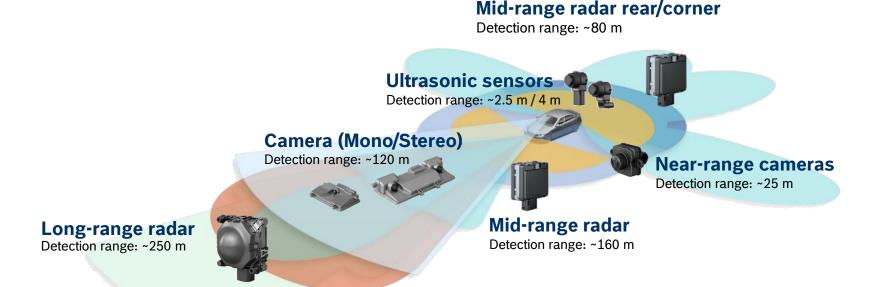
NTSB SAFETY FORUM

BOSCH PEDESTRIAN PROTECTION



NTSB Safety Forum – Bosch Pedestrian Protection Sensors for 360 degree surround sensing

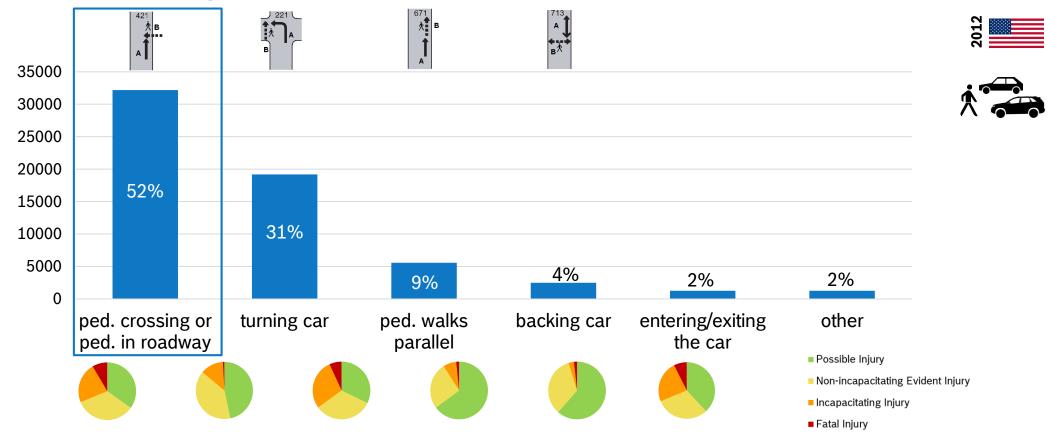




- · Dependent on DA functionality, different sensor set necessary (different range, field of view, ...)
- · For Pedestrian AEB, target is to have robust and highly reliable sensor set



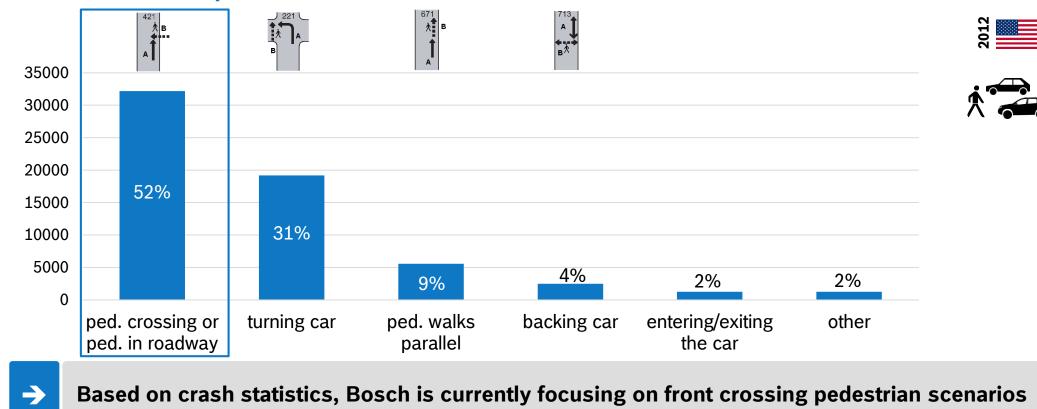
Distribution of pedestrian crashes in the US



Source: GES 2012 Report prepared by Bosch Accident Research Pedestrian accidents (n = 66 260) w/ primary collision of passenger car, utility vehicle, van, transporter or light truck.



Distribution of pedestrian crashes in the US



Source: GES 2012 Report prepared by Bosch Accident Research Pedestrian accidents (n = 66 260) w/ primary collision of passenger car, utility vehicle, van, transporter or light truck.



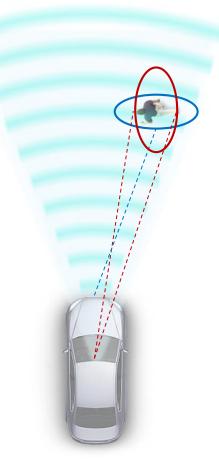
Radar / Video Standalone

→ Radar:

- Precise longitudinal distance and velocity in different weather and light conditions
- Less exact lateral position
- Classification as pedestrian based on micro-doppler

→ Video:

- Precise lateral position
- Angles of object edges
- Less exact longitudinal values
- Good object type classification





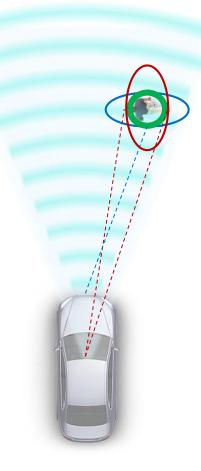
Radar / Video Fusion

→ Fusion

- Combines the advantages of both sensors
- Precise longitudinal distance & velocity measurement
- Precise lateral distance & velocity measurement
- Robust classification
- Best possible true/false performance

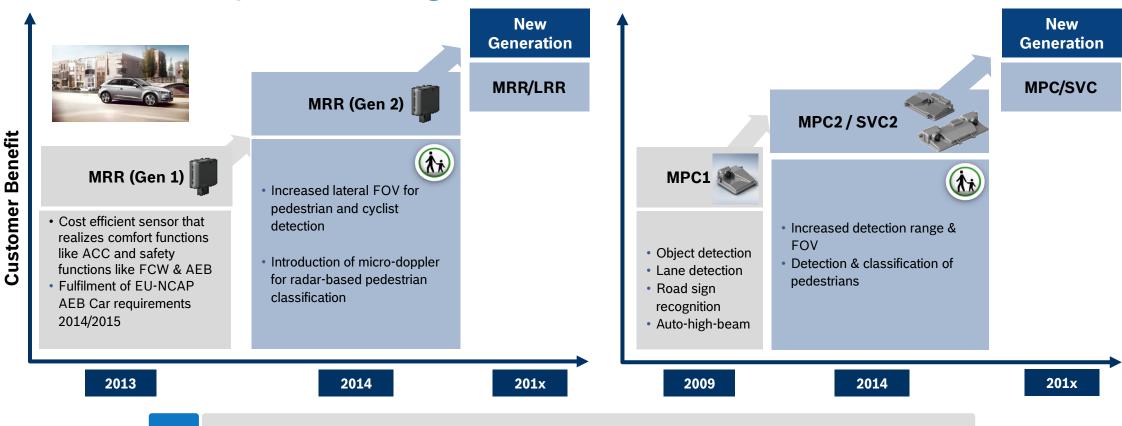
→

- Fusion between Radar and Camera required to achieve best possible AEB pedestrian performance
- AEB pedestrian can also be realized with single sensor solutions (may have limitations)





Evolution Steps Mid Range Radar / Cameras



Bosch improving sensor technology to realize AEB pedestrian scenarios



NTSB Safety Forum – Bosch Pedestrian Protection Object classification w/ Radar

Features for robust and reliable classification on crossing objects (e.g. pedestrian) **Radar Cross Section (RCS)** ~ 10-20dB difference between car rear and pedestrian Classification Patterns regarding **motion/dynamic** of locations Micro-doppler Direct measurement of arm/leg movement

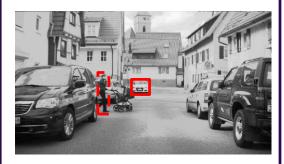


Articulation of pedestrian dummies critical for pedestrian classification with Radar



Object classification w/ Video

Classification



"Learn patterns and find it"

- Only trained objects are recognized
- → Huge training-database is necessary

Optical flow, Structure from Motion



"Compare one image with next"

- Ego-vehicle motion and its precise measurement necessary
- No exact measurement, only estimation

Disparity



"Measure by triangulation"

→ Exact measurement of the 3D position for each picture element; also if host vehicle in standstill



Mono

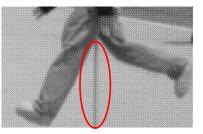


Stereo

Targets / Harmonization

- → Bosch has evaluated several artificial test targets
- Some targets are not representative of real pedestrians

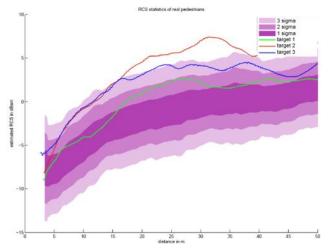








- **Realistic appearance, poses and articulation** are critical to ensure robust pedestrian classification.
- A **harmonization** of the pedestrian targets & test procedures between US and EU NCAP could reduce development and testing efforts.



Radar cross section (RCS) of artificial test targets compared to real pedestrians

(Source: ACEA pedestrian target specification and Bosch testing data)



- Bosch utilizes its Corporate Research activities to identify and develop relevant technologies to prevent collisions and minimize accident severity.
- → The current development focuses on **front crossing scenarios** which is in line with the recent US NCAP proposal.
- → **Harmonization** of test procedures and pedestrian targets with Euro NCAP will ensure the earlier introduction of already available pedestrian protection technologies to the US market.
- Scenarios with a turning vehicle require additional technologies and further research to realize robust systems.
- **→** Bosch's vision is **Accident-free Driving**.



