Verilog Implementation of Collision Avoidance System based on FlexRay Protocol

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Abstract

**Background/Objective:** The objective of this paper is to provide an insight into the FlexRay protocol, as well as build a simple collision avoidance system based on it. FlexRay is a next generation intra-vehicular communication protocol that provides fault-tolerant, flexible, high data rate and deterministic communication between the different electronic units in an automobile, mainly used for advanced automobile control and safety-critical applications. **Methods/Statistical Analysis:** Here, a simple collision avoidance system for an automobile is built using Verilog HDL, where data is transmitted according to the FlexRay protocol. Separate Verilog modules are designed for an ultrasonic sensor and a motor. Data is transmitted in the FlexRay frame format. Simulation of results are tested in ModelSim tool. **Findings:** It is observed that under the FlexRay protocol, data is transmitted at a much greater speed. Also, there are better fault tolerance and better error detection mechanisms, all of which are quintessential for a safety-critical application like collision avoidance. It also ensures safe communication between the devices inside an automobile. **Applications/Improvements:** More advanced automotive applications like automatic steering, temperature regulation, etc., can be implemented in a similar manner based on the protocol. The protocol is mainly used for safety-critical applications owing to its huge cost of implementation.

**Keywords:** Cyclic Redundancy Check, FlexRay, Frame Format, Generator Polynomial, Intra-Vehicular Communication

1. Introduction

With the ever increasing need for huge bunches of data to be transmitted with high reliability between the different electronic components in an automobile, the FlexRay protocol has been developed to meet the present day demand for a highly reliable, fault tolerant, flexible, high data rate communication protocol. The FlexRay protocol, with a high data rate of 10 Mbps, with favourable error detection techniques, and featuring both time and event triggered transmissions, is expected to become the future standard for intra-vehicular communication. Its scalable fault tolerance is achieved by featuring a dual channel communication. It displays a much better performance compared to its predecessors, Controller Area Network (CAN) and Local Interconnect Network (LIN). In the FlexRay topology, the nodes may be connected in active star, serial bus or hybrid configuration. Each node is a communication interface of a specific electronic device within the automobile. The paper mainly discusses how the transmission of data happens according to the protocol, and the FlexRay frame format.

Sections 2, 3 and 4 of this paper give a general overview of the FlexRay communication protocol and its features. The FlexRay frame format and communication cycles are discussed here. The 5th Section deals about a simple collision avoidance system that can be designed, where data is being transmitted according to the FlexRay protocol. The simulation results in ModelSim are given in the sixth section. The 7th Section presents the conclusion and future scope.

2. FlexRay Frame Format

In the FlexRay protocol, data is transmitted serially, and in the form of frames. Each slot of the static segment or
The design of a simple collision avoidance system for an automobile, where data is being transmitted in the

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**3. FlexRay Communication Cycle**

The communication in FlexRay is between different nodes, the nodes representing the different electronic components of an automobile. The FlexRay communication cycle has a typical length of 1 to 5 milliseconds. It consists of the Static segment, the Dynamic segment, the Symbol Window and the Network Idle Time.

- Static segment - This time slot is for deterministic data that arrives at a fixed time.
- Dynamic segment - This slot is for the non-deterministic, event triggered data.

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**Figure 1.** Frame format.

**Figure 2.** FlexRay communication cycle.
Distance of the obstacle from the sensor = Distance travelled by signal in 1 clock cycle × Number of clock cycles.

Where,

Distance travelled by signal in 1 clock cycle = Speed of radio waves × Duration of 1 clock cycle.

Once the distance of the obstacle is obtained, it is time to send appropriate signals to the receiver. For convenience, we pick certain limits, like, if the distance is less than 1m, the motor needs to be signaled to stop immediately. If the distance is between, say, 1 m and 5 m, the motor is signaled to reduce its speed. In a similar manner, the rotation of the motor is controlled according to the distance from the obstacle. We set up a counter and the number of clock cycles up to which it needs to count can be obtained from Equation (1). For each distance, we set as limits, we can get the number of clock cycles for the counter by substituting for distance in Equation (1).

5.1 Cyclic Redundancy Check

Cyclic Redundancy Check is used to detect any errors during transmission. In the header section of the FlexRay frame, we have 11 bits as header CRC bits. In the trailer section, we have three 8 bit CRCs for header and payload together. Separate CRC polynomials are used for each.

For the 11 bit header CRC, the generator polynomial is: \( x^{11}+x^9+x^8+x^7+1 \).

For the 24 bit trailer CRC, the generator polynomial is: \( x^{24}+x^{22}+x^{20}+x^{19}+x^{18}+x^{17}+x^{16}+x^{15}+x^{14}+x^{13}+x^{12}+x^7+x^6+x^5+x+1 \).

With the data bits that are to be transmitted, the corresponding CRC bits are also attached. These bits are obtained based on the remainder during division of the data bits by the corresponding generator polynomial. The resulting bits obtained are transmitted.

5.2 Finite State Machine

The transmitted data is then passed through a Finite State Machine module. It is here where the Header and Trailer segments are added to the data. The Header segment, with the start bits, Frame ID, payload length, and cycle count, as well as the trailer segment with the CRC bits are added to the data. The Finite State Machine used here has 18 states. Once the data comes out of the Finite State Machine, it achieves the FlexRay frame format.

The frame is then transmitted serially, one bit at a time, to the receiver section.

5.3 Reception of Data

At the receiver end, the bits are received serially, and the payload segment is separated from the frame. The payload data is now used to control the motor module. A counter is set up to control the speed of rotation of the motor. The number of clock cycles for the counter is calculated using equations mentioned before. The motor either stops immediately, i.e., brings its rpm to zero, or reduces its speed accordingly, based on the data from the sensor, i.e., based on the distance of the obstacle from the automobile. On reception, the CRC calculation is repeated, and in case the check values do not match, it can be confirmed that the data received is corrupted. Only if
the data bits are not corrupted, the receiver separates the data bits from the frame.

6. Results and Discussion

The modules are programmed in Verilog HDL, and simulated in ModelSim. The inputs to the test bench are the clock pulse, reset and the echo signals. In a hardware simulation, the echo signals are in fact the signals reflected off the obstacle. Standard procedures are applied for simulation. Figures 4, 5 and 6 show the results of software simulation.

![Simulation results-1](image1)

Figure 4. Simulation results-1.

![Simulation results-2](image2)

Figure 5. Simulation results-2.

![Simulation results-3](image3)

Figure 6. Simulation results-3.

The CRC bits, obtained from the generator polynomials, are used to check for errors during transmission. In case of detection of errors, a signal is sent to the transmitter, asking for retransmission. Hence, the possibility that the receiver receives a signal with error is minimized.

7. Conclusion and Future Scope

In this paper, the authors have tried to design and simulate a simple collision avoidance system, where data is transmitted in the FlexRay frame format. Simulation results are presented in ModelSim tool. Error detection was achieved using the CRC bits transmitted. Many applications can be implemented in a similar manner, based on the protocol, for example, autonomous driving. The major advantages obtained are high speed, scalable fault tolerance and flexibility. The embedded event triggered functionality is an added advantage of the protocol. As a further advanced communication security measure, advanced protocols have been designed by researchers for safe and secure communication between devices, using hash function and complex mathematical formulae. These advancements are expected to guard diverse attacks. Some researchers have also designed devices with advanced safety functions, like alerting a rescue team in case of a crash. These devices use Micro-Electro-Mechanical systems to detect the crash, through tilting.

FlexRay is likely to become the de-facto standard for the emerging X-by-wire systems in automobiles. Presently
it is implemented only in expensive luxury cars, mainly for safety-critical applications. Further developments in the protocol is expected to enhance its features, and also turn it more cost-effective. FlexRay meets the performance requirements of the next generation of automobiles. FlexRay networking standard provides new dimensions to the future of automobile electronics, and is an area where more researches and advancements are important.

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9. References