

# 基於 AUTOSAR CLASSIC 的 PORT DRIVER 開發

+  
•  
○

指導教授：張大緯

專題成員：曾宇弘



# 目錄

研究動機  
開發工具  
研究流程  
研究方法  
成果

# 研究動機



# 研究動機

汽車產業中大量地使用嵌入式系統，但卻苦無一個標準的架構規範，使系統的維護、升級與更換都遇上了不小的困難。因此陸續出現了使汽車系統標準化的協議。

為了能使系統更方便的去維護與設定，本專題將會基於 AUTOSAR Classic 架構，在現有的 OSEK/VDX 的車用作業系統 MilkShopOS 之下，進行 Port Driver 的開發。



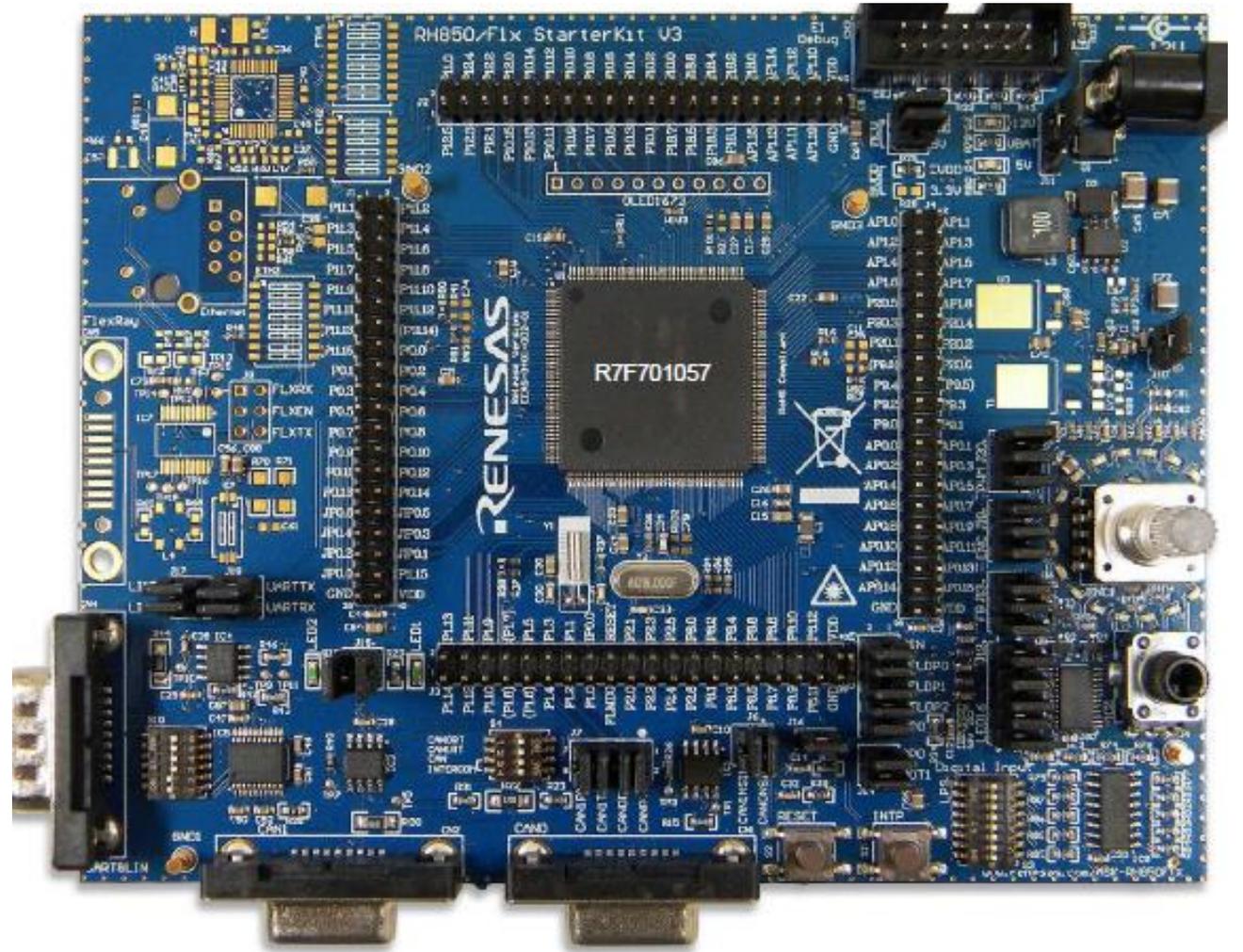


# 開發工具



# 開發工具

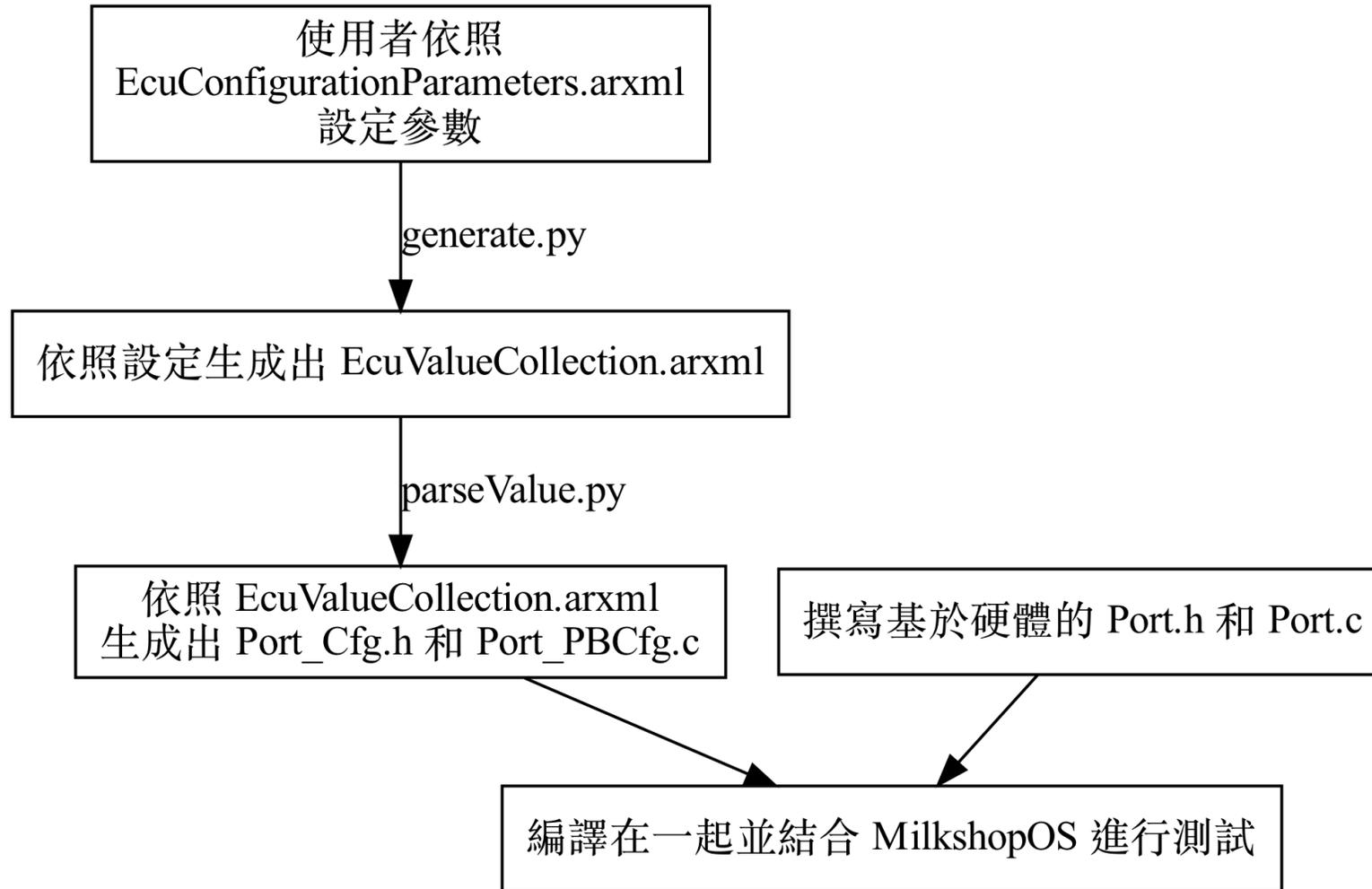
RH850/F1L  
Python 3.9.0  
CS+ for CC



# 研究流程



# 研究流程



# 研究方法



# 研究方法

基於 AUTOSAR CLASSIC 的 PORT DRIVER 開發

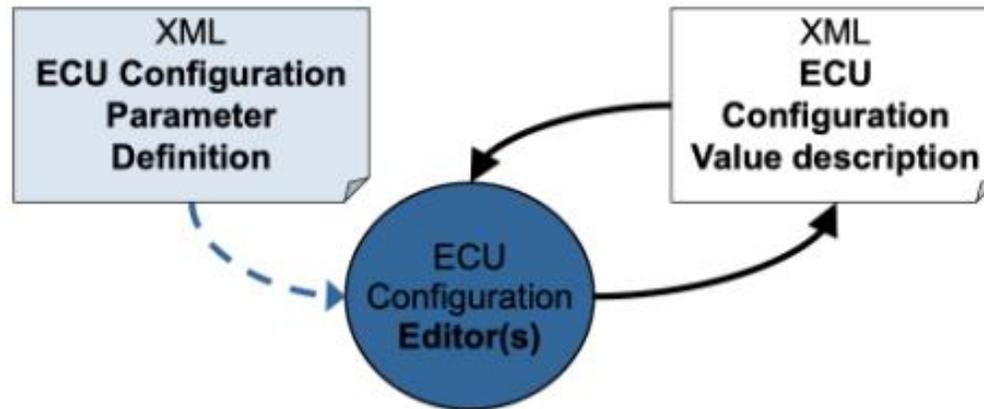
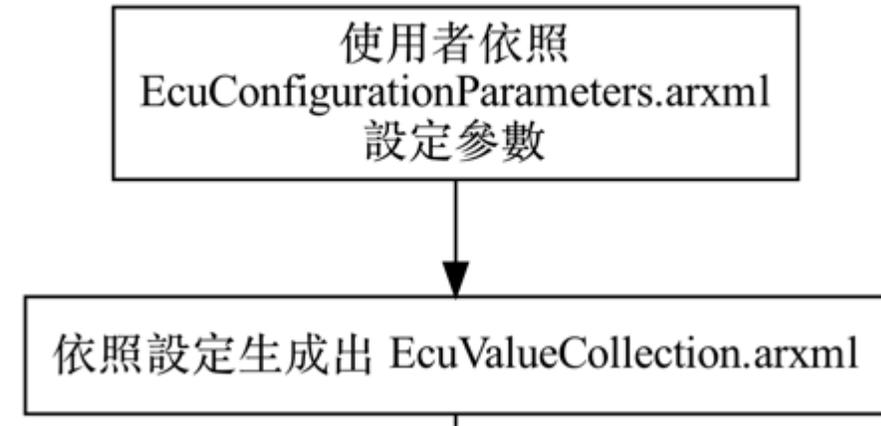


Figure 2.1: Parameter Definition and ECU Configuration Value files

## EcuConfigurationParameters.arxml (右圖)

```
<!-- PARAMETER DEFINITION: PortPinLevelValue -->
<ECUC-ENUMERATION-PARAM-DEF UUID="ECUC:83fdd686-ae98-423f-bdfb-c46dad6783f4">
  <SHORT-NAME>PortPinLevelValue</SHORT-NAME>
  <DESC>
    <L-2 L="EN">Port Pin Level value from Port pin list.</L-2>
  </DESC>
  <RELATED-TRACE-ITEM-REF BASE="ArTrace" DEST="TRACEABLE">ECUC_Port_00129</RELATED-TRACE-ITEM-REF>
  <LOWER-MULTIPLICITY>1</LOWER-MULTIPLICITY>
  <UPPER-MULTIPLICITY>1</UPPER-MULTIPLICITY>
  <SCOPE>LOCAL</SCOPE>
  <ORIGIN>AUTOSAR_ECUC</ORIGIN>
  <POST-BUILD-VARIANT-VALUE>true</POST-BUILD-VARIANT-VALUE>
  <VALUE-CONFIG-CLASSES>
    <ECUC-VALUE-CONFIGURATION-CLASS>
      <CONFIG-CLASS>POST-BUILD</CONFIG-CLASS>
      <CONFIG-VARIANT>VARIANT-POST-BUILD</CONFIG-VARIANT>
    </ECUC-VALUE-CONFIGURATION-CLASS>
    <ECUC-VALUE-CONFIGURATION-CLASS>
      <CONFIG-CLASS>PRE-COMPILE</CONFIG-CLASS>
      <CONFIG-VARIANT>VARIANT-PRE-COMPILE</CONFIG-VARIANT>
    </ECUC-VALUE-CONFIGURATION-CLASS>
  </VALUE-CONFIG-CLASSES>
  <SYMBOLIC-NAME-VALUE>false</SYMBOLIC-NAME-VALUE>
  <LITERALS>
    <ECUC-ENUMERATION-LITERAL-DEF UUID="ECUC:049ec56c-bfe5-853f-310c-f70254daa840">
      <SHORT-NAME>PORT_PIN_LEVEL_HIGH</SHORT-NAME>
      <ORIGIN>AUTOSAR_ECUC</ORIGIN>
    </ECUC-ENUMERATION-LITERAL-DEF>
    <ECUC-ENUMERATION-LITERAL-DEF UUID="ECUC:dea65423-5596-83dc-2604-8a2134878b00">
      <SHORT-NAME>PORT_PIN_LEVEL_LOW</SHORT-NAME>
      <ORIGIN>AUTOSAR_ECUC</ORIGIN>
    </ECUC-ENUMERATION-LITERAL-DEF>
  </LITERALS>
</ECUC-ENUMERATION-PARAM-DEF>
```

## EcuValueCollection.arxml (下圖)

```
<ECUC-TEXTUAL-PARAM-VALUE>
  <DEFINITION-REF DEST="ECUC-ENUMERATION-PARAM-DEF">/AUTOSAR/EcucDefs/Port/PortConfigSet/PortContainer/PortPin/PortPinLevelValue</DEFINITION-REF>
  <VALUE>PORT_PIN_LEVEL_HIGH</VALUE>
</ECUC-TEXTUAL-PARAM-VALUE>
```

# 研究方法

基於 AUTOSAR CLASSIC 的 PORT DRIVER 開發

依照 EcuValueCollection.arxml  
生成出 Port\_Cfg.h 和 Port\_PBCfg.c

```
<SHORT-NAME>PortContainer1</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF"/>/AUTOSAR/EcuDefs/Port/PortConfigSet/PortContainer</DEFINITION-REF>
<PARAMETER-VALUES>
  <ECUC-NUMERICAL-PARAM-VALUE>
    <DEFINITION-REF DEST="ECUC-INTEGGER-PARAM-DEF"/>/AUTOSAR/EcuDefs/Port/PortConfigSet/PortContainer/PortNumberOfPortPins</DEFINITION-REF>
    <VALUE>1</VALUE>
  </ECUC-NUMERICAL-PARAM-VALUE>
</PARAMETER-VALUES>
<SUB-CONTAINERS>
  <ECUC-CONTAINER-VALUE>
    <SHORT-NAME>P12_5</SHORT-NAME>
    <PARAMETER-VALUES>
      <ECUC-TEXTUAL-PARAM-VALUE>
        <DEFINITION-REF DEST="ECUC-ENUMERATION-PARAM-DEF"/>/AUTOSAR/EcuDefs/Port/PortConfigSet/PortContainer/PortPin/PortPinDirection</DEFINITION-REF>
        <VALUE>PORT_PIN_OUT</VALUE>
      </ECUC-TEXTUAL-PARAM-VALUE>
      <ECUC-NUMERICAL-PARAM-VALUE>
        <DEFINITION-REF DEST="ECUC-BOOLEAN-PARAM-DEF"/>/AUTOSAR/EcuDefs/Port/PortConfigSet/PortContainer/PortPin/PortPinDirectionChangeable</DEFINITION-REF>
        <VALUE>1</VALUE>
      </ECUC-NUMERICAL-PARAM-VALUE>
      <ECUC-NUMERICAL-PARAM-VALUE>
        <DEFINITION-REF DEST="ECUC-INTEGGER-PARAM-DEF"/>/AUTOSAR/EcuDefs/Port/PortConfigSet/PortContainer/PortPin/PortPinId</DEFINITION-REF>
        <VALUE>17</VALUE>
    </PARAMETER-VALUES>
  </ECUC-CONTAINER-VALUE>
</SUB-CONTAINERS>
</DEFINITION-REF>
```

```
#define PortConf_PortContainer1_P12_5 17
```

# 研究方法

撰寫基於硬體的 Port.h 和 Port.c

```
/* Function definition */

void Port_Init(const Port_ConfigType* ConfigPtr);

#if PORT_SET_PIN_DIRECTION_API == STD_ON
void Port_SetPinDirection(Port_PinType Pin, Port_PinDirectionType Direction);
#endif

void Port_RefreshPortDirection(void);

#if PORT_VERSION_INFO_API == STD_ON
void Port_GetVersionInfo(Std_VersionInfoType *versioninfo);
#endif

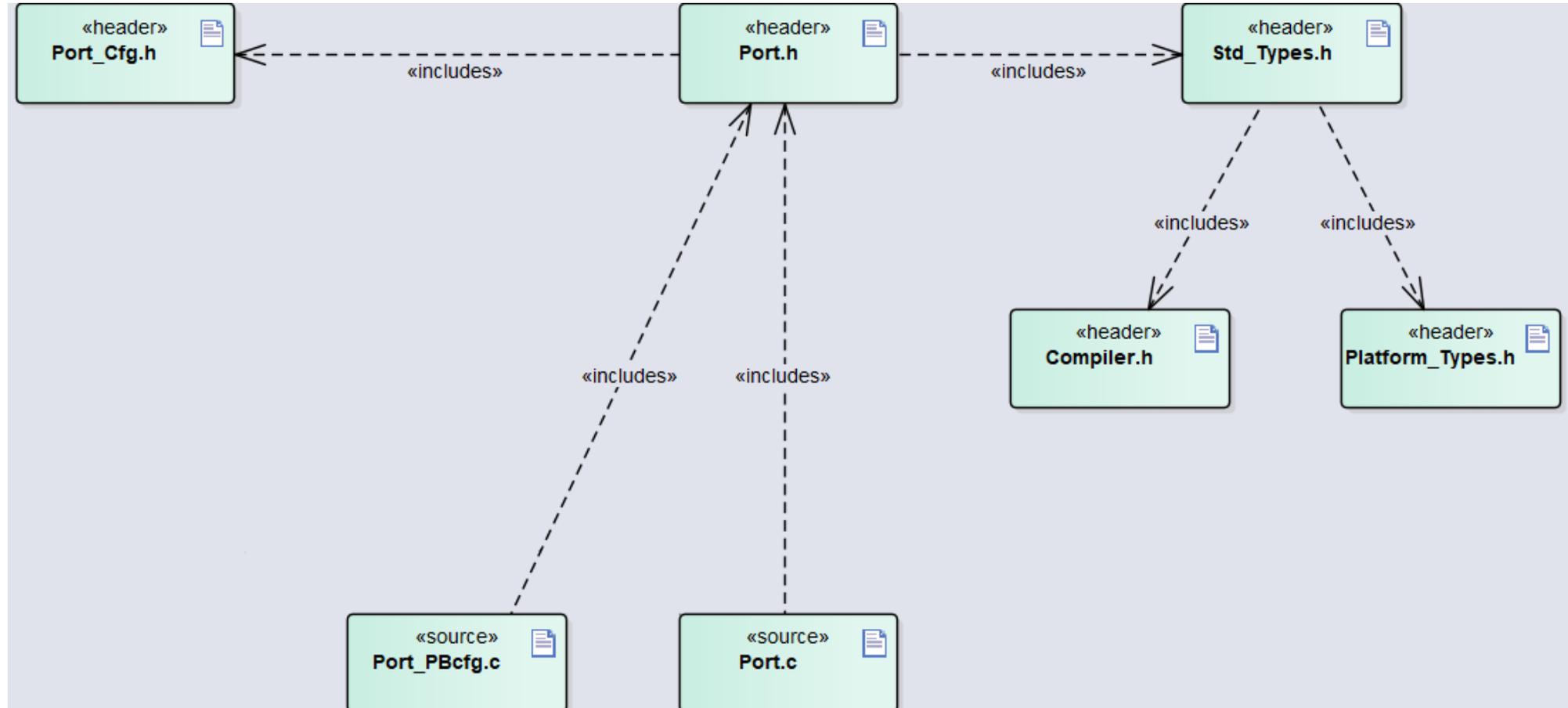
#if PORT_SET_PIN_MODE_API == STD_ON
void Port_SetPinMode(Port_PinType Pin, Port_PinModeType Mode);
#endif
```

# 研究方法

依照 EcuValueCollection.arxml  
生成出 Port\_Cfg.h 和 Port\_PBCfg.c

撰寫基於硬體的 Port.h 和 Port.c

編譯在一起並結合 MilkshopOS 進行測試



成果



# 成果

```
INFO: list of configuration files:
INFO: configuration file 1: application/osek.oil
INFO: list of files to be generated:
INFO: generated file 1: gen/boot.asm.php
INFO: output directory: device
INFO: reading application/osek.oil
INFO: generating gen/boot.asm.php to device/boot.asm
INFO: Generation Finished with WARNINGS: 0 and ERRORS: 0
cd port_driver && python3 generate.py
Generate EcuValueCollection.arxml Success !
cd port_driver && python3 parseValue.py
Generate Port_Cfg.h and Port_PBCfg.c Success !
PS C:\Users\Mickey\Downloads\MilkshopOSEK\MilkshopOSEK\MilkshopOSEK>
```

```
#include "mm_d11.h"

void WDTAInit(void)
{
    // Set interrupt flags
    MKWDTA0 = 1U; // Disables interrupt
    RFWDTA0 = 0U; // Clear interrupt
    TBWDTA0 = 1U; // Table reference
    ICWDTA0 &= 0xf8; // Set interrupt
    MKWDTA0 = 0U; // Enables interrupt

    WDTA0MD = 0x0b; // NMI error mode

    // 512 / 240kHz * 128 = 0.2731 s
    WDTA0WDTE = 0xAC;
}

void SoftwareResetWDTA0(void) {}

#pragma interrupt INTWDTA0(enable =
void INTWDTA0(void)
{
    WDTA0WDTE = 0xAC; // Restart the
```

COM3 - PuTTY

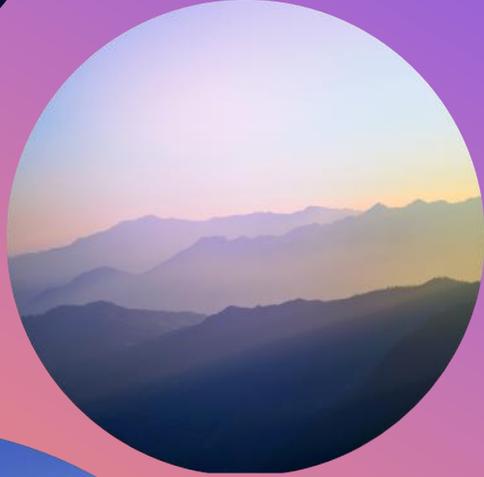
```
SetPinMode() testing. This should be the first line to print
Waiting...
SetPinDirection() testing, the Light should turn off
Waiting...
RefreshPortDirection() testing, the Light should turn on
Waiting...
Task T1 terminated
```

基於 AUTOSAR CLASSIC 的  
PORT DRIVER 開發

+



o



.



感謝聆聽