

VIVID – Virtual Validation Tool Chain for Automated and Connected Driving

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16ME0173

Goal

- RCS profiles in real test drives
 - Sensor movement
 - Different vehicles
- Public available data set with calibrated
 - Radar data in different mounting heights
 - Lidar data
 - RTK-GNSS reference data

Road User



3 Compact cars



2 Cabrios



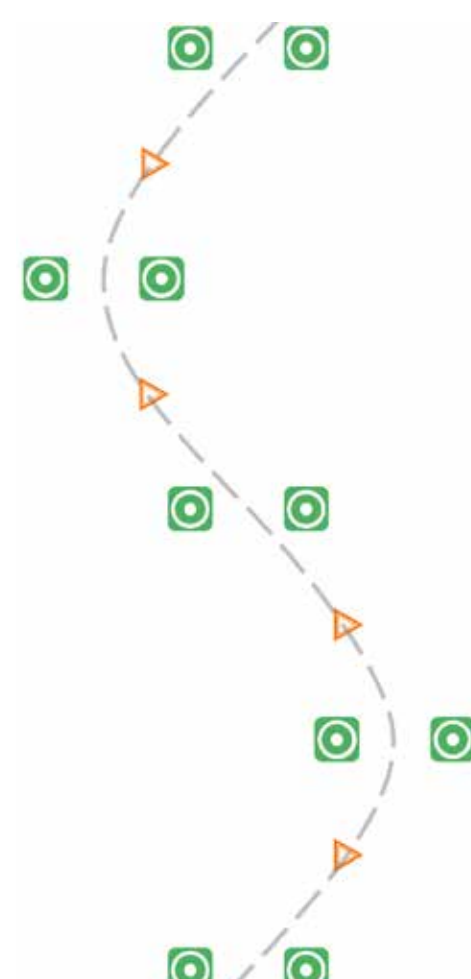
4 Small cars

3 Single track vehicles



4 Utility vehicles

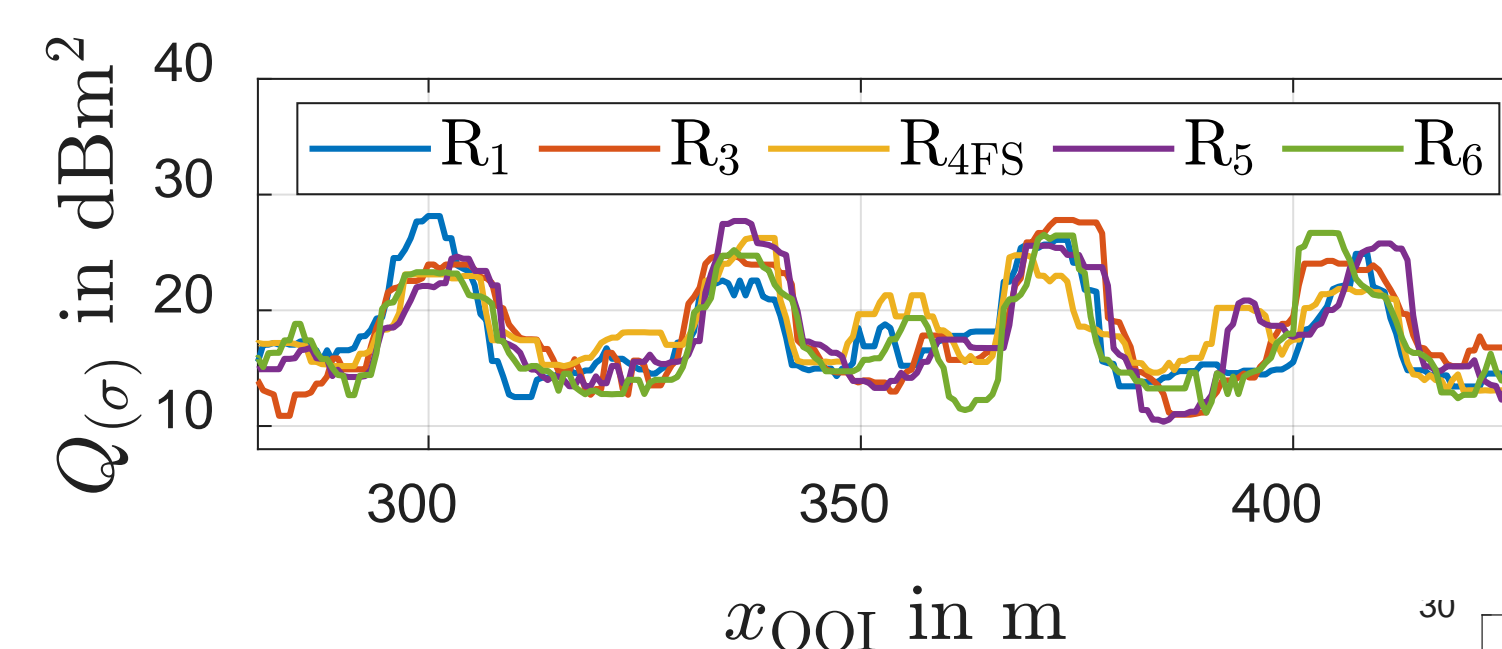
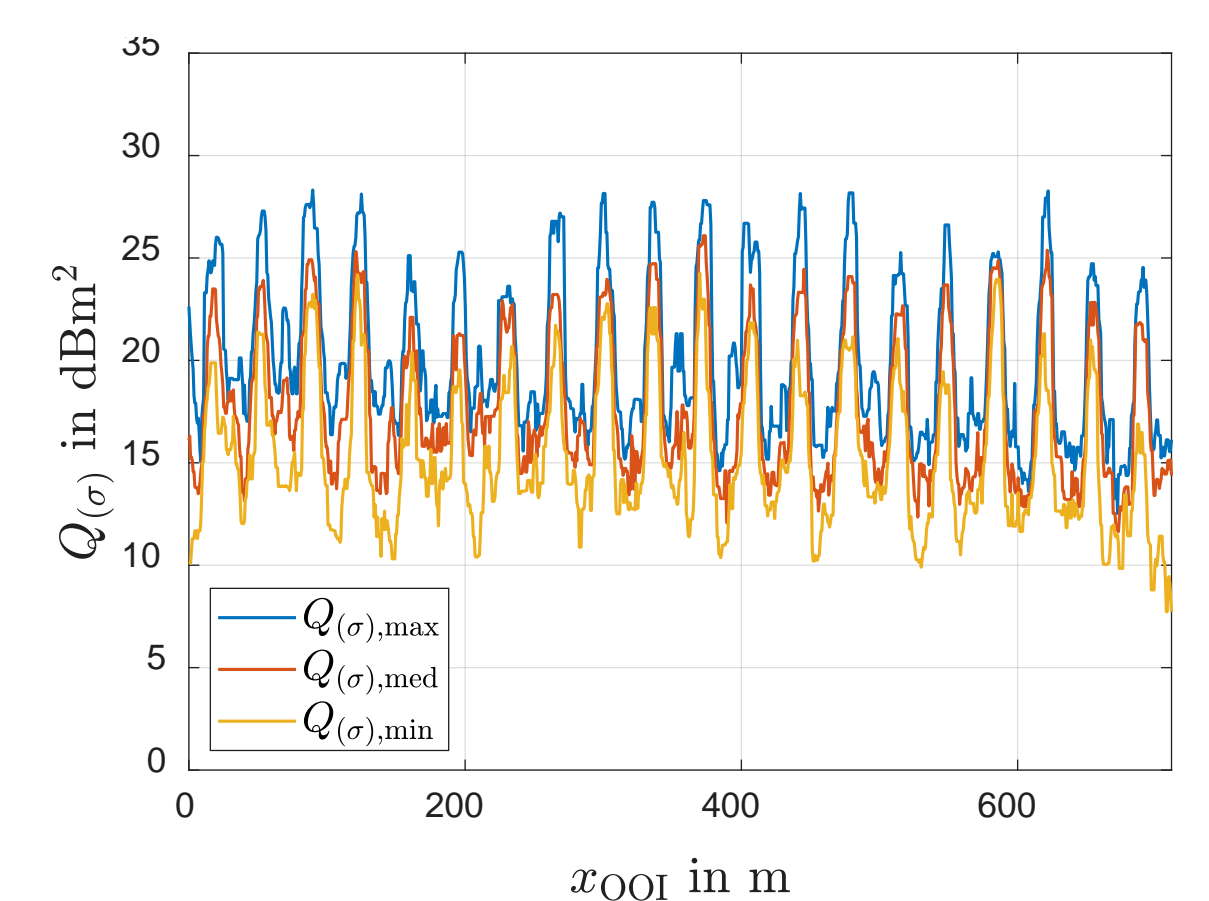
Slalom Setup



- 10 measurements per road user
- Time based measurement synchronization
- Metric based trajectory evaluation
- Varied distance throughout slalom
- Various azimuth and yaw angle combinations

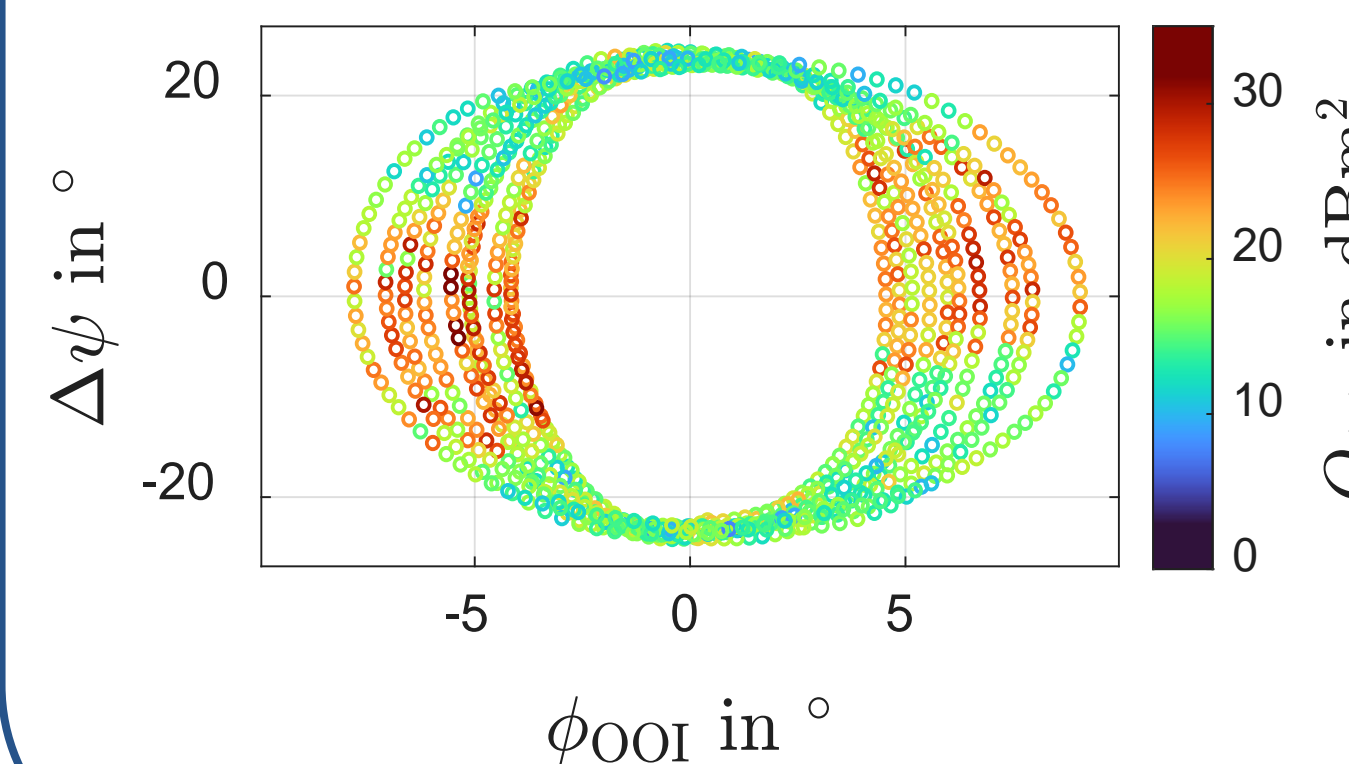
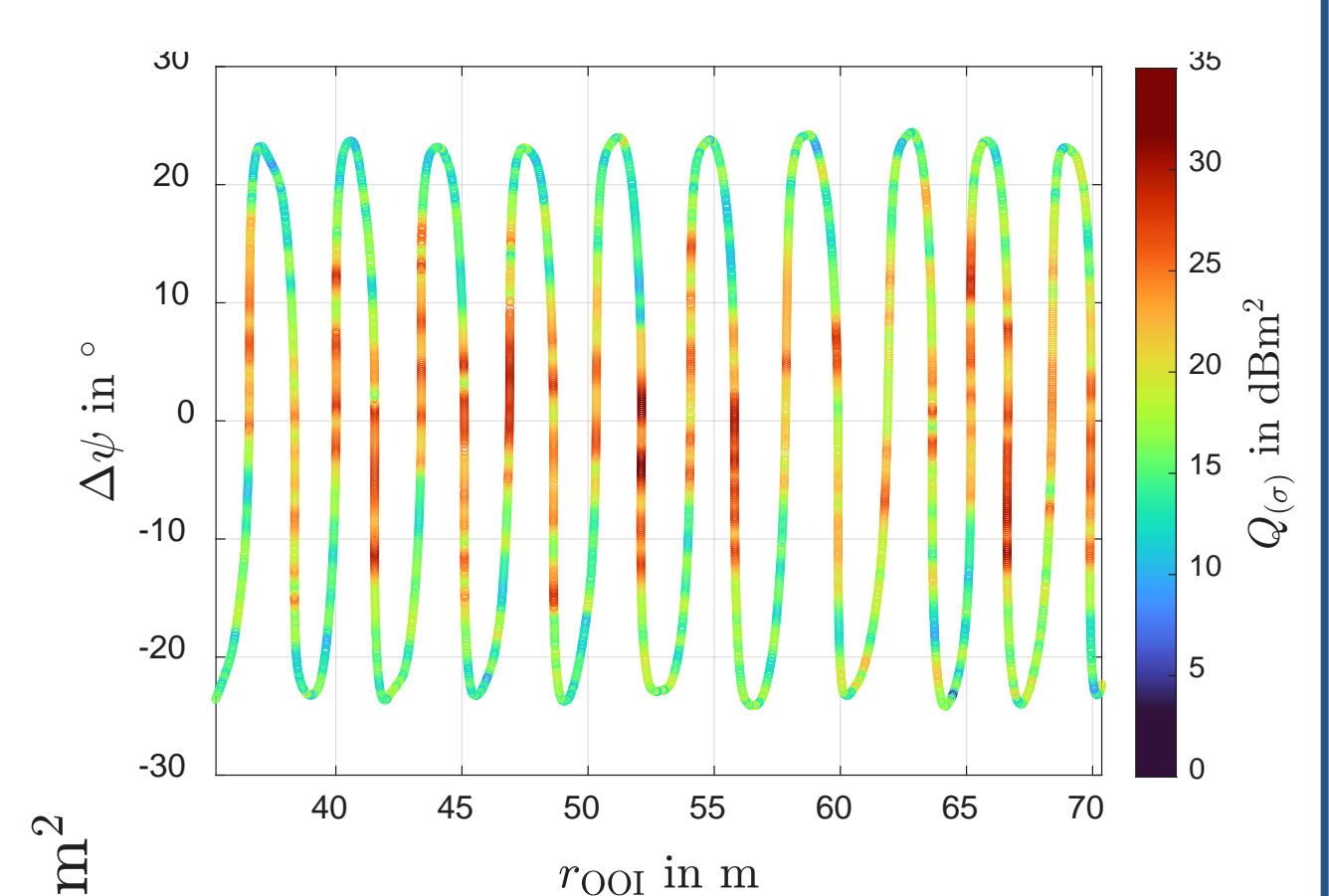
Results

Clear differences between maxima and minima



No influence by mounting position

Distance and RCS independent of each other



Dependence of RCS to aspect angle

Contact Partner

Name: Lukas Elster & Ken Mori
E-Mail: lukas.elster@tu-darmstadt.de
Phone: +49 6151 16 - 24230



TECHNISCHE UNIVERSITÄT DARMSTADT

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