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**Intelligent transport systems —  
Manoeuvring aids for low-speed  
operation (MALSO) — Performance  
requirements and test procedures**

*Systèmes de transport intelligents — Aides à la conduite pour  
manœuvre à vitesse réduite (MALSO) — Exigences de performance et  
procédures d'essai*

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## Foreword

ISO (the International Organization for Standardization) is a worldwide federation of national standards bodies (ISO member bodies). The work of preparing International Standards is normally carried out through ISO technical committees. Each member body interested in a subject for which a technical committee has been established has the right to be represented on that committee. International organizations, governmental and non-governmental, in liaison with ISO, also take part in the work. ISO collaborates closely with the International Electrotechnical Commission (IEC) on all matters of electrotechnical standardization.

The procedures used to develop this document and those intended for its further maintenance are described in the ISO/IEC Directives, Part 1. In particular, the different approval criteria needed for the different types of ISO document should be noted. This document was drafted in accordance with the editorial rules of the ISO/IEC Directives, Part 2 (see [www.iso.org/directives](http://www.iso.org/directives)).

ISO draws attention to the possibility that the implementation of this document may involve the use of (a) patent(s). ISO takes no position concerning the evidence, validity or applicability of any claimed patent rights in respect thereof. As of the date of publication of this document, ISO had not received notice of (a) patent(s) which may be required to implement this document. However, implementers are cautioned that this may not represent the latest information, which may be obtained from the patent database available at [www.iso.org/patents](http://www.iso.org/patents). ISO shall not be held responsible for identifying any or all such patent rights.

Any trade name used in this document is information given for the convenience of users and does not constitute an endorsement.

For an explanation of the voluntary nature of standards, the meaning of ISO specific terms and expressions related to conformity assessment, as well as information about ISO's adherence to the World Trade Organization (WTO) principles in the Technical Barriers to Trade (TBT), see [www.iso.org/iso/foreword.html](http://www.iso.org/iso/foreword.html).

This document was prepared by Technical Committee ISO/TC 204, *Intelligent transport systems*.

This third edition cancels and replaces the second edition (ISO 17386:2010), which has been technically revised.

The main changes are as follows:

- requirements updated according to state-of-the-art systems regarding detection characteristic;
- test method for detection latency added.

Any feedback or questions on this document should be directed to the user's national standards body. A complete listing of these bodies can be found at [www.iso.org/members.html](http://www.iso.org/members.html).

## Introduction

Today's aerodynamically-shaped vehicles often result in restricted rear and front visibility. Manoeuvring Aids for Low Speed Operation (MALSO) enhance security and driver convenience during parking or manoeuvring situations at very low speed, e.g. squeezing into small parking spaces or through narrow passages. Drivers can avoid collisions with obstacles that cannot be seen but can be detected by the system and they can make more effective use of limited parking space.

MALSO systems are detection devices with non-contact sensors which assist the driver during low-speed manoeuvring. MALSO systems indicate to the driver the presence of front, rear or corner objects. They are regarded as an aid to drivers for use at speeds of up to 0,5 m/s, and they do not relieve drivers of their responsibility when driving the vehicle.

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# Intelligent transport systems — Manoeuvring aids for low-speed operation (MALSO) — Performance requirements and test procedures

## 1 Scope

This document addresses light-duty vehicles, such as passenger cars, pick-up trucks, light vans and sport utility vehicles (motorcycles excluded) equipped with Manoeuvring Aids for Low Speed Operation (MALSO) systems. It specifies the minimum functionality requirements which the driver can generally expect of the device, i.e. detection of and information on the presence of relevant obstacles within a defined (short) detection range. It defines minimum requirements for failure indication as well as performance test procedures; it includes rules for the general information strategy but does not restrict the kind of information or display system.

MALSO systems use object-detection devices (sensors) for ranging in order to provide the driver with information based on the distance to obstacles. Although sensing technology is not addressed in this document, technology does affect the performance-test procedures set up in [Clause 7](#). The current test objects are defined based on systems using ultrasonic sensors, which reflect the most commonly used technology at the time of publication. For other sensing technologies which will potentially emerge in the future, these test objects shall be checked and changed if required.

Visibility-enhancement systems like video-camera aids without distance ranging and warning are not covered by this document.

Reversing aids and obstacle-detection devices on heavy commercial vehicles are not addressed by this document.

## 2 Normative references

The following documents are referred to in the text in such a way that some or all of their content constitutes requirements of this document. For dated references, only the edition cited applies. For undated references, the latest edition of the referenced document (including any amendments) applies.

ISO 2575, *Road vehicles — Symbols for controls, indicators and tell-tales*

ISO 15006, *Road vehicles — Ergonomic aspects of transport information and control systems — Specifications for in-vehicle auditory presentation*

ISO 15008, *Road vehicles — Ergonomic aspects of transport information and control systems — Specifications and test procedures for in-vehicle visual presentation*

## 3 Terms and definitions

For the purposes of this document, the following terms and definitions apply.

ISO and IEC maintain terminology databases for use in standardization at the following addresses:

- ISO Online browsing platform: available at <https://www.iso.org/obp>
- IEC Electropedia: available at <https://www.electropedia.org/>

**3.1  
audible warning and information**

acoustical signal that is used to present information about relevant obstacles to the driver

EXAMPLE Pulses, speech.

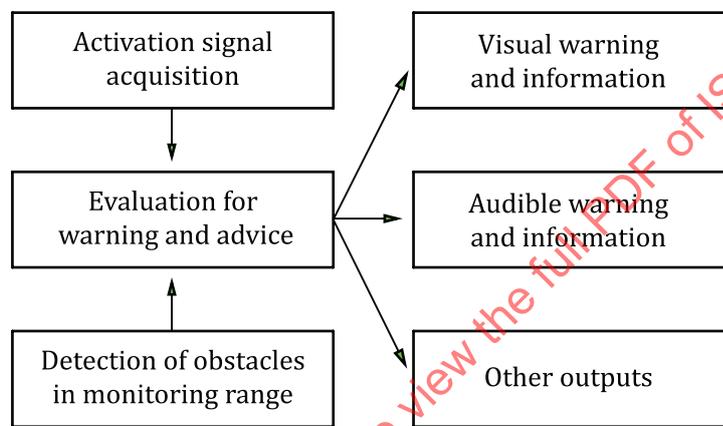
Note 1 to entry: Acoustical pulses can be coded mainly by carrier frequency, repetition rate and position of sound generator.

Note 2 to entry: See [Figure 1](#).

**3.2  
evaluation for warning and advice**

information about detected obstacles that, when the system is activated, is evaluated to warn and advise the driver in order to help with the current low speed manoeuvre

Note 1 to entry: See [Figure 1](#).



**Figure 1 — Block diagram of the potential sub-functions of a manoeuvring aid for low speed operation**

**3.3  
manoeuvring aid for low-speed operation  
MALSO**

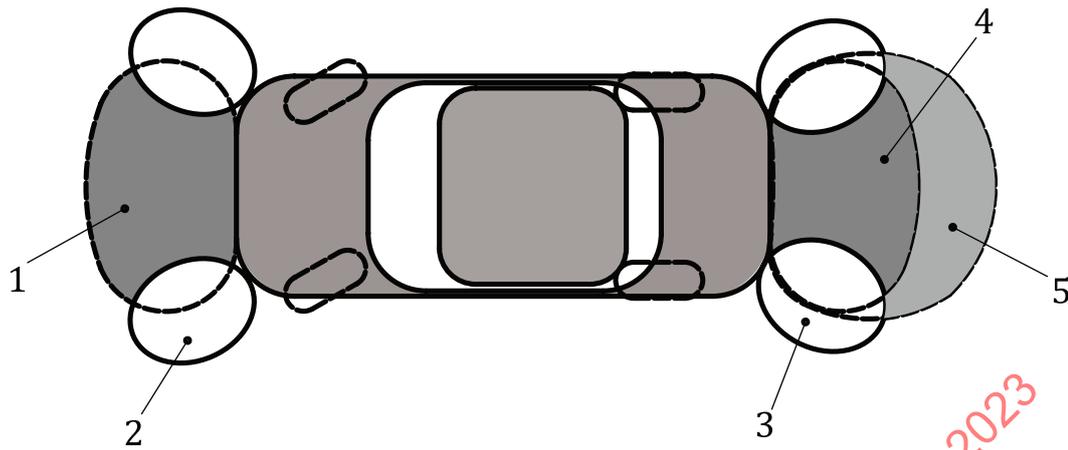
system that, at low speeds (< 0,5 m/s), is capable of informing the driver of the presence of stationary obstacles in particular areas in close proximity to the subject vehicle, mainly during parking and manoeuvring in narrow passages

**3.4  
monitoring range**

specific three-dimensional space around the vehicle, which is divided into rear and front corner monitoring range, front, rear-1 and rear-2 monitoring range

Note 1 to entry: The covered monitoring ranges depend on the intended use of the system (see [Clause 4](#)).

Note 2 to entry: See [Figure 2](#).

**Key**

- 1 front
- 2 front corner
- 3 rear corner
- 4 rear-1
- 5 rear-2

**Figure 2 — Monitoring ranges (plan view)**

**3.5****reversing detection system**

system that gives an indication to the driver, when the reverse gear is selected, whether there are objects in the monitoring range

**3.6****sensor**

component that detects objects in the monitoring range

Note 1 to entry: There are a variety of sensor principles which can be used. The most common principle is the flight time measurement (e.g. radar, lidar, sonar). Active sensor elements create a pulsed or continuously modulated field of microwaves, (infrared) light or ultrasonic sound. The reflected energy due to an object in the detection area is received, and the distance to the object is measured. The lateral position of the object is estimated based on the beam or field directional characteristics, or based on the timing relationships between sensors with overlapping coverage areas. Alternative principles include distance measurement by triangulation principle and passive sensor systems using image processing.

**3.7****system activation**

action of transitioning the system operation from a quiescent mode to an active one in which the system is monitoring the monitoring ranges, evaluating the objects detected and generating appropriate feedback to assist the driver

**3.8****test object**

object with a specific material, geometry and surface for testing the monitoring range

Note 1 to entry: This test object should give comparable results for the relevant sensor types.

**3.9****visual information and warning**

optical signal which is used to present information about relevant obstacles to the driver

EXAMPLE      Telltale, display.

Note 1 to entry: Visual information can be coded, for example, by colour, repetition rate, symbols or text. The driver can be warned by continuous or pulsating signalling of possibly coloured telltales. Information can be graphical or alphanumeric.

**3.10 warning levels**

progressive critical levels of audible/visual/tactile/kinaesthetic information or feedback to the driver regarding the hazard environment

**4 Classification**

The MALSO system classification reflects the diversity of driving behaviour and market demand in different regions of the world. For example, in certain countries, drivers manoeuvre within a very tight area and have come to rely on warnings given at very short range. In other regions, drivers expect warnings to be given at a relatively longer range. A manufacturer may select the most suitable system parameters based on the driving style and expectations of the target driver population.

The Manoeuvring Aids for Low Speed Operation are classified according to their capability of covering the different monitoring ranges. Each monitoring range corresponds to a particular part of the vehicle boundary to prevent colliding with an obstacle. See [Figure 2](#). The class of the system is indicated by an abbreviation corresponding to the monitoring ranges covered.

**Table 1 — Classification of Manoeuvring Aids for Low Speed Operation — Abbreviations of monitoring ranges**

Monitoring range	Abbreviation	Detection distance	Maximum driving speed
		m	m/s
Rear-1	R1	0,6	0,3
Rear-2	R2	1,0	0,5
Rear corner driver side	Rcd	0,5	0,3
Rear corner passenger side	Rcp	0,5	0,3
Front	F	0,6	0,3
Front corner driver side	Fcd	0,5	0,3
Front corner passenger side	Fcp	0,5	0,3

Any combination of monitoring ranges may be used if it is beneficial for the intended use of the system.

The corner type systems have monitoring ranges restricted to particular corners of the vehicle and are mainly intended to assist the driver while driving through narrow passages.

For convenience and most efficient use of the manoeuvring aid, the driver shall be informed about the type of system the vehicle is equipped with, according to the classification above.

**5 Functional and performance requirements**

**5.1 System activation**

**5.1.1 Systems with manual activation**

The system is turned on and off by the driver with a switch or push-button. After activation, the system may indicate readiness for service acoustically or visually. This indication shall be clearly distinguishable from distance information about obstacles.

### 5.1.2 Systems with automatic activation

The system is activated/deactivated automatically according to the driving situation. The possible monitoring ranges (see [Clause 4](#)) may be activated separately in order to avoid nuisance signals. After automatic activation, readiness for service may be indicated to the driver. There may be an on/off switch or push-button to override automatic (de)activation.

Recommended activation and deactivation criteria are the gear selection (reverse/forward), the vehicle speed,  $v$ , and the travelled distance,  $x$ , since system activation as described in [Table 2](#). Further criteria may be used by the OEM to improve comfort or safety of the system. The system shall be activated according to [Table 2](#) if the vehicle speed,  $v$ , is greater than zero. In the case that the vehicle speed,  $v$ , equals zero, application of [Table 2](#) is up to the manufacturers.

The vehicle speed  $v_{on}$  for activation and  $v_{off}$  for deactivation shall be  $\geq 0,5$  m/s or  $0,3$  m/s, depending on the monitoring range under consideration (see [Table 1](#), maximum driving speed).

**Table 2 — System activation/deactivation criteria**

Monitoring range	Reverse gear selected	Gear other than reverse is selected	
		$v < v_{on}$	$v \geq v_{off}$ OR $x > x_{off}$
Front	o	+	-
Front corners	o	+	-
Rear	+	o	-
Rear corners	+	o	-
"o" indicates optional "+" indicates active "-" indicates inactive			

On vehicles with automatic transmission, the MALSO system may be deactivated if the P (parking) gear position is selected. It is also possible to deactivate the system while the parking brake is engaged.

## 5.2 Driver interface and information strategy

### 5.2.1 General information presentation

For the driver interface, at least the audible information channel shall be used. Visual information and warning may be used as a supplement. A standardized information strategy will be the basis for the development of both types of information components, as this makes the use in different vehicles easier and safer. The most relevant information for the driver is the distance, i.e. the clearance, between the vehicle boundary and an obstacle. The location of the obstacle relative to the vehicle may be indicated as additional information.

Failures shall also be indicated to the driver.

A general information strategy cannot be established because of the following reasons:

- there are many different ways of coding the information;
- each car manufacturer will integrate the manoeuvring aids into its driver-information system with its specific driver interface.

[Subclauses 5.2.2](#) to [5.2.5](#) may be regarded as guidance in the implementation of an information strategy.

### 5.2.2 Audible information

The audible information shall be presented in accordance with ISO 15006.

The following basic code is recommended for the audible information channel.

- a) Distance should be coded into at least two levels. These zones may be represented by different repetition rates, with the basic rule that a high repetition rate or a continuous sound corresponds to short distances. If a different or an additional code is used, it should not interfere with the basic rule.
- b) The different areas may be represented by different carrier frequencies (e.g. high frequency for the front, low frequency for the back of the vehicle). In this case, not more than two different areas/ carrier frequencies should be used. Synthesized or recorded voice messages may also be used.
- c) The activation/deactivation of the system and the indication of failure/disturbance may be presented by an audible signal, clearly distinguishable from the other signals.

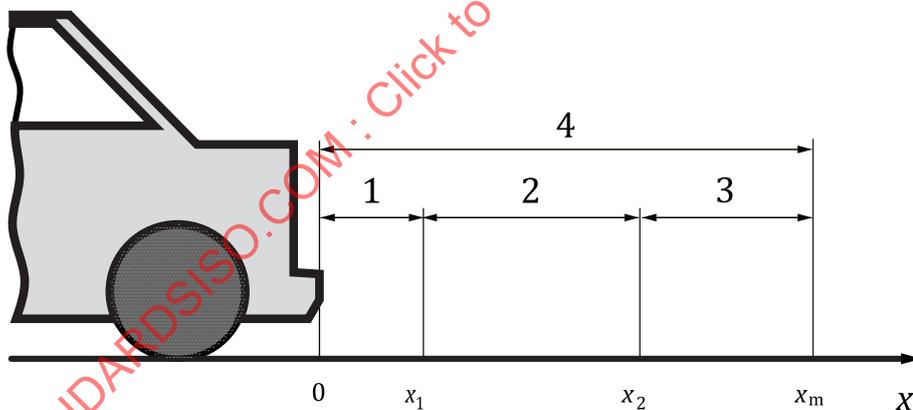
**5.2.3 Visual information**

The visual information shall be presented in accordance with ISO 15008.

If the visual information channel is used as a supplement to the audible channel, the following basic code is recommended.

- a) The information should be codified into at least two levels, represented by multiple colours: for example, red for level 1 (imminent collision level) and yellow or green for level 2 (attention level). If a different code or an additional advisory level is used, it should not interfere with these basic code elements. The two levels may be subdivided by using more than one display element with the same colour, e.g. a bar graph with three red and three yellow bars, allowing for six sub-levels. If a monochromatic element is used instead of multiple colours, the two levels may be represented by a combination of continuous and flashing illumination, or a display consisting of incremental bars.

Figure 3 shows the warning levels for the rear monitoring range.



**Key**

1 level 1	$x$	distance to vehicle
2 level 2	$x_1$	distance to beginning of level 1
3 advisory level	$x_2$	distance to beginning of level 2
4 rear monitoring range	$x_m$	distance to beginning of advisory level

**Figure 3 — Warning levels for rear monitoring range**

- b) The display should be located so as to minimize the likelihood of inducing drivers to change their direction of vision. For example, it is recommended to place the display for the rear monitoring range in the rear part of the passenger compartment, because this allows drivers to watch the display while simultaneously looking through the rear mirror or over their shoulder directly through the rear window. For the same reason it is recommended to locate the display for the front monitoring range in the dashboard.

- c) It is recommended to indicate the activation/deactivation and malfunction of the system by a telltale or a symbol in all active displays of the system. These symbols shall be in accordance with ISO 2575.

#### 5.2.4 Combination of visual and audible information

A combination of visual and audible information may be used to improve the system performance or to reduce the possibility of annoying the driver and passengers, taking into account the specific advantages of both information channels.

Level 1 (imminent collision level) information shall be given audibly and may additionally be given visually; level 2 (attention level) information may, however, be given by the visual or the audible channel only.

If the intensity of the audible information presentation can be reduced by the driver, e.g. from a menu of the onboard human-machine interface (HMI) system, there should be a note in the user manual or a message in the dialog with the HMI system, stating that warnings will possibly not be perceived in time if the volume is set too low.

#### 5.2.5 Duration of signalling

In general, the signalling of an obstacle shall be maintained as long as the obstacle is detected and shall cease when the obstacle is no longer detected or the system is deactivated. For activation/deactivation criteria of the system and specific monitoring ranges refer to [5.1](#).

In order to reduce annoyance of the driver, the system may automatically switch off the audible signal temporarily after a certain time (to be defined by the manufacturer). The system, however, shall remain in the active state.

As soon as the distance to the obstacle decreases, the audible signal shall be switched on automatically again. In the case of an increasing distance to the obstacle the audible signal may remain switched off.

If a visual display supplements the audible information channel, the system may automatically switch off the audible signal temporarily as described in this subclause. The visual signalling, however, should be maintained.

The driver may select temporary suppression of the audible signal manually. In this case the audible signal shall remain suppressed until the driver switches it on again; however, the audible signal shall be automatically reinstated when the system is activated the next time. For activation conditions, refer to [5.1](#).

### 5.3 Dynamic performance of object detection

#### 5.3.1 Relative velocity of objects

The system shall be able to detect stationary objects while the vehicle itself is either stationary or moving at a speed up to at least 0,3 m/s. Systems classified R2 (see [Table 1](#)) shall be able to detect stationary objects in the rear-2 monitoring range while moving at a speed up to at least 0,5 m/s. It is up to the manufacturer to extend the speed range to higher speeds.

#### 5.3.2 Start-up detection delay

As one major application of MALSO systems is to support the driver directly after starting the vehicle the MALSO system shall provide information about the monitoring range and warning about relevant obstacles in the monitoring range in a time period that enables the driver to react properly and in time.

The start-up detection delay definition strongly depends on the overall vehicle equipment (e.g. HMI concept for MALSO, readiness for service indication of MALSO, automatic/manual transmission, automatic/manual parking brake) which determines the readiness to start driving after ignition on or

after a stop. Therefore, it is not possible to specify a dedicated limit for the start-up detection delay and it is up to the manufacturer to keep the start-up detection delay as low as necessary for safe and comfortable manoeuvring. As a general indication, a warning about a relevant obstacle should be provided even when the vehicle immediately starts moving 1,5 s after ignition on.

### 5.3.3 Detection latency

As long as the system is active, the time delay between a relevant obstacle entering the corresponding monitoring range and presentation of the correct information to the driver shall not exceed 500 ms in all monitoring ranges. This capability is proved by a suitable test procedure with an accuracy better than 50 ms.

For reference, examples of test procedures are given in [Annex A](#).

The delay is calculated as the arithmetic mean of at least ten tests. The mean delay to indication within these tests shall not exceed 500 ms and no single value shall exceed 600 ms.

## 5.4 Monitoring range coverage

### 5.4.1 Sections of the monitoring range

As shown in [Figure 2](#), the total monitoring range is divided into seven monitoring ranges. Each monitoring range is characterized by horizontal and vertical areas of relevance.

### 5.4.2 Horizontal areas of relevance

The horizontal areas of relevance are the two-dimensional projections of the monitoring ranges on to the driveway. The minimum detection distances as measured from the vehicle boundary are defined in [Table 1](#).

The first 0,2 m starting from the vehicle boundary (see [Figure 4](#)) shall not be tested, because state-of-the-art sensing technology cannot guarantee detection in this close proximity.

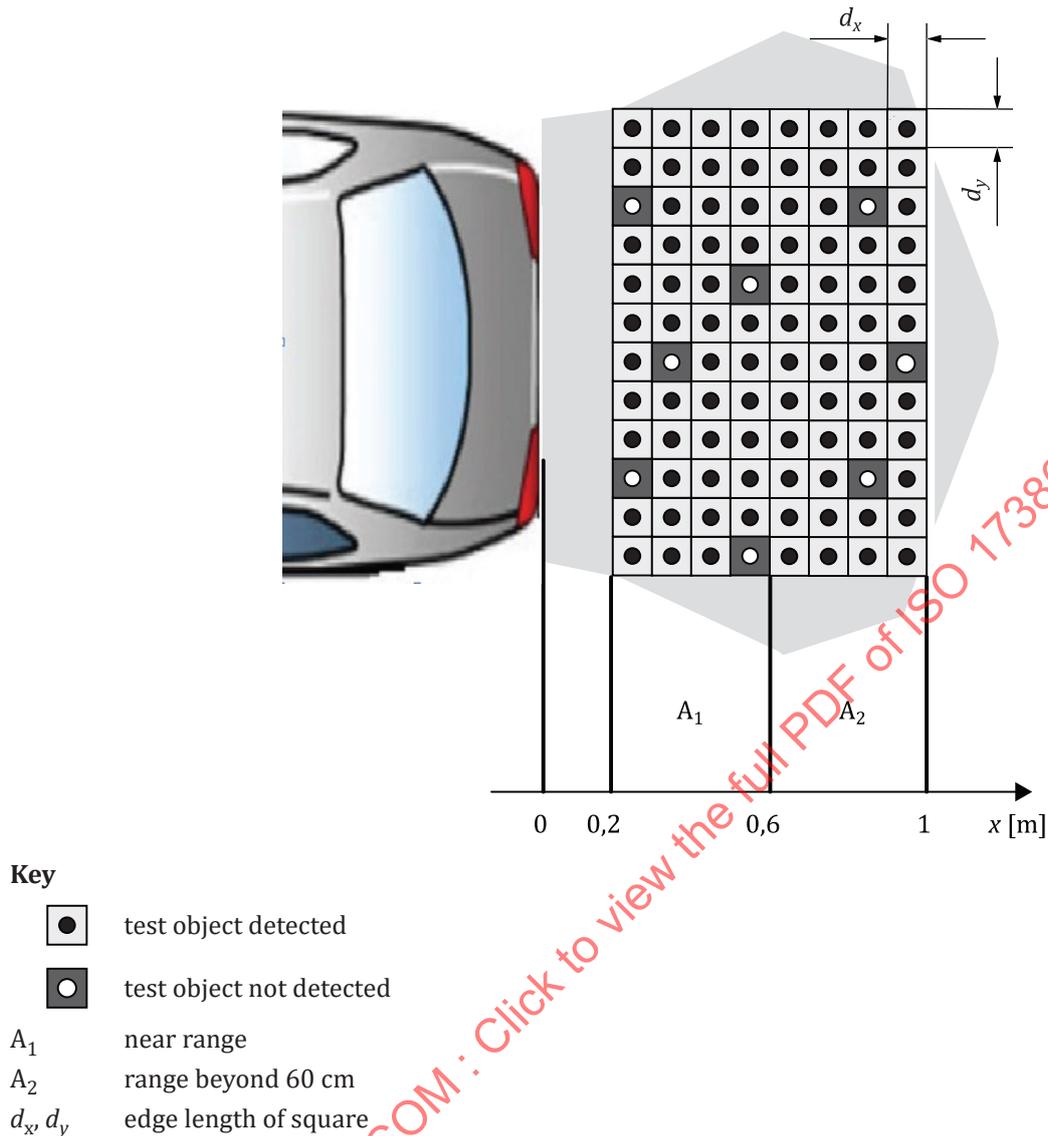
In order to perform the operational test described in [Clause 7](#), the relevant monitoring range shall be scanned horizontally with test object H, vertically with test object V. Each detected grid position is represented by a covered square with edge lengths labelled  $d_x$  and  $d_y$  ( $d_x = 0,1$  m,  $d_y = 0,1$  m for testing the horizontal coverage) and its centre at the position of the longitudinal axis of the standard obstacle.

The coverage ratio is defined as the ratio of the covered area over the total area of relevance.

**EXAMPLE** For a total area of relevance of 96 cells with a covered area of 88 cells, the average coverage ratio is 91,7 %. The area of a single detection hole is defined as the square corresponding to a “not detected” standard obstacle.

**NOTE** The small error due to the overestimation of the area by the integer number of cells can be neglected.

For the evaluation of the performance tests, the monitoring range is divided into a near range,  $A_1$ , that extends from the vehicle boundary up to 0,6 m, and  $A_2$  which covers the range beyond 0,6 m. These sub-areas are not related to the warning-level ranges. An example is shown in [Figure 4](#) for the rear horizontal area of relevance. The coverage ratio shall be determined separately for each of the two sub-areas.



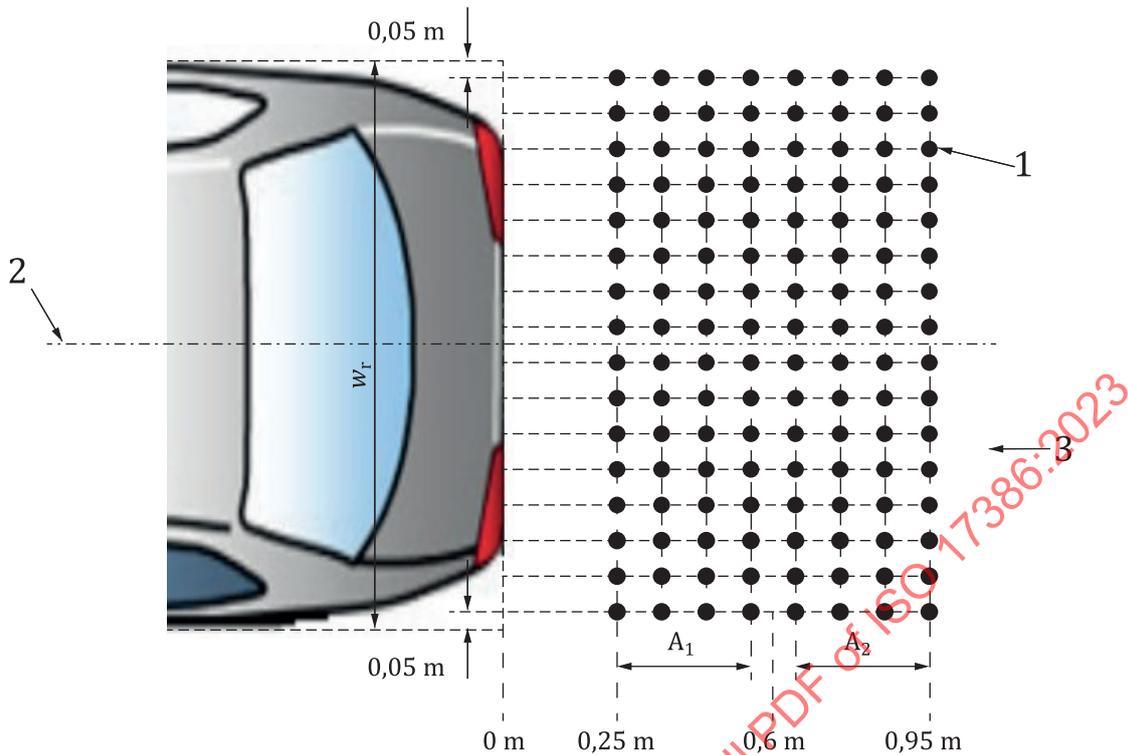
**Figure 4 — Determination of the rear horizontal coverage ratio in the sub-areas  $A_1$  and  $A_2$**

### 5.4.3 Rear horizontal area

In order to simplify the performance test procedure, the rear horizontal area of relevance is represented by a rectangle that begins 0,2 m off the rear vehicle boundary and extends to the maximum detection distance, which is 0,6 m for R1 and 1,0 m for R2.

The width of the rectangle,  $w_r$ , is equal to the vehicle width, measured along the rear axle. The dimensions shall be rounded up to the nearest 0,1 m.

The grid positions of the centre of test object H within this rectangle are shown in [Figure 5](#). The grid is arranged symmetrically to the vehicle centre line.



**Key**

- 1 positions of test object centre
- 2 vehicle centre line
- 3 grid 0,1 m × 0,1 m
- $w_r$  vehicle width along the rear axle
- $A_1$  near range
- $A_2$  range beyond 60 cm

**Figure 5 — Grid positions for testing the horizontal coverage of the rear monitoring range**

**5.4.4 Front horizontal area**

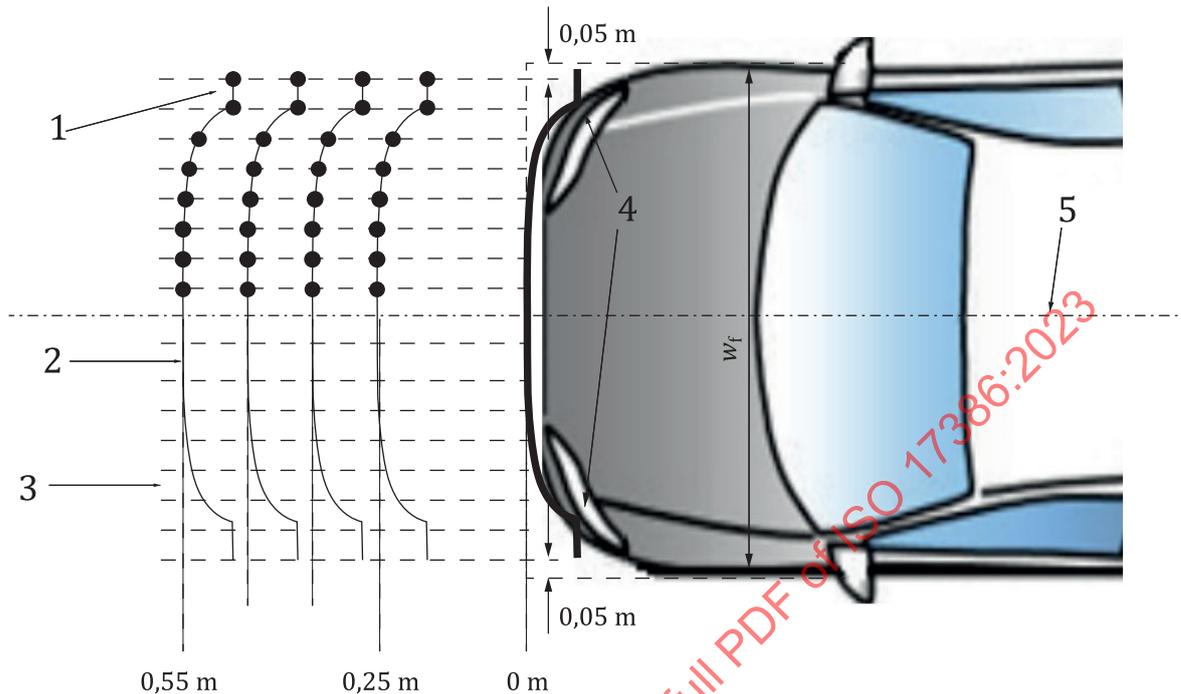
The front horizontal area of relevance is represented by an area that begins 0,2 m off the front vehicle boundary and extends to the maximum detection distance, which is 0,6 m. The width of this area,  $w_f$ , is equal to the vehicle width, measured along the front axle. The dimensions shall be rounded up to the nearest 0,1 m.

In contrast to the rear horizontal area of relevance, which is simply a rectangle, the test grid positions of the front horizontal area are located on an area that follows the contour of the front bumper which has a distinctive convex shape on many vehicles. There are two different methods to construct the test grid which give comparable test results. The test engineer responsible for conducting the test may choose the method that suits best the capabilities of the available test equipment. In either case the grid is arranged symmetrically to the vehicle centre line.

**Method 1:**

The distance lines perpendicular to the driving direction are replaced by a curve that follows the shape of the front bumper. The curve is displaced in parallel in the driving direction by multiples of 0,1 m. By using this curve instead of straight lines, the distance to obstacles in the driving direction is always referred to the vehicle surface, even in cases with extremely round or arrow-shaped front bumpers. The curve follows the shape of the front bumper (vertical projection on the ground as shown in [Figure 6](#)) between the two constructed vehicle corners. For the construction of the corners, see [Figure 7](#). Left and

right of the corners, the curve is completed by straight sections perpendicular to the driving direction to cover the whole vehicle width,  $w_f$ .



#### Key

- 1 positions of test object centre
- 2 shape of front bumper
- 3 grid 0,1 m × 0,1 m
- 4 constructed vehicle corners
- 5 vehicle centre line
- $w_f$  vehicle width

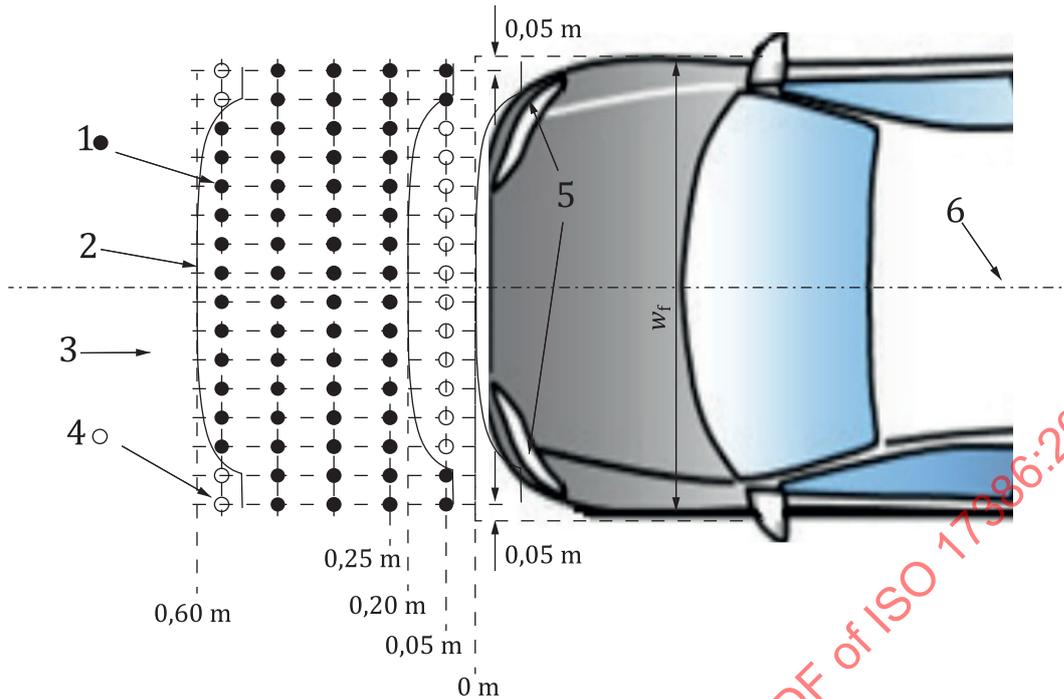
NOTE The positions of the test object centre are shown only in the upper part of the figure (right side of vehicle).

**Figure 6 — Grid positions for testing the horizontal coverage of the front monitoring range following Method 1**

#### Method 2:

The underlying grid is still rectangular, similarly to the rear horizontal area. However, the tested grid positions are cut out of the rectangle by two curves that follow the shape of the front bumper (vertical projection on the ground as shown in Figure 7) between the two constructed vehicle corners. For the construction of the corners, see Figure 8. Left and right of the corners, the curve is completed by straight sections perpendicular to the driving direction to cover the whole vehicle width,  $w_f$ .

The first curve has a distance of 0,2 m to the bumper, measured on the vehicle centre line; the second curve has a distance of 0,6 m.



**Key**

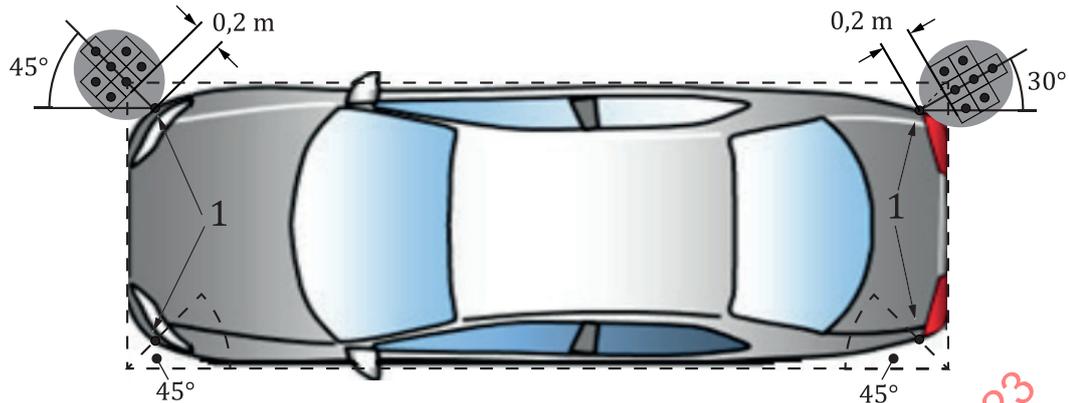
- 1 positions of test object centre
- 2 shape of front bumper
- 3 grid 0,1 m × 0,1 m
- 4 positions not required
- 5 constructed vehicle corners
- 6 vehicle centre line
- $w_f$  vehicle width

**Figure 7 — Grid positions for testing the horizontal coverage of the front monitoring range following Method 2**

**5.4.5 Corner horizontal areas**

For the definition of the corner horizontal areas of relevance, the following brick definition method shall be used:

- 1) Draw a rectangular box close around the vehicle outline.
- 2) Draw lines from each box corner to the vehicle at an angle of 45°.
- 3) The intersections of these lines and the vehicle boundary are the vehicle corners.
- 4) The elliptical areas at each corner indicate the horizontal areas of relevance to be evaluated in the test procedure using seven square grid positions with  $d_x = d_y = 0,1$  m (refer to [Figure 8](#)), the centres of which correspond to the positions of the longitudinal axis of the standard test obstacle.
- 5) The inclination of the ellipses to the straight forward/backward direction is 30° for the rear corners and 45° for the front corners.

**Key**

- 1 constructed vehicle corners

**Figure 8 — Brick definition of vehicle corners and minimum corner detection ranges**

#### 5.4.6 Minimum coverage ratios

The minimum required coverage ratios for the front and rear horizontal areas of relevance are as follows:

- 90 % in  $A_1$ ;
- 87 % in the rear-2 area of  $A_2$ .

The minimum coverage ratios for corner areas of relevance shall be 100 %.

Within the whole monitoring range, there shall be no more than two contiguous detection holes in a straight line, either horizontally, vertically or diagonally in the horizontal plane.

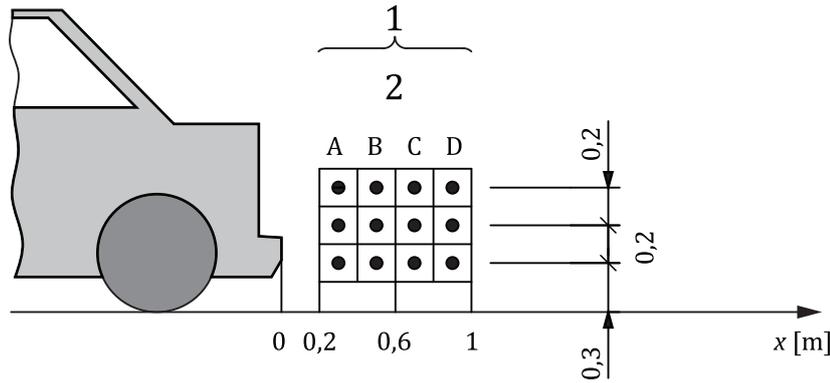
#### 5.4.7 Vertical areas of relevance

In order to simplify the performance test procedure, the vertical areas of relevance are represented by rectangles that begin 0,2 m off the vehicle boundary and extend to the maximum detection distance in the particular monitoring range (see [Clause 4](#)). In the front and the rear monitoring range, the test shall be carried out using test object V placed in a vertical plane coinciding with the longitudinal axis of the vehicle. Refer to the horizontal monitoring ranges, shown in [Figure 8](#), for the inclination of the corner vertical areas of relevance with respect to the vehicle boundary.

For testing the vertical coverage, it is sufficient to use a 0,2 m grid ( $d_x = d_y = 0,2$  m), since the capability of covering the whole area without excessive holes is already proven by the test of the horizontal areas. The height of the rectangles is 0,6 m, corresponding to three lines of grid squares, the centres of which correspond to the positions of the longitudinal axis of the standard test obstacle.

An example for the rear monitoring range is depicted in [Figure 9](#).

The centre of the lower line shall be 0,30 m above ground. In order to allow for the angular detection characteristics and different installation height of common sensors, at least one cell in column A (nearest to the bumper) shall be covered.



- Key**
- 1 rear vertical area of relevance
  - 2 column of test object grid
  - test object grid position

**Figure 9 — Determination of the rear vertical area coverage ratio by the test procedure**

The minimum coverage shall be as defined in [Table 3](#). See [Table 1](#) for the detection distances within the different monitoring ranges.

**Table 3 — Vertical coverage (minimum number of covered cells)**

Monitoring ranges	Column			
	A	B	C	D
Rear-2	1	2	2	1
Rear-1 and front	1	2	0	0
Rear and front corner	1	1	0	0

**5.5 Self-test capabilities and failure indication**

The system shall provide the following self-test functions (at least after each system activation):

- a) electronic circuit and wiring      The self-test unit shall check the function of the electronic components of the system.
- b) sensor components                  The self-test unit shall check whether there is any damage to the sensor elements which would lead to a malfunction of the system.

Procedures a) and b) shall:

- be executed automatically to detect faults leading to a failure of the system function;
- generate a warning signal [see [5.2.2 c\)](#) and [5.2.3 c\)](#)] whenever a fault condition is detected.

**5.6 Operation with trailers**

**5.6.1 Trailer hitch handling**

A trailer hitch mounted on the host vehicle can potentially affect the proper function of the sensors on the one hand and can potentially extend the rear boundary of the vehicle on the other.

Especially if a detachable trailer hitch is used, particular care shall be taken to ensure that the mounting of the hitch will not result in poor coverage of the rear monitoring range. It shall be taken into account

that the hitch will most probably protrude beyond the bumper and will thus determine the vehicle boundary.

If proper functioning with the hitch mounted cannot be effected, either the system shall automatically shut off when a hitch is mounted or the driver shall be able to deactivate the system manually. The user manual of the vehicle shall describe the appropriate operation in these cases.

### 5.6.2 System operation with trailer

For systems that cannot be deactivated manually, the electrical circuit of the vehicle shall be designed in such a way that the reversing detection system will automatically be suspended as soon as the electrical connection between towing and trailing vehicle is in operation. However, if the trailer is fitted with compatible sensors, these should now inform the driver of obstacles whilst reversing.

## 6 Requirements and tests components

The system components shall be designed according to specific automotive requirements. This shall be proved by standardized tests defined by the car manufacturer. As an alternative to car manufacturers' specific test procedures, ISO 16750 (all parts) may be the basis for component test procedures.

## 7 Operational test of obstacle detection

### 7.1 Test object

#### 7.1.1 Standard test object definition

The purpose of this subclause is to define the requirements of the standard test objects to be used when testing a system's obstacle detection capability.

**NOTE** If certain sensing technologies require a different standard, this needs to be investigated and evaluated. The plastic pipe for ultrasonic-based systems was chosen because it is commercially available, inexpensive, easily replaced in case of loss or damage, and easily transportable. For the same reasons the metal pipe for radar-based systems was chosen. Furthermore, it provides a well-defined radar cross-section (RCS) signature for any given frequency.

It is recognized that these test objects will represent different echo characteristics to different sensors, but this is true for any object chosen. The intent is to keep a constant test object that is representative of at least some of the expected real-world application objects (i.e. a round wooden, metal or concrete pole).

The geometry, reflection and absorption properties of the test object should lead to easy testability and good representation of a real obstacle. The standard obstacle should not favour one of the physical principles and should represent the most relevant objects in real manoeuvring situations. The intent of standardizing the test object is so that embodiments (systems) from various suppliers can be designed and manufactured with comparable performance to ensure that the minimum performance expectations of the driver are fulfilled.

#### 7.1.2 Ultrasonic-based systems

Reflectivity measurements on relevant objects have been conducted. Experiments have shown that the reflection of ultrasound does not significantly change for different materials, as long as the surface is smooth and hard for sound. For instance, metal and wooden poles exhibit the same sonic reflectivity as plastic poles of the same diameter (see [Table 4](#)). It should be noted that for use as a test object, metal poles are more rigid and can be more accurately manufactured.

Table 4 — Test objects for ultrasonic-based systems

Monitoring range		Material	Diameter mm	Length m
Horizontal areas (Test object H)		Wood, metal or hard plastic	75	$1_{+0,2}^0$
Vertical areas  (Test object V)	Rear-1, rear-2, front	Wood, metal or hard plastic	75	Length equal to width of test ve- hicle bumper plus 20 % to 40 %
	Corners	Wood, metal or hard plastic	75	$1_{+0,2}^0$

### 7.1.3 Radar-based systems

Reflectivity measurements on relevant objects have been conducted. The results of this testing proved that the tubular test objects listed in [Table 5](#) are suitable as representations of real objects that were detectable by systems using radar-based sensors.

Table 5 — Test objects for radar-based systems

Monitoring range		Material	Diameter mm	Length m
Horizontal areas Test object H		Metal	25	$1_{+0,2}^0$
Vertical areas  Test object V	Rear-1, rear-2, front	Metal	25	Length equal to width of test vehicle bumper plus 20 % to 40 %
	Corners	Metal	25	$1_{+0,2}^0$

## 7.2 General ambient conditions

During testing, the wind speed shall not exceed 5,4 m/s (wind force 3). Temperature shall be between 5 °C and 30 °C under non-precipitating conditions (not raining, sleeting, snowing, etc.). The test location shall be on a flat, dry, asphalt or concrete surface. The tests shall not be affected by reflections, neither of sonic nor of electromagnetic waves from walls in the environment, auxiliary test equipment or other objects.

## 7.3 Test procedure

### 7.3.1 Test setup

Perform the operational test on a vehicle or test structure that allows the installation conditions of the selected vehicle model or selected vehicle range to be reproduced. In case a vehicle is used to perform the test, it shall have curb weight. A tolerance of +5 % may be allowed. If the ride height is adjustable, it shall be set to normal driving condition on paved roads.

Sensor surfaces shall be visibly clean and free of contamination.

Depending on the class of the manoeuvring aid (see [Clause 4](#)), the detection performance shall be tested in the rear monitoring range, the front monitoring range and the corner monitoring ranges.

When testing the detection performance, care shall be taken to ensure that the activation criteria for the monitoring range under consideration are fulfilled. It shall be ensured that the relevant information is presented to the driver in a time period that enables the driver to react.