THE KEY INNOVATION IN KO-HAF...

...is a cooperative cross-manufacturer backend solution (“Safety Server”): Vehicles send information about the environment (road markings, traffic signs, break down vehicles etc.) collected by their sensors to the server via mobile communication systems. There, the information in the sense of collective perception is aggregated, evaluated, and condensed. The result is supplied to the vehicles in form of a high-definition and highly up-to-date digital map. This provides a considerably higher foresight compared to the car’s own sensors, which is vital for HAD* (SAE level 3) at higher speeds. This allows for a dynamic assessment of the suitability of certain sections for HAD*.

Human drivers were also intensively studied in the project: Amongst others, the activities focused on automation effects, the driver’s condition and availability or the influences on the driver take-over.

COME AND SEE FOR YOURSELF...

...in numerous interesting demonstrations, technical speeches, poster & video presentations and exhibits answers of the Ko-HAF consortium to the following questions:

- How to create high-precision and highly up-to-date digital maps (HD maps)?
- How to exchange data between vehicle fleets of different manufacturers and backend in the best possible way?
- How to update backend HD maps continuously and without errors on the basis of vehicle fleet data?
- How to merge sensors and backend HD maps in the vehicle?
- How to design highly automated driving (HAD) functions such as merging, overtaking, departing or emergency braking in a more robust and reliable manner?
- What do methods and tools for an efficient testing of highly automated driving look like (in simulation, in test tracks, in road traffic)?
- Do longer HAD* drives affect the driver and if yes, how?
- Can the driver’s condition be assessed reliably and if yes, how?
- How do the different non-driving related tasks affect the quality of the take-over?
- How would an ideal HMI* for HAD* look like?

* HAD: Highly automated driving (SAE level 3);
* HMI: Human Machine Interface

TOGETHER WE SEE BETTER!
Cooperative, highly automated driving for more safety and convenience in road traffic

Final Presentation of the Ko-HAF Project on September, 19th/20th 2018 in Rodgau-Dudenhofen

PROGRAM

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www.ko-haf.de
SEPTEMBER, 19th 2018

TIME | ROOM: AUDITORIUM (Topic/Speaker/Organization)
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10:30 – 11:45 | Arrival and registration of the guests at Rodgau Lake, bus transfer to Opel Test Center, Dudenhofen
12:00 – 12:15 | Welcome by the host
Dr. Burkhard Mille, Director Electric and Electronic Systems, Opel Automobile GmbH
12:15 – 12:30 | Welcome by the Ministry BMWi
Markus Hell, Head of the Industry department, Federal Ministry of Economic Affairs and Energy
12:30 – 13:00 | Ko-HAF – Safety by Cooperation
Dr. Andree Hohm, Project Coordinator Ko-HAF, Continental Teves AG & Co. oHG
14:30 – 15:15 | Safety and Comfort of Highly Automated Driving Functions
Dr. Andree Hohm, Project Coordinator Ko-HAF, Continental Teves AG & Co. oHG
15:15 – 15:45 | Driver State During Automated Driving
Jonas Radlmayr, Audi AG
15:45 – 16:30 | Empirical Data for an Integrative Framework
Veronika Weinbeer, Max-Bosch-Institut, Opel Automobile GmbH
16:30 – 17:15 | Are you Ready to Take Over?
Dr. Lukas Klejnowski, Robert Bosch GmbH
17:15 – 18:00 | Jauch, Thierry MAX – Chair of Ergonomics

SEPTEMBER, 20th 2018

TIME | ROOM: AUDITORIUM (Topic/Speaker/Organization)
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08:30 – 09:15 | Arrival and registration of the guests at Rodgau Lake, bus transfer to Opel Test Center, Dudenhofen
09:30 – 09:50 | Ko-HAF – Safety by Cooperation
Dr. Andree Hohm, Project Coordinator Ko-HAF, Continental Teves AG & Co. oHG
10:00 – 10:30 | Are you Ready to Take Over?
Driver State During Automated Driving
Jonas Radlmayr, TU München – Chair of Ergonomics
10:30 – 11:00 | Drowsiness and Fatigue in Automated Driving – Empirical Data for an Integrative Framework
Veronika Weinbeer, Audi AG
11:00 – 11:30 | Non-driving Related Tasks during Automated Driving – Implications for Take-Over Performance and MMI Design
Olivier Jarosch, BMW AG
12:00 – 12:30 | What’s his Plan? – Detection of Typical Motion Patterns for Maneuver Prediction
David Augustin, Opel Automobile GmbH
12:30 – 13:00 | Strategic and Tactical Aspects of Behavior Planning for Automated Driving on Highways
Björn Reuber, TU Braunschweig – Institute of Automotive Engineering
13:00 – 13:30 | Minimal Risk Maneuver
Thorsten Leonhardt, Audi AG

ROOM: KAPITÄN (Topic/Speaker/Organization)

10:00 – 10:30 | Are you Ready to Take Over?
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ORGANIZATIONAL DETAILS

Please register at WWW.KO-HAF.DE/ANMELDUNG
This event is free of charge. The number of attendees is restricted. Your registration will only be valid when confirmed.
Please find information on hotels, directions, and parking on the Ko-HAF website.

EVENING EVENT (STARTING AT 06:30 PM)
We would like to conclude the first day with a get-together at the Rodgau Lake.

LISTEN TO THE SPEECHES, VISIT THE DRIVING DEMONSTRATIONS AND MORE THAN 70 VIDEO AND POSTER PRESENTATIONS AS WELL AS DRIVING SIMULATORS!

OVERVIEW
SAFETY SERVER
FRONTEND
HUMAN-MACHINE-INTERACTION
FUNCTION DEVELOPMENT
SECURITY

LIVE TRANSLATION PROVIDED
All lectures, video and poster presentations are written in English. The lectures will be held in German language. A simultaneous translation will be provided in English.