More On Automatic Vehicle Signal Set Matching

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algorithm that would be used to estimate just how close two signals from two disjunctive sets are. The algorithm can be summarized just by a simple formula like this:

$p = \frac{\sum_{i=1}^{n} f_{i}w_{i}}{n}, where f_{i} \in [0,1] and w_{i} \in [0,1],$ $f_{i} is the comparison function, w_{i} is the adjusted weight.$ n is the number of attribute matching functions.

p is a number between 0..1, where the closer you get to 1, the more likely you will have signals that match.

To improve on this (original paper: Ideas for Vehicle Signal Set Matchingt) I have some new ideas presented in a paper: *Dynamic Weight Generation for Vehicle Signal Set Matching*. Here we are replacing static weights that are used to value attributes with some functions that increase the weight depending on the result of a more highly ranked attribute. I decided to value the description attribute higher and use that value for the weight generation. We want the weight to reflect when we believe we have a match, but also at the same time reflect when we believe we do not have a match. This will make sure that units such as m/s are dynamically valued and should prove a better result when we rank matching candidates – at least that is the theory.

The paper explores 3 different mathematical one-variable functions with different complexity. I added a test to see how the different functions handle the comparison where we have signals that match and those that don't although they share the same unit.

I welcome discussion and would like engage with others in solving this problem and turn it into a COVESA project. Please reach out, via COVESA Community Director if interested.