

ASSURING AUTONOMY

Identifying Run-time Monitoring Requirements for AS through Analysis of Safety Arguments Richard Hawkins & Philippa Ryan University of York

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Safety Monitoring for AS



Decision to Deploy

Pre-Deployment

System Development

Assurance Activities



















Our approach

- We currently rely heavily on engineering judgement to define monitoring requirements for AS
 - Difficult to justify the sufficiency of the monitoring
- Our approach uses an explicit analysis of the predeployment safety case to systematically identify run-time monitoring requirements
- Advantages of this approach
 - A) systematic
 - B) provides a way to justify the sufficiency of those monitoring requirements
 - C) Helps to distinguish real safety measures from performance measures
 - Correlation between metric and system-level safety of AS
- Based around the use of *dialectic arguments*













Operational Dialectic Argument

A systematic identification of *potential* runtime challenges to elements of the safety case.

- Prior to deployment these challenges are hypothetical
- However, if the counter-evidence becomes present during operation that challenge becomes valid
- So we must have sufficient monitoring for that counter-evidence
 - This must be put in place prior to deployment of the AS
 - Otherwise the system may be unsafe without system operator realising it
- The starting point is the AS safety case itself...















Identifying Run-time Monitoring Requirements

 Based on the Operational Dialectic Argument we can define:

what needs to be monitored

- System
- Component
- Process
- Operation
- How it can be measured
 - May require fleet-level aggregation
- What is the trigger (threshold)

Op. Evidence	Monitor	Criteria	Trigger
OpEv1 - [operational	Number of missed	Missed detections ob-	#misses/1000 miles
object detection per-	pedestrian detections	served per 1000 miles	exceeds rate report-
formance measures]	across the vehicle	of operation	ing in test results by
	fleet		10%
OpEv2 - [observa-	Input images arising	Measurement of key	Operational images
tions of the context	from the camera for	parameters within	outside of test distri-
of operation]	operation within de-	images (e.g., light	bution
	fined ODD	levels, surfaces,	
		colours etc.)	
OpEv3 - [vehicle	Physical changes	Changes that may	Notification of AV
change reports]	to vehicle platform	impact software per-	platform modifica-
	(such as updates to	formance	tion
	sensors, processors		
	etc.)		
OpEv4 - [Software	Software errors dis-	Errors identified in	Notification of error
bug report]	covered during oper-	object detection dur-	found in object de-
	ation	ing operation	tection
OpEv5 - [AV incident	Reports raised by op-	Incidents that relate	Notification of ob-
reports]	erators of the vehicle	to object detection	ject detection inci-
			dents that may be
			hazardous
OpEv6 - [Camera	Calibration of cam-	Time since last cali-	Greater than 6
maintenance records]	era	bration	months since last
			calibration
OpEv7 - [Camera	Drift measurement of	Rate of drift in oper-	Rate of drifting ex-
drift measurements]	camera images	ation	ceeds design assump-
			tion
OpEv8 - [Object de-	Software version	Change to object de-	Non-approved ver-
tection software up-		tection software	sion of software
date]			running
OpEv9 - [Lidar error	Lidar health moni-	Lidar availability	Lidar fails to provide
status]	toring		output to object de-
			tection component

Op. Evidence	Monitor	Criteria	Trigger		
OpEv1 - [operational	Number of missed	Missed detections ob-	#misses/1000 miles		
object detection per-	pedestrian detections	served per 1000 miles	exceeds rate report-		
formance measures]	across the vehicle	of operation	ing in test results by	N.,	
	fleet		10%		
OpEv2 - [observa-	Input images arising	Measurement of key	Operational images	Тг	2 1/ 22
tions of the context	from the camera for	parameters within	outside of test distri-		Component; Multi-
of operation]	operation within de-	images (e.g., light	bution		vehicle
	fined ODD	levels, surfaces,			
		colours etc.)			
OpEv3 - [vehicle	Physical changes	Changes that may	Notification of AV		
change reports]	to vehicle platform	impact software per-	platform modifica-		Issues:
	(such as updates to	formance	tion		
	sensors, processors				 How do we know
	etc.)				there's been a misse
OpEv4 - [Software	Software errors dis-	Errors identified in	Notification of error		there's been a missed
bug report]	covered during oper-	object detection dur-	found in object de-		detection?
	ation	ing operation	tection		
OpEv5 - [AV incident]	Reports raised by op-	Incidents that relate	Notification of ob-		 How does the data
reports]	erators of the vehicle	to object detection	ject detection inci-		get shared and with
			dents that may be		
			hazardous		wnom?
OpEv6 - Camera	Calibration of cam-	Time since last cali-	Greater than 6		
maintenance records]	era	bration	months since last		
	T	D	calibration		
OpEv7 - [Camera	Drift measurement of	Rate of drift in oper-	Rate of drifting ex-		
drift measurements]	camera images	ation	ceeds design assump-		
	<u> </u>		tion		
OpEv8 - [Object de-	Software version	Change to object de-	Non-approved ver-		
tection software up-		tection software	sion of software		
date]	T 1 1 1 1 1	T • 1 • • • • • • • •	running	-	
OpEv9 - Lidar error	Lidar health moni-	Lıdar availability	Lidar fails to provide		
status	toring		output to object de-		
			tection component		

Op. Evidence	Monitor	Criteria	Trigger	IV At
OpEv1 - [operational	Number of missed	Missed detections ob-	#misses/1000 miles	X/1/
object detection per-	pedestrian detections	served per 1000 miles	exceeds rate report-	- /X //
formance measures]	across the vehicle	of operation	ing in test results by	
	fleet		10%	
OpEv2 - [observa-	Input images arising	Measurement of key	Operational images	
tions of the context	from the camera for	parameters within	outside of test distri-	Process
of operation]	operation within de-	images (e.g., light	bution	
	fined ODD	levels, surfaces,		
		colours etc.)		
OpEv3 - [vehicle	Physical changes	Changes that may	Notification of AV	Issues:
change reports]	to vehicle platform	impact software per-	platform modifica-	
	(such as updates to	formance	tion	 How can we be sure
	sensors, processors			this happens?
	etc.)			
OpEv4 - [Software	Software errors dis-	Errors identified in	Notification of error	Who is responsible
bug report]	covered during oper-	object detection dur-	found in object de-	for checking?
	ation	ing operation	tection	TOT CHECKINg:
OpEv5 - [AV incident	Reports raised by op-	Incidents that relate	Notification of ob-	
reports]	erators of the vehicle	to object detection	ject detection inci-	
			dents that may be	
			hazardous	
OpEv6 - [Camera	Calibration of cam-	Time since last cali-	Greater than 6	
maintenance records]	era	bration	months since last	
			calibration	
OpEv7 - [Camera	Drift measurement of	Rate of drift in oper-	Rate of drifting ex-	
drift measurements]	camera images	ation	ceeds design assump-	
			tion	
OpEv8 - [Object de-	Software version	Change to object de-	Non-approved ver-	
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date]			running	
OpEv9 - [Lidar error	Lidar health moni-	Lidar availability	Lidar fails to provide	
[status]	toring		output to object de-	
			tection component	

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of operation]	operation within de-	images (e.g., light	bution	
	fined ODD	levels, surfaces,		
		colours etc.)		
OpEv3 - [vehicle	Physical changes	Changes that may	Notification of AV	Issues:
change reports]	to vehicle platform	impact software per-	platform modifica-	
	(such as updates to	formance	tion	 How are the
	sensors, processors			notifications
	etc.)			gonorated
OpEv4 - [Software	Software errors dis-	Errors identified in	Notification of error	generated
bug report]	covered during oper-	object detection dur-	found in object de-	• Is it always obvious
	ation	ing operation	tection	• IS IT AIWAYS ODVIOUS
OpEv5 - [AV incident	Reports raised by op-	Incidents that relate	Notification of ob-	which incidents are
reports]	erators of the vehicle	to object detection	ject detection inci-	relevant?
			dents that may be	
			hazardous	
OpEv6 - [Camera	Calibration of cam-	Time since last cali-	Greater than 6	
maintenance records]	era	bration	months since last	
			calibration	
OpEv7 - [Camera	Drift measurement of	Rate of drift in oper-	Rate of drifting ex-	
drift measurements]	camera images	ation	ceeds design assump-	
			tion	
OpEv8 - [Object de-	Software version	Change to object de-	Non-approved ver-	
tection software up-		tection software	sion of software	
date]			running	
OpEv9 - [Lidar error	Lidar health moni-	Lidar availability	Lidar fails to provide	
[status]	toring		output to object de-	
			tection component	

Post-deployment

What happens when a trigger occurs?

- This represents a "live challenge" in the safety case
 - E.g. OpEv1 No. of missed pedestrian detections per 1000 miles is higher than was claimed in the safety case
- Are there any possible rebuttals to the challenge
- What should the response be?
- Must identify responsible organisations and create processes to track and review monitors and triggers
 - the effectiveness of these also needs to be justified in the safety case

Conclusions

- Its imperative for safe operation of AS that we monitor for when things go wrong
 - Specifically we need to know that the safety case has not become invalid
- This requires that we can demonstrate that
 - we understand what will challenge validity of the safety case
 - We have sufficient monitoring in place for those things
- Monitors only have value for safety assurance if we can show that we are monitoring *all of the right things*
- Our approach enables systematic identification of monitoring requirements from analysis of the safety argument
 - This allows us to argue about the sufficiency of the monitoring





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