Criticality of Communications for Road Vehicle Automation

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A bit of history for context...

- National Automated
 Highway Systems
 Consortium Demo '97
 (August 1997, San Diego)
- 8 cars, automatic steering and spacing control (5.5 m), lane changing, switching positions
- Demo rides for a thousand visitors
- Each car driven by one Pentium @ 166 MHz



V2V Communication:

- Utilicom/Hughes spread spectrum radios
- 902-928 MHz
- Slotted ALOHA protocol
- 50 Hz updatę interval

Wireless Communications to Enable Vehicle Automation

- Intermediate developments at PATH:
 - 802.11b WiFi, 20 Hz updates, for merging and truck platooning (2000 - 2003) and cooperative collision warnings (2004-5)
- Current work on cooperative adaptive cruise control and intersection safety applications:
 - 5.9 GHz DSRC, 10 Hz updates (V2V and I2V)
- Requirements driven by safety criticality:
 - Low connection latency
 - High reliability of message receipt
 - Security against attacks or interferen

What are the V2V needs?

- Frequent enough state updates to not impede vehicle dynamic responses (50 – 100 ms)
 - Enough data to represent vehicle motions smoothly and safely for platooning (BSM +)
 - Emergency flags and maneuver commands
- Additional messages:
 - External hazard alerts
 - Negotiating cooperative maneuvers
- Well-suited to 5.9 GHz DSRC



What are the I2V/V2I needs?

• **I2V**:

- Traffic signal status (SPaT) 100 ms period
- Variable speed advisories
- Medium to long-range hazard alerts or traffic condition updates
- Emergency software updates

V2I:

- Traffic and road condition (probe) information
- Signal priority requests



Needed advances

• 5.9 GHz DSRC:

- Prove congestion management in highdensity traffic environment
- Define BSM extensions to support V2V cooperative control/platooning (and gain access to safety channel for them)

5G cellular:

- Show that it can scale to support these applications in high-density traffic
- Show an acceptable cost/business model for vehicle users