

FAILURE DETECTION IN AN AUTONOMOUS VEHICLE

ABSTRACT

The presently disclosed subject matter includes a failure detection sub-system operatively connectable to an autonomous vehicle that comprises an autonomous control sub-system that is configured to process real-time sensory data and generate commands for controlling the autonomous vehicle; the failure detection sub-system is configured to determine, based on real-time behavioral-data and real-time mapping data, whether a violation of the at least one safety rule is occurring; and generate one or more vehicle control commands for controlling at least one driving sub-system in case a violation of the safety rules is detected, wherein processing done by failure detection sub-system is less computationally intensive as compared to processing done by the autonomous control sub-system in the vehicle.

Fig. 1a