



The logo features the text "NIDays" in white, enclosed within a white rectangular border. To the right of this, the words "ENGINEER" and "NEXT" are stacked vertically in a large, bold, white sans-serif font. A yellow graphic element, consisting of three parallel lines forming a stylized arrow or chevron shape, is positioned between the two words. The entire logo is set against a blue background with diagonal stripes in various shades of blue, orange, and green.

NIDays **ENGINEER**
NEXT





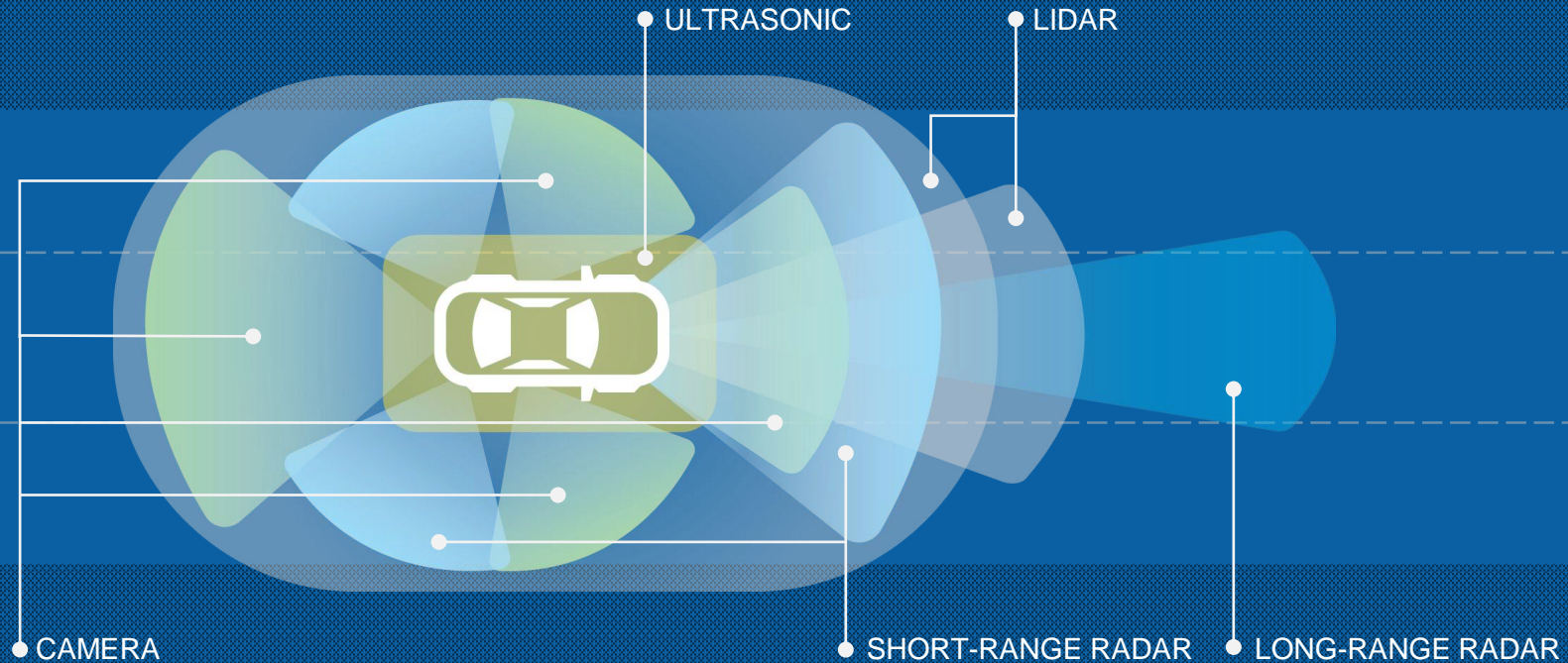
The Evolution of ADAS: Testing Systems That Include Cameras, Radar, and Sensor Fusion

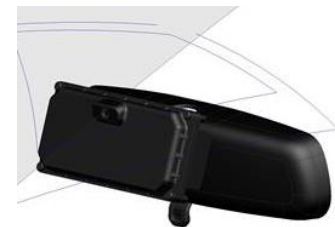
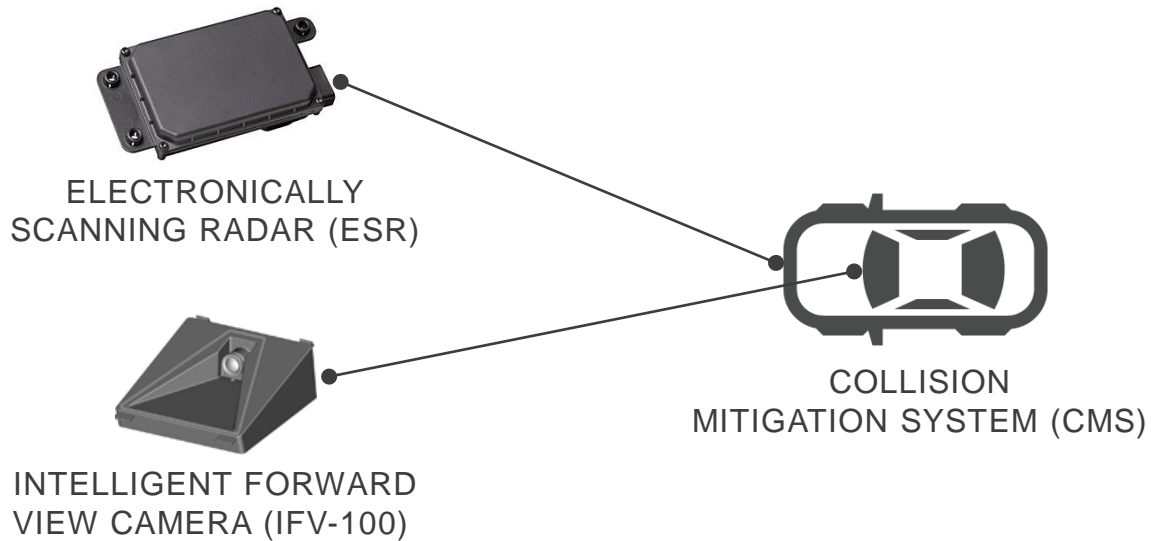
Smarter Test for Smart Vehicles

Stefano Caiola

Embedded Systems Engineer

Major ADAS Sensor Types and Applications

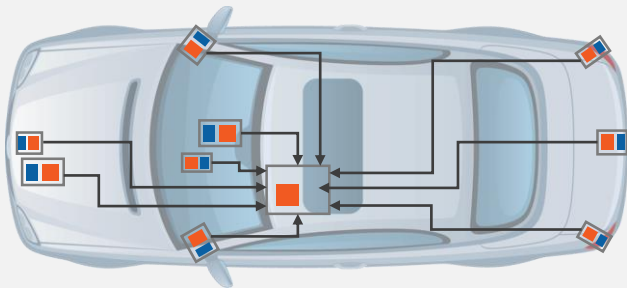




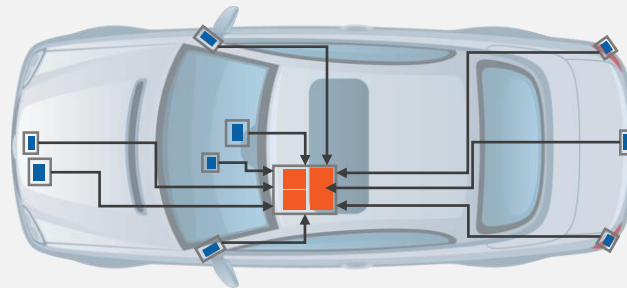
RACAM
(RADAR + CAMERA)

ADAS Sensor Fusion Evolution: Delphi Example

ADAS Architectures Continue to Evolve

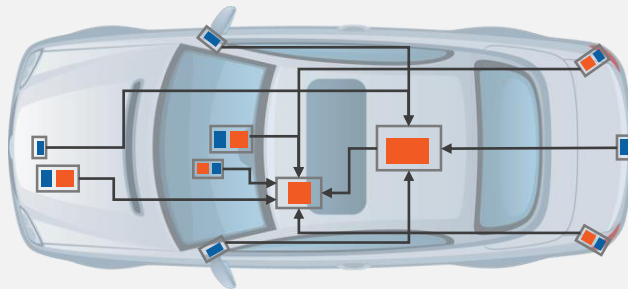


SMART SENSORS/DECENTRALIZED PROCESSING



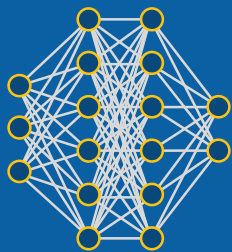
RAW SENSOR DATA/CENTRALIZED PROCESSING

■ Sensor
■ Electronic Control Module (ECM)



HYBRID SENSOR/PROCESSING

Source: electronics-eetimes

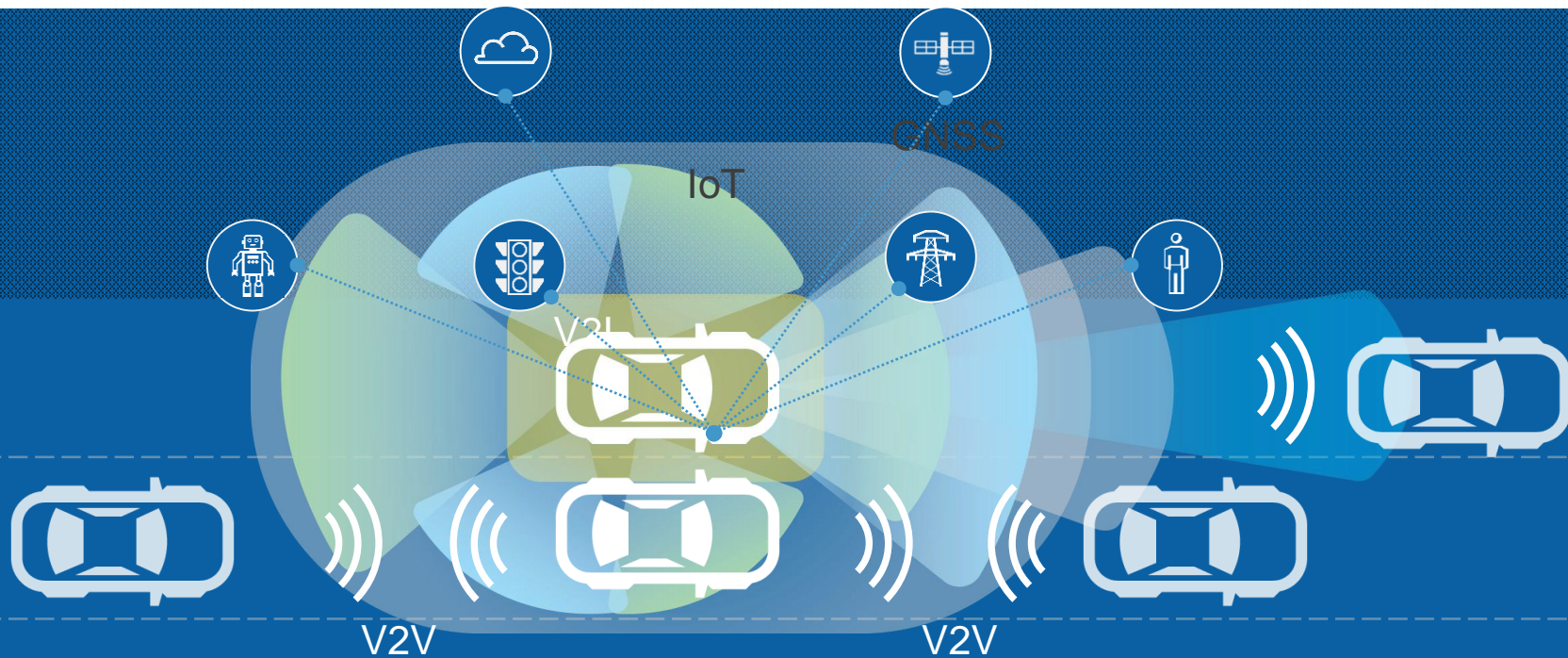


DEEP NEURAL NETWORK

Deep Learning for Self-Driving Cars

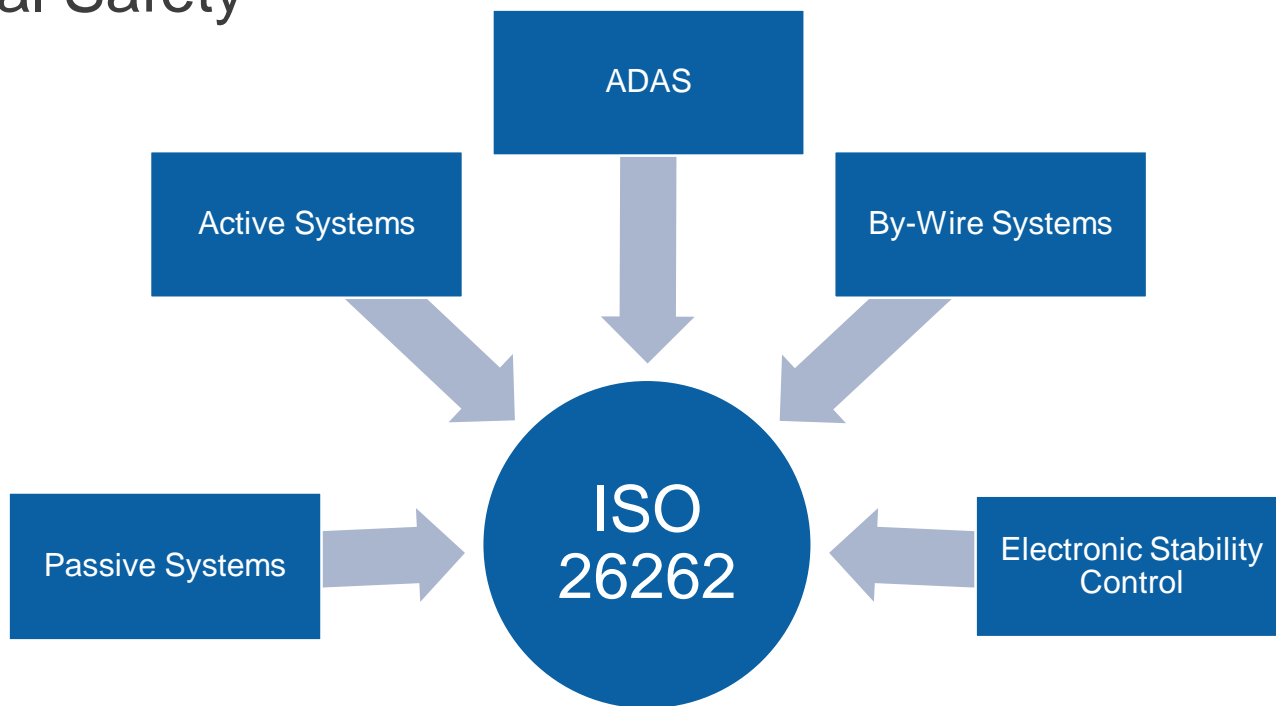
- Environmental perception is key to autonomous driving, e.g., lane position
- Traditional feature recognition and image processing techniques don't scale to needed complexity
- Deep neural networks learn efficient feature representation
- Inductive learning leads to evolving software operation that is challenging to test

The Connected Car



Functional Safety

ISO 26262



All interactions between systems of systems must be known and tested to determine how errors propagate across system and subsystem boundaries.

Challenges of ADAS Testing



Regulatory
Uncertainty



Volume
of Tests



Testing Systems Instead
of Discrete Components



Integrating New Technology
Into Existing Systems

Approaches to Test and Measurement

CLOSED

- “Vendor knows best”
- Fixed functionality
- Closed ecosystem
- Customer pays

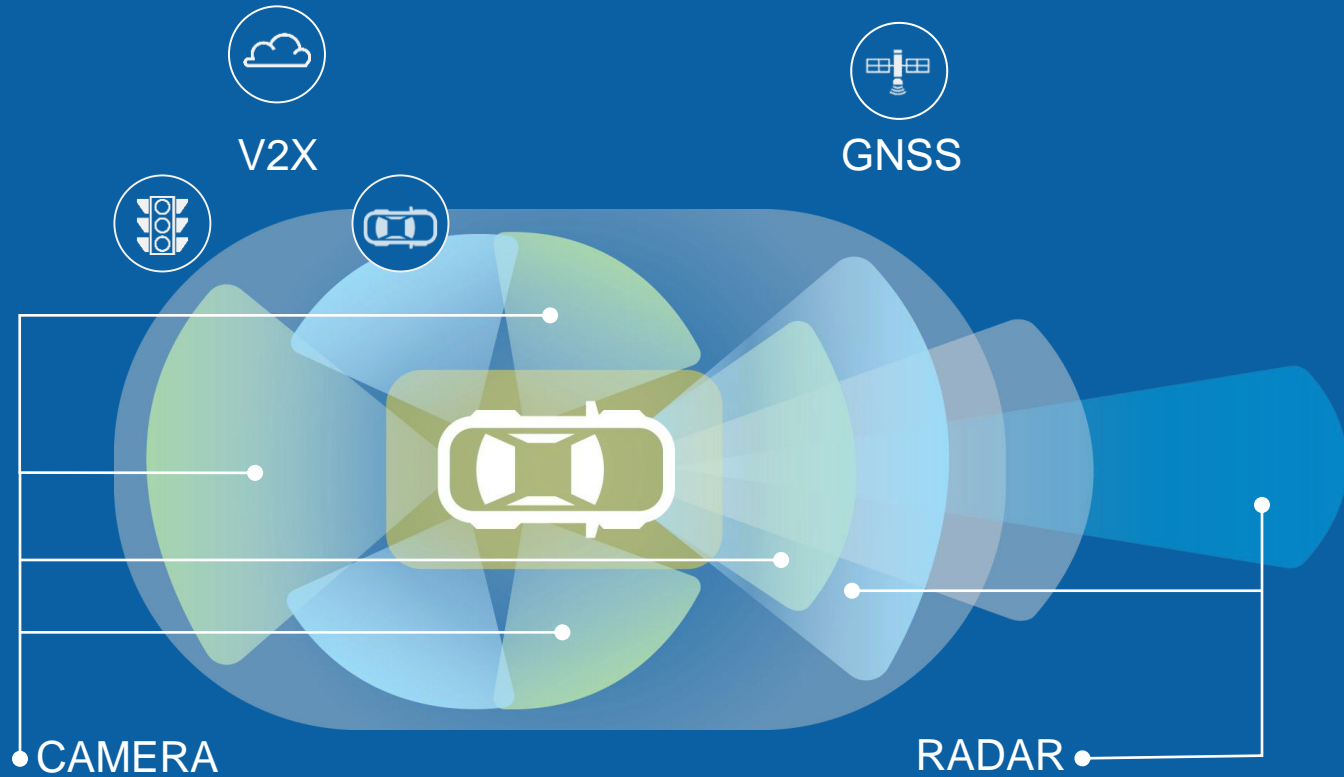


PLATFORM

- “Customer knows best”
- Customizable solution
- Open, vibrant ecosystem
- Customer designs



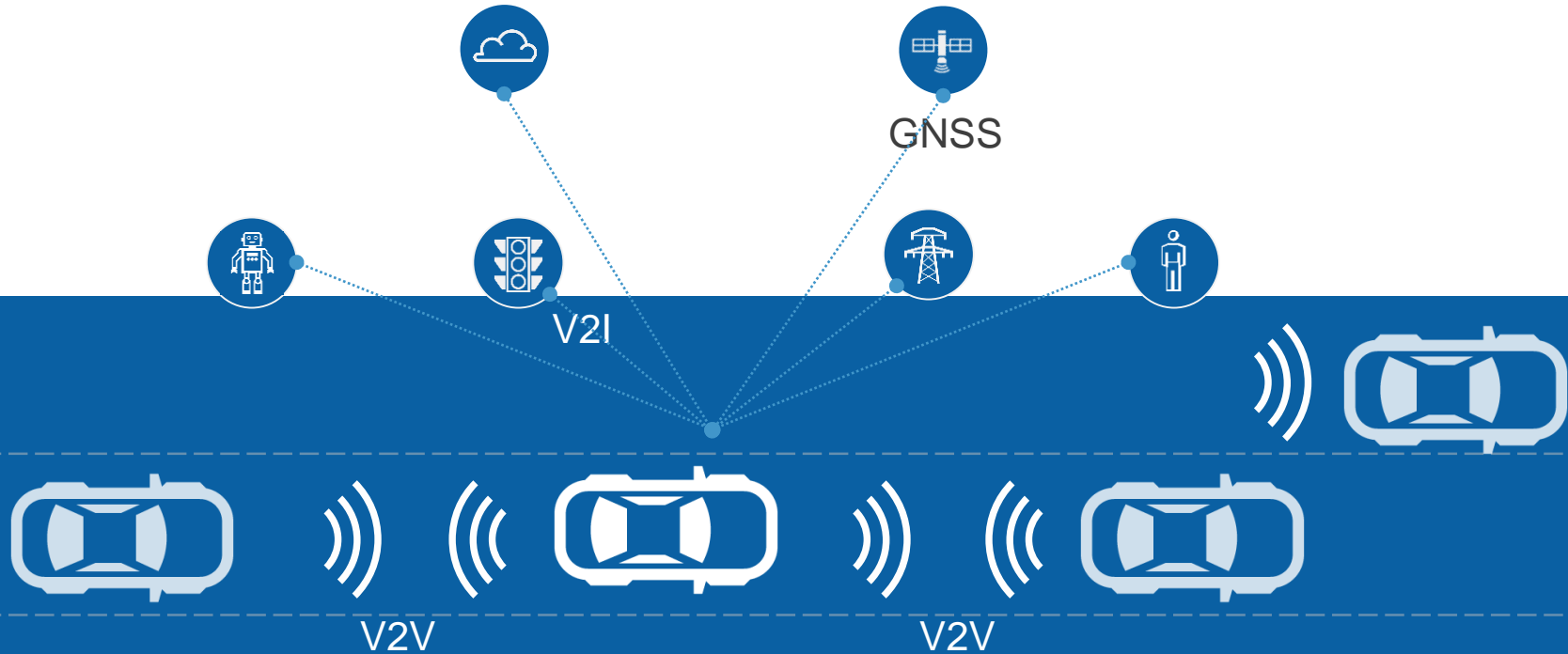
Major ADAS Technologies



Communications

V2X and GNSS

The Connected Car



V2V and V2I Communications With 802.11p and LTE

IEEE 802.11p (DSRC)

- Referred to as Dedicated Short-Range Communication (DSRC)
- Uses unlicensed spectrum in 5.9 GHz band
- Based on half-clocked IEEE 802.11a/g with 10 MHz channel bandwidth
- Effective Tx-Rx velocity differences of up to 200 km/hr
- Supports only V2V communication



LTE V2X (Cellular V2X)

- Part of 3GPP Release 14; targeted for 2017
- Uses existing licensed LTE spectrum and infrastructure
- Bandwidth configurations up to 10 MHz
- GNSS-based symbol synchronization
- Supports both V2V (PC5) and V2I (Uu) modes



NI's Approach for Integrating Other Standards

Flexible measurement IP from GSM to Wi-Fi

Partner IP

WLAN (802.11a/b/g/n/ac)

GSM/EDGE

Bluetooth

WCDMA/HSPA+

GPS Generation

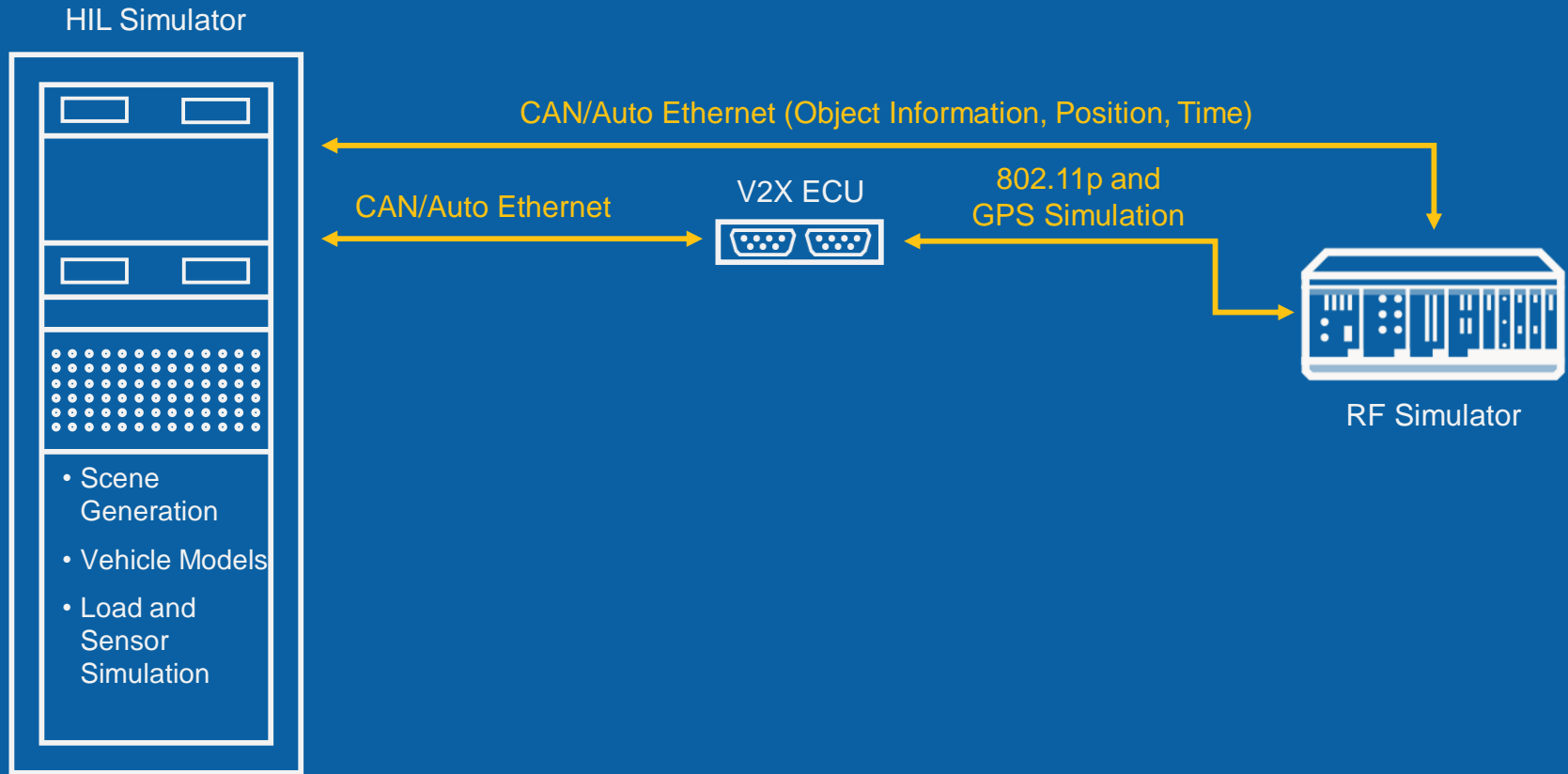
CDMA2k

FM/RDS Generation

LTE/LTE-A (TDD & FDD)

Wireless measurement algorithms execute on PXI controllers and reconfigurable FPGAs.





Radar

Trends in Automotive Radar

Focus on Safety

- Object identification/distinction
- Rear-end crash avoidance
- CAR2X (Car 2 Car and Car 2 Infrastructure Communication)
- 360 degrees vehicle surveillance

Adoption of 77–81 GHz

- More reliability and more accuracy
- Greater capability of distinguishing objects with high bandwidth
- Smaller footprint (multimode, multirange)

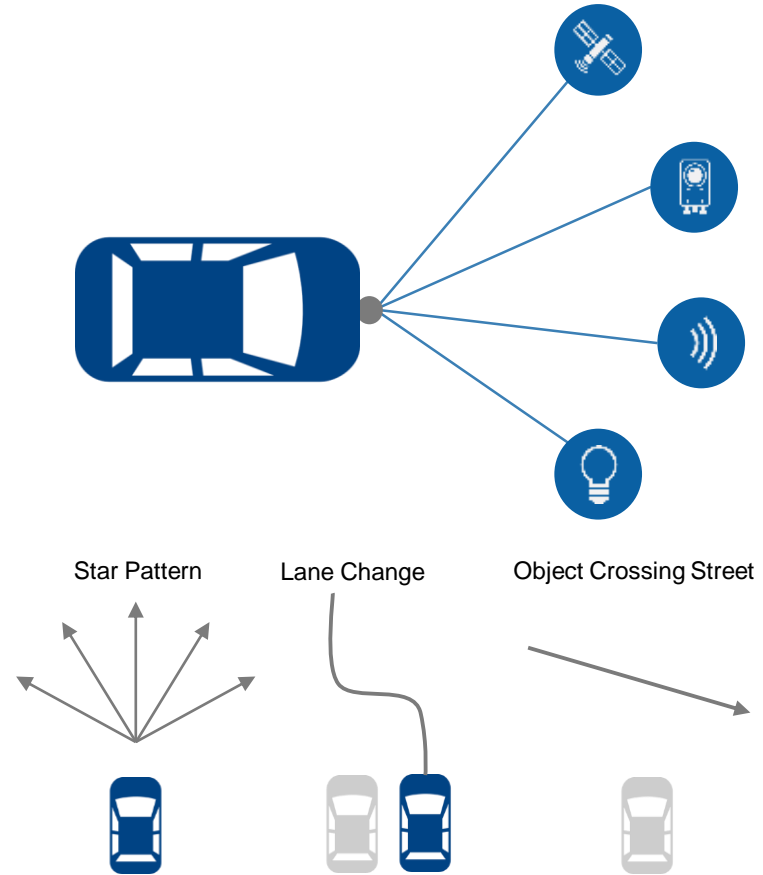
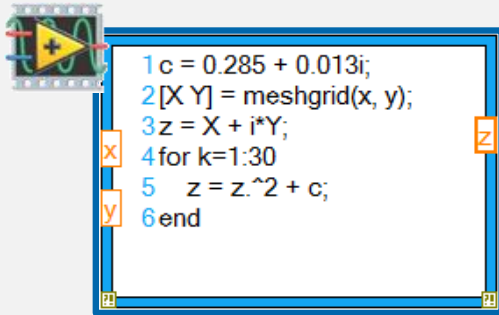


Image from <http://www.wykop.pl/link/2349196//>

Benefits and Trade-Offs of Testing Approaches

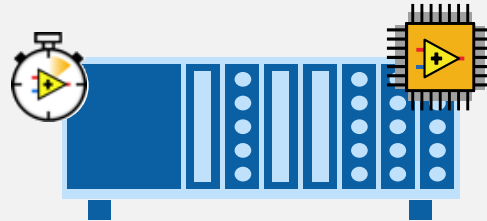
Simulation

- Uses software-only techniques
- Lowers setup complexity
- Does not truly emulate real-world behavior



Emulation

- Uses hardware-in-the-loop (HIL) techniques
- Allows the emulation of real-world scenarios
- Scales for future applications
- Requires knowledge of both hardware and software



Field Test

- Offers true real-world test
- Is difficult to set up and scale
- Limits test case coverage due to time and space complexity



Vehicle Radar Test System (VRTS)

FEATURES AT A GLANCE

- Single system performs both obstacle simulation and radar measurements
- Obstacle simulation settings include velocity, range, RCS, and angle of arrival (AoA)
- Measurements include: radiation pattern, EIRP, phase noise, spectrum occupancy, beam width, and chirp analysis
- Tight synchronization with modular PXI hardware for hardware-in-the-loop (HIL) and ADAS test applications

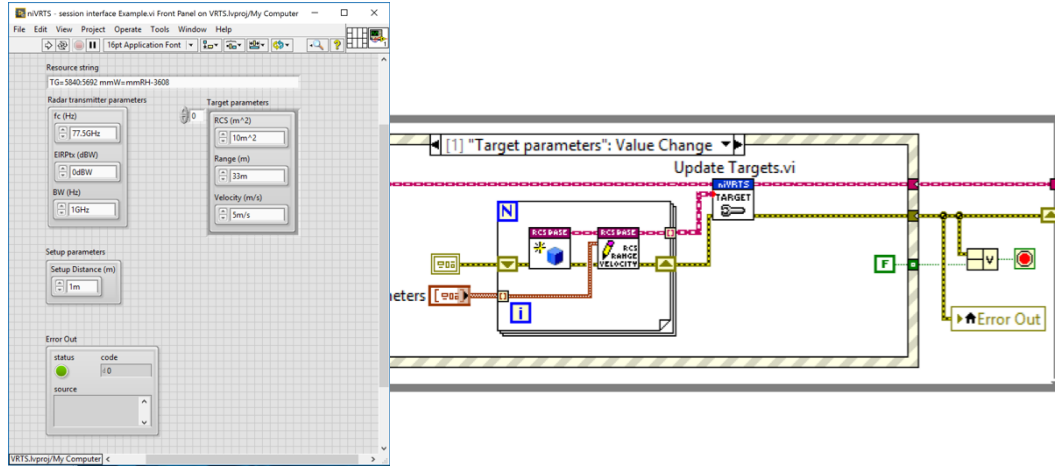
KEY SPECIFICATIONS

- Frequency Range: 76 – 81 GHz
- Number of Obstacles: 2 to 8+
- Obstacle range: 4m to 300+ meters
- Minimum VRTS to DUT: 70 cm
- Range resolution: 10 cm
- Range Accuracy: ± 70 cm
- Velocity: 0 to 500 km/hr (75 kHz)

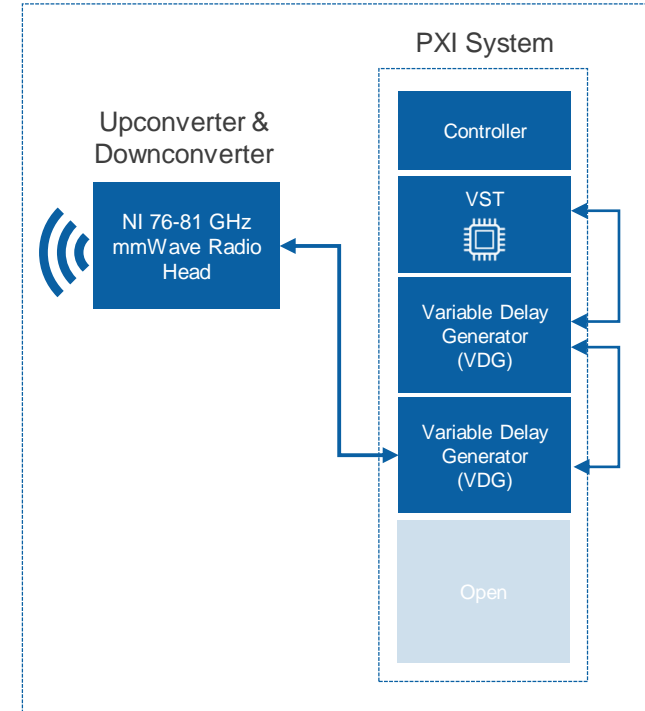


The NI VRTS is a flexible test system that combines PXI hardware with modular millimeterwave radio heads

VRTS Software

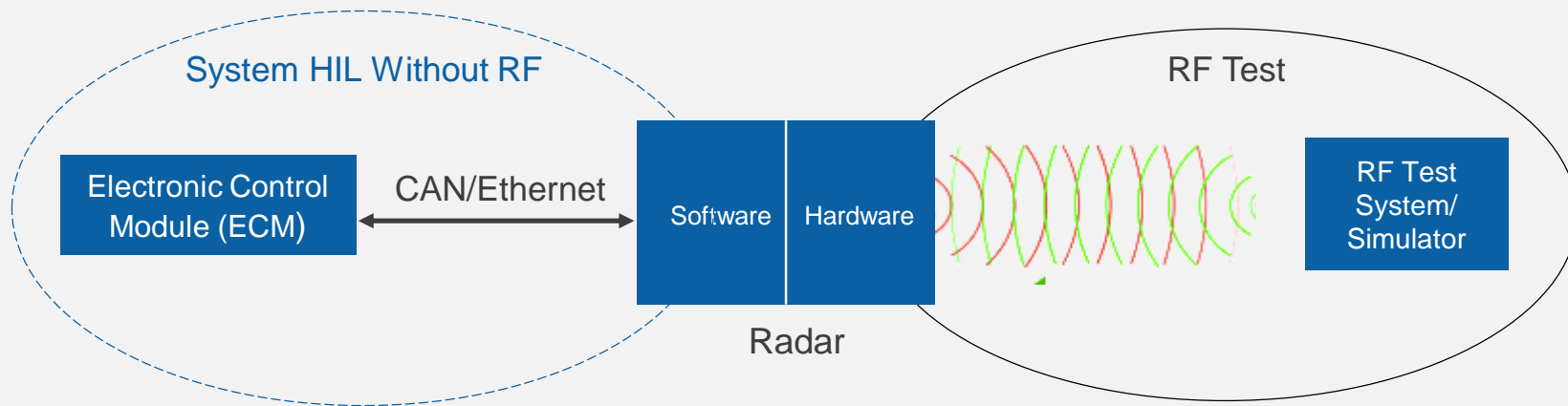


Vehicle Radar Test System (VRTS)

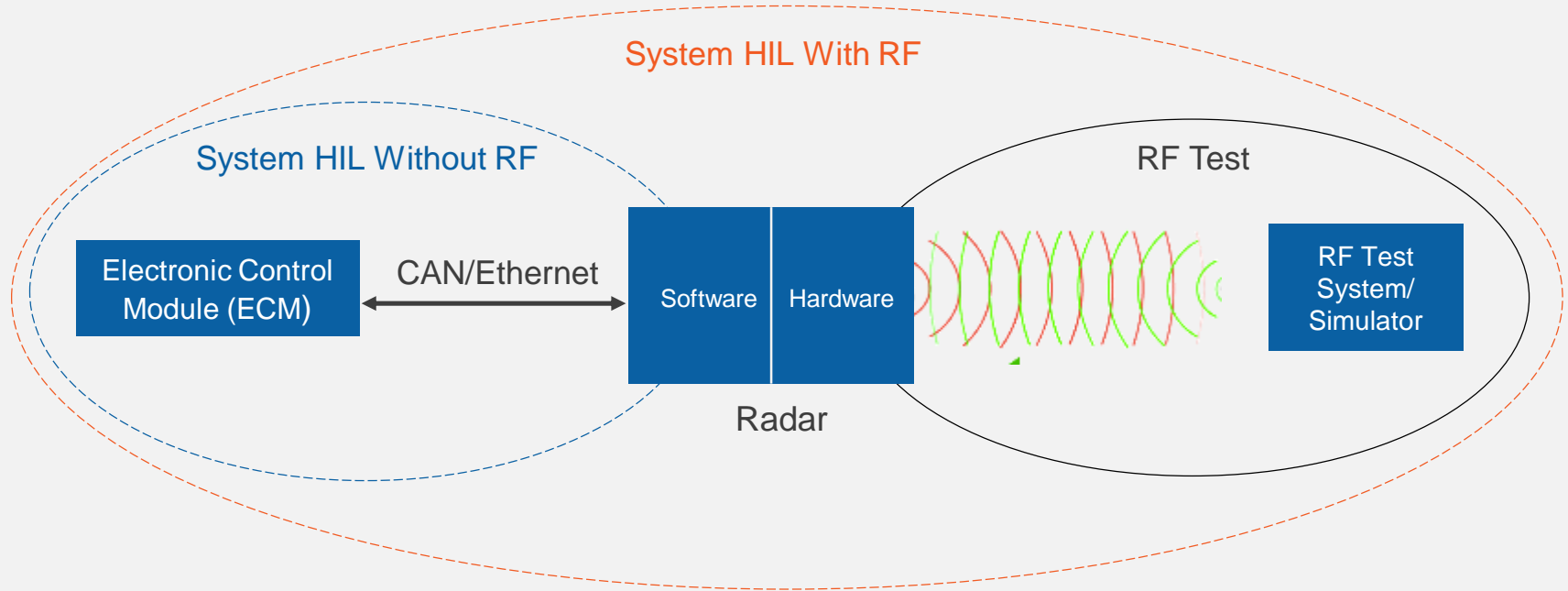


- VRTS partners provide highly customized turn-key solution based on end user requirements
- Partners build on VRTS LabVIEW reference application – which includes:
 - Measurement examples for radar hardware characterization
 - Object simulation examples for embedded software and system test

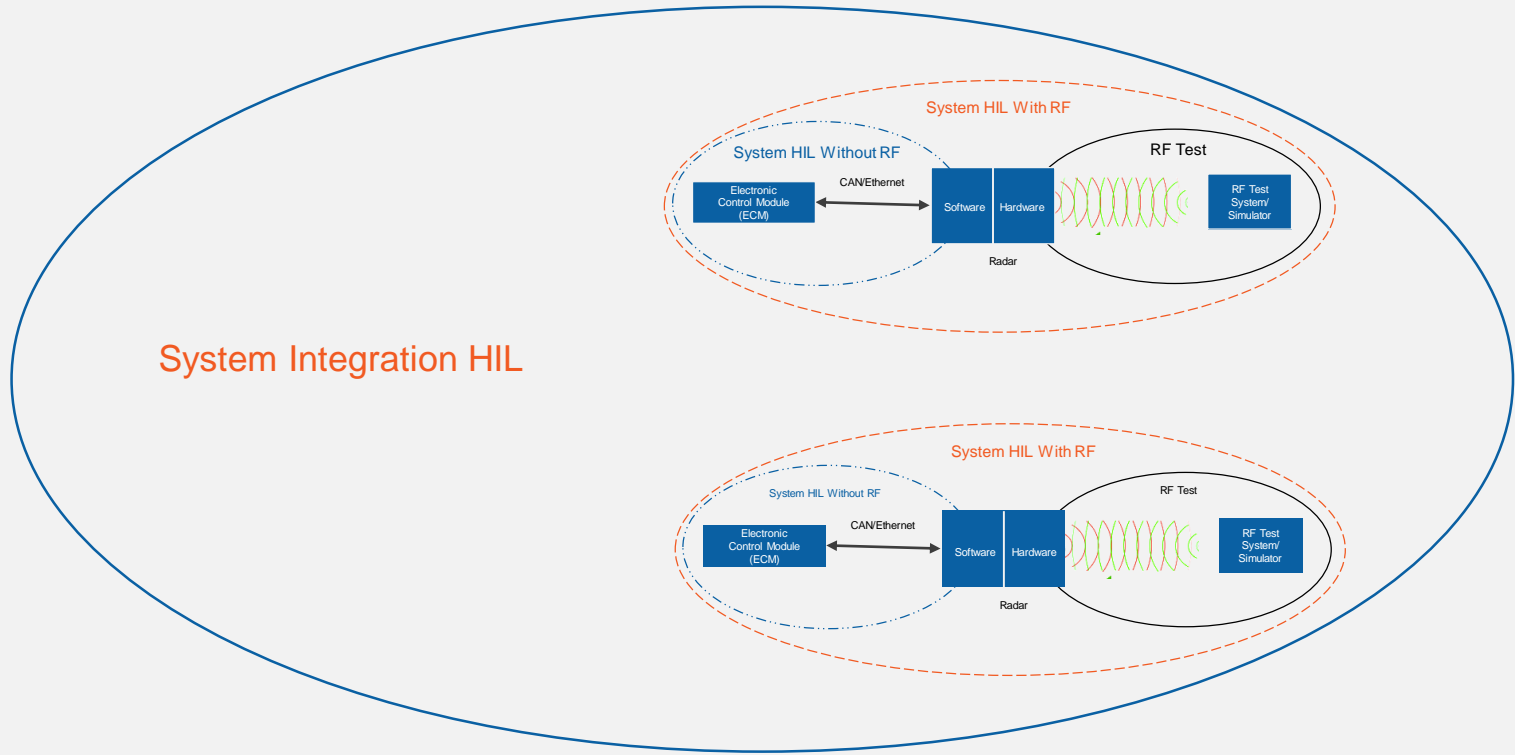
Automotive Subsystem Test Cases

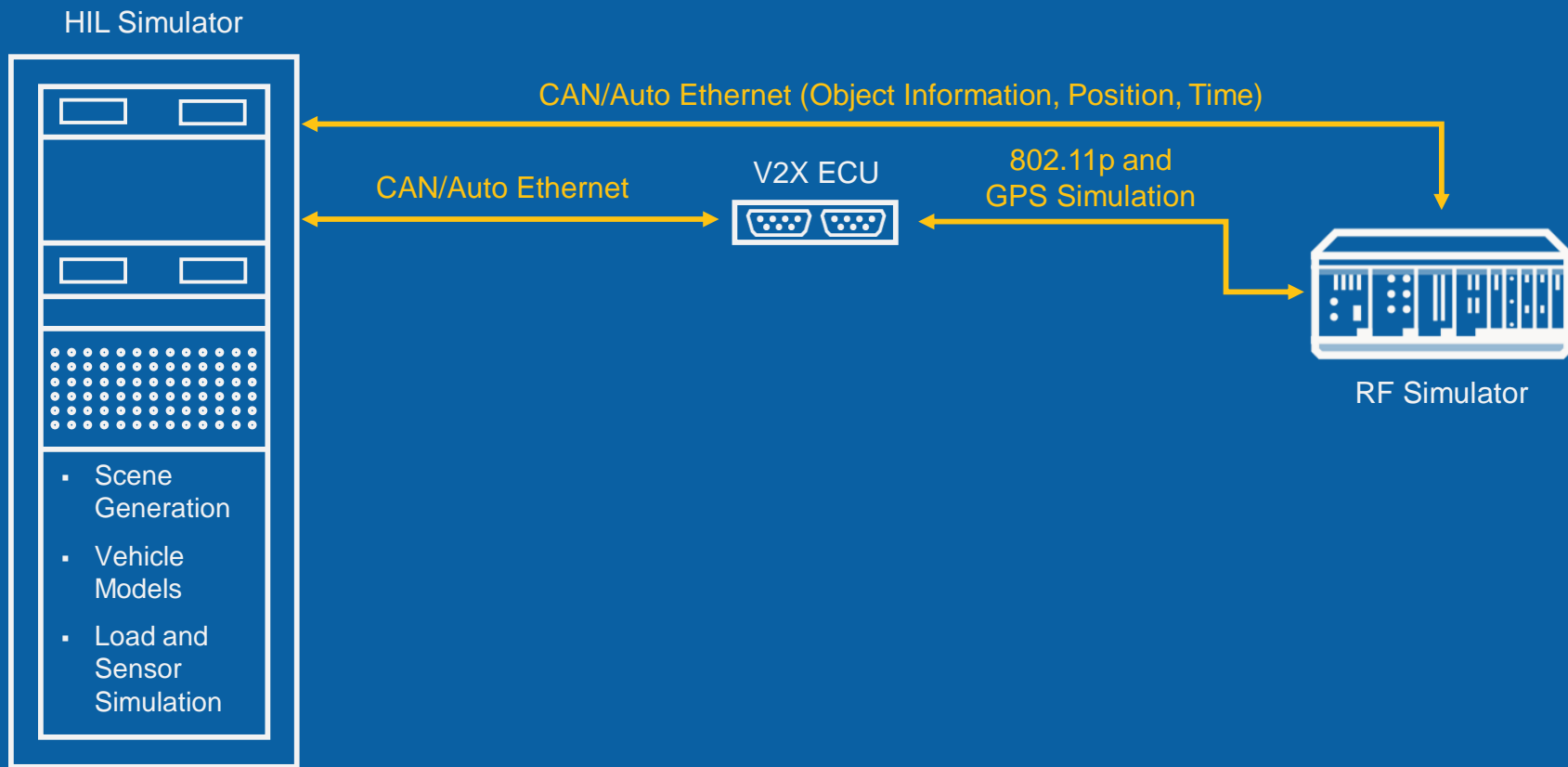


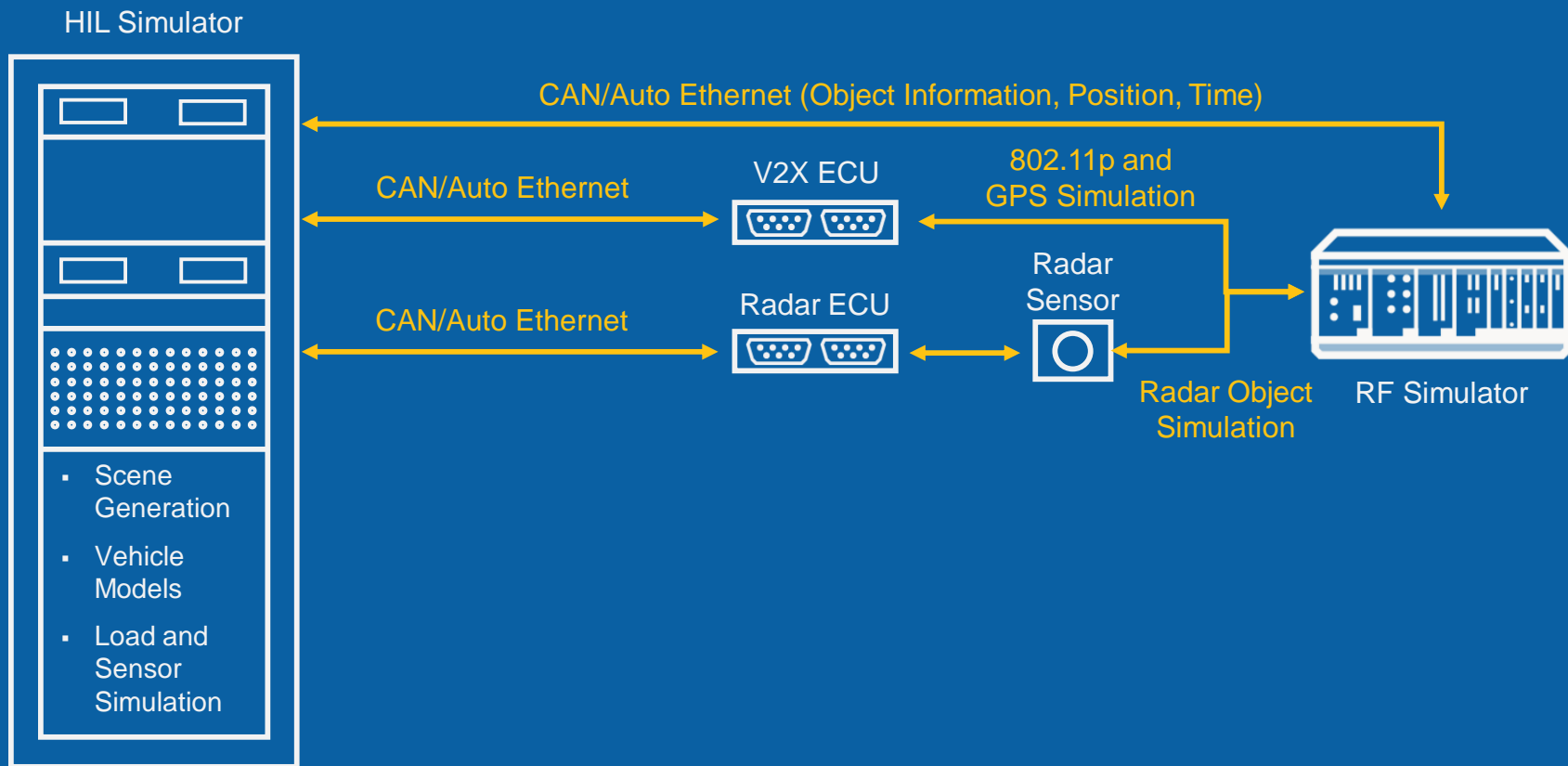
Automotive Subsystem Test Cases



Systems Integration Test







Camera

Challenges of Camera Test

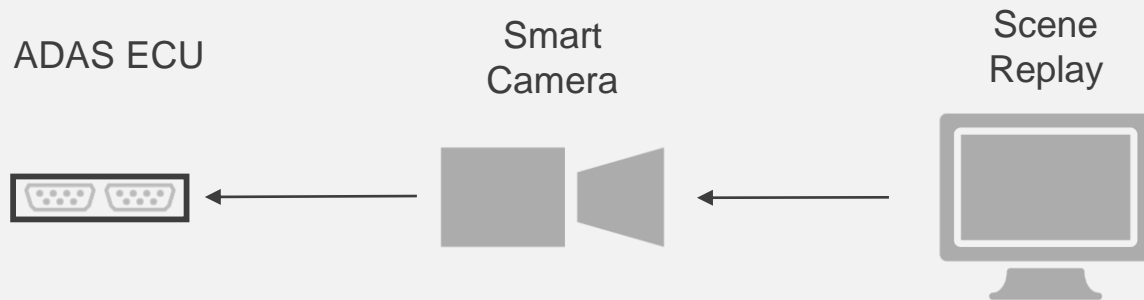
Increasing Number of Cameras



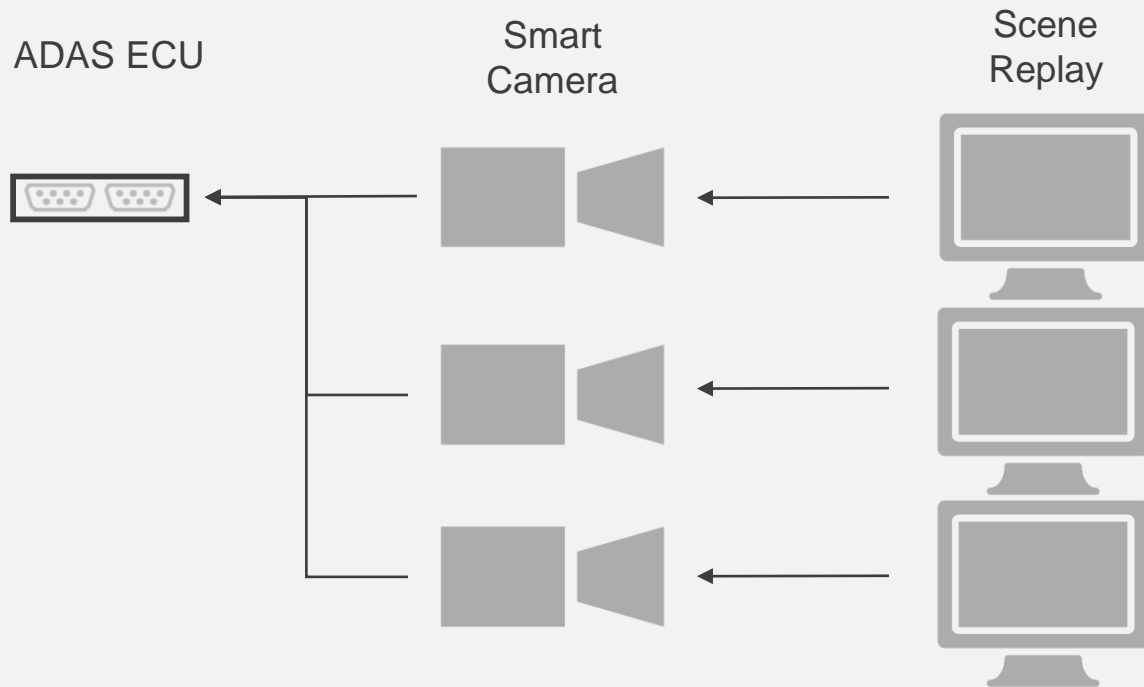
Properly Simulating Conditions



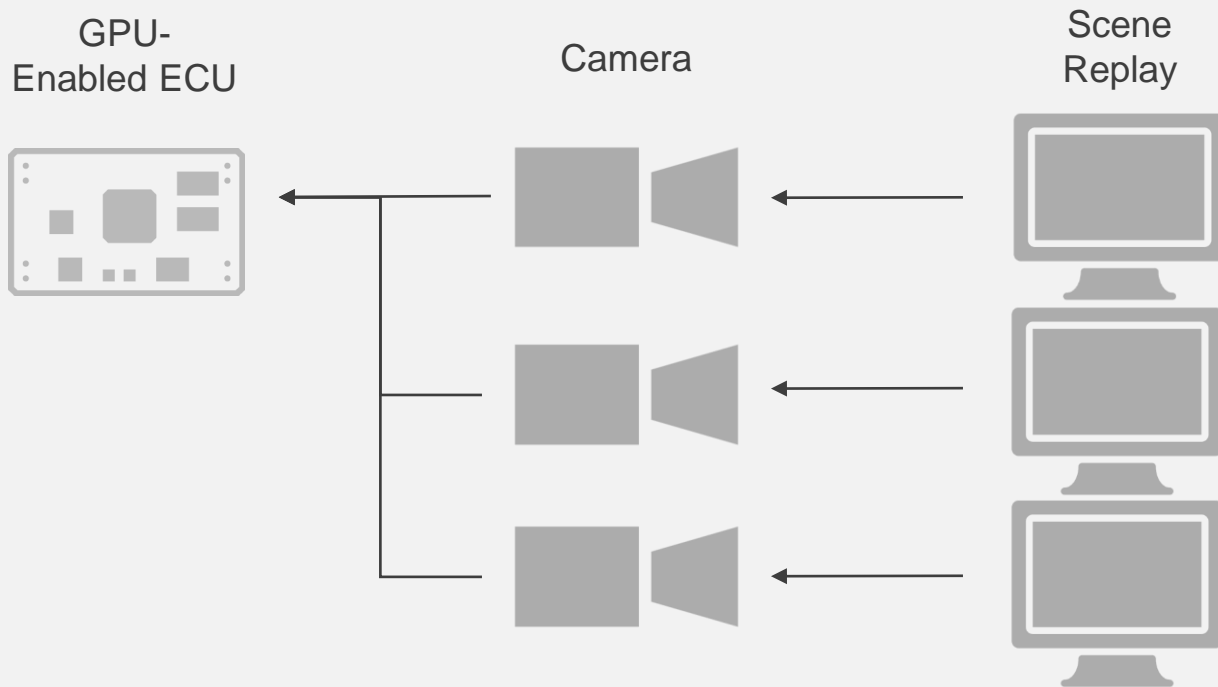
Approaches to Camera Test



Approaches to Camera Test



Approaches to Camera Test



Approaches to Camera Test

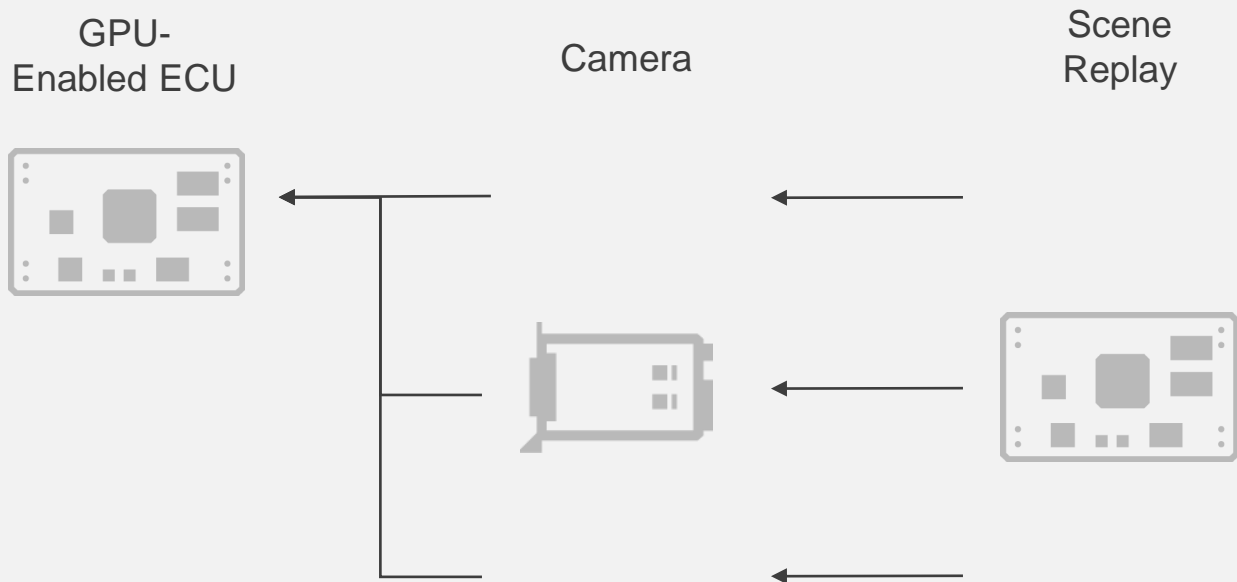


Image Manipulation With FPGA

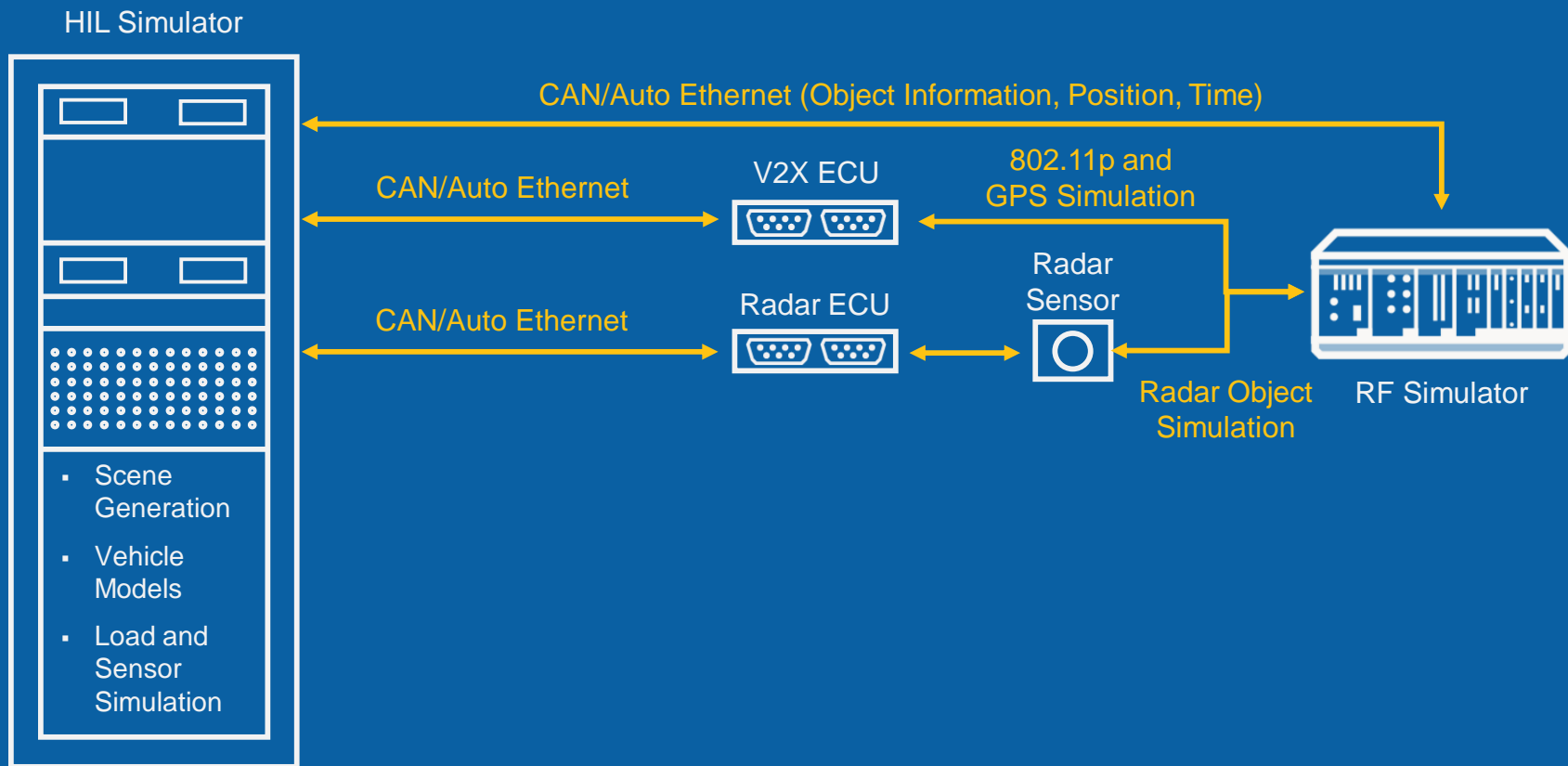
Dropped Frames
or Frame Delay

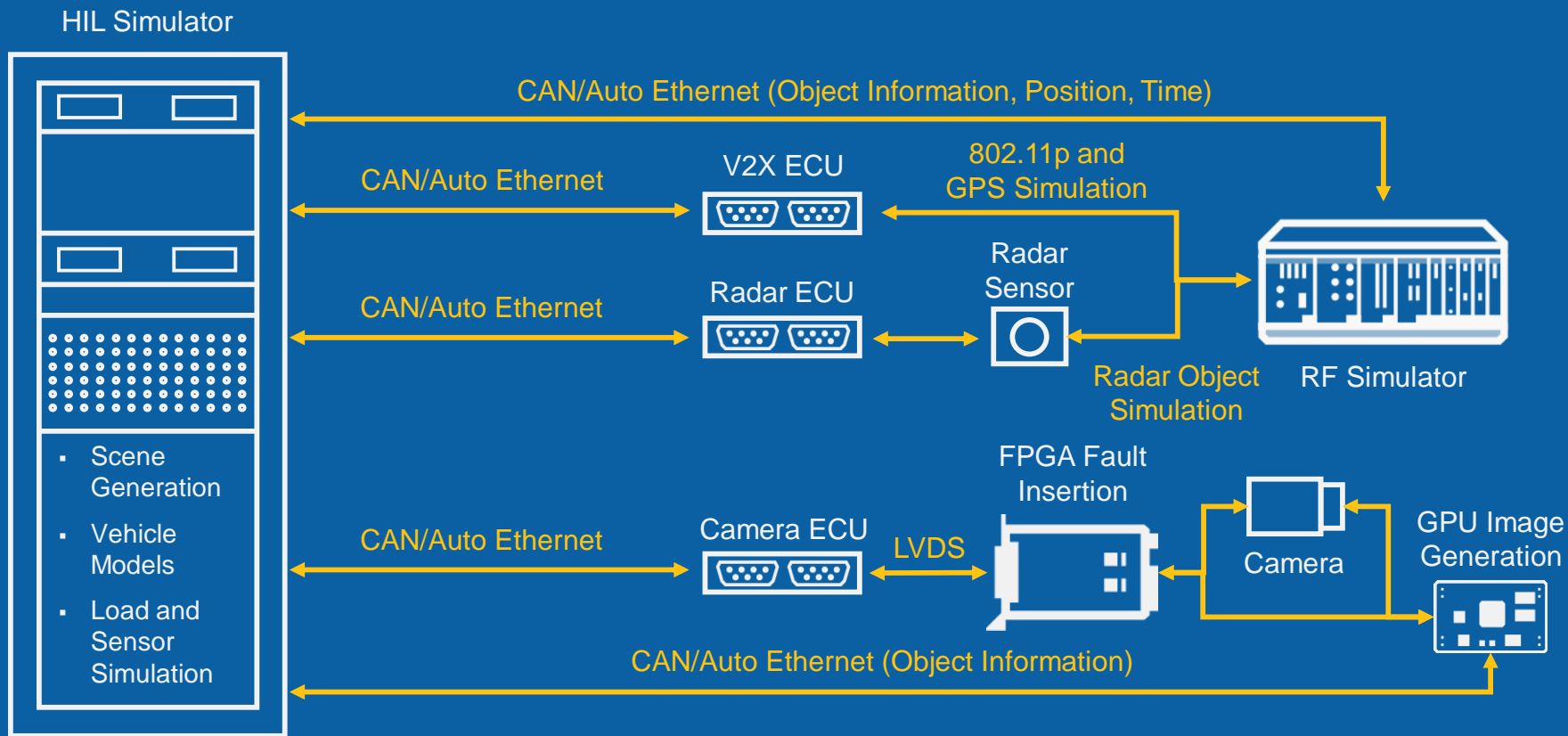
Noise and
Error Injection



Bitstream
Manipulation

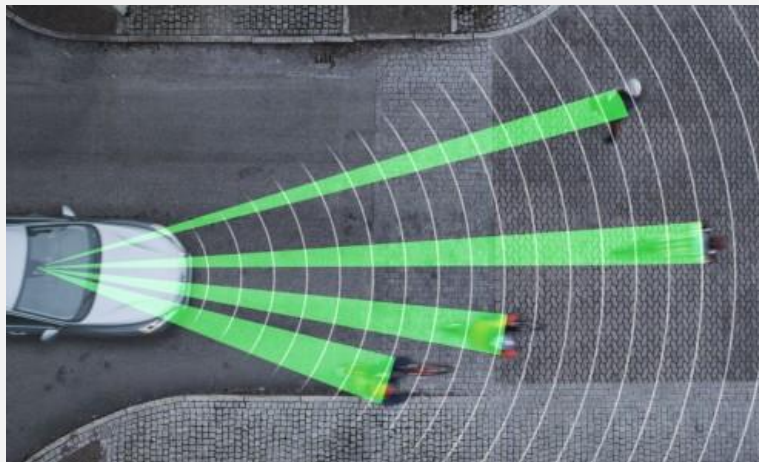
Custom
Protocols



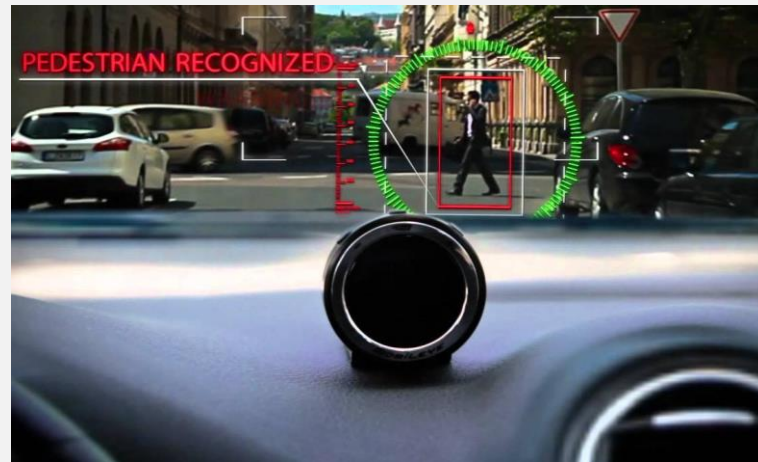


Sensor Fusion

Cameras and Radar Working Together

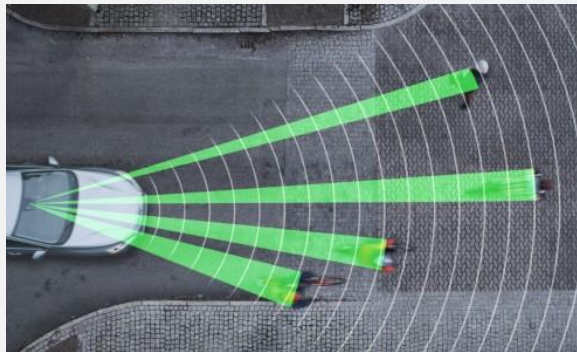


Object Detection Using Radar



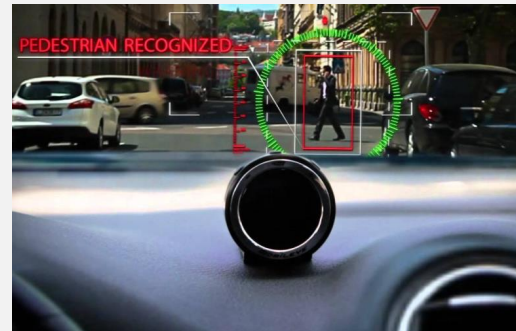
Object Classification Using Cameras

Cameras and Radar Working Together



Object Detection Using Radar

Synchronization



Object Classification Using Cameras



ADAS ECU for Safety Operations

Testing Sensor Fusion Embedded Software



Radar Target Emulation



Video Stream Manipulation



ADAS ECU for Safety Operations

Hardware-in-the-Loop Test

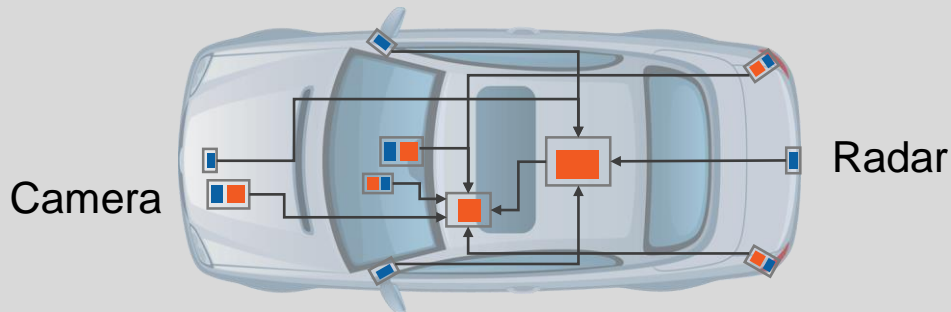


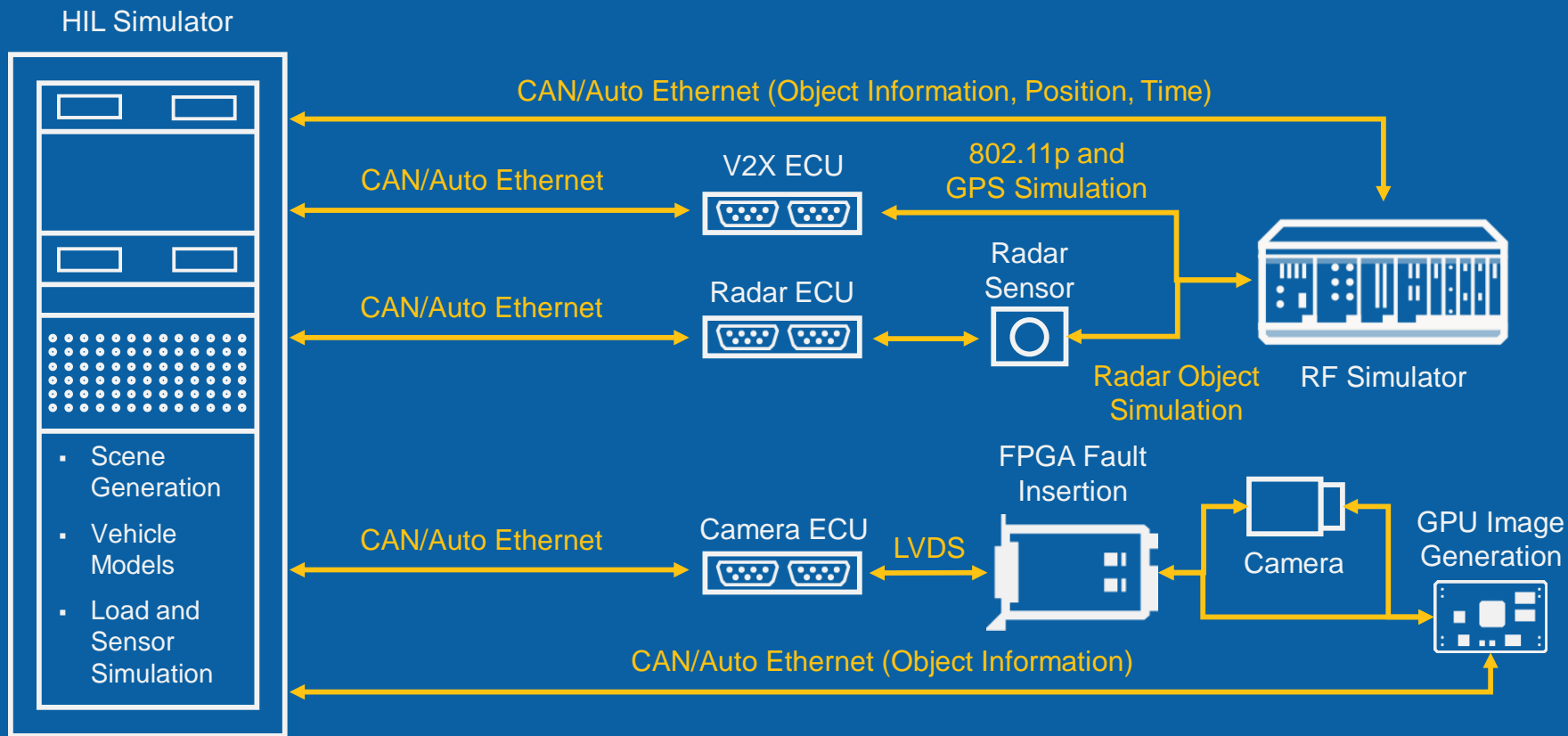
CAN
Interface

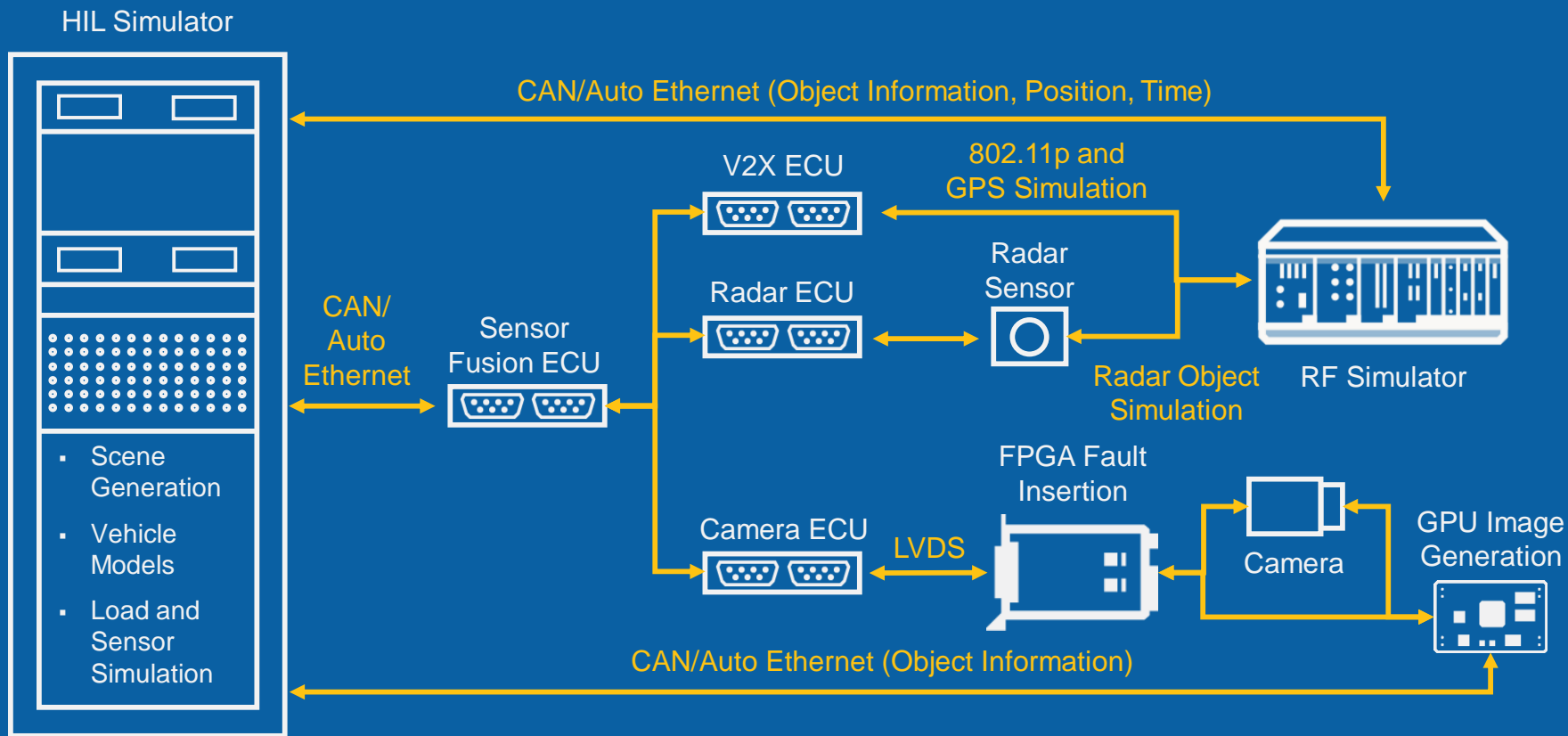
GNSS
Simulation

Radar Target
Simulation

Image
Simulation







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NIDays ENGINEER
NEXT