

El cotxe autònom a les competicions de *formula student* 

SEAT

LAS ORCHAYS

ADALLES

LEAND











**Reuse electric car** 

## **OUR TEAM**

**Compare with EV team** 

## **THE AUTONOMOUS SYSTEM**



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NAME AND POST OF TAXABLE PARTY.

a states



### **Stereo camera matching**

### LiDAR point cloud clustering

### **Sensor fusion**





### Stereo camera matching







### LiDAR point cloud clustering





velodyne

### **Sensors calibration**







### **Point cloud projection**

**Sensors fusion** 





![](_page_10_Figure_2.jpeg)

### **Cone detection**

### -Point cloud translation & projection

### -Detection: from 2D to 3D

![](_page_10_Picture_6.jpeg)

![](_page_10_Figure_7.jpeg)

![](_page_10_Picture_8.jpeg)

### **Sensors fusion**

![](_page_10_Picture_10.jpeg)

## THE AUTONOMOUS SYSTEM

![](_page_11_Figure_1.jpeg)

![](_page_12_Picture_0.jpeg)

![](_page_12_Picture_3.jpeg)

![](_page_12_Picture_4.jpeg)

![](_page_13_Figure_1.jpeg)

![](_page_14_Picture_0.jpeg)

specific at

![](_page_14_Picture_3.jpeg)

## control

![](_page_15_Figure_1.jpeg)

Planner points

Equispaced in <u>time</u> Difference in distance

Target speed

![](_page_15_Figure_5.jpeg)

![](_page_16_Picture_0.jpeg)

**fo**llowspectfie

![](_page_16_Picture_3.jpeg)

![](_page_17_Figure_0.jpeg)

![](_page_17_Figure_1.jpeg)

## **THE AUTONOMOUS SYSTEM**

![](_page_18_Figure_1.jpeg)

### **MicroAutoBox II**

![](_page_19_Picture_2.jpeg)

# dSPACE ==

![](_page_19_Picture_4.jpeg)

0

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![](_page_19_Picture_5.jpeg)

V

![](_page_19_Picture_6.jpeg)

![](_page_19_Picture_7.jpeg)

![](_page_19_Picture_8.jpeg)

## **JETSON TX2**

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![](_page_19_Picture_10.jpeg)

![](_page_19_Picture_11.jpeg)

**Remote Emergency System** 

11

LiDAR

**Emergency Brake System** + Service Brake

ETSEI

Pedals

dSpace

![](_page_20_Picture_5.jpeg)

in a

![](_page_21_Picture_1.jpeg)

![](_page_22_Picture_0.jpeg)

14/20

![](_page_22_Picture_2.jpeg)

![](_page_22_Picture_3.jpeg)

![](_page_22_Picture_4.jpeg)

## 2018-2019 season

![](_page_22_Picture_9.jpeg)

combustion, electric, driverless

![](_page_22_Picture_11.jpeg)

![](_page_22_Picture_12.jpeg)

![](_page_22_Picture_13.jpeg)

Formula Student Electric & Driverless Team Universität Stuttgart

![](_page_22_Picture_15.jpeg)

Cost event

**Business** Plan

**Engineering Design** 

![](_page_22_Picture_19.jpeg)

![](_page_22_Figure_20.jpeg)

![](_page_22_Picture_21.jpeg)

![](_page_22_Picture_22.jpeg)

![](_page_23_Picture_0.jpeg)

![](_page_23_Picture_1.jpeg)

One team, two cars

![](_page_23_Picture_3.jpeg)

### BUILD A COMPETITIVE CAR

We know that the vehicle works, now we want to win

![](_page_23_Picture_6.jpeg)

### GO TO FSG

If you want to compete with the best teams, you must go to the best competition

### TEAM BUILDING

**Teamwork and share spaces outside workshop work** 

### FUSION OF EL + DV

Lay the groundwork of the next season when the team will only make one car.

![](_page_23_Figure_13.jpeg)

![](_page_24_Picture_1.jpeg)

### Same system design, improve algorithms

- Improve detection
  - Range: 15m
  - FOV: >120°
- Robustness to high speeds
  - New NN architecture
  - LiDAR movement compensation

![](_page_24_Picture_9.jpeg)

![](_page_25_Figure_0.jpeg)

![](_page_26_Picture_1.jpeg)

![](_page_26_Picture_2.jpeg)

![](_page_27_Figure_1.jpeg)

![](_page_27_Picture_2.jpeg)

![](_page_27_Picture_3.jpeg)

![](_page_27_Picture_4.jpeg)

![](_page_28_Picture_0.jpeg)