

Amendments to ECE/TRANS/WP.29/GRVA/2021/12

This document is based on informal GRVA-10-13 prepared by the Task Force on Advanced Driver Assistance System (ADAS). It includes the modifications introduced during the tenth session of the Working Party on Automated/Autonomous and Connected Vehicles (GRVA) at its tenth session, which are highlighted in yellow.

(Text in red colour are amendments to document ECE/TRANS/WP.29/GRVA/2021/12.)

Proposal

Paragraph 2.4.8., amend to read:

“2.4.8. *"Remote Controlled Parking (RCP)"* means an ACSF of category A, actuated by the driver, providing parking or low speed manoeuvring. The actuation is made ~~by remote control~~ in close proximity to the vehicle.”

Paragraph 2.4.9., amend to read:

“2.4.9. *"Specified maximum RCP operating range (SRCPmax)"* means the maximum distance between the nearest point of the motor vehicle and the remote control device **or alternatively the driver (for systems based on detection of driver position and movement)**, up to which ACSF is designed to operate.”

Paragraphs 5.6.1.2.1. and 5.6.1.2.2. (5.6.1.2. for reference only), amend to read:

“5.6.1.2. Additional provisions for RCP

5.6.1.2.1. The parking manoeuvre shall be initiated by the driver but controlled by the system. A direct influence on steering angle, value of acceleration and deceleration via the remote-control device **or by the motion movement of the driver** shall not be possible.

5.6.1.2.2. **Either** a continuous actuation of the remote-control device by the driver **or alternatively (for systems based on detection of driver position and motion movement) a continuous motion movement of the driver in the same longitudinal direction as the vehicle**, is required during the parking manoeuvre.”

Paragraph 5.6.1.2.3., amend to read:

“5.6.1.2.3. **For systems based on continuous actuation of the remote-control device, the vehicle shall stop immediately if:**

- (a) The continuous actuation is interrupted; ~~or~~
 - (b) The distance between vehicle and remote-control device exceeds the specified maximum RCP operating range (S_{RCPmax}); ~~or~~
 - (c) The signal between remote control and vehicle is lost.
- the vehicle shall stop immediately.

For systems based on detection of driver position and motion movement, the vehicle shall stop immediately if:

- (a) The continuous ~~motion movement~~ of the driver is interrupted; ~~or~~
- (b) The distance between vehicle and remote-control device **or driver** exceeds the specified maximum RCP operating range (S_{RCPmax}); ~~or~~

- (c) The detection of the driver is lost; or
- (d) There is a rapid increase in the movement speed of the driver.”

Insert a new paragraph 5.6.1.2.9., to read:

5.6.1.2.9. For RCP systems based on detection of driver position and movement, the deactivation referred to in paragraph 3.6.1.1.3. shall be through a simple and obvious action that will be recognised by the system].

New paragraph 5.6.1.3.1.4., insert to read:

“5.6.1.3.1.4. For RCP systems based on detection of driver position and ~~motion~~ movement the manufacturer shall ~~provide the~~ demonstrate to the technical authorities with an explanation service during type approval how a person is identified as the driver, ~~and~~ how this person is tracked and how the driver initiates and terminates control. This shall be subject to agreement of the technical service.”
