



ConnRAD – Connectivity and Resilience for Automated Driving



Final Presentation

23.10.2025

UC1 - Demonstrators

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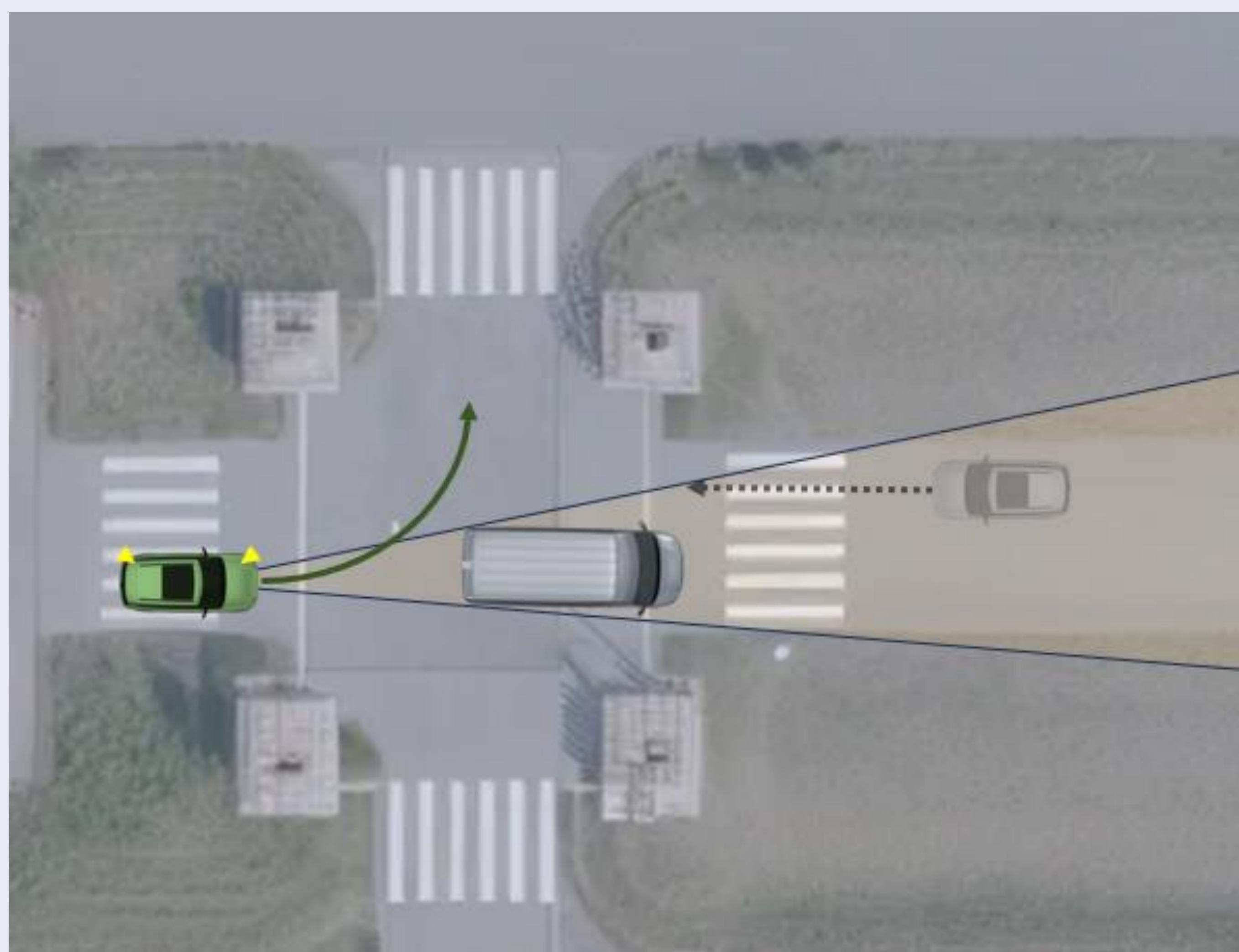
Demonstrator Setup & Scenarios

Base scenario:

Unprotected left turn with limited visibility
from ego perspective and infrastructure
support (Lidar & Radar based perception
system)

Show-case scenarios:

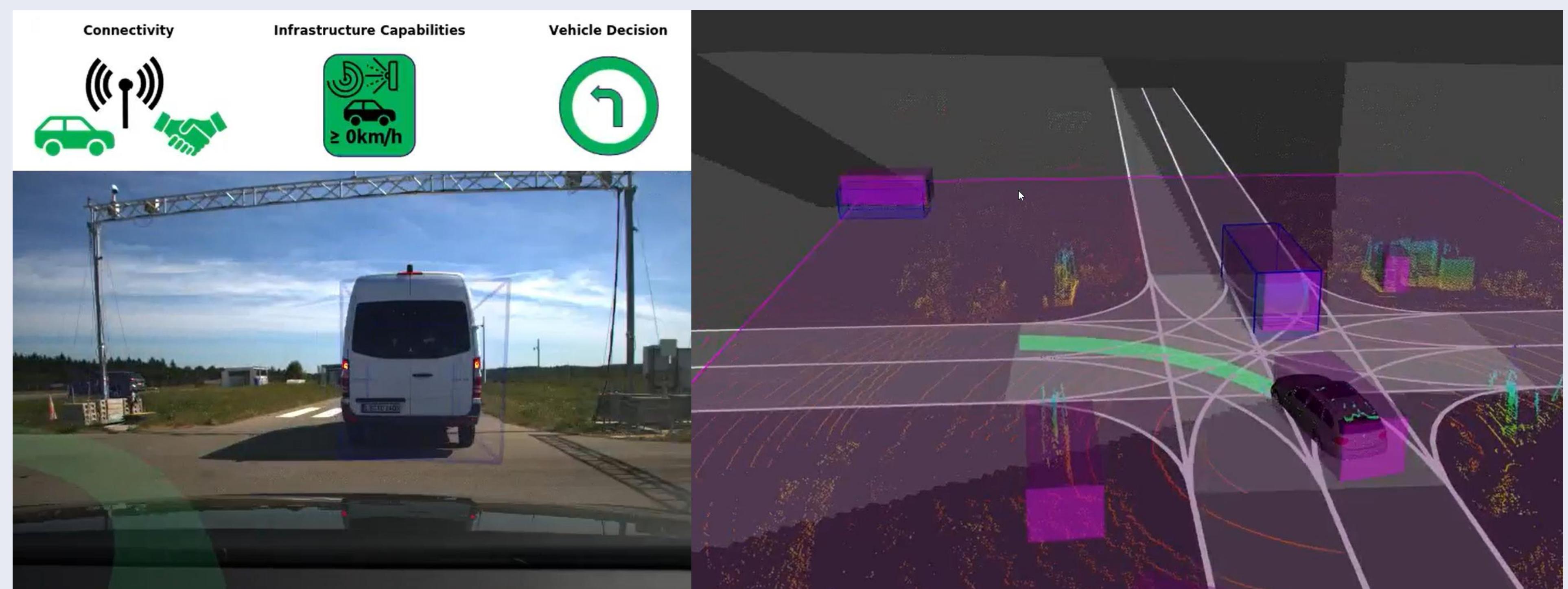
	w/ ConnRAD		w/o ConnRAD	
	trust	no trust	no trust	false trust
w/ oncoming vehicle	stop	stop	turn left (hazardous)	
w/o oncoming vehicle	turn left	stop	turn left	



Test Vehicles

- Lidar (and camera) based object tracking
- Map-based planner with intersection handling
- Unobservable areas determined by visibility grid

- In-vehicle trust evaluation based on sensor capabilities
- Cellular (5G) and WiFi connectivity



Implemented Architecture

