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(57) Abstract :

Through the use of electronic control unit identification analysis and data interpretation, we describe a method for automatically extracting proprietary in-vehicle data utilizing sensor data linked with the required information. As a first step, the suggested system uses an inertial measurement unit and global positioning system readings to ascertain the current driving situation of the vehicle via threshold, random forest, and long short-term memory-based algorithms. Improvements in vehicle technology have led to the installation of sensors in automobiles for retrieving standard information, such as engine speed and vehicle speed, from the onboard controller area network (CAN) system. However, it can be challenging to extract confidential data from CAN frames, such as the brake and steering functions that are essential to studying driver behavior. Next, the system uses the estimation to divide CAN frames from within the car and then uses our scoring method to rank each segment in order to select promising prospects based on a comparison between their estimated and actual distances. An estimating method is coupled to a nonlinear model-predictive control (NMPC) system, which is in charge of vehicle control. We tested the suggested method in a city environment with actual vehicles. The performance evaluation shows that the provided methods are effective at predicting driving conditions, indicating that they can be used for the autonomous extraction of confidential information stored in the car.

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