

openPASS Steering Committee

Meeting date: 24.10.2019

Location: Skype

Keeper of the minutes: Tuan Duong Quang, TÜV SÜD

Participants:

- Arun Das, BMW
- Manel Hammouda, BMW
- Thomas Platzer, BMW
- Jan Dobberstein, Daimler
- Per Lewerenz, Daimler
- Dr. Daniel Schmidt, Robert Bosch GmbH
- Fabian Gottwald, EDAG on behalf of VW GoA
- Tuan Duong Quang, TÜV SÜD

Topics:

High-Level Targets:

- Add support for pedestrian models: This epic is about the implementation of an interface for pedestrian models. The goal is to integrate a pedestrian model over an interface. There are discussions in SL4to5 whether there should be a standard interface or a general interface for agents. Until now there are now sidewalks and there is no interaction with pedestrians possible. This epic is secondary. Whenever there is more concrete information, we will decide if this epic should be realized within the V1.0.
- Bicycle model: This epic is about the implementation of an interface for bicycle models. Similar the upper epic. General question if there should be an implemented model in openPASS or the integration of a model over an interface. Reusability of this interface for both models possible? Whenever there is more concrete information, we will decide if this epic should be realized within the V1.0.
- Premodeled sensors: There should be already a premodeled sensor in the simulation framework. There is already a geometric 2D sensor (field of view) which is parameterized with an aperture angle and range. This sensor takes also sight coverage into account which can switch on and off. This functions with a 2D shadow. There are disposable sensors from Bosch. Prioritized after V1.0
- Following three epics are correlated
 - Driver models: interaction with traffic infrastructure
 - Extended driver behavior model
 - Modular driver architectureInteraction with the traffic (stop sign, traffic lights, ...) should be possible. Example: Driver recognizes stop sign, driver stops at this sign and continues afterwards. Bosch is working a driver model which recognizes speed limit signs. Structure: algorithm driver consists of submodules from information acquisition about situation deduction and action. Integrate stochastic, misconducting and driver reaction time. Prioritized before V1.0
- Bosch is working on “Deterministic Spawner”
- BMW is working on the epic “Spawn on multiple roads”
- Bosch and Daimler are working on the “crash” epics and on its visualization. Approach through converter.
- VW has presented their targets (see TULEAP) and there are no overlaps to other epics
- GUI epics are basically finished by VW

It is important that for V1.0 the platform is stable. Single models are secondary

To Dos:

- Tuan will write a summary of the targets with separation of targets until V1.0 or V1.0+
- Everybody should give feedback whether the categories from Tuan are reasonable. A category is the collection of epics with the same topic.
- Build requirement teams for each category. Deadline to build the requirement teams is the **07.11.2019** (next AC-meeting)

Meeting minutes can be found here: <https://wiki.eclipse.org/openPASS-WG>