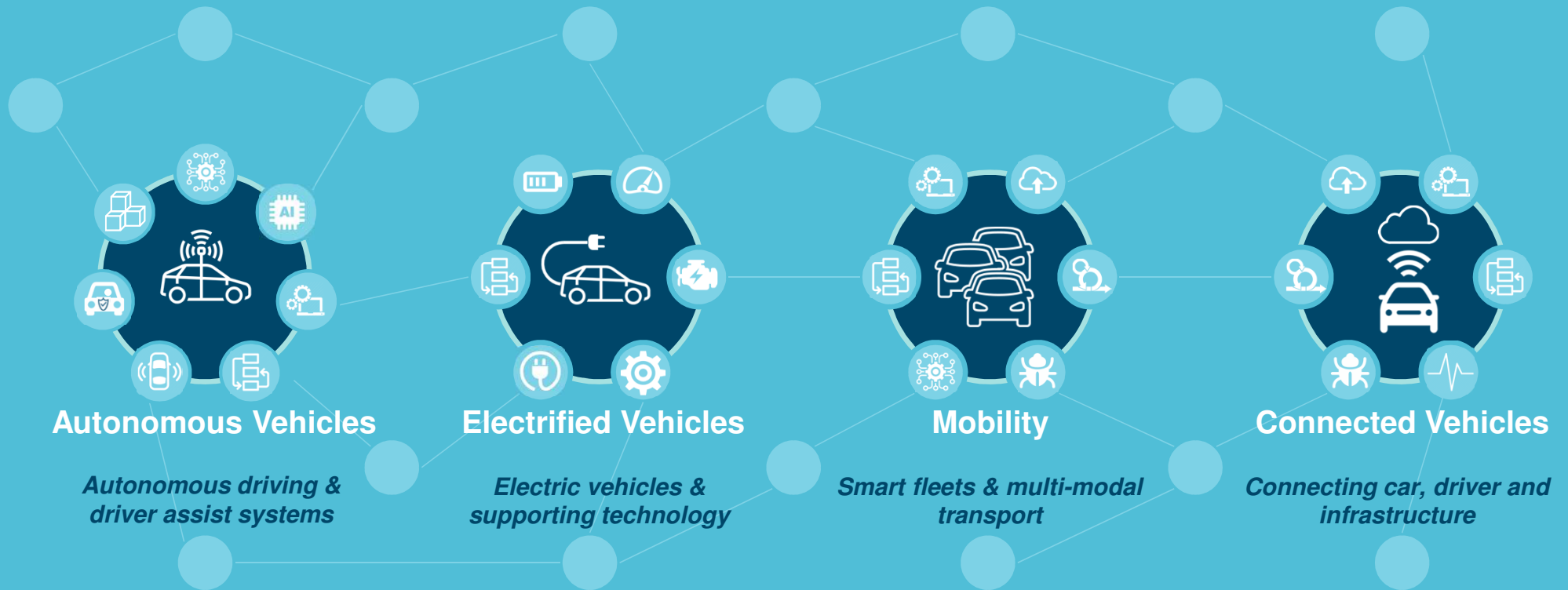


Physics Based Sensor simulation

Jordan Gorrochotegui - Product Manager Software and Services

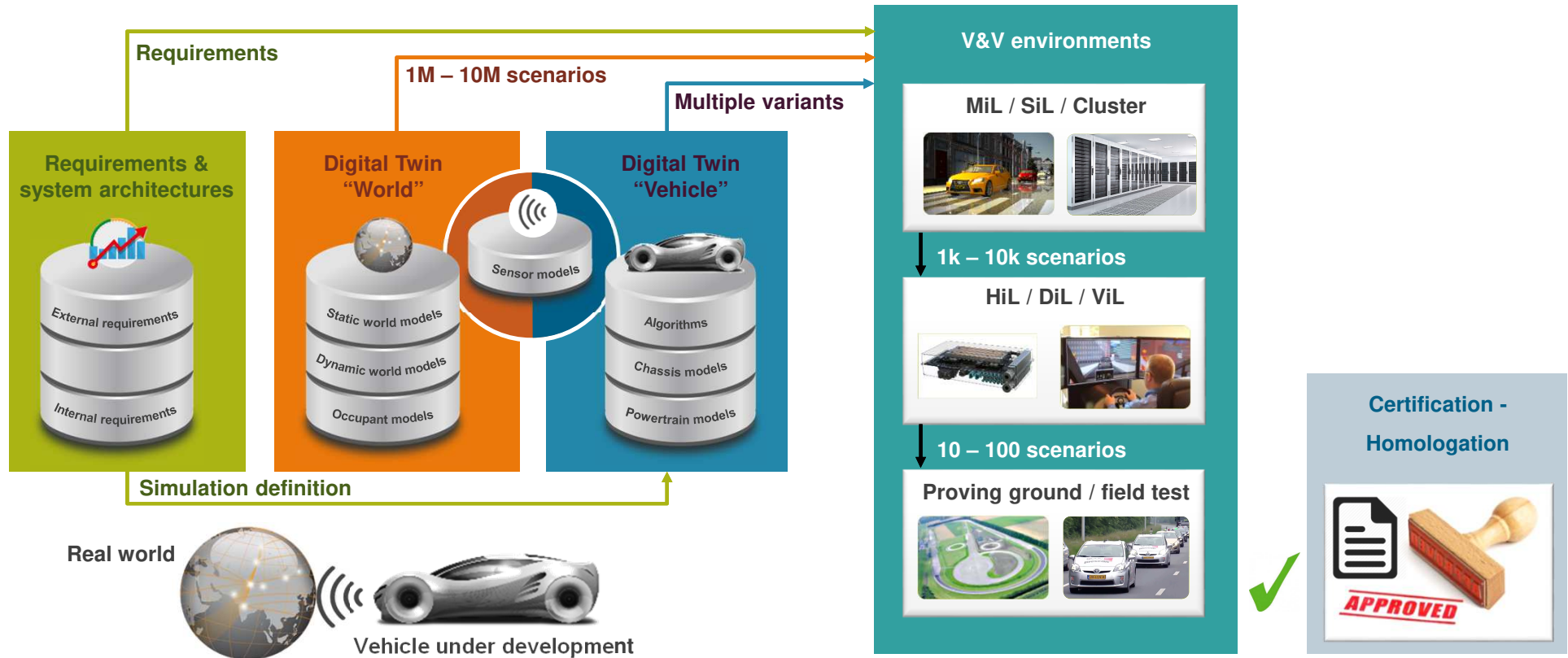
Mike Phillips – Software Engineer

Siemens offers solutions across all automotive mega trends

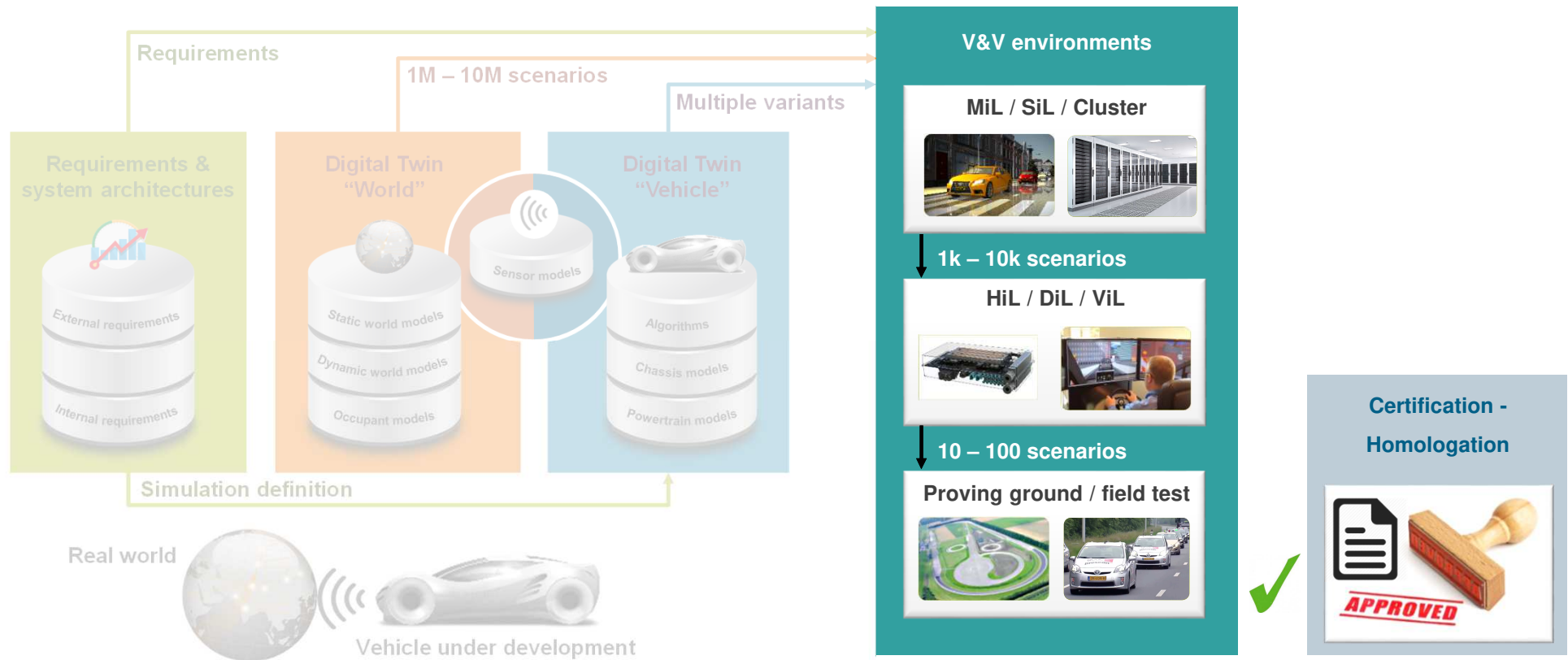


Engineering the **next** product not just the best product for the future

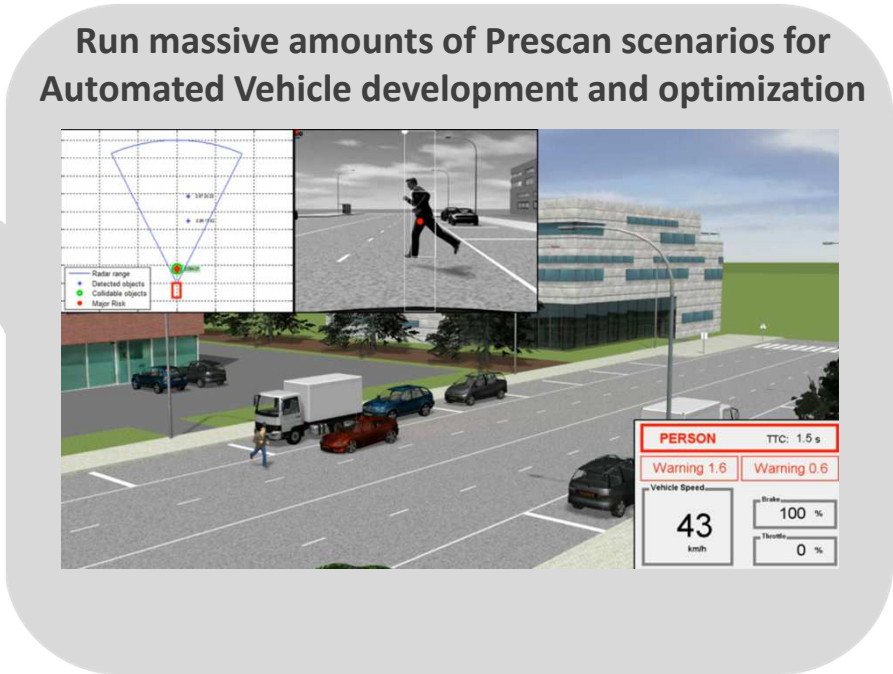
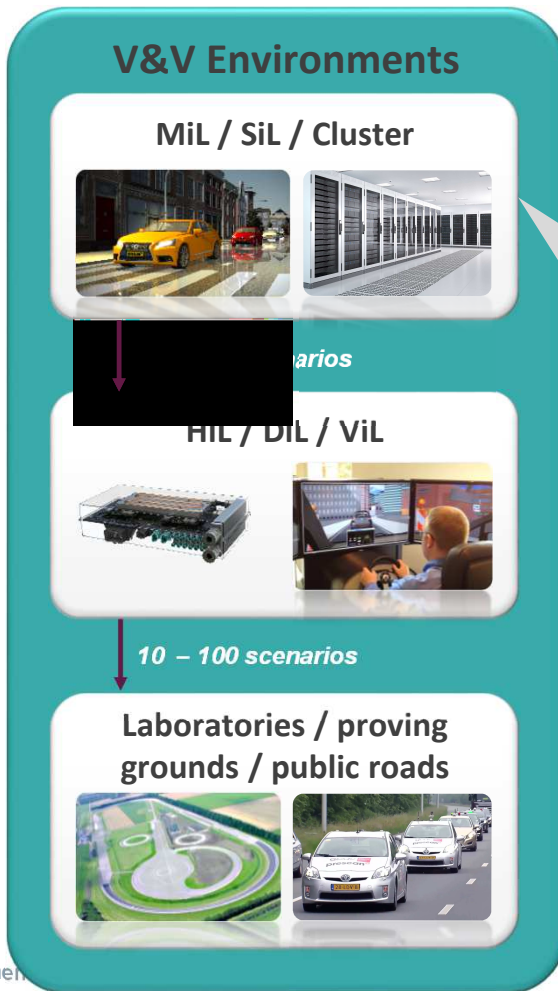
Validation and Verification framework for AVs



Validation and Verification framework for AVs



Example #1: MiL / SiL / Cluster

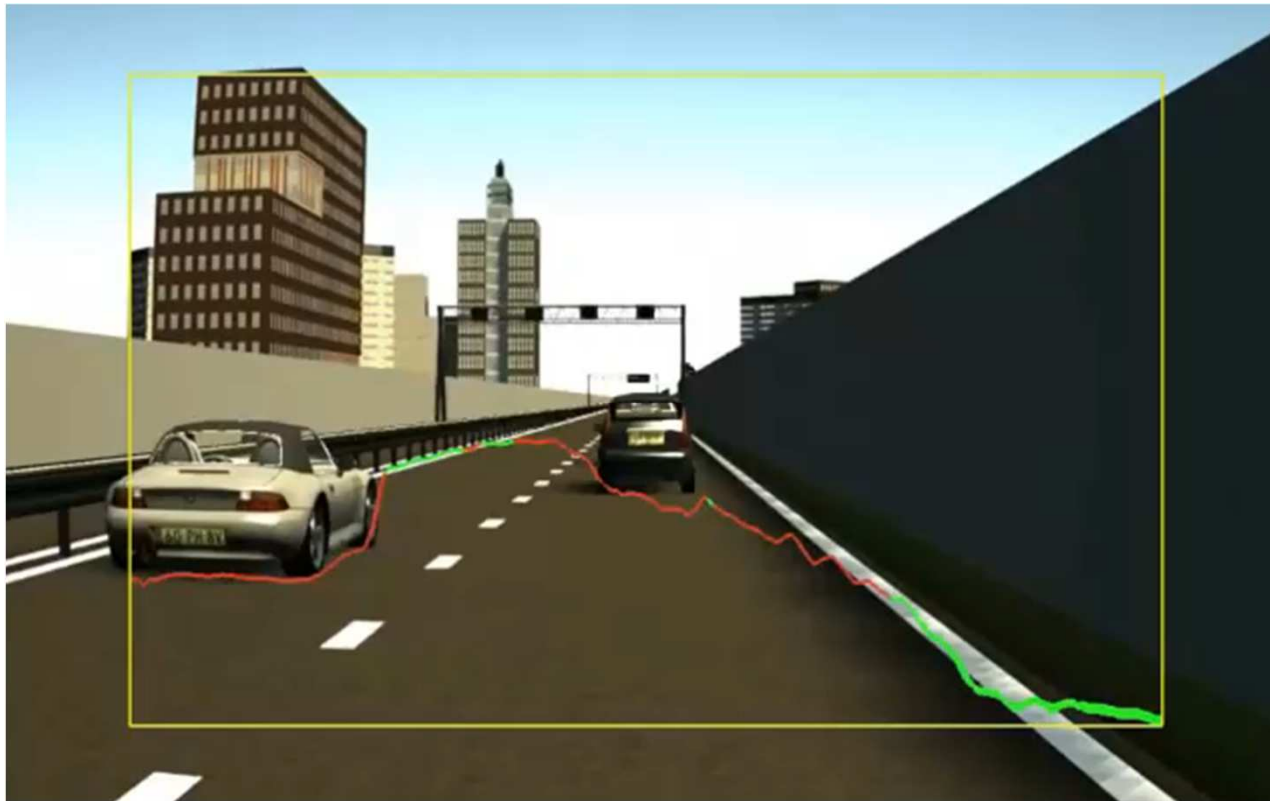


- Design space exploration using large scenario databases
- Virtual development, verification and robustness testing
- Optimized automated vehicle designs

18
18.MM.DD

Example #2: HiL testing of central AD processing unit

SIEMENS
Ingenuity for life

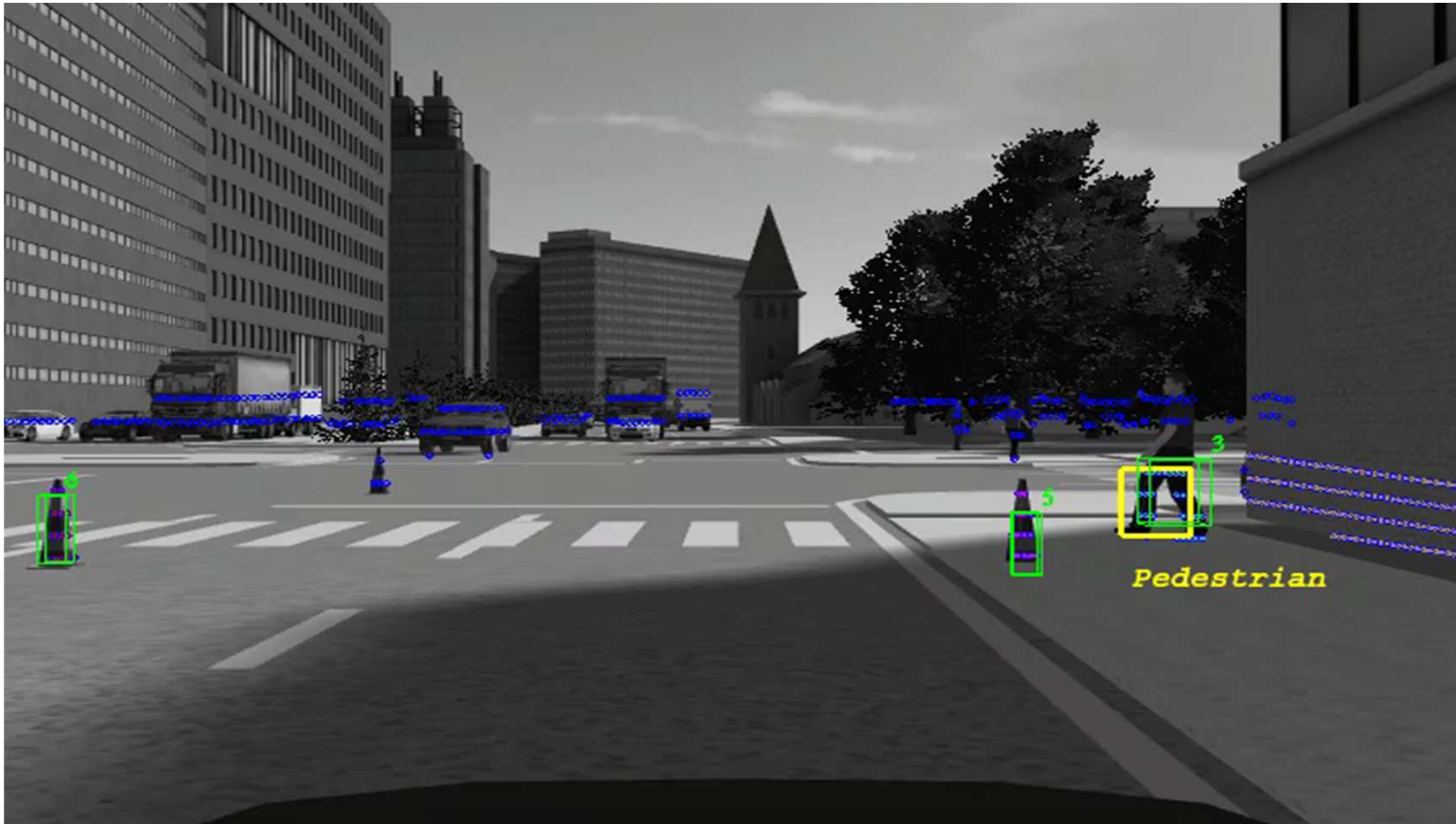


Free space detection on Nvidia Drive PX2



Example #2: HiL testing of central AD processing unit

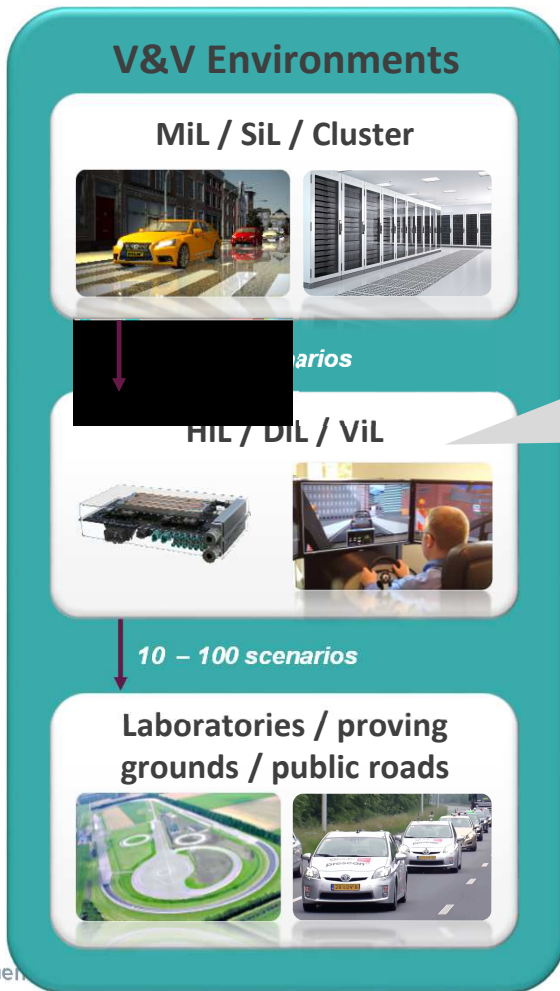
SIEMENS
Ingenuity for life



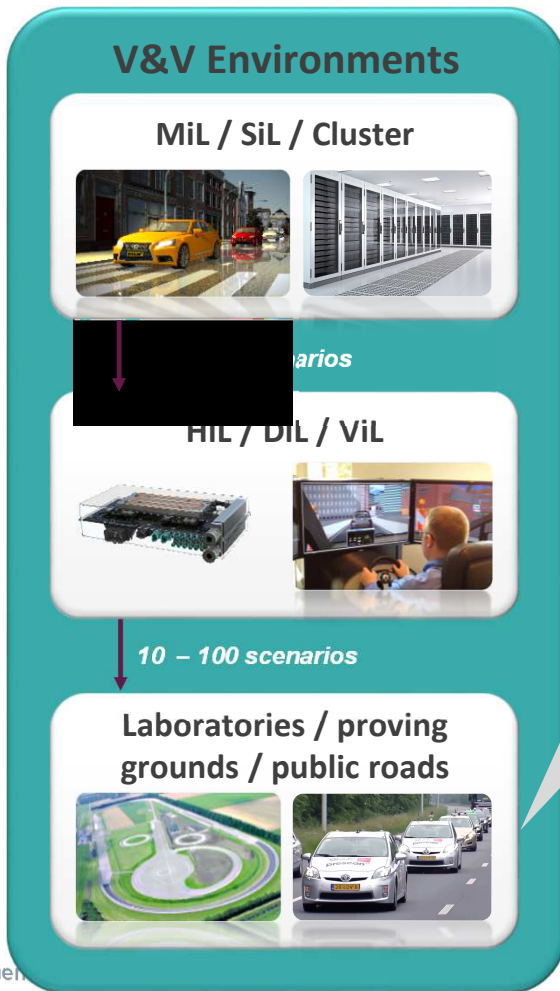
Object detection on Mentor DRS360



PreScan – HIL application examples



Example #3: Automated Driving physical validation



TASS International Services and Siemens Testing Solutions for physical validation of automated and connected driving technology

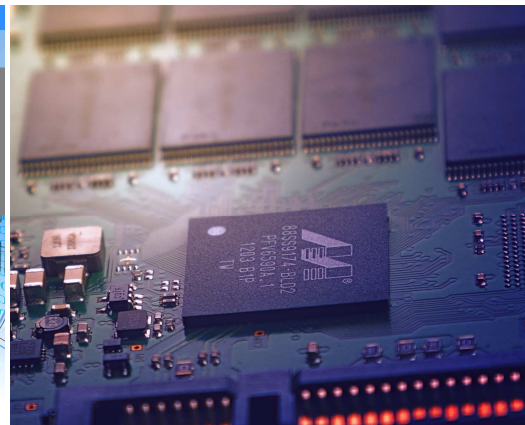
tass international
A Siemens Business

- Physical verification & validation services
- Certification of automated and connected systems
- Design consultancy for “next-generation” AD test facilities

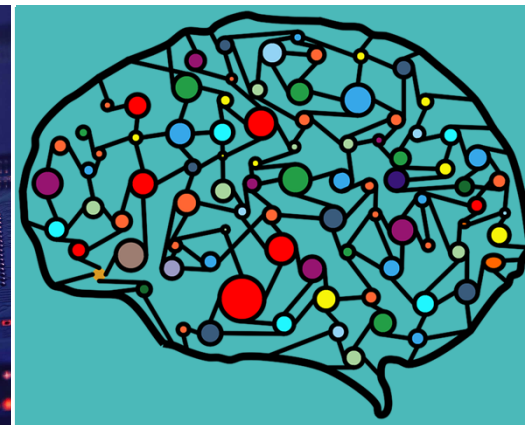
Development of automated vehicles requires realistic sensor data



Algorithm development



Sensor development



DNN Training



Validation

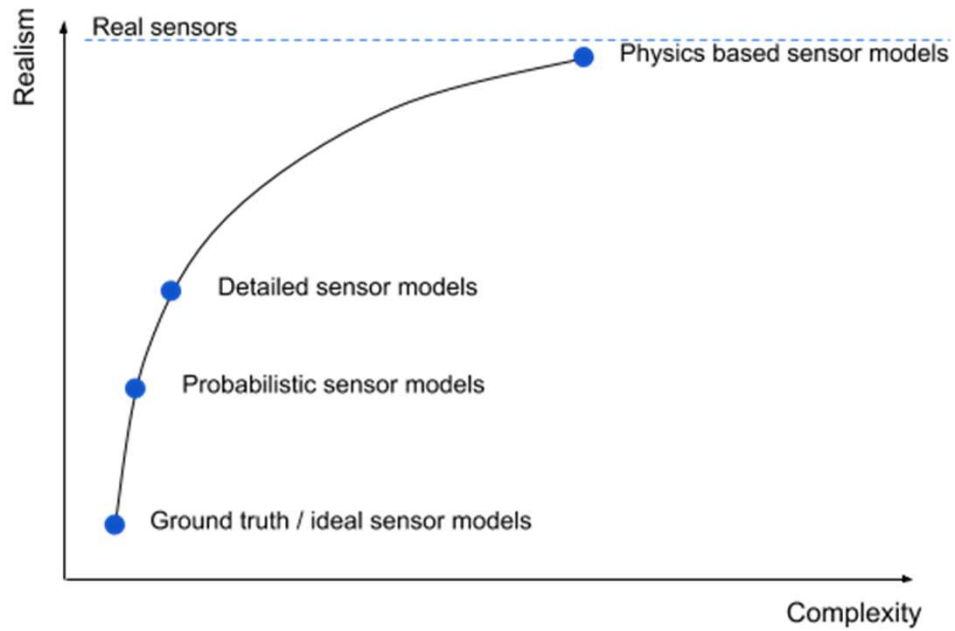
Two sources of sensor data

- + **Real data**
- Expensive
- Time consuming
- Not (easily) repeatable
- Requires a physical sensor
- Must be annotated
- Open loop (recorded)

Recorded

- ? Realistic data
- + **Inexpensive**
- + **Fast to acquire**
- + **Perfect repeatability**
- + **Physical sensor not needed**
- + **Annotation is free**
- + **Can be closed loop**

Simulated



Camera & Ground Truth

Radar & V2X

Lidar & Point Cloud

We use simulation to compute real world effects on actual sensors

Physical artefacts are faithfully reproduced

- Distortions
- Multi-bounce
- Time effects
- Weather
- ...

Raw signal is computed

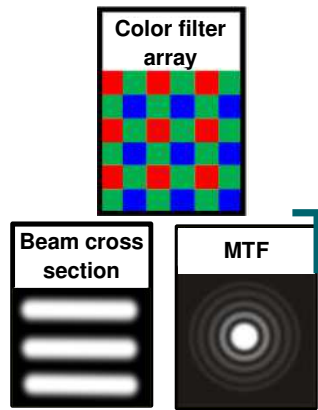
- Lidar full-waveform signal
- Radar channel response
- Raw camera images
- ...

Output verified & validated

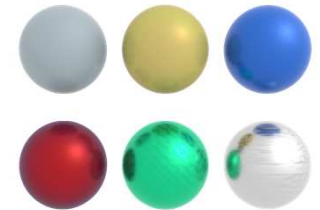
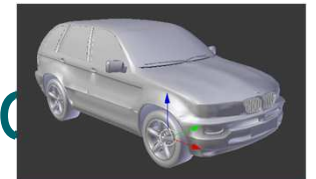
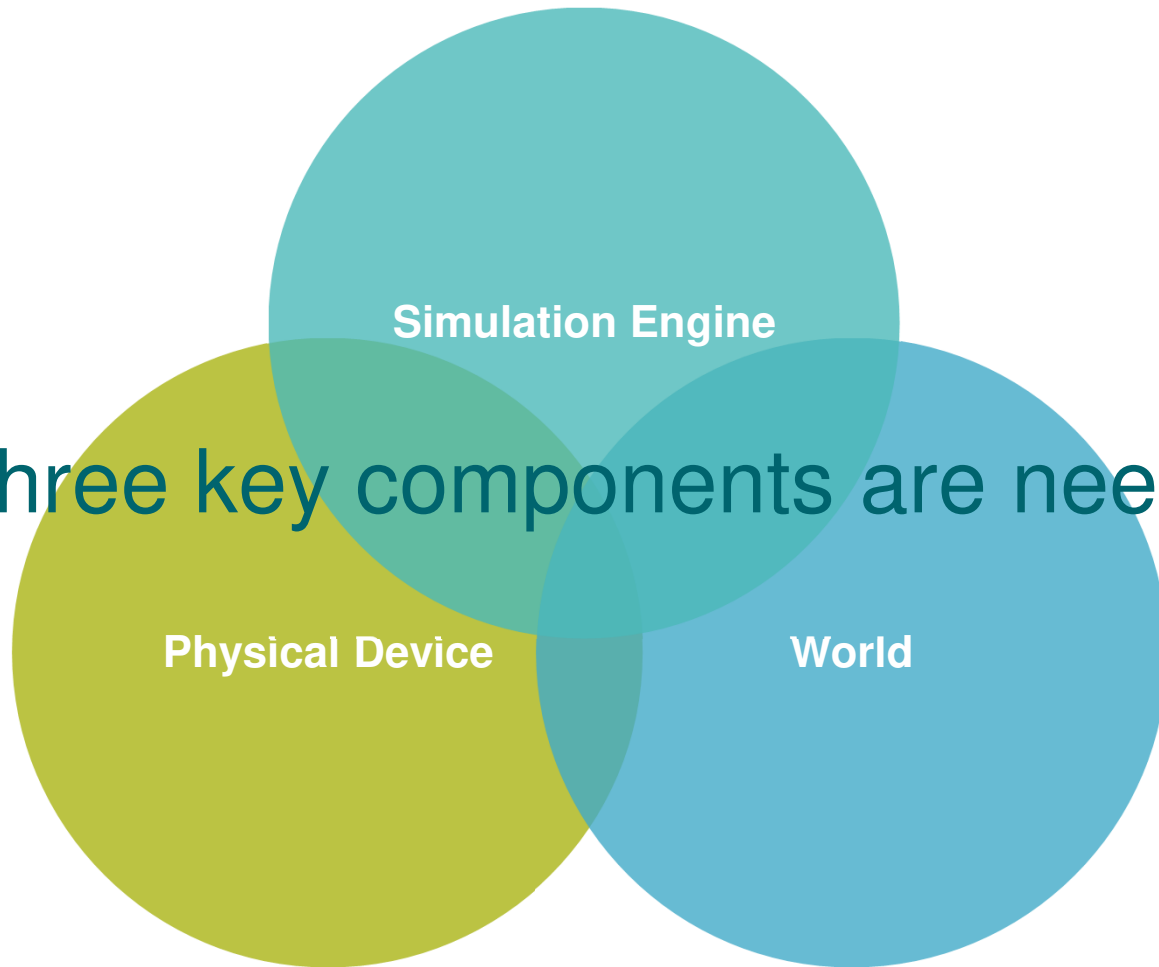
- Verify against real sensors
- Validate for specific use cases

prescan®

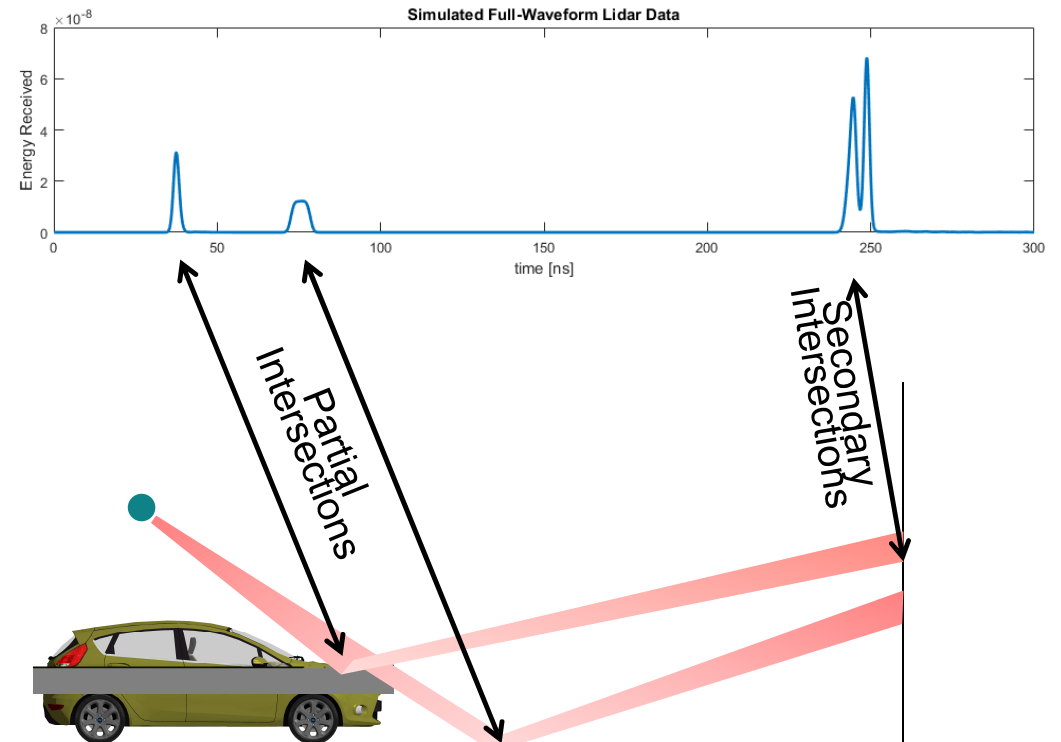
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Three key components are needed



Physics Based Lidar Simulation



Our solutions support autonomous vehicle development needs

Across all engineering domains

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Ensuring digital continuity, multi-domain traceability and functional safety of autonomous systems