ACC SW Architecture

ACC Node - Architecture Flow

Event: /tof_distance_mm

- Check Current Mode
- Mode == CRUISE?
  - yes → Read ToF Distance
  - no, Mode != CRUISE → Do Nothing (Logic Skipped)
- Distance < braking_dist_ ?
  - yes (AEB) → Set Speed = 0.0 (Braking)
- Distance > detect_threshold_ ?
  - yes (fixed) → Set Speed = cruise_speed_
  - no (PI control) → Calculate Speed (PI Control)
    - Goal: Maintain target_dist_
- Publish Speed to /planner/motion