

# Documentation Parkassist

## Graphische Programmierung und Simulation

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**Student ID, Course**

8540946; 6430174, STG-TINF17-ITA

**Lecturer**

Dr. Kai Pinnow

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# Acronyms

NaN      Not a Number

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# 1 Introduction

In this project Matlab version R2019b and ASCET version 7.4 have been used. The Matlab and Simulink code is in the Matlab subfolder and the ASCET project is in the ASCET subfolder. Simulink settings: The report is structured by devoting one chapter to each requirement.

In ASCET mainly graphical programming using block diagrams is used due to requirement D7. Even though D8 does not demand graphical programming, for consistency reasons D8 is being graphically modelled as well. Exceptions are the unit tests. The test are programmed in ESDL because some test have a lot of test cases which would lead to a large block diagram that would likely be unclear.

For the simulink models the ode8 solver is used, because it is the most precise fixed step solver. As step-width, 0.01s are used to provide efficiency but also the necessary precision.



## 2 D1: Time estimate based on three point estimation

For the three point estimation we use the formuals from the lecture. The expected effort is computed using a weighted mean formula:

$$\langle T \rangle = \frac{\text{optimistic} + 4 * \text{likely} + \text{pessimistic}}{6} \quad (2.1)$$

To compute the standard deviation we use the following equation:

$$\sigma = \frac{\text{pessimistic} - \text{optimistic}}{6} \quad (2.2)$$

In the following the time unit is hours.

Table 2.1 contains our effort estimates for the tasks at hand, the expected value, computed standard deviation and the actually needed time.

Table 2.1: Three point estimation of effort for meeting requirements

Requirement	Optimistic	Likely	Pessimistic	$\langle T \rangle$	$\sigma^2$	Actual
D1	0.75	1	1.5	1.0417	0.0156	0.75
D2	0.5	1	1.5	1	0.02778	1.25
D3	1.5	2	3	2.08333	0.0625	4
D4	2	3	4	3	0.11111	2
D5	2	3	4	3	0.11111	3
D6	2	2.5	3	2.5	0.02778	5
D7	3	4	5	4	0.11111	3
D8	1.5	2.5	3	0.0625	0.25	1
D9	4	4.5	5	4.5	0.02778	2
D10	3	3.5	4	3.5	0.02778	2.5
D11	1	1.5	2	1.5	0.02778	2
D12	6	7	8	7	0.11111	7
D13	1	1.5	2	1.5	0.02778	1
D14	1.5	2	2.5	2	0.02778	2
Total	29,75	39	48,5	39,04167	0.77951	36.5

The estimation of the 95 % estimate of the total duration is computed as:

$$\sum < T > + 2 * \sqrt{\sum \sigma(T)^2} \quad (2.3)$$

This results in a 95 % estimate of 40.8 hours.

The total actually needed time is slightly less than the expected value of 39 hours. Some tasks, like D3 (human velocity profile extraction) and D6 (pulse signal in Simulink) took significantly longer than expected. But on the other hand tasks like D8 (pulse signal in ASCET) and D9 (Unit tests) took less time than expected. The pulse signal implementation in Simulink took long, because finding a functioning concept on how to create the pulse was challenging, but then the ASCET implementation basically followed the Simulink implementation, which resulted in less time needed than expected. The experiences from this estimation will be used, to make future effort estimations more precise.

Nonetheless the actually needed time is well within 95 % confidence interval.

## 3 D2: Feasibility study

The aim of the feasibility study is to analyse whether it is possible to realise smooth braking with the introduced model and parameters based on the given formulas

$$\frac{\partial v}{\partial t} = -c - b * p \quad (3.1)$$

$$\frac{\partial x}{\partial t} = v \quad (3.2)$$

with  $c = 1.5 \text{ m/s}^2$  and  $b = 10 \text{ m/s}^2$ . For that, in the next section a Simulink model is created, based on the equations above. After that, a test scenario to test the feasibility is described and in section 3.3 the results of the study are outlined. Section

### 3.1 Simulink model

Figure 3.1 shows the simulink model representing the differential equations above. The parameter  $p$  is configured on execution of the simulation in Matlab. The initial velocity  $v_0$  is set to 10 km/h and the initial car position  $x_0$  is set to 0, corresponding to the scenario, that should be tested. Since the output of the first integrator is in m/s,  $v_0$  needs to be divided by 3.6 to convert  $v_0$  from km/h to m/s. The minimal velocity of 0.29 km/h from requirement R5 has been included in the model. Otherwise, the car would not come to a full stop because the velocity would become negative eventually. R5 is realised with a switch, that sets velocity to zero if the computed velocity is below 0.29 km/h, which corresponds to approximately 0.0806 m/s. The velocity is integrated to compute the location, following the second differential equation. The output parameters acceleration (a), velocity (v) and travelled distance (s) are output using the out block. Input parameters are input as constants. In this preliminary test a constant  $p$  is used, which is not time-dependent.

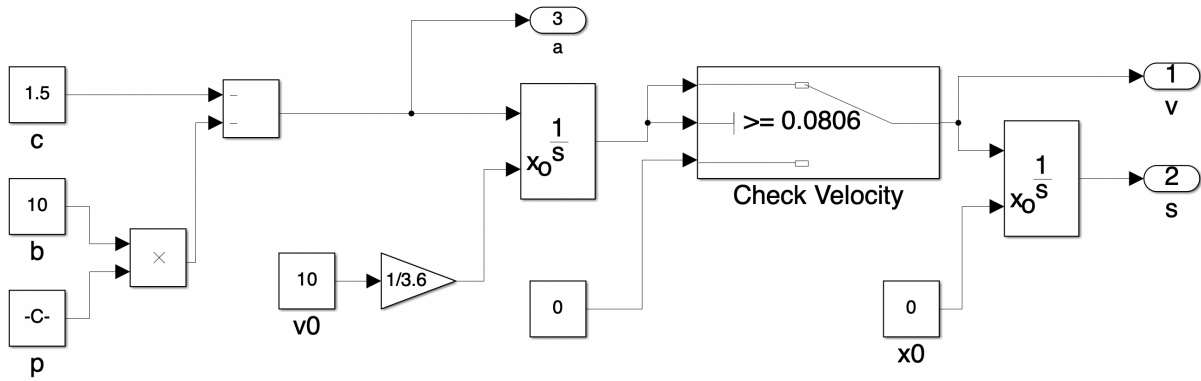


Figure 3.1: Simulink model of the differential equations

## 3.2 Test scenario

The goal of this scenario is to check whether it is possible, with the given model, to realize a smooth stop with a stopping location  $< 2$  m. The idea is to demonstrate, that a full stop before 2 m can be realised with a reasonable brake pedal pressure and a reasonable deceleration. If, for example a stop before 2 m could only be realised with 100 % brake pressure, that would mean that a smooth stop can not be realised.

It is not necessary to implement a human-like smooth stop, but to show that this is possible. Therefore the proposed test scenario is to run the model and find a reasonable small brake pressure where the car comes to a full stop with a location  $< 2$  m. This would show the feasibility of the task. Creating a human-like brake profile where the brake parameter  $p$  can be adjusted over time is not an objective of this feasibility study, this will be covered at a later stage.

The execution of this scenario is automated using a Matlab script, which parametrizes the model and displays the outputs. Listing 3.1 shows the script that executes the simulation and stores the results. The code to create the result plots has been excluded. In lines one to eight the simulation is parametrized. A stop time of 2 seconds is chosen because the car will come to a stop before.

todo solver begründen

The constant brake pressure is set to 5 %. This value results in a stop before the car traveled 2 meters of distance and is also reasonably small.

```
1 %% Parametrize Model
2 set_param('D2', 'StopTime', '2');
3 %set solver
4 set_param('D2', 'Solver', ['ode', sprintf('%d', 8)]);
5 %set simulation step size
6 set_param('D2', 'FixedStep', sprintf('%f', 0.01));
7 %set brake pressure parameter
```

```
8 set_param('D2/p','value',sprintf('%f',0.05));
9
10
11 %% Simulate and get output
12 res = sim('D2','SaveOutput','on','SaveState','on');
13 t = res.tout;
14 v = res.yout{1}.Values.Data;
15 s = res.yout{2}.Values.Data;
16 a = res.yout{3}.Values.Data;
17 %convert velocity to km/h
18 v = v*3.6;
```

Listing 3.1: Execution of the feasibility test

### 3.3 Results

The following figure 3.2 shows the simulation results with a constant brake pressure of 5%. This results in a constant deceleration of  $-2 \text{ m/s}^2$ . Setting the velocity to zero, when reaching the minimal velocity, has no impact on the computed acceleration. This is the reason, why the acceleration still remains the same, even though the car is not moving anymore.

The velocity linearly decreases from  $v_0 = 10 \text{ km/h}$  to zero (except the decrease from minimal velocity to zero, which was expected). The third subplot shows the covered distance of the car, which is clearly under the 2 m mark. Therefore, with a constant brake pressure of 5 % the car can be stopped before reaching 2 m travelled distance with an acceptable deceleration of  $2 \text{ m/s}^2$ . In the cruise control project we have discussed that an acceleration of less than  $4 \text{ m/s}^2$  is not uncomfortable.

These simulation results demonstrate that it should be possible, with variation of the brake pressure over time, to realise a smooth stop with a human-like brake profile.



Figure 3.2: Simulation results of feasibility study

## 4 D3: Analysis of human velocity profile

In this section the provided human velocity profile is analysed in order to find a pattern that can be abstracted as a human-like brake profile. This pattern will be used in the following sections and will be adapted to the braking function of the ParkAssist. For the analysis Matlab functions are used, as demanded by requirement D3.

### 4.1 Import the measurement data

The human velocity profile contains a time dimension and the four wheel velocities. The following listing shows how the measurement data is imported in Matlab. A Matlab library function is used for the import of the textfile. This results in a standard numeric matrix.

```
1 %import velocity data
2 velocity_data = importdata('MeasuredVelocities.txt');
```

Listing 4.1: Import measurement data in Matlab

### 4.2 Data preparation

The aim of the analysis is to make conclusions that lead to a time dependant brake profile. Since the brake pedal has a linear influence on the acceleration (see model formula) the goal is to extract an acceleration curve from the human velocity profile, from which to make deductions on the brake profile. For that, a cars acceleration and in consequence the cars velocity is needed. Therefore a mean car velocity has to be extracted from the given four wheel velocities.

Listing 4.2 shows the Matlab script that pre-processes the data. As a first step, the four wheel velocities are extracted from the measurement data and a mean velocity is calculated with the following equation (lines 2 and 3 in listing 4.2):

$$v_{car} = (v_{w1} + v_{w2} + v_{w3} + v_{w4})/4 \quad (4.1)$$

This mean velocity serves as an estimate for the car velocity. It is only an estimate, because friction losses, other physical influences and cornering are not considered. The mean velocity is converted to [m/s] for further calculations in line 4 in listing 4.2. Before calculating the acceleration, a moving average filter is applied on the mean velocity (line 8 in listing 4.2). Further details about the moving average filter are given in the next paragraph. The acceleration can be calculated by differentiating the mean velocity (line 11 in listing 4.2).

```

1 %compute mean velocity of all 4 wheels
2 velocity_per_wheel = velocity_data(:,2:5);
3 mean_velocity = mean(velocity_per_wheel,2);
4 mean_velocity = mean_velocity/3.6;      %convert velocity from km/h to m/s
5 raw_mean_velocity = mean_velocity;      %for demonstration purposes
6
7 %apply moving average filter to smoothen the data
8 mean_velocity = movmean(mean_velocity, 200);
9
10 %differentiate velocity to get acceleration
11 acceleration = diff(mean_velocity);
12 raw_acceleration = diff(raw_mean_velocity); %for demonstration purposes

```

Listing 4.2: Preprocessing measurement data

As can be seen in the upper subplot of figure 4.1 the calculated acceleration is noisy due to noise in the measured velocity. Because of the noise it would be harder to analyse the braking behaviour. Therefore we used a moving average filter to smoothen the data. A moving average filter is calculating a mean value of neighbouring elements within a sliding window of a predefined size. Applying a moving average filter results in a filtered graph that can be seen in the lower subplot of figure 4.1. However, applying a moving average filter distorts the acceleration values because the exact value is replaced by the average of the neighbouring elements. This reduces the difference between the values of neighbouring elements. As a result the differentiation of the velocity results in an acceleration that is in our case approximately 10 times smaller than the non-filtered results. Although the values of the acceleration are smaller the course of the acceleration is not changed. Therefore the filtered data is not used to extract exact acceleration values but rather to get an understanding of the acceleration curve during braking.



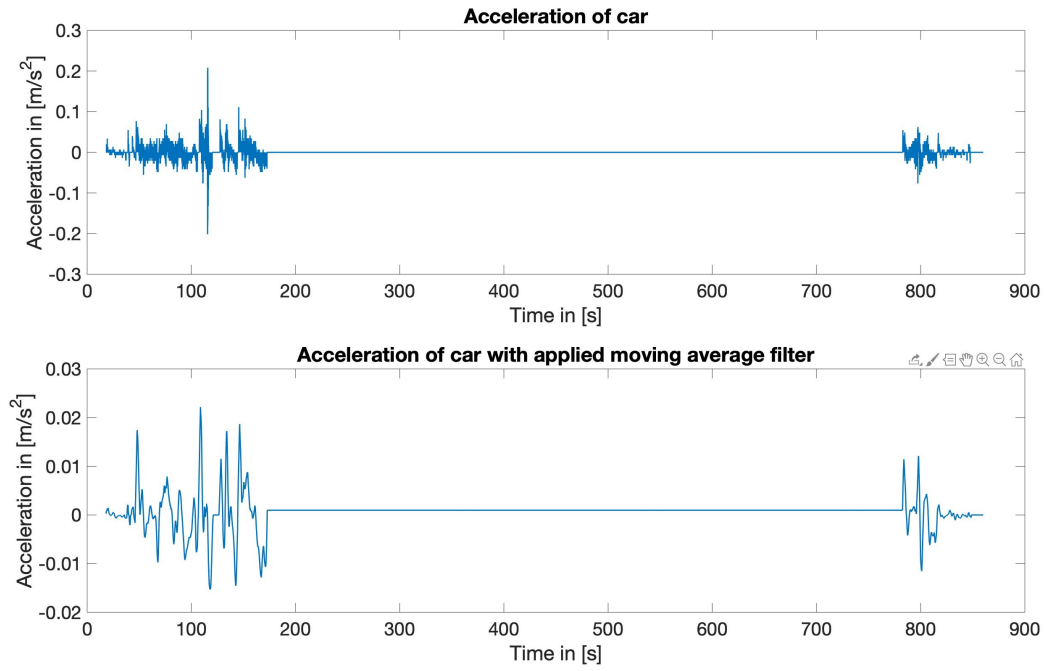


Figure 4.1: Impact of applying a moving average filter on the cars acceleration

Figure 4.2 shows the mean velocity of the car as well as the corresponding smoothened acceleration of the car over time.

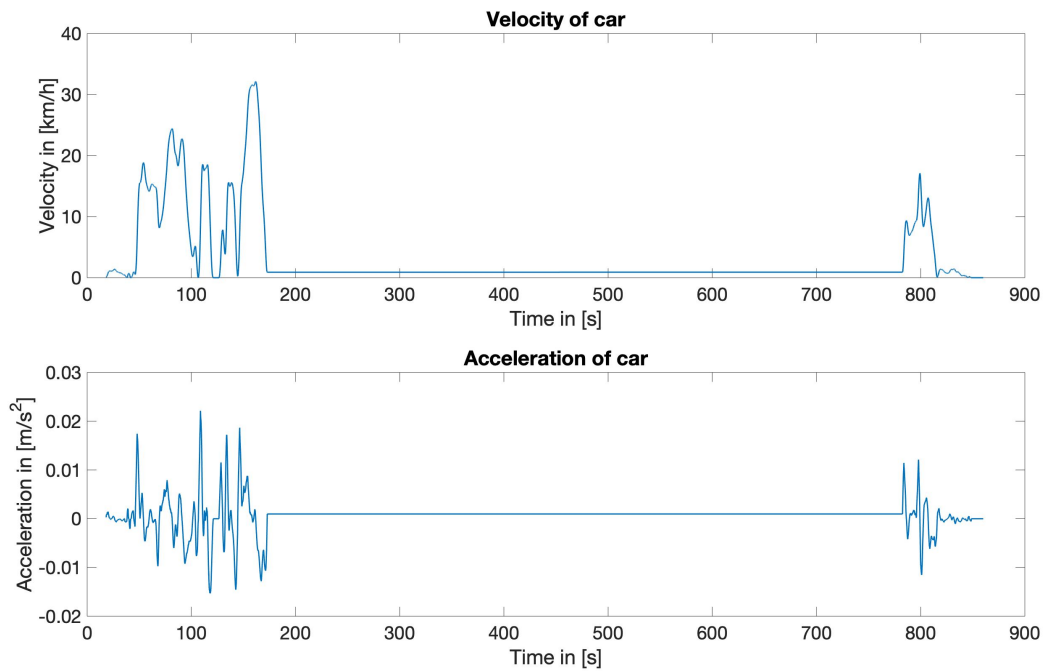


Figure 4.2: Extracted human velocity profile

### 4.3 Extracting negative acceleration

As the goal is to analyse the braking behaviour, only negative acceleration is relevant and is thus being extracted from the overall acceleration (line 5 in listing 4.3). Also, all velocities that are based on a positive acceleration are not considered anymore (line 6 in listing 4.3). We decided to set those values to Not a Number (NaN) because this way we are still able to plot the velocity and the acceleration over time without cut-outs. The result can be seen in figure 4.3.

```

1 %search for negative acceleration and set positive acceleration to NaN
2 %set all velocities that have a positive acceleration to NaN
3 neg_acceleration = acceleration;
4 decreasing_velocity = mean_velocity;
5 neg_acceleration(neg_acceleration > 0) = nan;
6 decreasing_velocity(isnan(neg_acceleration)) = nan;

```

Listing 4.3: Extracting negative acceleration

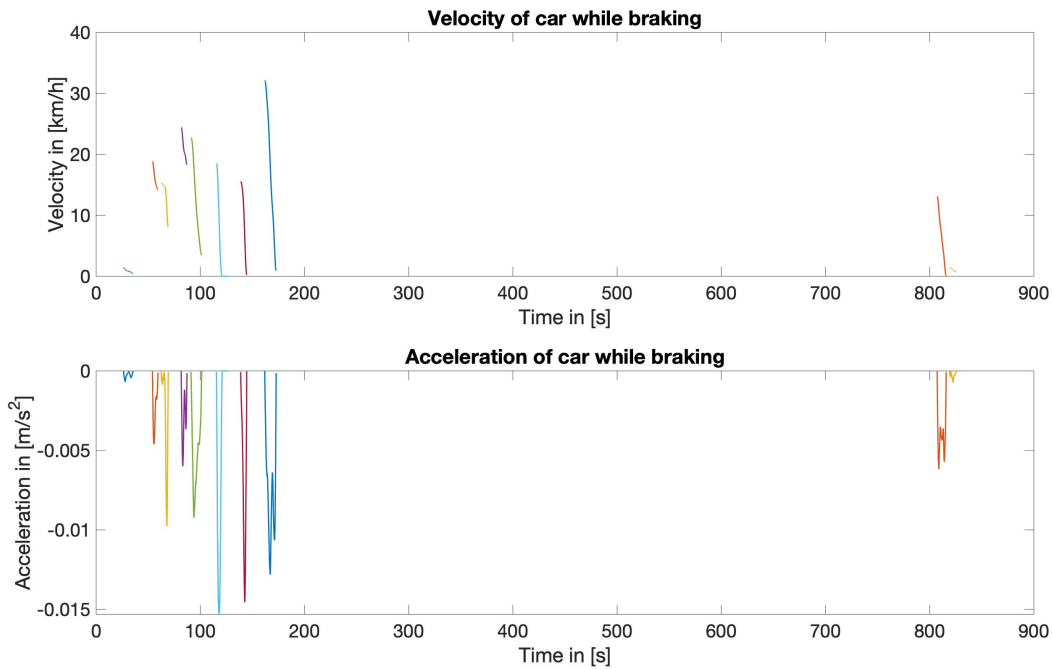


Figure 4.3: Braking manoeuvres in human velocity profile

### 4.4 Separating breaking sequences

For better visualisation, the breaking sequences that can be seen in figure 4.3 will be stored separately. One breaking sequence consists of multiple consequent velocity measurements. This means that the breaking sequences can be separated by searching for a gap in

the velocity measurements (NaN values). Therefore, the indices of all velocities that are set not NaN are extracted (line 2 in listing 4.4) and differentiated (line 3 in listing 4.4). Consequently, every differentiation that is greater than 1 marks a gap between velocities because indices of one braking sequence are subsequent (differentiation equals 1). Furthermore, short braking sequences are not considered because they are most likely not relevant for recognizing a braking pattern (line 13 in listing 4.4). Two individual braking sequences can be seen in figure 4.4 and figure 4.6.

```

1 %find individual breaking sequences
2 notNaN_velocity = find(~isnan(decreasing_velocity)); % find index of every velocity
   that is not NaN -> one breaking sequence has consequent time steps -> one breaking
   sequence has consequent indices
3 diff_notNaN_velocity = diff(notNaN_velocity); % differentiate indices -> if
   indices are not consequent (unequal 1), a new breaking sequence has begun
4 n = 1; % set start values
5 start = 1;
6
7 %seperate breaking sequences with previous findings
8 for i=1:length(diff_notNaN_velocity)
9     %for every index check if indices are consequent -> equals 1
10    if diff_notNaN_velocity(i) > 1
11        %if not check if a breaking sequence consists of min 500 time
12        %steps, this way small breaking sequences are sorted out
13        if (i-start) > 500
14            %add breaking sequence to section
15            %i is end of sequence
16            section{n} = notNaN_velocity(start:i);
17            %start for new sequence is end of old sequence + 1
18            start = i+1;
19            %increment n
20            n = n+1;
21        else
22            %if breaking sequence is to small, set start for new sequence
23            %to end of old sequence + 1 anyway
24            start = i+1;
25        end
26    end
27 end

```

Listing 4.4: Separating breaking sequences

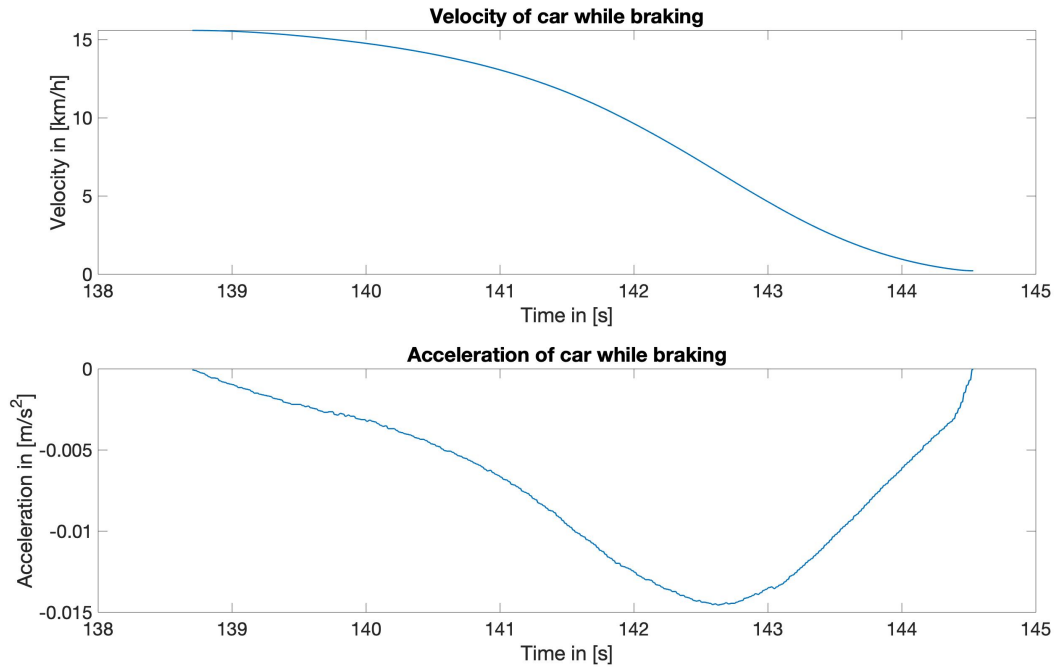


Figure 4.4: Individual braking manoeuvre 1 extracted from the human velocity profile

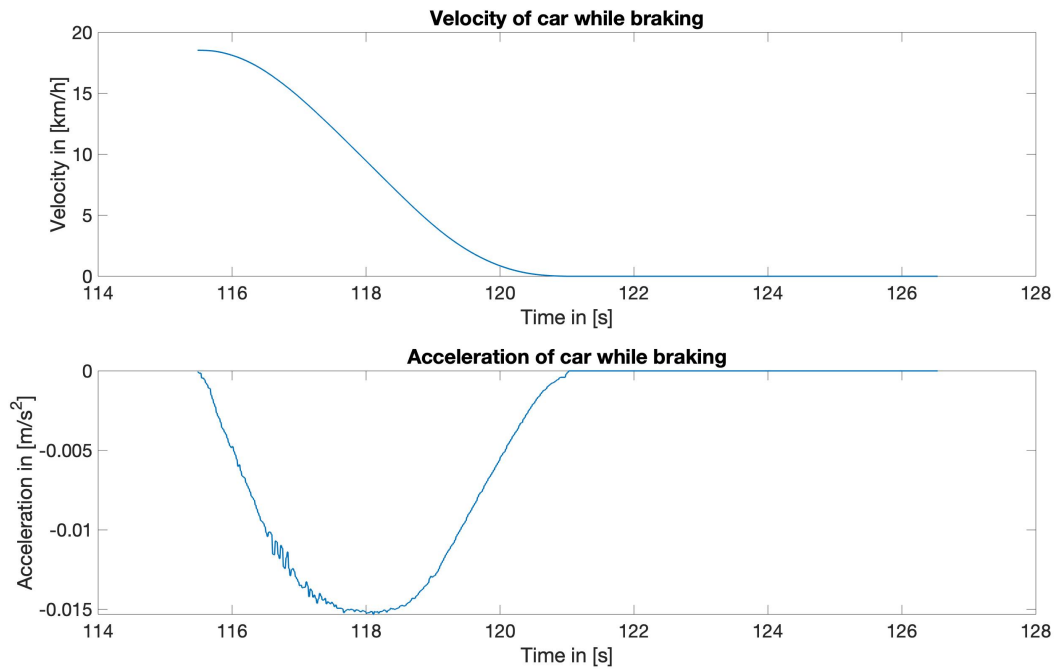


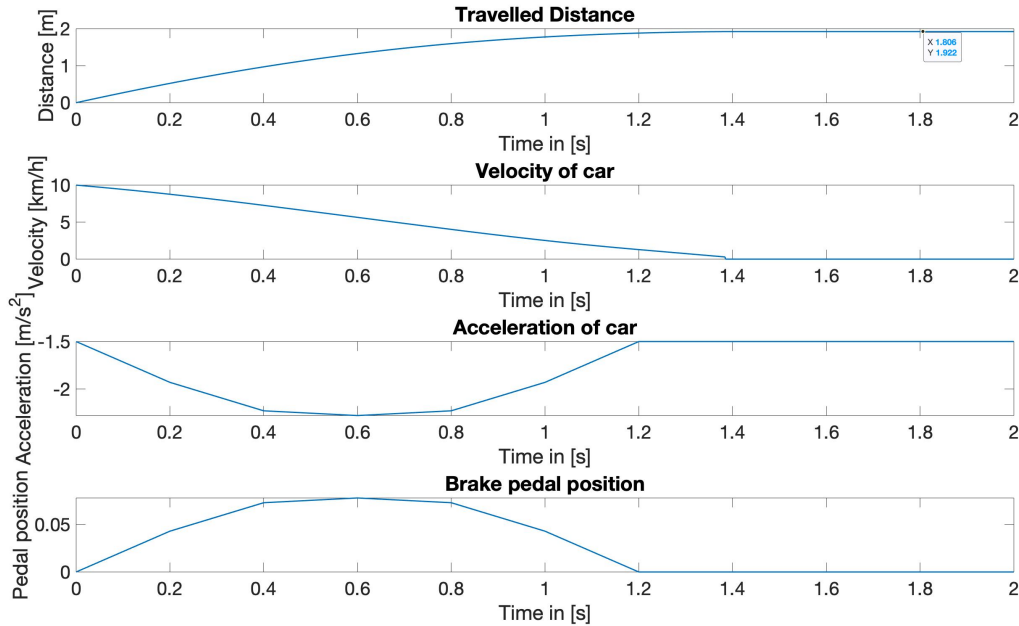
Figure 4.5: Individual braking manoeuvre 2 extracted from the human velocity profile



Table 4.1: Determined  $p(t)$  parameters

Time in [s]	Brake pressure
0	0
0.2	0.043
0.4	0.073
0.6	0.078
0.8	0.073
1	0.043
1.2	0

Figure 4.7 shows the results of the Simulink simulation using the parameters from the table above. With 10 km/h as  $v_0$  the car comes to a stop at approximately 1.92 meters. This leaves a margin for velocity measurement inaccuracies, which will be analysed in chapter 6 todo check. The acceleration curve in the third subplot is similar to a human profile, with the exception of the offset of  $-1.5 \text{ m/s}^2$ . This can not be prevented because there is no gas pedal. It can also be seen that at the end of the braking procedure at approximately 1.2 s, the brake pedal is released and the friction brings the car to stop.


Figure 4.7: Simulation results with  $p(t)$

## 5 D4\*: Consideration of uneven parking spaces

For consideration of uneven parking spaces, the physical car model needs to be expanded to include slope downforce (Hangabtriebskraft). Also the height profile of the parking space would have to be stored, to be used in the model. A lookup-table could be used to store the height profile.

A negative slope would increase stopping time and position. A negative slope is critical since a collision could occur. Depending on the steepness the  $p(t)$ , that is used now, would not suffice and harder braking would be necessary.

A positive slope would make stopping time and location shorter. This would not lead to a collision, but the car would stop further away from the obstacle. That could also be not wanted, since then parking space would be used less efficient.

If the distance from the obstacle should be the same, regardless of positive/negative slope or even parking space, the brake power needs to be varied depending on steepness. With a negative slope it is needed to brake harder in comparison to an even parking space. With a positive slope lesser braking would be necessary.

Depending on  $v_0$ , with a negative slope, it might not be possible to stop before 2 m of travelled distance.

Also after the car is stopped it should not start to roll forwards or backwards. On a plain surface, the brake can be released, after the car is stopped. That might not be the case with an uneven parking space and the car could start rolling. A brake assist on a positive or negative slope would need to keep holding the brake or engaging the handbrake.

If the slope is known beforehand (the same as we know now that the parking space is even), that can be included when determining  $p(t)$  and adjusting the brake pedal position according to the slope. Of course the feasibility study (D1) would have to be done again, to determine the feasibility of the task with the changed slope.

Also, it does not have to be a solely positive or negative slope. It could also be first a positive and then a negative slope (or any other height profile) when approaching the parking spot. For each different slope, a different  $p(t)$  would be needed to result in the same stopping position.

If the car should be able to stop before 2 m with an unknown slope, a controller with feedback would have to be used instead of  $p(t)$ , to dynamically adjust the brake pedal position depending on car behaviour.

## 6 D5: Discussion of inaccuracies in velocity measurement

### 6.1 Inaccuracy in car velocity

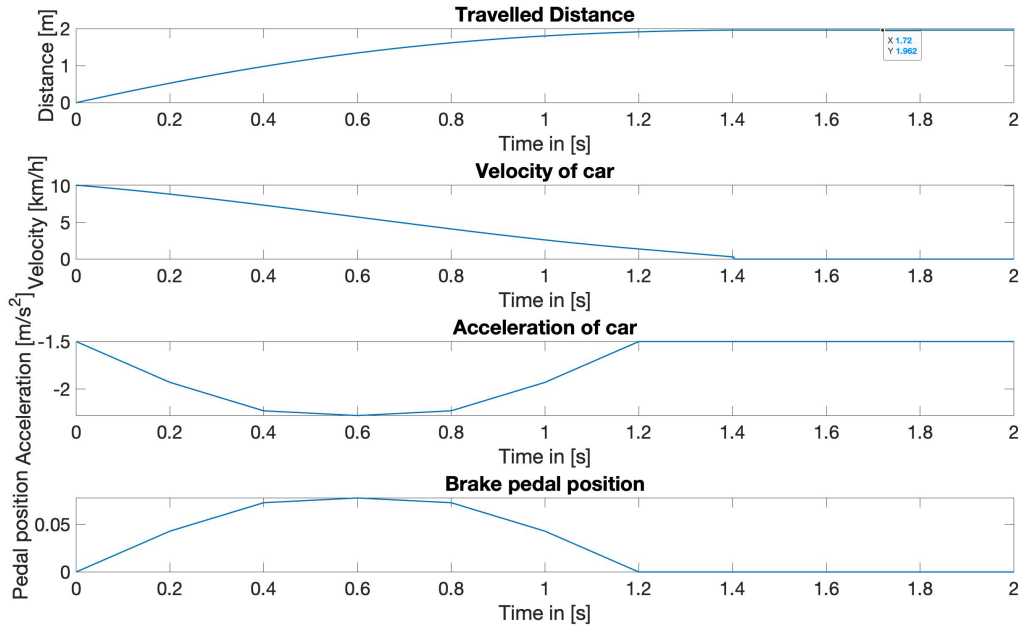
The velocity information of the car has an inaccuracy of velocity  $\pm 0.1$  km/h. Also the minimal velocity is 0.29 km/h which is not realistic, because velocity does not drop from 0.29 km/h to zero in one step.

The brake pedal function is not dependant on the velocity, therefore inaccuracies in the velocity measurement during the braking procedure do not influence the braking procedure. This has one exception. Considering the velocity measurement inaccuracy, the initial velocity could be in a range of  $9.9 \text{ km/h} \leq v \leq 10.1 \text{ km/h}$ . This would certainly influence the braking behaviour of the car. It would be dangerous if the initial velocity would be higher than expected, because the car would travel further than expected because of that. This might cause an accident. If it would be lower, the car might stop earlier but that would not lead to an accident.

A simulation is used to evaluate the danger of the initial velocity being higher than expected. The, highest initial velocity that is possible with R5 is 10.1 km/h. So this is used as  $v_0$  for the impact evaluation. The model from Figure 4.6 from before is used for the evaluation, to see if the margin to 2 m is enough with a  $v_0$  of 10.1 km/h.

As can be seen from the results of the simulation in figure 6.1 the margin is enough, since the stopping distance is approximately 1.96 m. The stopping distance from the correct  $v_0$  of 10 km/h (see section 4.6) is 1.92 m. So the velocity difference of 0.1 km/h results in a stopping distance difference of circa 4 centimeters.



Figure 6.1: Simulation of inaccurate  $v_0$ 

Uncertainties in the measured velocity also influence the computed travelled distance. The velocity is needed to compute the travelled distance. The travelled distance is computed as the integral of the velocity. Therefore errors in the velocity accumulate in travelled distance.

However if the error follows a gaussian distribution, the integrated error would be relatively small, because over- and under-estimation would be equally likely.

## 6.2 Inaccuracy in velocity measurement of human velocity profile

In the human velocity profile 4 tire velocities are recorded. To estimate the car velocity the mean of the 4 wheel velocities has been computed. It was assumed, that the car is moving in a straight line and not going around corners.

Also the minimal velocity in the recorded measurement data is 0.29 km/h. Therefore the braking behaviour below this threshold can not be analysed.

The inaccuracies in the measured velocity also influence the computed acceleration. The acceleration that has been computed by time-discrete differentiation from the measured velocity is only an estimate and not the real acceleration during recording.

In chapter 4 (D3) a moving averaging filter has been used to smoothen the data and reduce the measurement noise.

## 7 D6: Implementation of pulse signal in Simulink

In D6 a pulsing information signal is described. This chapter documents the implementation of that signal. Both signals are needed for the frequency computation. The pulsing signal should only be present if the nonzero velocity of the car is  $\leq 1$  m/s and the position of the car is between 1 and 2 meters. From a frequency of 1 Hz at 1 meter it should rise up to 9 Hz at 1.9 meters. If the traveled distance is greater than 1.9 meters, the signal should become continuous.

This requirement can be divided into two separate components with separate responsibilities.

In the first component it is determined in which state the signal is (off, pulsing, continuous) and in the case of a pulsing signal the frequency of that pulse is computed.

The second component is responsible for outputting the pulse signal corresponding to the output of the first component.

The components are implemented using simulink subsystems which enables re-usability, encapsulation and also creates a better overview when looking at the main simulink model.

### 7.1 Computation of pulse signal frequency

Figure 7.1 shows the simulink subsystem for the computation of the frequency of the pulse signal. The inputs are the velocity and position of the car. The if-condition determines in which state the signal is.

In the first case the nonzero car velocity is  $\leq 1$  m/s and the position of the car is  $> 1.9$  meters. In this case, the pulsing signal should provide a continuous output as demanded by requirement D6. The subsystem outputs a value of 10 in that case. This value is the indication for a continuous signal.

In the second case of the if condition the nonzero car velocity is also  $\leq 1$  m/s but the position of the car is between 1 and 1.9 meters. In this case the frequency of the pulsing signal should be between 1 and 9 Hz depending on the location. For that a lookup table is used, that provides an output frequency that linearly increases from 1 to 9 Hz depending on the position from 1 to 1.9 meters. A linear increase is used, because then the driver

could estimate the position linearly by the signal.

When none of the above mentioned conditions are the case, the subsystem outputs 0, which indicates that the pulsing signal is not present.

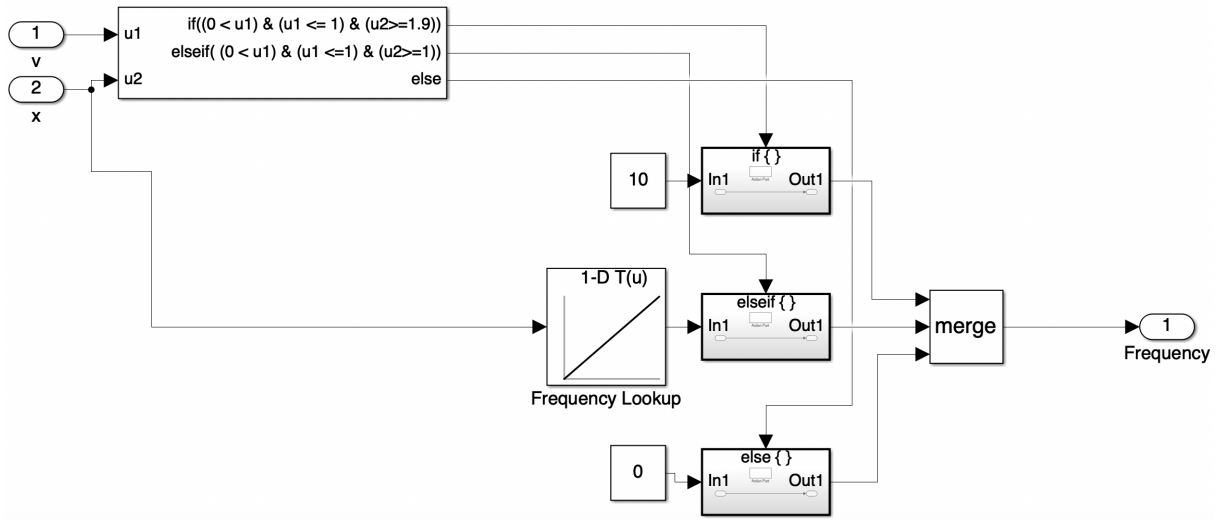


Figure 7.1: Simulink model of the frequency computation subsystem

## 7.2 Pulse signal generation

Figure 7.2 shows the simulink model of the pulse signal generator. This component provides a pulse signal with a variable frequency input. The input is the output of the before described component. Therefore if the input is 10, a continuous signal should be output. This is realised by the if-condition, which, if the input signal is 10 provides a continuous high output.

If the frequency is 0, 0 should be output.

If that is not the case either the pulse signal is generated. The frequency is the input to the integrator. The integrator has a reset input port and will be reset after each period. For each period the output of integrator will start at 0 and will go up to 1. Until the output reaches 0.5 a high pulse will be output (50 % duty cycle). This is the purpose of the less or equal 0.5 check. If the output of the integrator is greater than 0.5 a low pulse is output.



1.4 seconds the frequency goes back to zero, which indicates no pulse. The fourth subplot shows the output pulse signal. It starts when the frequency rises from zero, and the period of the pulses gets shorter with the time increasing. When the frequency starts to indicate a continuous pulse (from approximately 1.25 s) the pulse signal outputs a continuous high signal until the car comes to a stop. When the car stops, the continuous pulse stops and no pulse is output.

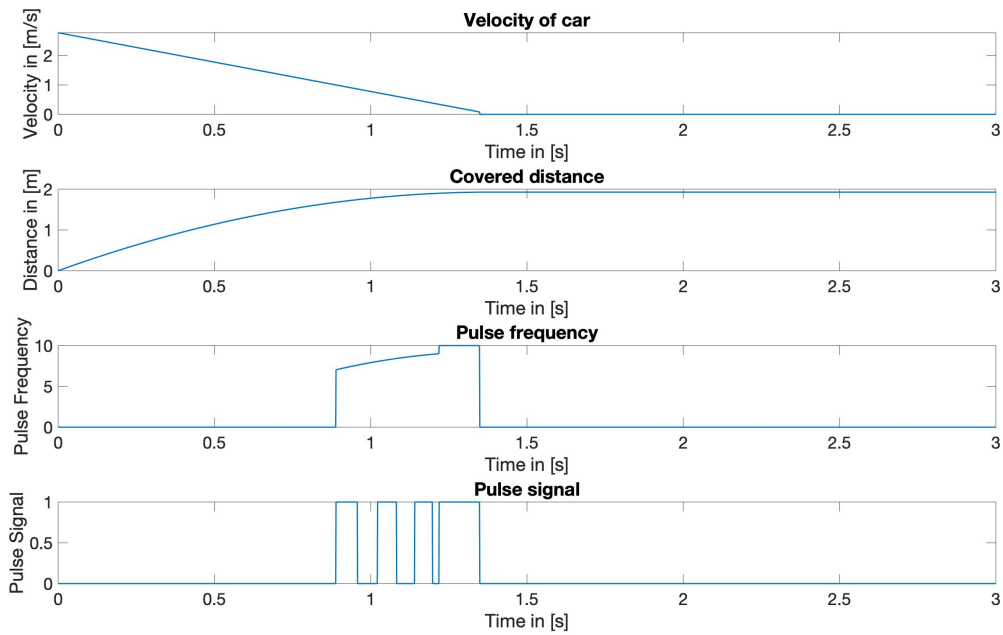


Figure 7.4: Demonstration of pulse signal

## 8 D7: Transfer of Simulink model to ASCET

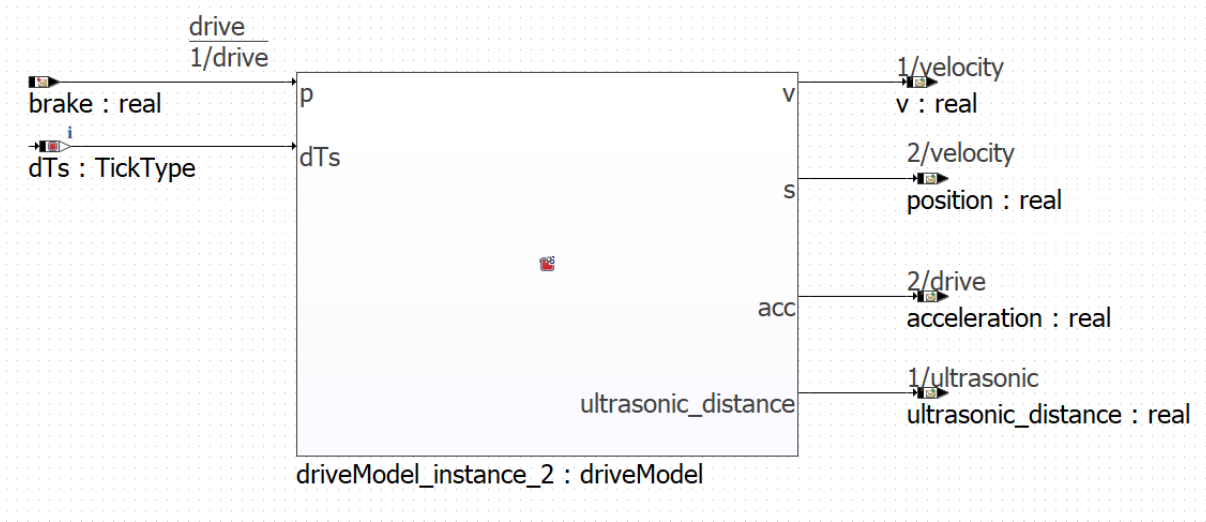
This chapter describes how the Simulink model from section 4.6 is transferred to ASCET (and the ultrasonic distance is added). Furthermore, as ASCET is time discrete execution slots for threads are defined.

First, messages are defined to describe the needed data interfaces. Listing 8.1 shows the two defined message interfaces. The first interface represents messages regarding the car including its velocity, its acceleration, its position, the ultrasonic distance and the pulse signal. The other interface contains a message that describes the current brake pedal position.

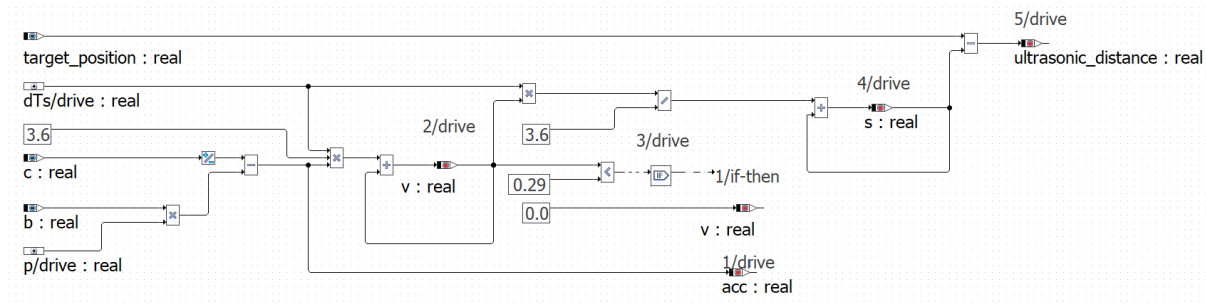
```
1 data interface CarMessages {
2     real v = 0.0;
3     real acceleration = 0.0;
4     real position = 0.0;
5     real ultrasonic_distance = 0.0;
6     real pulse_signal = 0.0;
7 }
8
9 data interface ParkAssistMessages {
10     real brake = 0.0;
11 }
```

Listing 8.1: Defined messages in ASCET

The car model is built using the static class *Car* whose block diagram is shown in Figure 8.1. The class consists of three thread functions: *drive*, *velocity* and *ultrasonic*. The *drive* function reads the brake pedal message and passes it together with a time constant to an instance of the *DriveModel* class (shown in Figure 8.2). Consequently, the function writes the acceleration message based on the *DriveModel* class output. The *velocity* function writes the v message and the position message. The *ultrasonic* function writes the ultrasonic\_distance message. The functionality of the *Car* class is split in three thread functions because of the given requirements demand the ultrasonic\_distance to be available every 2ms and the velocity to be available every 10ms. The implemented functions can be called individually in the specified time intervals.

Figure 8.1: ASCET block diagram of static class *Car*

The *DriveModel* class is responsible for calculating the acceleration, velocity and position of the car as well as the ultrasonic distance. These calculations are based on the input brake pedal position. The block diagram of the class is shown in Figure 8.2. Similar to the Simulink model, the acceleration is calculated by multiplying brake pedal position and the braking constant and subtracting it from the negative friction constant. The velocity is calculated by integrating the acceleration. Unlike Simulink ASCET is time-discrete, so acceleration, time constant and the factor 3.6 to convert the acceleration from [m/s] to [km/h] are multiplied to compute the velocity change. The product is then added to the previous velocity. The default velocity is set to 10 km/h due to the requirements (as default value in the *v* variable). If the velocity is less than 0.29 km/h it is set to zero based on requirement R5. The position is obtained by multiplying velocity and time constant and dividing it by 3.6 to get the position in meters and not in kilometres. The product is then also being added to the previous position whose default value is zero. The ultrasonic distance is gained by subtracting target position (2m) and position.

Figure 8.2: ASCET block diagram of class *DriveModel*

The static class *ParkAssistController* (see Figure 8.3) is implemented for generating the brake pedal position. Based on the elapsed time since starting the experiment, the class

uses an instance of the class *ParkAssistControllerClass* to generate the brake pedal position and writes the brake pedal message afterwards.

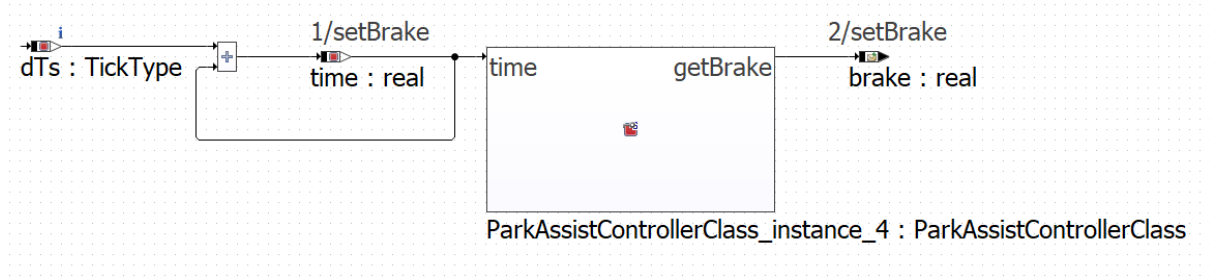


Figure 8.3: ASCET block diagram of static class *ParkAssistController*

The brake pedal position is determined based on a look-up table that represents the brake pedal function described in section 4.6. After determining the brake pedal position, the position is returned. The class *ParkAssistControllerClass* is implemented as a non static class in order to unit test the class. The block diagram of the class is shown in Figure 8.4.

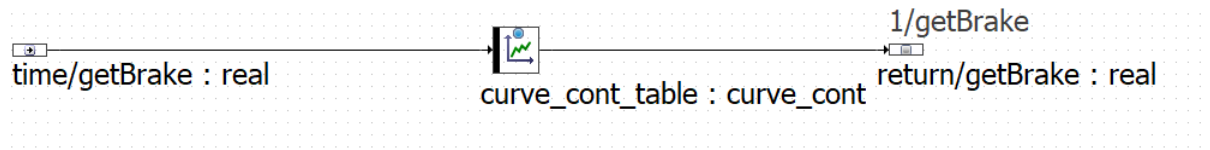


Figure 8.4: ASCET block diagram of class *ParkAssistControllerClass*

The brake pedal position look-up table is shown in Listing 8.2.

```
1 characteristic curve_cont curve_cont_table = {{0.0, 0.2, 0.4, 0.6, 0.8, 1.0, 1.2}, {0.0,
0.043, 0.073, 0.078, 0.073, 0.043, 0.0}};
```

Listing 8.2: Braking pressure look up table

In order to execute the experiment, it is necessary to define the scheduling. As can be seen in Figure 8.5, the experiment is divided in two tasks, one being executed every 2ms and the other task being executed every 10ms. As defined in requirement R4, the ultrasonic distance message is computed every 2ms. Alongside this, the ParkAssistController adjusts the brake pedal position and the pulse signal is computed also every 2ms for a higher precision. The velocity however is generated every 10ms as described in requirement R5. Furthermore, the check for the *SystemTestEnvironment* (see chapter 11) is executed every 10ms as this is precise enough for the check because mainly the end result is of interest.



Schedule				
Execution Slots	Prio...	Period	Delay	Scheduling
Startup				
Task1	0	2ms	0ms	FULL
car.ParkAssistController.setBrake				
car.FrequencyComputation.computePuls				
car.car.drive				
car.car.ultrasonic				
Task0	0	10ms	0ms	FULL
car.car.drive				
car.car.velocity				
test.SystemTestEnvironment.calc				
Shutdown				

Figure 8.5: Scheduling of ASCET model

The following Figure 8.6 shows the simulation results. The acceleration that can be seen in the upper subplot has the form of a parable as desired. The third subplot shows the covered distance of the car, which is clearly under the 2 m mark.

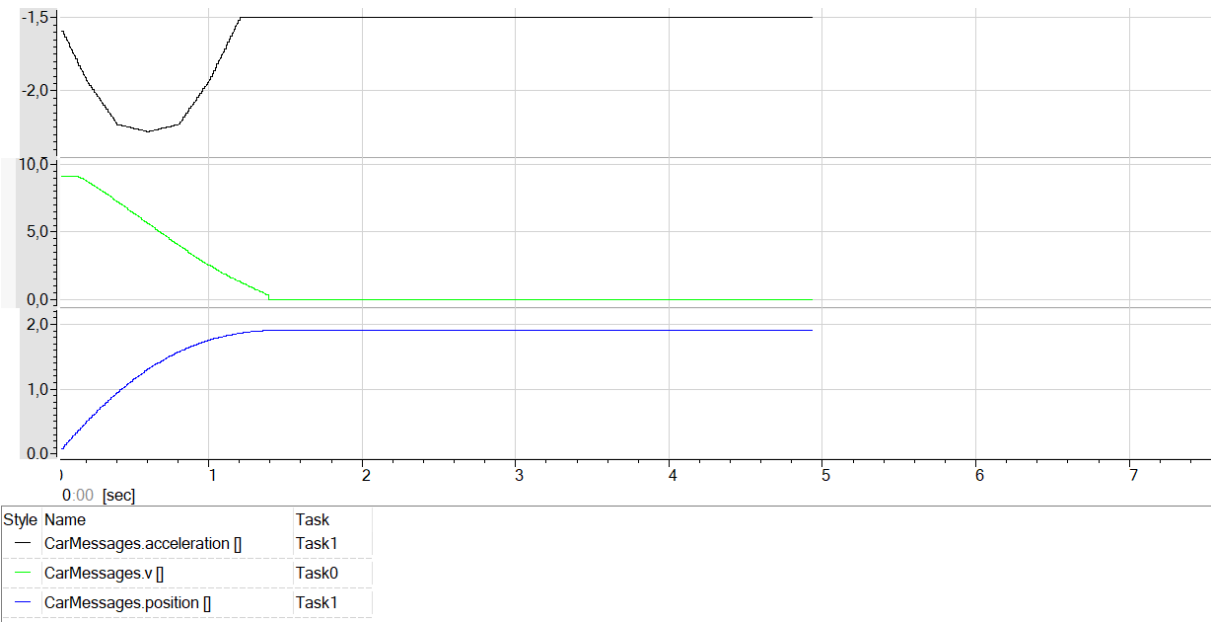


Figure 8.6: ASCET car model

## 9 D8: Implementation of pulse signal in ASCET

The pulse signal that has been implemented in Simulink (see chapter 7) is transferred to ASCET in this chapter. The ASCET model consists of three sub-models described in three block diagrams. Two of the sub-models are regular classes that can be instantiated. This makes the whole model modular and the sub-models are able to be unit tested. One of the two classes calculates a frequency based on a given velocity and position of the car. The second class generates a pulse signal based on the calculated frequency. The third class is a static class that passes the calculated frequency to the pulse signal generating class. The static class is also responsible for receiving the velocity and position messages of the car and pass them to the frequency computation class as well as sending the generated pulse signal as a new message. This can be seen in figure 9.1 that shows the block diagram of the static class.

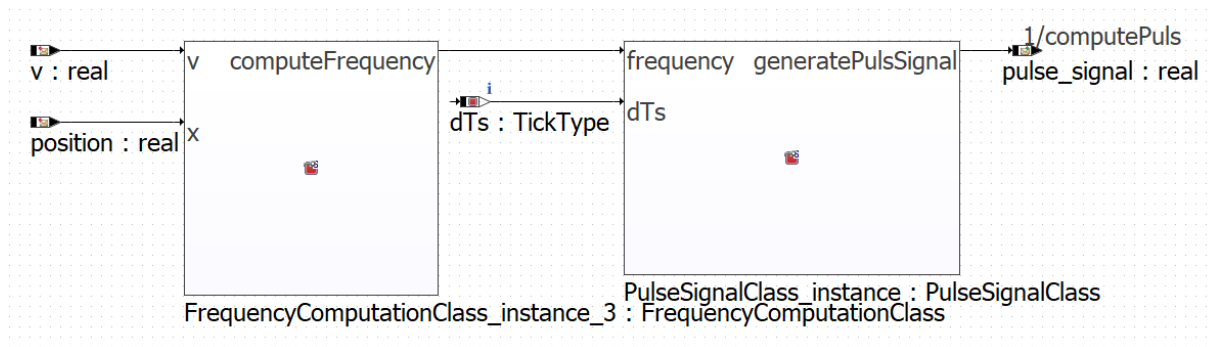


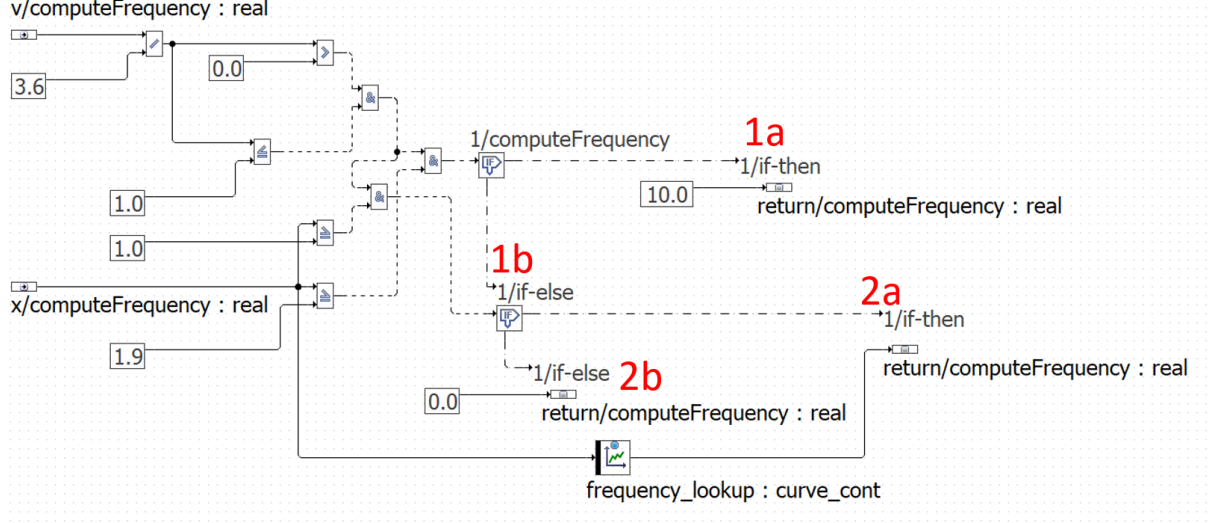
Figure 9.1: ASCET block diagram of static class *FrequencyComputation*

The frequency is calculated based on the Simulink implementation. However, in ASCET if-clauses with multiple conditions need to be implemented in series. The model can be seen in Figure 9.2 and the sequencing process is described in the following:

1. If  $x \geq 1.9m$ ,  $v \leq 1.0$  and  $v > 0.0$  return 10 (**1a** in Figure 9.2)
2. Otherwise (**1b** in Figure 9.2) if  $x \geq 1.0$ ,  $v \leq 1.0$  and  $v > 0.0$  find frequency in lookup table (**2a** in Figure 9.2). The lookup table is shown in Listing 9.1. If none of the conditions haven't been met return 0 (**2b** in Figure 9.2)

```
1 characteristic curve_cont frequency_lookup = {{1.0, 1.9}, {1.0, 9.0}};
```

Listing 9.1: ASCET frequency lookup table


 Figure 9.2: ASCET block diagram of class *FrequencyComputationClass*

After the frequency has been calculated, it is passed to generate the pulse signal. If the frequency equals 10, the desired output is a continuous pulse. This means the pulse is set to 1 (**1a** in Figure 9.3). If however the frequency equals 0, no pulse is desired resulting in the pulse being set to 0 (**2a** in Figure 9.3). If  $0 < frequency < 10$ , the frequency is integrated to generate the pulse signal. For integration a time component is required. To be able to unit test the component, the time component is passed through a method argument. The frequency is integrated by multiplying frequency and time and adding the result to the previous results (**2b** in Figure 9.3). In Simulink it is possible to reset the integration block. Due to this not being possible in ASCET, the integrated frequency is reset as soon as the integrated frequency is greater or equal 1 because then one period is over and the new periodic time can be calculated (**2b** in Figure 9.3). While the integrated frequency is smaller or equal 0.5 the pulse signal is set to 1 (**3a** in Figure 9.3). Once the frequency is greater than 0.5 the pulse signal is set to 0 (**3b** in Figure 9.3). This means the signal is high for one half of a period and low for the other half of a period.

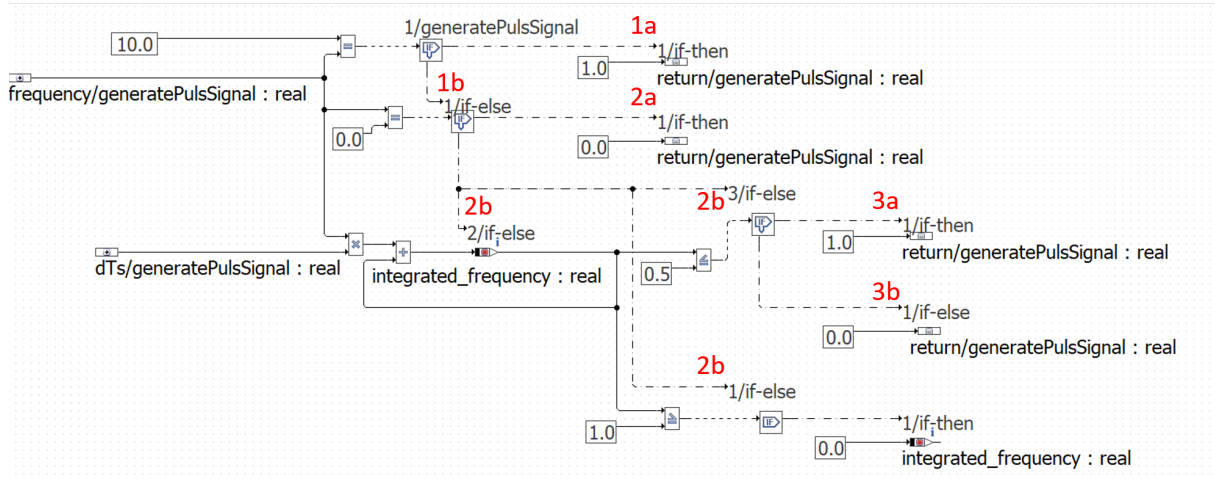


Figure 9.3: ASCET block diagram of class *PulseSignalClass*

The resulting pulse signal is shown in Figure 9.4. It shows that the period of the pulse signal is getting shorter once the car approaches the target position. The plot also shows that the pulse signal starts once the car is slower than 3.6 km/h ( $\hat{=}$  1m/s) and ends once the car is standing. The exact stopping position of the car is 1.905 m which is why the pulse signal becomes continuous for a short time and then gets reset, once the car stops.

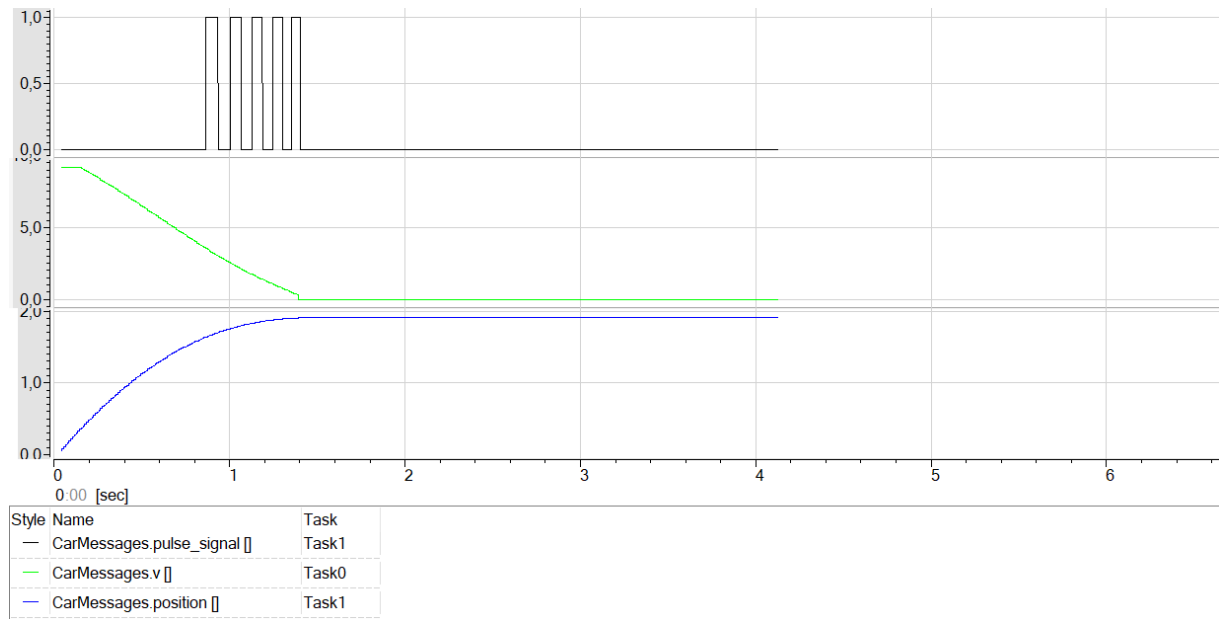


Figure 9.4: Output pulse signal

# 10 D9: Implementation of unit tests for ASCET model parts

This section covers the unit tests of all components of the ASCET model. The components are designed in a modular way to allow easy unit testing. Also wrapper classes, passing messages into the components, are used to make it possible to unit test the components. This is the only functionality the wrapper classes have. That is necessary to make sure that no new bugs are introduced by the wrapper classes, because they can not be unit tested.

The unit tests are bundled in a package called *test* in the ASCET project. The `assertLib` is imported for the assertions that are used in the unit tests. The unit tests are grouped by component with a static test class for each component. One test case corresponds to one method within the unit test classes.

Test cases are derived by analysing the requirements and finding equivalence classes. The goal of the test case coverage is to cover every equivalence class and, in addition to that, select values that might result in errors based on experience.

## 10.1 Unit tests for DriveModel

*DriveModel* computes acceleration, velocity, position and ultrasonic distance based on a defined time and brake pedal position. There are two equivalence classes. One equivalence class covers all velocities greater than 0.29 km/h and the other all velocities less or equal 0.29 km/h. As only one time step is simulated while unit testing the position will remain zero if the computed velocity is zero. Defined test cases can be seen in the table below.

Table 10.1: Test cases for unit testing driveModel

Brake pedal	Time constant [s]	Acceleration [m/s]	Velocity [km/h]	Position [m]	Ultrasonic distance [m]
p = 0.0	dTs = 1.0	acc = -1.5	v = 4.6	s $\approx$ 1.278	u $\approx$ 0.722
p = 0.5	dTs = 0.1	acc = -6.5	v = 7.66	s $\approx$ 0.213	u $\approx$ 1.787

## 10.2 Unit tests ParkAssistControllerTest

*ParkAssistControllClass* generates a brake pedal position based on a defined time using a look-up table. There are two equivalence classes defined for the *ParkAssistControllClass* that cover the brake pedal position if the time is inside the time span of the look-up table and if the time is greater than the time span of the look-up table.

Table 10.2: Equivalence classes for unit testing ParkAssistControll

Time [s]	Output $p(t)$
$0 \leq t \leq 1.2$	$0 \leq p(t) \leq 0.078$
$t > 1.2$	$p(t) = 0$

Based on the equivalence classes three test cases have been derived. Two test cases correspond to the first equivalence class and the third test case corresponds to the second equivalence class.

Table 10.3: Unit test test cases pulse signal frequency generation

Test case name	Time [s]	Expected brake pedal value
time_0_0	0.0	0.0
time_0_6	0.6	0.078
time_2_0	2.0	0.0

## 10.3 Unit tests FrequencyComputationTest

*FrequencyComputationClass* generates a frequency based on a defined position and velocity using a look-up table. There are three equivalence classes defined for the *FrequencyComputationClass* class that cover three output scenarios: zero frequency, variable frequency based on a defined function (computed from look-up table) and continuous frequency.

Table 10.4: Equivalence classes for unit testing pulse signal frequency generation

Position	Velocity	Output
irrelevant	$v = 0\text{m/s}$ or $v > 1\text{m/s}$	Zero
$1\text{ m} \leq s \leq 1.9\text{ m}$	$0\text{ m/s} < v \leq 1\text{ m/s}$	$f(s) = -7.889\text{ Hz} + 8.889 * s\text{ Hz}$
$1.9\text{ m} < s \leq 2\text{ m}$	$0\text{ m/s} < v \leq 1\text{ m/s}$	Continuous (10)

Table 10.5 shows the test cases derived from the equivalence classes above.

Table 10.5: Unit test test cases pulse signal frequency generation

Test case name	Velocity [m/s]	Position [m]	Expected frequency
continuousPulse	0.5	1.91	10
noFrequencyBecauseVelocityHigh	1.5	1	1
noFrequencyBecauseVelocityZero	0	1.8	0
noFrequencyBecausePosition	0.9	0.9	0
noFrequencyBecauseVelocityAndPosition	1.1	0.9	0
frequencyLow	1.0	1.0	1
frequencyHigh	1.0	1.9	9
frequencyMid	1.0	1.5	$5.44 < \text{result} < 5.45$

## 10.4 Unit tests PulseSignalClass

*PulseSignalClass* generates a pulse signal based on a defined frequency. There are three equivalence classes defined for the *PulseSignalClass* class that refer to the equivalence classes in section 10.3. The table below shows the equivalence classes for the pulse signal.

Table 10.6: Equivalence classes for unit testing pulse signal

Position	Velocity	Pulse Signal
irrelevant	$V = 0\text{m/s}$ oder $V > 1\text{m/s}$	Zero
$1\text{m} \leq X \leq 1.9\text{m}$	$0\text{m/s} < V \leq 1\text{m/s}$	Alternating 0,1
$1.9\text{m} < X \leq 2\text{m}$	$0\text{m/s} < V \leq 1\text{m/s}$	Continuous

The derived test cases are shown below.

Table 10.7: Pulse signal test cases

Frequency	dt	Expected result
0	1	0
1	0.1	1
1	0.6	0
10	1	1

# 11 D10: Development and implementation of a system test environment for ASCET simulation

The system test environment in Figure 11.1 features an oscilloscope and several textboxes. The oscilloscope shows the velocity, acceleration and position of the car as well as the ultrasonic distance signal and the pulse signal. The textboxes show the value of the signal in the oscilloscope next to them. The checkbox at the right bottom shows whether the car did a full brake within less than 2m.

With the parameters that have been evaluated in this project, the car stops at 1.905 m.



Figure 11.1: ASCET Experiment Environment

For monitoring whether the car stopped within 2 m, a new class is introduced that is shown in Figure 11.2. As can be seen in the block diagram, the class consists of a simple check whether the velocity is zero and the position less than 2 m.



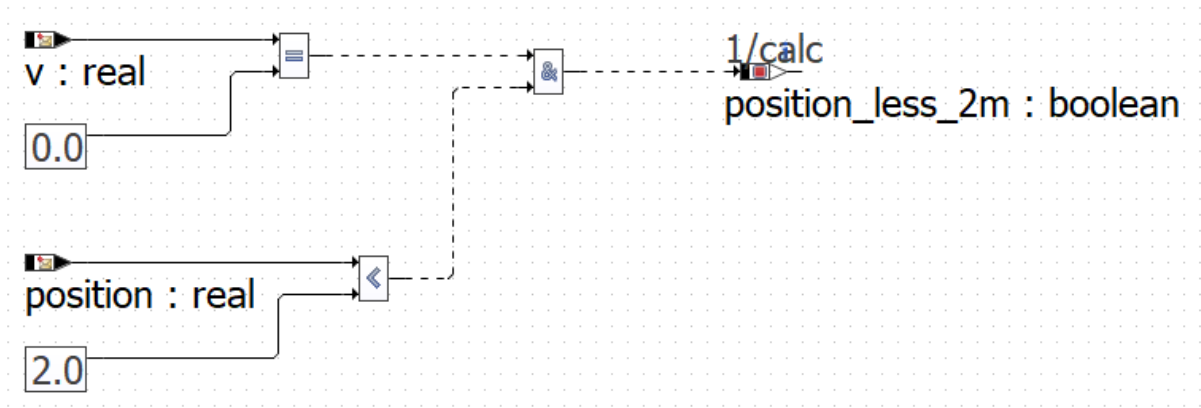


Figure 11.2: ASCET block diagram of *SystemTestEnvironment*

## 12 D11\*: Plausibility check comparing measured velocities and distances

The distance signal from the ultrasonic sensor (in case there is a non-moving object in front of it) and the measured car velocity are two measurements that provide independent measurement of travelled distance.

In the given scenario it is known that a non-moving object is 2 m in front of the car. So the ultrasonic sensor can be used to compute travelled distance by comparing consequent distance measurements. E. g. if the distance measurement before was 0.8 m to the object ahead and the next measurement was 0.6 m, the car travelled a distance of 20 cm.

Integrating the velocity also provides a measurement of the travelled distance. These two measurements provide a redundancy in measuring travelled distance. If these measurements would be significantly different, one of the measurements must be inaccurate.

Because of inaccuracies in the measurements the two signal are likely to never be exactly the same, so an allowed difference between the signals needs to be defined. If the object in front of the ultrasonic sensor is moving or if there is no object at all, this procedure can not be used.

# 13 D13\*: Impact of inaccuracies

## 13.1 Ultrasonic Sensor

Using one ultrasonic sensor has limits when measuring distance to objects while parking. Several scenarios can be imagined, in which a distance measurement from one ultrasonic sensor does not provide enough information to securely park without causing an accident. The scenario in 13.1 shows the limits of one ultrasound sensor. One ultrasonic sensor in the middle of the front of the car might not be able to detect the two poles. In this case parking based on the information of the ultrasonic sensor might result in an accident. Using multiple ultrasonic distributed over the front of the vehicle might be able to resolve such an issue.

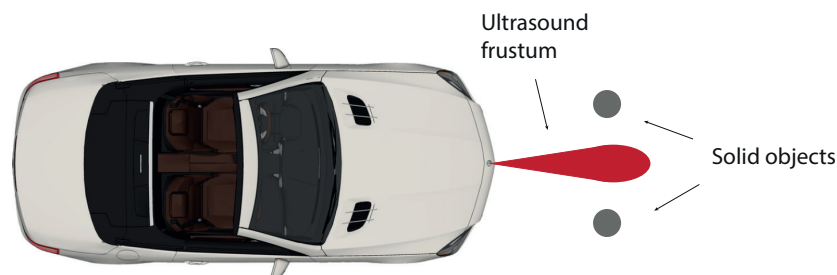


Figure 13.1: Ultrasonic sensor limits 2

With one ultrasonic sensor, also blind spots over and under an ultrasonic sensor can occur. Figure 13.2 demonstrates that. Depending on the used sensor, the sensor frustum might vary, but the concept remains the same. If there is an object above the sensor frustum (for example a gate) it might not be detected by the ultrasonic sensor. Then the driver would have to intervene, because he would probably see the object. But then the driver would be responsible for safe parking, not the ParkAssist.



Figure 13.2: Ultrasonic sensor limits

The inaccuracy of the ultrasonic sensor of  $\pm 2$  cm does not have an influence on the current  $p(t)$ . But if a feedback controller would be used, that relies on the distance information to brake, the inaccuracy would have an influence on the braking procedure. The inaccuracy would have to be considered. Using multiple sensors might be a way to reduce the inaccuracy. Also using a safety margin when parking is reasonable.

## 13.2 Velocity measurement sensor

Inaccuracy in velocity measurement (Requirement R5) have been discussed in section [6.1](#).

## 13.3 Impact of execution timing

This section analyses the impact of the given period times. The vehicle velocity is available every 10 ms and the ultrasonic distance is available every 2 ms. As discussed in chapter 6 the brake pedal function is not dependent on the velocity and neither of the ultrasonic distance. This means that the actual "physical" stopping position is not dependant of the given period times. However, if the velocity was available every 2 ms the velocity curve would look slightly smoother due to more available measurement points. This can be seen in figure 13.3. Even though the "physical" stopping position remains the same, if the velocity is available every 2 ms the computed stopping position is 1.918 m. If the velocity is available every 10 ms the computed stopping position is 1.905 m. These stopping positions differ because the computed position is dependent on the velocity. If the velocity is available every 10 ms, the position is more inaccurate. As can be seen in the Simulink

model in figure 4.7 the computed stopping position in Simulink, using the ode8 differential equation solver, is 1.92 m. The computed stopping position, if the velocity is available every 2 ms, is thus closer to the "physical" stopping position, which makes sense because the position is computed in smaller steps.

Considering only the different execution times and neglecting other inaccuracies, the ultrasonic sensor signal that is available every 2 ms is more accurate than the position based on the velocity that is available every 10 ms.



Figure 13.3: Simulation results with velocity available every 2 ms

# 14 D14\*: Reflection

This chapter consists of a reflection on the project and a description which observations have been made concerning the planning, the modeling, the requirements, the prescribed functions, our solution, the testing and the selected graphical approach.

- The Planning was very helpful and it is interesting to compare the expected complexity and the actual complexity of the tasks. Overall, we are satisfied with our estimation of the complexity. The only thing we underestimated significantly was the generation of the pulse signal.
- The model is not completely realistic. There is no possibility to accelerate and a drop from 0.29 km/h to 0 km/h is also unrealistic. The model could also be extended to include objects at variable distances so that it would be necessary to include the ultrasonic distance in the controller.
- Requirements D5 and D13 overlap and it was difficult for us to separate them. Moreover, we were not sure if in requirement D3 the brake pedal function should already be determined or if only an idea for the function should be described.
- The prescribed functions/values made the implementation easier. It would have been more complicated if for example stops from various initial velocities or within various distances would have had to be considered. The friction and braking constant are comparatively high so that without accelerating it was not possible to get an entirely smooth velocity drop.
- The developed brake pedal function in our solution is only dependant on the time, therefore external conditions are not recognised. If, for example a person would step in front of the car, the car would run over that person, even though the ultrasonic sensor might recognise the person. To prevent that the distance from the ultrasonic sensor would have to be included in the ParkAssist controller. In the future, it would be better to implement a controller with feedback for the applied braking pressure.
- Unit tests were easy to implement and very helpful. This way, bug that have been included along the development could be detected quickly.
- Graphical modeling worked out well for us. The only disadvantage that we experienced was that if-clauses can be complex to implement graphically, in particular

if there are various if-clauses in series. Having many if-clauses may also lead to an unclear block diagram.