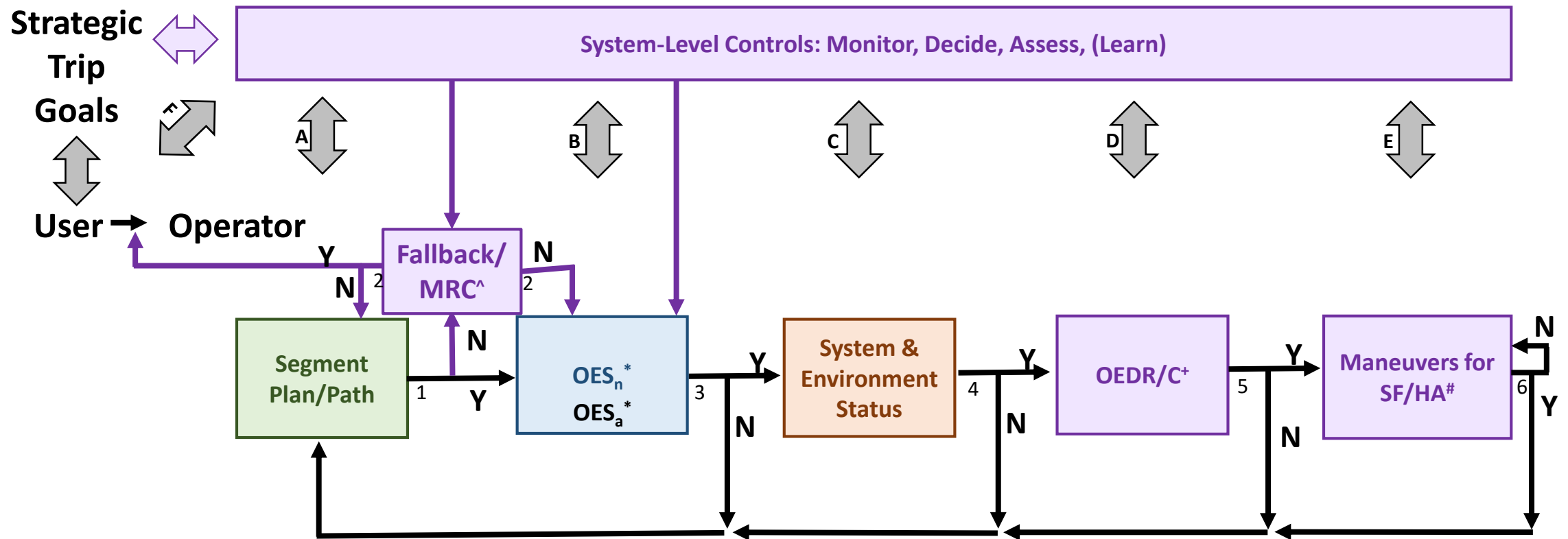


# Automated Driving System (ADS) Assurance

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# ADS Logic Chart



\*OEDR/C: Object and event detection, recognition, and categorization

+OES: Operating Envelope Specification, n= nominal; a=actual

>DDT: Dynamic Execution Task

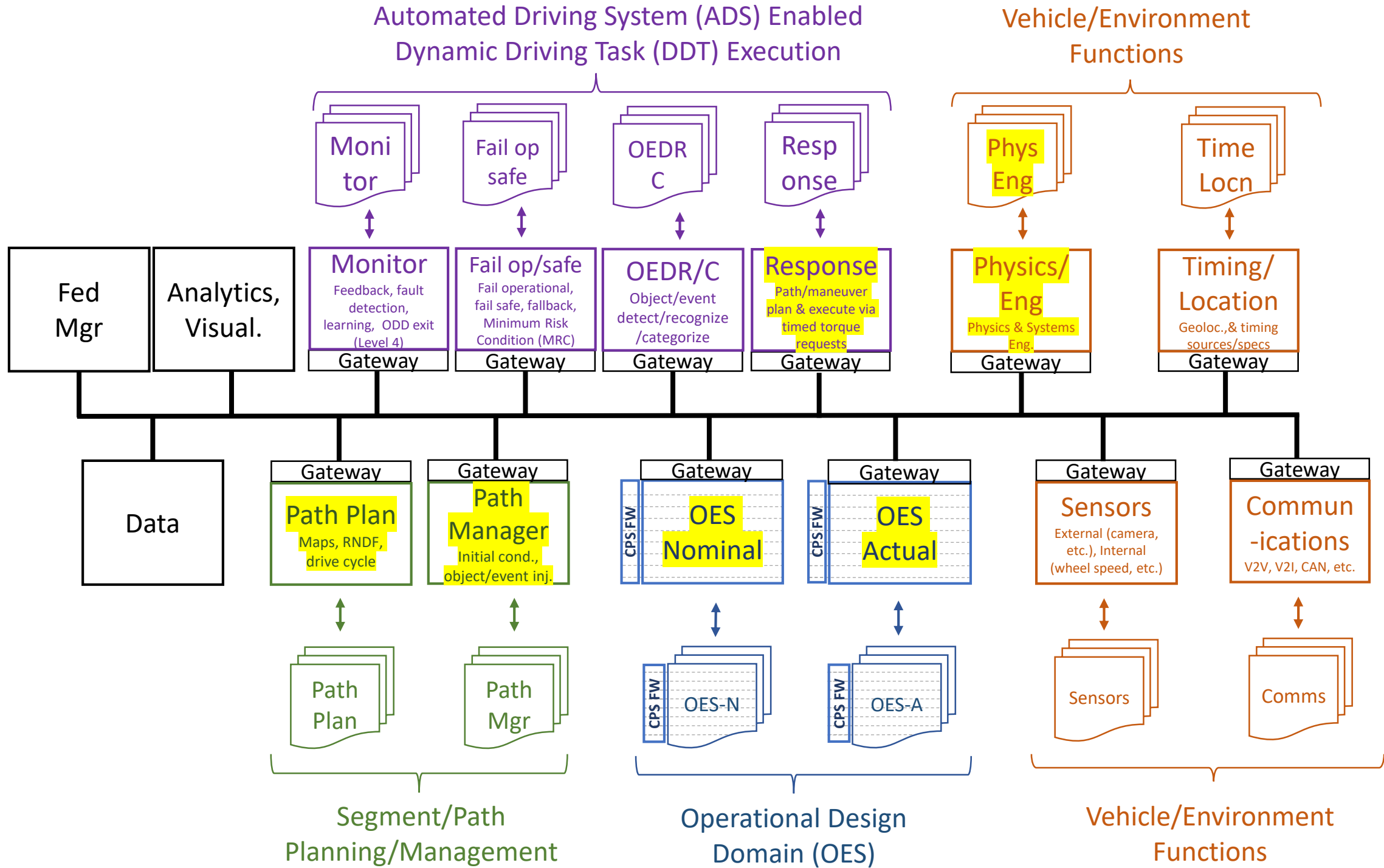
#SF/HA: Segment following/Hazard avoidance

^MRC: Minimal Risk Condition; Fallback/MRC execution via CPS is a minimal segment/path to achieve minimal risk condition

# Decision Gates/Categories

1. Can the segment plan be produced that is feasible and meets the strategic trip goals?
2. Has the user (e.g., passenger, safety driver) responded to request to take over the dynamic driving task (DDT)?
3. Does the segment plan/path conform to all ODD constraints?
4. Is the status of the vehicle (e.g., fault status) and of the environment (e.g. visibility) suitable for the segment plan and ODD?
5. Are all detected objects and events reliably identified and categorized?
6. Is the maneuvering process approaching successful completion of the segment plan?

# Notional Testbed Architecture



# Notional Information Model

