



# ANCAP Assessment Protocol.

Safety Assist v8.0.2

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## PREFACE

During the test preparation, vehicle manufacturers are encouraged to liaise with ANCAP and to observe the way cars are set up for testing. Where a vehicle manufacturer feels that a particular feature should be altered, they should raise this with the ANCAP assessor present at the test, or in writing to the ANCAP Chief Executive Officer if no assessor is present. ANCAP will consider the matter and at their sole discretion and give direction to the test facility.

Vehicle manufacturers warrant not to, whether directly or indirectly, interfere with testing and are forbidden from making changes to any feature that may influence the test, including but not limited to dummy positioning, vehicle setting, laboratory environment etc.

Illustrations in this protocol are reproduced from Euro NCAP publications, and therefore show Euro NCAP markings on left-hand-drive vehicles. Where relevant, the layouts depicted should be adapted to right-hand-drive application.

VERSION	PUBLISHED	DETAILS
8.0.1	July 2017	First version of ANCAP protocol.
8.0.2	November 2017	Added visualisation for AEB Inter-urban and LSS.

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# AUSTRALASIAN NEW CAR ASSESSMENT PROGRAM (ANCAP)

## ASSESSMENT PROTOCOL – SAFETY ASSIST

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## **1 INTRODUCTION**

The following protocol deals with the assessments made in the area of Safety Assist, in particular for the Seat Belt Reminder, Speed Assist Systems, Lane Support Systems and Autonomous Emergency Braking Systems.

## 2 METHOD OF ASSESSMENT

Unlike the assessment of protection offered in the event of a crash, the assessment of Safety Assist functions does not require destructive testing of the vehicle. Assessment of the Safety Assist functions is based both on performance requirements verified by ANCAP.

It is important to note that ANCAP only considers assessment of safety assist systems that meet the fitment requirements for base safety equipment or dual rating (as defined in the Vehicle Specification, Selection, Testing and Re-testing protocol). For the performance assessment of seat belt reminder and speed assistance systems, the car is subjected to a number of trial sequences designed to highlight the effectiveness of the systems. The car performance is scored using the observations made by the inspector during driving. In addition to the basic ANCAP assessment, additional information may be recorded that may be added to the ANCAP assessment in the future.

## 3 SEAT BELT REMINDER ASSESSMENT

### 3.1 General requirements

All seating positions in the vehicle will be assessed including optional and removable seats.

The seatbelt reminder system should "start" at the commencement of each "journey" that the vehicle makes. Short breaks in the journey are allowed, where the reminder system is not required to start again. Such short breaks, of up to 30 seconds, are to allow for events such as stalling of the engine where passengers may remain in the vehicle.

For the purpose of defining the start of the final audible signal, forward motion at less than 10 km/h, or rearward motion, is not deemed to be motion.

#### 3.1.1 Signal

All seatbelt reminder systems shall be audiovisual, where there must be a clear and obvious link between the audible and visual signals. As soon as the audible part of the seatbelt reminder signal starts, the visual signal needs to flash and be synchronised (not necessarily at the same frequency, but an integer multiple of each other, e.g. two flashes with every chime) with the audible part.

Any visual signal must be clearly visible to the driver, without the need for the head to be moved from the normal driving position (e.g. instrument panel, head-up display, rear-view mirror, centre console). Any final audible signal must be "Loud and Clear" for the driver.

#### 3.1.2 Airbag deactivation switch

There must be no link between the front seat passenger airbag and the front seat passenger SBR signals. It is NOT acceptable to ANCAP for the passenger seat SBR to be disabled via the passenger airbag switch.

#### 3.1.3 Occupant detection

In the case of the driver's seat, occupancy can be assumed so the system does not have to be capable of detecting whether or not the seat is in use. For the front seat passengers, seat use must be detected. Systems that feature rear seat occupant detection are eligible for higher scores. ANCAP defines occupancy as use by an occupant larger, taller or heavier than a small female (5<sup>th</sup> percentile).

#### 3.1.4 Secondary buckles

Monitoring of rear seat belt secondary buckles that require a tool to unlock, is not required.

#### 3.1.5 Change of Status

During a change of status (from buckled to unbuckled) at speeds over 25 km/h, the system must immediately deploy the audiovisual signal meeting the requirements of section 3.2 for the front seats and that of section 3.3 for the rear seats.

Where the change of status occurs below 25km/h, and no doors are opened, the signal may be

delayed until before at least one of the below requirements (at the choice of the manufacturer) are met:

- The car has reached a forward speed of 25 km/h, or
- The car has been in "Forward Motion" for 500 meters.

Where the change of status occurs below 25km/h, and doors are opened, the system should consider this situation as a "new journey", and warn accordingly.

Where the system is able to track the number of buckled positions in the rear, no change of status signal (for the rear seats) is required as long as all doors remain closed, and the number of buckled positions remains the same. This is to minimize the number of false positives (ex: children remaining in the vehicle but swapping seats in the rear while at a traffic light).

### 3.1.6 End of signal

Once the audible part of the SBR signal has started, it must only stop under one of the following circumstances.

- The signal has operated for the duration as specified in 3.2.3.
- The related seat belts are put into use. Where the system is able to track the number of buckled positions in the rear, the change of status signal (for the rear seats) can be terminated as long as all doors remain closed, and the number of buckled positions remains the same.
- The vehicle speed is below 10 km/h. When no doors have been opened, and the seatbelts remain unbuckled, the signal must resume again when the vehicle speed goes above 25 km/h.

## 3.2 Front seating positions

### 3.2.1 Visual signal

A visual signal must be activated when the ignition switch is engaged (engine running or not) and the seatbelt is not fastened, and in case of a change of status as defined in 3.1.5. This signal must remain until the seatbelt is fastened and recommence once a seatbelt is unfastened.

### 3.2.2 Initial Audible Signal

An Initial Audible Signal needs to be deployed before at least one of the following (at the choice of the manufacturer):

- The car has reached a forward speed of 25 km/h, or
- The engine has been running for 60 seconds, or
- The car has been in "Forward Motion" for 500 meters.

The duration of the initial audible signal can have a maximum duration of 30 seconds and must start with a positive audiovisual signal (not a gap). There must be no gaps greater than 10 seconds.

### 3.2.3 Final Audible Signal

A Final Audible Signal (Loud and Clear) is to be deployed before at least one of the following (at the choice of the manufacturer):

- The car has reached a forward speed of 40 km/h, or
- The engine has been running for 90 seconds, or
- The car has been in "Forward Motion" for 90 seconds, or
- The car has been in "Forward Motion" for 1000 meters, or
- The Initial Audible Signal (lasting maximum 30 seconds) is finished.

The duration of the final audible signal must be at least 90 seconds not counting gaps exceeding 3 seconds and must start with a positive audible signal (not a gap). There must be no gaps greater than 10 seconds.

NOTE: The manufacturer has the option to utilize the Initial Audible Signal as the Final Audible Signal, as long as it is "Loud and Clear", and the duration is at least 90 seconds not counting gaps exceeding 3 seconds and must start with a positive audible signal (not a gap). There must be no gaps greater than 10 seconds.

## 3.3 Rear seating positions

### 3.3.1 Visual signal

3.3.1.1 A visual signal must be activated when the ignition switch is engaged (engine running or not), and any of the rear seatbelts are not fastened. No signal is required if the system is able to determine that there are no occupants in the rear seating positions. The signal must remain for at least 60 seconds or until the rear belts are buckled for the seats in use.

The system may allow the driver to acknowledge the signal, switching it off for this unique event (a new trigger of the warning should not be prevented).

3.3.1.2 For systems with seat occupant detection on all rear seating positions, the visual signal does not need to indicate the number of seat belts in use or not in use, but the signal must remain as long as the seatbelt remain unfastened on any of the occupied seats in the rear.

3.3.1.3 For systems without occupant detection on all rear seating positions, the visual signal must clearly indicate to the driver the seating positions showing the rear seat belts in use and not in use. No signal is required if all of the rear occupants are belted.

### 3.3.2 Audible signal

A "Loud and Clear" audible signal is to be deployed for all rear seating positions in case of a change of status (from buckled to unbuckled) as defined in 3.1.5.



Except for change of status events, the system may allow the driver to acknowledge the signal, switching it off for this unique event (a new trigger of the warning should not be prevented).

For systems with occupant detection on any rear seating positions, a “Loud and Clear” audible signal needs to be deployed before at least one of the following (at the choice of the manufacturer) when any of those seats are occupied and the belt of the occupied seat is unbuckled.

- The car has reached a forward speed of 25 km/h, or
- The car has been in "Forward Motion" for 500 meters.

The duration of the audible signal must be at least 30 seconds not counting gaps exceeding 3 seconds and must start with a positive audible signal (not a gap). There must be no gaps greater than 10 seconds. The system may allow the driver to acknowledge the signal, so switching it off.

Alternatively, the manufacturer may use the same warning strategy (including initial and final warning) as described in Section 3.2 in case of occupant detection in all rear seating positions.

### 3.4 Scoring & Visualisation

For Seat Belt Reminder systems which fully comply with the ANCAP requirements, the following points will be awarded to the overall occupant score for that vehicle:

#### 3.4.1 Front row seating positions

Where ALL front row seating positions meet the assessment criteria, 1 point will be awarded.

#### 3.4.2 Rear seating positions

Where 1 point have been awarded for front seating positions the rear seating positions are also eligible for scoring points as follows.

Rear seating positions (including optional third or more rows of seats),  $1.5/n$  points (with  $n$  the number of rear seating positions) are awarded for seating positions without occupant detection. An additional  $0.5/n$  points is available for rear seating positions with occupant detection systems.

#### 3.4.3 Scoring examples

- 5-Seater (2 Front + 3 Rear) with occupant detection on all seats
  - o Driver & Passenger 1.000 Point
  - o Rear Seats 1.500 Points
  - o Rear occupant detection on 3 seats 0.500 Points
  - $\left(\frac{0.5}{n}\right) * \# \text{ of seats with detection} = \left(\frac{0.5}{3}\right) * 3$
  - o **Total Score 3.000 Points**

- 5-Seater (2 Front + 3 Rear) with occupant detection on outboard rear seats.
  - o Driver & Passenger 1.000 Point
  - o Rear Seats 1.500 Points
  - o Rear occupant detection on 2 seats 0.333 Points
  - $\left(\frac{0.5}{n}\right) * \# \text{ of seats with detection} = \left(\frac{0.5}{3}\right) * 2$
  - o **Total Score** **2.833 Points**
  
- 7-Seater (2 Front + 3 2<sup>nd</sup> Row + 2 3<sup>rd</sup> Row) with occupant detection on all seats in the 2<sup>nd</sup> row.
  - o Driver & Passenger 1.000 Point
  - o Rear Seats 1.500 Points
  - o Rear occupant detection on 3 seats 0.300 Points
  - $\left(\frac{0.5}{n}\right) * \# \text{ of seats with detection} = \left(\frac{0.5}{5}\right) * 3$
  - o **Total Score** **2.800 Points**
  
- 7-Seater (2 Front + 3 2<sup>nd</sup> Row + 2 3<sup>rd</sup> Row) with occupant detection on outboard seats in the 2<sup>nd</sup> row.
  - o Driver & Passenger 1.000 Point
  - o Rear Seats 1.500 Points
  - o Rear occupant detection on 2 seats 0.200 Points
  - $\left(\frac{0.5}{n}\right) * \# \text{ of seats with detection} = \left(\frac{0.5}{5}\right) * 2$
  - o **Total Score** **2.700 Points**
  
- 7-Seater (2 Front + 3 2<sup>nd</sup> Row + 2 3<sup>rd</sup> Row) with occupant detection on outboard seats in the 2<sup>nd</sup> row, and no SBR in the third row.
  - o Driver & Passenger 1.000 Point
  - o Rear Seats 0.900 Points
  - $\left(\frac{1.5}{n}\right) * \# \text{ of seats} = \left(\frac{1.5}{5}\right) * 3$
  - o Rear occupant detection on 2 seats 0.200 Points
  - $\left(\frac{0.5}{n}\right) * \# \text{ of seats with detection} = \left(\frac{0.5}{5}\right) * 2$
  - o **Total Score** **2.100 Points**

## 4 ASSESSMENT OF SPEED ASSIST SYSTEMS

### 4.1 Introduction

This version of the protocol contains technical requirements for both Speed Limit information functions to continuously inform the driver of the speed limit and Speed Control Functions supporting the driver in his driving task by limiting or maintaining the set speed.

### 4.2 Definitions

Throughout this protocol the following terms are used:

- **Vindicated** – The speed the vehicle travels as displayed to the driver by the speedometer as in ECE R39.
- **Vlimit** – Maximum allowed legal speed for the vehicle at the location, time and in the circumstance the vehicle is driving.
- **SLIF - Speed Limit Information Function.** SLIF means a function with which the vehicle knows and communicates the speed limit.
- **Vadj** – Adjustable speed Vadj means the voluntarily set speed for the speed control functions, which is based on **Vindicated** and includes the offset set by the driver.
- **SLF – Speed Limitation Function.** SLF means a system which allows the driver to set a vehicle speed Vadj, to which he wishes the speed of his car to be limited and above which he wishes to be warned.
- **ISA – Intelligent Speed Assistance.** ISA is a SLF combined with SLIF, where the Vadj is set by the SLIF with or without driver confirmation.
- **iACC – Intelligent Adaptive Cruise Control.** iACC is an ACC combined with SLIF, where the speed is set by the SLIF with or without driver confirmation.

The following terms are used for the assessment of the Speed Limitation function:

- **Vstab** – Stabilised speed Vstab means the mean actual vehicle speed when operating. Vstab is calculated as the average actual vehicle speed over a time interval of 20 seconds beginning 10 seconds after first reaching Vadj – 10 km/h.

### 4.3 Requirements for SLIF and Speed Control Functions

The Speed Assist Systems is developed in such a way that it allows different types of Speed Assist Systems to be assessed in two areas; SLIF and Speed Control functions which may be combined.

Speed Limit Information Function

- Basic SLIF meeting the General Requirements
- Advanced Functions
- System Accuracy
- Warning Function

## Speed Control function

- Speed Limitation function (standalone function or combined with SLIF without coupling)
- Intelligent Speed Assistance (SLIF and Speed Limitation function coupled)
- Intelligent ACC (SLIF and ACC coupled)

### 4.4 Speed Limit Information Function

The Speed Limit Information Function can be a standalone function or an integrated part of a speed control function. Any SLIF, camera or map based or a combination of both, is eligible for scoring points of this section when meeting the General Requirements when the SLIF is default ON at the start of a journey.

The speed limit information could either be provided by vehicle-integrated devices or by mobile devices connected to the vehicle network. A list of compatible devices needs to be mentioned in the vehicle handbook.

#### 4.4.1 General Requirements

- 4.4.1.1 The speed limit shall be shown using a traffic sign and shall be clearly seen in the direct field of view of the driver, without the need for the head to be moved from the normal driving position, i.e. instrument cluster or head-up display.
- 4.4.1.2 The speed limit information must be shown or accessible at any time with a simple operation and needs to be shown at the start of the next journey (excluding the initialization period).
- 4.4.1.3 The indicated speed limit information may indicate the level of reliability of the speed limit.
- 4.4.1.4 In the presence of conditional speed limits the system needs to either properly identify and show (for example when raining) the applicable speed limit or alternatively, needs to indicate the presence of a conditional speed limit which the system is not able to compute.
- 4.4.1.5 Manufacturers need to supply ANCAP with background information of the SLIF (if applicable to the technology).

#### 4.4.2 Advanced Functions

- 4.4.2.1 Systems that are able to properly identify conditions and act accordingly can attract additional points based on the number of advanced functions.

Advanced Functions		Points	Required Action
Weather	Rain / Wetness	2	Show correct speed limit
	Snow / Icy	2	Warning only and ignore if irrelevant
Time	Time	3	Show correct speed limit
Distance	Distance for / in	1	Show correct speed limit
Arrows	Arrows	1	Show correct speed limit or ignore if irrelevant
Vehicle Categories	Other vehicle / weight categories	1	Ignore if irrelevant
Implicit Speed	Highway / Motorway	2	Show correct speed limit

<b>Limits</b>	City Entry / Exit	3	
	Residential zones	2	
<b>Dynamic Speed Limits</b>	Dynamic speed signs including roadworks	3	Show correct speed limit
<b>TOTAL</b>		<b>20</b>	

4.4.2.2 The Advanced Functions score is calculated by multiplying the points achieved by 0.025.

#### 4.4.3 System Accuracy

4.4.3.1 A system that achieves more than 12 out of 20 points from the Advanced Functions will be awarded the score for System Accuracy. If map based data is required to achieve any of the points up to 12 the speed limits must be updated frequently (at least quarterly) and automatically for the first six years, without user action. (ex. sending DVD/USB to customer allowed).

#### 4.4.4 Warning Function

Speed Limit Information Functions that meet the warning requirements below to indicate the driver that Vlimit is exceeded will score for Warning Function. The warning function may be switched ON/OFF by the driver where the last user mode may be used.

4.4.4.1 The warning shall be a flashing traffic sign used to communicate the speed limit or an additional visual signal adjacent to the traffic sign.

4.4.4.2 The warning commences when Vindicated is exceeding Vlimit by more than 5km/h (3 mph). A negative and/or positive offset with respect to the known speed limit is allowed but may not be larger than 10 km/h (5 mph).

4.4.4.3 The driver continues to be informed for the duration of the time that Vlimit is exceeded by more than 5 km/h, with a total duration of at least 10 seconds. Gaps of less than 1 second, which allow for signals which flash are ignored, but the signal may not start with a gap. If the signal is not continuous for the first 10 seconds, it needs to be repeated every 30 seconds or less, resulting in a minimum total duration of at least 10 seconds.

4.4.4.4 The warning sequence does not need to be reinitiated for each exceedence of Vlimit until Vindicated has reduced to more than 5km/h below Vlimit.

### 4.5 Speed Control Function

Three speed control functions are considered in this section; Speed Limitation Function (manually set), Intelligent Speed Assist and Intelligent Adaptive Cruise Control which need to meet the following requirements to score points:

Type Speed Control Function	Sections
Speed Limitation Function (SLF)	4.5.1, 4.5.2.1 & 4.5.3
Intelligent Speed Assist (ISA)	4.5.1, 4.5.2.2 & 4.5.3
Intelligent Adaptive Cruise Control (iACC)	

#### 4.5.1 Activation / de-activation of the function

- The speed control function must be capable of being activated/de-activated at any time with a simple operation.
- At the start of a new journey, the system should be de-activated by default.

#### 4.5.2 Setting of Vadj

##### 4.5.2.1 Manually setting the speed

- It shall be possible to set Vadj, by a control device operated directly by the driver, by steps not greater than 10km/h (5mph) between 30km/h (20mph) and 130km/h (80mph).
- It shall be possible to set Vadj independently of the vehicle speed.
- If Vadj is set to a speed lower than the current vehicle speed, the system shall limit the vehicle speed to the new Vadj within 30s or shall initiate a warning (section 4.5.3.4) no later than 30s after Vadj has been set.
- The Vadj value shall be permanently indicated to the driver and visible from the driver's seat. This does not preclude temporary interruption of the indication for safety reasons or driver's demand.

##### 4.5.2.2 Automatic setting the speed

An automatic setting is using the speed limit information from the SLIF to set the Vadj with or without driver confirmation. Both ISA and iACC functions fulfilling the requirements from this section are eligible for scoring points:

- The system should adopt, or offer the driver to adopt, an adjusted Vadj within 5s after a change in the speed limit.
- If Vadj is set to a speed lower than the current vehicle speed, the system starts to limit the vehicle speed to the new Vadj or shall initiate a warning (section 4.5.3.4) no later than 30s after Vadj has been set.
- A negative and/or positive offset with respect to the known speed limit is allowed but may not be larger than 10 km/h (5 mph). This offset is included in Vadj.
- The Vadj in the automatic mode of an ISA system may be retained at the end of a journey.
- Where Vadj is set to the speed limit advised by the SLIF, the indication of Vadj may be suppressed.

#### 4.5.3 Speed Control

4.5.3.1 The vehicle speed shall be limited or controlled to Vadj.

4.5.3.2 It shall still be possible to exceed Vadj by applying a positive action – e.g. kickdown (SLF/ISA) or depressing the accelerator (iACC).

4.5.3.2.1 After exceeding Vadj by applying a positive action, the speed control function shall be reactivated when the vehicle speed drops to a speed less than or equal to Vadj.

4.5.3.2.2 The speed control function shall permit a normal use of the accelerator control for gear selection.

4.5.3.3 The speed control function shall ensure that when stable speed control has been achieved, Vstab shall be within -5/+0 km/h of Vadj (see test protocol)

- 4.5.3.4 When the speed control function is not able to limit to and/or maintain  $V_{adj}$  and  $V_{adj}$  is exceeded by more than 5 km/h an audiovisual warning is issued, with a total duration of at least 10 seconds. No warning needs to be given when  $V_{adj}$  is exceeded as a result of a positive action.

Gaps of less than 1 second, which allow for signals which flash are ignored, but the signal may not start with a gap. If the signal is not continuous for the first 10 seconds, it needs to be repeated every 30 seconds or less, resulting in a minimum total duration of at least 10 seconds.

For systems where active braking is applied to maintain and/or limit the speed, this warning requirement does not apply.

Note: The warning signal does not preclude temporary interruption of the indication for safety reasons.

## 4.6 Scoring and Visualisation

The following points are awarded for systems that meet the requirements. These points will contribute to the Safety Assist Score.

<b>Speed Limit Information Function</b>	<b>1.50</b>
Basic SLIF	0.50
Advanced SLIF	0.50
System Accuracy	0.25
Warning Function	0.25
<b>Speed Control Function</b>	<b>1.50</b>
Speed Limitation Function <i>For cars <u>without</u> SLIF</i>	1.25
<i>For cars <u>with</u> SLIF</i>	0.75
ISA and/or intelligent ACC	1.50

## 5 ASSESSMENT OF AEB INTER-URBAN SYSTEMS

### 5.1 Introduction

AEB Inter-Urban systems are AEB systems that are designed to work at speeds typical for driving outside of the city environment, for example on urban roads or highways. For the assessment of AEB Inter-Urban systems, three areas of assessment are considered: the Autonomous Emergency Braking function, Forward Collision Warning function and the Human Machine Interface (HMI). The AEB function is assessed in two different types of scenarios, while the FCW function is scored separately and assessed in three different types of scenarios. The FCW function is only considered when the system provides dynamic brake support.

### 5.2 Definitions

Throughout this protocol the following terms are used:

**Autonomous Emergency Braking (AEB)** – braking that is applied automatically by the vehicle in response to the detection of a likely collision to reduce the vehicle speed and potentially avoid the collision.

**Forward Collision Warning (FCW)** – an audiovisual warning that is provided automatically by the vehicle in response the detection of a likely collision to alert the driver.

**Dynamic Brake Support (DBS)** – a system that further amplifies the driver braking demand in response to the detection of a likely collision to achieve a greater deceleration than would otherwise be achieved for the braking demand in normal driving conditions.

**Car-to-Car Rear Stationary (CCRs)** – a collision in which a vehicle travels forwards towards another stationary vehicle and the frontal structure of the vehicle strikes the rear structure of the other.

**Car-to-Car Rear Moving (CCRm)** – a collision in which a vehicle travels forwards towards another vehicle that is travelling at constant speed and the frontal structure of the vehicle strikes the rear structure of the other.

**Car-to-Car Rear Braking (CCRb)** – a collision in which a vehicle travels forwards towards another vehicle that is travelling at constant speed and then decelerates, and the frontal structure of the vehicle strikes the rear structure of the other.

**Vrel\_test** – means the relative speed between the VUT and the EVT by subtracting the velocity of the EVT from that of the VUT at the start of test

**Vimpact** – means the speed at which the VUT hits the EVT

**Vrel\_impact** – means the relative speed at which the VUT hits the EVT by subtracting the velocity of the EVT from Vimpact at the time of collision

### 5.3 Criteria and Scoring

- 5.3.1 To be eligible for scoring points in AEB Inter-Urban, the AEB and/or FCW system must operate up to speeds of at least 80 km/h, needs to be default ON at the start of every journey and and



deactivation of the system should not be possible with a single push on a button.

5.3.1.1 The audible component of the FCW system (if applicable) needs to be loud and clear.

5.3.2 Assessment Criteria

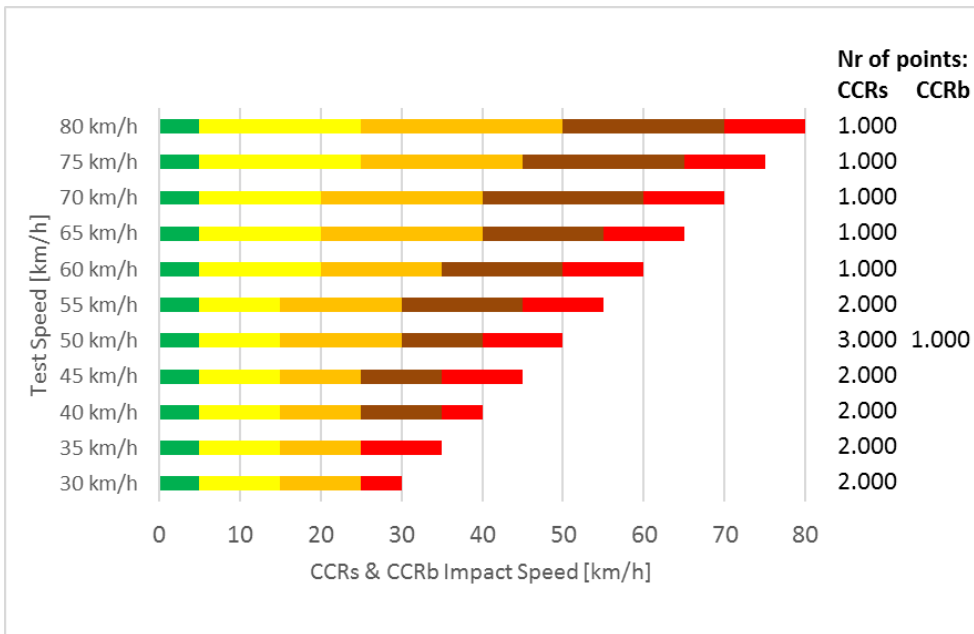
5.3.2.1 For both AEB and FCW system tests, the assessment criteria used is the relative impact speed  $V_{rel\_impact}$ . For CCRb scenarios, the relative test speed is assumed equal to the initial test speed.

5.3.3 Scoring

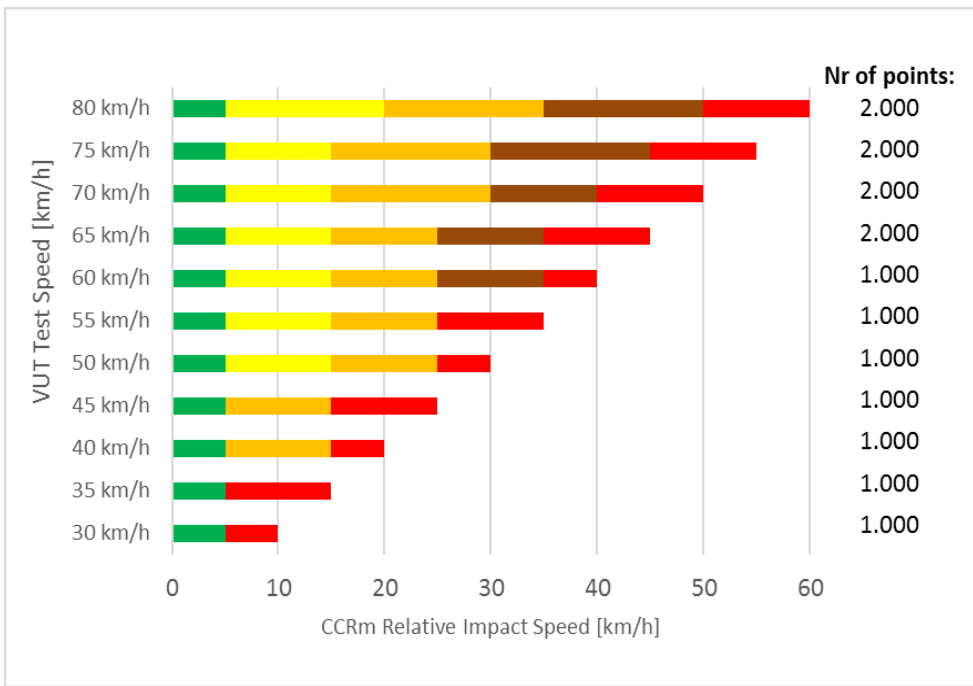
The scoring is based on normalized scores of the AEB and FCW functions, assessed in the CCRs, CCRm and CCRb scenarios.

For the CCRs and CCRm scenarios, the total score for all five grid points per test speed is calculated as a percentage of the maximum achievable score per test speed, which is then multiplied by the points available for this test speed. It should be noted that the 100% overlap score is double counted.

The points available and the colour distribution for the different test speeds for CCRs and CCRb (50 km/h only) are detailed in the graph below:



Similar for CCRm, where the relative impact speed is used:



For each predicted colour the following scaling is applied to the grid point:

<i>Green</i>	<i>1.000</i>
<i>Yellow</i>	<i>0.750</i>
<i>Orange</i>	<i>0.500</i>
<i>Brown</i>	<i>0.250</i>
<i>Red</i>	<i>0.000</i>

#### 5.3.4 AEB Inter-Urban Correction factors

The data provided by the manufacturer is scaled using two correction factors, one for AEB and one for FCW, which are calculated based on a number of verification tests performed. The vehicle sponsor will fund 20 verification tests, 10 for AEB and 10 for FCW where applicable. The vehicle manufacturer has the option of sponsoring up to 10 additional verification tests for AEB and 10 for FCW.

The verification points are randomly selected grid points, distributed in line with the predicted colour distribution (excluding red points).

The actual tested total score of the verification test points is divided by the predicted total score of these verification test points. This is called the correction factor, which can be lower or higher than 1.

$$\text{Correction Factor} = \frac{\text{Actual tested score}}{\text{Predicted score}}$$

The correction factor is used to calculate the AEB and FCW function scores. The final AEB and FCW scores for the vehicle can never exceed 100% (1.5 and 1.0 points respectively) regardless of the correction factor.

### 5.3.5 Impact speed tolerance

As test results can be variable between labs and in-house tests and/or simulations a 2 km/h tolerance to the impact speeds of the verification test is applied. The tolerance is applied in both directions, meaning that when a tested point scores better than predicted, but within tolerance, the predicted result is applied. The tolerance only applies to verify whether the predicted colour of the tested verification point is correct. When, including tolerance, the colour is not in line with the prediction, the true colour of the test point will be determined by comparing the actual measured impact speed with the colour band in section 5.3.3 without applying a tolerance to the impact speed. As an example the accepted impact speed ranges for the 50km/h CCRs and CCRb tests are as follows:

<b>Prediction</b>	<b>Impact speed range [km/h]</b>	<b>Accepted range [km/h]</b>
<i>Green</i>	$0 \leq v_{impact} < 5$	$0 \leq v_{impact} < 7$
<i>Yellow</i>	$5 \leq v_{impact} < 15$	$3 \leq v_{impact} < 17$
<i>Orange</i>	$15 \leq v_{impact} < 30$	$13 \leq v_{impact} < 32$
<i>Brown</i>	$30 \leq v_{impact} < 40$	$28 \leq v_{impact} < 42$
<i>Red</i>	$40 \leq v_{impact}$	<i>excluded</i>

### 5.3.6 Human Machine Interface (HMI)

HMI points can be achieved for the following:

- **Supplementary warning for the FCW system** **1 point**

In addition to the required audiovisual warning, a more sophisticated warning like head-up display, belt jerk, brake jerk or any other haptic feedback is awarded when it is issued at the same time as the audiovisual warning.

**NOTE:** The supplementary warning point is not applicable to AEB only systems

- **Reversible pre-tensioning of the belt in the pre-crash phase** **1 point**

When the system detects a critical situation that can possibly lead to a crash, the belt can already be pre-tensioned to prepare for the oncoming impact.

The HMI score is calculated by dividing the points achieved by 2.

### 5.3.7 Total AEB Inter-Urban Score

The total score in points is the weighted sum of the AEB score, FCW score and HMI score as shown below.

*(AEB score x AEB Correction factor x 1.5)*

*+(FCW score x FCW Correction factor x 1.0)*

*+(HMI score x 0.5)*

***AEB Inter Urban total score***

#### 5.3.7.1 Scoring Example

Manufacturer X has provided the following prediction to ANCAP, where the predicted score is 2.669 points:

AEB Inter-Urban		AEB					FCW				
TESTNUMBER											
CCRs		-50%	-75%	100%	75%	50%	-50%	-75%	100%	75%	50%
Test Speed	30 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	35 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	40 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	45 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	50 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	55 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	60 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	65 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	70 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
	75 km/h	-	-	-	-	-	Green	Green	Green	Green	Green
80 km/h	-	-	-	-	-	Red	Red	Red	Red	Red	
Predicted CCRs score		-					75.93%				

CCRm		-50%	-75%	100%	75%	50%	-50%	-75%	100%	75%	50%
Test Speed	30 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	35 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	40 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	45 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	50 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	55 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	60 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	65 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	70 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
	75 km/h	Green	Green	Green	Green	Green	Green	Green	Green	Green	Green
80 km/h	Red	Red	Red	Red	Red	Red	Red	Red	Red	Red	
Predicted CCRm score		89.81%					47.69%				

The randomly chosen verification points and test results provide the following scores:

	Predicted score	Actual tested score	Correction Factor
AEB	9.250	9.000	0.973
FCW	7.750	8.000	1.032

Using the following AEB Inter-Urban scenario and HMI scores:

SUMMARY			
CCRs	-		75.9%
CCRm	89.8%		47.7%
CCRb	100.0%		100.0%
HMI		100.0%	

The FINAL AEB Inter-Urban score is:

AEB	$1.424 \times 0.973 =$	1.385
FCW	$0.745 \times 1.032 =$	0.769
HMI		0.500
<b>TOTAL</b>		<b>2.654</b>

## 5.4 Visualisation

The AEB Inter-Urban scores are presented separately using a coloured top view of the scenario for the different overlap situations (where applicable); left overlap, full overlap and right overlap. The colours used are based on the overlap scores respectively, rounded to three decimal places.

<b>Colour</b>	<b>Verdict</b>	<b>Applied to Total Score</b>	<b>For sub Scores</b>
Green	'Good'	2.251 - 3.000 points	75.0% - 100.0%
Yellow	'Adequate'	1.501 - 2.250 points	50.0% - 75.0%
Orange	'Marginal'	0.751 - 1.500 points	25.0% - 50.0%
Brown	'Weak'	0.001 - 0.750 points	00.0% - 25.0%
Red	'Poor'	0.000 points	00.0

## 6 ASSESSMENT OF LANE SUPPORT SYSTEMS

### 6.1 Introduction

[Not used – numbering retained for clarity]

### 6.2 Definitions

**Emergency Lane Keeping (ELK)** – default ON heading correction that is applied automatically by the vehicle in response to the detection of the vehicle that is about to drift beyond the edge of the road or into oncoming or overtaking traffic in the adjacent lane.

**Lane Keeping Assist (LKA)** – heading correction that is applied automatically by the vehicle in response to the detection of the vehicle that is about to drift beyond a delineated edge line of the current travel lane.

**Lane Departure Warning (LDW)** – a warning that is provided automatically by the vehicle in response to the vehicle that is about to drift beyond a delineated edge line of the current travel lane.

**Vehicle under test (VUT)** – means the vehicle tested according to this protocol with a Lane Keep Assist and/or Lane Departure Warning system.

**Time To Collision (TTC)** – means the remaining time before the VUT strikes the GVT, assuming that the VUT and GVT would continue to travel with the speed it is travelling.

**Lane Edge** – means the inner side of the lane marking or the road edge

**Distance To Lane Edge (DTLE)** – means the remaining lateral distance (perpendicular to the Lane Edge) between the Lane Edge and most outer edge of the tyre, before the VUT crosses Lane Edge, assuming that the VUT would continue to travel with the same lateral velocity towards it.

### 6.3 Criteria and Scoring

6.3.1 To be eligible for scoring points in Lane Support Systems, the vehicle must be equipped with an ESC system that complies with UNECE Regulation 13H.

For any system, the driver must be able to override the intervention by the system.

6.3.2 Human Machine Interface (HMI)

HMI points can be achieved for the following:

- **Lane Departure Warning** **0.25 points**

Any LDW system that issues an audible and/or haptic warning before a DTLC of -0.2m is awarded.

Where an LKA system fulfils the requirements of all the single line marking tests, the LDW points are awarded automatically.

- **Blind Spot Monitoring**

**0.25 points**

The vehicle is additionally equipped with a Blind Spot Monitoring system to warn the driver of other vehicles present in the blind spot.

Where the vehicle is fitted with an ELK system fulfilling the requirements of the overtaking tests, the BSM points are awarded automatically.

6.3.3 Lane Keep Assist (LKA)

6.3.3.1 For LKA system tests, the assessment criteria used is the Distance to Lane Edge (DTLE).

6.3.3.2 The limit value for DTLE for LKA tests is set to -0.3m for testing against lines, meaning that the LKA system must not permit the VUT to cross the inner edge of the lane marking by a distance greater than 0.3m.

6.3.3.3 The limit value for DTLE for LKA Road Edge tests is set to -0.1m for testing against the road edge, meaning that the LKA system only allows the VUT to have a part of the front wheel outside of the road edge.

6.3.3.4 The available points per test are awarded based on a pass/fail basis where all tests within the scenario and road marking combination need to be a pass. The points available for the different LKA scenario and road marking combinations are detailed in the table below:

<b>LKA Scenario</b>	<b>Road marking</b>	<b>Points</b>
Road Edge	Road Edge only	0.25
	Road Edge with central lane marking	0.25
Dashed Line	Single lane marking	0.25
	Fully marked lane	0.50
Solid line	Single lane marking	0.25
	Fully marked lane	0.50
<b>TOTAL</b>		<b>2.00</b>

6.3.4 Emergency Lane Keeping (ELK)

6.3.4.1 For ELK Road Edge tests, the assessment criteria used is the Distance to Lane Edge (DTLE).

6.3.4.2 The limit value for DTLE for ELK Road Edge tests is set to -0.1m, meaning that the vehicle is only allowed to have a part of the front wheel outside of the road edge.

6.3.4.3 For ELK tests with oncoming and overtaking vehicles, the assessment criteria used is no impact, meaning that the VUT is not allowed to contact the overtaking or oncoming vehicle target at any time during the test.

- 6.3.4.4 The available points per test are awarded based on a pass/fail basis where all tests within the scenario and road marking combination need to be a pass. The points available for the different ELK scenario and road marking combinations are detailed in the table below:

<b>ELK Scenario</b>	<b>Road marking</b>	<b>Points</b>
Road Edge	Dashed centreline & no line next to Road Edge	0.25
	Dashed centreline & dashed line next to Road Edge	0.25
	Dashed centreline & solid line next to Road Edge	0.25
Oncoming vehicle	Fully marked lanes	0.50
Overtaking vehicle	Fully marked lanes	0.25
<b>TOTAL</b>		<b>1.50</b>

### 6.3.5 Total LSS Score

The total score in points is the sum of the HMI score, LKA score and ELK score.

<b>LSS function</b>		<b>Points</b>
HMI	Section 6.3.2	0.50
LKA	Section 6.3.3	2.00
ELK	Section 6.3.4	1.50
<b>TOTAL</b>		<b>4.00</b>

## 6.4 Visualisation

The LSS scores are presented separately using a colour for the different LSS functions; HMI, LKA and ELK. The colours used are based on the function scores respectively, rounded to three decimal places.

<b>Colour</b>	<b>Verdict</b>	<b>Applied to Total Score</b>	<b>For sub Scores</b>
Green	'Good'	3.001 - 4.000 points	75.0% - 100.0%
Yellow	'Adequate'	2.001 - 3.000 points	50.0% - 75.0%
Orange	'Marginal'	1.001 - 2.000 points	25.0% - 50.0%
Brown	'Weak'	0.001 - 1.000 points	00.0% - 25.0%
Red	'Poor'	0.000 points	00.0