#### **IMPACT ASSESSMENT**

**SIP-ADUS WORKSHOP** 

EG-342 | 16th November 2016

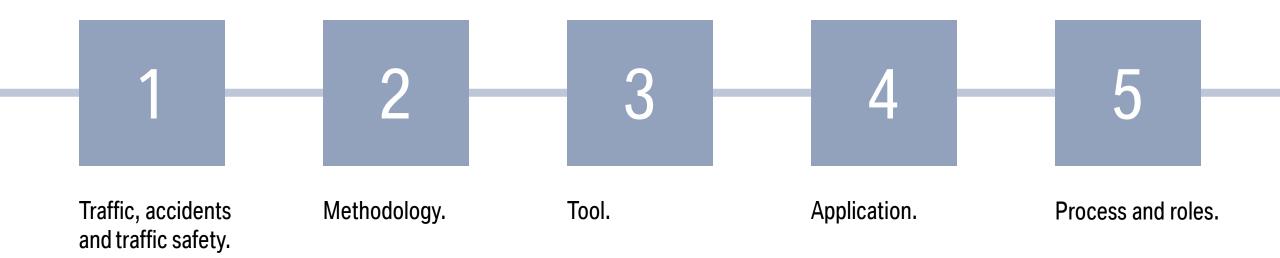


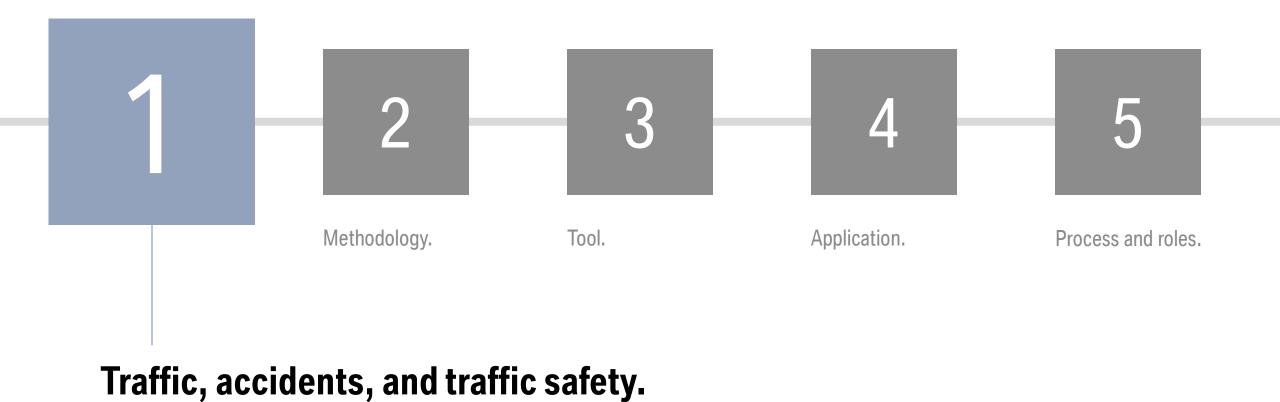






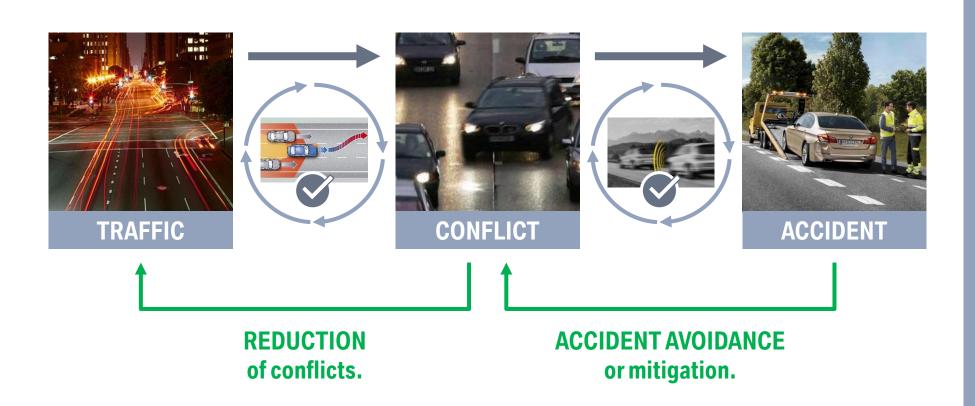




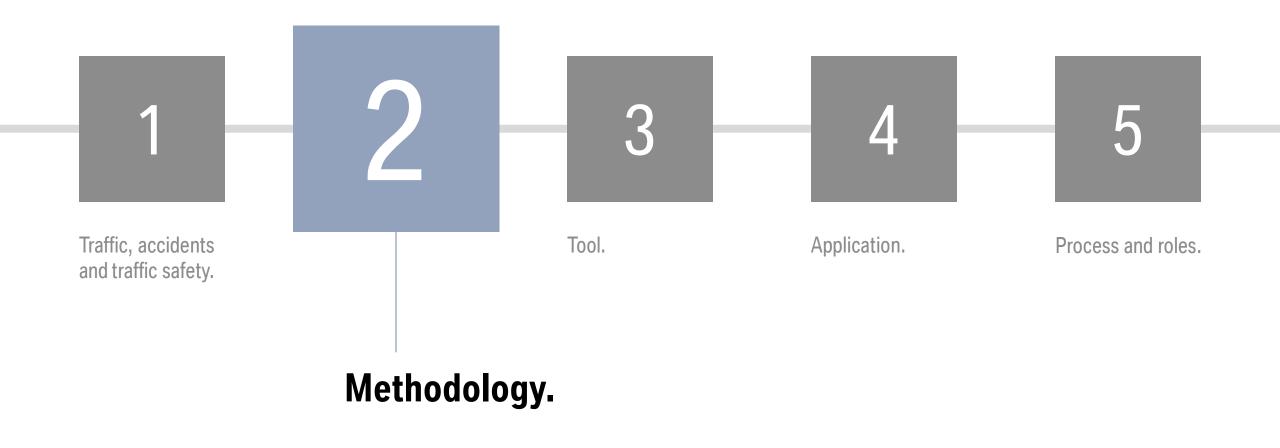


# TRAFFIC, ACCIDENTS AND TRAFFIC SAFETY. UNDERSTANDING TRAFFIC AND ACCIDENTS.

#### **Accident as a process of interacting factors**



- Accident is a result of multiple interacting factors in traffic.
- The safety performance of Assistance Systems must be evaluated by taking these complex interactions into account.



#### METHODOLOGY. ACCIDENT- VS. TRAFFIC-BASED APPROACH

Stochastic simulation of traffic situation with ADAS

#### **Accident-based Accident reconstruction** + Initial constellation ∆Single-Case Simulation of reconstructed case with ADAS **Identification of relevant traffic scenarios** 2 Relevant traffic scenarios **Stochastic simulation of traffic situation without ADAS**

#### **Effectiveness result** cannot be generalized!

- How does the system work in a realistic distribution of (highly) critical non-accident situations?
- What is the consequence
   of a system reaction for the
   surrounding traffic
   (e.g., depending on traffic
   density)?
- What would a falsepositive system reaction induce into traffic?

 $\sum \Delta_{pos} - \sum \Delta_{neq}$ 

**Traffic-based** 

Impact Assessment I Felix Fahrenkrog, BMW AG Page 6

#### METHODOLOGY. ACCIDENT- VS. TRAFFIC-BASED APPROACH.

#### **Accident-based approach**

#### **Traffic-based approach**

#### SYSTEM ACTION

Yes	No		
True Positive Correct action	False Negative Conflict not detected (no action)	Yes	OBJECTIVE RISK
<b>Near Miss</b> Almost	True Negative Correct "non-action"		BJECT
MISSING ASSESSMENT False Positive		2	0
Unnecessary action	~		

#### **SYSTEM ACTION**

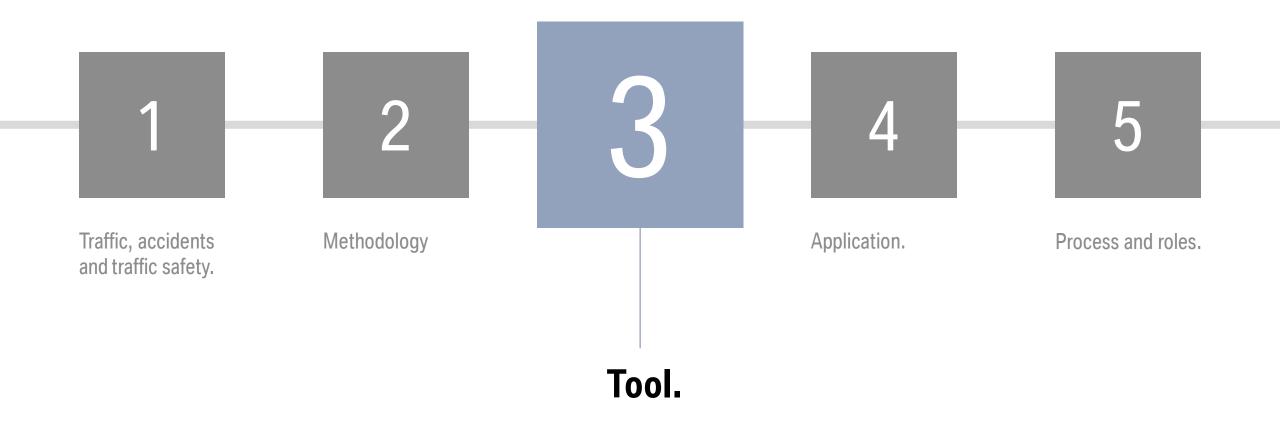
Yes	No		
True Positive Correct action	False Negative Conflict not detected (no action)	Yes	VE RISK
Near Miss Almost	True Negative Correct "non-action"	No	OBJECTIVE RISK
False Positive Unnecessary action	<b>&gt;</b>	4	

# METHODOLOGY. PROSPECTIVE EFFECTIVENESS ASSESSMENT OF ROAD SAFETY.



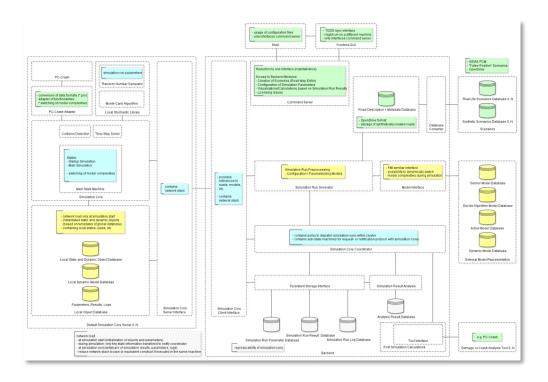
- Representative assessment of active safety requires harmonized methods.
- Harmonization enables comparable and comprehensible assessments.
- For simulation: methods, processes, and models for prospective assessment have to be harmonized.
- Objective of this open working platform is the creation of a worldwide standard for the evaluation of systems within the pre-crash phase, which is created, discussed, and finally accepted by all relevant stakeholders.

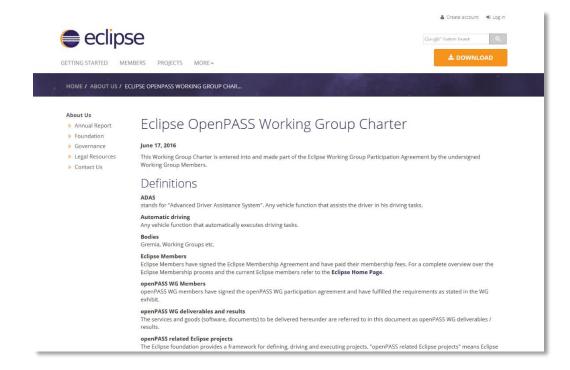
- Worldwide harmonization/standardization as primary objective.
- Open harmonization initiative was very well received and supported by all stakeholders (OEMs, suppliers, research institutes, insurances, consumer protection, and governmental institutions).
- So far over 30 organizations are participating and contributing to P.E.A.R.S.
  - Audi, Daimler, BMW, FCA, Renault, Volvo, VW,
     Toyota,...

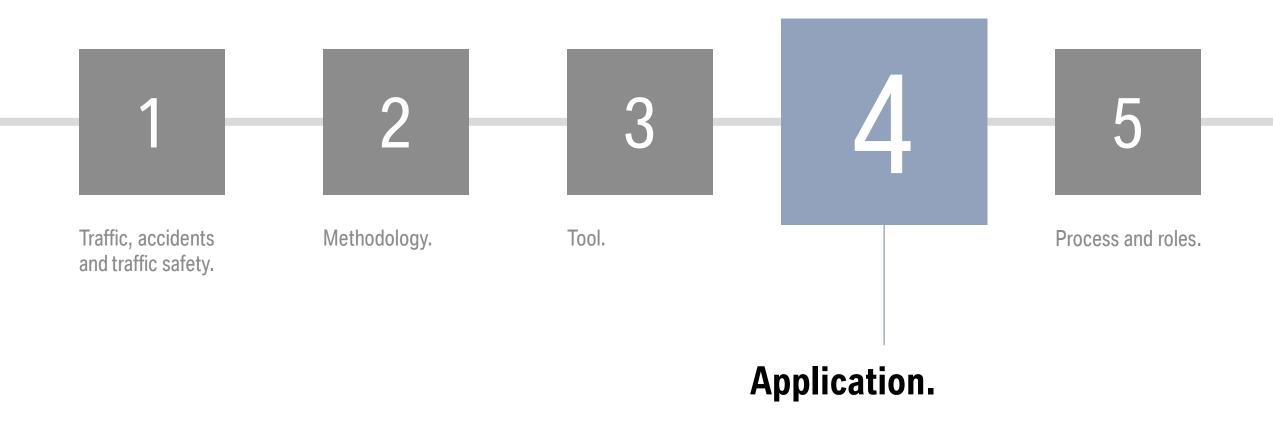


### TOOL. OPENPASS.

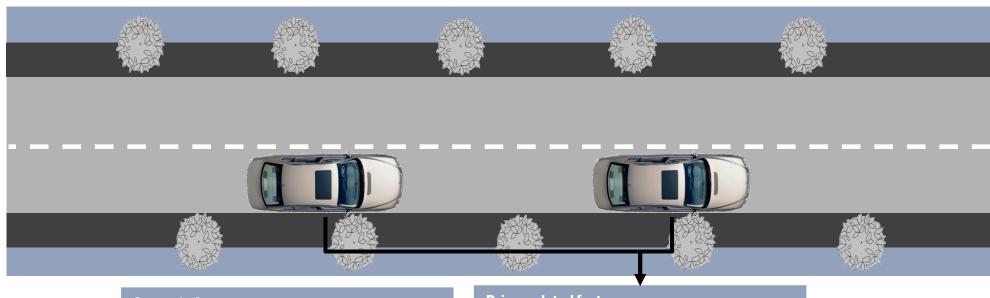
- OpenPASS is a new software framework for simulation and evaluation of ADAS and automated driving
- **Joint initiative of OEMs** (Daimler, VW and BMW) with scope of harmonization of simulation tools
- Open-Source approach under the umbrella of the eclipse foundation (project: sim@openpass)







### APPLICATION. EXAMPLE: REAR-END CONFLICT - INFLUENCING FACTORS.



Traffic-based simulation with stochastic variation is theoretically capable to cover all variations of a traffic scenario.

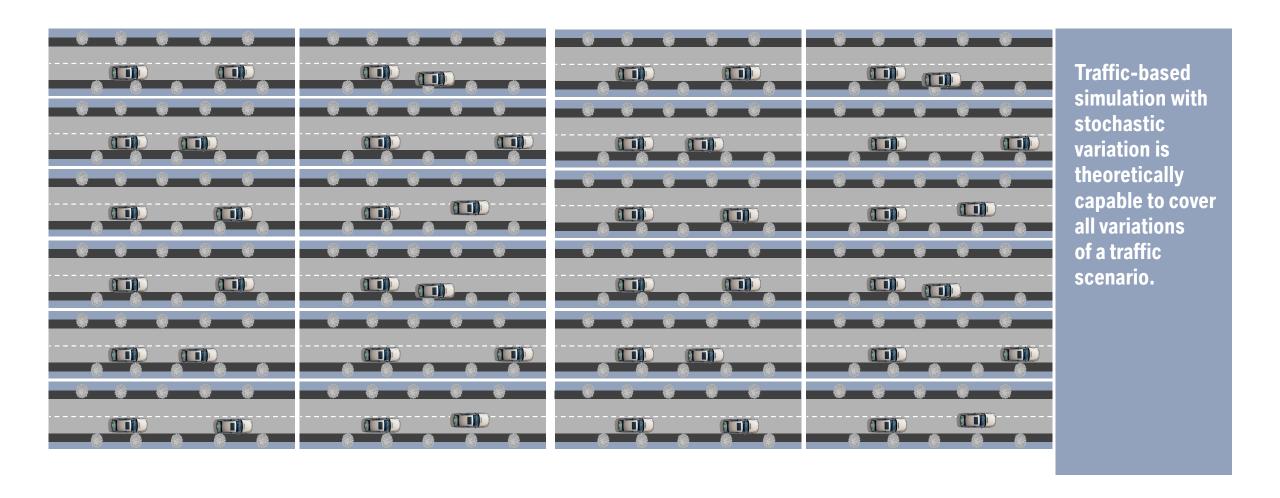
#### **Scenario factors**

- Driving speed (rear vehicle / front vehicle).
- Relative distance.
- Acceleration (rear vehicle / front vehicle).
- Offset.
- Road friction.
- Traffic.
- ..

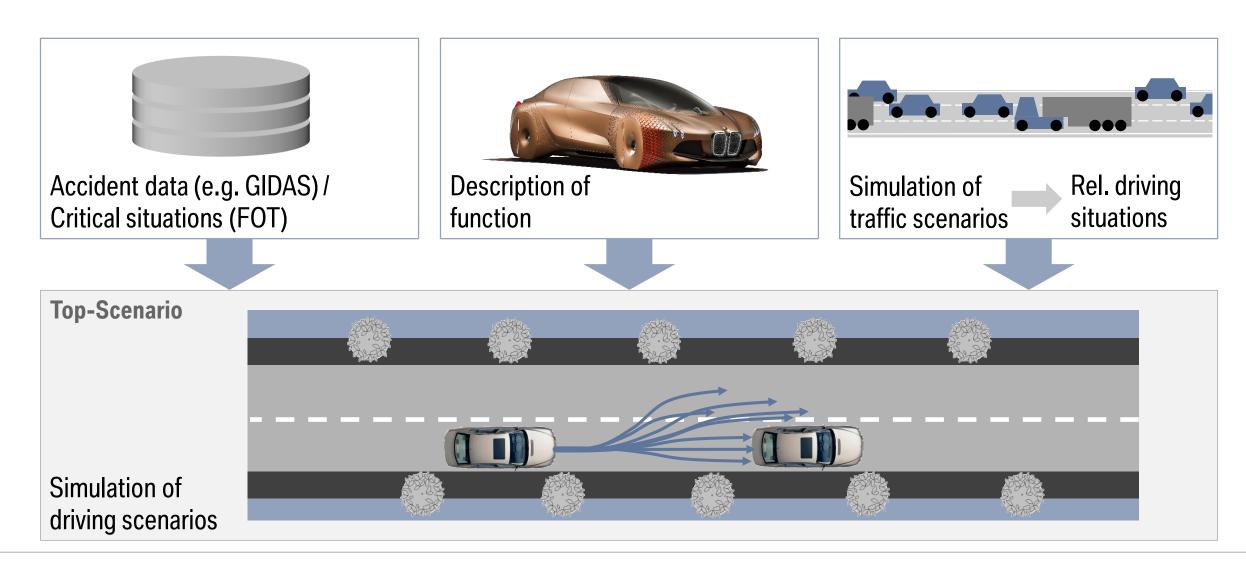
#### **Driver related factors**

- Driving speed.
- Mental Fitness.
- Visually distracted.
- Current mental activation.
- Seating position.
- Field of view.
- ..

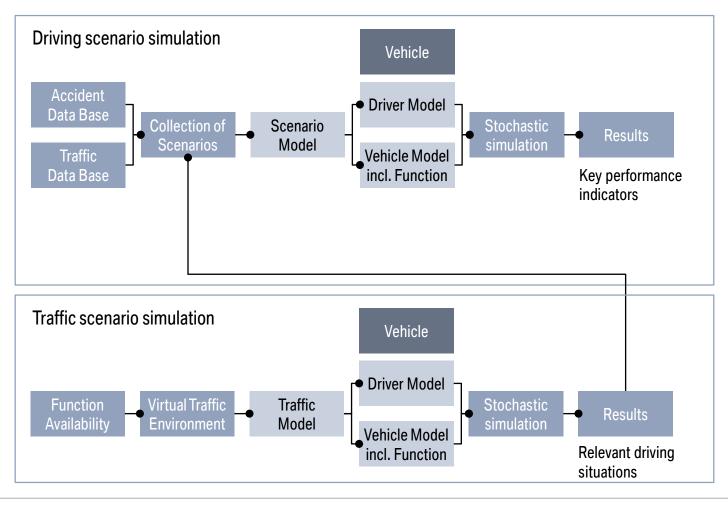
### APPLICATION. EXAMPLE: REAR-END CONFLICT - STOCHASTIC VARIATION.

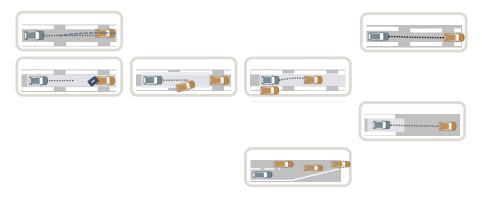


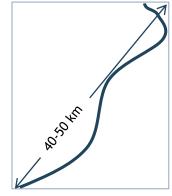
# APPLICATION. IDENTIFICATION OF TOP-SCENARIOS FOR AUTOMATED DRIVING.



### APPLICATION. FROM AEB TO HIGH/FULL AUTONOMOUS DRIVING FUNCTIONS.



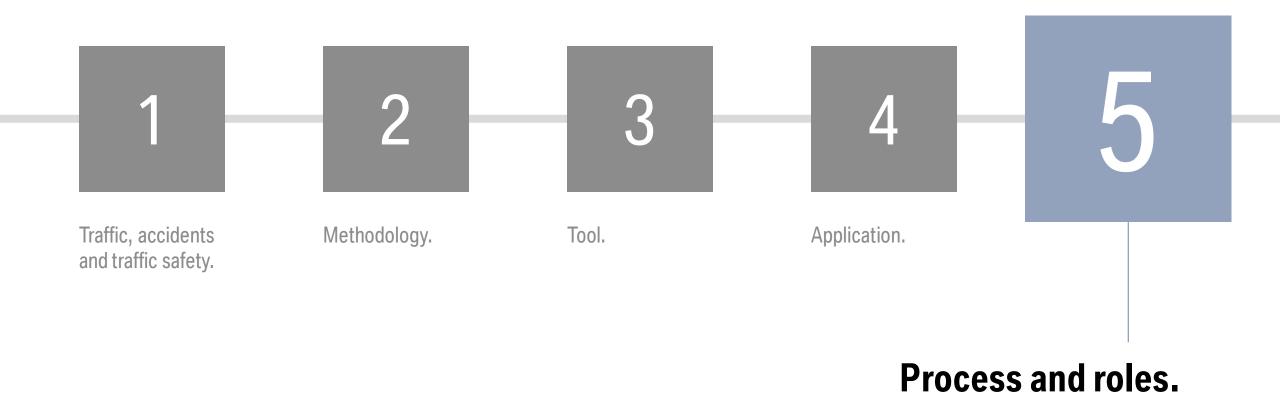




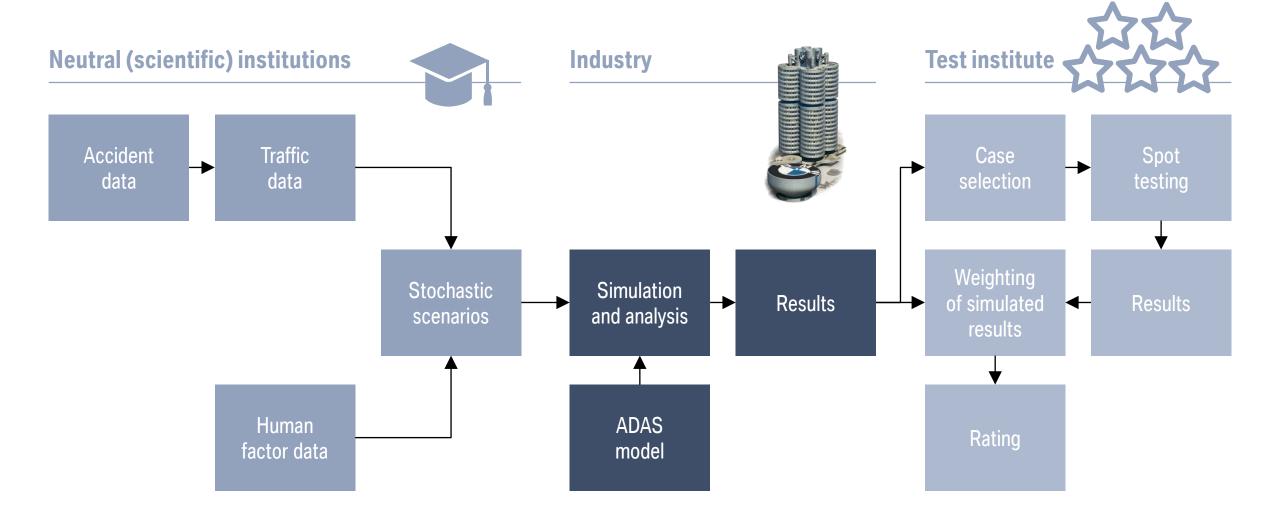
#### Virtual traffic environment including naturalistic stochastic variations:

- Road geometry (curvature, number of lanes).
- Traffic state (traffic volume, traffic density).
- Traffic signs.
- Weather condition (visibility, road surface).

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### PROCESS AND ROLES. VISION OF ACTIVE SAFETY EVALUATION.



#### THANK YOU FOR YOUR ATTENTION.