SimpleExample/init
/InitialData.VarVal
[12:48:00] 6 of 7: Building fmu archives
[12:48:03] 7 of 7: Running scripts triggered through "after_build_fmus"
                   - No script defined in the vEcuConf.yaml file
*** SUCCESS ***
Please wait 4 seconds.
```

Fig. 5-7: Building FMU completed (Windows)

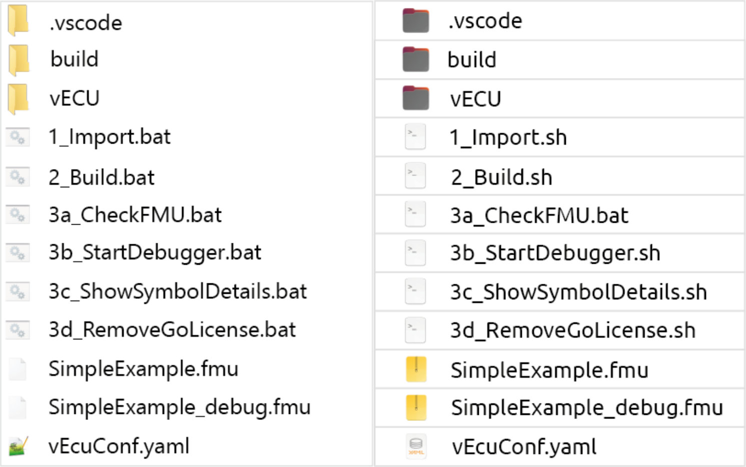


```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
#######################################################################
### Building FMU                                                    ###
#######################################################################
[16:39:50] 1 of 7: Reading config: vEcuConf.yaml
[16:39:51] 2 of 7: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[16:39:51] 3 of 7: Building inputs, outputs, parameters, tasks
[16:39:53] 4 of 7: Patching a2l file
                   - No a2l file defined in the vEcuConf.yaml file
[16:39:53] 5 of 7: Processing initial data
                   - /opt/etas/VECU-BUILDER/Examples_<version>/SimpleExample/init
/InitialData.VarVal
[16:39:53] 6 of 7: Building fmu archives
[16:39:54] 7 of 7: Running scripts triggered through "after_build_fmus"
                   - No script defined in the vEcuConf.yaml file
*** SUCCESS ***
Please wait 4 seconds.
```

Fig. 5-8: Building FMU completed (Ubuntu 22.04 LTS)

5.5 Workspace content

You have now successfully created the VECU-BUILDER workspace and built your first vECU based on the provided Simple Example sources. In this chapter, you find a description of the workspace content for Windows, Ubuntu 22.04 LTS and Ubuntu 22.04 LTS on WSL.



.vscode	.vscode
build	build
vECU	vECU
1_Import.bat	1_Import.sh
2_Build.bat	2_Build.sh
3a_CheckFMU.bat	3a_CheckFMU.bat
3b_StartDebugger.bat	3b_StartDebugger.sh
3c_ShowSymbolDetails.bat	3c_ShowSymbolDetails.sh
3d_RemoveGoLicense.bat	3d_RemoveGoLicense.sh
SimpleExample.fmu	SimpleExample.fmu
SimpleExample_debug.fmu	SimpleExample_debug.fmu
vEcuConf.yaml	vEcuConf.yaml

Fig. 5-9: Workspace contents

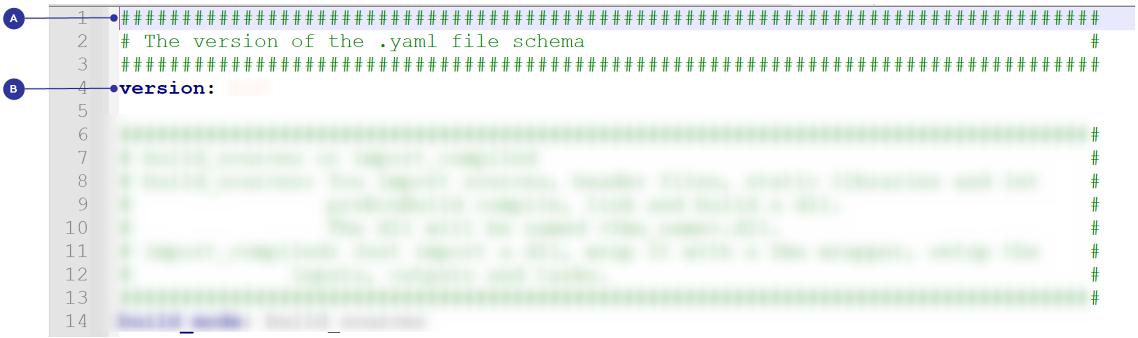
The content of the workspace consists of several artefacts:

- `vscode` folder:
  - `launch.json` file for vECU debugging in VS Code
- `build` folder:
  - `additional_scripts` folder: Location for your project specific additional scripts
  - `log` folder:
    Log files from executed stages
  - `scripts` folder: Batch and shell scripts to perform the individual stages
  - `last_build_footprint.txt`: Details of last performed build stage
  - `RawSymbolDetails.txt`: Subset of `SymbolDetails` and for internal purposes only
  - `SymbolDetails.txt`: Symbols within your sources and their attributes
- `vECU` folder:
  - `buildArtifacts` folder: Library file and its associated debug information
  - `CMake` folder: CMake project artifacts
  - `imported` folder: All imported artifacts
  - `CMakeLists.txt`: Set of directives and instructions for building your sources
- `1_Import.bat`/`1_Import.sh`
  File to trigger the Importing files and folders stage.

- `2_Build.bat/2_Build.sh`
  File to trigger the Building the vECU stage.
- `3a_CheckFMU.bat/3a_CheckFMU.sh`
  File to call fmusim and inspect the vECU outputs.
- `3b_StartDebugger.bat/3b_StartDebugger.sh`
  File to call MSVC or VS Code as debugger.
- `3c_ShowSymbolDetails.bat/3c_ShowSymbolDetails.sh`
  File to call Notepad++/new Terminal and display the Symbol Details.
- `3d_RemoveGoLicense.bat/3d_RemoveGoLicense.sh`
  File to remove the GO license from the vECU (only relevant if vECU was built with GO-license).
- `SimpleExample.fmu`
  Release version of your vECU, for more information, see Simple example.
- `SimpleExample_debug.fmu`
  Debug version of your vECU, for information, see Simple example.
- `vEcuConf.yaml`
  YAML configuration file, for more information, see Configuration.

5.6 Configuration

The YAML file contains the configurations for the import and build process as well as for the vECU itself. It is the only configuration you need to create and maintain. The YAML file is divided into several sections, each section configuring a particular attribute. You are guided through the YAML file with comments on each section and configuration attributes. Every section is structured in a standardized way:



```
##################################################################################
# The version of the .yaml file schema                                           #
##################################################################################
version:
```

A: comment with information on the corresponding section

B: configuration attributes and values

The following is a list of all attributes available in the YAML file:

- `version`

  This is the version of the used YAML file schema and must not be changed.

- `build_mode`

  You can select between 2 modes:

  `build_sources`: You import source code (either as AUTOSAR Classic compliant or legacy C-code), header files, and static libraries. VECU-BUILDER then builds your vECU in the form of an FMU container.

  The vECU will be named `<fmu_name>.fmu`.

  `import_compiled`:

  You import an existing, already compiled and linked, software in the form of a DLL/SO containing the functionality of your vECU. VECU-BUILDER then wraps it in an FMU container. VECU-BUILDER sets up the inputs, outputs and tasks, patches the A2L file, sets up the XCP slave port, etc.

- `fmu_name`

  Enter the name of your vECU.

  The code of your vECU is located inside the FMU in the folder `resources/<fmu_name>.dll/so`.

  This and other DLL/SO files are loaded and executed by the FMU runner.

- `import_into_project`

  Enter the paths to the files and folders to be imported.

You can specify paths to folders and/or individual files such as `*.c`, `*.h`, `*.cpp`, `*.hpp` or `*.zip` archives which will be extracted during import.

The import target is `vEcu/imported` folder in your workspace.

You can use environment variables like this:

"`${VECUBUILDER_EXAMPLES}\SimpleExample\eeprom_data.txt`"

- `link_into_project`

  To create a symbolic link; use `link_into_project`.

  A symbolic link is a reference to a file or directory in a file system. A symbolic link is created to the default folder `vEcu/imported` from another directory. This can be either the `source` directory or optionally a `destination` subdirectory in `vEcu/imported` folder. You can also create nested folders.

  `source`: Source of the folder to be linked.

  `destination`: Name of the linked folder or name of the linked nested folder.

  You can use environment variables like this:
  `${SomeEnvironmentVariable}`

  If you do not state a destination, the source will be linked in `vECU/imported/NameOfSource`.

  For more information about link_into_project, see Usage of link_into_project.

- `import_external_compiled_vecu`

  Only needed if you selected `import_compiled` as `build_mode`.

  That DLL/SO already contains the code of your vECU. You can skip the compiling and linking and just import your DLL/SO into the FMU wrapper. Here you enter the DLL/SOname and the path for updates:

  `dll_so_name`: The name of the DLL/SO. There must exist a corresponding PDB file with the same filename.

  `get_updates_from`: If VECU-BUILDER can find a DLL/SO and the PDB file in this folder, it will update the imported DLL/SO.

  You can use environment variables like this:"`${SystemDrive}/Sandbox`".

- `additional_resources`

  You can use additional resources to resolve dependencies by integrating DLL/SO libraries that your software relies on into the build and execution process. You can reference the necessary files and folders for the vECU assembly to function properly. When adding resources, copy folders recursively (including their contents) to the root of the resources folder, while copying files directly to the root of the resources folder. There is no limit to the number of additional resources you can inc

> **Note**
>
> additional_resources does not support wildcards.

Specify all additional resources that are to be included in the FMU. Additional resources will be copied to the resources folder of the FMU during the Building FMU stage i.e.

`${VECUBUILDER_WORKSPACE}/vECU/imported/additional_DLLs/UsedByVECU.dll` for **Windows**

or

`${VECUBUILDER_WORKSPACE}/vECU/imported/additional_DLLs/UsedByVECU.so` for **Ubuntu 22.04 LTS**.

You can use and include plug-ins as additional resources the same way. For more information, see Template for plug-in V1 (FMI2) and Template for plug-in V2 (FMI3).

- `architecture`

  Specify the architecture.

  When importing sources, the setting of this attribute has to match the integration and simulation system where the vECU is to be used.

  In case you are importing an DLL/SO precompiled for either 32-bit or 64-bit architecture, you need to set the attribute to the same.

  > **Note**
  >
  > For Ubuntu 22.04 LTS only 64-bit is supported.

- `xcp_slave`

  Enter the port and IP address of the XCP slave to be setup in your vECU.

  These values are transferred to the patched A2L file. The used protocol is TCP. For more information, see A2L file patching.

  > **Note**
  >
  > You can only use a socket (IP address + port + protocol) for the XCP connection between INCA and XCP slave once.
  >
  > If a port is busy, you must define another port in the YAML file.

- `operating_system`

  Enter the operating system. Currently Windows and Ubuntu 22.04 LTS supported.

- `build_tool`

  Set up the build tool to be used for your build.

  Built tool differs between Windows and Ubuntu 22.04 LTS.

Windows

> **Note**
>
> VECU-BUILDER configures the build tool for the underlying CMake.

If you select Visual Studio, a Visual Studio solution is generated.

If you select MinGW Makefiles, a CMake project is generated.

These artefacts are stored in `vECU/CMake` folder in your workspace.

- `path_to_mingw`: If you define a specific MinGW version, CMake builds the sources using that MinGW version.

  Ubuntu 22.04 LTS

  You can select Unix Makefiles.

- `cmake_generator_toolset`

  Define which toolset should be used by CMake during the build process.

  For more information, see CMAKE_GENERATOR_TOOLSET.

- `inputs, outputs, parameters, locals`

  Enter the variables you want to expose as ports of your FMU.

  Inputs, outputs, parameters, and locals refer to the causality of the FMI.

  You can use wildcards (`*` and `?`) in your expressions. You can add arrays and structures using `myArray*`. If your wildcard expression breaks the YAML compatibility, enclose it in single apostrophes.

  EXAMPLE

  `*a` finds all symbols ending with an a.

  You can define aliases for variables, which results in renaming of FMI ports. The aliases are used in `modelDescription.xml` and the original variable names are used in `resources.txt`.

  > **Note**
  >
  > Variables of type `enumeration` will be interpreted as integers in `modelDescription.xml` file of the FMU. The name-value mapping of enumerations will be ignored when enumerations are used as interfaces. Only the integer value will be exchanged.

- `initial_data`

  To define the initial values of calibration variables, enter the path for source and target destination

  The initial data is virtually flashed into memory during initialization. The data file in the FMU (defined by destination) is read and its values are written to RAM. This simulates a part of the NVRAM (non-volatile RAM).

  `source`: Location to obtain the file. During build time this file will be copied from source.

`destination`: Where to store the file inside the FMU, relative to the resources folder of the FMU (optional). This file is used during run-time.

`encoding`: Character encoding for DCM files (optional) specifies the standard used for text content within the file. If the encoding is not defined, the default UTF-8 encoding is used.

Supported formats:

`VarVal`: List of pairs separated by one space, where the `lhs` refers to the C variable and the `rhs` to the value.

`DCM`: Format containing ASAP2 labels and their values in physical form which are processed according to information in A2L file.

For more information, see InitialData functionality.

- `eeprom`

  Specify the eeprom simulation attributes.

  `source`: Path where to get the file. This is used during the build.

  `destination`: Path where to store the file relative to the resources folder of the FMU. This is the working copy (optional).

  `sync`: This can be a UNC path or a regular path name. When the vECU is initializing, this file is copied to `destination`, if it exists. When the vECU terminates, the updated file in `destination` is copied to the `sync` location (optional). To setup the UNC Path, see Windows cannot access localhost while using sync attribute in EEPROM.

  `c_variables`: The C variable names that store the eeprom data.

  Supported format:

  TXT: A line starting with # denotes a comment. All other lines contain the data stream to be flashed to the C variables. The order of the data stream lines corresponds to the order of the C variables listed. A data stream consists of bytes in HEX format, with each byte separated by a space.

  EXAMPLE

  01 02 ee 4f.

  In the default YAML file the sync is commented out.

  For more information about eeprom, see eeprom functionality.

- `arxml_tasks`

  To retrieve tasks from ARXML files in `vECU/imported` folder, use `arxml_tasks`. These tasks will be added to the tasks list.

  Supported events:

  - INIT-EVENT
  - TIMING-EVENT

  Per default, `arxml_tasks` are disabled. To enable `arxml_tasks` and place your ARXML files in the `imported` folder, use `enabled`. For more information about `arxml_tasks`, see ARXML-defined tasks.

- `tasks`

  > ⓘ **Note**
  >
  > Task functions must have no arguments.

  Define the tasks that are to be executed and their attributes. To simulate the microcontroller behavior with its periodically executed functions of your software, define the functions as tasks. You can define a task only once, duplicated functions will be ignored.

  `function_name`: "<function name>", without brackets, set in apostrophes, no arguments allowed.

  `trigger`: Select between cyclic, initial or terminate, the default is cyclic.

  `initial`: Functions are called from `fmi2DoStep` before cyclic tasks.

  `cyclic`: Functions are called from `fmi2DoStep` before terminate tasks. For more information about task scheduling with cyclic task trigger, see Task scheduling with task trigger defined as cyclic.

  > ⓘ **Note**
  >
  > The period of a cyclic task must not be less than 1 ns.

  `terminate`: Functions are called from `fmi2Terminate`.

  `fmi2_enter_init`: Functions are called from `fmi2EnterInitializationMode`.

  `fmi2_exit_init`: Functions are called from `fmi2ExitInitializationMode`.

  `period:` <number> [in seconds], the default is 1.0.

  `first_call`: <number> [in seconds] for the cyclic tasks, the default is period.

  `priority`: The lower the number, the higher the priority. The default is 0.

  > ⓘ **Note**
  >
  > If two functions run at the same time, the one with the lower priority runs first.

  `max_calls`: <number>, -1 means infinite, 0 means no call.

  `trigger_function`: The function is written in `Multiply.c`. You can use trigger_function only, if `trigger` is set to `event`. The trigger function predicts when the next event might occur and returns if the next events needs to be triggered. You can find the defined arguments of the trigger function in `Multiply.c` `trigger_inputs`: A list of additional inputs that refer to variables accessible via symbol details. Trigger inputs must be included in `SymbolDetails.txt`.

For more information, see EventTrigger example.

- `redirect_function_calls`

  Enter the names functions to be replaced and their substitutes.

  The function signatures of the two functions must be identical. This allows you to test the behavior of your software using alternative implementation without changing the original source code. Also you do not need to replace unfinished or hardware-dependent functions with mock functions.

  `replaced_function`: Enter the function name of the function to be replaced.

  `substitute_function`: The function name of the function that substitutes the replaced function.

  Note

  Sometimes `redirect_function_calls` does not work as expected. For more information, see additional_compile_flags in this chapter and Redirecting function calls did not work as expected.

- `build_include_filters, build_exclude_filters`

  Only usable if you selected `build_sources` as `build_mode`. You can select files and/or folders to be included or excluded in/from the vECU build process. Files are only included into the build if they are matched by at least one `build_include_filter` and are not matched by any `build_exclude_filter`.

- `assembly_list_files`

  Specify your assembly list files for the build process.

  Only the sources listed in a file will be passed to the compiler from the given sources defined by `build_include_filters` and `build_exclude_filters`.

  If you did not configured assembly list files, all sources are compiled.

- `additional_include_directories`

  Only usable if you selected `build_sources` as `build_mode`.

  Specify the path of the directory to be added with `additional_include_directories`. This directory will be included in the list of directories searched for include files. Additional include directories are passed to the preprocessor.

  Wildcards `*` and `?` are allowed. The environment variable `${VECUBUILDER_WORKSPACE}` points to the workspace.

- `additional_defines`

  Only usable if you selected `build_sources` as `build_mode`.

  Specify the preprocessor macro definitions you want to add. These definitions are passed to the preprocessor. This is useful if you need to set or unset some of the definitions to adapt them to the new Windows target.

  Brackets (', ') must be escaped as \(', '\).

- `additional_compile_flags`

  Only usable if you selected `build_sources` as `build_mode`. `additional_compile_flags` will be applied to C and C++.

  Specify how the compiler should work. Each individual flag must be written in a separate line and put in single apostrophes, for example. `/ZI`.

  The flags are written into the CMakeLists.

  For more information about compling, see MSVC compiler options or gcc compiler options.

  A successful use of `redirect_function_calls` depends on `additional_compile_flags`. Only if you set `additional_compile_flags` correctly, `redirect_function_calls` will work.

  To prevent the GNU compiler from using incompatible optimizations when `redirect_function_calls` feature is enabled, optimizations are disabled by using the following flags:

  `# - '-O0'` for gcc

  For more information, see Options that control optimization and Redirecting function calls did not work as expected.

- `additional_c_compile_flags`

  The same prerequisites as for "additional_compile_flags" above must be met. `additional_c_compile_flags` will be applied only to C.

  A successful use of `redirect_function_calls` depends on `additional_c_compile_flags`. Only if `additional_c_compile_flags` is set correctly, `redirect_function_calls` will work.

  To prevent the GNU compiler from using incompatible optimizations when `redirect_function_calls` feature is enabled, optimizations are disabled by using the following flags:

  `# - '-fhosted'`

- `additional_cxx_compile_flags`

  The same prerequisites as for additional_compile_flags must be met. `additional_cxx_compile_flags` will be applied only to C++.

  A successful use of `redirect_function_calls` depends on `additional_cxx_compile_flags`. Only if you set `additional_cxx_compile_flags` correctly, `redirect_function_calls` will work.

  To prevent the GNU compiler from using incompatible optimizations when `redirect_function_calls` feature is enabled, optimizations are disabled by using the following flags:

```
# - '-fpermissive'
```

- `additional_static_libraries`

  Only usable if you selected `build_sources` for `build_mode`.

  The libraries need to be located in the folder `./projects/vEcu/imported`.

- `environment_variables`

  You can define process-level environment variables that are set by the build process and by the FMI wrapper during the vECU execution.

  EXAMPLE

  ```
  PATH=c:/Temp;${PATH}
  ```

  You can configure and modify these variables in one location and you can access them from scripts and configuration files. Process-level environment variable of `VECUBUILDER_WORKSPACE` is created automatically during the build process with its value pointing to the current workspace.

- `import_additional_scripts`

  To include additional files, use `import_additional_scripts`.

  With `import_additional_scripts`, additional scripts are imported at the beginning of the import stage into the following target folder: `build/additional_scripts`

  You can define paths to single files and to folders. If you define a path to a folder, all files and subfolders in that folder are imported.

  You can use environment variables like this: `${SomeEnvironmentVariable`.

  ```
  - '${VECUBUILDER_EXAMPLES}/additional_scripts_library/'
  ```

- `additional_scripts`

  Define additional scripts to be executed at various phases of the import and/or the build stage.

  Use batch files on Windows/shell scripts on Ubuntu to simplify the execution of your project-specific scripts, such as those implemented in Python or Perl, if they are executable on your system. You can use these scripts for tasks such as file manipulation, adding files to the FMU archive, parsing etc..

  `command`:The script to be executed by the OS, the default search path is `${VECUBUILDER_WORKSPACE}/build/additional_scripts/` (utf-8 only).

  `trigger`: Select when your script should be executed from these options:

  - `before_import`
  - `after_import`

- `before_build_sources`
- `before_build_fmus`
- `after_build_fmus`

`priority:` Specify the priority at which your script should be executed. A lower number indicates a higher priority, with the default value set to 1.

For more information about `additional_scripts`, see Example of additional scripts - A2L characteristics as parameters.

– `patch_a2l_file`

You require an A2L file to connect an MCD software such as ETAS INCA to the running vECU. The A2L file needs to be located in the folder `vEcu/imported`.

`filename`: Enter the name of your A2L file to be patched.

– `symbol_name_mapping`

When you use A2L or DCM files, ASAP2 labels might differ from the symbol names. If both, DCM and A2L, files are provided, then for each DCM entry, an A2L entry of the identical ASAP2 label name must exist.

based_on_csv:

CSV file, where `lhs` is the symbol name and `rhs` is the ASAP2 label. The CSV file must follow the following format: `SYMBOL_name;ASAP2_label`. You need to use a semicolon as a delimiter.

When you use a CSV file, you can use simple string search & replace only. Ensure that there are no header or any comments in the CSV file and every line is treated as a data record.

> **Note**
>
> VECU-BUILDER removes all leading and trailing spaces before and after the first character.

EXAMPLE

`my_symbol ; ASAP2_LABEL_5`

This is a valid entry and will be treated as defined below:

`my_symbol;ASAP2_LABEL_5`

based_on_adx:

If a mapping between ASAP2 labels and symbols is available in an ADX file format (a proprietary format of Bosch, used exclusively within Bosch projects), you can include this file in the build to apply the mappings. When using the ADX file format for mappings, a simple string search and replace is applied.

Note

The content of an ADX file will be processed as is, no interpretation or validation will be performed by VECU-BUILDER. The file is assumed to be complete and correct.

based on symbol_link (only on Windows):

In A2L files, SYMBOL_LINK information refers to the linkage between symbols or variables defined in the file. It provides information about how different symbols are related or connected to each other.

based_on_assignments:

If the right side includes a dollarsign `$` (like in a reference to a group, e.g. (`$1`), then a regular expression search & substitute is applied. Else a simple string search and replace is applied.

One such regular expression allows to map multiple names at once. To see an example, see the following table.

RegEx	(array)\[(\d+)\]	->	$1_$2
Mapping	array[1]	->	array_1

The mappings can be verified by examining the JSON files appended to the debug FMU, located in `resources\mappings` folder.

VECU-BUILDER will update the memory addresses of entries in the provided A2L file. The original A2L file is renamed by appending `.bak` to its name. For more information, see A2L file patching and A2L name mapping.

- `debug_hook`

  Specify whether to enable or disable a debug hook. When enabled, the FMU execution is interrupted when the FMU is instantiated until a debugger is attached. For more information, see Debugging vECU.

- `additional_link_flags`

  Only usable if you selected `build_sources` as `build_mode`.

  Specify how the linker should work. You need to write each individual flag in a separate line and needs to be put in single apostrophes, i.e. `/DEBUG`.

  The flags are written into the `CMakeLists.txt`.

  For more information, see MSVC linker options or gcc linker options.

- `simple_file_modifications`

  Specify file modifications that must be applied to files imported in `vECU/imported` folder.

  In case you specify multiple modifications, they will be applied sequentially following the order in which they were specified.

  The next two attributes are mandatory for all types of modifications.

file_regex: Specify the search RegEx for a file or a set of files that must be modified.

trigger: Specify when the modification must be applied from the 2 below options:

- after_import (default)
- before_build_sources

You can specify a single or multiple actions (modification types) from the 4 below options:

- comment_line: Comment out a single line of code by adding // at the beginning of the line.
- search_and_replace: Replace a line of code that matches the Search_regex with the replacement.
- insert_code_above: Insert code above a matched line.
- insert_code_below: Insert code below a matched line.

You must specify line_regex and to which match(es) the modification are to be applied to (apply_to) for each action from the below 3 options:

- all_matches (default)
- last_match
- first_match

For insert_code_above and insert_code_below, you must specify the code section that is to be inserted.

When youuse simple_file_modifications, consider the following procedure to ensure that modifications are not included in .bak file.

1. Get the set of files and apply the file filter.

2. Revert backups for all files to be modified: Move the .bak files to overwrite the normal filename.

→ The backup file is deleted.

3. Create the backup on all files that need to be modified, excluding files ending with .bak.

4. Apply the file modifications to all files that need to be modified.

ⓘ **Note**

If you need more sophisticated file modifications, use a project-specific script via the additional_scripts.

– include_symbol_details

The use of plug-ins may require that the release FMU contains symbol information.

EXAMPLE

If you want to change the cycle time of "task_10ms" using a plug-in, then the symbol name "task_10ms" must be disclosed in the release vECU.

For more information about release FMU, see Difference between debug and release vECUs and Keeping symbol information in a release FMU.

fmi_<type>: disabled (default) or enabled. When enabled, all symbol details of that fmi type will be included.

symbol_names: All symbol details matching the regular expressions will be included.

- fmi

  You can use the functional mockup interface. Default version is 2.0. The use of version 3.0 is also possible. Follow the convention below:

  ```
  #fmi: '2.0'
  ```

  For more information about FMI,see FMI standard.

6 Exploring the examples/templates

This chapter contains details on examples/templates that are designed to help you familiarize with the features of VECU-BUILDER.

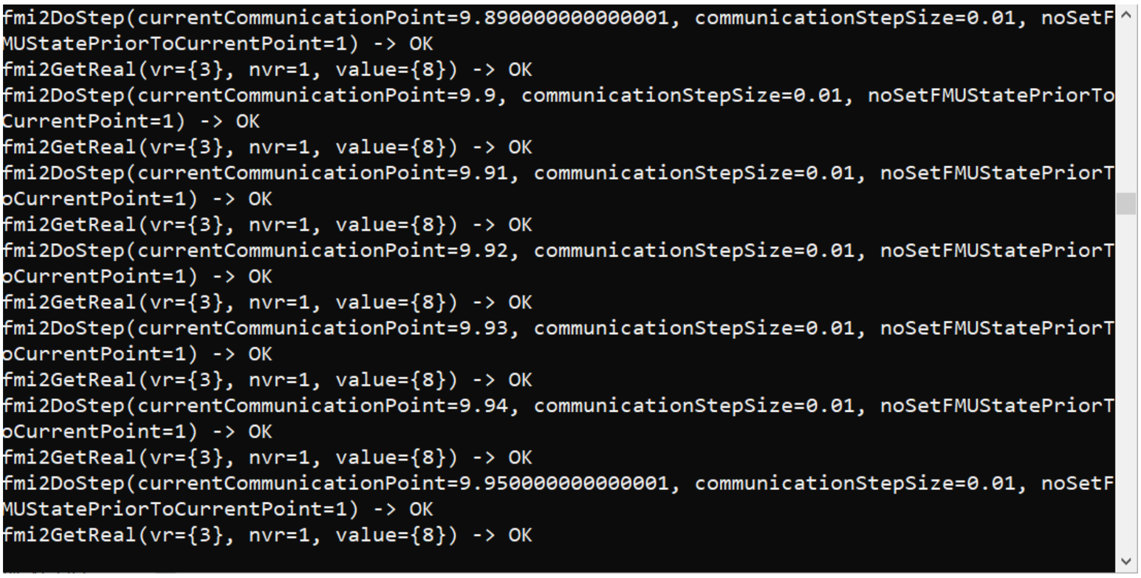
6.1 Simple example

If you followed the instructions in the chapter Working with VECU-BUILDER, you now have a workspace on your computer based on the Simple Example.

6.1.1 fmusim

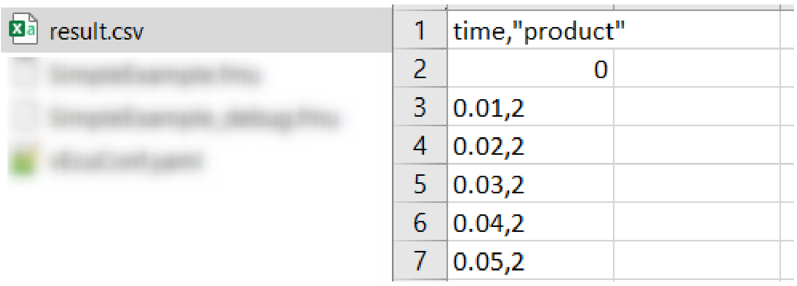
To conduct a quick smoke test of the created vECU, fmusim is delivered along with VECU-BUILDER. You can invoke this software via the `3a_CheckFMU.bat` on **Windows** or `3a_CheckFMU.sh` on **Ubuntu 22.04 LTS**. Execute this file to run the release vECU. Alternatively, you can drag-and-drop the debug vECU into this batch/shell script file to run the debug vECU.

fmusim opens a terminal and prints the simulation outputs.



```
fmi2DoStep(currentCommunicationPoint=9.890000000000001, communicationStepSize=0.01, noSetF
MUStatePriorToCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.9, communicationStepSize=0.01, noSetFMUStatePriorTo
CurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.91, communicationStepSize=0.01, noSetFMUStatePriorT
oCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.92, communicationStepSize=0.01, noSetFMUStatePriorT
oCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.93, communicationStepSize=0.01, noSetFMUStatePriorT
oCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.94, communicationStepSize=0.01, noSetFMUStatePriorT
oCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
fmi2DoStep(currentCommunicationPoint=9.950000000000001, communicationStepSize=0.01, noSetF
MUStatePriorToCurrentPoint=1) -> OK
fmi2GetReal(vr={3}, nvr=1, value={8}) -> OK
```

Fig. 6-1: fmusim output



result.csv

1	time,"product"	
2	0	
3	0.01,2	
4	0.02,2	
5	0.03,2	
6	0.04,2	
7	0.05,2	

Fig. 6-2: Cutout of result.csv

An FMU, that is built by VECU-BUILDER will set the environment variable `VECUBUILDER_FMURESOURCES`. The environment variable is set for the process that runs the FMU. It is not set on system-level or user-level.

This environment variable stores the absolute path to the `resources` folder of the FMU. You can find the environment variable when inspecting the process properties in a process monitor software.

6.1.2 Difference between debug and release vECUs

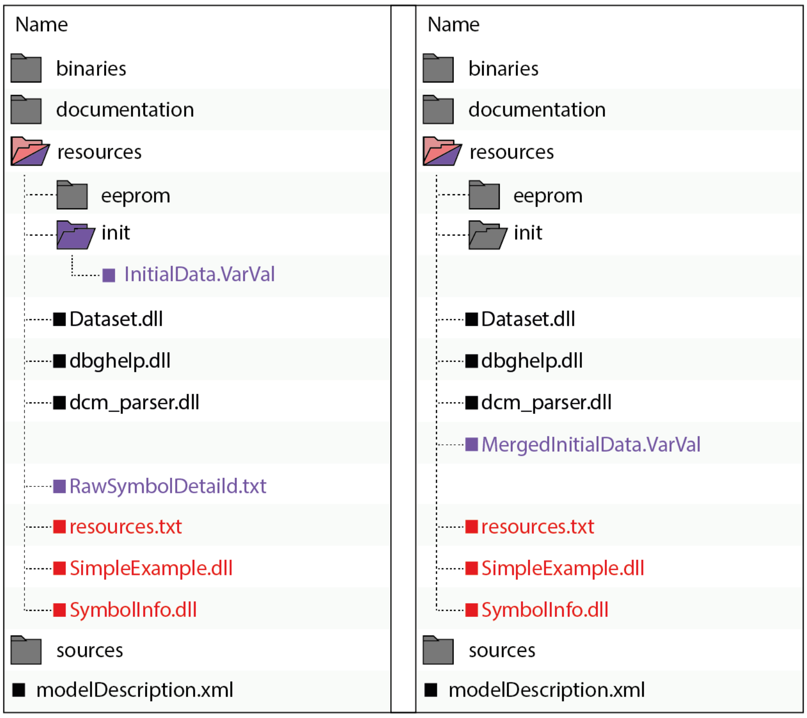
You find two FMUs in this workspace. One named `SimpleExample.fmu` (which will be referred to as release vECU and the other one named `SimpleExample_debug.fmu` (which will be referred to as debug vECU).

Extract each of these two FMU archives into its own folder and explore their contents and differences.

The functional behavior of both vECUs is identical.

The debug vECU contains symbol information and additional artefacts, e.g., PDB (when build tool is MSVC) or DIE (when build tool is MinGW). To debug and step through your code, use the debug vECU.

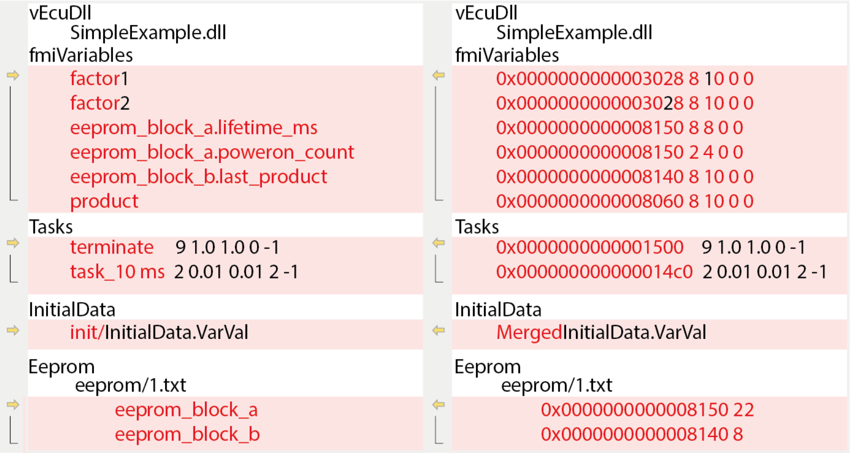
When you compare the two extracted folders, you can notice that the main difference is in the resources folder.



Name	Name
binaries	binaries
documentation	documentation
resources	resources
eeprom	eeprom
init	init
InitialData.VarVal	
Dataset.dll	Dataset.dll
dbghelp.dll	dbghelp.dll
dcm_parser.dll	dcm_parser.dll
	MergedInitialData.VarVal
RawSymbolDetaild.txt	
resources.txt	resources.txt
SimpleExample.dll	SimpleExample.dll
SymbolInfo.dll	SymbolInfo.dll
sources	sources
modelDescription.xml	modelDescription.xml

Fig. 6-3: Comparison of debug and release vECU (GCC compiler)

The release vECU exclusively includes address information, while the debug vECU contains both variables and function names. The release vECU protects the IP contained in the vECU and does not contain symbol information. To share your vECU, use the release vECU.



```
vEcuDll
      SimpleExample.dll
fmiVariables
      factor1
      factor2
      eeprom_block_a.lifetime_ms
      eeprom_block_a.poweron_count
      eeprom_block_b.last_product
      product
Tasks
      terminate    9 1.0 1.0 0 -1
      task_10 ms  2 0.01 0.01 2 -1

InitialData
      init/InitialData.VarVal

Eeprom
       eeprom/1.txt
             eeprom_block_a
             eeprom_block_b
```

```
vEcuDll
      SimpleExample.dll
fmiVariables
      0x0000000000003028 8 10 0 0
      0x0000000000003028 8 10 0 0
      0x0000000000008150 8 8 0 0
      0x0000000000008150 2 4 0 0
      0x0000000000008140 8 10 0 0
      0x0000000000008060 8 10 0 0
Tasks
      0x0000000000001500    9 1.0 1.0 0 -1
      0x00000000000014c0  2 0.01 0.01 2 -1

InitialData
      MergedInitialData.VarVal

Eeprom
       eeprom/1.txt
             0x0000000000008150 22
             0x0000000000008140 8
```

Fig. 6-4: Comparison of resources.txt

6.1.2.1 Keeping symbol information in a release FMU

When using a plug-in in your vECU, variables and functions are accessed by name. This is possible in a debug FMU, but not in a release FMU.

Searching for symbols in the plug-in it is done by name. In the release FMU all symbols names are replaced by their memory addresses. When FMU Runner runs in release mode, it accesses the symbols directly by addresses instead of symbol names. As a result, SymbolDetails file like `RawSymbolDetails.txt` file has to be kept in `release.fmu` file

> **Note**
>
> The release FMU does not contain the PDB/DWARF file. Thus, debugging the release FMU is not possible. `RawSymboldetails.txt` is a subset of `SymbolDetails.txt` and is used by the plug-in.

For more information, see include_symbol_details in configuration chapter.

For more information about the plug-in Feature, see Template for plug-in V1 (FMI2) and "Template for plug-in V2 (FMI3)" on page 88.

6.1.3 InitialData functionality

Usually, software function and its data are separated. While the logic of the software function is defined in the source files, the data is stored in separate files in various formats. Common formats for such calibration data are DCM and CDF.

VECU-BUILDER provides support of DCM format. For more information about DCM Format, see DCM file format. A DCM file stores the data in their physical form which typically need to be processed into ECU-internal form. This processing is done based on COMPU_METHOD and RECORD_LAYOUT entries in an A2L file. You need to provide the A2L file in the `patch_a2l_file` attribute in the YAML file.

In case the Symbols do not match the ASAP2 labels (entries in the DCM and A2L files), you can resolve this by applying mappings. These mappings are then used to map ASAP2 labels to their respective symbols and can be defined in one of these three ways:

- direct definition in the YAML file making use of regular expressions
- via ADX file
- via CSV file
- via symbol_link (only available for Windows)

For more information about these options, see symbol_name_mapping section in configuration chapter.

You also can define the initial data in the VARVAL format. These initial data will not be processed based on entries in the A2L file neither will any mapping be applied. Thus the VARVAL file must contain the symbols and the ECU-internal values.

Simple example contains sample files of both supported formats. You can find the files in this folder:

`C:/ProgramData/ETAS/VECU-BUILDER/Examples_1.8.0/SimpleExample/init` on **Windows**

or

`/opt/etas/VECU-BUILDER/Examples_1.8.0` on **Ubuntu 22.04 LTS.**

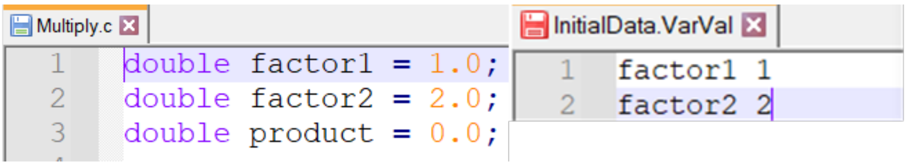
The `vEcuConf.yaml` file is preconfigured and uses the `InitialData.VarVal`.

To experiment with VARVAL functionality

1. Open `Multiply.c` file located within your workspace in `vECU/imported` folder.

   The `Multiply.c` file contains the variable definitions. The variables **factor1** and **factor2** serve as the inputs, with assigned values of 1 and 2. The variable **product** serves as the output and is calculated as the product of **factor1** and **factor2**.

   As `InitialData.VarVal` file is already activated in the YAML file, it is already used in the default Simple Example vECU.



```
double factor1 = 1.0;
double factor2 = 2.0;
double product = 0.0;
```

```
factor1 1
factor2 2
```

2. Close the source file and navigate back to the workspace.
3. Check the output using

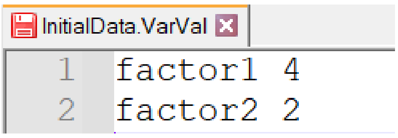
   `3a_CheckFMU.bat` on **Windows**

   or

   `3a_CheckFMU.sh` on **Ubuntu 22.04 LTS**, described in fmusim.

⇨ The output for SimpleExample is 2.

4. Change the value for factor 1 to 4.



```
factor1 4
factor2 2
```

5. Save the change.
6. Rebuild the vECU using

   `2_Build.bat` in the workspace on **Windows**

   or

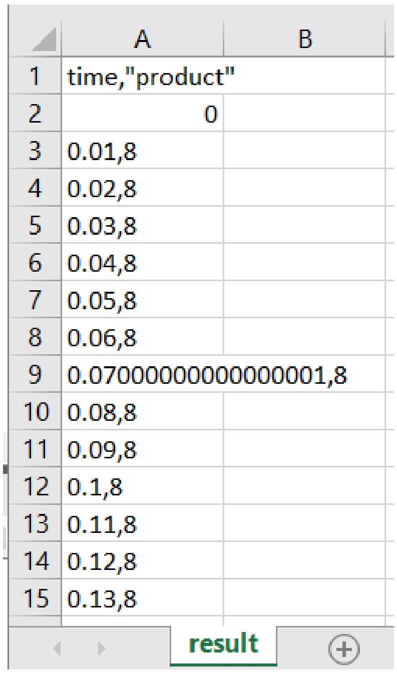
   `2_Build.sh` in the workspace on **Ubuntu 22.04 LTS**.
7. To show the changed output in the FMU, execute

   `3a_CheckFMU.bat` on **Windows**

   or

   `3a_CheckFMU.sh` on **Ubuntu 22.04 LTS**.

⇨ The new output is now 8.



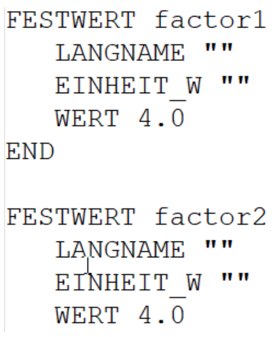
	A	B
1	time,"product"	
2	0	
3	0.01,8	
4	0.02,8	
5	0.03,8	
6	0.04,8	
7	0.05,8	
8	0.06,8	
9	0.07000000000000001,8	
10	0.08,8	
11	0.09,8	
12	0.1,8	
13	0.11,8	
14	0.12,8	
15	0.13,8	

⇨ The initial data set in the VARVAL file are thus correctly used in the vECU.

⇨ The sources in `Multiply.c` stay the same. The variables are overwritten at run time by the values of the `InitialData.VarVal`.

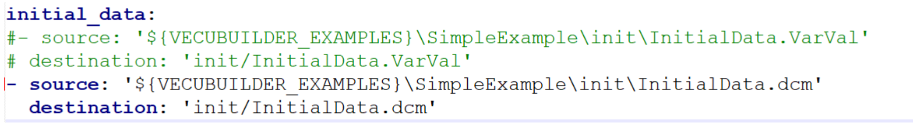
To experiment with intialData.dcm

1. Open the `.InitialData.dcm` in `Examples/SimpleExample/init`.
2. Change the value for factor 1 to 4.
3. Change the value for factor 2 to 4.
4. Save the changes.



```
FESTWERT factor1
   LANGNAME ""
   EINHEIT_W ""
   WERT 4.0
END

FESTWERT factor2
   LANGNAME ""
   EINHEIT_W ""
   WERT 4.0
```

5. Open the YAML file and navigate to the `initial_data` section.
6. Uncomment the source and destination for `InitialData.VarVal`.
7. Comment the source and destination for `InitialData.dcm`.



```
initial_data:
#- source: '${VECUBUILDER_EXAMPLES}\SimpleExample\init\InitialData.VarVal'
# destination: 'init/InitialData.VarVal'
- source: '${VECUBUILDER_EXAMPLES}\SimpleExample\init\InitialData.dcm'
  destination: 'init/InitialData.dcm'
```

8. Save the changes.
9. Rebuild the vECU using

   `2_Build.bat` in the workspace on **Windows**

   or

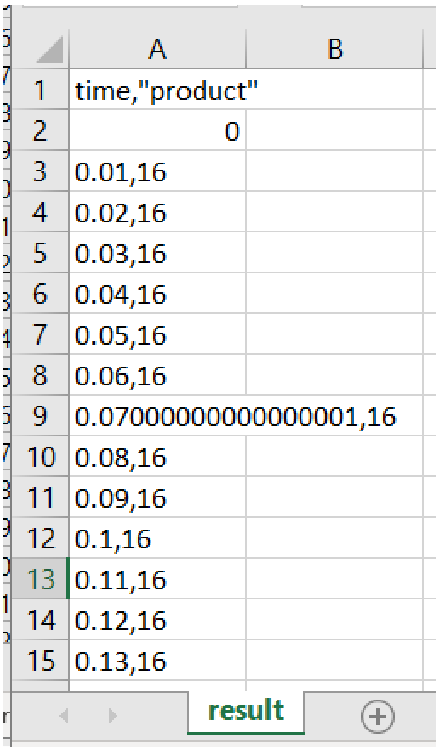
   `2_Build.sh` in the workspace on **Ubuntu 22.04 LTS**.
10. To show the changed output in the FMU, execute

    `3a_CheckFMU.bat` on **Windows**

    or

    `3a_CheckFMU.sh` on **Ubuntu 22.04 LTS**.

⇨ The new output is now 16.



	A	B
1	time,"product"	
2	0	
3	0.01,16	
4	0.02,16	
5	0.03,16	
6	0.04,16	
7	0.05,16	
8	0.06,16	
9	0.07000000000000001,16	
10	0.08,16	
11	0.09,16	
12	0.1,16	
13	0.11,16	
14	0.12,16	
15	0.13,16	

⇨ The initial data set in the DCM file are thus correctly used in the vECU.

⇨ The sources in `Multiply.c` stay the same. The variables are overwritten at run time by the values of the `InitialData.dcm`.

Note

You can define several files and formats. If one variable is set in multiple files, the value of the last file is used.

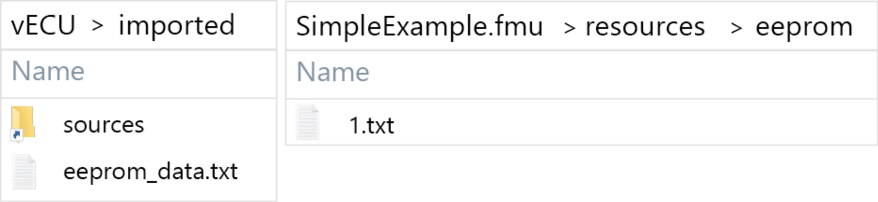
For release vECU all initial data is merged into `MergedInitialData.VarVal`. This VARVAL file protects the IP. Release and debug vECU behave the same. To get the different folder structures, see Difference between debug and release vECUs .

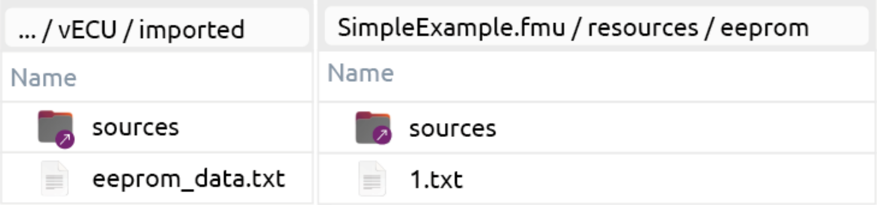
6.1.4 eeprom functionality

During vECU initialization, the EEPROM data is loaded from a file to RAM. The data is saved to the file before running terminate tasks and when unloading the vECU. This can be utilized to simulate a soft reset behavior, ensuring that EEPROM-stored data is preserved and not lost once the vECU simulation terminates. A typical usage of this feature is the storage of total mileage information in the ESP controller.

1. Open `vEcuConf.yaml` file of SimpleExample and navigate to `eeprom` section.

   The `eeprom_data.txt` file is initially copied from `VECUBUILDER_EXAMPLES/SimpleExample/src` to the workspace in `vECU/imported` during the import process with standard configuration. During `SimpleExample.fmu` build, `eeprom_data.txt` file is integrated into the FMU as `1.txt` in `resources/eeprom` folder. This happens because the optional `destination` attribute is enabled. You can change the destination path and file name accordingly. This file serves as the working copy.





   Note

   If destination attribute is deactivated, `eeprom_data.txt` is integrated into the FMU (release and debug FMu)in `resources` folder.

2. Open `eeprom_data.txt` in `imported` folder and check the content.

   Note

   `eeprom_data.txt` must include the relevant data in expected HEX format.

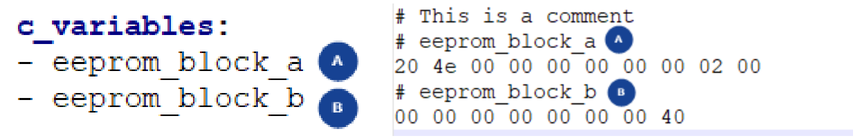
3. Go back to YAML file.

   In the standard configuration, the following **c_variables** are used:

- eeprom_block_a: Shows the lifetime of the vECU in ms and counts, how often vECU was powered on.
- eeprom_block_b: Shows the last value of product calculated in the previous execution.

`eeprom_data.txt` contains the data stream that should be used for the c_variables.

> **Note**
>
> Ensure that the order of c_variables in `vEcuConf.yaml` file matches the order of the data stream in `eeprom_data.txt`.



```
c_variables:
 - eeprom_block_a
 - eeprom_block_b
```

```
# This is a comment
# eeprom_block_a
20 4e 00 00 00 00 00 00 02 00
# eeprom_block_b
00 00 00 00 00 00 00 40
```

4. In `eeprom_data.txt`, ensure that the size of the variables in HEX format matches with the size defined in `SymbolDetails.txt`.

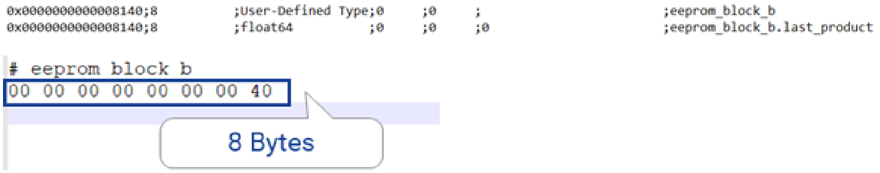
   To open `SymbolDetails.txt`, run

   `3c_ShowSymbolDetails.bat` on **Windows**

or

   `3c_ShowSymbolDetails.sh` on **Ubuntu 22.04 LTS**.

   i.e. eeprom_block_b has a size of 8 bytes and comprises eeprom_block_b.last_product which also has a size of 8 bytes.



```
0x0000000000008140;8        ;User-Defined Type;0    ;0    ;                    ;eeprom_block_b
0x0000000000008140;8        ;float64           ;0    ;0    ;0                   ;eeprom_block_b.last_product
```

```
# eeprom block b
00 00 00 00 00 00 00 40
```

5. Delete the comment under sync and use the following:

   `sync:'C:/TEMP/eeprom_data.txt'` on **Windows**

or

   `sync: '//localhost/c$/TEMP/eeprom_data.txt'` on **Ubuntu 22.04 LTS**.

> **Note**
>
> Data from the imported eeprom file is used as initial data for the first simulation. After this step, the data will be always written back to the sync path at the end of each simulation and used by the next one.
>
> – If the file is not existing in sync location, it will be created.
>
> – If the file is already existing in sync location, this file will be taken by the first simulation run.

6. Save the changes.
7. Rebuild the workspace using

   `2_Build.bat` in the workspace on **Windows**

or

   `2_Build.sh` in the workspace on **Ubuntu 22.04 LTS**.

8. To start the simulation, execute

   `3a_CheckFMU.bat` on **Windows**

or

   `3a_CheckFMU.sh` on **Ubuntu 22.04 LTS**.

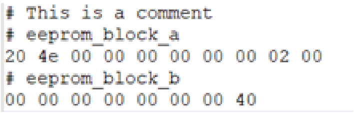
9. Navigate to

   `C:/TEMP` on **Windows**

or

   `//localhost/c$/TEMP` on **Ubuntu 22.04 LTS**.

⇨ `eeprom_data.txt` was added to sync location.



```
# This is a comment
# eeprom_block_a
20 4e 00 00 00 00 00 00 02 00
# eeprom_block_b
00 00 00 00 00 00 00 40
```

6.1.5 Usage of link_into_project

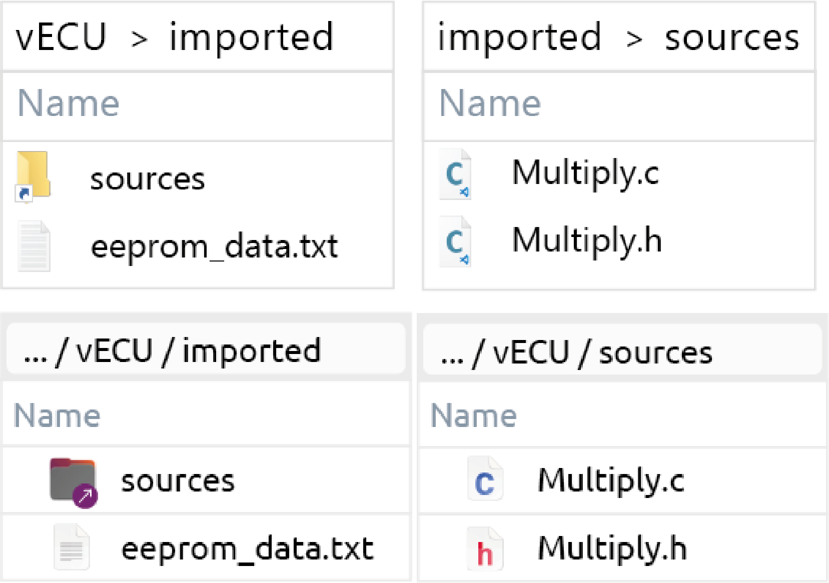
You can link folders into your project. When you copy a file or folder, its contents are duplicated. Changes made to one copy do not affect the other.

In contrast, creating a link generates a file or folder that references the same content. Changes to one linked item are reflected in both. A link acts as an additional name for the same file or folder. It exists only once on the file system and occupies space just once. This method is useful for conserving disk space.

To use link_into_project

1. Open `vEcuConf.yaml` file of SimpleExample.
2. Navigate to `link_into_project` section.

   With the standard configuration, the content of `VECUBUILDER_EXAMPLES/SimpleExample/src` was linked into `imported/sources`.



vECU > imported

Name

sources

eeprom_data.txt

imported > sources

Name

Multiply.c

Multiply.h

... / vECU / imported

Name

sources

eeprom_data.txt

... / vECU / sources

Name

Multiply.c

Multiply.h

3. To add a new linked folder, add the respective `source` and `destination` path.
4. Save your changes.
5. Import the files and folders using

   `1_Import.bat` in the workspace on **Windows**

   or

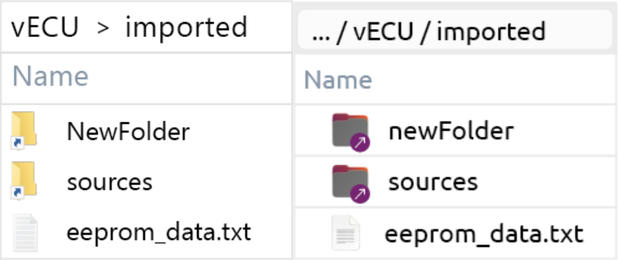
   `1_Import.sh` in the workspace on **Ubuntu 22.04 LTS**.
6. As there are already sources in the workspace, they will be overwritten.

   Agree to the deletion by clicking **Yes**.

   The files and folders are imported.

7. Proceed as described in Creating a new workspace.

⇨ The folder is linked into `vEcu/imported`.



vECU > imported	... / vECU / imported
Name	Name
NewFolder	newFolder
sources	sources
eeprom_data.txt	eeprom_data.txt

6.1.6 ARXML-defined tasks

To retrieve tasks from ARXML files, you can use `arxml_tasks` in the YAML file. To retrieve tasks from ARXML files, enable `arxml_tasks` and ensure the ARXML files are located in the `vECU/imported` folder. VECU-BUILDER will read all the ARXML files and will take all the timing and init tasks.

<u>To use arxml_tasks by using import_into_project</u>

1. Open `vEcuConf.yaml` file in your workspace.
2. Navigate to `arxml_tasks` section.
3. Uncomment `arxml_tasks`.
4. Change the value to `enabled`.
5. Navigate to `import_into_project` section.
6. Enter the paths to the ARXML files or folders containing the ARXML files to be imported.
7. Save your changes.
8. Rebuild the workspace using

   `1_Import.bat` in the workspace on **Windows**

   or

   `2_Import.sh` in the workspace on **Ubuntu 22.04 LTS.**

   The import target is the `vEcu/imported` folder in your workspace.

⇨ `arxml_tasks.json` file was created in the `build` folder.

<u>To use arxml_tasks by manually copying ARXML files</u>

1. Open `vEcuConf.yaml` file in your workspace.
2. Navigate to `arxml_tasks` section.
3. Uncomment `arxml_tasks`.
4. Change the value to `enabled`.
5. Save your changes.
6. Place your ARXML files into `vECU/imported` folder.
7. Rebuild the workspace using

   `2_Build.bat` in the workspace on **Windows**

   or

   `2_Build.sh` in the workspace on **Ubuntu 22.04 LTS.**

⇨ `arxml_tasks.json` file was created in the `build` folder.

6.2 BCU example (only available for Windows)

To create a workspace based on the BCU example, follow the steps described in Creating a new workspace to the point where the YAML file opens in Notepad++.

1. Replace the entire content of the YAML file with the content of prepared BCU configuration YAML file located in:

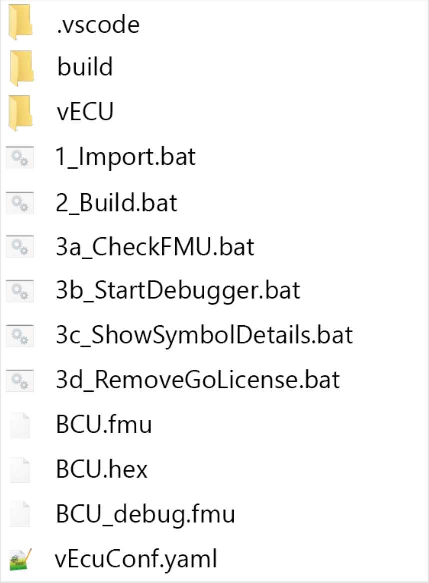
   `C:/ProgramData/ETAS/VECU-BUILDER/Examples_1.8.0/BCU` on **Windows**.

   A2L file patching is enabled In the YAML file.

2. Continue the process as described in Working with VECU-BUILDER.

⇨ When the A2L file patching is enabled, a HEX file is generated during the build process and is available in the workspace after the build. For more information see patch_a2l_file and HEX file generation.

> **Note**
>
> The HEX file will only be part of the workspace if the A2L file patching is activated.



.vscode
build
vECU
1_Import.bat
2_Build.bat
3a_CheckFMU.bat
3b_StartDebugger.bat
3c_ShowSymbolDetails.bat
3d_RemoveGoLicense.bat
BCU.fmu
BCU.hex
BCU_debug.fmu
vEcuConf.yaml

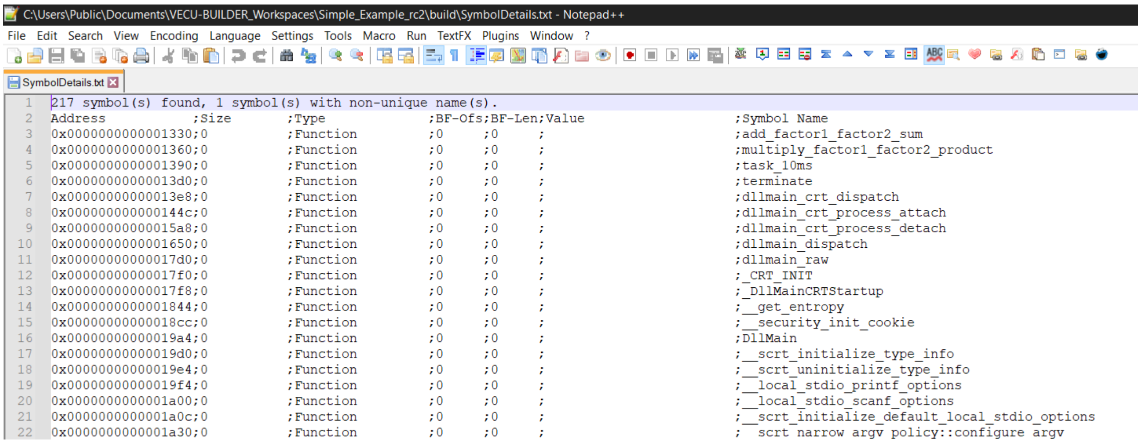
6.2.1 Show symbol information

To see all the symbols available in your vECU, open the `SymbolDetails.txt` file.

1. To see the details, run the command:

   `3c_ShowSymbolDetails.bat` on **Windows**.

⇨ A text editor window opens and symbol details are shown.


C:\Users\Public\Documents\VECU-BUILDER_Workspaces\Simple_Example_rc2\build\SymbolDetails.txt - Notepad++
File Edit Search View Encoding Language Settings Tools Macro Run TextFX Plugins Window ?
SymbolDetails.txt

```
217 symbol(s) found, 1 symbol(s) with non-unique name(s).
Address           ;Size       ;Type             ;BF-Ofs;BF-Len;Value                   ;Symbol Name
0x0000000000001330;0          ;Function         ;0     ;0     ;                        ;add_factor1_factor2_sum
0x0000000000001360;0          ;Function         ;0     ;0     ;                        ;multiply_factor1_factor2_product
0x0000000000001390;0          ;Function         ;0     ;0     ;                        ;task_10ms
0x00000000000013d0;0          ;Function         ;0     ;0     ;                        ;terminate
0x00000000000013e8;0          ;Function         ;0     ;0     ;                        ;dllmain_crt_dispatch
0x000000000000144c;0          ;Function         ;0     ;0     ;                        ;dllmain_crt_process_attach
0x00000000000015a8;0          ;Function         ;0     ;0     ;                        ;dllmain_crt_process_detach
0x0000000000001650;0          ;Function         ;0     ;0     ;                        ;dllmain_dispatch
0x00000000000017d0;0          ;Function         ;0     ;0     ;                        ;dllmain_raw
0x00000000000017f0;0          ;Function         ;0     ;0     ;                        ;_CRT_INIT
0x00000000000017f8;0          ;Function         ;0     ;0     ;                        ;_DllMainCRTStartup
0x0000000000001844;0          ;Function         ;0     ;0     ;                        ;__get_entropy
0x00000000000018cc;0          ;Function         ;0     ;0     ;                        ;__security_init_cookie
0x00000000000019a4;0          ;Function         ;0     ;0     ;                        ;DllMain
0x00000000000019d0;0          ;Function         ;0     ;0     ;                        ;__scrt_initialize_type_info
0x00000000000019e4;0          ;Function         ;0     ;0     ;                        ;__scrt_uninitialize_type_info
0x00000000000019f4;0          ;Function         ;0     ;0     ;                        ;__local_stdio_printf_options
0x0000000000001a00;0          ;Function         ;0     ;0     ;                        ;__local_stdio_scanf_options
0x0000000000001a0c;0          ;Function         ;0     ;0     ;                        ;__scrt_initialize_default_local_stdio_options
0x0000000000001a30;0          ;Function         ;0     ;0     ;                        ;  scrt narrow argv policy::configure argv
```

Fig. 6-5: Symbol Details of BCU example

6.2.2 A2L file patching

Most ECU software authoring tools can generate an A2L file for you. It contains the addresses of your labels for a specific target. In addition, it can contain software-specific statements or even non-standard clauses. The label addresses of a vECU target differ from the addresses of a physical ECU target. This means that the original A2L file cannot be used for an XCP connection with a vECU target.

The generation of A2L files is an intricate task. VECU-BUILDER does not include this functionality. Instead, VECU-BUILDER reads, modifies, and writes a given A2L file. This patching procedure preserves most of the original contents of the A2L file but changes all addresses to those of the vECU target. A backup copy of the original A2L file is preserved (named as `*.a2l.bak`).

VECU-BUILDER includes its own XCP slave software component. Currently, it supports TCP connections only. The communication parameters for an XCP connection are part of an A2L file. VECU-BUILDER patches in the values for TCP port and IP address, which are specified in the YAML file. For instance:

Original A2L file	Patched A2L file

`/begin XCP_ON_TCP_IP`
`0x0100 /* XCP on IP 1.0 */`
<TCPPORT> `/* Port */`
`/ADDRESS "`**<IPADDR>**`"`
`/end XCP_ON_TCP_IP`
	`/begin XCP_ON_TCP_IP`
	`*/0x0100 /* XCP on IP 1.0 */`
	`12345 /* Port */`
	`ADDRESS "127.0.0.1"`
	`/end XCP_ON_TCP_IP`

The integrated XCP slave supports a limited subset of the commands of the ASAM MCD-1 (XCP) standard version 1.0. It supports a limited subset of the clauses from ASAM MCD-2 (ASAP2 / A2L) standard version 1.7.1.

If your ECU software already includes an XCP slave, it is possible to remove this software component from the vECU software stack.

6.2.3 A2L name mapping

By default, the A2L file contains the symbol names of characteristics and measurements. Sometimes the symbol names in the A2L file are renamed. Because the addresses in the A2L must refer to the original symbol names, you must map them.

Original A2L file	Mapped and patched A2L file
/begin CHARACTERISTIC Hysteresis_LightOffIntensity "unsigned integer 16bit" VALUE 0x00000000 RTAA2L_Internal_Scalar_UnsignedWord 0 CompuMethods_STEP_100_OFFSET_0 0 100 DISPLAY_IDENTIFIER Hysteresis_LightOffIntensity /end CHARACTERISTIC	/begin CHARACTERISTIC HystLiOfInt "unsigned integer 16bit" VALUE 00x00003016 RTAA2L_Internal_Scalar_UnsignedWord 0 CompuMethods_STEP_100_OFFSET_0 0 100 DISPLAY_IDENTIFIER Hysteresis_LightOffIntensity /end CHARACTERISTIC

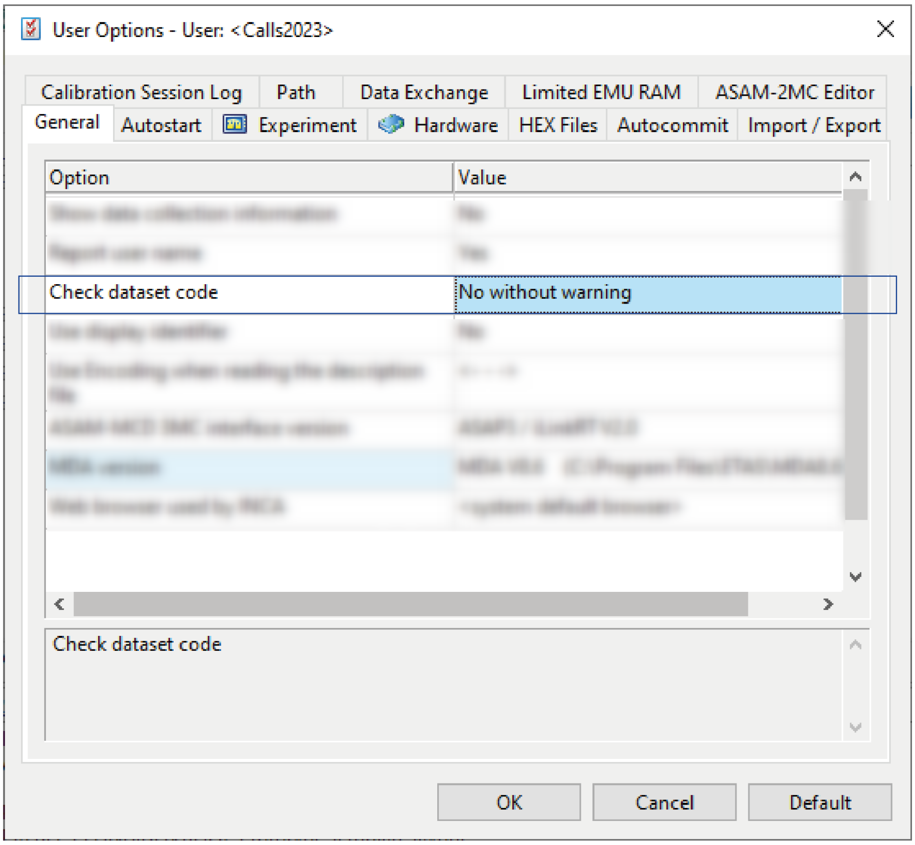
6.2.4 HEX file generation

When the A2L patching mechanism is activated, VECU-BUILDER creates a HEX file. The HEX file (`BCU.hex`) is located in the corresponding workspace. You can use the HEX file for working with ETAS INCA. The HEX file contains the data INCA considers as the so-called reference page. INCA uses these data to calculate CRC check.

You can upload this generated HEX file while creating an INCA experiment. After uploading the file, workflows within INCA will be enabled. For more information about INCA and HEX file upload with INCA, see the corresponding INCA User Guides available in the ETAS download center.

To enable settings in INCA for a successful HEX file upload:

1. Open **User Options**.
2. Click **General** tab.
3. Go to **Check dataset code**.
4. Ensure that the value is set to **No without warning**.
5. Click **OK**.



User Options - User: <Calls2023>

Option	Value
Check dataset code	No without warning

Check dataset code

Note

If the settings are not as described, INCA will display an error and the HEX file will not be accepted.

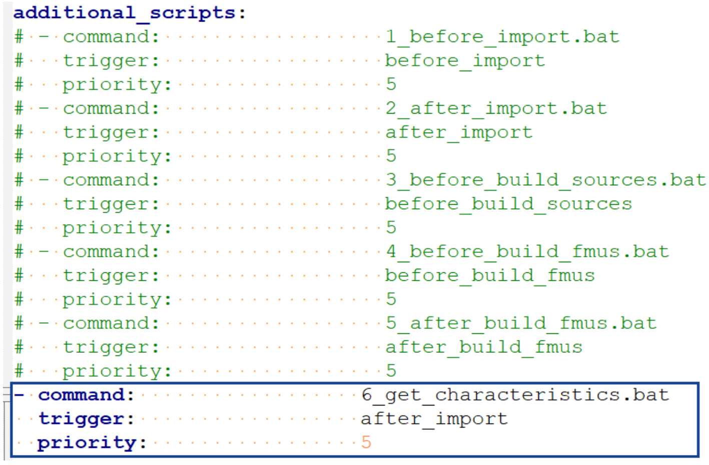
6.2.5 Example of additional scripts - A2L characteristics as parameters

This is an example of how additional scripts can be used. With the following script, it is possible to use A2L characteristics as parameters of a vECU.

To run the script

1. To create a BCU workspace, follow the steps described in BCU example (only available for Windows)
2. Copy from `${VECUBUILDER_EXAMPLES}/BCU/additional_scripts`
   - `6_get_characteristics.bat`
   - `6_get_characteristics.py`

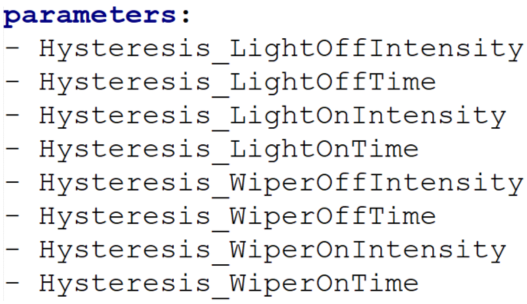
   to `<My_BCU_Workspace>/build/additional_scripts`.
3. Add the path of your Python interpreter directory to the Path environmental variable.
4. In `vEcuConf.yaml` file uncomment the following lines in the `additional_scripts` section.



```
additional_scripts:
# - command:                  1_before_import.bat
#   trigger:                  before_import
#   priority:                 5
# - command:                  2_after_import.bat
#   trigger:                  after_import
#   priority:                 5
# - command:                  3_before_build_sources.bat
#   trigger:                  before_build_sources
#   priority:                 5
# - command:                  4_before_build_fmus.bat
#   trigger:                  before_build_fmus
#   priority:                 5
# - command:                  5_after_build_fmus.bat
#   trigger:                  after_build_fmus
#   priority:                 5
- command:                  6_get_characteristics.bat
  trigger:                  after_import
  priority:                 5
```

5. Start building your workspace using `1_Import.bat` on **Windows**.

⇨ Characteristics were added in `parameters` section of `vEcuConf.yaml` file and are also available as parameters in the built `BCU.fmu`.



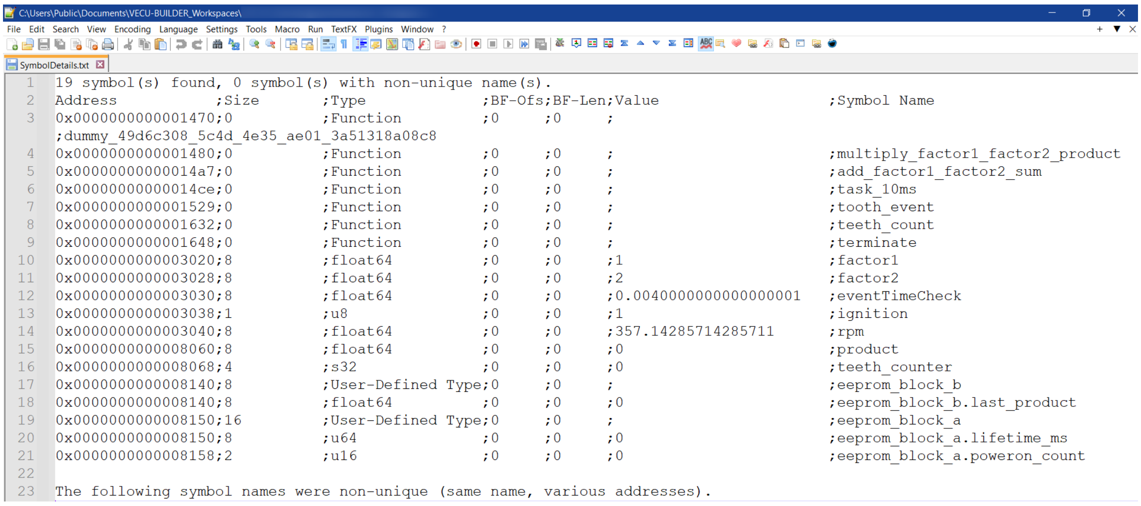
```
parameters:
- Hysteresis_LightOffIntensity
- Hysteresis_LightOffTime
- Hysteresis_LightOnIntensity
- Hysteresis_LightOnTime
- Hysteresis_WiperOffIntensity
- Hysteresis_WiperOffTime
- Hysteresis_WiperOnIntensity
- Hysteresis_WiperOnTime
```

6.3 EventTrigger example

This example shows the possibility of using event-triggered tasks. Therefore you need a function and a trigger function. The use of trigger inputs is optional. You can add up to 16 trigger inputs. This trigger function predicts when the next event might occur and returns if the next events needs to be triggered. You can find the event-triggered task in the `task` section in the `vEcuConf.yaml` file.

The function name is `teeth_count` and the trigger function is `tooth_event`.

The function and the trigger function are defined in the `Multiply.c` file in `vECU` folder of the corresponding workspace. Optional inputs of `trigger_function` must be included in `SymbolDetails.txt`.



C:\Users\Public\Documents\VECU-BUILDER_Workspaces\
File Edit Search View Encoding Language Settings Tools Macro Run TextFX Plugins Window ?
SymbolDetails.txt

```
19 symbol(s) found, 0 symbol(s) with non-unique name(s).
Address           ;Size       ;Type             ;BF-Ofs;BF-Len;Value                    ;Symbol Name
0x0000000000001470;0          ;Function         ;0     ;0     ;
;dummy_49d6c308_5c4d_4e35_ae01_3a51318a08c8
0x0000000000001480;0          ;Function         ;0     ;0     ;                         ;multiply_factor1_factor2_product
0x00000000000014a7;0          ;Function         ;0     ;0     ;                         ;add_factor1_factor2_sum
0x00000000000014ce;0          ;Function         ;0     ;0     ;                         ;task_10ms
0x0000000000001529;0          ;Function         ;0     ;0     ;                         ;tooth_event
0x0000000000001632;0          ;Function         ;0     ;0     ;                         ;teeth_count
0x0000000000001648;0          ;Function         ;0     ;0     ;                         ;terminate
0x0000000000003020;8          ;float64          ;0     ;0     ;1                        ;factor1
0x0000000000003028;8          ;float64          ;0     ;0     ;2                        ;factor2
0x0000000000003030;8          ;float64          ;0     ;0     ;0.0040000000000000001   ;eventTimeCheck
0x0000000000003038;1          ;u8               ;0     ;0     ;1                        ;ignition
0x0000000000003040;8          ;float64          ;0     ;0     ;357.14285714285711       ;rpm
0x0000000000008060;8          ;float64          ;0     ;0     ;0                        ;product
0x0000000000008068;4          ;s32              ;0     ;0     ;0                        ;teeth_counter
0x0000000000008140;8          ;User-Defined Type;0     ;0     ;                         ;eeprom_block_b
0x0000000000008140;8          ;float64          ;0     ;0     ;0                        ;eeprom_block_b.last_product
0x0000000000008150;16         ;User-Defined Type;0     ;0     ;                         ;eeprom_block_a
0x0000000000008150;8          ;u64              ;0     ;0     ;0                        ;eeprom_block_a.lifetime_ms
0x0000000000008158;2          ;u16              ;0     ;0     ;0                        ;eeprom_block_a.poweron_count

The following symbol names were non-unique (same name, various addresses).
```

Fig. 6-6: Symbol Details of EventTrigger Example (Windows)

It is checked if the defined conditions of the trigger function are met. The default check time is 4 ms. If the conditions are met, the function is called. E.g. if the conditions of trigger function `tooth_event` are met, the function `teeth_count` is called.

6.3.1 Event-triggered tasks

To create a workspace based on the EventTrigger example, follow the steps described in Creating a new workspace to the point where the YAML file opens in Notepad++.

1. Replace the entire content of the YAML file with the content of prepared EventTrigger configuration YAML file located in:

   `C:/ProgramData/ETAS/VECU-BUILDER/Examples_1.8.0/EventTriggerExample` on **Windows**

   or

   `/opt/etas/VECU-BUILDER/Examples_1.8.0/EventTriggerExample` on **Ubuntu 22.04 LTS**.

2. Continue the process as described in Working with VECU-BUILDER.

⇨ The workspace was created.

6.3.2 Task scheduling with task trigger defined as cyclic

VECU-BUILDER does not have a built-in task scheduler. Instead, the task scheduling process is handled by the simulation environment that runs the FMU. VECU-BUILDER creates an FMU file that contains information about vECU tasks and their properties, which the simulation environment reads and uses to schedule the tasks.

In the tasks section of `vEcuConf.yaml`, you define the tasks that are supposed to execute when the FMU is run by the simulation environment.

When the task trigger is defined as `cyclic` (executed periodically), the following task properties become relevant:

- **period**: Specifies, how long the simulation environment has to wait between task executions
- **first_call**: Denotes the duration before the task is initially called.
- **priority**: Specifies, which task the simulation environment executes first, in case two or more tasks are supposed to be executed.
- **max_calls**:Enables the setting of a maximum limit for the total number of task executions during a simulation run.

The `first_call` property determines the initial delay before the task is first executed. Typically, it is set to zero. Nonetheless, there are instances where setting a non-zero value for `first_call` is necessary to avoid running the same task twice during the initial simulation step.

The repeated execution of some tasks in the very first step is by design. The convention adopted by VECU-BUILDER is that the time internal used by `fmi2DoStep()` is treated as right-closed, meaning the endpoint of the time interval is included in the interval itself. This sometimes results in duplicate execution of a task within the first simulation interval.

One way to address this issue is to disregard the initial simulation interval (or multiple intervals). If this is not a viable option, the alternative is to adjust the `first_call` parameter to match the `period` for the impacted tasks in the `vEcuConf.yaml` file.

6.4 Template for plug-in V1 (FMI2)

6.4.1 Plug-In feature

With VECU-BUILDER plug-in feature it is possible to implement an own logic at run time into the following phases of FMU Runner:

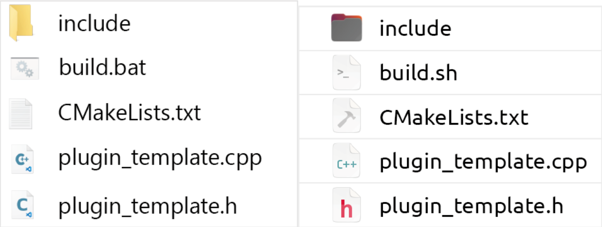
- Instantiation
- Initialization
- Step execution
- Task execution

The phases follow the rules of FMI2 standard. For more information about FMI,see FMI standard.

Your configured plug-in implementation occurs in form of a CMake project. This CMake project needs to be used to implement the functionality of plug-in interface. For more information, see Plug-In interface.

Within `plugin_template_v1_FMI2` folder (see Installed files and folders for installation path), the following files and folders are installed:

- `include` folder: Includes the header files containing VECU-BUILDER type definitions which you are not allowed to modify.
- `build.bat/build.sh`: Script, that contains a small list of commands which builds plugin_template shared object (DLL/SO).
- `CMakeLists.txt`: File, which contains CMake configuration for the plugin_template project.
- `plugin_template.cpp` and `plugin_template.h`: Main files dedicated for plug-in implementation.



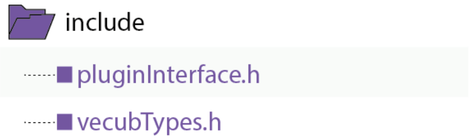
include
build.bat
CMakeLists.txt
plugin_template.cpp
plugin_template.h

include
build.sh
CMakeLists.txt
plugin_template.cpp
plugin_template.h

Fig. 6-7: Installed files and folders for plug-in

The plug-in project uses two header files that defines VECU-BUILDER types. They are located in the `include` folder of the project template:

- `plugininterface.h`
- `vecubTypes.h`



include
pluginInterface.h
vecubTypes.h

Fig. 6-8: plugin_template folder

Once you implemented your own logic, the plug-in can be included in VECU-BUILDER as an additional resource.

As plug-in feature is supported for FMI2 and FMI3, the functions for each plug-in are grouped in `pluginInterface.h`.

For plug-in version V1 (FMI2) look for `#define FMI_2_VERS_1` and `#ifdef FMI_2_VERS_1` (obsolete:`#define FMI2` and `#ifdef FMI2`.)

ⓘ **Note**

When using the plug-in, you must use include_symbol_details.

EXAMPLE

If you want to change the cycle time of `"task_10ms"` using a plug-in, then the symbol name `"task_10ms"` must be disclosed in the release vECU.

6.4.2 Plug-In configuration

You can include plug-ins as additional ressources, i.e.:

- `additional_resources:`

  `- ${VECUBUILDER_EXAMPLES}\plugin_template\CMake\Debug\plugin_template.dll` on **Windows**

or

- `additional_resources:`

  `- ${VECUBUILDER_EXAMPLES}/Linux/plugin_template/CMake/libplugin_template.so` for **Ubuntu 22.04 LTS**.

  > **Note**
  >
  > The plug-in can reside in a different location than `${VECUBUILDER_EXAMPLES}\...` and in `vEcuconf.yaml` you need to give the absolute path to the location of the build plug-in.

> **Note**
>
> You can rename a plug-in. However it is mandatory to follow the conventions mentioned below in any case:
>
> - A `*.dll` file (for Windows) must start with **`plugin`**. It then will be managed as plug-in by VECU-BUILDER.
> - A `*.so` file (for Linux) must start with **`libplugin`**. It then will be managed as plug-in by VECU-BUILDER.
>
> If the plug-in does not follow this naming convention,VECU-BUILDER will not consider the `*.dll` or `*.so` as plug-in.

The files are saved in `.fmu` file in `resources` folder. From here VECU-BUILDER will load them as plug-ins.

6.4.3 Plug-In interface

To see and use the plug-in interface, open `pluginInterface.h` in `include` folder.

Plug-In functions

You can use several plug-in functions. There are optional and mandatory plug-in functions and therefore not all functions from plug-in interface have to be implemented.

Pointer and function pointers

For Visual Studio compiler on Windows and GNU complier from MinGW on Ubuntu:

All plug-in interface functions have one argument as a pointer of type `struct VecubCallbacks1`.

For Visual Studio compiler on Windows and GNU compiler on Ubuntu and GNU compiler from MinGW on Windows and Ubuntu

All plug-in interface functions have one argument as a pointer of type `struct VecubCallbacks1`. Furthermore, the structure also contains conditional compilation instructions that only define certain function pointers if the `PLUGIN_EXTENSION` macro is defined.

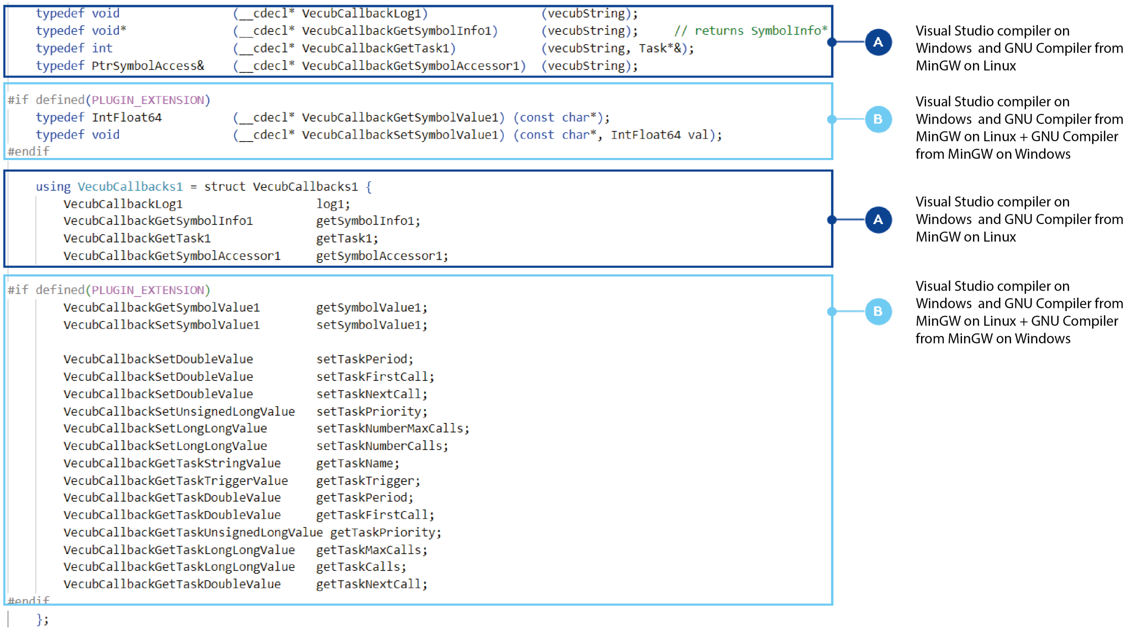
The following plug-in callback functions are available. The trigger for each plug-in function call is related to the FMI protocol.

Callback Function Name	Trigger	Priority
vecubPluginVersion	During fmi2Instantiate and before vecubInstantiate1	mandatory
vecubInstantiate1	During fmi2Instantiate and after vecubPluginVersion	mandatory
vecubFmi2EnterInit1	During fmi2EnterInitializationMode	optional
vecubFmi2ExitInit1	During fmi2ExitInitializationMode	optional
vecubPreDoStep1	At the beginning of fmi2DoStep	optional
vecubPostDoStep1	At the end of fmi2DoStep	optional
vecubPreTask1	Before calling a task	optional
vecubPostTask1	After calling a task	optional
Terminate1	During fmi2Terminate	mandatory

`VecubCallbacks1` pointer keeps a list of function pointers which could be used in order for plug-in to grab information from VECU-BUILDER.

Available functionalities (callbacks) are:

- logging
- accessing symbol information like: address, size, symbol type, bitfield_offset, bitfield_length
- managing task objects
- handling symbols data like read and write their values



```
    typedef void              (__cdecl* VecubCallbackLog1)               (vecubString);
    typedef void*             (__cdecl* VecubCallbackGetSymbolInfo1)     (vecubString);     // returns SymbolInfo*
    typedef int               (__cdecl* VecubCallbackGetTask1)           (vecubString, Task*&);
    typedef PtrSymbolAccess&  (__cdecl* VecubCallbackGetSymbolAccessor1) (vecubString);

#if defined(PLUGIN_EXTENSION)
    typedef IntFloat64        (__cdecl* VecubCallbackGetSymbolValue1) (const char*);
    typedef void              (__cdecl* VecubCallbackSetSymbolValue1) (const char*, IntFloat64 val);
#endif

    using VecubCallbacks1 = struct VecubCallbacks1 {
        VecubCallbackLog1                   log1;
        VecubCallbackGetSymbolInfo1         getSymbolInfo1;
        VecubCallbackGetTask1               getTask1;
        VecubCallbackGetSymbolAccessor1     getSymbolAccessor1;

#if defined(PLUGIN_EXTENSION)
        VecubCallbackGetSymbolValue1        getSymbolValue1;
        VecubCallbackSetSymbolValue1        setSymbolValue1;

        VecubCallbackSetDoubleValue         setTaskPeriod;
        VecubCallbackSetDoubleValue         setTaskFirstCall;
        VecubCallbackSetDoubleValue         setTaskNextCall;
        VecubCallbackSetUnsignedLongValue   setTaskPriority;
        VecubCallbackSetLongLongValue       setTaskNumberMaxCalls;
        VecubCallbackSetLongLongValue       setTaskNumberCalls;
        VecubCallbackGetTaskStringValue     getTaskName;
        VecubCallbackGetTaskTriggerValue    getTaskTrigger;
        VecubCallbackGetTaskDoubleValue     getTaskPeriod;
        VecubCallbackGetTaskDoubleValue     getTaskFirstCall;
        VecubCallbackGetTaskUnsignedLongValue getTaskPriority;
        VecubCallbackGetTaskLongLongValue   getTaskMaxCalls;
        VecubCallbackGetTaskLongLongValue   getTaskCalls;
        VecubCallbackGetTaskDoubleValue     getTaskNextCall;
#endif
    };
```

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux + GNU Compiler from MinGW on Windows

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux + GNU Compiler from MinGW on Windows

Fig. 6-9: function pointers

Example for usage of callbacks for Visual Studio compiler on Windows and GNU compiler on Ubuntu

The following code visualizes how you can use callbacks for plug-in version 1.

```
// ===== plug-in vers. 01 =====
DllExport vecub1Status __cdecl vecubFmi2EnterInit1(const VecubCall-
backs1* vecubCallbacks)
{
    if (!vecubCallbacks)
        return vecub1Status::vecubError;
```

The code defines the function `vecubFmi2EnterInit1` that takes a pointer to the structure `VecubCallbacks1` as input. It checks if the passed pointer `vecubCallbacks` is valid. If not, it returns `vecub1Status::vecubError`.

```
// logging
if (vecubCallbacks->log1)
 {
   vecubCallbacks->log1("user message");
 }
```

It checks if the `log1` function is defined in `vecubCallbacks` structure. If yes, it calls the function with the argument `user message`.

```
// get symbol info
SymbolInfo* symbol = static_cast<SymbolInfo*>(vecubCallbacks->getSym-
bolInfo1("factor1"));
std::cout << "The symbol has address: " << std::hex << symbol->addr <<
std::endl;
```

It calls `getSymbolInfo1` function to obtain information about a symbol named `factor1`. The returned symbol is stored in the variable `symbol`. The address of the symbol is printed using `std::cout`.

```
// get symbol accessor
PtrSymbolAccess& symbolAccessor = vecubCallbacks->getSymbolAccessor1
("factor1");
IntFloat64 val = (*symbolAccessor).get();
´val.f = 5;
(*symbolAccessor).set(val);
```

It calls `getSymbolAccessor1` function to obtain an accessor for the `factor1` symbol. The accessor is stored in the reference variable `symbolAccessor`. It reads a value of type `IntFloat64` from the symbol and assigns the value `5` to it. Then, it writes the value back to the symbol.

Note

`PtrSymbolAccess` and `symbolAccessor` with its own methods became obsolete but are still supported. They are replaced by methods like:

vecubCallbacks->getSymbolValue1

vecubCallbacks->setSymbolValue1

```
// get task object
Task* task{nullptr};
vecubCallbacks->getTask1("task_10ms", task);
task->setTNextCall(123);
 if (task) {
  std::cout << "FOUND! task: " << " ~ " << task->getName() <<
std::endl;
  }
```

It calls `getTask1` function to obtain a task object with the name `task_0ms`. The task object is stored in the pointer variable `task`. `setTNextCall` function is called on the task object with the value `123` as the argument. If the task object is valid, a message is printed with the task's name.

```
return vecub1Status::vecubOK;
}
```

It returns `vecub1Status::vecubOK`.

Example for usage of callbacks for Visual Studio compiler on Windows and GNU compiler on Ubuntu and GNU compiler from MinGW on Windows and Ubuntu

The following code visualizes how you can use callbacks for plug-in version 1.

```
// ===== plug-in vers. 01 =====
DllExport vecub1Status __cdecl vecubFmi2EnterInit1(const VecubCall-
backs1* vecubCallbacks)
{
    if (!vecubCallbacks)
        return vecub1Status::vecubError;
```

The code defines the function `vecubFmi2EnterInit1` that takes a pointer to the structure `VecubCallbacks1` as input. It checks if the passed pointer `vecubCallbacks` is valid. If not, it returns `vecub1Status::vecubError`.

```
// logging
if (vecubCallbacks->log1)
 {
   vecubCallbacks->log1("user message");
  }
```

It checks if the `log1` function is defined in `vecubCallbacks` structure. If yes, it calls the function with the argument `user message`.

```
// get symbol info
SymbolInfo* symbol = static_cast<SymbolInfo*>(vecubCallbacks->getSym-
bolInfo1("factor1"));
std::cout << "The symbol has address: " << std::hex << symbol->addr <<
std::endl;
```

It calls `getSymbolInfo1` function to obtain information about a symbol named `factor1`. The returned symbol is stored in the variable `symbol`. The address of the symbol is printed using `std::cout`.

```
// get symbol accessor
IntFloat64 symbolValue = vecubCallbacks->getSymbolValue1("factor1");
symbolValue.f = 10.00;
vecubCallbacks->setSymbolValue1("factor1", symbolValue);
```

It is using `getSymbolValue1` function pointer to retrieve the value of a symbol named "`factor1`" and stores it in a variable called `symbolValue`. It is assumed that `symbolValue` is a structure containing an integer and a float value, and the code is accessing the float value using the `.f` notation and setting it to 10.00. Secondly, it is using `setSymbolValue1` function pointer to update the value of the `factor1` symbol with the modified `symbolValue`.

```
// get task object
Task* tasknullptr{};
vecubCallbacks->getTask1("task_10ms", task);
std::cout << "Task getTaskNextCall: " << vecubCallbacks->getTaskNextCall(&task) << std::endl;
std::cout << "Task setTaskNextCall: " << vecubCallbacks->setTaskNextCall(&task, 1) << std::endl;
std::cout << "Task getTaskNextCall: " << vecubCallbacks->getTaskNextCall(&task) << std::endl;
```

A variable `task` of type `task*` is created and initialized with the value `nullptr`. Then the `getTask1` method of the `vecubCallbacks` object is called to retrieve the task named `task_10ms` and store it in the `task` variable. The methods `getTaskNextCall` and `setTaskNextCall` of the `vecubCallbacks` object are then called to get and set the next call time of the task. The results of these method calls are then output to the console using `std::cout`.

```
return vecub1Status::vecubOK;
}
```

It returns `vecub1Status::vecubOK`.

6.4.4 What a plug-in can do with tasks

A plug-in can access a task defined in VECU-BUILDER and can change different properties of a task at run time.

As described in Plug-In functions, you can use several functions. One of these functions is used to get a task. The used function pointer is `getTask1`, which returns a task type. For more information, see Fig. 6-9

Once the plug-in access a task, it can manage through the task interface and the behavior of a task during run time.

The interface of the task is available in plug-in template project through the definition of `task` class in `include/vecubTypes.h` file.

In this class, you can see specific functions of task class which manage i.e the task name, task period, or task priority.

6.5 Template for plug-in V2 (FMI3)

6.5.1 Plug-In feature V2

With VECU-BUILDER plug-in feature it is possible to implement an own logic at run time into the following phases of FMU Runner:

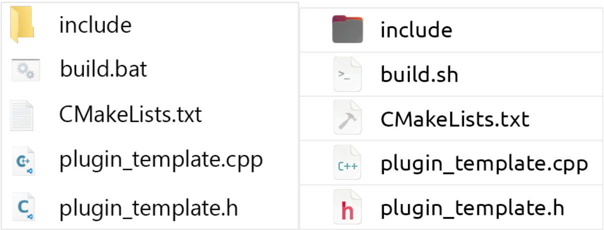
- Instantiation
- Initialization
- Step execution
- Task execution

The phases follow the rules of FMI3 standard. For more information about FMI,see FMI standard.

Your configured plug-in implementation occurs in form of a CMake project. This CMake project needs to be used to implement the functionality of plug-in interface. For more information, see Plug-In interface V2.

Within `plugin_template_v2_FMI3` folder (see Installed files and folders for installation path), the following files and folders are installed:

- `include` folder: Includes the header files containing VECU-BUILDER type definitions which you are not allowed to modify.
- `build.bat/build.sh`: Script, that contains a small list of commands which builds plugin_template shared object (DLL/SO).
- `CMakeLists.txt`: File, which contains CMake configuration for the plugin_template project.
- `plugin_template.cpp` and `plugin_template.h`: Main files dedicated for plug-in implementation.

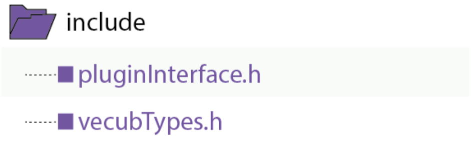


include	include
build.bat	build.sh
CMakeLists.txt	CMakeLists.txt
plugin_template.cpp	plugin_template.cpp
plugin_template.h	plugin_template.h

Fig. 6-10: Installed files and folders for plug-in

The plug-in project uses two header files that defines VECU-BUILDER types. They are located in the `include` folder of the project template:

- `pluginterface.h`
- `vecubTypes.h`



include
pluginInterface.h
vecubTypes.h

Fig. 6-11: plugin_template folder

Once you implemented your own logic, the plug-in can be included in VECU-BUILDER as an additional resource.

As plug-in feature is supported for FMI2 and FMI3, the functions for each plug-in are grouped in `pluginInterface.h`.

For plug-in version V2 (FMI3) look for `#define FMI_3_VERS_2` and `#ifdef FMI_3_VERS_2` (obsolete:`#define FMI3` and `#ifdef FMI3`.)

Note

When using the plug-in, you must use include_symbol_details.

EXAMPLE

If you want to change the cycle time of `"task_10ms"` using a plug-in, then the symbol name `"task_10ms"` must be disclosed in the release vECU.

6.5.2 Plug-In confuguration V2

You can include plug-ins as additional ressources:

- `additional_resources:`

  `- ${VECUBUILDER_EXAMPLES}\plugin_template\CMake\Debug\plugin_template.dll` on **Windows**

or

- `additional_resources:`

  `- ${VECUBUILDER_EXAMPLES}/Linux/plugin_template/CMake/libplugin_template.so` on **Ubuntu 22.04 LTS**.

> **Note**
>
> The plug-in can reside in a different location than `${VECUBUILDER_EXAMPLES}\...` and in `vEcuconf.yaml` you need to give the absolute path to the location of the build plug-in.

> **Note**
>
> You can rename a plug-in. However it is mandatory to follow the conventions mentioned below in any case:
>
> - A `*.dll` file (for Windows) must start with **`plugin`**. It then will be managed as plug-in by VECU-BUILDER.
> - A `*.so` file (for Ubuntu) must start with **`libplugin`**. It then will be managed as plug-in by VECU-BUILDER.
>
> If the plug-in does not follow this naming convention,VECU-BUILDER will not consider the `*.dll` or `*.so` as plug-in.

The files are saved in `.fmu` file in `resources` folder. From here VECU-BUILDER will load them as plug-ins.

6.5.3 Plug-In interface V2

To see and use the plug-in interface, open `pluginInterface.h` in `include` folder.

Plug-In functions

You can use several plug-in functions. There are optional and mandatory plug-in functions and therefore not all functions from plug-in interface have to be implemented.

Pointer and function pointers

For Visual Studio Compiler on Windows and GNU complier from MinGW on Ubuntu:

All plug-in interface functions have one argument as a pointer of type `struct VecubCallbacks2`.

For Visual Studio Compiler on Windows and GNU compiler on Ubuntu and GNU compiler from MinGW on Windows and Ubuntu

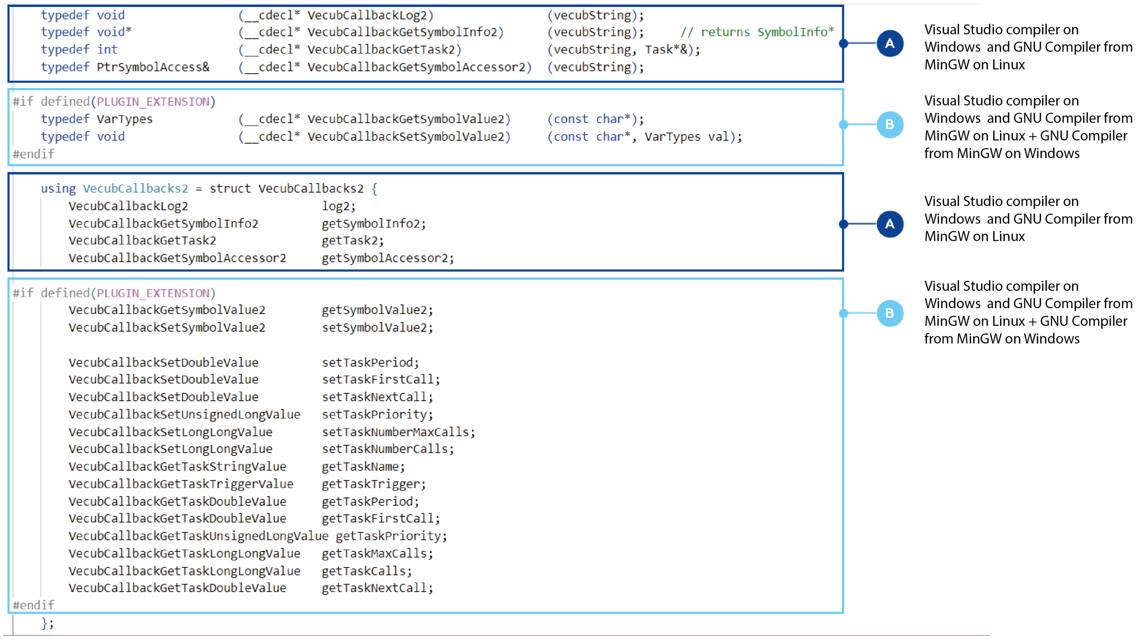
All plug-in interface functions have one argument as a pointer of type `struct VecubCallbacks2`. Furthermore, the structure also contains conditional compilation instructions that only define certain function pointers if the `PLUGIN_EXTENSION` macro is defined.

Callback	**Trigger**	**Priority**
vecubPluginVersion	During fmi3Instantiate and before vecubInstantiate2	mandatory
vecubInstantiate2	During "fmi3Instantiate" and after "vecubPluginVersion"	mandatory
vecubFmi3EnterInit2	During fmi3EnterInitializationMode	optional
vecubFmi3ExitInit2	During fmi3ExitInitializationMode	optional
vecubPreDoStep1	At the beginning of fmi3DoStep	optional
vecubPostDoStep2	At the end of fmi3DoStep	optional
vecubPreTask2	Before calling a task	optional
vecubPostTask2	After calling a task	optional
Terminate2	During fmi3Terminate	mandatory

This `VecubCallbacks2` pointer keeps a list of function pointers which could be used in order for plug-in to grab information from VECU-BUILDER.

Available functionalities (callbacks) are:

- logging
- accessing symbol information like: address, size, symbol type, bitfield_offset, bitfield_length
- managing task objects
- handling symbols data like read and write their values



```
    typedef void              (__cdecl* VecubCallbackLog2)                (vecubString);
    typedef void*             (__cdecl* VecubCallbackGetSymbolInfo2)      (vecubString);    // returns SymbolInfo*
    typedef int               (__cdecl* VecubCallbackGetTask2)            (vecubString, Task*&);
    typedef PtrSymbolAccess&  (__cdecl* VecubCallbackGetSymbolAccessor2)  (vecubString);
#if defined(PLUGIN_EXTENSION)
    typedef VarTypes          (__cdecl* VecubCallbackGetSymbolValue2)     (const char*);
    typedef void              (__cdecl* VecubCallbackSetSymbolValue2)     (const char*, VarTypes val);
#endif
    using VecubCallbacks2 = struct VecubCallbacks2 {
        VecubCallbackLog2                  log2;
        VecubCallbackGetSymbolInfo2        getSymbolInfo2;
        VecubCallbackGetTask2              getTask2;
        VecubCallbackGetSymbolAccessor2    getSymbolAccessor2;
#if defined(PLUGIN_EXTENSION)
        VecubCallbackGetSymbolValue2       getSymbolValue2;
        VecubCallbackSetSymbolValue2       setSymbolValue2;

        VecubCallbackSetDoubleValue        setTaskPeriod;
        VecubCallbackSetDoubleValue        setTaskFirstCall;
        VecubCallbackSetDoubleValue        setTaskNextCall;
        VecubCallbackSetUnsignedLongValue  setTaskPriority;
        VecubCallbackSetLongLongValue      setTaskNumberMaxCalls;
        VecubCallbackSetLongLongValue      setTaskNumberCalls;
        VecubCallbackGetTaskStringValue    getTaskName;
        VecubCallbackGetTaskTriggerValue   getTaskTrigger;
        VecubCallbackGetTaskDoubleValue    getTaskPeriod;
        VecubCallbackGetTaskDoubleValue    getTaskFirstCall;
        VecubCallbackGetTaskUnsignedLongValue getTaskPriority;
        VecubCallbackGetTaskLongLongValue  getTaskMaxCalls;
        VecubCallbackGetTaskLongLongValue  getTaskCalls;
        VecubCallbackGetTaskDoubleValue    getTaskNextCall;
#endif
    };
```

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux + GNU Compiler from MinGW on Windows

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux

Visual Studio compiler on Windows and GNU Compiler from MinGW on Linux + GNU Compiler from MinGW on Windows

Fig. 6-12: function pointers

Example for Usage of callbacks for Visual Studio compiler on Windows and GNU compiler on Ubuntu

The following code visualizes how you can use callbacks for plug-in version 2.

```
// ===== plug-in vers. 02 =====
DllExport vecub2Status __cdecl vecubFmi3EnterInit2(const VecubCall-
backs2* vecubCallbacks)
{
    if (!vecubCallbacks)
        return vecub2Status::vecubError;
```

The code defines the function `vecubFmi3EnterInit2` that takes a pointer to the structure `VecubCallbacks2` as input. It checks if the passed pointer `vecubCallbacks` is valid. If not, it returns `vecub1Status::vecubError`.

```
// logging
if (vecubCallbacks->log2)
{
 vecubCallbacks->log2("user message");
}
```

It checks if the `log2` function is defined in `vecubCallbacks` structure. If yes, it calls the function with the argument `user message`.

```
// get symbol info
SymbolInfo* symbol = static_cast<SymbolInfo*>(vecubCallbacks->getSym-
bolInfo2("factor1"));
std::cout << "The symbol has address: " << std::hex << symbol->addr <<
std::endl;
```

It calls `getSymbolInfo2` function to obtain information about a symbol named `factor1`. The returned symbol is stored in the variable `symbol`. The address of the symbol is printed using `std::cout`.

```
// get symbol accessor
PtrSymbolAccess& symbolAccessor = vecubCallbacks->getSymbolAccessor2
("factor1");
VarTypes val = (*symbolAccessor).get();
val.f64 = 5;
(*symbolAccessor).set(val);
```

It calls `getSymbolAccessor2` function to obtain an accessor for the `factor1` symbol. The accessor is stored in the reference variable `symbolAccessor`. It reads a value of type `IntFloat64` from the symbol and assigns the value `5` to it. Then, it writes the value back to the symbol.

Note

`PtrSymbolAccess` and `symbolAccessor` with its own methods became obsolete but are still supported. They are replaced by methods like:

vecubCallbacks->getSymbolValue2

vecubCallbacks->setSymbolValue2

```
// get task object
Task* task{nullptr};
 vecubCallbacks->getTask2("task_10ms", task);
task->setTNextCall(123);
 if (task) {
  std::cout << "FOUND! task: " << " ~ " << task->getName() <<
std::endl;
  }
```

It calls `getTask2` function to obtain a task object with the name `task_0ms`. The task object is stored in the pointer variable `task`. `setTNextCall` function is called on the task object with the value `123` as the argument. If the task object is valid, a message is printed with the task's name.

```
return vecub2Status::vecubOK;
}
```

It returns `vecub1Status::vecubOK`.

Example for usage of callbacks for Visual Studio compiler on Windows and GNU compiler on Ubuntu and GNU compiler from MinGW on Windows and Ubuntu

The following code visualizes how you can use callbacks for plug-in version 2.

```
// ===== plug-in vers. 02 =====
DllExport vecub2Status __cdecl vecubFmi3EnterInit2(const VecubCall-
backs2* vecubCallbacks)
{
    if (!vecubCallbacks)
        return vecub2Status::vecubError;
```

The code defines the function `vecubFmi3EnterInit2` that takes a pointer to the structure `VecubCallbacks2` as input. It checks if the passed pointer `vecubCallbacks` is valid. If not, it returns `vecub1Status::vecubError`.

```
// logging
if (vecubCallbacks->log2)
  {
    vecubCallbacks->log2("user message");
   }
```

It checks if the `log2` function is defined in `vecubCallbacks` structure. If yes, it calls the function with the argument `user message`.

```
// get symbol info
SymbolInfo* symbol = static_cast<SymbolInfo*>(vecubCallbacks->getSym-
bolInfo2("factor1"));
std::cout << "The symbol has address: " << std::hex << symbol->addr <<
std::endl;
```

It calls `getSymbolInfo2` function to obtain information about a symbol named `factor1`. The returned symbol is stored in the variable `symbol`. The address of the symbol is printed using `std::cout`.

```
// get symbol accessor
 VarTypes val2 = vecubCallbacks->getSymbolValue2("factor1");
std::cout << "symbol has value: " << val2.f64 << std::endl;
 val2.f64 = 123.45;
 vecubCallbacks->setSymbolValue2("factor1", val2);
```

It retrieves the symbol value associated with the key `factor1` using `getSymbolValue2` method and stores it in a variable called `val2` of type `VarTypes`. It then prints the value of the symbol to the console using `std::cout`. It modifies the value of the symbol by assigning a new value (123.45) to the `f64` field of the `val2` variable. Finally, it uses the `setSymbolValue2` method to update the value of the symbol associated with the key `factor1` to the new value stored in the `val2` variable.

```
// get task object
Task* tasknullptr{};
vecubCallbacks->getTask1("task_10ms", task);
std::cout << "Task getTaskNextCall: " << vecubCallbacks->getTaskNextCall(&task) << std::endl;
std::cout << "Task setTaskNextCall: " << vecubCallbacks->setTaskNextCall(&task, 1) << std::endl;
std::cout << "Task getTaskNextCall: " << vecubCallbacks->getTaskNextCall(&task) << std::endl;
```

A variable `task` of type `task*` is created and initialized with the value `nullptr`. Then the `getTask1` method of the `vecubCallbacks` object is called to retrieve the task named `task_10ms` and store it in the `task` variable. The methods `getTaskNextCall` and `setTaskNextCall` of the `vecubCallbacks` object are then called to get and set the next call time of the task. The results of these method calls are then output to the console using `std::cout`.

```
return vecub2Status::vecubOK;
}
```

It returns `vecub1Status::vecubOK`.

6.5.4 What a plug-in can do with tasks V2

A plug-in can access a task defined in VECU-BUILDER and can change different properties of a task at run time.

As described in Plug-In functions, you can use several functions. One of these functions is used to get a task. The used function pointer is `getTask2`, which returns a task type. For more information, see Fig. 6-12

Once the plug-in access a task, it can manage through the task interface and the behavior of a task during run time.

The interface of the task is available in plug-in template project through the definition of `task` class in `include/vecubTypes.h` file.

In this class, you can see specific functions of task class which manage i.e the task name, task period, or task priority.

7 Controlling VECU-BUILDER

7.1 Manual interaction

You can operate VECU-BUILDER via the provided batch/shell scripts. For some user inputs, such as selecting a workspace directory, the software displays dialogs.

7.2 Command Line Interface (CLI)

Besides the manual interaction method you can also operate VECU-BUILDER via a Command Line Interface (CLI). VECU-BUILDER is a CLI native software, and the batch/shell scripts allow manual interaction. For more information about the Installation using CLI, see Silent installation of VECU-BUILDER.

The following arguments exist:

`--new-project-path`: Path where the workspace is to be created.

`--no-dialogs`: Suppress all dialogs and always select the default option.

`--stop-on-success`: Prevents automatic forwarding to the next stage (create workspace, import, build).

`--version`: Prints the version information.

`-h`: Prints list of all optional arguments.

To see all CLI optional arguments and their description

1. Open a command prompt on **Windows**

   or

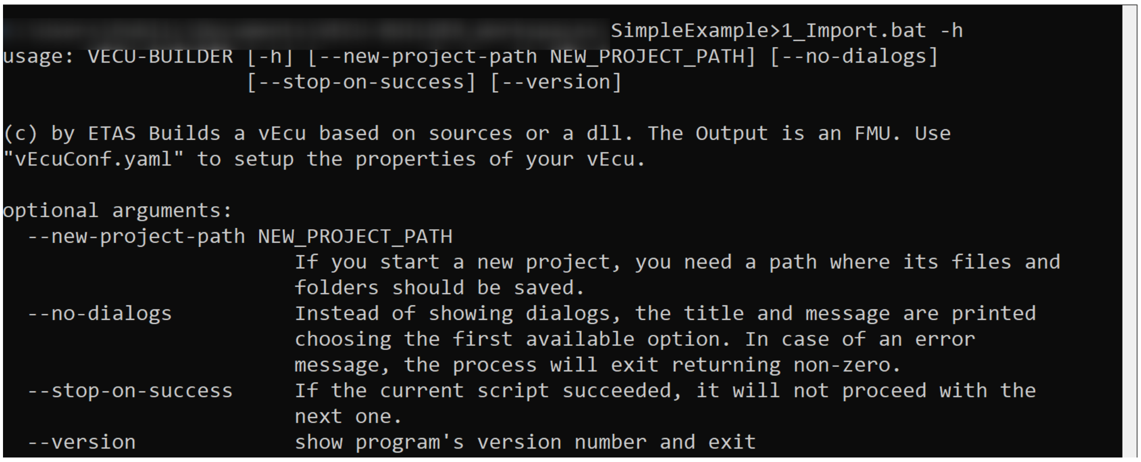
   Open a terminal on **Ubuntu 22.04 LTS**.

2. Execute the following command:

   `1_Import.bat -h` for **Windows**

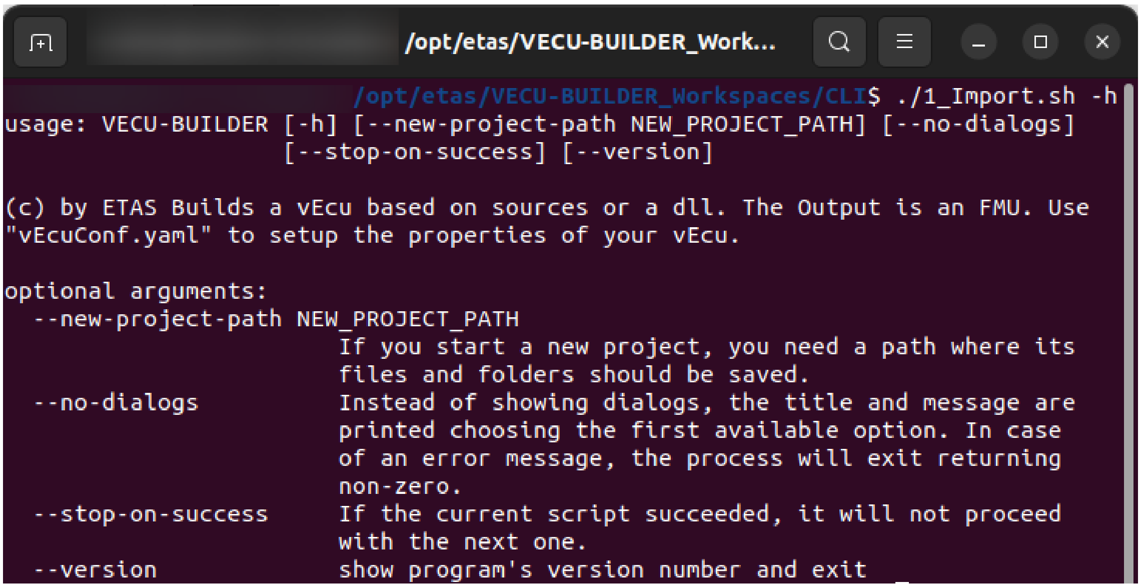
   or

   `./1_Import.sh -h` for **Ubuntu 22.04 LTS**.



```
[redacted]SimpleExample>1_Import.bat -h
usage: VECU-BUILDER [-h] [--new-project-path NEW_PROJECT_PATH] [--no-dialogs]
                    [--stop-on-success] [--version]

(c) by ETAS Builds a vEcu based on sources or a dll. The Output is an FMU. Use
"vEcuConf.yaml" to setup the properties of your vEcu.

optional arguments:
  --new-project-path NEW_PROJECT_PATH
                        If you start a new project, you need a path where its files and
                        folders should be saved.
  --no-dialogs          Instead of showing dialogs, the title and message are printed
                        choosing the first available option. In case of an error
                        message, the process will exit returning non-zero.
  --stop-on-success     If the current script succeeded, it will not proceed with the
                        next one.
  --version             show program's version number and exit
```

Fig. 7-1: CLI optional arguments on Windows 10



```
[redacted]/opt/etas/VECU-BUILDER_Workspaces/CLI$ ./1_Import.sh -h
usage: VECU-BUILDER [-h] [--new-project-path NEW_PROJECT_PATH] [--no-dialogs]
                    [--stop-on-success] [--version]

(c) by ETAS Builds a vEcu based on sources or a dll. The Output is an FMU. Use
"vEcuConf.yaml" to setup the properties of your vEcu.

optional arguments:
  --new-project-path NEW_PROJECT_PATH
                        If you start a new project, you need a path where its
                        files and folders should be saved.
  --no-dialogs          Instead of showing dialogs, the title and message are
                        printed choosing the first available option. In case
                        of an error message, the process will exit returning
                        non-zero.
  --stop-on-success     If the current script succeeded, it will not proceed
                        with the next one.
  --version             show program's version number and exit
```

Fig. 7-2: CLI optional arguments on Windows 10

The CLI control method is ideal for integrating VECU-BUILDER into an automation pipeline. The CLI behavior is the same as running the scripts manually. Each script calls the next script to proceed through the stages of create a workspace, import, build. To change this behavior, use `--stop-on-success`.

The following table gives an overview of which batch/shell script file uses which arguments:

argument	CreateWorkspace	1_Import	2_Build
--new-project-path	Used (required)	Ignored	Ignored
--no-dialogs	Used (optional)	Used (optional)	Used (optional)
--stop-on-success	Used (optional)	Used (optional)	Ignored
--version	Used (optional)	Used (optional)	Used (optional)
-h	Used (optional)	Used (optional)	Used (optional)

Tab. 7-1: Mapping of CLI arguments to scripts

To build the SimpleExample via two command lines

After creating the workspace, stop the process so you can copy a specific YAML file into your workspace. Then trigger the import without `stop-on-success` and let it finish the build automatically.

1. Open a command prompt on **Windows**

   or

   Open a terminal on **Ubuntu 22.04 LTS**.
2. Navigate to the directory where the installer is located executing the following command:

`cd %VECUBUILDER_HOME%.`

3. Execute the following command:

   `CreateWorkspace.bat` on **Windows**

 or

   `./CreateWorkspace.sh` on **Ubuntu 22.04 LTS**.

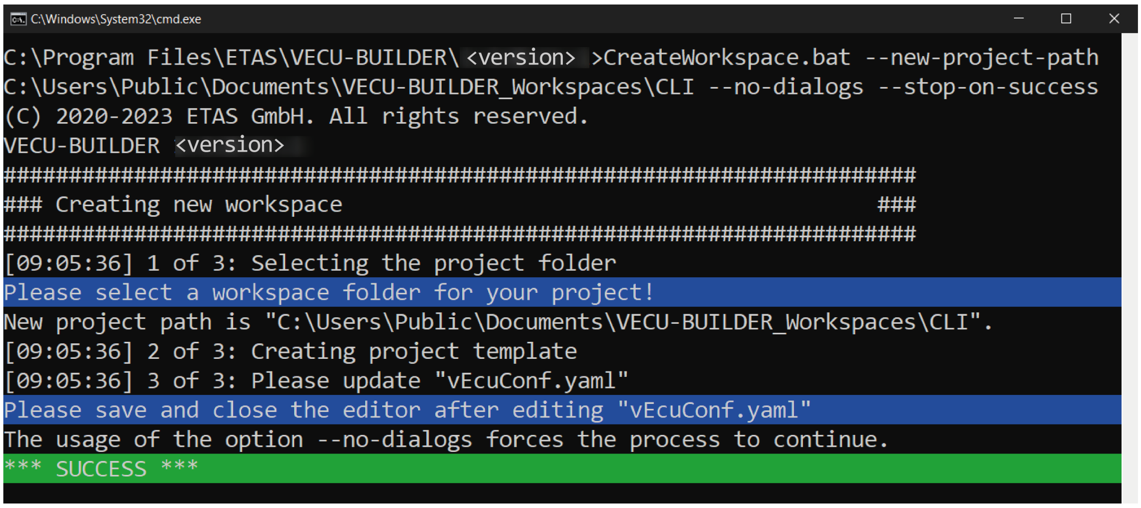
   with the arguments

   `--new-project-path <destination>`

   `--no-dialogs`

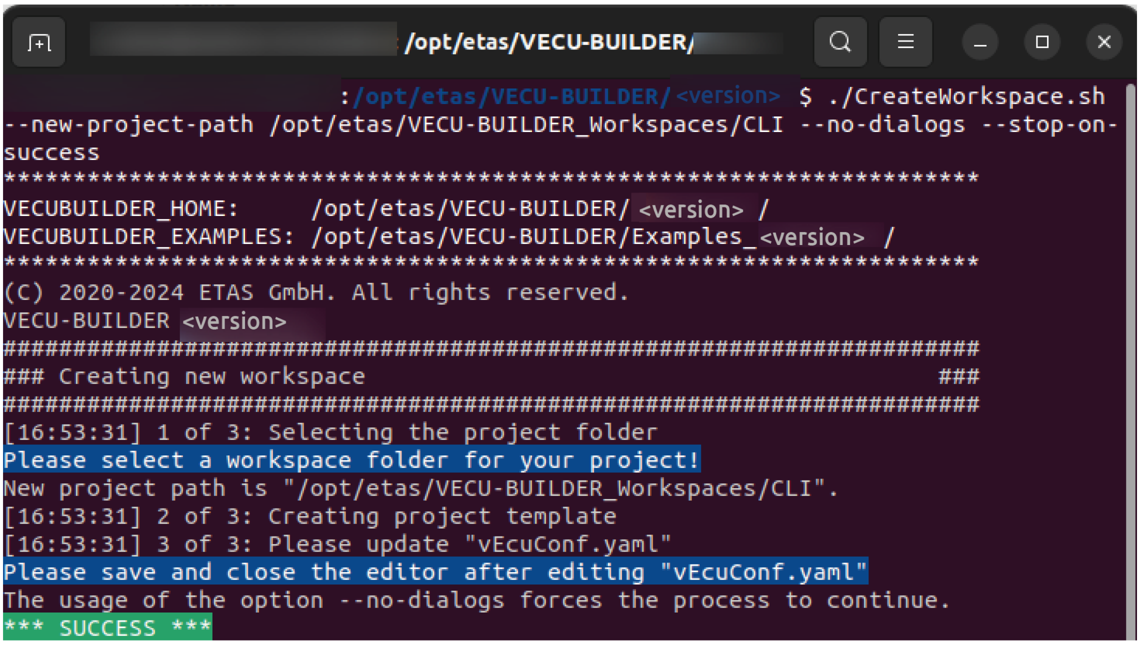
   `--stop-on-success`

   where `<destination>` points to your workspace folder.



```
C:\Program Files\ETAS\VECU-BUILDER\ <version> >CreateWorkspace.bat --new-project-path
C:\Users\Public\Documents\VECU-BUILDER_Workspaces\CLI --no-dialogs --stop-on-success
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Creating new workspace                                         ###
######################################################################
[09:05:36] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
New project path is "C:\Users\Public\Documents\VECU-BUILDER_Workspaces\CLI".
[09:05:36] 2 of 3: Creating project template
[09:05:36] 3 of 3: Please update "vEcuConf.yaml"
Please save and close the editor after editing "vEcuConf.yaml"
The usage of the option --no-dialogs forces the process to continue.
*** SUCCESS ***
```

Fig. 7-3: Workspace creation via CLI on Windows



```
[redacted]:/opt/etas/VECU-BUILDER/<version> $ ./CreateWorkspace.sh
--new-project-path /opt/etas/VECU-BUILDER_Workspaces/CLI --no-dialogs --stop-on-
success
**********************************************************************
VECUBUILDER_HOME:     /opt/etas/VECU-BUILDER/ <version> /
VECUBUILDER_EXAMPLES: /opt/etas/VECU-BUILDER/Examples_<version> /
**********************************************************************
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Creating new workspace                                         ###
######################################################################
[16:53:31] 1 of 3: Selecting the project folder
Please select a workspace folder for your project!
New project path is "/opt/etas/VECU-BUILDER_Workspaces/CLI".
[16:53:31] 2 of 3: Creating project template
[16:53:31] 3 of 3: Please update "vEcuConf.yaml"
Please save and close the editor after editing "vEcuConf.yaml"
The usage of the option --no-dialogs forces the process to continue.
*** SUCCESS ***
```

Fig. 7-4: Workspace creation via CLI on Ubuntu 22.04 LTS

> **Note**
>
> A default YAML file is used in all newly created workspaces.
>
> Project specific YAML file can be either prepared manually or in the previous step of your automation pipeline.

<u>To use your project specific YAML file in this newly created workspace:</u>

1. Execute the following command:

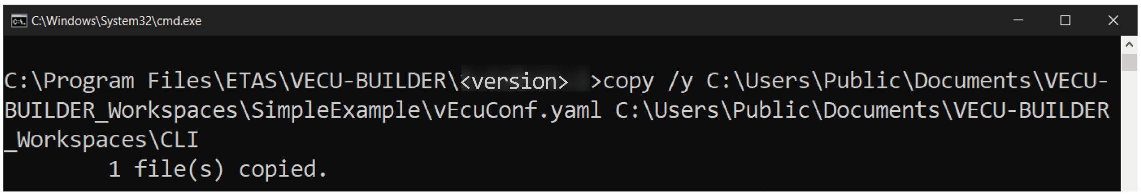
   `copy /y <source> <destination>` on **Windows**

   > **Note**
   >
   > The argument `/y` suppresses the prompt and thus overwrites the destination file.

   or

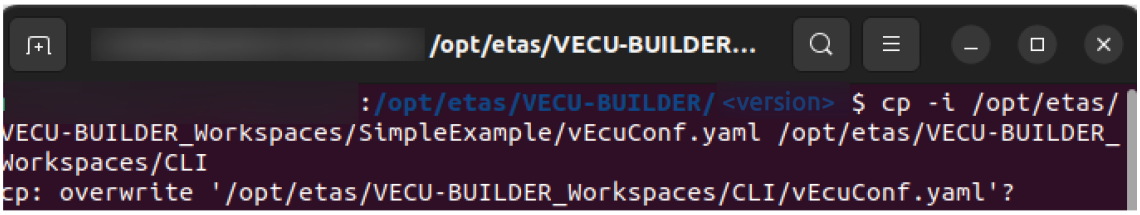
   `cp -i <source> <destination>` on **Ubuntu 22.04 LTS**.

   You are asked if you want to overwrite the file.



```
C:\Program Files\ETAS\VECU-BUILDER\<version>  >copy /y C:\Users\Public\Documents\VECU-BUILDER_Workspaces\SimpleExample\vEcuConf.yaml C:\Users\Public\Documents\VECU-BUILDER_Workspaces\CLI
        1 file(s) copied.
```

Fig. 7-5: Copy your project specific YAML file on Windows



```
[redacted]:/opt/etas/VECU-BUILDER/<version> $ cp -i /opt/etas/VECU-BUILDER_Workspaces/SimpleExample/vEcuConf.yaml /opt/etas/VECU-BUILDER_Workspaces/CLI
cp: overwrite '/opt/etas/VECU-BUILDER_Workspaces/CLI/vEcuConf.yaml'?
```

Fig. 7-6: Copy your project specific YAML file on Ubuntu 22.04 LTS

<u>To continue building your workspace:</u>

1. Navigate to this new workspace by executing the following command:

   `cd <destination>`.

2. Run the command:

   `1_Import.bat --no-dialogs` on **Windows**

   or

   `./1_Import.sh --no-dialogs` on **Ubuntu 22.04 LTS**.

7.3 Ubuntu 22.04 LTS Command Line Interface

You can create a new workspace on WSL Ubuntu 22.04 LTS using the Ubuntu Command Line Interface.

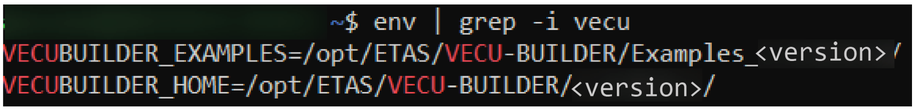
> **Note**
>
> Downloading dependencies or installing VECU-BUILDER only runs in WSL1, working with VECU-BUILDER only runs in WSL2. Ensure that the WSL version aligns with the specific action. If necessary, you need to change the version.
>
> – For WSL1:
> - wsl --set-version Ubuntu-22.04 1
>
> – For WSL2:
> - wsl --set-version Ubuntu-22.04 2

1. Open PowerShell and set WSL Ubuntu 22.04 LTS version to 2 using the following command:

   ```
   wsl --set-version Ubuntu-22.04 2
   ```

2. Open Ubuntu 22.04 LTS and ensure that the environment variables are set correctly using the following command:

   ```
   env | grep -i vecu
   ```

   ```
   [redacted] ~$ env | grep -i vecu
   VECUBUILDER_EXAMPLES=/opt/ETAS/VECU-BUILDER/Examples_<version>/
   VECUBUILDER_HOME=/opt/ETAS/VECU-BUILDER/<version>/
   ```

3. Change directory using the following command:

   ```
   cd $VECUBUILDER_HOME
   ```

4. Create a new workspace using the following command:

   ```
   ./CreateWorkspace.sh --no-dialogs --new-project-path
   /opt/etas/VECU-BUILDER_Workspaces/SimpleExample/
   ```

or

With installed gnome terminal workspace creation also works in dialog mode using the following command:

```
./CreateWorkspace.sh --new-project-path /opt/etas/VECU-
BUILDER_Workspaces/SimpleExample/
```

⇨ A new workspace was created. For more information about workspace content, see Workspace content.

8 Debugging vECU

VECU-BUILDER provides useful functionalities to debug your vECU. It is possible to debug the vECU by using an Integrated Development Environment (IDE), such as Visual Studio Code or Visual Studio.

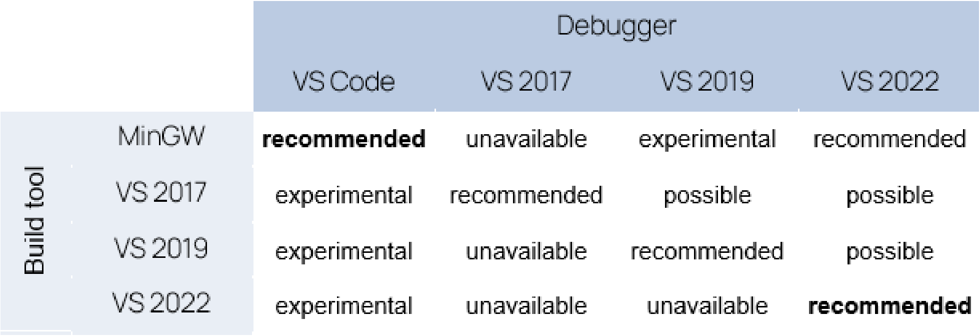
As the folder `<workspace>/vECU` is a CMake project, any IDE that can import CMake projects can be used for debugging.

During the build stage, the debugging environment and batch/shell script files are created. This enables you to enter a debugging session in just a few clicks.

You can use the `debug_hook` attribute, which can be enabled in the YAML file. vECUs built with this attribute enabled enter their instantiation and wait for a debugger you need to attach before continuing.

> **Note**
>
> The VECU-BUILDER debugging functionality is intended to be used for debugging of a single vECU within its workspace. If your vECU is integrated into a simulation, the `debug_hook` might be the best option for debugging,

The below table summarizes the possible combinations of build tool and debugger:



		Debugger			
		VS Code	VS 2017	VS 2019	VS 2022
Build tool	MinGW	**recommended**	unavailable	experimental	recommended
	VS 2017	experimental	recommended	possible	possible
	VS 2019	experimental	unavailable	recommended	possible
	VS 2022	experimental	unavailable	unavailable	**recommended**

Tab. 8-1: Debugging possibilities

Combinations marked as experimental, are neither tested nor supported and their use is solely your responsibility.

Among the recommended combinations, two are particularly recommended for use and are described in detail in the following chapters.

8.1 Debugging with Visual Studio 2019

This chapter describes how you can debug a vECU built with Visual Studio 2019 using Visual Studio 2019 as the debugger.

For more information about Visual Studio 2019, see Visual Studio documentation.

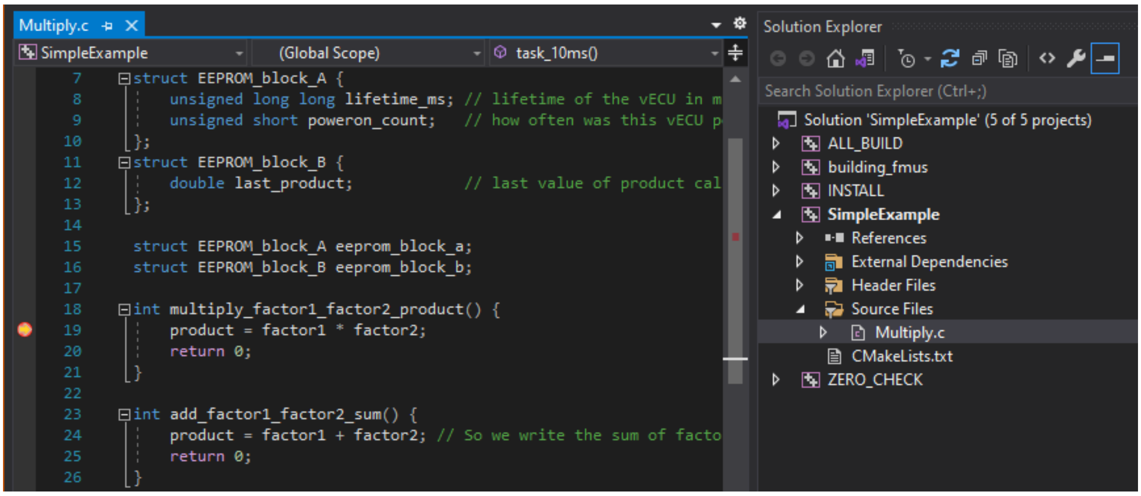
To debug with Visual Studio 2019

1. Navigate to your workspace.
2. Execute the `3b_StartDebugger.bat` file on **Windows** or `3b_StartDebugger.sh` on **Ubuntu 22.04 LTS**.

⇨ The VS2019 debugger is invoked and loads the CMake project.

3. Navigate to where you want to start debugging and set a breakpoint there.
4. In the **Menu** tab **click Debug › Start Debugging (F5)**.

⇨ fmusim is invoked and the debugger is attached.



```c
struct EEPROM_block_A {
    unsigned long long lifetime_ms; // lifetime of the vECU in m
    unsigned short poweron_count;   // how often was this vECU p
};
struct EEPROM_block_B {
    double last_product;            // last value of product cal
};

struct EEPROM_block_A eeprom_block_a;
struct EEPROM_block_B eeprom_block_b;

int multiply_factor1_factor2_product() {
    product = factor1 * factor2;
    return 0;
}

int add_factor1_factor2_sum() {
    product = factor1 + factor2; // So we write the sum of facto
    return 0;
}
```

Fig. 8-1: VS 2019 Debugger attached

8.2 Debugging with Visual Studio Code

This chapter describes how you can debug a vECU built with MinGW using Visual Studio Code as the debugger.

Prerequisites for debugging with Visual Studio Code

It is obligatory to install the following packages in Visual Studio Code:

- Microsoft C/C++ Extension Pack

For Debugging in WSL Ubuntu with Visual Studio Code additionally install the following packages:

- C/C++ extensions for Visual Studio Code and WSL Ubuntu in Windows computer Host
- CMake extensions for Visual Studio Code and WSL Ubuntu in Windows computer Host
- CMake Tools extensions for Visual Studio Code and WSL Ubuntu in Windows computer Host
- gdb in Ubuntu WSL (see Installing dependent software packages.)

Debugging is not possible without installing these packages.

Visual Studio Code requires some further extensions and will prompt you to install them by default.

For more Information about Visual Studio Code, see Visual Studio Code documentation.

To debug with Visual Studio Code in Windows

1. Navigate to your workspace.
2. Right-click in your workspace and select **Open with Code**.

⇨ Visual Studio Code opens.

3. Navigate to where you want to start the debugging and set a breakpoint there.
4. Click **Start Debugging (F5)**.
5. In the **menu** panel on the left click **Run and Debug**.

⇨ fmusim is invoked and the debugger is attached.

To debug with Visual Studio Code in Ubuntu 22.04 LTS

1. Navigate to your workspace.
2. Start debugging using the following command:

```
$ ./3b_StartDebugger.sh
```

⇨ Visual Studio Code opens.

3. Navigate to where you want to start the debugging and set a breakpoint there.
4. In the **menu** panel on the left click **Run and Debug**.
5. Click **Start Debugging (F5)**.

⇨ fmusim is invoked and the debugger is attached.

To debug with Visual Studio Code in WSL

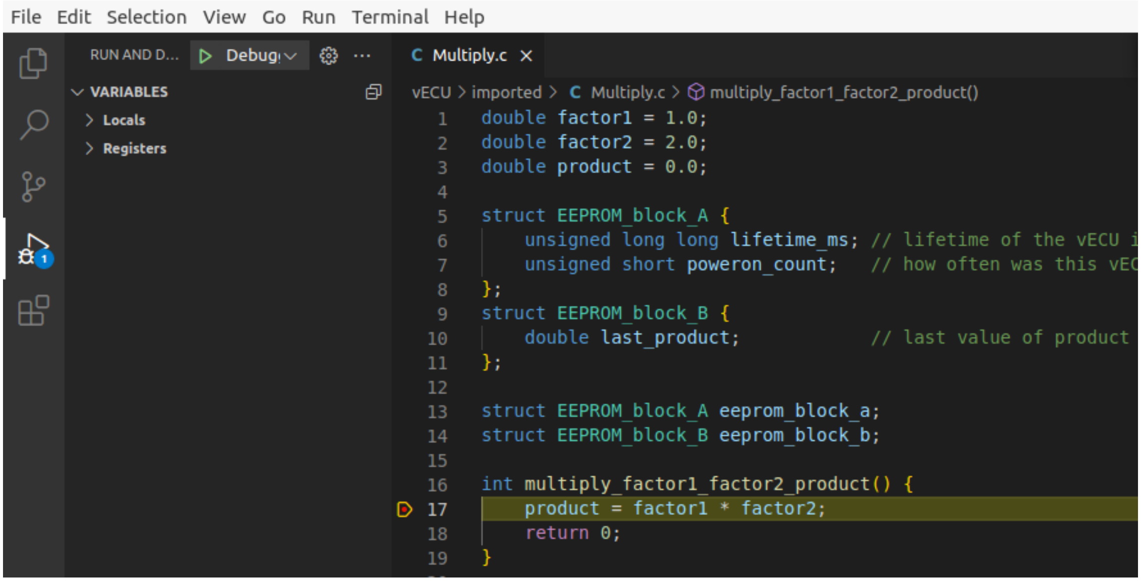
1. Check if gnome-terminal and gdb are installed. If not installed, see Installing VECU-BUILDER on Ubuntu 22.04 LTS for WSL.
2. Navigate to your workspace.
3. Start debugging using the following command:

```
./3b_StartDebugger.sh
```

⇨ Visual Studio Code opens.

4. Navigate to where you want to start the debugging and set a breakpoint there.
5. Click **Start Debugging (F5)**.
6. In the **menu** panel on the left click **Run and Debug**.

⇨ fmusim is invoked and the debugger is attached.



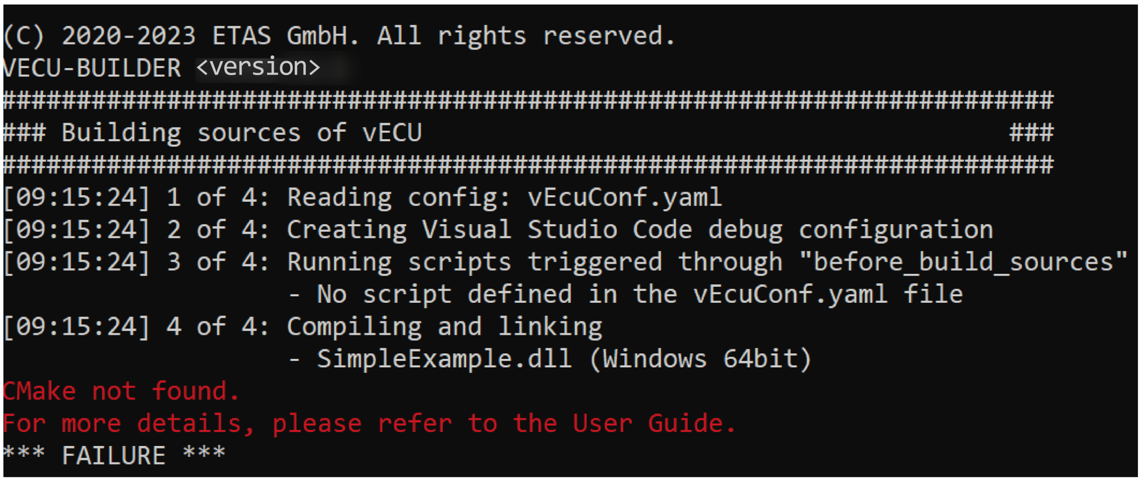
```
double factor1 = 1.0;
double factor2 = 2.0;
double product = 0.0;

struct EEPROM_block_A {
    unsigned long long lifetime_ms; // lifetime of the vECU i
    unsigned short poweron_count;   // how often was this vEC
};
struct EEPROM_block_B {
    double last_product;            // last value of product
};

struct EEPROM_block_A eeprom_block_a;
struct EEPROM_block_B eeprom_block_b;

int multiply_factor1_factor2_product() {
    product = factor1 * factor2;
    return 0;
}
```

Fig. 8-2: VS Code Debugger attached

9 Troubleshooting

This chapter lists possible warning or error messages, their possible reasons and a possible solution to fix the issue.

9.1 CMake not found



```
(C) 2020-2023 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Building sources of vECU                                       ###
######################################################################
[09:15:24] 1 of 4: Reading config: vEcuConf.yaml
[09:15:24] 2 of 4: Creating Visual Studio Code debug configuration
[09:15:24] 3 of 4: Running scripts triggered through "before_build_sources"
                   - No script defined in the vEcuConf.yaml file
[09:15:24] 4 of 4: Compiling and linking
                   - SimpleExample.dll (Windows 64bit)
CMake not found.
For more details, please refer to the User Guide.
*** FAILURE ***
```

Fig. 9-1: CMake not found error

Possible reason

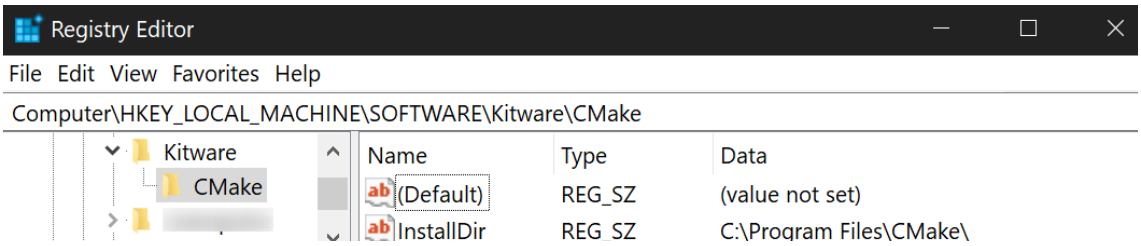
A CMake installation is required and must be registered properly (seeSoftware requirements for Windows 10). This registry entry is used to locate the CMake installation. If it does not exist, the build fails.

It seems that CMake is either not installed or not properly registered on your computer.

Possible solution

Ensure the following:

- CMake is installed (version 3.15 or higher).
- Kitware and CMake keys exist in the Windows Registry.
- The CMake registry key `Computer\HKEY_LOCAL_MACHINE\SOFTWARE\Kitware\CMake` contains the string value `InstallDir` pointing to the CMake installation path:



Computer\HKEY_LOCAL_MACHINE\SOFTWARE\Kitware\CMake

Name	Type	Data
(Default)	REG_SZ	(value not set)
InstallDir	REG_SZ	C:\Program Files\CMake\

Fig. 9-2: Windows Registry with Kitware\CMake registry key

9.2 Notepad++ does not open during workspace creation

Notepad++ is the recommended text editor to be used along with VECU-BUILDER. For it to work as intended, you need to install and register it properly.

If Notepad++ does not open during the Workspace Creation stage, but Windows Notepad opens instead it is either not installed at all or is not properly registered on your computer.

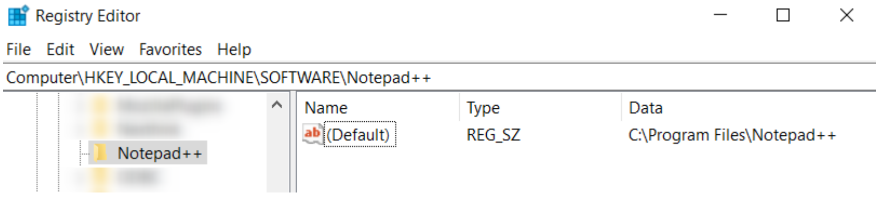
Possible solution

Ensure the following:

- Notepad++ is installed.
- Notepad++ key exists in the Windows registry.

A. **For 64-bit version:**

- The Notepad++ registry key `Computer/HKEY_LOCAL_MACHINE/SOFTWARE/Notepad++` contains the string value (Default) pointing to the Notepad++ installation path:

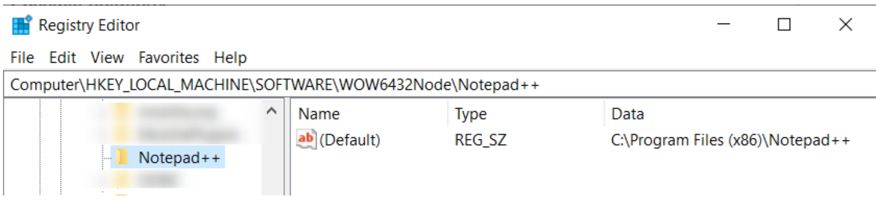


Computer\HKEY_LOCAL_MACHINE\SOFTWARE\Notepad++

Name	Type	Data
ab (Default)	REG_SZ	C:\Program Files\Notepad++

B. **For 32-bit version:**

- The Notepad++ registry key `Computer/HKEY_LOCAL_MACHINE/SOFTWARE/WOW6432Node/Notepad++` contains the string value (`Default`) pointing to the Notepad++ installation path:



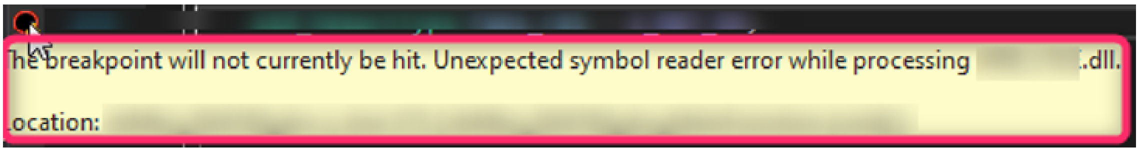
Computer\HKEY_LOCAL_MACHINE\SOFTWARE\WOW6432Node\Notepad++

Name	Type	Data
ab (Default)	REG_SZ	C:\Program Files (x86)\Notepad++

9.3 Some breakpoints not being hit

Possible reason

Depending on your compiler configurations, the resulting vECU may be built without some debugging information. This may result in the debugger not being able to hit some breakpoints.



The breakpoint will not currently be hit. Unexpected symbol reader error while processing [redacted].dll.

ocation: [redacted]

Fig. 9-3: Breakpoint not being hit

Possible solution

In order to prevent such compiler optimization, include the following pragma statements:

- For MSVC compiler: `#pragma optimize("", off)`
- For MinGW compiler: `#pragma GCC optimize ("O0")`

9.4 (SymbolInfo.dll) the *.die file is too large to load

Possible reason

The operating system does not provide sufficient amount of memory required to load the `*.die` file.

Possible solution

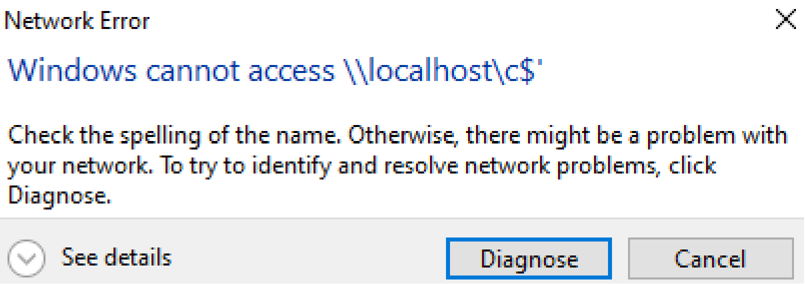
Use a computer with sufficient amount of memory.

9.5 Windows cannot access localhost while using sync attribute in EEPROM

Possible reason

EEPROM simulation feature requires entering the value of sync sub-attribute as UNC path.

If the defined location (e.g. `C:/drive` of your localhost) cannot be accessed during the vECU execution, the data defined by the sync sub-attribute cannot be used.



Network Error

Windows cannot access \\localhost\c$'

Check the spelling of the name. Otherwise, there might be a problem with your network. To try to identify and resolve network problems, click Diagnose.

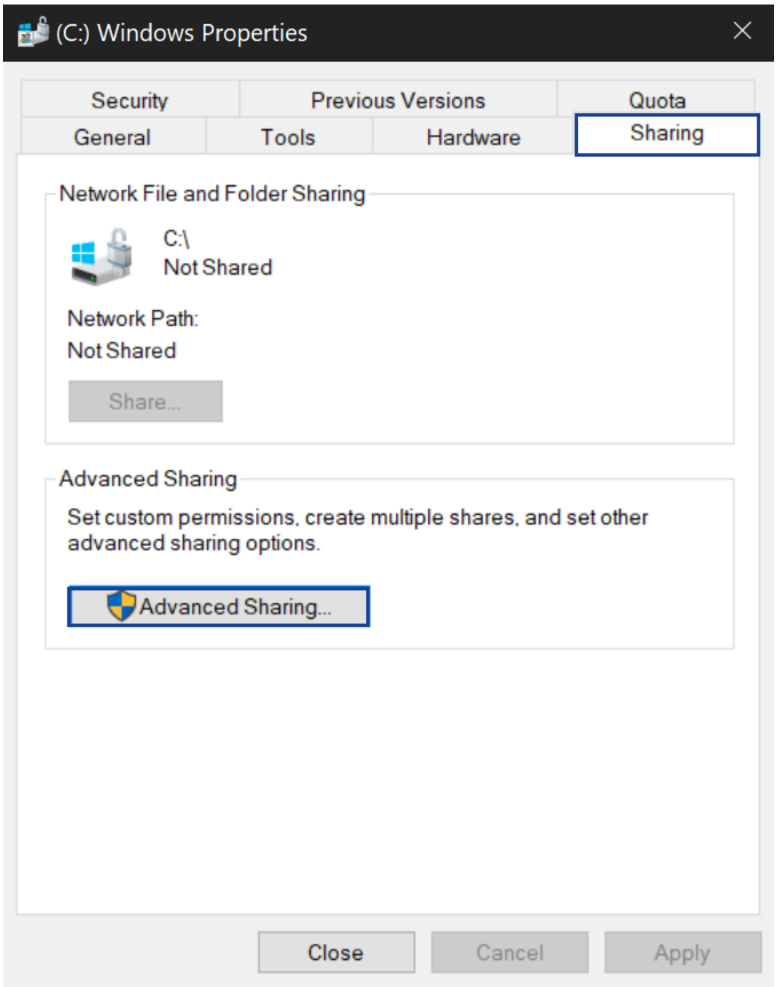
Fig. 9-4: Network Error - Localhost cannot be accessed

Possible solution

Setup the local share and obtain the UNC path name.

To setup a local share:

1. Navigate to the drive, you want to share. (e.g. `C:/drive`)
2. Right-click the drive and click **Properties**.
3. Click the **Sharing** tab.
4. Click **Advanced Sharing**. You will need Admin Rights to proceed.



Network File and Folder Sharing

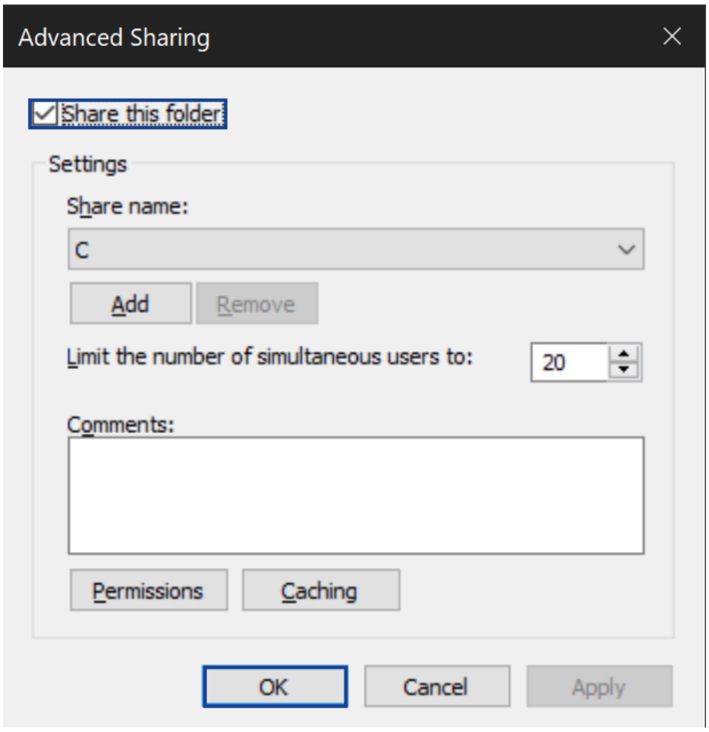
C:\
Not Shared

Network Path:
Not Shared

Advanced Sharing

Set custom permissions, create multiple shares, and set other advanced sharing options.

5. Activate the checkbox **Share this folder**.
6. Click **OK**.



Advanced Sharing

☑ Share this folder

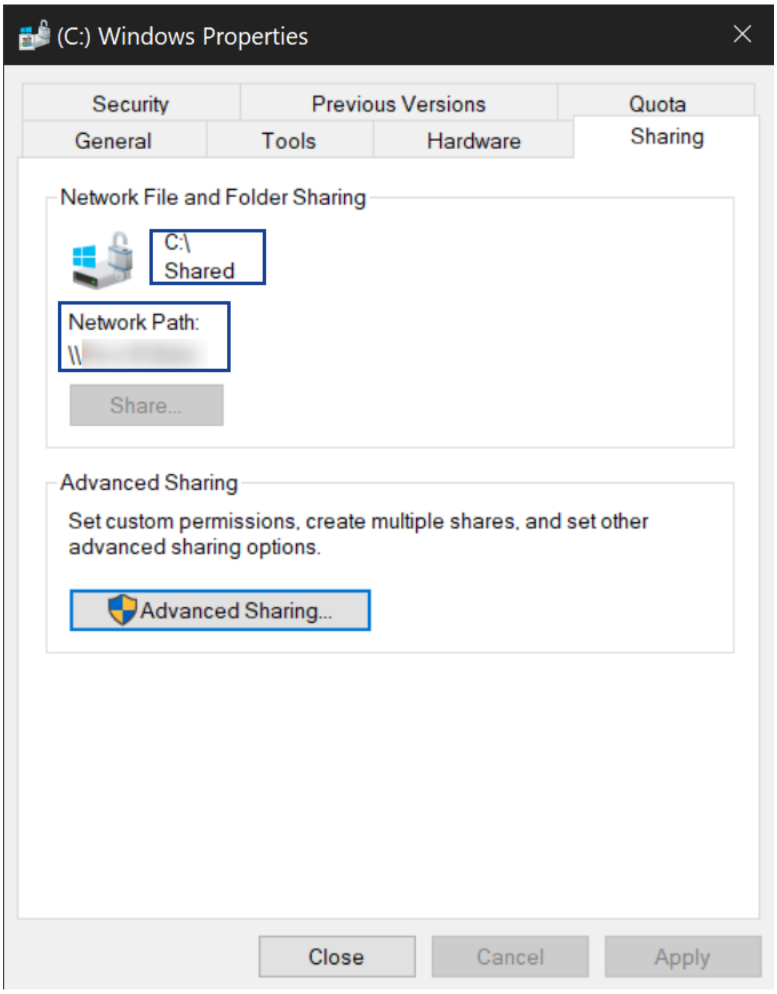
Settings

Share name: C

Limit the number of simultaneous users to: 20

Comments:

⇨ The drive is now shared and the network path is displayed.



(C:) Windows Properties

Network File and Folder Sharing

C:\
Shared

Network Path:
\\[redacted]

Advanced Sharing

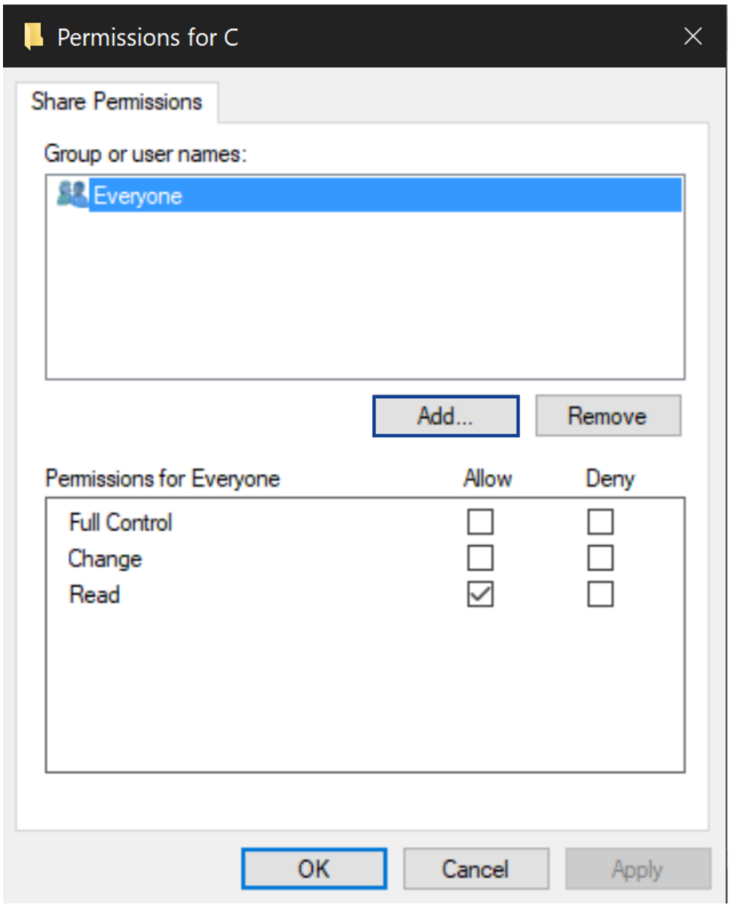
Set custom permissions, create multiple shares, and set other advanced sharing options.

When you are logged in during the execution of the vECU, you need full control permissions to the shared location.

Per default, Windows will provide permissions to everyone. The permissions should only be provided to the user, that will be logged in during the execution of the vECU. Therefore, the permissions must to be changed for security reasons.

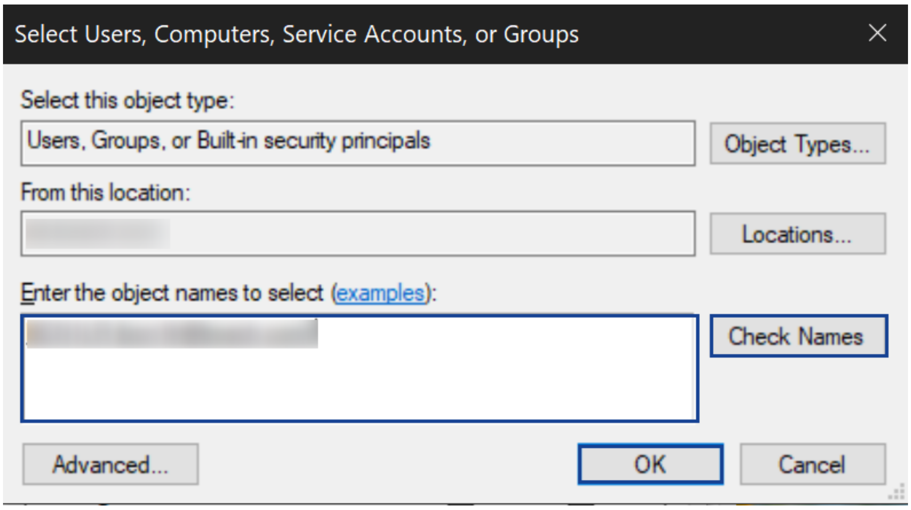
To change the permissions

1. Click **Advanced Sharing**. You might need Admin Rights to proceed.
2. Click **Permissions**.
3. Click **Add**.



Permissions for Everyone	Allow	Deny
Full Control	□	□
Change	□	□
Read	☑	□

4. Enter the object name (username) to be selected.
5. Click **Check Names**.
6. Chose the displayed name.
7. Click **OK**.



Select Users, Computers, Service Accounts, or Groups

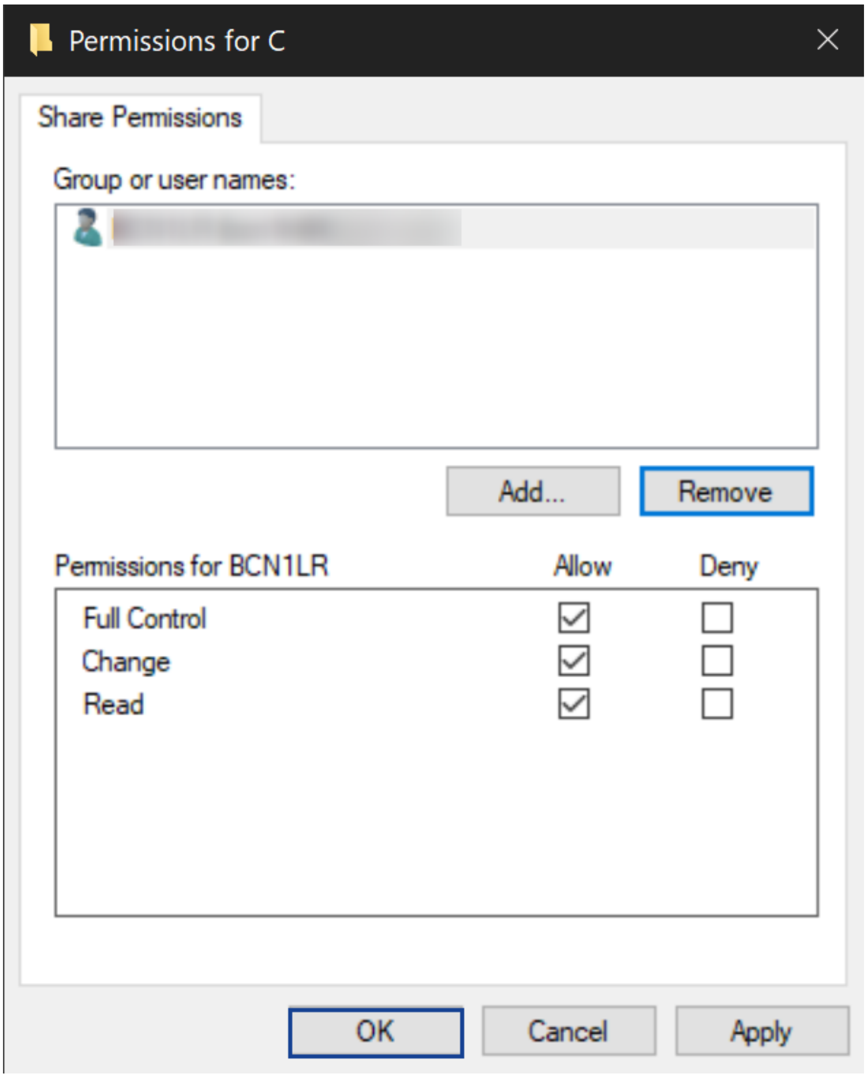
Select this object type:
Users, Groups, or Built-in security principals

From this location:
[redacted]

Enter the object names to select (examples):
[redacted]

8. To mark the entry, click the user name.
9. Activate the checkboxes **Full Control** and **Change**.
10. To mark the entry, click **Everyone**.
11. To remove the permission for **everyone**, click **Remove**.

⇨ The group **Everyone** is removed and the selected user has now full permissions.



Permissions for C

Share Permissions

Group or user names:

[redacted]

Permissions for BCN1LR

Permissions for BCN1LR	Allow	Deny
Full Control	☑	□
Change	☑	□
Read	☑	□

12. To confirm the User Selection, click **OK**.
13. To confirm the updated **Advanced Sharing**" properties, click **OK**.
14. Close the **Properties** window.

9.6 Redirecting function calls did not work as expected

Possible reason

The GNU compiler optimization level 2 (**-O2**) includes `inline-small-functions` which is incompatible with `redirect_function_calls`.

By default VECU-BUILDER uses the compile settings `RelWithDebInf`, which includes some optimizations. For gcc this uses the setting **-O2**, which includes `inline-small-functions`.

Possible solution

Change the settings in `additional_compile_flags` to enable `redirect_function_calls`.

There are 3 ways to deactivate the optimization:

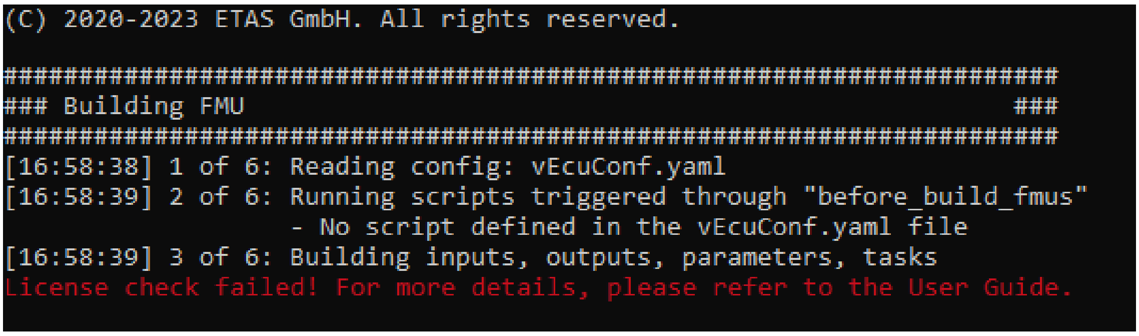
A. -O0: Completely deactivates optimization. This has the advantage that the compiler time of user workspace decreases.

B. -O1: Reduces the level of optimization from default 2 to 1.

C. -O2 -f-no-inline-small-functions: Keeps optimization to level 2 but only disables the special optimization with `-f-no-inline-small-functions`.

For more information, see Options that control optimization.

9.7 License check failed



```
(C) 2020-2023 ETAS GmbH. All rights reserved.

######################################################################
### Building FMU                                                   ###
######################################################################
[16:58:38] 1 of 6: Reading config: vEcuConf.yaml
[16:58:39] 2 of 6: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[16:58:39] 3 of 6: Building inputs, outputs, parameters, tasks
License check failed! For more details, please refer to the User Guide.
```

Possible reason

- The LiMa installation is corrupt.
- LiMa can not reach the license server.

Possible solution

- Reinstall VECU-BUILDER described in Installation on Windows 10 and Installation on Ubuntu 22.04 LTS or contact technical support.
- Check network settings to get a connection to the license server.

9.8 Building sources failed

Possible reason

In some cases, building sources fails with various error messages. To save time, CMake uses caches, e.g. a link to the build tool is stored.

Possible solution

To fix a broken CMake cache, delete the cache and rebuild the sources.

1. Navigate to the `vECU` folder.
2. Delete everything except the `imported` folder.
3. Rebuild the sources using `2_Build.bat` on **Windows** or `2_Build.sh` on **Ubuntu 22.04 LTS**.

If the build fails due to CMake reason, you can find more details in `build/-log/build_cmake.log` file.

9.9 Indentation errors in YAML file

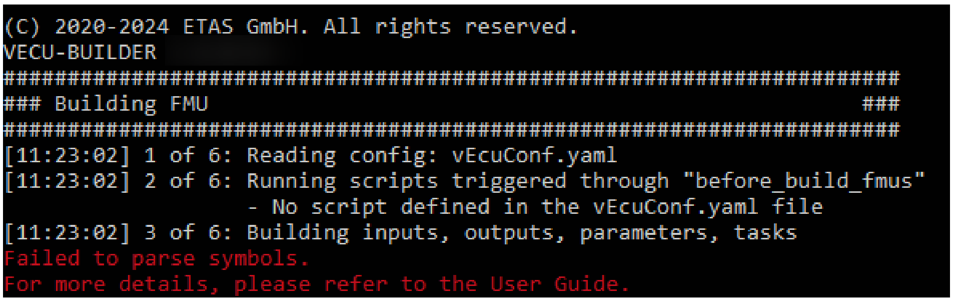
Indentation errors can occur and they are difficult to detect.

Possible solution

To check for indentation errors in YAML file, use a YAML Checker. There are online softwares available. You can search for YAML checker in any search engine. Follow the instructions given by the selected YAML Checker.

9.10 Failed to parse symbols

It is possible, that symbol/debug information is missing in the binary. The error message below treats the missing debug information during build process when `build_mode` is `import_compiled`.



```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER
########################################################################
### Building FMU                                                     ###
########################################################################
[11:23:02] 1 of 6: Reading config: vEcuConf.yaml
[11:23:02] 2 of 6: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[11:23:02] 3 of 6: Building inputs, outputs, parameters, tasks
Failed to parse symbols.
For more details, please refer to the User Guide.
```

Possible reason

The error occurs due to some mishandling of DLL/SO when `build_mode` in YAML file is set to `import_compiled`.

Possible solution

- If the used `build_tool` is one of the Visual Studio compile versions (like 16 2016 or 17 2022), ensure that besides the DLL loaded, there must also exist a mandatory PDB file. The source location for DLL & PDB is given by YAML settings `import_external_compiled_vecu` and `get_updates_from`.
- If the `build_tool` used is **MinGW Makefiles for Windows** or **Unix Makefiles for Ubuntu**, only the DLL/SO is required. Ensure that the DLL/SO compulsory contains debug information. A DIE file is created locally when building FMUs runs. Afterwards also `SymbolDetails.txt` is created.
- Ensure that the `build_tool` YAML settings match the compiler used to build the DLL:
  - If the imported DLL was built with the GNU compiler from MinGW, ensure that `build_tool` is **MinGW Makefiles** (`build_tool: MinGW Makefiles`).
  - If the imported DLL was built with a Visual Studio compiler, ensure that `build_tool` is **Visual Studio xx xxxx** (`build_tool: Visual Studio xx xxxx`).

For more information see import_external_compiled_vecu in configuration chapter.

9.11 Could not load the vECU binary

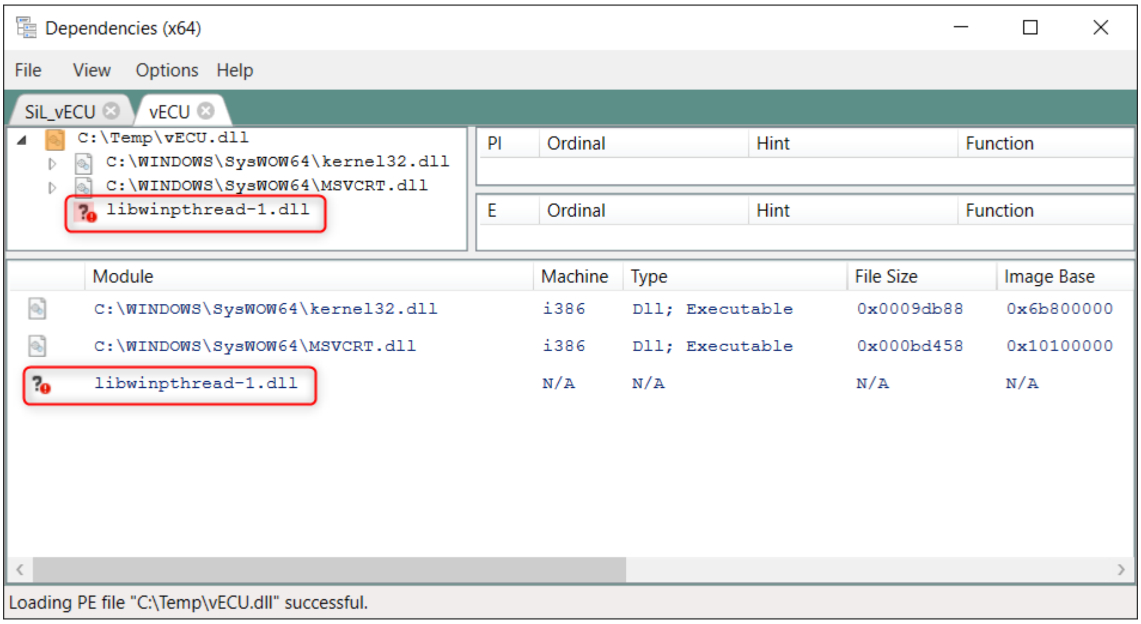
During the vECU FMU build the `SymbolDetails.txt` variables are updated with the initial values by loading of the `vECU.dll/so` binary and reading the values from RAM. In cases where the`vECU.dll/so` cannot be loaded, the `SymbolDetails.txt` variables receive the default value 0. You are informed with an appropriate message in the `build_fmu.log` file. In this case, the FMU build is possible, but the generated FMU execution will not work due to the same `vECU.dll/so` loading problem as during the build.

<u>Possible reason</u>

One or more dynamic libraries, required for the `vECU.dll/so` execution are missing / could not be found by the OS.

<u>Possible solution for Windows:</u>

Check by loading the `vECU.dll`, which dynamic libraries are missing using the open source SW Dependencies.



```
C:\Temp\vECU.dll
    C:\WINDOWS\SysWOW64\kernel32.dll
    C:\WINDOWS\SysWOW64\MSVCRT.dll
    libwinpthread-1.dll
```

Module	Machine	Type	File Size	Image Base
C:\WINDOWS\SysWOW64\kernel32.dll	i386	Dll; Executable	0x0009db88	0x6b800000
C:\WINDOWS\SysWOW64\MSVCRT.dll	i386	Dll; Executable	0x000bd458	0x10100000
libwinpthread-1.dll	N/A	N/A	N/A	N/A

Loading PE file "C:\Temp\vECU.dll" successful.

Provide the missing info about the dynamic library to the system using the `vECUConf.yaml` options:

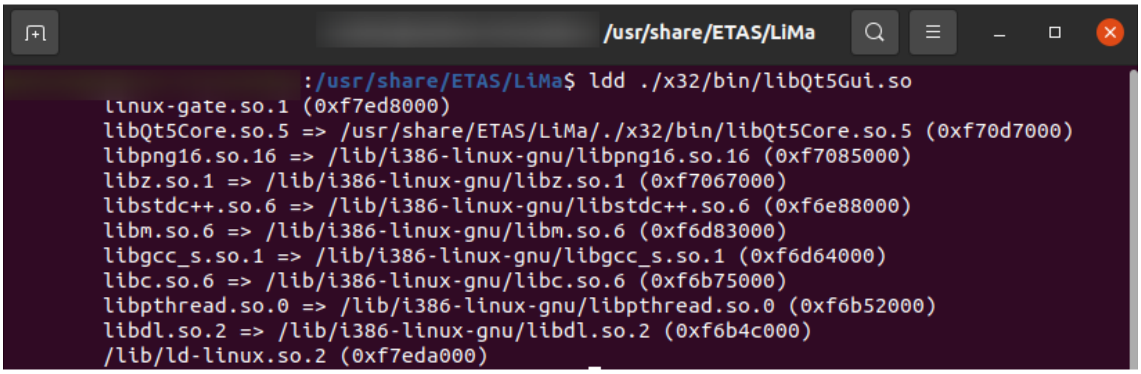
Option 1: (most recommended): Add the library to the resources folder of the `vECU.fmu` using `additional_resources`.

Option 2: Provide the corresponding path to the missing library using `environment_variables`.

Possible solution for Ubuntu 22.04 LTS

To check the dependencies in Linux run `ldd` command on a `*.so` file.

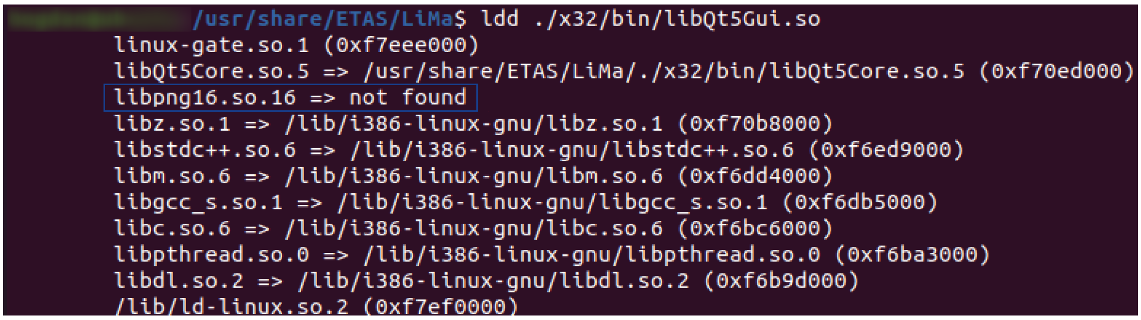
Example: `ldd libQt5Gui.so`



```
[redacted]:/usr/share/ETAS/LiMa$ ldd ./x32/bin/libQt5Gui.so
        linux-gate.so.1 (0xf7ed8000)
        libQt5Core.so.5 => /usr/share/ETAS/LiMa/./x32/bin/libQt5Core.so.5 (0xf70d7000)
        libpng16.so.16 => /lib/i386-linux-gnu/libpng16.so.16 (0xf7085000)
        libz.so.1 => /lib/i386-linux-gnu/libz.so.1 (0xf7067000)
        libstdc++.so.6 => /lib/i386-linux-gnu/libstdc++.so.6 (0xf6e88000)
        libm.so.6 => /lib/i386-linux-gnu/libm.so.6 (0xf6d83000)
        libgcc_s.so.1 => /lib/i386-linux-gnu/libgcc_s.so.1 (0xf6d64000)
        libc.so.6 => /lib/i386-linux-gnu/libc.so.6 (0xf6b75000)
        libpthread.so.0 => /lib/i386-linux-gnu/libpthread.so.0 (0xf6b52000)
        libdl.so.2 => /lib/i386-linux-gnu/libdl.so.2 (0xf6b4c000)
        /lib/ld-linux.so.2 (0xf7eda000)
```

Fig. 9-5: Check dependencies in Linux

This command will give you the list of the dependencies. If one file is missing, this command will give a **not found** message.

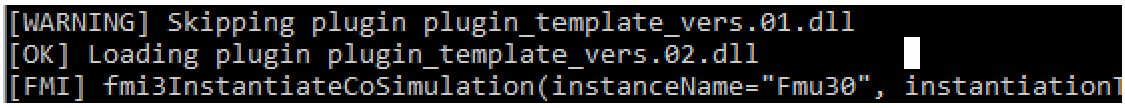


```
[redacted] /usr/share/ETAS/LiMa$ ldd ./x32/bin/libQt5Gui.so
        linux-gate.so.1 (0xf7eee000)
        libQt5Core.so.5 => /usr/share/ETAS/LiMa/./x32/bin/libQt5Core.so.5 (0xf70ed000)
        libpng16.so.16 => not found
        libz.so.1 => /lib/i386-linux-gnu/libz.so.1 (0xf70b8000)
        libstdc++.so.6 => /lib/i386-linux-gnu/libstdc++.so.6 (0xf6ed9000)
        libm.so.6 => /lib/i386-linux-gnu/libm.so.6 (0xf6dd4000)
        libgcc_s.so.1 => /lib/i386-linux-gnu/libgcc_s.so.1 (0xf6db5000)
        libc.so.6 => /lib/i386-linux-gnu/libc.so.6 (0xf6bc6000)
        libpthread.so.0 => /lib/i386-linux-gnu/libpthread.so.0 (0xf6ba3000)
        libdl.so.2 => /lib/i386-linux-gnu/libdl.so.2 (0xf6b9d000)
        /lib/ld-linux.so.2 (0xf7ef0000)
```

Fig. 9-6: Not found message

One way to tell to a software where to search for its SO dependencies is to set `LD_LIBRARY_PATH` to the location where these SO resides.

9.12 Skipping plug-in



```
[WARNING] Skipping plugin plugin_template_vers.01.dll
[OK] Loading plugin plugin_template_vers.02.dll
[FMI] fmi3InstantiateCoSimulation(instanceName="Fmu30", instantiationT
```

Possible reason

The FMI version set in YAML file configuration does not fit to the plug-in version.

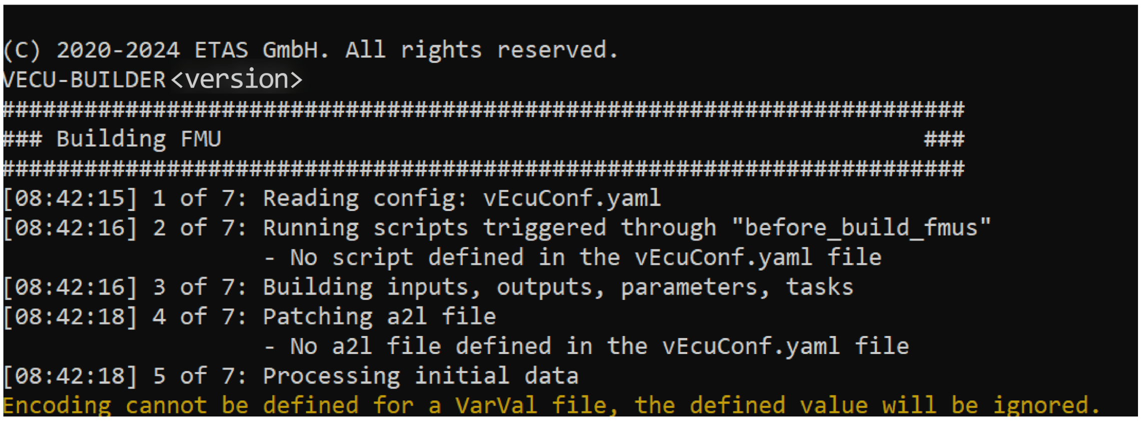
Possible solution

Check the selected FMI version in the YAML file and ensure that it corresponds to the correct and required plug-in version.

- If FMI version is set to 2 in YAML file, then the plug-in version must be 1.
- If FMI version is set to 3 in YAML file, then the plug-in version must be 2.

If there is no correspondence between FMI version and plug-in version, change it accordingly.

9.13 Encoding cannot be defined for a VARVAL file



```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER<version>
######################################################################
### Building FMU                                                   ###
######################################################################
[08:42:15] 1 of 7: Reading config: vEcuConf.yaml
[08:42:16] 2 of 7: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[08:42:16] 3 of 7: Building inputs, outputs, parameters, tasks
[08:42:18] 4 of 7: Patching a2l file
                   - No a2l file defined in the vEcuConf.yaml file
[08:42:18] 5 of 7: Processing initial data
Encoding cannot be defined for a VarVal file, the defined value will be ignored.
```

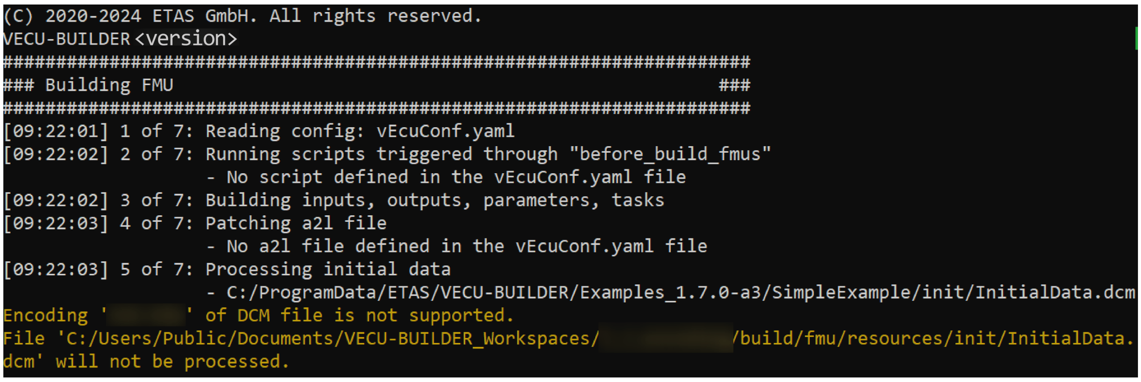
Possible reason

The encoding was used for VARVAL file and not for DCM file.

Possible solution

Ensure that the encoding is defined for DCM file. For more information, see initial_data in configuration chapter.

9.14 Encoding of DCM file is not supported



```
(C) 2020-2024 ETAS GmbH. All rights reserved.
VECU-BUILDER <version>
######################################################################
### Building FMU                                                   ###
######################################################################
[09:22:01] 1 of 7: Reading config: vEcuConf.yaml
[09:22:02] 2 of 7: Running scripts triggered through "before_build_fmus"
                   - No script defined in the vEcuConf.yaml file
[09:22:02] 3 of 7: Building inputs, outputs, parameters, tasks
[09:22:03] 4 of 7: Patching a2l file
                   - No a2l file defined in the vEcuConf.yaml file
[09:22:03] 5 of 7: Processing initial data
                   - C:/ProgramData/ETAS/VECU-BUILDER/Examples_1.7.0-a3/SimpleExample/init/InitialData.dcm
Encoding '[redacted]' of DCM file is not supported.
File 'C:/Users/Public/Documents/VECU-BUILDER_Workspaces/[redacted]/build/fmu/resources/init/InitialData.
dcm' will not be processed.
```

Possible reason

The used encoding is not supported or there is a misspelling in the encoding.

Possible solution

Ensure that the encoding is supported and there is no misspelling in the encoding. For more information, see initial_data in configuration chapter.

10 Contact information

Technical support

For details of your local sales office as well as your local technical support team and product hotlines, take a look at the ETAS website:

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