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(54) **ACCIDENT FAULT DETERMINATION FOR AUTONOMOUS VEHICLES**

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(58) **Field of Classification Search**
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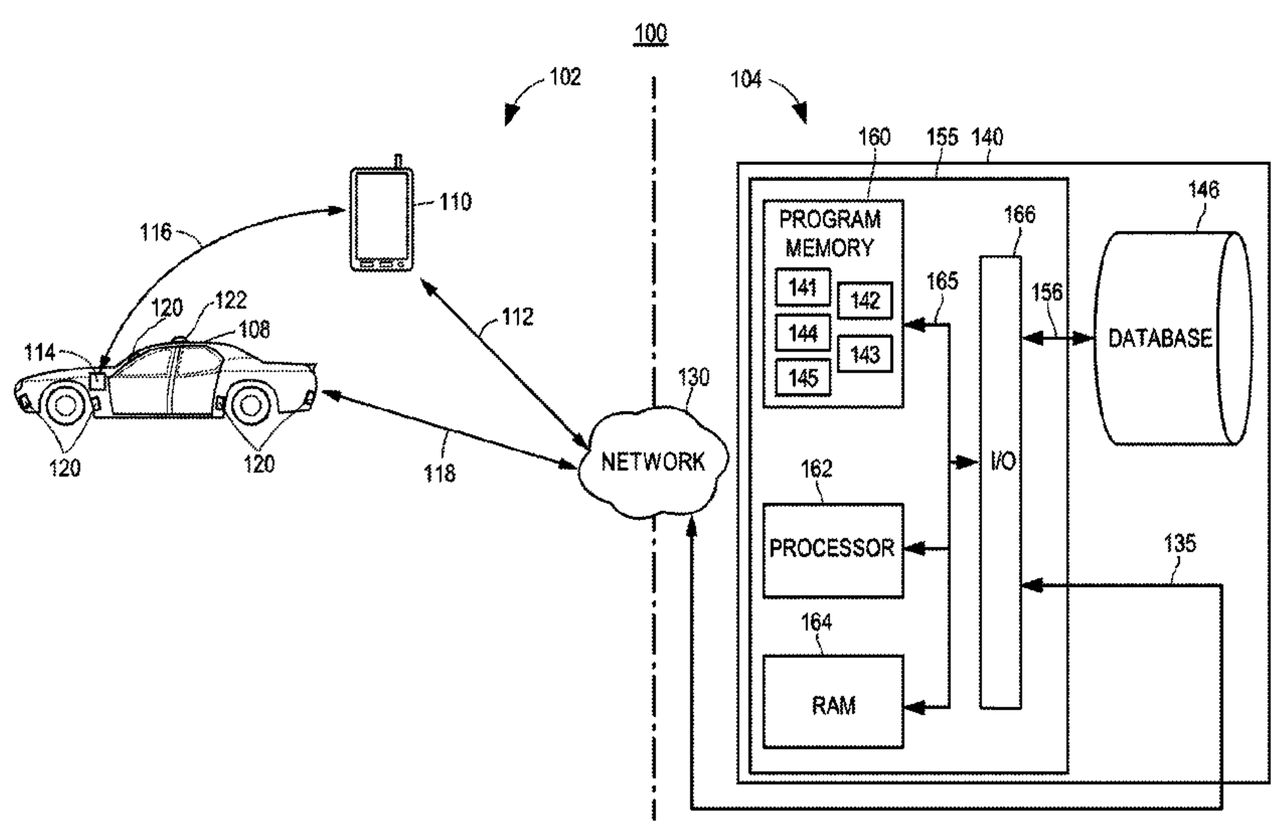
(57) **ABSTRACT**

Methods and systems for determining fault for an accident involving a vehicle having one or more autonomous (and/or semi-autonomous) operation features are provided. According to certain aspects, operating data from sensors within or near the vehicle may be used to determine fault for a vehicle accident, such as a collision. The operating data may include information regarding use of the features at the time of the accident and may further be used to determine an allocation of fault for the accident between a vehicle operator, the autonomous operation features, or a third party. The allocation of fault may be used to determine and/or adjust coverage levels for an insurance policy associated with the vehicle. The allocation of fault may further be used to adjust risk levels or profiles associated with the vehicle operator or with the autonomous operation features.

20 Claims, 15 Drawing Sheets



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(58) **Field of Classification Search**
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See application file for complete search history.

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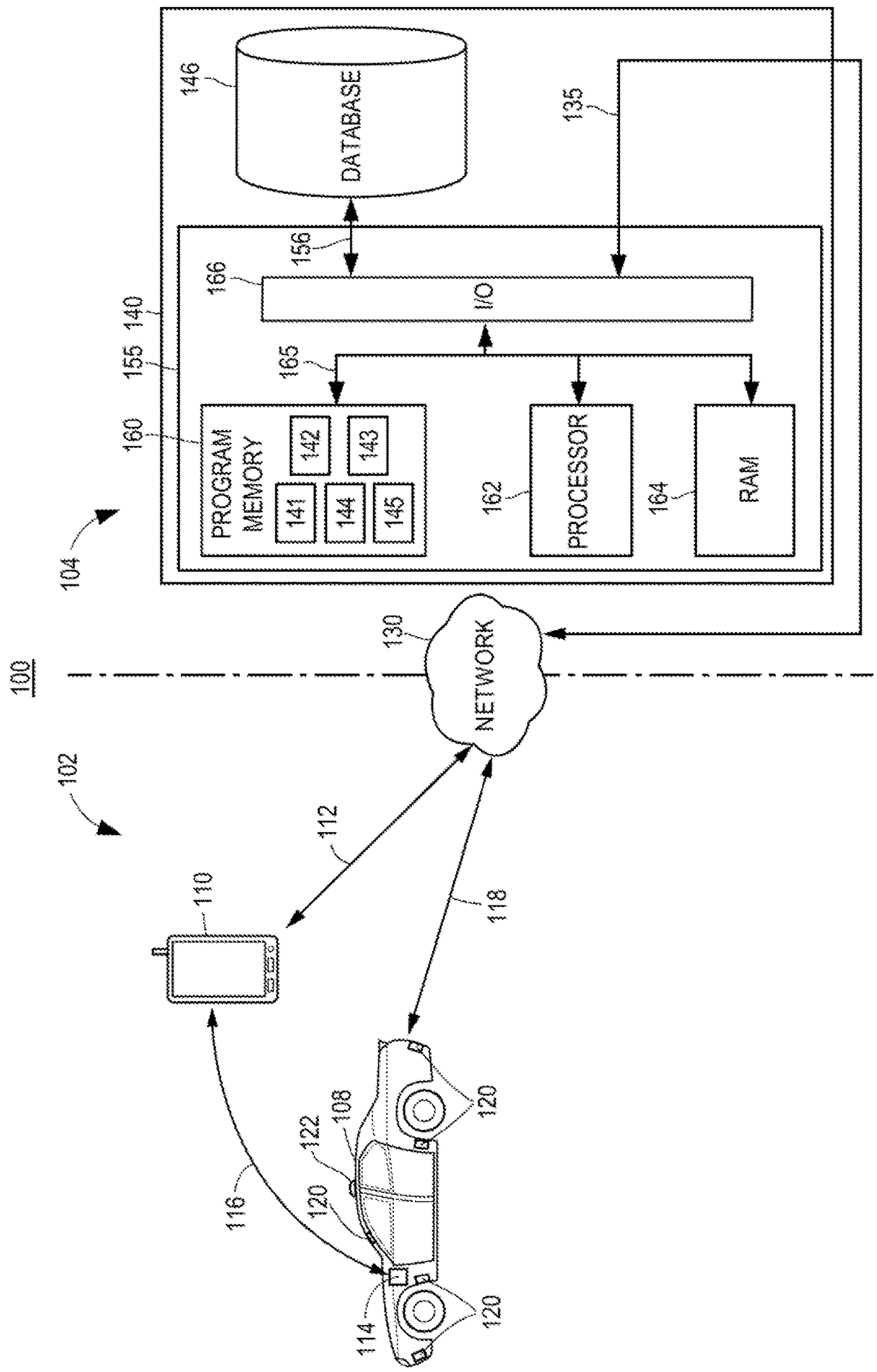
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102
104
DATABASE
146
135
156
166
I/O
140
155
165
160
PROGRAM MEMORY
141
142
143
144
145
162
PROCESSOR
164
RAM
130
NETWORK
112
118
110
116
114
120
122
108

FIG. 1

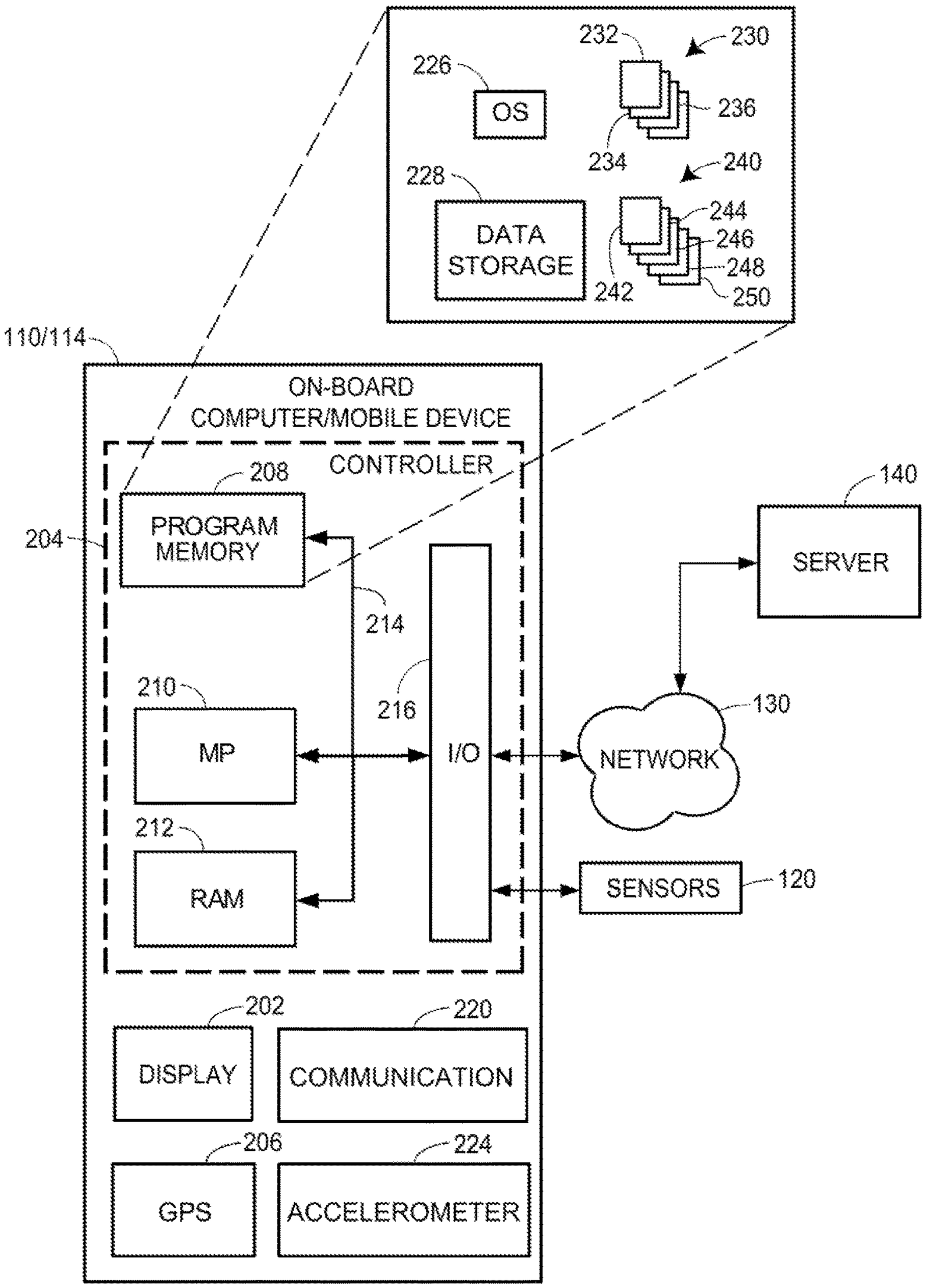
232
230
226
OS
236
234
240
228
DATA STORAGE
244
246
248
242
250
110/114
ON-BOARD COMPUTER/MOBILE DEVICE
CONTROLLER
208
PROGRAM MEMORY
204
140
SERVER
214
210
216
130
MP
I/O
NETWORK
212
RAM
SENSORS
120
202
220
DISPLAY
COMMUNICATION
206
224
GPS
ACCELEROMETER

FIG. 2

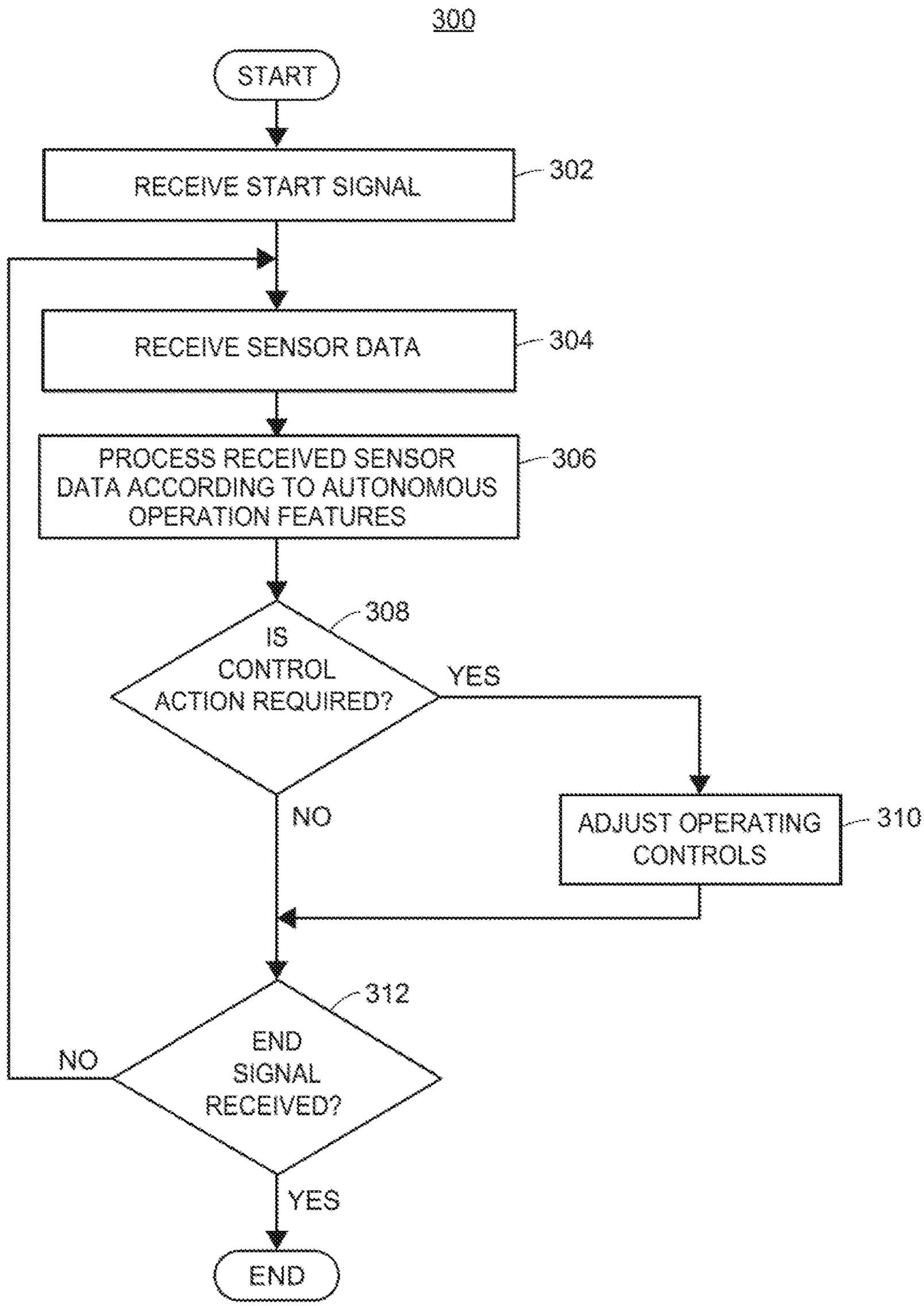
300
START
RECEIVE START SIGNAL
302
RECEIVE SENSOR DATA
304
PROCESS RECEIVED SENSOR DATA ACCORDING TO AUTONOMOUS OPERATION FEATURES
306
IS CONTROL ACTION REQUIRED?
308
YES
NO
ADJUST OPERATING CONTROLS
310
END SIGNAL RECEIVED?
312
NO
YES
END

FIG. 3

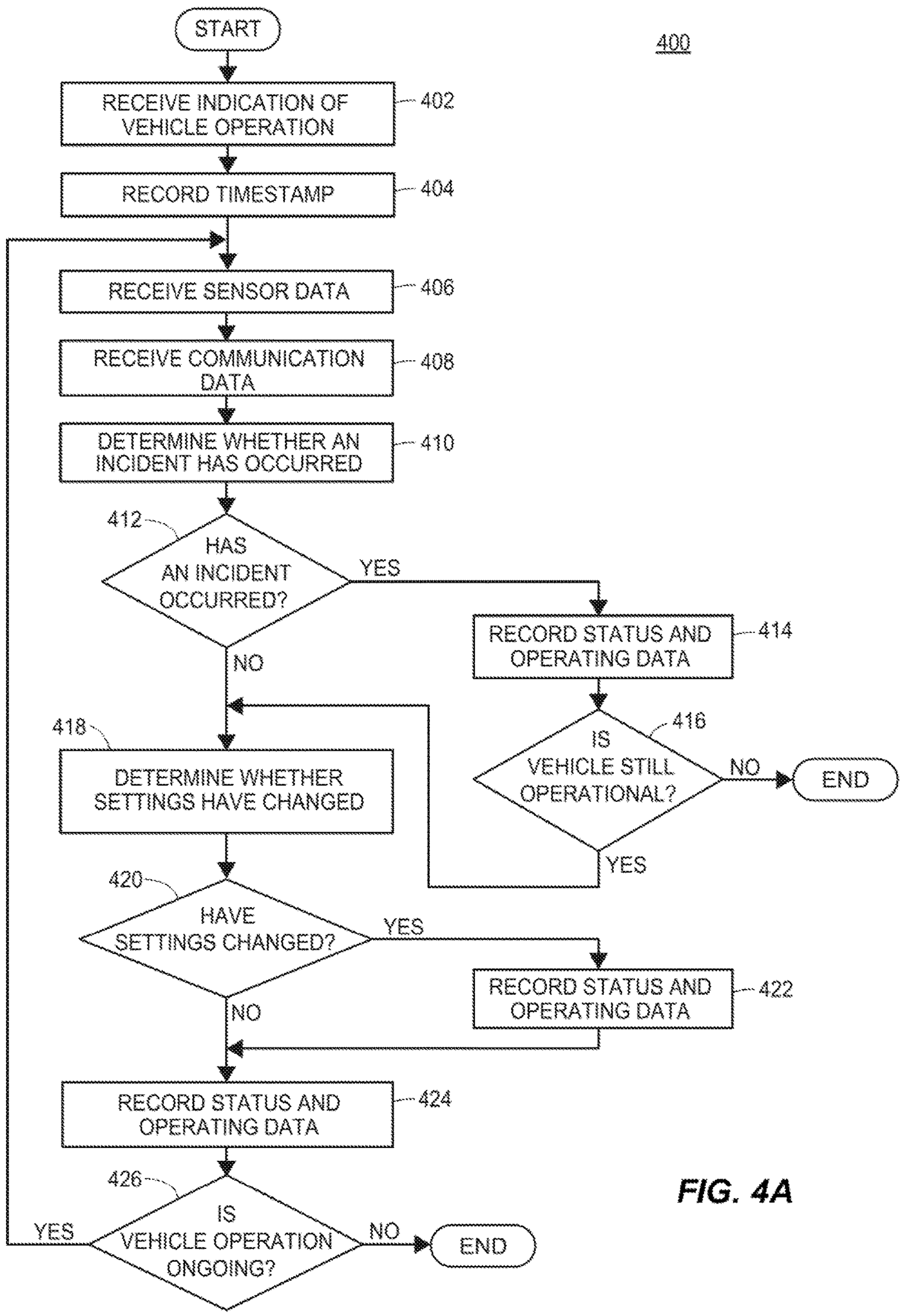
400
START
RECEIVE INDICATION OF VEHICLE OPERATION
402
RECORD TIMESTAMP
404
RECEIVE SENSOR DATA
406
RECEIVE COMMUNICATION DATA
408
DETERMINE WHETHER AN INCIDENT HAS OCCURRED
410
412
HAS AN INCIDENT OCCURRED?
YES
NO
RECORD STATUS AND OPERATING DATA
414
416
IS VEHICLE STILL OPERATIONAL?
NO
END
YES
418
DETERMINE WHETHER SETTINGS HAVE CHANGED
420
HAVE SETTINGS CHANGED?
YES
NO
RECORD STATUS AND OPERATING DATA
422
RECORD STATUS AND OPERATING DATA
424
426
IS VEHICLE OPERATION ONGOING?
YES
NO
END

FIG. 4A

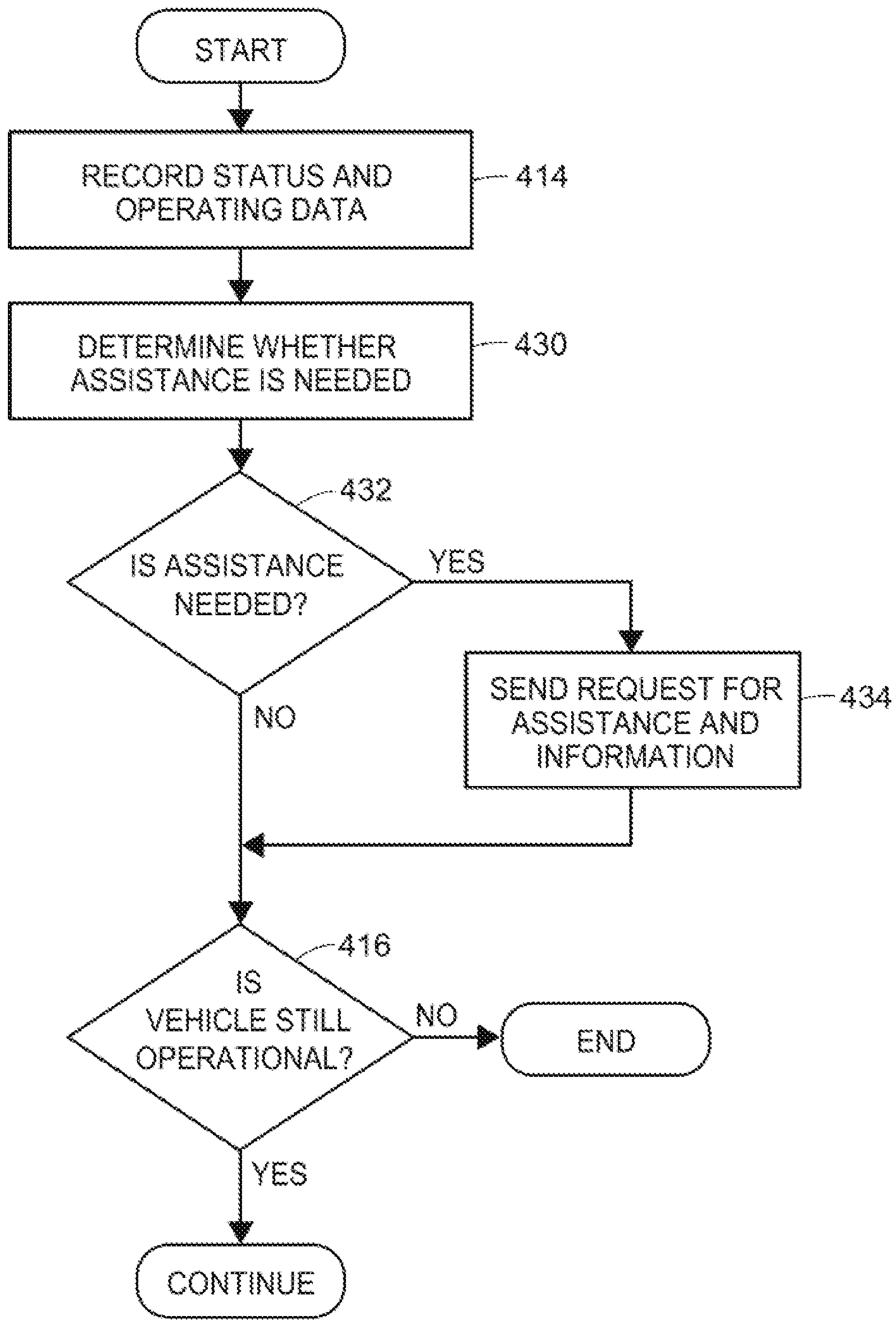
START
RECORD STATUS AND OPERATING DATA
414
DETERMINE WHETHER ASSISTANCE IS NEEDED
430
IS ASSISTANCE NEEDED?
432
YES
NO
SEND REQUEST FOR ASSISTANCE AND INFORMATION
434
IS VEHICLE STILL OPERATIONAL?
416
NO
END
YES
CONTINUE

FIG. 4B

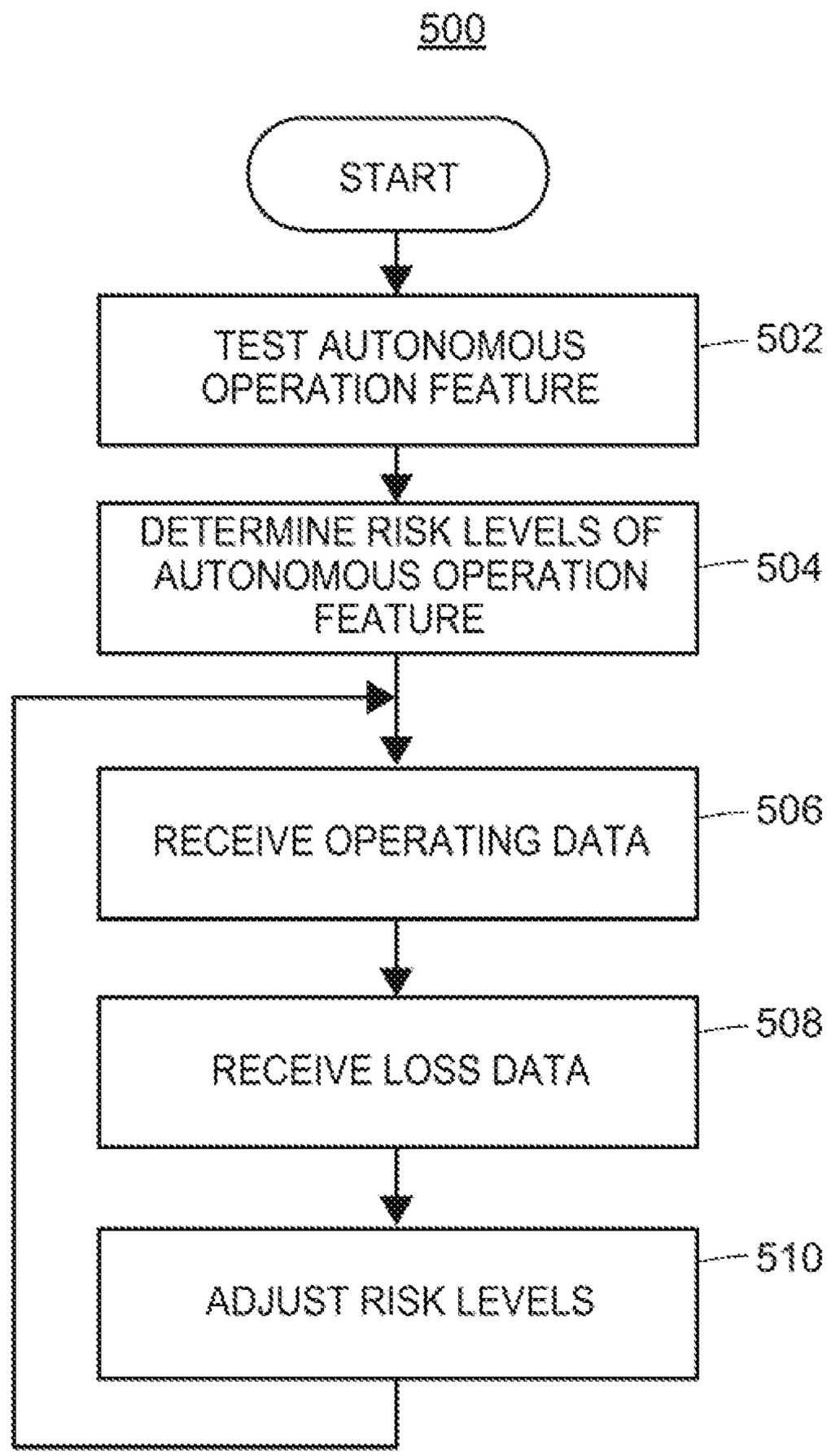
500
START
TEST AUTONOMOUS OPERATION FEATURE
502
DETERMINE RISK LEVELS OF AUTONOMOUS OPERATION FEATURE
504
RECEIVE OPERATING DATA
506
RECEIVE LOSS DATA
508
ADJUST RISK LEVELS
510

FIG. 5

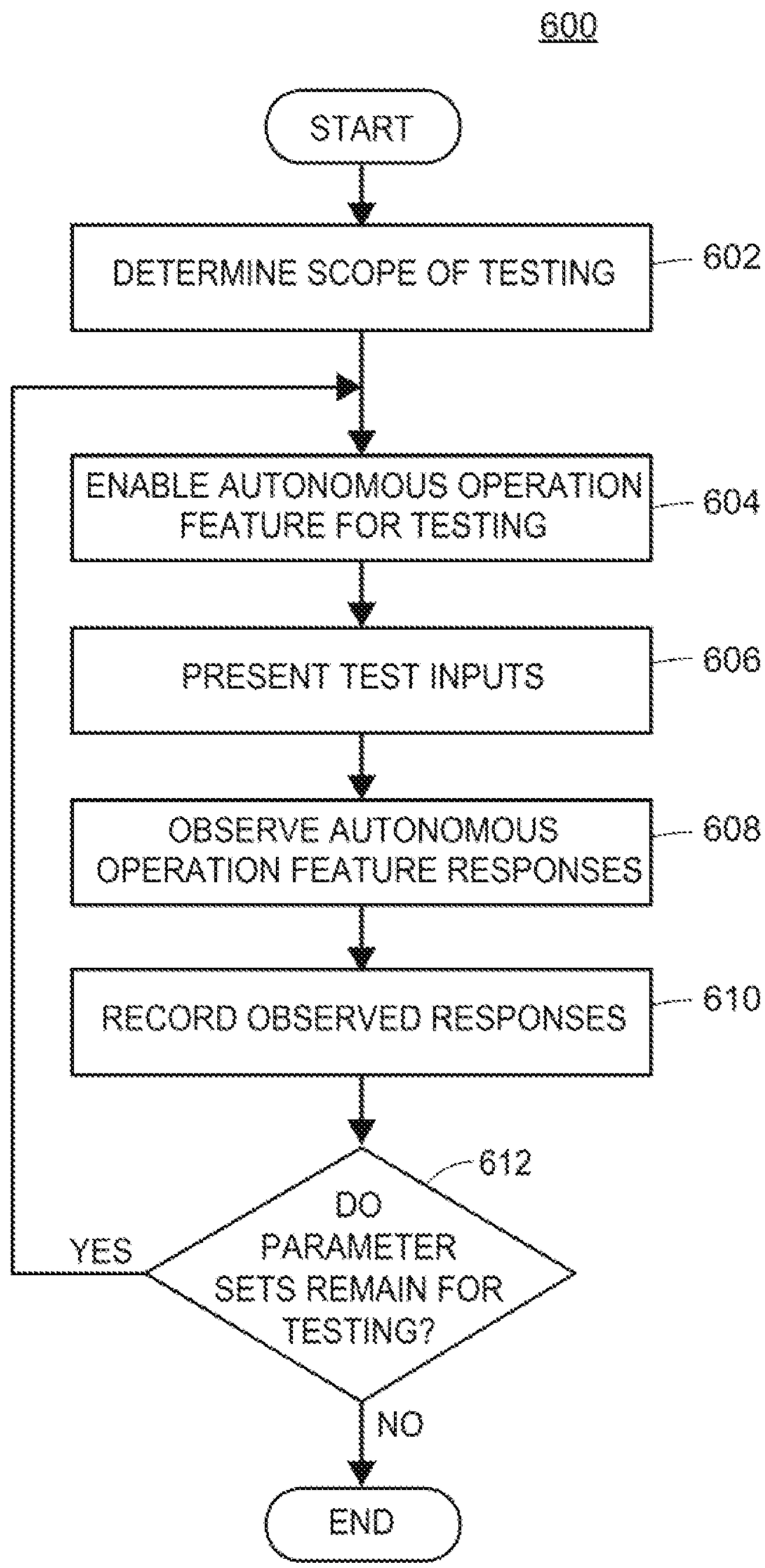
600
START
DETERMINE SCOPE OF TESTING
602
ENABLE AUTONOMOUS OPERATION FEATURE FOR TESTING
604
PRESENT TEST INPUTS
606
OBSERVE AUTONOMOUS OPERATION FEATURE RESPONSES
608
RECORD OBSERVED RESPONSES
610
612
DO PARAMETER SETS REMAIN FOR TESTING?
YES
NO
END

FIG. 6

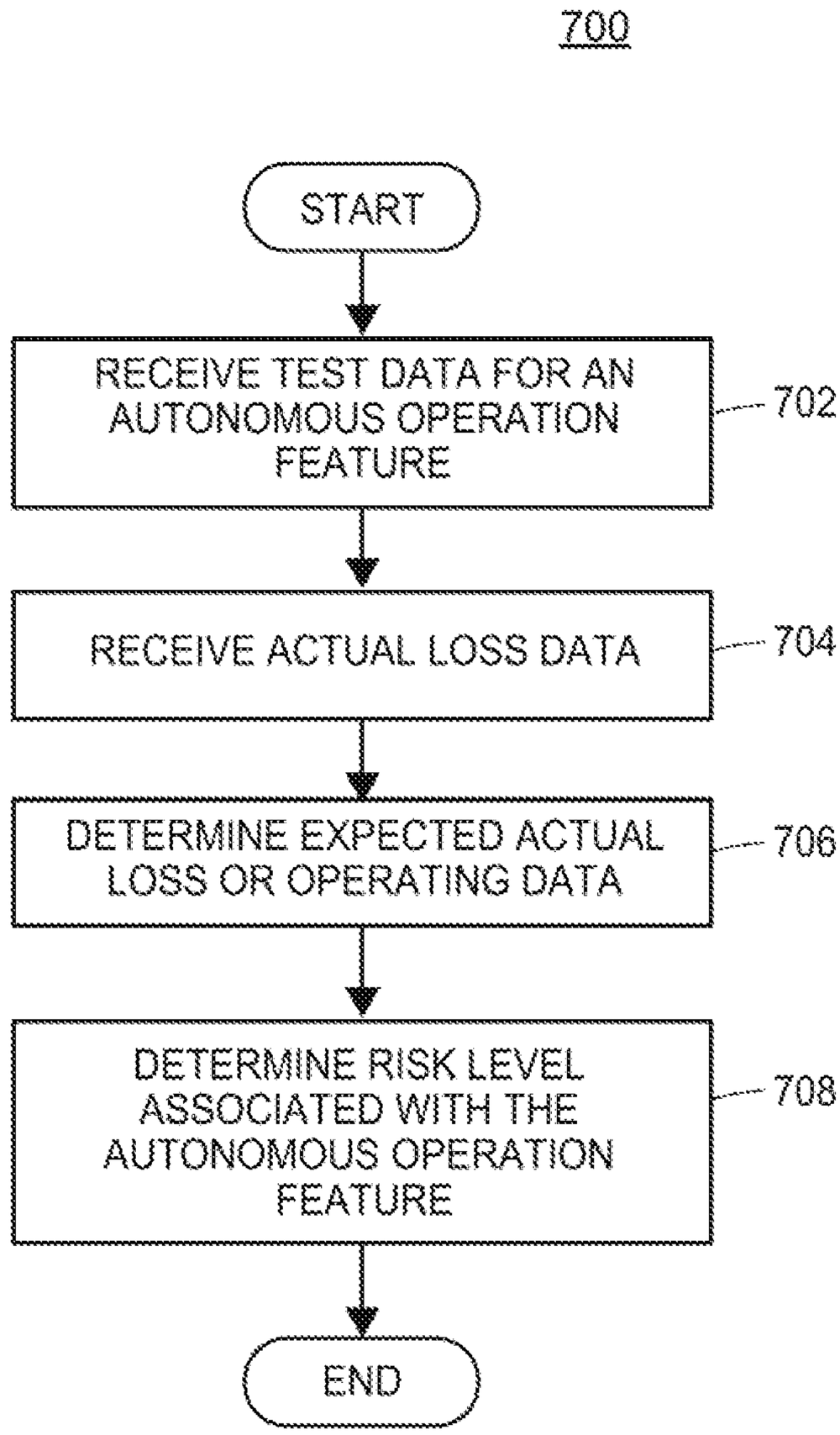
700
START
RECEIVE TEST DATA FOR AN AUTONOMOUS OPERATION FEATURE
702
RECEIVE ACTUAL LOSS DATA
704
DETERMINE EXPECTED ACTUAL LOSS OR OPERATING DATA
706
DETERMINE RISK LEVEL ASSOCIATED WITH THE AUTONOMOUS OPERATION FEATURE
708
END

FIG. 7

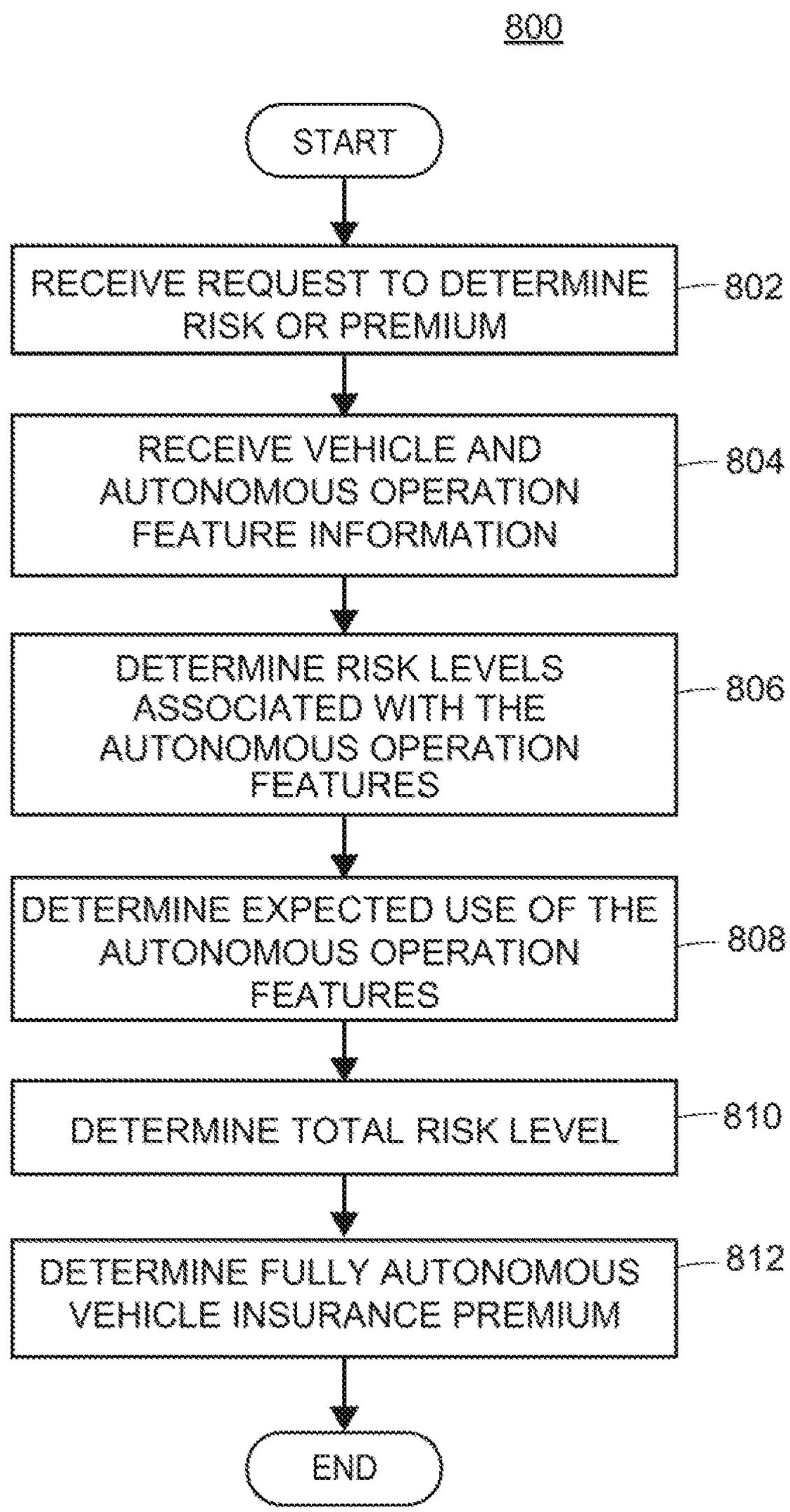
800
START
RECEIVE REQUEST TO DETERMINE RISK OR PREMIUM
802
RECEIVE VEHICLE AND AUTONOMOUS OPERATION FEATURE INFORMATION
804
DETERMINE RISK LEVELS ASSOCIATED WITH THE AUTONOMOUS OPERATION FEATURES
806
DETERMINE EXPECTED USE OF THE AUTONOMOUS OPERATION FEATURES
808
DETERMINE TOTAL RISK LEVEL
810
DETERMINE FULLY AUTONOMOUS VEHICLE INSURANCE PREMIUM
812
END

FIG. 8

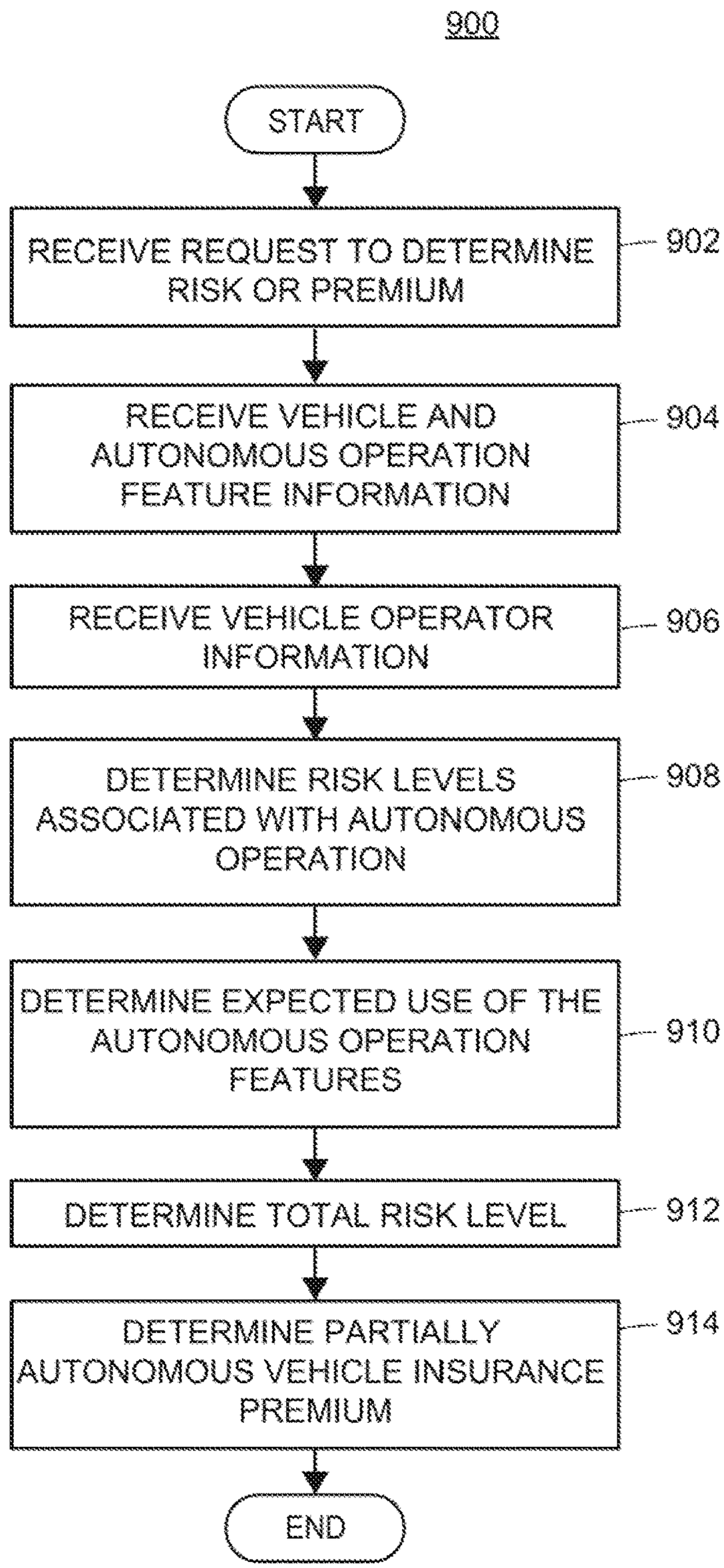
900
START
RECEIVE REQUEST TO DETERMINE RISK OR PREMIUM
902
RECEIVE VEHICLE AND AUTONOMOUS OPERATION FEATURE INFORMATION
904
RECEIVE VEHICLE OPERATOR INFORMATION
906
DETERMINE RISK LEVELS ASSOCIATED WITH AUTONOMOUS OPERATION
908
DETERMINE EXPECTED USE OF THE AUTONOMOUS OPERATION FEATURES
910
DETERMINE TOTAL RISK LEVEL
912
DETERMINE PARTIALLY AUTONOMOUS VEHICLE INSURANCE PREMIUM
914
END

FIG. 9

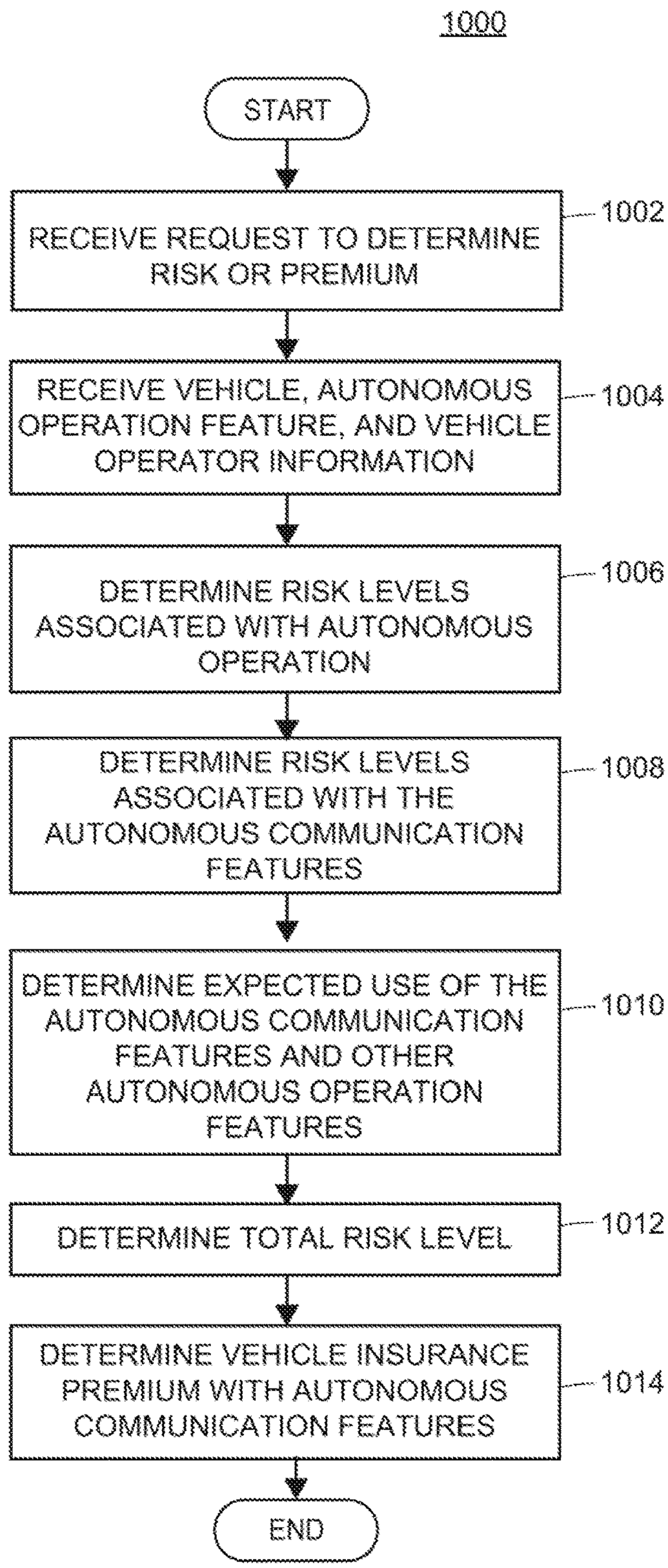
1000
START
RECEIVE REQUEST TO DETERMINE RISK OR PREMIUM
1002
RECEIVE VEHICLE, AUTONOMOUS OPERATION FEATURE, AND VEHICLE OPERATOR INFORMATION
1004
DETERMINE RISK LEVELS ASSOCIATED WITH AUTONOMOUS OPERATION
1006
DETERMINE RISK LEVELS ASSOCIATED WITH THE AUTONOMOUS COMMUNICATION FEATURES
1008
DETERMINE EXPECTED USE OF THE AUTONOMOUS COMMUNICATION FEATURES AND OTHER AUTONOMOUS OPERATION FEATURES
1010
DETERMINE TOTAL RISK LEVEL
1012
DETERMINE VEHICLE INSURANCE PREMIUM WITH AUTONOMOUS COMMUNICATION FEATURES
1014
END

FIG. 10

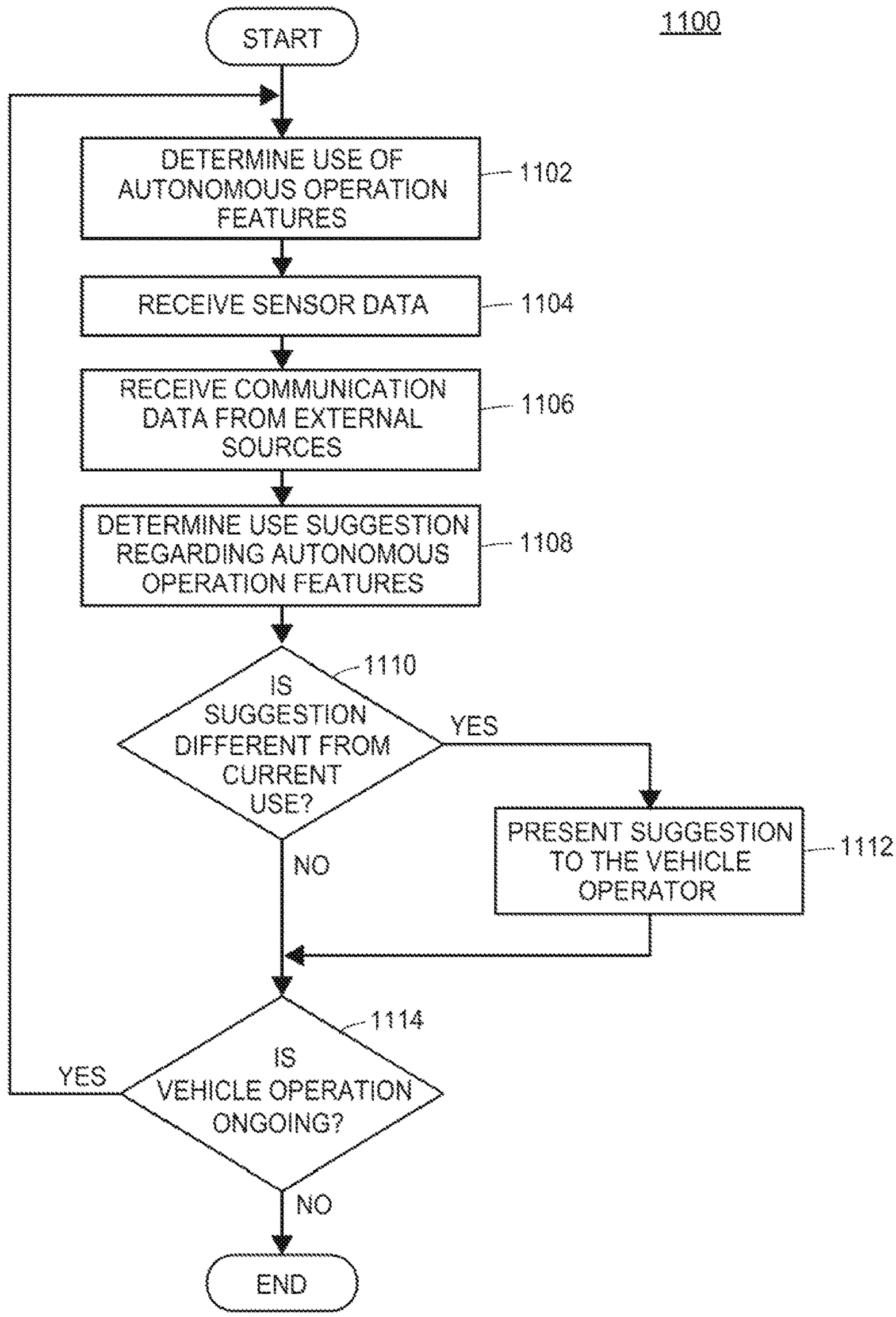
1100
START
DETERMINE USE OF AUTONOMOUS OPERATION FEATURES
1102
RECEIVE SENSOR DATA
1104
RECEIVE COMMUNICATION DATA FROM EXTERNAL SOURCES
1106
DETERMINE USE SUGGESTION REGARDING AUTONOMOUS OPERATION FEATURES
1108
IS SUGGESTION DIFFERENT FROM CURRENT USE?
1110
YES
NO
PRESENT SUGGESTION TO THE VEHICLE OPERATOR
1112
IS VEHICLE OPERATION ONGOING?
1114
YES
NO
END

FIG. 11

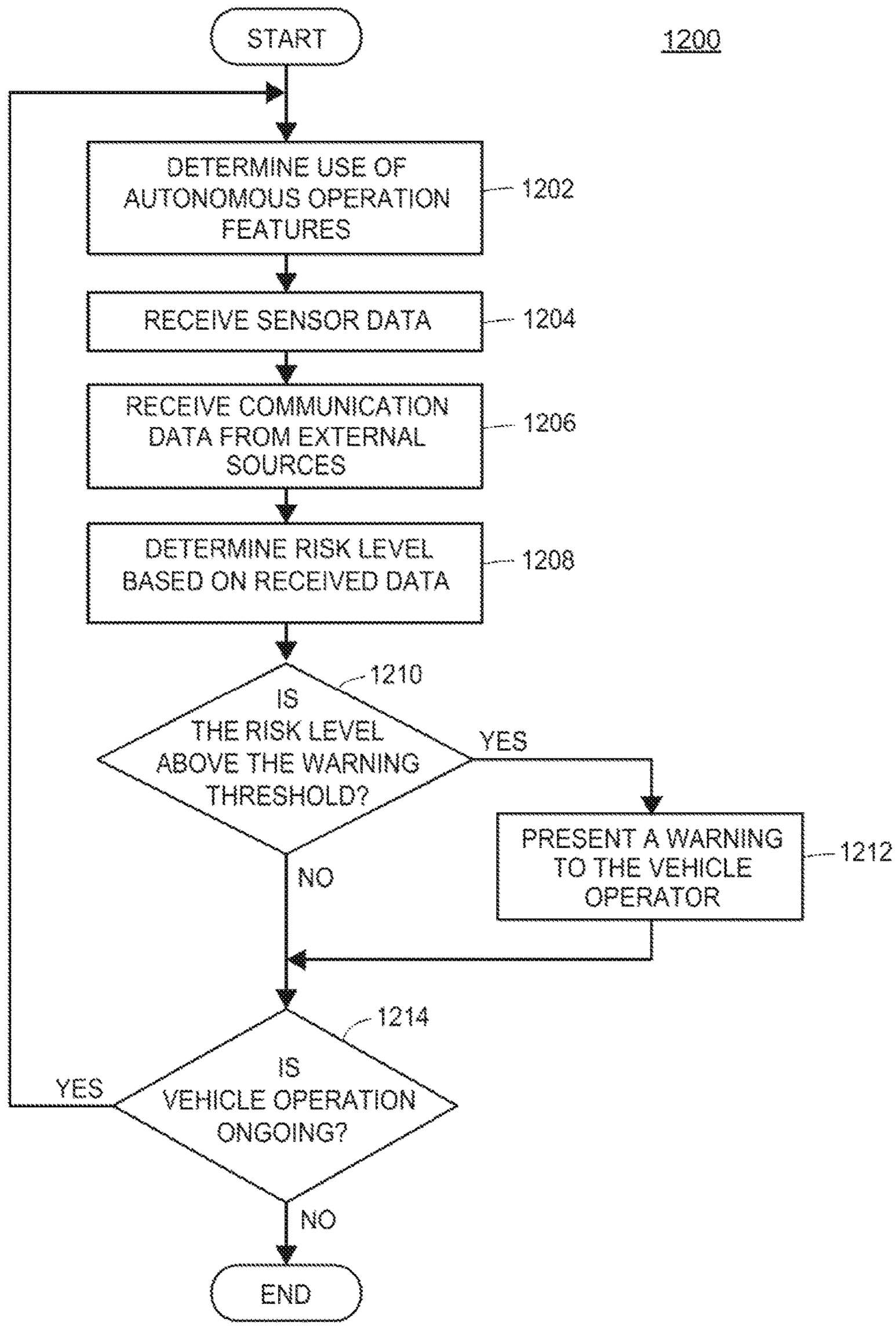
START
1200
DETERMINE USE OF AUTONOMOUS OPERATION FEATURES
1202
RECEIVE SENSOR DATA
1204
RECEIVE COMMUNICATION DATA FROM EXTERNAL SOURCES
1206
DETERMINE RISK LEVEL BASED ON RECEIVED DATA
1208
IS THE RISK LEVEL ABOVE THE WARNING THRESHOLD?
1210
YES
NO
PRESENT A WARNING TO THE VEHICLE OPERATOR
1212
IS VEHICLE OPERATION ONGOING?
1214
YES
NO
END

FIG. 12

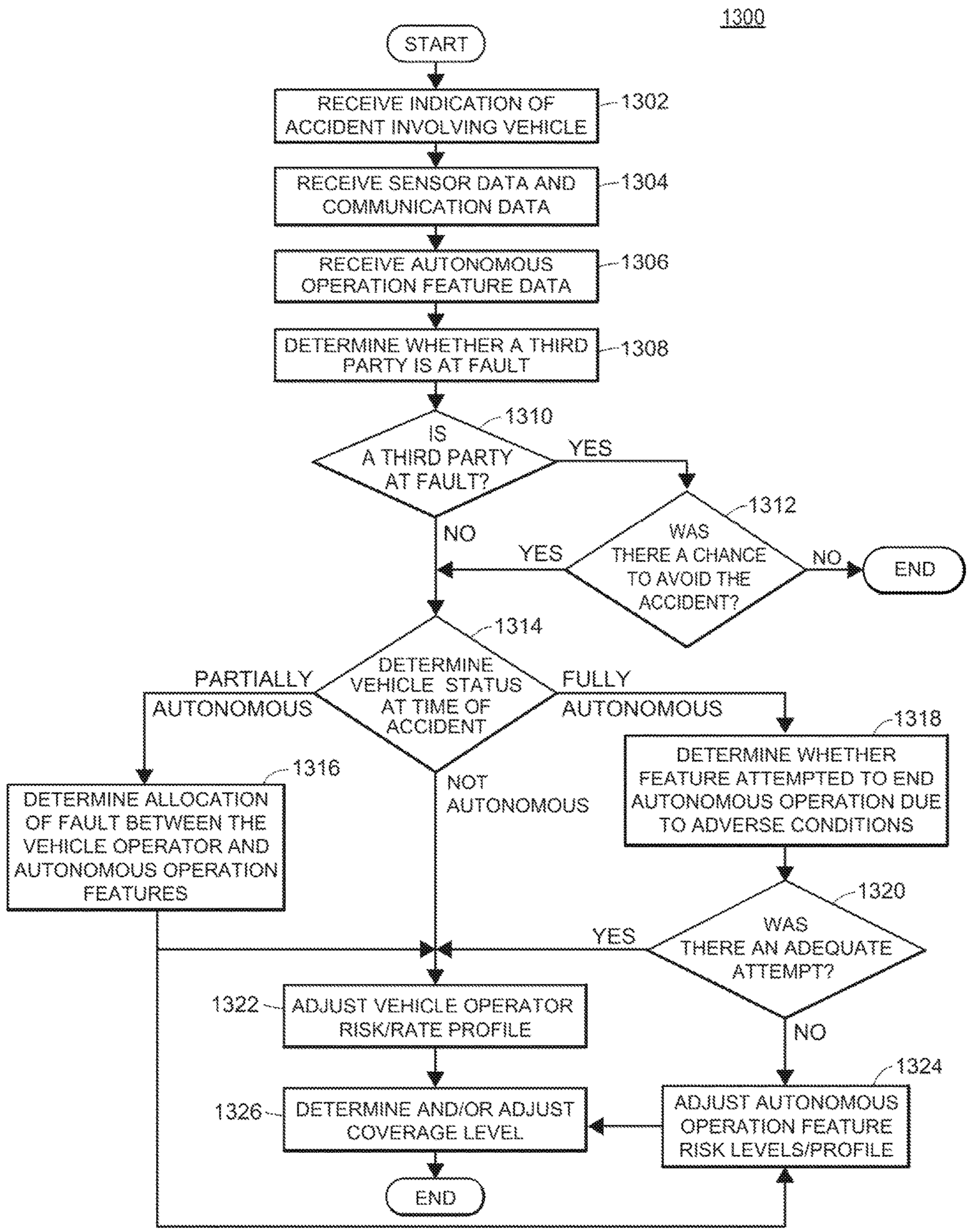
1300
START
RECEIVE INDICATION OF ACCIDENT INVOLVING VEHICLE
1302
RECEIVE SENSOR DATA AND COMMUNICATION DATA
1304
RECEIVE AUTONOMOUS OPERATION FEATURE DATA
1306
DETERMINE WHETHER A THIRD PARTY IS AT FAULT
1308
IS A THIRD PARTY AT FAULT?
1310
YES
NO
WAS THERE A CHANCE TO AVOID THE ACCIDENT?
1312
YES
NO
END
DETERMINE VEHICLE STATUS AT TIME OF ACCIDENT
1314
PARTIALLY AUTONOMOUS
FULLY AUTONOMOUS
NOT AUTONOMOUS
DETERMINE ALLOCATION OF FAULT BETWEEN THE VEHICLE OPERATOR AND AUTONOMOUS OPERATION FEATURES
1316
DETERMINE WHETHER FEATURE ATTEMPTED TO END AUTONOMOUS OPERATION DUE TO ADVERSE CONDITIONS
1318
WAS THERE AN ADEQUATE ATTEMPT?
1320
YES
NO
ADJUST VEHICLE OPERATOR RISK/RATE PROFILE
1322
DETERMINE AND/OR ADJUST COVERAGE LEVEL
1326
ADJUST AUTONOMOUS OPERATION FEATURE RISK LEVELS/PROFILE
1324
END

FIG. 13

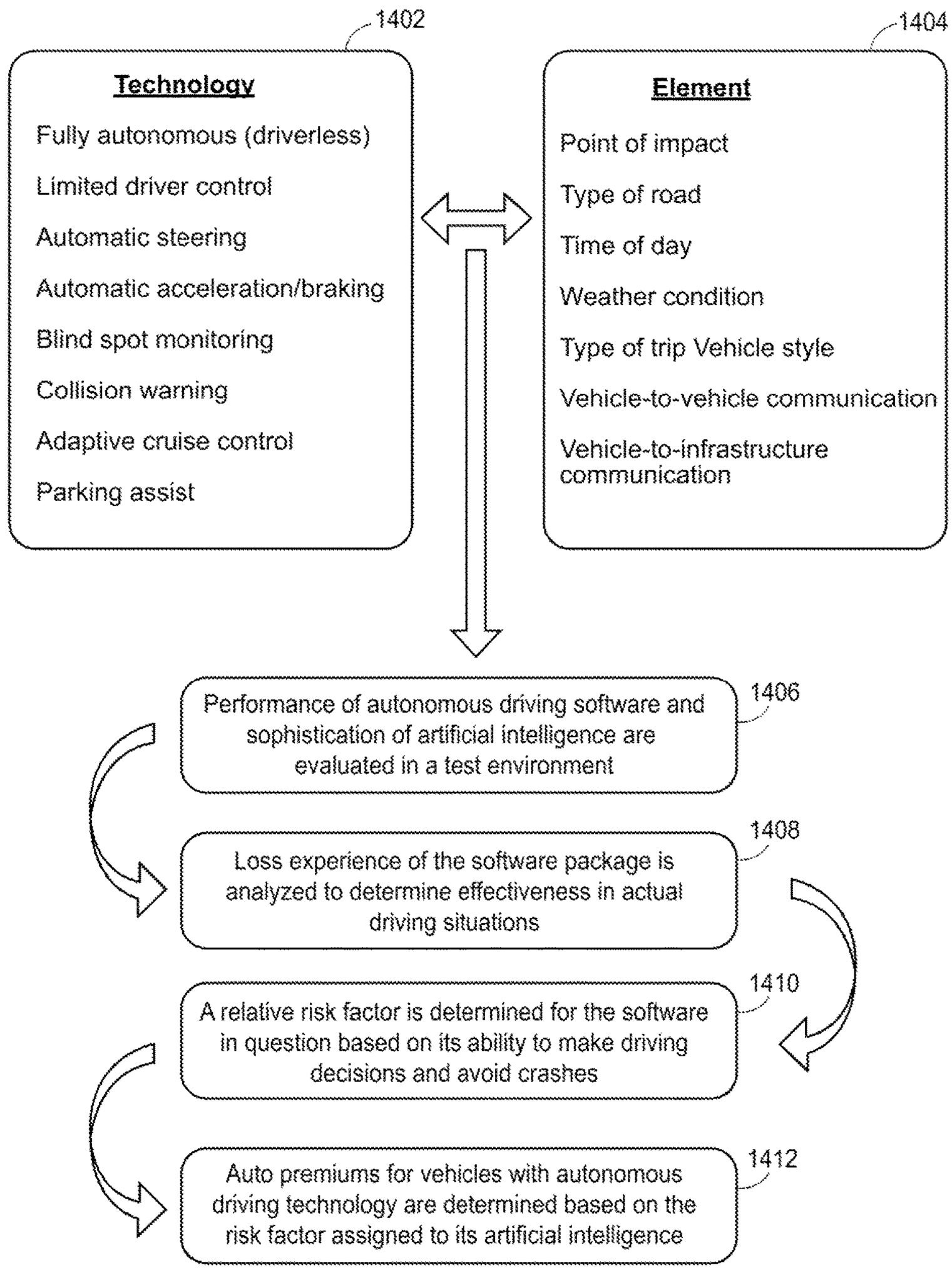
1402
Technology
Fully autonomous (driverless)
Limited driver control
Automatic steering
Automatic acceleration/braking
Blind spot monitoring
Collision warning
Adaptive cruise control
Parking assist
1404
Element
Point of impact
Type of road
Time of day
Weather condition
Type of trip Vehicle style
Vehicle-to-vehicle communication
Vehicle-to-infrastructure communication
Performance of autonomous driving software and sophistication of artificial intelligence are evaluated in a test environment
1406
Loss experience of the software package is analyzed to determine effectiveness in actual driving situations
1408
A relative risk factor is determined for the software in question based on its ability to make driving decisions and avoid crashes
1410
Auto premiums for vehicles with autonomous driving technology are determined based on the risk factor assigned to its artificial intelligence
1412

FIG. 14

ACCIDENT FAULT DETERMINATION FOR AUTONOMOUS VEHICLES

CROSS-REFERENCE TO RELATED APPLICATIONS

This application is a continuation-in-part application of U.S. patent application Ser. No. 14/713,254, filed May 15, 2015, which claims the benefit of U.S. Provisional Application No. 62/000,878 (filed May 20, 2014); U.S. Provisional Application No. 62/018,169 (filed Jun. 27, 2014); U.S. Provisional Application No. 62/035,660 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,669 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,723 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,729 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,769 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,780 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,832 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,859 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,867 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,878 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,980 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/035,983 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/036,090 (filed Aug. 11, 2014); U.S. Provisional Application No. 62/047,307 (filed Sep. 8, 2014); and U.S. Provisional Application No. 62/056,893 (filed Sep. 29, 2014). The entirety of each of the foregoing provisional applications is incorporated by reference herein.

Additionally, the present application is related to co-pending U.S. patent application Ser. No. 14/713,271 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/951,774 (filed Nov. 25, 2015); co-pending U.S. patent application Ser. No. 14/713,184 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,188 (filed May 15, 2015); co-pending Ser. No. 14/978,266 (filed Dec. 22, 2015); co-pending U.S. patent application Ser. No. 14/713,194 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,201 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,206 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,214 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,217 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,223 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,226 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,230 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,237 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,240 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,244 (May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,249 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,254 (May 15, 2015); co-pending U.S. patent application Ser. No. 14/713,261 (filed May 15, 2015); co-pending U.S. patent application Ser. No. 14/951,798 (filed Nov. 25, 2015); and co-pending U.S. patent application Ser. No. 14/713,266 (May 15, 2015).

FIELD

The present disclosure generally relates to systems and methods for determining risk, pricing, and offering vehicle insurance policies, specifically vehicle insurance policies where vehicle operation is partially or fully automated.

BACKGROUND

Vehicle or automobile insurance exists to provide financial protection against physical damage and/or bodily injury resulting from traffic accidents and against liability that could arise therefrom. Typically, a customer purchases a vehicle insurance policy for a policy rate having a specified term. In exchange for payments from the insured customer, the insurer pays for damages to the insured which are caused by covered perils, acts, or events as specified by the language of the insurance policy. The payments from the insured are generally referred to as "premiums," and typically are paid on behalf of the insured over time at periodic intervals. An insurance policy may remain "in-force" while premium payments are made during the term or length of coverage of the policy as indicated in the policy. An insurance policy may "lapse" (or have a status or state of "lapsed"), for example, when premium payments are not being paid or if the insured or the insurer cancels the policy.

Premiums may be typically determined based upon a selected level of insurance coverage, location of vehicle operation, vehicle model, and characteristics or demographics of the vehicle operator. The characteristics of a vehicle operator that affect premiums may include age, years operating vehicles of the same class, prior incidents involving vehicle operation, and losses reported by the vehicle operator to the insurer or a previous insurer. Past and current premium determination methods do not, however, account for use of autonomous vehicle operating features. The present embodiments may, inter alia, alleviate this and/or other drawbacks associated with conventional techniques.

BRIEF SUMMARY

The present embodiments may be related to autonomous or semi-autonomous vehicle functionality, including driverless operation, accident avoidance, or collision warning systems. These autonomous vehicle operation features may either assist the vehicle operator to more safely or efficiently operate a vehicle or may take full control of vehicle operation under some or all circumstances. The present embodiments may also facilitate risk assessment and premium determination for vehicle insurance policies covering vehicles with autonomous operation features.

In accordance with the described embodiments, the disclosure herein generally addresses systems and methods for determining risk levels associated with one or more autonomous (and/or semi-autonomous) operation features for controlling a vehicle or assisting a vehicle operator in controlling the vehicle. A server or other computer system may present test input signals to the one or more autonomous operation features to test the response of the features in a virtual environment. This virtual testing may include presentation of fixed inputs or may include a simulation of a dynamic virtual environment in which a virtual vehicle is controlled by the one or more autonomous operation features. The one or more autonomous operation features generate output signals that may then be used to determine the effectiveness of the control decisions by predicting the responses of vehicles to the output signals. Risk levels associated with the effectiveness of the autonomous operation features may be used to determine a premium for an insurance policy associated with the vehicle, which may be determined by reference to a risk category.

In one aspect, a computer-implemented method for testing the effectiveness of one or more autonomous operation features for controlling a virtual vehicle in a virtual test environment may be provided. The computer-implemented method may include receiving a set of computer-readable instructions for implementing the one or more autonomous operation features, executing the one or more software routines, receiving one or more test input signals that simulate the one or more signals from at least one sensor, generating one or more test output signals for the virtual vehicle in response to the received one or more test input signals, predicting one or more responses of the virtual vehicle in the virtual test environment to the one or more test output signals, and/or determining a measure of the effectiveness of the one or more autonomous operation features based upon the one or more predicted responses of the virtual vehicle to the one or more test output signals. The set of computer-readable instructions may include one or more software routines configured to receive one or more input signals from at least one sensor and generate one or more output signals for controlling a vehicle. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer system for testing the effectiveness of one or more autonomous operation features for controlling a virtual vehicle in a virtual test environment may be provided. The computer system may include one or more processors and a non-transitory program memory coupled to the one or more processors and storing executable instructions. The executable instruction may, when executed by the one or more processors, cause the computer system to receive a set of computer-readable instructions for implementing the one or more autonomous operation features, execute the one or more software routines, receive one or more test input signals that simulate the one or more signals from at least one sensor, generate one or more test output signals for the virtual vehicle in response to the received one or more test input signals, predict one or more responses of the virtual vehicle in the virtual test environment to the one or more test output signals, and/or determine a measure of the effectiveness of the one or more autonomous operation features based upon the one or more predicted responses of the virtual vehicle to the one or more test output signals. The set of computer-readable instructions may include one or more software routines configured to receive one or more input signals from at least one sensor and generate one or more output signals for controlling a vehicle. The system may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In yet another aspect, a tangible, non-transitory computer-readable medium storing instructions for testing the effectiveness of one or more autonomous operation features for controlling a virtual vehicle in a virtual test environment may be provided. The instructions may, when executed by at least one processor of a computer system, cause the computer system to receive a set of computer-readable instructions for implementing the one or more autonomous operation features, execute the one or more software routines, receive one or more test input signals that simulate the one or more signals from at least one sensor, generate one or more test output signals for the virtual vehicle in response to the received one or more test input signals, predict one or more responses of the virtual vehicle in the virtual test environment to the one or more test output signals, and/or determine a measure of the effectiveness of the one or more autonomous operation features based upon the one or more predicted responses of the virtual vehicle to the one or more test output signals. The set of computer-readable instructions may include one or more software routines configured to receive one or more input signals from at least one sensor and generate one or more output signals for controlling a vehicle. The instructions of the computer-readable medium may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In some systems or methods, the one or more test input signals may be received from a database containing a plurality of test signals. Alternatively, the test input signals may be received by generating a simulation of the virtual vehicle in the virtual test environment, determining simulated sensor data associated with the virtual vehicle in the virtual test environment, and determining the one or more test input signals based upon the simulated sensor data.

In further embodiments, the measure of the effectiveness of the one or more autonomous operation features may include one or more risk levels associated with autonomous operation of the virtual vehicle by the one or more autonomous operation features. Determining the measure of the effectiveness of the one or more autonomous operation features may also include determining the measure of the effectiveness of the one or more autonomous operation features in a plurality of virtual test environments. Each such virtual test environments may be based upon observed data regarding actual environments recorded by one or more sensors communicatively connected to a plurality of vehicles operating outside the virtual test environment.

Determining the one or more risk levels associated with the one or more autonomous operation features may include predicting the one or more risk levels based upon a comparison of (i) the one or more test output signals generated by the one or more software routines, (ii) one or more other test output signals generated by one or more other software routines of one or more other autonomous operation features in response to one or more other test input signals, and/or (iii) observed operating data regarding the one or more other autonomous operation features disposed within a plurality of other vehicles operating outside the virtual test environment. Additionally, the observed operating data may include data regarding actual losses associated with insurance policies covering the plurality of other vehicles having the one or more other autonomous operation features.

In accordance with the described embodiments, the disclosure herein also generally addresses systems and methods for monitoring the use of a vehicle having one or more autonomous (and/or semi-autonomous) operation features and determining risk associated with the one or more autonomous (and/or semi-autonomous) operation features based upon control decisions generated by the one or more autonomous (and/or semi-autonomous) operation features. An on-board computer or mobile device may monitor and record vehicle operating data, including information regarding the decisions made by the autonomous operation features, regardless of whether the decisions are actually used to control the vehicle. A server may receive the operating data and may process this data to determine risk levels associated with operation of the vehicle under the current conditions using a variety of available autonomous operation features, configurations, or settings.

In one aspect, a computer-implemented method for monitoring a vehicle having one or more autonomous operation features for controlling the vehicle may be provided. The computer-implemented method may include receiving operating data regarding operation of the vehicle, recording a log of the received operating data, receiving actual loss data regarding losses associated with insurance policies covering

a plurality of other vehicles having the one or more autonomous operation features, and/or determining at least one risk level associated with the vehicle based at least in part upon the recorded log of the operating data and the received actual loss data. The operating data may include (i) information from one or more sensors disposed within the vehicle, (ii) information regarding the one or more autonomous operation features, and/or (iii) information regarding control decisions generated by the one or more autonomous operation features. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer system for monitoring a vehicle having one or more autonomous operation features for controlling the vehicle may be provided. The computer system may include one or more processors and a non-transitory program memory coupled to the one or more processors and storing executable instructions. The executable instruction may, when executed by the one or more processors, cause the computer system to receive operating data regarding operation of the vehicle, record a log of the received operating data, receive actual loss data regarding losses associated with insurance policies covering a plurality of other vehicles having the one or more autonomous operation features, and/or determine at least one risk level associated with the vehicle based at least in part upon the recorded log of the operating data and the received actual loss data. The operating data may include (i) information from one or more sensors disposed within the vehicle, (ii) information regarding the one or more autonomous operation features, and/or (iii) information regarding control decisions generated by the one or more autonomous operation features. The system may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In yet another aspect, a tangible, non-transitory computer-readable medium storing instructions for monitoring a vehicle having one or more autonomous operation features for controlling the vehicle may be provided. The instructions may, when executed by at least one processor of a computer system, cause the computer system to receive operating data regarding operation of the vehicle, record a log of the received operating data, receive actual loss data regarding losses associated with insurance policies covering a plurality of other vehicles having the one or more autonomous operation features, and/or determine at least one risk level associated with the vehicle based at least in part upon the recorded log of the operating data and the received actual loss data. The operating data may include (i) information from one or more sensors disposed within the vehicle, (ii) information regarding the one or more autonomous operation features, and/or (iii) information regarding control decisions generated by the one or more autonomous operation features. The instructions of the computer-readable medium may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In some embodiments, the information regarding the control decisions generated by the one or more autonomous operation features may include information regarding control decisions not implemented to control the vehicle, which may include the following: an alternative control decision not selected by the one or more autonomous operation features to control the vehicle and/or a control decision not implemented because the autonomous operation feature was disabled.

Each entry in the log of the operating data may include a timestamp associated with the recorded operating data, and each timestamp may include the following: date, time, location, vehicle environment, vehicle condition, autonomous operation feature settings, and/or autonomous operation feature configuration information. External data regarding the vehicle environment for each entry in the log of the operating data may be further included, including information regarding the following: road conditions, weather conditions, nearby traffic conditions, type of road, construction conditions, presence of pedestrians, presence of other obstacles, and/or availability of autonomous communications from external sources. The external data may be associated with log entries based upon the timestamp associated with each entry. In some embodiments, the at least one risk level associated with the vehicle may be further determined based at least in part upon the external data regarding the vehicle environment. Additionally, the operating data may be received by a mobile device within the vehicle. The mobile device may communicate the received operating data to a server via a network, and the server may record the log of the operating data.

Some systems or methods may further receive a request for a quote of a premium associated with a vehicle insurance policy and presenting an option to purchase the vehicle insurance policy to a customer associated with the vehicle. They may also determine a premium associated with the vehicle insurance policy based upon the at least one risk level.

In accordance with the described embodiments, the disclosure herein also generally addresses systems and methods for monitoring the use of a vehicle having one or more autonomous (and/or semi-autonomous) operation features and determining fault following the occurrence of an accident involving the vehicle. An on-board computer or mobile device may monitor and record vehicle operating data, including sensor data and data from the one or more autonomous operation features. A server may receive the operating data and may process this data to determine the cause of and fault for the accident. These fault determination may then be used, at least in part (i.e., wholly or partially), to determine coverage levels associated with an insurance policy associated with the vehicle and/or an adjustment to risk levels associated with the autonomous operation features.

In one aspect, a computer-implemented method for determining fault relating to a collision or other loss may be provided. The computer-implemented method may include receiving an indication of an accident involving a vehicle having one or more autonomous (and/or semi-autonomous) operation features for controlling the vehicle, receiving operating data regarding operation of the vehicle during a time period including the time of the accident, receiving information regarding use levels of the one or more autonomous operation features during the time period including the time of the accident, determining an allocation of fault for the accident based upon, at least in part (i.e., wholly or partially), the received operating data and the use levels of the one or more autonomous operation features, and/or determining one or more coverage levels associated with a vehicle insurance policy based upon, at least in part (i.e., wholly or partially), the determined allocation of fault. The indication of the accident may be generated based upon the received operating data. The operating data may include information from one or more sensors disposed within the vehicle and/or information regarding the operation of the one or more autonomous operation features. Additionally, the autonomous operation features may include one or more autonomous communication features, in which case the operating data may include communication data from exter-

nal sources. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer system for determining fault relating to a collision or other loss may be provided. The computer system may include one or more processors, one or more communication modules adapted to communicate data, and a non-transitory program memory coupled to the one or more processors and storing executable instructions. The executable instruction may, when executed by the one or more processors, cause the computer system to receive an indication of an accident involving a vehicle having one or more autonomous (and/or semi-autonomous) operation features for controlling the vehicle, receive operating data regarding operation of the vehicle during a time period including the time of the accident, receive information regarding use levels of the one or more autonomous operation features during the time period including the time of the accident, determine an allocation of fault for the accident based upon the received operating data and the use levels of the one or more autonomous operation features, and/or determine one or more coverage levels associated with a vehicle insurance policy based upon the determined allocation of fault. The indication of the accident may be generated based upon the received operating data. The operating data may include information from one or more sensors disposed within the vehicle and/or information regarding the operation of the one or more autonomous operation features. Additionally, the autonomous operation features may include one or more autonomous communication features, in which case the operating data may include communication data from external sources. The system may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In yet another aspect, a tangible, non-transitory computer-readable medium storing instructions for determining fault relating to a collision or other loss may be provided. The instructions may, when executed by at least one processor of a computer system, cause the computer system to receive an indication of an accident involving a vehicle having one or more autonomous (and/or semi-autonomous) operation features for controlling the vehicle, receive operating data regarding operation of the vehicle during a time period including the time of the accident, receive information regarding use levels of the one or more autonomous operation features during the time period including the time of the accident, determine an allocation of fault for the accident based upon the received operating data and the use levels of the one or more autonomous operation features, and/or determine one or more coverage levels associated with a vehicle insurance policy based upon the determined allocation of fault. The indication of the accident may be generated based upon the received operating data. The operating data may include information from one or more sensors disposed within the vehicle and/or information regarding the operation of the one or more autonomous operation features. Additionally, the autonomous operation features may include one or more autonomous communication features, in which case the operating data may include communication data from external sources. The instructions of the computer-readable medium may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

Determining the allocation of fault may include allocating fault for the accident between one or more of the following: the vehicle operator, the one or more autonomous operation (and/or semi-autonomous) features as a group, each of the one or more autonomous (and/or semi-autonomous) operation features separately, and/or a third party. Allocating fault may further include determining one or more of the following: a point of impact on the vehicle, a point of impact on one or more additional vehicles, a velocity of the vehicle, a velocity of one or more additional vehicles, a movement of the vehicle, a movement of one or more additional vehicles, a location of one or more obstructions, a movement of one or more obstructions, a location of one or more pedestrians, a movement of one or more pedestrians, a measure of road surface integrity, a measure of road surface friction, a location of one or more traffic signs, a location of one or more traffic signals, an indication of a state of one or more traffic signals, a control signal generated by one or more autonomous operation features of the vehicle, and/or a control signal generated by one or more autonomous operation features of one or more additional vehicles.

In some embodiments, the one or more coverage levels may be determined based upon whether the determined allocation of fault indicates a vehicle operator is at least partially at fault for the accident. The coverage levels may be further determined based upon the proportion of fault allocated to the vehicle operator. The one or more coverage levels may include the following: a deductible, a type of coverage, a maximum coverage limit, an estimate of a cost to repair the vehicle, an estimate of a cost to replace the vehicle, an estimate of a cost to repair other property, an estimate of a cost to replace other property, and/or an estimate of a payment of medical expenses. In some embodiments, determining the one or more coverage levels may further include determining to cancel the vehicle insurance policy.

Some embodiments may include determining an adjustment to a cost associated with a vehicle insurance policy based upon the allocation of fault when the at least a portion of the fault is determined to be allocated to the vehicle operator. Additionally, some embodiments may include determining an adjustment to a risk level associated with one or more autonomous (and/or semi-autonomous) operation features based upon the allocation of fault when the at least a portion of the fault is determined to be allocated to the one or more autonomous (and/or semi-autonomous) operation features. The cost associated with the vehicle insurance policy may include a premium, a surcharge, a penalty, a rate, and/or a rate category. Other embodiments may include presenting the determined allocation of fault and/or the determined coverage levels to a reviewer for verification and/or receiving an indication of verification from the reviewer.

In some embodiments, the system or method may cause one or more options associated with the determined one or more coverage levels to be presented to a customer for review. A selection by the customer of at least one of the one or more options may be received, based upon which the vehicle insurance policy may be adjusted.

BRIEF DESCRIPTION OF THE DRAWINGS

Advantages will become more apparent to those skilled in the art from the following description of the preferred embodiments which have been shown and described by way of illustration. As will be realized, the present embodiments may be capable of other and different embodiments, and their details are capable of modification in various respects. Accordingly, the drawings and description are to be regarded as illustrative in nature and not as restrictive.

The figures described below depict various aspects of the applications, methods, and systems disclosed herein. It should be understood that each figure depicts an embodiment of a particular aspect of the disclosed applications, systems and methods, and that each of the figures is intended to accord with a possible embodiment thereof. Furthermore, wherever possible, the following description refers to the reference numerals included in the following figures, in which features depicted in multiple figures are designated with consistent reference numerals.

FIG. **1** illustrates a block diagram of an exemplary computer network, a computer server, a mobile device, and an on-board computer for implementing autonomous vehicle operation, monitoring, evaluation, and insurance processes in accordance with the described embodiments;

FIG. **2** illustrates a block diagram of an exemplary on-board computer or mobile device;

FIG. **3** illustrates a flow diagram of an exemplary autonomous vehicle operation method in accordance with the presently described embodiments;

FIGS. **4**A-B illustrate flow diagrams of an exemplary autonomous vehicle operation monitoring method in accordance with the presently described embodiments;

FIG. **5** illustrates a flow diagram of an exemplary autonomous operation feature evaluation method for determining the effectiveness of autonomous operation features in accordance with the presently described embodiments;

FIG. **6** illustrates a flow diagram of an exemplary autonomous operation feature testing method for presenting test conditions to an autonomous operation feature and observing and recording responses to the test conditions in accordance with the presently described embodiments;

FIG. **7** illustrates a flow diagram of an exemplary autonomous feature evaluation method for determining the effectiveness of an autonomous operation feature under a set of environmental conditions, configuration conditions, and settings in accordance with the presently described embodiments;

FIG. **8** illustrates a flow diagram depicting an exemplary embodiment of a fully autonomous vehicle insurance pricing method in accordance with the presently described embodiments;

FIG. **9** illustrates a flow diagram depicting an exemplary embodiment of a partially autonomous vehicle insurance pricing method in accordance with the presently described embodiments; and

FIG. **10** illustrates a flow diagram depicting an exemplary embodiment of an autonomous vehicle insurance pricing method for determining risk and premiums for vehicle insurance policies covering autonomous vehicles with autonomous communication features in accordance with the presently described embodiments; and

FIG. **11** illustrates a flow diagram of an exemplary autonomous operation feature monitoring and feedback method;

FIG. **12** illustrates a flow diagram of an exemplary autonomous operation feature monitoring and alert method;

FIG. **13** illustrates a flow diagram of an exemplary fault determination method for determining fault following an accident based upon sensor data and communication data; and

FIG. **14** illustrates a high-level flow diagram of an exemplary autonomous automobile insurance pricing system.

DETAILED DESCRIPTION

The systems and methods disclosed herein generally relate to evaluating, monitoring, pricing, and processing vehicle insurance policies for vehicles including autonomous (or semi-autonomous) vehicle operation features. The autonomous operation features may take full control of the vehicle under certain conditions, viz. fully autonomous operation, or the autonomous operation features may assist the vehicle operator in operating the vehicle, viz. partially autonomous operation. Fully autonomous operation features may include systems within the vehicle that pilot the vehicle to a destination with or without a vehicle operator present (e.g., an operating system for a driverless car). Partially autonomous operation features may assist the vehicle operator in limited ways (e.g., automatic braking or collision avoidance systems). The autonomous operation features may affect the risk related to operating a vehicle, both individually and/or in combination. To account for these effects on risk, some embodiments evaluate the quality of each autonomous operation feature and/or combination of features. This may be accomplished by testing the features and combinations in controlled environments, as well as analyzing the effectiveness of the features in the ordinary course of vehicle operation. New autonomous operation features may be evaluated based upon controlled testing and/or estimating ordinary-course performance based upon data regarding other similar features for which ordinary-course performance is known.

Some autonomous operation features may be adapted for use under particular conditions, such as city driving or highway driving. Additionally, the vehicle operator may be able to configure settings relating to the features or may enable or disable the features at will. Therefore, some embodiments monitor use of the autonomous operation features, which may include the settings or levels of feature use during vehicle operation. Information obtained by monitoring feature usage may be used to determine risk levels associated with vehicle operation, either generally or in relation to a vehicle operator. In such situations, total risk may be determined by a weighted combination of the risk levels associated with operation while autonomous operation features are enabled (with relevant settings) and the risk levels associated with operation while autonomous operation features are disabled. For fully autonomous vehicles, settings or configurations relating to vehicle operation may be monitored and used in determining vehicle operating risk.

Information regarding the risks associated with vehicle operation with and without the autonomous operation features may then be used to determine risk categories or premiums for a vehicle insurance policy covering a vehicle with autonomous operation features. Risk category or price may be determined based upon factors relating to the evaluated effectiveness of the autonomous vehicle features. The risk or price determination may also include traditional factors, such as location, vehicle type, and level of vehicle use. For fully autonomous vehicles, factors relating to vehicle operators may be excluded entirely. For partially autonomous vehicles, factors relating to vehicle operators may be reduced in proportion to the evaluated effectiveness and monitored usage levels of the autonomous operation features. For vehicles with autonomous communication features that obtain information from external sources (e.g., other vehicles or infrastructure), the risk level and/or price determination may also include an assessment of the availability of external sources of information. Location and/or timing of vehicle use may thus be monitored and/or weighted to determine the risk associated with operation of the vehicle.

Autonomous Automobile Insurance

The present embodiments may relate to assessing and pricing insurance based upon autonomous (or semi-autonomous) functionality of a vehicle, and not the human driver. A smart vehicle may maneuver itself without human intervention and/or include sensors, processors, computer instructions, and/or other components that may perform or direct certain actions conventionally performed by a human driver.

An analysis of how artificial intelligence facilitates avoiding accidents and/or mitigates the severity of accidents may be used to build a database and/or model of risk assessment. After which, automobile insurance risk and/or premiums (as well as insurance discounts, rewards, and/or points) may be adjusted based upon autonomous or semi-autonomous vehicle functionality, such as by groups of autonomous or semi-autonomous functionality or individual features. In one aspect, an evaluation may be performed of how artificial intelligence, and the usage thereof, impacts automobile accidents and/or automobile insurance claims.

The types of autonomous or semi-autonomous vehicle-related functionality or technology that may be used with the present embodiments to replace human driver actions may include and/or be related to the following types of functionality: (a) fully autonomous (driverless); (b) limited driver control; (c) vehicle-to-vehicle (V2V) wireless communication; (d) vehicle-to-infrastructure (and/or vice versa) wireless communication; (e) automatic or semi-automatic steering; (f) automatic or semi-automatic acceleration; (g) automatic or semi-automatic braking; (h) automatic or semi-automatic blind spot monitoring; (i) automatic or semi-automatic collision warning; (j) adaptive cruise control; (k) automatic or semi-automatic parking/parking assistance; (l) automatic or semi-automatic collision preparation (windows roll up, seat adjusts upright, brakes pre-charge, etc.); (m) driver acuity/alertness monitoring; (n) pedestrian detection; (o) autonomous or semi-autonomous backup systems; (p) road mapping systems; (q) software security and anti-hacking measures; (r) theft prevention/automatic return; (s) automatic or semi-automatic driving without occupants; and/or other functionality.

The adjustments to automobile insurance rates or premiums based upon the autonomous or semi-autonomous vehicle-related functionality or technology may take into account the impact of such functionality or technology on the likelihood of a vehicle accident or collision occurring. For instance, a processor may analyze historical accident information and/or test data involving vehicles having autonomous or semi-autonomous functionality. Factors that may be analyzed and/or accounted for that are related to insurance risk, accident information, or test data may include (1) point of impact; (2) type of road; (3) time of day; (4) weather conditions; (5) road construction; (6) type/length of trip; (7) vehicle style; (8) level of pedestrian traffic; (9) level of vehicle congestion; (10) atypical situations (such as manual traffic signaling); (11) availability of internet connection for the vehicle; and/or other factors. These types of factors may also be weighted according to historical accident information, predicted accidents, vehicle trends, test data, and/or other considerations.

In one aspect, the benefit of one or more autonomous or semi-autonomous functionalities or capabilities may be determined, weighted, and/or otherwise characterized. For instance, the benefit of certain autonomous or semi-autonomous functionality may be substantially greater in city or congested traffic, as compared to open road or country driving traffic. Additionally or alternatively, certain autonomous or semi-autonomous functionality may only work effectively below a certain speed, i.e., during city driving or driving in congestion. Other autonomous or semi-autonomous functionality may operate more effectively on the highway and away from city traffic, such as cruise control. Further individual autonomous or semi-autonomous functionality may be impacted by weather, such as rain or snow, and/or time of day (day light versus night). As an example, fully automatic or semi-automatic lane detection warnings may be impacted by rain, snow, ice, and/or the amount of sunlight (all of which may impact the imaging or visibility of lane markings painted onto a road surface, and/or road markers or street signs).

Automobile insurance premiums, rates, discounts, rewards, refunds, points, etc. may be adjusted based upon the percentage of time or vehicle usage that the vehicle is the driver, i.e., the amount of time a specific driver uses each type of autonomous (or even semi-autonomous) vehicle functionality. In other words, insurance premiums, discounts, rewards, etc. may be adjusted based upon the percentage of vehicle usage during which the autonomous or semi-autonomous functionality is in use. For example, automobile insurance risk, premiums, discounts, etc. for an automobile having one or more autonomous or semi-autonomous functionalities may be adjusted and/or set based upon the percentage of vehicle usage that the one or more individual autonomous or semi-autonomous vehicle functionalities are in use, anticipated to be used or employed by the driver, and/or otherwise operating.

Such usage information for a particular vehicle may be gathered over time and/or via remote wireless communication with the vehicle. One embodiment may involve a processor on the vehicle, such as within a vehicle control system or dashboard, monitoring in real-time whether vehicle autonomous or semi-autonomous functionality is currently operating. Other types of monitoring may be remotely performed, such as via wireless communication between the vehicle and a remote server, or wireless communication between a vehicle-mounted dedicated device (that is configured to gather autonomous or semi-autonomous functionality usage information) and a remote server.

In one embodiment, if the vehicle is currently employing autonomous or semi-autonomous functionality, the vehicle may send a Vehicle-to-Vehicle (V2V) wireless communication to a nearby vehicle also employing the same or other type(s) of autonomous or semi-autonomous functionality.

As an example, the V2V wireless communication from the first vehicle to the second vehicle (following the first vehicle) may indicate that the first vehicle is autonomously braking, and the degree to which the vehicle is automatically braking and/or slowing down. In response, the second vehicle may also automatically or autonomously brake as well, and the degree of automatically braking or slowing down of the second vehicle may be determined to match, or even exceed, that of the first vehicle. As a result, the second vehicle, traveling directly or indirectly, behind the first vehicle, may autonomously safely break in response to the first vehicle autonomously breaking.

As another example, the V2V wireless communication from the first vehicle to the second vehicle may indicate that the first vehicle is beginning or about to change lanes or turn. In response, the second vehicle may autonomously take appropriate action, such as automatically slow down, change lanes, turn, maneuver, etc. to avoid the first vehicle.

As noted above, the present embodiments may include remotely monitoring, in real-time and/or via wireless communication, vehicle autonomous or semi-autonomous func-

tionality. From such remote monitoring, the present embodiments may remotely determine that a vehicle accident has occurred. As a result, emergency responders may be informed of the location of the vehicle accident, such as via wireless communication, and/or quickly dispatched to the accident scene.

The present embodiments may also include remotely monitoring, in real-time or via wireless communication, that vehicle autonomous or semi-autonomous functionality is, or is not, in use, and/or collect information regarding the amount of usage of the autonomous or semi-autonomous functionality. From such remote monitoring, a remote server may remotely send a wireless communication to the vehicle to prompt the human driver to engage one or more specific vehicle autonomous or semi-autonomous functionalities.

Another embodiment may enable a vehicle to wirelessly communicate with a traffic light, railroad crossing, toll both, marker, sign, or other equipment along the side of a road or highway. As an example, a traffic light may wirelessly indicate to the vehicle that the traffic light is about to switch from green to yellow, or from yellow to red. In response to such an indication remotely received from the traffic light, the autonomous or semi-autonomous vehicle may automatically start to brake, and/or present or issue a warning/alert to the human driver. After which, the vehicle may wirelessly communicate with the vehicles traveling behind it that the traffic light is about to change and/or that the vehicle has started to brake or slow down such that the following vehicles may also automatically brake or slow down accordingly.

Insurance premiums, rates, ratings, discounts, rewards, special offers, points, programs, refunds, claims, claim amounts, etc. may be adjusted for, or may otherwise take into account, the foregoing functionality and/or the other functionality described herein. For instance, insurance policies may be updated based upon autonomous or semi-autonomous vehicle functionality; V2V wireless communication-based autonomous or semi-autonomous vehicle functionality; and/or vehicle-to-infrastructure or infrastructure-to-vehicle wireless communication-based autonomous or semi-autonomous vehicle functionality.

Exemplary Embodiments

Insurance providers may currently develop a set of rating factors based upon the make, model, and model year of a vehicle. Models with better loss experience receive lower factors, and thus lower rates. One reason that this current rating system cannot be used to assess risk for autonomous technology is that many autonomous features vary for the same model. For example, two vehicles of the same model may have different hardware features for automatic braking, different computer instructions for automatic steering, and/or different artificial intelligence system versions. The current make and model rating may also not account for the extent to which another "driver," in this case the vehicle itself, is controlling the vehicle.

The present embodiments may assess and price insurance risks at least in part based upon autonomous or semi-autonomous vehicle technology that replaces actions of the driver. In a way, the vehicle-related computer instructions and artificial intelligence may be viewed as a "driver."

In one computer-implemented method of adjusting or generating an insurance policy, (1) data may be captured by a processor (such as via wireless communication) to determine the autonomous or semi-autonomous technology or functionality associated with a specific vehicle that is, or is to be, covered by insurance; (2) the received data may be compared by the processor to a stored baseline of vehicle data (such as actual accident information, and/or autonomous or semi-autonomous vehicle testing data); (3) risk may be identified or assessed by the processor based upon the specific vehicle's ability to make driving decisions and/or avoid or mitigate crashes; (4) an insurance policy may be adjusted (or generated or created), or an insurance premium may be determined by the processor based upon the risk identified that is associated with the specific vehicle's autonomous or semi-autonomous ability or abilities; and/or (5) the insurance policy and/or premium may be presented on a display or otherwise provided to the policyholder or potential customer for their review and/or approval. The method may include additional, fewer, or alternate actions, including those discussed below and elsewhere herein.

The method may include evaluating the effectiveness of artificial intelligence and/or vehicle technology in a test environment, and/or using real driving experience. The identification or assessment of risk performed by the method (and/or the processor) may be dependent upon the extent of control and decision making that is assumed by the vehicle, rather than the driver.

Additionally or alternatively, the identification or assessment of insurance and/or accident-based risk may be dependent upon the ability of the vehicle to use external information (such as vehicle-to-vehicle and vehicle-to-infrastructure communication) to make driving decisions. The risk assessment may further be dependent upon the availability of such external information. For instance, a vehicle (or vehicle owner) may be associated with a geographical location, such as a large city or urban area, where such external information is readily available via wireless communication. On the other hand, a small town or rural area may or may not have such external information available.

The information regarding the availability of autonomous or semi-autonomous vehicle technology, such as a particular factory-installed hardware and/or software package, version, revision, or update, may be wirelessly transmitted to a remote server for analysis. The remote server may be associated with an insurance provider, vehicle manufacturer, autonomous technology provider, and/or other entity.

The driving experience and/or usage of the autonomous or semi-autonomous vehicle technology may be monitored in real time, small timeframes, and/or periodically to provide feedback to the driver, insurance provider, and/or adjust insurance policies or premiums. In one embodiment, information may be wirelessly transmitted to the insurance provider, such as from a transceiver associated with a smart car to an insurance provider remote server.

Insurance policies, including insurance premiums, discounts, and rewards, may be updated, adjusted, and/or determined based upon hardware or software functionality, and/or hardware or software upgrades. Insurance policies, including insurance premiums, discounts, etc. may also be updated, adjusted, and/or determined based upon the amount of usage and/or the type(s) of the autonomous or semi-autonomous technology employed by the vehicle.

In one embodiment, performance of autonomous driving software and/or sophistication of artificial intelligence may be analyzed for each vehicle. An automobile insurance premium may be determined by evaluating how effectively the vehicle may be able to avoid and/or mitigate crashes and/or the extent to which the driver's control of the vehicle is enhanced or replaced by the vehicle's software and artificial intelligence.

When pricing a vehicle with autonomous driving technology, artificial intelligence capabilities, rather than human decision making, may be evaluated to determine the relative risk of the insurance policy. This evaluation may be conducted using multiple techniques. Vehicle technology may be assessed in a test environment, in which the ability of the artificial intelligence to detect and avoid potential crashes may be demonstrated experimentally. For example, this may include a vehicle's ability to detect a slow-moving vehicle ahead and/or automatically apply the brakes to prevent a collision.

Additionally, actual loss experience of the software in question may be analyzed. Vehicles with superior artificial intelligence and crash avoidance capabilities may experience lower insurance losses in real driving situations.

Results from both the test environment and/or actual insurance losses may be compared to the results of other autonomous software packages and/or vehicles lacking autonomous driving technology to determine a relative risk factor (or level of risk) for the technology in question. This risk factor (or level of risk) may be applicable to other vehicles that utilize the same or similar autonomous operation software package(s).

Emerging technology, such as new iterations of artificial intelligence systems, may be priced by combining its individual test environment assessment with actual losses corresponding to vehicles with similar autonomous operation software packages. The entire vehicle software and artificial intelligence evaluation process may be conducted with respect to various technologies and/or elements that affect driving experience. For example, a fully autonomous vehicle may be evaluated based on its vehicle-to-vehicle communications. A risk factor could then be determined and applied when pricing the vehicle. The driver's past loss experience and/or other driver risk characteristics may not be considered for fully autonomous vehicles, in which all driving decisions are made by the vehicle's artificial intelligence.

In one embodiment, a separate portion of the automobile insurance premium may be based explicitly on the artificial intelligence software's driving performance and characteristics. The artificial intelligence pricing model may be combined with traditional methods for semi-autonomous vehicles. Insurance pricing for fully autonomous, or driverless, vehicles may be based upon the artificial intelligence model score by excluding traditional rating factors that measure risk presented by the drivers. Evaluation of vehicle software and/or artificial intelligence may be conducted on an aggregate basis or for specific combinations of technology and/or driving factors or elements (as discussed elsewhere herein). The vehicle software test results may be combined with actual loss experience to determine relative risk.

Exemplary Autonomous Vehicle Operation System

FIG. **1** illustrates a block diagram of an exemplary autonomous vehicle insurance system **100** on which the exemplary methods described herein may be implemented. The high-level architecture includes both hardware and software applications, as well as various data communications channels for communicating data between the various hardware and software components. The autonomous vehicle insurance system **100** may be roughly divided into front-end components **102** and back-end components **104**. The front-end components **102** may obtain information regarding a vehicle **108** (e.g., a car, truck, motorcycle, etc.) and the surrounding environment. An on-board computer **114** may utilize this information to operate the vehicle **108** according to an autonomous operation feature or to assist the vehicle operator in operating the vehicle **108**. To monitor the vehicle **108**, the front-end components **102** may include one or more sensors **120** installed within the vehicle **108** that may communicate with the on-board computer **114**. The front-end components **102** may further process the sensor data using the on-board computer **114** or a mobile device **110** (e.g., a smart phone, a tablet computer, a special purpose computing device, etc.) to determine when the vehicle is in operation and information regarding the vehicle. In some embodiments of the system **100**, the front-end components **102** may communicate with the back-end components **104** via a network **130**. Either the on-board computer **114** or the mobile device **110** may communicate with the back-end components **104** via the network **130** to allow the back-end components **104** to record information regarding vehicle usage. The back-end components **104** may use one or more servers **140** to receive data from the front-end components **102**, determine use and effectiveness of autonomous operation features, determine risk levels or premium price, and/or facilitate purchase or renewal of an autonomous vehicle insurance policy.

The front-end components **102** may be disposed within or communicatively connected to one or more on-board computers **114**, which may be permanently or removably installed in the vehicle **108**. The on-board computer **114** may interface with the one or more sensors **120** within the vehicle **108** (e.g., an ignition sensor, an odometer, a system clock, a speedometer, a tachometer, an accelerometer, a gyroscope, a compass, a geolocation unit, a camera, a distance sensor, etc.), which sensors may also be incorporated within or connected to the on-board computer **114**. The front end components **102** may further include a communication component **122** to transmit information to and receive information from external sources, including other vehicles, infrastructure, or the back-end components **104**. In some embodiments, the mobile device **110** may supplement the functions performed by the on-board computer **114** described herein by, for example, sending or receiving information to and from the mobile server **140** via the network **130**. In other embodiments, the on-board computer **114** may perform all of the functions of the mobile device **110** described herein, in which case no mobile device **110** may be present in the system **100**. Either or both of the mobile device **110** or on-board computer **114** may communicate with the network **130** over links **112** and **118**, respectively. Additionally, the mobile device **110** and on-board computer **114** may communicate with one another directly over link **116**.

The mobile device **110** may be either a general-use personal computer, cellular phone, smart phone, tablet computer, or a dedicated vehicle use monitoring device. Although only one mobile device **110** is illustrated, it should be understood that a plurality of mobile devices **110** may be used in some embodiments. The on-board computer **114** may be a general-use on-board computer capable of performing many functions relating to vehicle operation or a dedicated computer for autonomous vehicle operation. Further, the on-board computer **114** may be installed by the manufacturer of the vehicle **108** or as an aftermarket modification or addition to the vehicle **108**. In some embodiments or under certain conditions, the mobile device **110** or on-board computer **114** may function as thin-client devices that outsource some or most of the processing to the server **140**.

The sensors **120** may be removably or fixedly installed within the vehicle **108** and may be disposed in various arrangements to provide information to the autonomous operation features. Among the sensors **120** may be included

one or more of a GPS unit, a radar unit, a LIDAR unit, an ultrasonic sensor, an infrared sensor, a camera, an accelerometer, a tachometer, or a speedometer. Some of the sensors **120** (e.g., radar, LIDAR, or camera units) may actively or passively scan the vehicle environment for obstacles (e.g., other vehicles, buildings, pedestrians, etc.), lane markings, or signs or signals. Other sensors **120** (e.g., GPS, accelerometer, or tachometer units) may provide data for determining the location or movement of the vehicle **108**. Other sensors **120** may be directed to the interior or passenger compartment of the vehicle **108**, such as cameras, microphones, pressure sensors, thermometers, or similar sensors to monitor the vehicle operator and/or passengers within the vehicle **108**. Information generated or received by the sensors **120** may be communicated to the on-board computer **114** or the mobile device **110** for use in autonomous vehicle operation.

In some embodiments, the communication component **122** may receive information from external sources, such as other vehicles or infrastructure. The communication component **122** may also send information regarding the vehicle **108** to external sources. To send and receive information, the communication component **122** may include a transmitter and a receiver designed to operate according to predetermined specifications, such as the dedicated short-range communication (DSRC) channel, wireless telephony, Wi-Fi, or other existing or later-developed communications protocols. The received information may supplement the data received from the sensors **120** to implement the autonomous operation features. For example, the communication component **122** may receive information that an autonomous vehicle ahead of the vehicle **108** is reducing speed, allowing the adjustments in the autonomous operation of the vehicle **108**.

In addition to receiving information from the sensors **120**, the on-board computer **114** may directly or indirectly control the operation of the vehicle **108** according to various autonomous operation features. The autonomous operation features may include software applications or modules implemented by the on-board computer **114** to control the steering, braking, or throttle of the vehicle **108**. To facilitate such control, the on-board computer **114** may be communicatively connected to the controls or components of the vehicle **108** by various electrical or electromechanical control components (not shown). In embodiments involving fully autonomous vehicles, the vehicle **108** may be operable only through such control components (not shown). In other embodiments, the control components may be disposed within or supplement other vehicle operator control components (not shown), such as steering wheels, accelerator or brake pedals, or ignition switches.

In some embodiments, the front-end components **102** communicate with the back-end components **104** via the network **130**. The network **130** may be a proprietary network, a secure public internet, a virtual private network or some other type of network, such as dedicated access lines, plain ordinary telephone lines, satellite links, cellular data networks, combinations of these. Where the network **130** comprises the Internet, data communications may take place over the network **130** via an Internet communication protocol. The back-end components **104** include one or more servers **140**. Each server **140** may include one or more computer processors adapted and configured to execute various software applications and components of the autonomous vehicle insurance system **100**, in addition to other software applications. The server **140** may further include a database **146**, which may be adapted to store data related to the operation of the vehicle **108** and its autonomous operation features. Such data might include, for example, dates and times of vehicle use, duration of vehicle use, use and settings of autonomous operation features, speed of the vehicle **108**, RPM or other tachometer readings of the vehicle **108**, lateral and longitudinal acceleration of the vehicle **108**, incidents or near collisions of the vehicle **108**, communication between the autonomous operation features and external sources, environmental conditions of vehicle operation (e.g., weather, traffic, road condition, etc.), errors or failures of autonomous operation features, or other data relating to use of the vehicle **108** and the autonomous operation features, which may be uploaded to the server **140** via the network **130**. The server **140** may access data stored in the database **146** when executing various functions and tasks associated with the evaluating feature effectiveness or assessing risk relating to an autonomous vehicle.

Although the autonomous vehicle insurance system **100** is shown to include one vehicle **108**, one mobile device **110**, one on-board computer **114**, and one server **140**, it should be understood that different numbers of vehicles **108**, mobile devices **110**, on-board computers **114**, and/or servers **140** may be utilized. For example, the system **100** may include a plurality of servers **140** and hundreds of mobile devices **110** or on-board computers **114**, all of which may be interconnected via the network **130**. Furthermore, the database storage or processing performed by the one or more servers **140** may be distributed among a plurality of servers **140** in an arrangement known as "cloud computing." This configuration may provide various advantages, such as enabling near real-time uploads and downloads of information as well as periodic uploads and downloads of information. This may in turn support a thin-client embodiment of the mobile device **110** or on-board computer **114** discussed herein.

The server **140** may have a controller **155** that is operatively connected to the database **146** via a link **156**. It should be noted that, while not shown, additional databases may be linked to the controller **155** in a known manner. For example, separate databases may be used for autonomous operation feature information, vehicle insurance policy information, and vehicle use information. The controller **155** may include a program memory **160**, a processor **162** (which may be called a microcontroller or a microprocessor), a random-access memory (RAM) **164**, and an input/output (I/O) circuit **166**, all of which may be interconnected via an address/data bus **165**. It should be appreciated that although only one microprocessor **162** is shown, the controller **155** may include multiple microprocessors **162**. Similarly, the memory of the controller **155** may include multiple RAMs **164** and multiple program memories **160**. Although the I/O circuit **166** is shown as a single block, it should be appreciated that the I/O circuit **166** may include a number of different types of I/O circuits. The RAM **164** and program memories **160** may be implemented as semiconductor memories, magnetically readable memories, or optically readable memories, for example. The controller **155** may also be operatively connected to the network **130** via a link **135**.

The server **140** may further include a number of software applications stored in a program memory **160**. The various software applications on the server **140** may include an autonomous operation information monitoring application **141** for receiving information regarding the vehicle **108** and its autonomous operation features, a feature evaluation application **142** for determining the effectiveness of autonomous operation features under various conditions, a com-

patibility evaluation application **143** for determining the effectiveness of combinations of autonomous operation features, a risk assessment application **144** for determining a risk category associated with an insurance policy covering an autonomous vehicle, and an autonomous vehicle insurance policy purchase application **145** for offering and facilitating purchase or renewal of an insurance policy covering an autonomous vehicle. The various software applications may be executed on the same computer processor or on different computer processors.

FIG. **2** illustrates a block diagram of an exemplary mobile device **110** or an exemplary on-board computer **114** consistent with the system **100**. The mobile device **110** or on-board computer **114** may include a display **202**, a GPS unit **206**, a communication unit **220**, an accelerometer **224**, one or more additional sensors (not shown), a user-input device (not shown), and/or, like the server **140**, a controller **204**. In some embodiments, the mobile device **110** and on-board computer **114** may be integrated into a single device, or either may perform the functions of both. The on-board computer **114** (or mobile device **110**) interfaces with the sensors **120** to receive information regarding the vehicle **108** and its environment, which information is used by the autonomous operation features to operate the vehicle **108**.

Similar to the controller **155**, the controller **204** may include a program memory **208**, one or more microcontrollers or microprocessors (MP) **210**, a RAM **212**, and an I/O circuit **216**, all of which are interconnected via an address/data bus **214**. The program memory **208** includes an operating system **226**, a data storage **228**, a plurality of software applications **230**, and/or a plurality of software routines **240**. The operating system **226**, for example, may include one of a plurality of general purpose or mobile platforms, such as the Android™, iOS®, or Windows® systems, developed by Google Inc., Apple Inc., and Microsoft Corporation, respectively. Alternatively, the operating system **226** may be a custom operating system designed for autonomous vehicle operation using the on-board computer **114**. The data storage **228** may include data such as user profiles and preferences, application data for the plurality of applications **230**, routine data for the plurality of routines **240**, and other data related to the autonomous operation features. In some embodiments, the controller **204** may also include, or otherwise be communicatively connected to, other data storage mechanisms (e.g., one or more hard disk drives, optical storage drives, solid state storage devices, etc.) that reside within the vehicle **108**.

As discussed with reference to the controller **155**, it should be appreciated that although FIG. **2** depicts only one microprocessor **210**, the controller **204** may include multiple microprocessors **210**. Similarly, the memory of the controller **204** may include multiple RAMs **212** and multiple program memories **208**. Although FIG. **2** depicts the I/O circuit **216** as a single block, the I/O circuit **216** may include a number of different types of I/O circuits. The controller **204** may implement the RAMs **212** and the program memories **208** as semiconductor memories, magnetically readable memories, or optically readable memories, for example.

The one or more processors **210** may be adapted and configured to execute any of one or more of the plurality of software applications **230** or any one or more of the plurality of software routines **240** residing in the program memory **204**, in addition to other software applications. One of the plurality of applications **230** may be an autonomous vehicle operation application **232** that may be implemented as a series of machine-readable instructions for performing the various tasks associated with implementing one or more of the autonomous operation features according to the autonomous vehicle operation method **300**. Another of the plurality of applications **230** may be an autonomous communication application **234** that may be implemented as a series of machine-readable instructions for transmitting and receiving autonomous operation information to or from external sources via the communication module **220**. Still another application of the plurality of applications **230** may include an autonomous operation monitoring application **236** that may be implemented as a series of machine-readable instructions for sending information regarding autonomous operation of the vehicle to the server **140** via the network **130**.

The plurality of software applications **230** may call various of the plurality of software routines **240** to perform functions relating to autonomous vehicle operation, monitoring, or communication. One of the plurality of software routines **240** may be a configuration routine **242** to receive settings from the vehicle operator to configure the operating parameters of an autonomous operation feature. Another of the plurality of software routines **240** may be a sensor control routine **244** to transmit instructions to a sensor **120** and receive data from the sensor **120**. Still another of the plurality of software routines **240** may be an autonomous control routine **246** that performs a type of autonomous control, such as collision avoidance, lane centering, or speed control. In some embodiments, the autonomous vehicle operation application **232** may cause a plurality of autonomous control routines **246** to determine control actions required for autonomous vehicle operation. Similarly, one of the plurality of software routines **240** may be a monitoring and reporting routine **248** that transmits information regarding autonomous vehicle operation to the server **140** via the network **130**. Yet another of the plurality of software routines **240** may be an autonomous communication routine **250** for receiving and transmitting information between the vehicle **108** and external sources to improve the effectiveness of the autonomous operation features. Any of the plurality of software applications **230** may be designed to operate independently of the software applications **230** or in conjunction with the software applications **230**.

When implementing the exemplary autonomous vehicle operation method **300**, the controller **204** of the on-board computer **114** may implement the autonomous vehicle operation application **232** to communicate with the sensors **120** to receive information regarding the vehicle **108** and its environment and process that information for autonomous operation of the vehicle **108**. In some embodiments including external source communication via the communication component **122** or the communication unit **220**, the controller **204** may further implement the autonomous communication application **234** to receive information for external sources, such as other autonomous vehicles, smart infrastructure (e.g., electronically communicating roadways, traffic signals, or parking structures), or other sources of relevant information (e.g., weather, traffic, local amenities). Some external sources of information may be connected to the controller **204** via the network **130**, such as the server **140** or internet-connected third-party databases (not shown). Although the autonomous vehicle operation application **232** and the autonomous communication application **234** are shown as two separate applications, it should be understood that the functions of the autonomous operation features may be combined or separated into any number of the software applications **230** or the software routines **240**.

When implementing the autonomous operation feature monitoring and evaluation methods **400-700**, the controller

204 may further implement the autonomous operation monitoring application 236 to communicate with the server 140 to provide information regarding autonomous vehicle operation. This may include information regarding settings or configurations of autonomous operation features, data from the sensors 120 regarding the vehicle environment, data from the sensors 120 regarding the response of the vehicle 108 to its environment, communications sent or received using the communication component 122 or the communication unit 220, operating status of the autonomous vehicle operation application 232 and the autonomous communication application 234, or commands sent from the on-board computer 114 to the control components (not shown) to operate the vehicle 108. The information may be received and stored by the server 140 implementing the autonomous operation information monitoring application 141, and the server 140 may then determine the effectiveness of autonomous operation under various conditions by implementing the feature evaluation application 142 and the compatibility evaluation application 143. The effectiveness of autonomous operation features and the extent of their use may be further used to determine risk associated with operation of the autonomous vehicle by the server 140 implementing the risk assessment application 144.

In addition to connections to the sensors 120, the mobile device 110 or the on-board computer 114 may include additional sensors, such as the GPS unit 206 or the accelerometer 224, which may provide information regarding the vehicle 108 for autonomous operation and other purposes. Furthermore, the communication unit 220 may communicate with other autonomous vehicles, infrastructure, or other external sources of information to transmit and receive information relating to autonomous vehicle operation. The communication unit 220 may communicate with the external sources via the network 130 or via any suitable wireless communication protocol network, such as wireless telephony (e.g., GSM, CDMA, LTE, etc.), Wi-Fi (802.11 standards), WiMAX, Bluetooth, infrared or radio frequency communication, etc. Furthermore, the communication unit 220 may provide input signals to the controller 204 via the I/O circuit 216. The communication unit 220 may also transmit sensor data, device status information, control signals, or other output from the controller 204 to one or more external sensors within the vehicle 108, mobile devices 110, on-board computers 114, or servers 140.

The mobile device 110 or the on-board computer 114 may include a user-input device (not shown) for receiving instructions or information from the vehicle operator, such as settings relating to an autonomous operation feature. The user-input device (not shown) may include a "soft" keyboard that is displayed on the display 202, an external hardware keyboard communicating via a wired or a wireless connection (e.g., a Bluetooth keyboard), an external mouse, a microphone, or any other suitable user-input device. The user-input device (not shown) may also include a microphone capable of receiving user voice input.

Exemplary Autonomous Vehicle Operation Method

FIG. 3 illustrates a flow diagram of an exemplary autonomous vehicle operation method 300, which may be implemented by the autonomous vehicle insurance system 100. The method 300 may begin at block 302 when the controller 204 receives a start signal. The start signal may be a command from the vehicle operator through the user-input device to enable or engage one or more autonomous operation features of the vehicle 108. In some embodiments, the vehicle operator 108 may further specify settings or configuration details for the autonomous operation features. For fully autonomous vehicles, the settings may relate to one or more destinations, route preferences, fuel efficiency preferences, speed preferences, or other configurable settings relating to the operation of the vehicle 108. In some embodiments, fully autonomous vehicles may include additional features or settings permitting them to operate without passengers or vehicle operators within the vehicle. For example, a fully autonomous vehicle may receive an instruction to find a parking space within the general vicinity, which the vehicle may do without the vehicle operator. The vehicle may then be returned to a selected location by a request from the vehicle operator via a mobile device 110 or otherwise. This feature may further be adapted to return a fully autonomous vehicle if lost or stolen.

For other autonomous vehicles, the settings may include enabling or disabling particular autonomous operation features, specifying thresholds for autonomous operation, specifying warnings or other information to be presented to the vehicle operator, specifying autonomous communication types to send or receive, specifying conditions under which to enable or disable autonomous operation features, or specifying other constraints on feature operation. For example, a vehicle operator may set the maximum speed for an adaptive cruise control feature with automatic lane centering. In some embodiments, the settings may further include a specification of whether the vehicle 108 should be operating as a fully or partially autonomous vehicle. In embodiments where only one autonomous operation feature is enabled, the start signal may consist of a request to perform a particular task (e.g., autonomous parking) or to enable a particular feature (e.g., autonomous braking for collision avoidance). In other embodiments, the start signal may be generated automatically by the controller 204 based upon predetermined settings (e.g., when the vehicle 108 exceeds a certain speed or is operating in low-light conditions). In some embodiments, the controller 204 may generate a start signal when communication from an external source is received (e.g., when the vehicle 108 is on a smart highway or near another autonomous vehicle).

After receiving the start signal at block 302, the controller 204 receives sensor data from the sensors 120 during vehicle operation at block 304. In some embodiments, the controller 204 may also receive information from external sources through the communication component 122 or the communication unit 220. The sensor data may be stored in the RAM 212 for use by the autonomous vehicle operation application 232. In some embodiments, the sensor data may be recorded in the data storage 228 or transmitted to the server 140 via the network 130. The sensor data may alternately either be received by the controller 204 as raw data measurements from one of the sensors 120 or may be preprocessed by the sensor 120 prior to being received by the controller 204. For example, a tachometer reading may be received as raw data or may be preprocessed to indicate vehicle movement or position. As another example, a sensor 120 comprising a radar or LIDAR unit may include a processor to preprocess the measured signals and send data representing detected objects in 3-dimensional space to the controller 204.

The autonomous vehicle operation application 232 or other applications 230 or routines 240 may cause the controller 204 to process the received sensor data at block 306 in accordance with the autonomous operation features. The controller 204 may process the sensor data to determine whether an autonomous control action is required or to determine adjustments to the controls of the vehicle 108. For example, the controller 204 may receive sensor data indicating a decreasing distance to a nearby object in the

vehicle's path and process the received sensor data to determine whether to begin braking (and, if so, how abruptly to slow the vehicle **108**). As another example, the controller **204** may process the sensor data to determine whether the vehicle **108** is remaining with its intended path (e.g., within lanes on a roadway). If the vehicle **108** is beginning to drift or slide (e.g., as on ice or water), the controller **204** may determine appropriate adjustments to the controls of the vehicle to maintain the desired bearing. If the vehicle **108** is moving within the desired path, the controller **204** may nonetheless determine whether adjustments are required to continue following the desired route (e.g., following a winding road). Under some conditions, the controller **204** may determine to maintain the controls based upon the sensor data (e.g., when holding a steady speed on a straight road).

When the controller **204** determines an autonomous control action is required at block **308**, the controller **204** may cause the control components of the vehicle **108** to adjust the operating controls of the vehicle to achieve desired operation at block **310**. For example, the controller **204** may send a signal to open or close the throttle of the vehicle **108** to achieve a desired speed. Alternatively, the controller **204** may control the steering of the vehicle **108** to adjust the direction of movement. In some embodiments, the vehicle **108** may transmit a message or indication of a change in velocity or position using the communication component **122** or the communication module **220**, which signal may be used by other autonomous vehicles to adjust their controls. As discussed further below, the controller **204** may also log or transmit the autonomous control actions to the server **140** via the network **130** for analysis.

The controller **204** may continue to receive and process sensor data at blocks **304** and **306** until an end signal is received by the controller **204** at block **312**. The end signal may be automatically generated by the controller **204** upon the occurrence of certain criteria (e.g., the destination is reached or environmental conditions require manual operation of the vehicle **108** by the vehicle operator). Alternatively, the vehicle operator may pause, terminate, or disable the autonomous operation feature or features using the user-input device or by manually operating the vehicle's controls, such as by depressing a pedal or turning a steering instrument. When the autonomous operation features are disabled or terminated, the controller **204** may either continue vehicle operation without the autonomous features or may shut off the vehicle **108**, depending upon the circumstances.

Where control of the vehicle **108** must be returned to the vehicle operator, the controller **204** may alert the vehicle operator in advance of returning to manual operation. The alert may include a visual, audio, or other indication to obtain the attention of the vehicle operator. In some embodiments, the controller **204** may further determine whether the vehicle operator is capable of resuming manual operation before terminating autonomous operation. If the vehicle operator is determined not be capable of resuming operation, the controller **204** may cause the vehicle to stop or take other appropriate action.

Exemplary Monitoring Method

FIG. **4**A is a flow diagram depicting an exemplary autonomous vehicle operation monitoring method **400**, which may be implemented by the autonomous vehicle insurance system **100**. The method **400** monitors the operation of the vehicle **108** and transmits information regarding the vehicle **108** to the server **140**, which information may then be used to determine autonomous operation feature effectiveness or usage rates to assess risk and price vehicle insurance policy premiums. The method **400** may be used both for testing autonomous operation features in a controlled environment of for determining feature use by an insured party. In alternative embodiments, the method **400** may be implemented whenever the vehicle **108** is in operation (manual or autonomous) or only when the autonomous operation features are enabled. The method **400** may likewise be implemented as either a real-time process, in which information regarding the vehicle **108** is communicated to the server **140** while monitoring is ongoing, or as a periodic process, in which the information is stored within the vehicle **108** and communicated to the server **140** at intervals (e.g., upon completion of a trip or when an incident occurs). In some embodiments, the method **400** may communicate with the server **140** in real-time when certain conditions exist (e.g., when a sufficient data connection through the network **130** exists or when no roaming charges would be incurred).

The method **400** may begin at block **402** when the controller **204** receives an indication of vehicle operation. The indication may be generated when the vehicle **108** is started or when an autonomous operation feature is enabled by the controller **204** or by input from the vehicle operator. In response to receiving the indication, the controller **204** may create a timestamp at block **404**. The timestamp may include information regarding the date, time, location, vehicle environment, vehicle condition, and autonomous operation feature settings or configuration information. The date and time may be used to identify one vehicle trip or one period of autonomous operation feature use, in addition to indicating risk levels due to traffic or other factors. The additional location and environmental data may include information regarding the position of the vehicle **108** from the GPS unit **206** and its surrounding environment (e.g., road conditions, weather conditions, nearby traffic conditions, type of road, construction conditions, presence of pedestrians, presence of other obstacles, availability of autonomous communications from external sources, etc.). Vehicle condition information may include information regarding the type, make, and model of the vehicle **108**, the age or mileage of the vehicle **108**, the status of vehicle equipment (e.g., tire pressure, non-functioning lights, fluid levels, etc.), or other information relating to the vehicle **108**. In some embodiments, the timestamp may be recorded on the client device **114**, the mobile device **110**, or the server **140**.

The autonomous operation feature settings may correspond to information regarding the autonomous operation features, such as those described above with reference to the autonomous vehicle operation method **300**. The autonomous operation feature configuration information may correspond to information regarding the number and type of the sensors **120**, the disposition of the sensors **120** within the vehicle **108**, the one or more autonomous operation features (e.g., the autonomous vehicle operation application **232** or the software routines **240**), autonomous operation feature control software, versions of the software applications **230** or routines **240** implementing the autonomous operation features, or other related information regarding the autonomous operation features. For example, the configuration information may include the make and model of the vehicle **108** (indicating installed sensors **120** and the type of on-board computer **114**), an indication of a malfunctioning or obscured sensor **120** in part of the vehicle **108**, information regarding additional after-market sensors **120** installed within the vehicle **108**, a software program type and version for a control program installed as an application **230** on the on-board computer **114**, and software program types and

versions for each of a plurality of autonomous operation features installed as applications **230** or routines **240** in the program memory **208** of the on-board computer **114**.

During operation, the sensors **120** may generate sensor data regarding the vehicle **108** and its environment. In some embodiments, one or more of the sensors **120** may preprocess the measurements and communicate the resulting processed data to the on-board computer **114**. The controller **204** may receive sensor data from the sensors **120** at block **406**. The sensor data may include information regarding the vehicle's position, speed, acceleration, direction, and responsiveness to controls. The sensor data may further include information regarding the location and movement of obstacles or obstructions (e.g., other vehicles, buildings, barriers, pedestrians, animals, trees, or gates), weather conditions (e.g., precipitation, wind, visibility, or temperature), road conditions (e.g., lane markings, potholes, road material, traction, or slope), signs or signals (e.g., traffic signals, construction signs, building signs or numbers, or control gates), or other information relating to the vehicle's environment. In some embodiments, sensors **120** may indicate the number of passengers within the vehicle **108**, including an indication of whether the vehicle is entirely empty.

In addition to receiving sensor data from the sensors **120**, in some embodiments the controller **204** may receive autonomous communication data from the communication component **122** or the communication module **220** at block **408**. The communication data may include information from other autonomous vehicles (e.g., sudden changes to vehicle speed or direction, intended vehicle paths, hard braking, vehicle failures, collisions, or maneuvering or stopping capabilities), infrastructure (road or lane boundaries, bridges, traffic signals, control gates, or emergency stopping areas), or other external sources (e.g., map databases, weather databases, or traffic and accident databases). The communication data may be combined with the sensor data received at block **406** to obtain a more robust understanding of the vehicle environment. For example, the server **140** or the controller **204** may combine sensor data indicating frequent changes in speed relative to tachometric data with map data relating to a road upon which the vehicle **108** is traveling to determine that the vehicle **108** is in an area of hilly terrain. As another example, weather data indicating recent snowfall in the vicinity of the vehicle **108** may be combined with sensor data indicating frequent slipping or low traction to determine that the vehicle **108** is traveling on a snow-covered or icy road.

At block **410**, the controller **204** may process the sensor data, the communication data, and the settings or configuration information to determine whether an incident has occurred. As used herein, an "incident" is an occurrence during operation of an autonomous vehicle outside of normal safe operating conditions, such that one or more of the following occurs: (i) there is an interruption of vehicle operation, (ii) there is damage to the vehicle or other property, (iii) there is injury to a person, and/or (iv) the conditions require action to be taken by a vehicle operator, autonomous operation feature, pedestrian, or other party to avoid damage or injury. Incidents may include collisions, hard braking, hard acceleration, evasive maneuvering, loss of traction, detection of objects within a threshold distance from the vehicle **108**, alerts presented to the vehicle operator, component failure, inconsistent readings from sensors **120**, or attempted unauthorized access to the on-board computer by external sources. Incidents may also include accidents, vehicle breakdowns, flat tires, empty fuel tanks, or medical emergencies. In some embodiments, the controller **204** may anticipate or project an expected incident based upon sensor or external data, allowing the controller **204** to send control signals to minimize the negative effects of the incident. For example, the controller **204** may cause the vehicle **108** to slow and move to the shoulder of a road immediately before running out of fuel. As another example, adjustable seats within the vehicle **108** may be adjusted to better position vehicle occupants in anticipation of a collision.

When an incident is determined to have occurred at block **412**, information regarding the incident and the vehicle status may be recorded at block **414**, either in the data storage **228** or the database **146**. The information recorded at block **414** may include sensor data, communication data, and settings or configuration information prior to, during, and immediately following the incident. The information may further include a determination of whether the vehicle **108** has continued operating (either autonomously or manually) or whether the vehicle **108** is capable of continuing to operate in compliance with applicable safety and legal requirements. If the controller **204** determines that the vehicle **108** has discontinued operation or is unable to continue operation at block **416**, the method **400** may terminate. If the vehicle **108** continues operation, then the method **400** may continue at block **418**.

FIG. **4**B illustrates an alternative portion of the method **400** following an incident. When an incident is determined to have occurred at block **412**, the controller **204** or the server **140** may record status and operating information at block **414**, as above. In some instances, the incident may interrupt communication between the vehicle **108** and the server **140** via network **130**, such that not all information typically recorded will be available for recordation and analysis by the server **140**. Based upon the data recorded in block **414**, the server **140** or the controller **204** may determine whether assistance may be needed at the location of the vehicle **108** at block **430**. For example, the controller may determine that a head-on collision has occurred based on sensor data (e.g., airbag deployment, automatic motor shut-off, LIDAR data indicating a collision, etc.) and may further determine based on information regarding the speed of the vehicle **108** and other information that medical, police, and/or towing services will be necessary. The determination that assistance is needed at block **430** may further include a determination of types of assistance needed (e.g., police, ambulance, fire, towing, vehicle maintenance, fuel delivery, etc.). The determination at block **430** may include analysis of the type of incident, the sensor data regarding the incident (e.g., images from outward facing or inward facing cameras installed within the vehicle, identification of whether any passengers were present within the vehicle, determination of whether any pedestrians or passengers in other vehicles were involved in the incident, etc.). The determination of whether assistance is needed at block **430** may further include information regarding the vehicle status determined at block **414**.

In some embodiments, the determination at block **430** may be supplemented by a verification attempt, such as a phone call or communication through the on-board computer **114**. Where the verification attempt indicates assistance is required or communication attempts fail, the server **140** or controller **204** would then determine that assistance is needed, as described above. For example, when assistance is determined to be needed at block **430** following an accident involving the vehicle **108**, the server **140** may direct an automatic telephone call to a mobile telephone number associated with the vehicle **108** or the vehicle operator. If no

response is received, or if the respondent indicates assistance is required, the server **140** may proceed to cause a request for assistance to be generated.

When assistance is determined to be needed at block **432**, the controller **204** or the server **140** may send a request for assistance at block **434**. The request may include information regarding the vehicle **108**, such as the vehicle's location, the type of assistance required, other vehicles involved in the incident, the pedestrians involved in the incident, vehicle operators or passengers involved in the incident, and/or other relevant information. The request for assistance may include telephonic, data, or other requests to one or more emergency or vehicular service providers (e.g., local police, fire departments, state highway patrols, emergency medical services, public or private ambulance services, hospitals, towing companies, roadside assistance services, vehicle rental services, local claims representative offices, etc.). After sending a request for assistance at block **434** or when assistance is determined not to be needed at block **432**, the controller **204** or the server **140** may next determine whether the vehicle is operational at block **416**, as described above. The method **400** may then end or continue as indicated in FIG. **4**A.

In some embodiments, the controller **204** may further determine information regarding the likely cause of a collision or other incident. Alternatively, or additionally, the server **140** may receive information regarding an incident from the on-board computer **114** and determine relevant additional information regarding the incident from the sensor data. For example, the sensor data may be used to determine the points of impact on the vehicle **108** and another vehicle involved in a collision, the relative velocities of each vehicle, the road conditions at the time of the incident, and the likely cause or the party likely at fault. This information may be used to determine risk levels associated with autonomous vehicle operation, as described below, even where the incident is not reported to the insurer.

At block **418**, the controller **204** may determine whether a change or adjustment to one or more of the settings or configuration of the autonomous operation features has occurred. Changes to the settings may include enabling or disabling an autonomous operation feature or adjusting the feature's parameters (e.g., resetting the speed on an adaptive cruise control feature). If the settings or configuration are determined to have changed, the new settings or configuration may be recorded at block **422**, either in the data storage **228** or the database **146**.

At block **424**, the controller **204** may record the operating data relating to the vehicle **108** in the data storage **228** or communicate the operating data to the server **140** via the network **130** for recordation in the database **146**. The operating data may include the settings or configuration information, the sensor data, and the communication data discussed above, as well as data regarding control decisions generated by one or more autonomous operation features, as discussed below. In some embodiments, operating data related to normal autonomous operation of the vehicle **108** may be recorded. In other embodiments, only operating data related to incidents of interest may be recorded, and operating data related to normal operation may not be recorded. In still other embodiments, operating data may be stored in the data storage **228** until a sufficient connection to the network **130** is established, but some or all types of incident information may be transmitted to the server **140** using any available connection via the network **130**.

At block **426**, the controller **204** may determine whether the vehicle **108** is continuing to operate. In some embodiments, the method **400** may terminate when all autonomous operation features are disabled, in which case the controller **204** may determine whether any autonomous operation features remain enabled at block **426**. When the vehicle **108** is determined to be operating (or operating with at least one autonomous operation feature enabled) at block **426**, the method **400** may continue through blocks **406-426** until vehicle operation has ended. When the vehicle **108** is determined to have ceased operating (or is operating without autonomous operation features enabled) at block **426**, the controller **204** may record the completion of operation at block **428**, either in the data storage **228** or the database **146**. In some embodiments, a second timestamp corresponding to the completion of vehicle operation may likewise be recorded, as above.

Exemplary Evaluation Methods

FIG. **5** illustrates a flow diagram of an exemplary autonomous operation feature evaluation method **500** for determining the effectiveness of autonomous operation features, which may be implemented by the autonomous vehicle insurance system **100**. The method **500** begins by monitoring and recording the responses of an autonomous operation feature in a test environment at block **502**. The test results are then used to determine a plurality of risk levels for the autonomous operation feature corresponding to the effectiveness of the feature in situations involving various conditions, configurations, and settings at block **504**. Once a baseline risk profile of the plurality of risk levels has been established at block **504**, the method **500** may refine or adjust the risk levels based upon operating data and actual losses for insured autonomous vehicles operation outside the test environment in blocks **506-510**. Although FIG. **5** shows the method for only one autonomous operation feature, it should be understood that the method **500** may be performed to evaluate each of any number of autonomous operation features or combinations of autonomous operation features. In some embodiments, the method **500** may be implemented for a plurality of autonomous operation features concurrently on multiple servers **140** or at different times on one or more servers **140**.

At block **502**, the effectiveness of an autonomous operation feature is tested in a controlled testing environment by presenting test conditions and recording the responses of the feature. The testing environment may include a physical environment in which the autonomous operation feature is tested in one or more vehicles **108**. Additionally, or alternatively, the testing environment may include a virtual environment implemented on the server **140** or another computer system in which the responses of the autonomous operation feature are simulated. Physical or virtual testing may be performed for a plurality of vehicles **108** and sensors **120** or sensor configurations, as well as for multiple settings of the autonomous operation feature. In some embodiments, the compatibility or incompatibility of the autonomous operation feature with vehicles **108**, sensors **120**, communication units **122**, on-board computers **114**, control software, or other autonomous operation features may be tested by observing and recording the results of a plurality of combinations of these with the autonomous operation feature. For example, an autonomous operation feature may perform well in congested city traffic conditions, but that will be of little use if it is installed in an automobile with control software that operates only above 30 miles per hour. Additionally, some embodiments may further test the response of autonomous operation features or control software to attempts at unauthorized access (e.g., computer

hacking attempts), which results may be used to determine the stability or reliability of the autonomous operation feature or control software.

The test results may be recorded by the server **140**. The test results may include responses of the autonomous operation feature to the test conditions, along with configuration and setting data, which may be received by the on-board computer **114** and communicated to the server **140**. During testing, the on-board computer **114** may be a special-purpose computer or a general-purpose computer configured for generating or receiving information relating to the responses of the autonomous operation feature to test scenarios. In some embodiments, additional sensors may be installed within the vehicle **108** or in the vehicle environment to provide additional information regarding the response of the autonomous operation feature to the test conditions, which additional sensors may not provide sensor data to the autonomous operation feature.

In some embodiments, new versions of previously tested autonomous operation features may not be separately tested, in which case the block **502** may not be present in the method **500**. In such embodiments, the server **140** may determine the risk levels associated with the new version by reference to the risk profile of the previous version of the autonomous operation feature in block **504**, which may be adjusted based upon actual losses and operating data in blocks **506-510**. In other embodiments, each version of the autonomous operation feature may be separately tested, either physically or virtually. Alternatively, or additionally, a limited test of the new version of the autonomous operation feature may be performed and compared to the test results of the previous version, such that additional testing may not be performed when the limited test results of the new version are within a predetermined range based upon the test results of the previous version.

FIG. **6** illustrates a flow diagram of an exemplary autonomous operation feature testing method **600** for presenting test conditions to an autonomous operation feature and observing and recording responses to the test conditions in accordance with the method **500**. Although the method **600** is illustrated for one autonomous operation feature, it should be understood that the exemplary method **600** may be performed to test any number of features or combinations of features. At block **602**, the server **140** may determine the scope of the testing based upon the autonomous operation feature and the availability of test results for related or similar autonomous operation features (e.g., previous versions of the feature). The scope of the testing may include parameters such as configurations, settings, vehicles **108**, sensors **120**, communication units **122**, on-board computers **114**, control software, other autonomous operation features, or combinations of these parameters to be tested.

At block **604**, the autonomous operation feature is enabled within a test system with a set of parameters determined in block **602**. The test system may be a vehicle **108** or a computer simulation, as discussed above. The autonomous operation feature or the test system may be configured to provide the desired parameter inputs to the autonomous operation feature. For example, the controller **204** may disable a number of sensors **120** or may provide only a subset of available sensor data to the autonomous operation feature for the purpose of testing the feature's response to certain parameters.

At block **606**, test inputs are presented to the autonomous operation feature, and responses of the autonomous operation feature are observed at block **608**. The test inputs may include simulated data presented by the on-board computer **114** or sensor data from the sensors **120** within the vehicle **108**. In some embodiments, the vehicle **108** may be controlled within a physical test environment by the on-board computer **114** to present desired test inputs through the sensors **120**. For example, the on-board computer **114** may control the vehicle **108** to maneuver near obstructions or obstacles, accelerate, or change directions to trigger responses from the autonomous operation feature. The test inputs may also include variations in the environmental conditions of the vehicle **108**, such as by simulating weather conditions that may affect the performance of the autonomous operation feature (e.g., snow or ice cover on a roadway, rain, or gusting crosswinds, etc.).

In some embodiments, additional vehicles may be used to test the responses of the autonomous operation feature to moving obstacles. These additional vehicles may likewise be controlled by on-board computers or remotely by the server **140** through the network **130**. In some embodiments, the additional vehicles may transmit autonomous communication information to the vehicle **108**, which may be received by the communication component **122** or the communication unit **220** and presented to the autonomous operation feature by the on-board computer **114**. Thus, the response of the autonomous operation feature may be tested with and without autonomous communications from external sources. The responses of the autonomous operation feature may be observed as output signals from the autonomous operation feature to the on-board computer **114** or the vehicle controls. Additionally, or alternatively, the responses may be observed by sensor data from the sensors **120** and additional sensors within the vehicle **108** or placed within the vehicle environment.

At block **610**, the observed responses of the autonomous operation feature are recorded for use in determining effectiveness of the feature. The responses may be recorded in the data storage **228** of the on-board computer **114** or in the database **146** of the server **140**. If the responses are stored on the on-board computer **114** during testing, the results may be communicated to the server **140** via the network either during or after completion of testing.

At block **612**, the on-board computer **114** or the server **140** may determine whether the additional sets of parameters remain for which the autonomous operation feature is to be tested, as determined in block **602**. When additional parameter sets are determined to remain at block **612**, they are separately tested according to blocks **604-610**. When no additional parameter sets are determined to exist at block **612**, the method **600** terminates.

Although the method **600** is discussed above as testing the autonomous (and/or semi-autonomous) operation features in a test vehicle operating within a test environment, it should be understood that the exemplary method **600** may be similarly performed in an uncontrolled environment (i.e., on public roadways) or in a virtual environment. Testing of autonomous features within a virtual environment may include the presentation of electrical signals mimicking signals generated by one or more sensors in a plurality of operating scenarios at block **606**. For example, a control unit or on-board computer **114** removed from a vehicle may be connected to one or more sensor input simulators (e.g., a computer or computer-controlled signal generator) that present input signals to the control unit or on-board computer that correspond to signals that would be received from the sensors **120** in the vehicle **108** under certain conditions. In such case, the same or another computer may be connected to the control unit or on-board computer **114** to receive and record the control outputs determined by the one or more

autonomous operation features in response to the simulated sensor input at blocks **608** and **610**.

Additionally, or alternatively, the virtual test environment may include a simulation of an autonomous (and/or semi-autonomous) operation feature running on a general-purpose or special-purpose computer system. In such an embodiment, the autonomous operation feature may include one or more software routines, processes, applications, or modules that implement the autonomous operation feature to generate control signals for a vehicle when executed on a general-purpose or special-purpose processor. For example, an adaptive cruise control feature may include a software routine to monitor the speed of the vehicle using a combination of speedometer and other sensor data, as well as a software routine to determine the distance of the vehicle from obstacles or other vehicles in the vehicle's path using LIDAR and autonomous communication data. The adaptive cruise control feature may further include a control software routine to determine adjustments to the vehicle's speed to maintain a safe distance from other vehicles and obstacles then generate a control signal to maintain or adjust the throttle of the vehicle. In a virtual test environment, the software routines of the autonomous operation feature may be executed on a processor of a computer system not connected to any vehicle, in which case test input signals simulating signals from sensors within a vehicle may be presented to the software routines to test the routines' responses. Thus, a process of the computer system may execute instructions causing the processor to access a set of simulated sensor test input signals at block **606**, determine a response (such as one or more output test signals) of the autonomous operation feature based on the executable instructions representing one or more software routines of the autonomous operation feature at block **608**, and record the determined response at block **610**.

As the software routines of the autonomous operation feature are not directly connected to a vehicle to control the vehicle's operation during virtual testing, virtual testing may further include predicting a response of a vehicle to output test signals generated by the software routines of the tested autonomous operation feature. The simulated sensor inputs and/or test input signals may include sets of data corresponding to generated or recorded signals from a plurality of sensors. In some embodiments, the computer system may access a first set of sensor data and sequentially update the sensor data using the determined responses of the simulated autonomous operation feature. Thus, the test input signals may include input signals stored in a database and accessed by a testing program or application for presentation to the software routines of the autonomous operation feature being tested. Additionally, or alternatively, the computer system may generate sensor input signals based on a simulation of a physical test environment and update the virtual test environment based on the determined responses of the autonomous operation features. In some embodiments, a virtual testing program or application may further control the virtual testing process and may simulate the operation of a virtual vehicle within a virtual test environment. The virtual test environment may include a computer simulation of an environment in which an autonomous vehicle may be expected to operate (e.g., a congested highway, a city street with multiple intersections, etc.). The virtual testing program or application may, thus, generate a simulation of the operation of the virtual vehicle in the virtual test environment, including vehicle attributes such as position, speed, or momentum. The virtual testing program may further simulate the presence or operation of other vehicles, traffic control devices, obstacles, pedestrians, or other relevant features of a vehicle environment. Based upon these simulated features of the virtual vehicle environment, one or more simulated sensor readings or data may be determined, which may further be used to determine one or more test input signals to the software routines of the autonomous operation feature. The virtual testing program or application may then present the test input signals to the software routines and cause test output signals to be generated in response to the test input signals. From these test output signals, the virtual testing program may then predict the response of the virtual vehicle to the test output signals, including the responses of the virtual vehicle in relation to other virtual vehicles or other features in the simulated virtual test environment.

In any of the foregoing virtual test environments, the input data may include sensor data recorded during operation of an autonomous (and/or semi-autonomous) vehicle **108**, which may include operation by a vehicle operator or by other autonomous (and/or semi-autonomous) operation features. For example, a vehicle operator may choose to operate the vehicle **108** manually under some conditions (e.g., snow, fog, or construction), or the autonomous operation features may not support autonomous operation under such conditions. The sensors **120** of the vehicle **108** may, however, continue to collect and record data regarding the surrounding environment. The sensor data may then be used to simulate autonomous operation feature responses (i.e., the control signals the autonomous operation feature would have generated had it been in control of the vehicle). The data and responses may be stored or transmitted via the network **130**, and the responses of the autonomous operation features may be determined at the time of operation or at a later time.

As discussed with reference to FIG. **5** and elsewhere herein, the effectiveness of one or more autonomous operation features may be further used to determine one or more risk levels or risk profiles associated with the autonomous operation features. Specifically, the test output responses generated by the software routines of the autonomous operation features or the predicted responses of the virtual vehicle to the test output responses may be compared with other similar virtual test data related to other autonomous operation features. Where available, actual observed operating data regarding the one or more other autonomous operation features disposed within a plurality of other vehicles operating outside the virtual test environment may also be compared with the virtual test data using known statistical modeling techniques. Additionally, actual loss data for vehicles operating outside the virtual test environment and having the other autonomous operating features may further be compared with the virtual test data to better assess the risk levels and risk profiles associated with the tested autonomous operating features.

It will be apparent that performance of the exemplary method **600** in a virtual test environment offers advantages in terms of cost and time. Once set up, hundreds or thousands of test scenarios may be automatically run to evaluate autonomous (and/or semi-autonomous) operation feature performance under a variety of conditions without input from a user or vehicle operator. For example, a new autonomous operation feature or a software update including a new version of an autonomous operation feature may be tested in a virtual test environment prior to installation within autonomous vehicles, allowing immediate adjustment of risk levels or risk profiles for vehicles using the new autonomous operation feature or version. In this way, adjustments to risks

associated with autonomous operation features may be made without reference to actual loss data relating to the specific autonomous operation features. Such advantages must be weighed against the limitations of virtual testing, however, because the test results are limited by the quality of the virtual test environment. It will be readily apparent that responses from physical and virtual test environments may be combined in order to determine the performance and risk levels associated with autonomous operation features.

Referring again to FIG. **5**, the server **140** may determine a baseline risk profile for the autonomous operation feature from the recorded test results at block **504**, including a plurality of risk levels corresponding to a plurality of sets of parameters such as configurations, settings, vehicles **108**, sensors **120**, communication units **122**, on-board computers **114**, control software, other autonomous operation features, or combinations of these. The server **140** may determine the risk levels associated with the autonomous operation feature by implementing the feature evaluation application **142** to determine the effectiveness of the feature. In some embodiments, the server **140** may further implement the compatibility evaluation application **143** to determine the effectiveness of combinations of features based upon test results and other information. Additionally, or alternatively, in some embodiments, the baseline risk profile may not depend upon the type, make, model, year, or other aspect of the vehicle **108**. In such embodiments, the baseline risk profile and adjusted risk profiles may correspond to the effectiveness or risk levels associated with the autonomous operation features across a range of vehicles, disregarding any variations in effectiveness or risk levels associated with operation of the features in different vehicles.

FIG. **7** illustrates a flow diagram of an exemplary autonomous feature evaluation method **700** for determining the effectiveness of an autonomous operation feature under a set of environmental conditions, configuration conditions, and settings. Although the method **700** shows determination of a risk level associated with an autonomous operation feature within one set of parameters, it should be understood that the method **700** may be implemented for any number of sets of parameters for any number of autonomous features or combinations thereof.

At block **702**, the server **140** receives the test result data observed and recorded in block **502** for the autonomous operation feature in conjunction with a set of parameters. In some embodiments, the rest result data may be received from the on-board computer **114** or from the database **146**. In addition, in some embodiments, the server **140** may receive reference data for other autonomous operation features in use on insured autonomous vehicles at block **704**, such as test result data and corresponding actual loss or operating data for the other autonomous operation features. The reference data received at block **704** may be limited to data for other autonomous operation features having sufficient similarity to the autonomous operation feature being evaluated, such as those performing a similar function, those with similar test result data, or those meeting a minimum threshold level of actual loss or operating data.

Using the test result data received at block **702** and the reference data received at block **704**, the server **140** determines the expected actual loss or operating data for the autonomous operation feature at block **706**. The server **140** may determine the expected actual loss or operating data using known techniques, such as regression analysis or machine learning tools (e.g., neural network algorithms or support vector machines). The expected actual loss or operating data may be determined using any useful metrics, such as expected loss value, expected probabilities of a plurality of collisions or other incidents, expected collisions per unit time or distance traveled by the vehicle, etc.

At block **708**, the server **140** may further determine a risk level associated with the autonomous operation feature in conjunction with the set of parameters received in block **702**. The risk level may be a metric indicating the risk of collision, malfunction, or other incident leading to a loss or claim against a vehicle insurance policy covering a vehicle in which the autonomous operation feature is functioning. The risk level may be defined in various alternative ways, including as a probability of loss per unit time or distance traveled, a percentage of collisions avoided, or a score on a fixed scale. In a preferred embodiment, the risk level is defined as an effectiveness rating score such that a higher score corresponds to a lower risk of loss associated with the autonomous operation feature.

Referring again to FIG. **5**, the method **700** may be implemented for each relevant combination of an autonomous operation feature in conjunction with a set of parameters relating to environmental conditions, configuration conditions, and settings. It may be beneficial in some embodiments to align the expected losses or operating data metrics with loss categories for vehicle insurance policies. Once the baseline risk profile is determined for the autonomous operation feature, the plurality of risk levels in the risk profile may be updated or adjusted in blocks **506-510** using actual loss and operating data from autonomous vehicles operating in the ordinary course, viz. not in a test environment.

At block **506**, the server **140** may receive operating data from one or more vehicles **108** via the network **130** regarding operation of the autonomous operation feature. The operating data may include the operating data discussed above with respect to monitoring method **400**, including information regarding the vehicle **108**, the vehicle's environment, the sensors **120**, communications for external sources, the type and version of the autonomous operation feature, the operation of the feature, the configuration and settings relating to the operation of the feature, the operation of other autonomous operation features, control actions performed by the vehicle operator, or the location and time of operation. The operating data may be received by the server **140** from the on-board computer **114** or the mobile device **110** implementing the monitoring method **400** or from other sources, and the server **140** may receive the operating data either periodically or continually.

At block **508**, the server **140** may receive data regarding actual losses on autonomous vehicles that included the autonomous operation feature. This information may include claims filed pursuant to insurance policies, claims paid pursuant to insurance policies, accident reports filed with government agencies, or data from the sensors **120** regarding incidents (e.g., collisions, alerts presented, etc.). This actual loss information may further include details such as date, time, location, traffic conditions, weather conditions, road conditions, vehicle speed, vehicle heading, vehicle operating status, autonomous operation feature configuration and settings, autonomous communications transmitted or received, points of contact in a collision, velocity and movements of other vehicles, or additional information relevant to determining the circumstances involved in the actual loss.

At block **510**, the server **140** may process the information received at blocks **506** and **508** to determine adjustments to the risk levels determined at block **504** based upon actual loss and operating data for the autonomous operation fea-

ture. Adjustments may be necessary because of factors such as sensor failure, interference disrupting autonomous communication, better or worse than expected performance in heavy traffic conditions, etc. The adjustments to the risk levels may be made by methods similar to those used to determine the baseline risk profile for the autonomous operation feature or by other known methods (e.g., Bayesian updating algorithms). The updating procedure of blocks **506-510** may be repeatedly implemented periodically or continually as new data become available to refine and update the risk levels or risk profile associated with the autonomous operation feature. In subsequent iterations, the most recently updated risk profile or risk levels may be adjusted, rather than the initial baseline risk profile or risk levels determined in block **504**.

Exemplary Autonomous Vehicle Insurance Risk and Price Determination Methods

The risk profiles or risk levels associated with one or more autonomous operation features determined above may be further used to determine risk categories or premiums for vehicle insurance policies covering autonomous vehicles. FIGS. **8-10** illustrate flow diagrams of exemplary embodiments of methods for determining risk associated with an autonomous vehicle or premiums for vehicle insurance policies covering an autonomous vehicle. In some embodiments or under some conditions, the autonomous vehicle may be a fully autonomous vehicle operating without a vehicle operator's input or presence. In other embodiments or under other conditions, the vehicle operator may control the vehicle with or without the assistance of the vehicle's autonomous operation features. For example, the vehicle may be fully autonomous only above a minimum speed threshold or may require the vehicle operator to control the vehicle during periods of heavy precipitation. Alternatively, the autonomous vehicle may perform all relevant control functions using the autonomous operation features under all ordinary operating conditions. In still further embodiments, the vehicle **108** may operate in either a fully or a partially autonomous state, while receiving or transmitting autonomous communications.

Where the vehicle **108** operates only under fully autonomous control by the autonomous operation features under ordinary operating conditions or where control by a vehicle operator may be disregarded for insurance risk and price determination, the method **800** may be implemented to determine the risk level or premium associated with an insurance policy covering the autonomous vehicle. Where the vehicle **108** may be operated manually under some conditions, the method **900** may be implemented to determine the risk level or premium associated with an insurance policy covering the autonomous vehicle, including a determination of the risks associated with the vehicle operator performing manual vehicle operation. Where the vehicle **108** may be operated with the assistance of autonomous communications features, the method **1000** may be implemented to determine the risk level or premium associated with an insurance policy covering the autonomous vehicle, including a determination of the expected use of autonomous communication features by external sources in the relevant environment of the vehicle **108** during operation of the vehicle **108**.

FIG. **8** illustrates a flow diagram depicting an exemplary embodiment of a fully autonomous vehicle insurance pricing method **800**, which may be implemented by the autonomous vehicle insurance system **100**. The method **800** may be implemented by the server **140** to determine a risk level or price for a vehicle insurance policy covering a fully autonomous vehicle based upon the risk profiles of the autonomous operation features in the vehicle. It is important to note that the risk category or price is determined without reference to factors relating to risks associated with a vehicle operator (e.g., age, experience, prior history of vehicle operation). Instead, the risk and price may be determined based upon the vehicle **108**, the location and use of the vehicle **108**, and the autonomous operation features of the vehicle **108**.

At block **802**, the server **140** receives a request to determine a risk category or premium associated with a vehicle insurance policy for a fully autonomous vehicle. The request may be caused by a vehicle operator or other customer or potential customer of an insurer, or by an insurance broker or agent. The request may also be generated automatically (e.g., periodically for repricing or renewal of an existing vehicle insurance policy). In some instances, the server **140** may generate the request upon the occurrence of specified conditions.

At block **804**, the server **140** receives information regarding the vehicle **108**, the autonomous operation features installed within the vehicle **108**, and anticipated or past use of the vehicle **108**. The information may include vehicle information (e.g., type, make, model, year of production, safety features, modifications, installed sensors, on-board computer information, etc.), autonomous operation features (e.g., type, version, connected sensors, compatibility information, etc.), and use information (e.g., primary storage location, primary use, primary operating time, past use as monitored by an on-board computer or mobile device, past use of one or more vehicle operators of other vehicles, etc.). The information may be provided by a person having an interest in the vehicle, a customer, or a vehicle operator, and/or the information may be provided in response to a request for the information by the server **140**. Alternatively, or additionally, the server **140** may request or receive the information from one or more databases communicatively connected to the server **140** through the network **130**, which may include databases maintained by third parties (e.g., vehicle manufacturers or autonomous operation feature manufacturers). In some embodiments, information regarding the vehicle **108** may be excluded, in which case the risk or premium determinations below may likewise exclude the information regarding the vehicle **108**.

At block **806**, the server **140** may determine the risk profile or risk levels associated with the vehicle **108** based upon the vehicle information and the autonomous operation feature information received at block **804**. The risk levels associated with the vehicle **108** may be determined as discussed above with respect to the method **500** and/or may be determined by looking up in a database the risk level information previously determined. In some embodiments, the information regarding the vehicle may be given little or no weight in determining the risk levels. In other embodiments, the risk levels may be determined based upon a combination of the vehicle information and the autonomous operation information. As with the risk levels associated with the autonomous operation features discussed above, the risk levels associated with the vehicle may correspond to the expected losses or incidents for the vehicle based upon its autonomous operation features, configuration, settings, and/or environmental conditions of operation. For example, a vehicle may have a risk level of 98% effectiveness when on highways during fair weather days and a risk level of 87% effectiveness when operating on city streets at night in moderate rain. A plurality of risk levels associated with the

vehicle may be combined with estimates of anticipated vehicle use conditions to determine the total risk associated with the vehicle.

At block **808**, the server **140** may determine the expected use of the vehicle **108** in the relevant conditions or with the relevant settings to facilitate determining a total risk for the vehicle **108**. The server **140** may determine expected vehicle use based upon the use information received at block **804**, which may include a history of prior use recorded by the vehicle **108** and/or another vehicle. For example, recorded vehicle use information may indicate that 80% of vehicle use occurs during weekday rush hours in or near a large city, that 20% occurs on nights and weekends. From this information, the server **140** may determine that 80% (75%, 90%, etc.) of the expected use of the vehicle **108** is in heavy traffic and that 20% (25%, 10%, etc.) is in light traffic. The server **140** may further determine that vehicle use is expected to be 60% on limited access highways and 40% on surface streets. Based upon the vehicle's typical storage location, the server **140** may access weather data for the location to determine expected weather conditions during the relevant times. For example, the server **140** may determine that 20% of the vehicle's operation on surface streets in heavy traffic will occur in rain or snow. In a similar manner, the server **140** may determine a plurality of sets of expected vehicle use parameters corresponding to the conditions of use of the vehicle **108**. These conditions may further correspond to situations in which different autonomous operation features may be engaged and/or may be controlling the vehicle. Additionally, or alternatively, the vehicle use parameters may correspond to different risk levels associated with the autonomous operation features. In some embodiments, the expected vehicle use parameters may be matched to the most relevant vehicle risk level parameters, viz. the parameters corresponding to vehicle risk levels that have the greatest predictive effect and/or explanatory power.

At block **810**, the server **140** may use the risk levels determined at block **806** and the expected vehicle use levels determined at block **808** to determine a total expected risk level. To this end, it may be advantageous to attempt to match the vehicle use parameters as closely as possible to the vehicle risk level parameters. For example, the server **140** may determine the risk level associated with each of a plurality of sets of expected vehicle use parameters. In some embodiments, sets of vehicle use parameters corresponding to zero or negligible (e.g., below a predetermined threshold probability) expected use levels may be excluded from the determination for computational efficiency. The server **140** may then weight the risk levels by the corresponding expected vehicle use levels, and aggregate the weighted risk levels to obtain a total risk level for the vehicle **108**. In some embodiments, the aggregated weighted risk levels may be adjusted or normalized to obtain the total risk level for the vehicle **108**. In some embodiments, the total risk level may correspond to a regulatory risk category or class of a relevant insurance regulator.

At block **812**, the server **140** may determine one or more premiums for vehicle insurance policies covering the vehicle **108** based upon the total risk level determined at block **810**. These policy premiums may also be determine based upon additional factors, such as coverage type and/or amount, expected cost to repair or replace the vehicle **108**, expected cost per claim for liability in the locations where the vehicle **108** is typically used, discounts for other insurance coverage with the same insurer, and/or other factors unrelated to the vehicle operator. In some embodiments, the server **140** may further communicate the one or more policy premiums to a customer, broker, agent, or other requesting person or organization via the network **130**. The server **140** may further store the one or more premiums in the database **146**.

FIG. **9** illustrates a flow diagram depicting an exemplary embodiment of a partially autonomous vehicle insurance pricing method **900**, which may be implemented by the autonomous vehicle insurance system **100** in a manner similar to that of the method **800**. The method **900** may be implemented by the server **140** to determine a risk category and/or price for a vehicle insurance policy covering an autonomous vehicle based upon the risk profiles of the autonomous operation features in the vehicle and/or the expected use of the autonomous operation features. In addition to information regarding the vehicle **108** and the autonomous operation features, the method **900** includes information regarding the vehicle operator, including information regarding the expected use of the autonomous operation features and/or the expected settings of the features under various conditions. Such additional information is relevant where the vehicle operator may control the vehicle **108** under some conditions and/or may determine settings affecting the effectiveness of the autonomous operation features.

At block **902**, the server **140** may receive a request to determine a risk category and/or premium associated with a vehicle insurance policy for an autonomous vehicle in a manner similar to block **802** described above. At block **904**, the server **140** likewise receives information regarding the vehicle **108**, the autonomous operation features installed within the vehicle **108**, and/or anticipated or past use of the vehicle **108**. The information regarding anticipated or past use of the vehicle **108** may include information regarding past use of one or more autonomous operation features, and/or settings associated with use of the features. For example, this may include times, road conditions, and/or weather conditions when autonomous operation features have been used, as well as similar information for past vehicle operation when the features have been disabled. In some embodiments, information regarding the vehicle **108** may be excluded, in which case the risk or premium determinations below may likewise exclude the information regarding the vehicle **108**. At block **906**, the server **140** may receive information related to the vehicle operator, including standard information of a type typically used in actuarial analysis of vehicle operator risk (e.g., age, location, years of vehicle operation experience, and/or vehicle operating history of the vehicle operator).

At block **908**, the server **140** may determine the risk profile or risk levels associated with the vehicle **108** based upon the vehicle information and the autonomous operation feature information received at block **904**. The risk levels associated with the vehicle **108** may be determined as discussed above with respect to the method **500** and/or as further discussed with respect to method **800**.

At block **910**, the server **140** may determine the expected manual and/or autonomous use of the vehicle **108** in the relevant conditions and/or with the relevant settings to facilitate determining a total risk for the vehicle **108**. The server **140** may determine expected vehicle use based upon the use information received at block **904**, which may include a history of prior use recorded by the vehicle **108** and/or another vehicle for the vehicle operator. Expected manual and autonomous use of the vehicle **108** may be determined in a manner similar to that discussed above with respect to method **800**, but including an additional determination of the likelihood of autonomous and/or manual operation by the vehicle operation under the various condi-

tions. For example, the server **140** may determine based upon past operating data that the vehicle operator manually controls the vehicle **108** when on a limited-access highway only 20% of the time in all relevant environments, but the same vehicle operator controls the vehicle 60% of the time on surface streets outside of weekday rush hours and 35% of the time on surface streets during weekday rush hours. These determinations may be used to further determine the total risk associated with both manual and/or autonomous vehicle operation.

At block **912**, the server **140** may use the risk levels determined at block **908** and the expected vehicle use levels determined at block **910** to determine a total expected risk level, including both manual and autonomous operation of the vehicle **108**. The autonomous operation risk levels may be determined as above with respect to block **810**. The manual operation risk levels may be determined in a similar manner, but the manual operation risk may include risk factors related to the vehicle operator. In some embodiments, the manual operation risk may also be determined based upon vehicle use parameters and/or related autonomous operation feature risk levels for features that assist the vehicle operator in safely controlling the vehicle. Such features may include alerts, warnings, automatic braking for collision avoidance, and/or similar features that may provide information to the vehicle operator or take control of the vehicle from the vehicle operator under some conditions. These autonomous operation features may likewise be associated with different risk levels that depend upon settings selected by the vehicle operator. Once the risk levels associated with autonomous operation and manual operation under various parameter sets that have been weighted by the expected use levels, the total risk level for the vehicle and operator may be determined by aggregating the weighted risk levels. As above, the total risk level may be adjusted or normalized, and/or it may be used to determine a risk category or risk class in accordance with regulatory requirements.

At block **914**, the server **140** may determine one or more premiums for vehicle insurance policies covering the vehicle **108** based upon the total risk level determined at block **812**. As in method **800**, additional factors may be included in the determination of the policy premiums, and/or the premiums may be adjusted based upon additional factors. The server **140** may further record the premiums or may transmit one or more of the policy premiums to relevant parties.

FIG. **10** illustrates a flow diagram depicting an exemplary embodiment of an autonomous vehicle insurance pricing method **1000** for determining risk and/or premiums for vehicle insurance policies covering autonomous vehicles with autonomous communication features, which may be implemented by the autonomous vehicle insurance system **100**. The method **1000** may determine risk levels as without autonomous communication discussed above with reference to methods **800** and/or **900**, then adjust the risk levels based upon the availability and effectiveness of communications between the vehicle **108** and external sources. Similar to environmental conditions, the availability of external sources such as other autonomous vehicles for communication with the vehicle **108** affects the risk levels associated with the vehicle **108**. For example, use of an autonomous communication feature may significantly reduce risk associated with autonomous operation of the vehicle **108** only where other autonomous vehicles also use autonomous communication features to send and/or receive information.

At block **1002**, the server **140** may receive a request to determine a risk category or premium associated with a vehicle insurance policy for an autonomous vehicle with one or more autonomous communication features in a manner similar to blocks **802** and/or **902** described above. At block **1004**, the server **140** likewise receives information regarding the vehicle **108**, the autonomous operation features installed within the vehicle **108** (including autonomous communication features), the vehicle operator, and/or anticipated or past use of the vehicle **108**. The information regarding anticipated or past use of the vehicle **108** may include information regarding locations and times of past use, as well as past use of one or more autonomous communication features. For example, this may include locations, times, and/or details of communication exchanged by an autonomous communication feature, as well as information regarding past vehicle operation when no autonomous communication occurred. This information may be used to determine the past availability of external sources for autonomous communication with the vehicle **108**, facilitating determination of expected future availability of autonomous communication as described below. In some embodiments, information regarding the vehicle **108** may be excluded, in which case the risk or premium determinations below may likewise exclude the information regarding the vehicle **108**.

At block **1006**, the server **140** may determine the risk profile or risk levels associated with the vehicle **108** based upon the vehicle information, the autonomous operation feature information, and/or the vehicle operator information received at block **1004**. The risk levels associated with the vehicle **108** may be determined as discussed above with respect to the method **500** and as further discussed with respect to methods **800** and **900**. At block **1008**, the server **140** may determine the risk profile and/or risk levels associated with the vehicle **108** and/or the autonomous communication features. This may include a plurality of risk levels associated with a plurality of autonomous communication levels and/or other parameters relating to the vehicle **108**, the vehicle operator, the autonomous operation features, the configuration and/or setting of the autonomous operation features, and/or the vehicle's environment. The autonomous communication levels may include information regarding the proportion of vehicles in the vehicle's environment that are in autonomous communication with the vehicle **108**, levels of communication with infrastructure, types of communication (e.g., hard braking alerts, full velocity information, etc.), and/or other information relating to the frequency and/or quality of autonomous communications between the autonomous communication feature and the external sources.

At block **1010**, the server **140** may then determine the expected use levels of the vehicle **108** in the relevant conditions, autonomous operation feature settings, and/or autonomous communication levels to facilitate determining a total risk for the vehicle **108**. The server **140** may determine expected vehicle use based upon the use information received at block **1004**, including expected levels of autonomous communication under a plurality of sets of parameters. For example, the server **140** may determine based upon past operating data that the 50% of the total operating time of the vehicle **108** is likely to occur in conditions where approximately a quarter of the vehicles utilize autonomous communication features, 40% of the total operating time is likely to occur in conditions where a negligible number of vehicles utilize autonomous communication features, and/or 10% is likely to occur in conditions where approximately half of vehicles utilize autonomous communication features. Of course, each of the categories in the preceding example may be further divided by other conditions, such as traffic levels,

weather, average vehicle speed, presence of pedestrians, location, autonomous operation feature settings, and/or other parameters. These determinations may be used to further determine the total risk associated with autonomous vehicle operation including autonomous communication.

At block **1012**, the server **140** may use the risk levels determined at block **1010** to determine a total expected risk level for the vehicle **108** including one or more autonomous communication features, in a similar manner to the determination described above in block **810**. The server **140** may weight each of the risk levels corresponding to sets of parameters by the expected use levels corresponding to the same set of parameters. The weighted risk levels may then be aggregated using known techniques to determine the total risk level. As above, the total risk level may be adjusted or normalized, or it may be used to determine a risk category or risk class in accordance with regulatory requirements.

At block **1014**, the server **140** may determine one or more premiums for vehicle insurance policies covering the vehicle **108** based upon the total risk level determined at block **1012**. As in methods **800** and/or **900**, additional factors may be included in the determination of the policy premiums, and/or the premiums may be adjusted based upon additional factors. The server **140** may further record the premiums and/or may transmit one or more of the policy premiums to relevant parties.

In any of the preceding embodiments, the determined risk level or premium associated with one or more insurance policies may be presented by the server **140** to a customer or potential customer as offers for one or more vehicle insurance policies. The customer may view the offered vehicle insurance policies on a display such as the display **202** of the mobile device **110**, select one or more options, and/or purchase one or more of the vehicle insurance policies. The display, selection, and/or purchase of the one or more policies may be facilitated by the server **140**, which may communicate via the network **130** with the mobile device **110** and/or another computer device accessed by the user.

Additionally, or alternatively, any of the preceding embodiments may determine or adjust vehicle insurance coverage types or levels (e.g., deductibles, coverage amounts, etc.) based upon use conditions and/or autonomous (and/or semi-autonomous) operation feature use, configuration, or settings. For example, deductibles or premiums for a level of vehicle insurance coverage for theft of a vehicle may be reduced for policies where a fully autonomous vehicle includes autonomous operation features capable of returning the vehicle if stolen. As another example, coverage levels of a vehicle insurance policy may vary based upon whether an autonomous vehicle contains any passengers or vehicle operators. Additionally, coverage types or levels may be adjusted based upon use levels of the autonomous operation features and/or information regarding a vehicle operator. For example, certain coverage types or levels may be unavailable to a vehicle operator (e.g., inexperienced drivers, drivers with extensive accident histories, etc.), except that such coverage may be available when certain autonomous operation features are enabled or activated. In some embodiments, vehicle operators who may be otherwise unable or legally prevented from operating a vehicle (e.g., due to blindness, physical disabilities, revocation of an operating license, etc.) may be insured for operation of an autonomous vehicle with certain autonomous operation features enabled.

Exemplary Methods of Providing Insurance Coverage

In one aspect, a computer-implemented method of adjusting or creating an insurance policy may be provided. The method may include: (1) capturing or gathering data, via a processor, to determine an autonomous or semi-autonomous technology or functionality associated with a specific vehicle; (2) comparing the received data, via the processor, to a stored baseline of vehicle data created from (a) actual accident data involving automobiles equipped with the autonomous or semi-autonomous technology or functionality, and/or (b) autonomous or semi-autonomous vehicle testing; (3) identifying (or assessing) accident or collision risk, via the processor, based upon an ability of the autonomous or semi-autonomous technology or functionality associated with the specific vehicle to make driving decisions and/or avoid or mitigate crashes; (4) adjusting or creating an insurance policy, via the processor, based upon the accident or collision risk identified that is based upon the ability of the autonomous or semi-autonomous technology or functionality associated with the specific vehicle; and/or (5) presenting on a display screen, or otherwise providing or communicating, all or a portion of (such as a monthly premium or discount) the insurance policy adjusted or created to a potential or existing customer, or an owner or operator of the specific vehicle equipped with the autonomous or semi-autonomous technology or functionality, for review, acceptance, and/or approval. The method may include additional, fewer, or alternative steps or actions, including those discussed elsewhere herein.

For instance, the method may include evaluating, via the processor, an effectiveness of the autonomous or semi-autonomous technology or functionality, and/or an associated artificial intelligence, in a test environment, and/or using real driving experience or information.

The identification (or assessment) of accident or collision risk performed by the processor may be dependent upon the extent of control and/or decision making that is assumed by the specific vehicle equipped with the autonomous or semi-autonomous technology or functionality, rather than the human driver. Additionally or alternatively, the identification (or assessment) of accident or collision risk may be dependent upon (a) the ability of the specific vehicle to use external information (such as vehicle-to-vehicle, vehicle-to-infrastructure, and/or infrastructure-to-vehicle wireless communication) to make driving decisions, and/or (b) the availability of such external information, such as may be determined by a geographical region (urban or rural) associated with the specific vehicle or vehicle owner.

Information regarding the autonomous or semi-autonomous technology or functionality associated with the specific vehicle, including factory-installed hardware and/or versions of computer instructions, may be wirelessly transmitted to a remote server associated with an insurance provider and/or other third party for analysis. The method may include remotely monitoring an amount or percentage of usage of the autonomous or semi-autonomous technology or functionality by the specific vehicle, and based upon such amount or percentage of usage, (a) providing feedback to the driver and/or insurance provider via wireless communication, and/or (b) adjusting insurance policies or premiums.

Data Acquisition

In one aspect, the present embodiments may relate to data acquisition. Data may be gathered via devices employing wireless communication technology, such as Bluetooth or other IEEE communication standards. In one embodiment, a Bluetooth enabled smartphone or mobile device, and/or an in-dash smart and/or communications device may collect data. The data associated with the vehicle, and/or vehicle or driver performance, that is gathered or collected at, or on, the vehicle may be wirelessly transmitted to a remote

processor or server, such as a remote processor or server associated with an insurance provider. The mobile device **110** may receive the data from the on-board computer **114** or the sensors **120**, and may transmit the received data to the server **140** via the network **130**, and the data may be stored in the database **146**. In some embodiments, the transmitted data may include real-time sensor data, a summary of the sensor data, processed sensor data, operating data, environmental data, communication data, or a log such data.

A. Vehicle Decision Making

Data may be generated by autonomous or semi-autonomous vehicles and/or vehicle mounted sensors (or smart sensors), and then collected by vehicle mounted equipment or processors, including Bluetooth devices, and/or an insurance provider remote processor or server. The data gathered may be used to analyze vehicle decision making. A processor may be configured to generate data on what an autonomous or semi-autonomous vehicle would have done in a given situation had the driver not taken over manual control/driving of the vehicle or alternative control actions not taken by the autonomous or semi-autonomous operation features. This type of control decision data (related to vehicle decision making) may be useful with respect to analyzing hypothetical situations.

In one embodiment, an application, or other computer or processor instructions, may interact with a vehicle to receive and/or retrieve data from autonomous or semi-autonomous processors and sensors. The data retrieved may be related to radar, cameras, sensor output, computer instructions or application output. Other data related to a smart vehicle controller, car navigation unit information (including route history information and typical routes taken), GPS unit information, odometer and/or speedometer information, and smart equipment data may also be gathered or collected. The application and/or other computer instructions may be associated with an insurance provider remote processor or server.

The control decision data may further include information regarding control decisions generated by one or more autonomous operation features within the vehicle. The operating data and control decision data gathered, collected, and/or acquired may facilitate remote evaluation and/or analysis of what the autonomous or semi-autonomous vehicle was "trying to do" (brake, slow, turn, accelerate, etc.) during operation, as well as what the vehicle actually did do. The data may reveal decisions, and the appropriateness thereof, made by the artificial intelligence or computer instructions associated with one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment. The data may include information related to what the vehicle would have done in a situation if the driver had not taken over (beginning manual vehicle control). Such data may include both the control actions taken by the vehicle and control actions the autonomous or semi-autonomous operation features would have caused the vehicle to take. Thus, in some embodiments, the control decisions data may include information regarding control decisions not implemented by the autonomous operation features to control the vehicle. This may occur when an autonomous operation feature generates a control decision or associated control signal, but the control decision or signal is prevented from controlling the vehicle because the autonomous feature or function is disabled, the control decision is overridden by the vehicle operator, the control signal would conflict with another control signal generated by another autonomous operation feature, a more preferred control decision is generated, or an error occurs in the on-board computer **114** or the control system of the vehicle.

For example, a vehicle operator may disable or constrain the operation of some or all autonomous operation features, such as where the vehicle is operated manually or semi-autonomously. The disabled or constrained autonomous operation features may, however, continue to receive sensor data and generate control decision data that is not implemented. Similarly, one or more autonomous operation features may generate more than one control decision in a relevant period of time as alternative control decisions. Some of these alternative control decisions may not be selected by the autonomous operation feature or an autonomous operation control system to control the vehicle. For example, such alternative control decisions may be generated based on different sets of sensor or communication data from different sensors **120** or include or excluding autonomous communication data. As another example, the alternative control decisions may be generated faster than they can be implemented by the control system of the vehicle, thus preventing all control decisions from being implemented.

In addition to control decision data, other information regarding the vehicle, the vehicle environment, or vehicle operation may be collected, generated, transmitted, received, requested, stored, or recorded in connection with the control decision data. As discussed elsewhere herein, additional operating data including sensor data from the sensors **120**, autonomous communication data from the communication component **122** or the communication module **220**, location data, environmental data, time data, settings data, configuration data, and/or other relevant data may be associated with the control decision data. In some embodiments, a database or log may store the control decision data and associated information. In further embodiments, the entries in such log or database may include a timestamp indicating the date, time, location, vehicle environment, vehicle condition, autonomous operation feature settings, and/or autonomous operation feature configuration information associated with each entry. Such data may facilitate evaluating the autonomous or semi-autonomous technology, functionality, system, and/or equipment in hypothetical situations and/or may be used to calculate risk, and in turn adjust insurance policies, premiums, discounts, etc.

B. Evaluating Risk

The data gathered may be used to evaluate risk associated with the autonomous or semi-autonomous operation feature or technology at issue. As discussed elsewhere herein, information regarding the operation of the vehicle may be monitored or associated with test data or actual loss data regarding losses associated with insurance policies for other vehicles having the autonomous technology or feature to determine risk levels and/or risk profiles. Specifically, the control decision data, sensor data, and other operating data discussed above may be used to determine risk levels, loss models, and/or risk profiles associated with one or more autonomous or semi-autonomous operation features. External data may further be used to determine risk, as discussed below. Such determined risk levels may further be used to determine insurance rates, premiums, discounts, or costs as discussed in greater detail below.

In one embodiment, the data gathered may be used to determine an average distance to another vehicle ahead of, and/or behind, the vehicle during normal use of the autonomous or semi-autonomous vehicle technology, functionality,

system, and/or equipment. A safe driving distance to other vehicles on the road may lower the risk of accident.

The data gathered may also relate to how quickly the technology, functionality, system, and/or equipment may properly stop or slow a vehicle in response to a light changing from green to yellow, and/or from yellow to red. Timely stopping at traffic lights may also positively impact risk of collision.

The data gathered may indicate issues not entirely related to the autonomous or semi-autonomous technology, functionality, system, and/or equipment. For instance, tires spinning and low vehicle speed may be monitored and identified to determine that vehicle movement was being affected by the weather (as compared to the technology, functionality, system, and/or equipment during normal operation). Vehicle tires may spin with little or no vehicle movement in snow, rain, mud, ice, etc.

The data gathered may indicate a current version of artificial intelligence or computer instructions that the autonomous or semi-autonomous system or equipment is utilizing. A collision risk factor may be assigned to each version of computer instructions. The insurance provider may then adjust or update insurance policies, premiums, rates, discounts, and/or other insurance-related items based upon the collision risk factor and/or the artificial intelligence or computer instruction versions presently employed by the vehicle (and/or upgrades there to).

C. Outside Data

The decision and operating data gathered may be merged with outside data, such as information related to weather, traffic, construction, and/or other factors, and/or collected from sources besides the vehicle. In some embodiments, such data from outside the vehicle may be combined with the control decision data and other operating data discussed above to determine risks associated with the operation of one or more autonomous or semi-autonomous operation features. External data regarding the vehicle environment may be requested or received via the network **130** and associated with the entries in the log or database based on the timestamp. For example, the location, date, and time of a timestamp may be used to determine weather and traffic conditions in which vehicle operation occurred. Additional external data may include road conditions, weather conditions, nearby traffic conditions, type of road, construction conditions, presence of pedestrians, presence of other obstacles, and/or availability of autonomous communications from external sources. For instance, weather may impact certain autonomous or semi-autonomous technology, functionality, system, and/or equipment performance, such as fog, visibility, wind, rain, snow, and/or ice. Certain autonomous or semi-autonomous functionality may have degraded performance: (1) on ice covered roads; (2) during snow or rain, and/or on snow or rain covered roads; (3) during poor visibility conditions, such as foggy weather; (4) in "stop and go" traffic, such as during rush hour traffic, or slow moving traffic through high construction areas or downtown areas; and/or (5) caused by other factors.

The system and method may consider the geographical area associated with the user, or the owner or operator of a vehicle. For instance, rain mitigation functionality or technology for vehicles may be pertinent to reducing the amount of accidents and/or the severity of such accidents in areas of high rain fall, such as the Pacific Northwest or Florida. On the other hand, such functionality may have less of a beneficial impact on accidents or potential accidents in desert locations, such as Nevada or New Mexico.

Construction-related data may also be collected and analyzed. Construction-related accident avoidance and/or mitigation technology, functionality, systems, or associated equipment may be more pertinent in large urban areas involving significant and lengthy construction or road connector projects that may include frequently changing travel patterns with little notice to drivers.

D. Autonomous Vehicle Telematics

The data gathered may relate to autonomous vehicle telematics variables. From which, usage-based insurance policies, premiums, rates, discounts, rewards, and/or other insurance-related items may be estimated, as discussed elsewhere herein.

For instance, if sensor data indicates that automatic braking is only used by the driver 50% of the time, an updated or adjusted insurance policy, premium, rate, and/or discount may be estimated for the driver, such as by a remote processor or server associated with the insurance provider. A message may be wirelessly communicated to the vehicle or mobile device associated with the driver that indicates that they may save a given amount of money on their auto insurance if they increase usage of the automatic braking technology or functionality to a certain percentage of time, such as up to 90% of vehicle driving time for example. Usage of other technologies and functionalities (including the technologies and functionalities discussed elsewhere herein) may be monitored, and recommended usages thereof (and associated insurance savings) may be provided to the insured or driver for their review and/or approval.

Other manners of saving money on existing auto insurance coverage may be provided to the driver via wireless communication. For instance, a percentage of time that the vehicle is in a (1) "manual" mode or operation; (2) semi-automated, semi-automatic, or "semi-autonomous" mode or operation; and/or (3) fully automated, fully automatic, or fully "autonomous" mode or operation may be determined from vehicle sensor data that is remotely collected, such as at or by an insurance provider remote processor or server.

The insurance provider remote processor or server may determine auto insurance discounts increases or premium reductions based upon proposed changes to the time that the vehicle is operated in each mode, i.e., manual, semi-autonomous, or fully autonomous. For instance, driving in a semi-autonomous, or even autonomous mode, of operation may be the safest for a given technology or functionality and/or under certain driving conditions (e.g., freeway driving in clear weather and moderate traffic). The driver may be offered a reduced insurance premium or rate to increase usage of the semi-autonomous, or even autonomous, technology or functionality, and/or to increase usage of the semi-autonomous, or even autonomous, technology or functionality in certain driving conditions.

Additionally or alternatively, the insurance provider may offer a plurality of separate tiers of auto insurance policies, premiums, rates, discounts, etc. For example, the insurance provider may offer three separate tiers. The three separate insurance tiers of premiums, rates, discounts, etc. may be based upon (a) a manual insurance rate; (b) a semi-autonomous insurance rate; and/or (c) a fully autonomous insurance rate. The manual insurance rate may be associated with manual operation of the vehicle; the semi-autonomous insurance rate may be associated with semi-autonomous operation of the vehicle; and/or the fully autonomous insurance rate may be associated with autonomous operation of the vehicle.

Also, the data gathered may be used to provide feedback to the customer or insured. For instance, if the vehicle is

presently traveling on the highway, a recommendation or offer may be presented to the driver, such as via wireless communication with the vehicle that indicates that if the driver places the vehicle into autonomous or semi-autonomous driving mode, the risk of collision may be reduced and/or the driver may receive a discount, and/or lower premium on his or her auto insurance.

Other manners of potential risk reductions may also be communicated to the driver or owner of the vehicle. For instance, recommendations and/or adjustments to insurance policies, premiums, rates, discounts, rewards, and/or other insurance-related items may be based upon driver characteristics or age, such as beginning or teenage drivers.

As an example, auto insurance policies, premiums, rates, discounts, rewards, and/or other insurance-related items may be adjusted, updated, or generated based upon (1) the autonomous or semi-autonomous technology and/or functionality; (2) an amount or percentage of driver usage of that technology and/or functionality; and/or (3) driver characteristics. The driver characteristics that may be taken into consideration include driver age, driver health, and/or past driving or accident history.

E. Smart Equipment

The data gathered may originate from various smart parts and/or pieces of smart equipment mounted on a vehicle, including parts configured for wired or wireless communication. For instance, a vehicle may be equipped with smart brakes; smart tail, head, or turn lights; smart tires; etc. Each piece of smart equipment may have a wired or wireless transmitter. Each piece of smart equipment may be configured to monitor its operation, and/or indicate or communicate a warning to the driver when it is not operating properly.

As an example, when a rear brake light is out, such as from faulty repair or from normal burn out, that fact may be detected by smart vehicle functionality and the driver may be promptly notified. As a result, the driver may be able to repair the faulty brake light before an accident caused by the faulty brake light occurs. In another embodiment, the data gathered may also indicate window wipers are not operating properly, and need to be replaced. The insurance provider may adjust or update insurance policies, premiums, rates, discounts, and/or other insurance-related items based upon the smart equipment warning functionality that may alert drivers of vehicle equipment or vehicle safety equipment (lights, brakes, etc.) that need to be replaced or repaired, and thus may reduce collision risk.

In addition to addressing liability for collision risk, the technology may also reduce risk of theft. For instance, stolen vehicles may be tracked via on-board GPS units and wireless transmitters. Also, the breaking and entering, and/or hot wiring, of vehicles may be more difficult through the use of anti-hacking measures for smart vehicles or vehicles with electrical or electronic control systems. The insurance provider may adjust insurance premiums, rates, and/or other insurance-related items based upon the reduced risk of theft.

Assignment of Fault

The present embodiments may relate to the assignment of fault. The assignment of fault may be based upon sensor data and/or other data gathered or collected from, or by, the vehicle. The assignment of fault may impact the future rating for one or more drivers, and/or one or more vehicles equipped with one or more autonomous or semi-autonomous technologies, functionalities, systems, and/or pieces of equipment.

The assignment of fault determination from sensor and/or vehicle data may relate to, and/or involve, determining who was in control of, or driving, the vehicle at the time of the accident (such as either the human driver or the vehicle itself), and/or determining who was at fault or liable for the collision or accident—the human driver or the vehicle. For instance, did the vehicle give the driver enough time (e.g., half a second) to take manual control of the vehicle before the time of impact, or was the driver not attentive enough before an accident.

The assignment of fault may include a determination of who pays the claim associated with a vehicle accident and/or determine future ratings for certain types of technology or functionality, and/or certain insurance policy holders. Fault for a vehicle collision or accident may be partially or fully assigned to one or more drivers, and/or one or more vehicles equipped with one or more autonomous or semi-autonomous technologies, functionalities, systems, and/or pieces of equipment.

In one embodiment, insurance coverage may provide for immediate coverage/payment to an insured in the case of an accident. After which, based upon data collected from the smart vehicle or sensors, blame or fault may be assigned for the accident, such as to either the driver or the autonomous or semi-autonomous technology or functionality, and/or to another driver, or autonomous or semi-autonomous vehicle involved in the accident.

Alluded to above, the data gathered may help determine who was in control of the vehicle before, during, and/or after a vehicle collision or accident. For instance, a human driver, or an autonomous or semi-autonomous vehicle (and/or associated technology, functionality, system, and/or equipment) may have been in control of the vehicle at the time of accident. The data may be used to identify whether there was enough time for a driver to takeover manually. For instance, once a hazardous condition is identified (e.g., vehicles slowing down abruptly or heavy congestion ahead, or vehicle accident ahead), did a semi-autonomous technology function correctly, and/or did the human driver have the time to take manual control of the vehicle and avoid a collision or accident.

For a fully autonomous vehicle, technology, or functionality whether or not the collision or accident could have been avoided may be determined. For example, a performance of the artificial intelligence or computer instructions associated with the autonomous vehicle, technology, or functionality may be evaluated. In accidents or collisions involving one, two, or more autonomous vehicles, evaluating the performance of the autonomous technology or functionality may determine fault—such as which autonomous vehicle was at fault (for an accident involving two autonomous vehicles) or whether an autonomous vehicle or a human driver was at fault (for an accident involving two vehicles, one driven by a human driver and one driven by autonomous vehicle technology, functionality, or systems that may include associated artificial intelligence and/or processors).

Insurance Adjustment Recommendations

Autonomous or semi-autonomous technology, functionality, and/or system usage data may be used to identify and present a driver one or more potential premium or rate reductions with increased usage of the technology, functionality, and/or system. A number of "what if" insurance-related scenarios may be calculated and then presented to a driver and/or insured for their review, approval, and/or modification. The different scenarios may be presented to a driver on their mobile device or a smart vehicle display screen, or other in dash display.

Autonomous or semi-autonomous vehicle technology or functionality may relate to vehicle parking. The technology or functionality may determine an available parking spot in

an urban area or large city. The smart vehicle may make recommendations to the driver regarding the best available parking spot remotely identified. For instance, the best available parking spot may be determined based upon the cost of the parking; safety of the parking spot, lot, or garage; the risk of theft or other liability associated with the parking spot, lot, or garage; and/or other factors.

The recommendation may be generated by an insurance provider remote processor or server. The recommendation with respect to best available parking spot may include information regarding an adjustment to the driver's present insurance policy, premium, rate, and/or discount based upon the driver accepting the recommendation and parking the vehicle in the best available parking spot. A discount and/or lower premium may be offered to the driver to encourage safer parking habits that may reduce the risk of vehicle damage or theft.

Alternatively, based upon an actual parking spot, additional insurance coverage may be offered to the driver. For instance, if the vehicle is going to be parked on a busy street and overnight, it may have a higher risk of damage or theft. A remote processor or server associated with the insurance provider may estimate and/or offer an appropriate increase in auto insurance coverage to the insured or driver, such as via wireless communication with a smart vehicle controller or a mobile device of the insured or driver.

Exemplary Feedback Method

Beyond determining risk categories or premiums for vehicle insurance policies covering autonomous (and/or semi-autonomous) vehicles, in some embodiments the system **100** may operate to monitor use of autonomous (and/or semi-autonomous) operation features and present feedback to vehicle operators. This may occur in real time as operating conditions change or may occur on a periodic basis in response to vehicle use and environmental conditions. The use of autonomous operation features may be assessed to determine whether changes to the number, type, configuration, or settings of the autonomous operation features used may reduce the risk associated with vehicle operation under various conditions. Presenting or otherwise providing the information to the vehicle operator may improve the effective use of the autonomous operation features and/or reduce the risks associated with vehicle operation. Upon receiving a suggestion regarding autonomous operation feature use, the vehicle operator may be able to maximize the effectiveness of the autonomous operation feature, maximize vehicle insurance coverage, and/or minimize vehicle insurance expense.

FIG. **11** illustrates an exemplary autonomous (and/or semi-autonomous) operation feature monitoring and feedback method **1100**. The method **1100** may be performed by the controller **204** or the server **140** at any time while the vehicle **108** is in operation. In some embodiments, the method **1100** may be implemented only when the vehicle **108** is stationary, when the autonomous (and/or semi-autonomous) operation features are controlling the vehicle **108**, when the controller **204** or server **140** determines that the conditions meet certain criteria (e.g., when the vehicle is more than a predetermined distance from environmental obstacles on a restricted access highway, etc.), and/or when the vehicle **108** is first started, such that the method **1100** does not distract the vehicle operator. During implementation of the method **1100**, the controller **204** may determine actual use levels of the autonomous operation features at block **1102**. This may include current use of the features and/or past use of the features, either generally or under similar conditions. In some embodiments, the determination of use levels may include a determination of the use of versions, configurations, or settings related to the autonomous operation features.

At block **1104**, the controller **204** may receive sensor data from the sensors **120**, as discussed above. The received sensor data may include information regarding the vehicle **108**, the vehicle's environment (e.g., traffic conditions, weather conditions, etc.), and/or the vehicle operator. The sensor data may include information regarding the physical or mental state of the vehicle operator using sensors **120** disposed within the vehicle **108** or communicatively connected thereto (e.g., disposed within or communicatively connected to a mobile device **110**, such as a smart phone, and/or a wearable computing device, such as a smart watch or smart glasses). This sensor data may include data from interior cameras, microphones, accelerometers, and/or physiological sensors (e.g., thermometer, microphone, thermal image capture device, electroencephalograph, galvanic skin response sensor, heart rate sensors, respiratory rate sensor, other biometric sensors, etc.). In some embodiments, the received sensor data may exclude sensor data regarding the vehicle operator or the physical or mental state of the vehicle operator.

At block **1106**, the controller **204** or the server **140** may receive communication data from external sources. The communication data may include direct communication data from other autonomous vehicles, communicating infrastructure, and/or other smart devices (e.g., mobile devices carried or worn by pedestrians, passengers in other vehicles, etc.). The communication data may also include indirect communication data received by the controller **204** or the server **140** via the network **130** (e.g., information regarding traffic, construction, accidents, weather, local time, local events, local traffic patterns, local accident statistics, general accident statistics, etc.). The indirect information may be obtained from database **146** or from other networked or third-party databases. For example, indirect communication data may be obtained regarding the risk level of autonomous operation features relative to manual vehicle operation on major highways during typical commuting times in urban areas in light rain, which may be combined with information from a weather service indicating light rain and information from a map service indicating the vehicle **108** is on a major highway (using GPS data from the sensors **120**). As a further example, traffic databases could be accessed to receive information regarding accidents and/or construction further ahead along a route.

At block **1108**, the server **140** or the controller **204** may determine an optimal use level for the autonomous operation features available within the vehicle **108** and/or a suggestion regarding the optimal autonomous operation feature use level under the conditions. The optimal use level or suggestion may include the types and versions of autonomous operation features to use, configurations of the features, and/or settings relating to the features. The server **140** or the controller **204** may determine one or more optimal use levels for the autonomous operation features based upon the sensor data and communication data received in blocks **1104** and **1106** using any known or later-developed optimization techniques. In some embodiments, the risk levels associated with each combination of use levels for autonomous operation features may be determined and stored in one or more databases, such that the server **140** or controller **204** may access and compare the appropriate database entries to determine the optimal use levels. In further embodiments, one or more optimal use levels may be determined and stored in one or more databases, such that the server **140** or

controller **204** may determine the optimal use level by accessing the database entry corresponding to the sensor data and communication data. Alternatively, the server **140** or controller **204** may determine optimal use levels by determining risk levels for a variety of combinations of configurations and settings associated with autonomous operation features based on the received sensor data and communication data. In such embodiments, the combination or combinations determined to have the lowest risk may be determined to be the optimal feature use levels.

The determination of optimal feature use may be based upon the received sensor data and/or the communication data. In some embodiments, the received sensor data and/or communication data may include information regarding the physical, mental, and/or emotional state of the vehicle operator, as noted above. In various embodiments, the determination of the optimal feature use level may either include or exclude information regarding the state of the vehicle operator from the determination. For example, the determination may be based in part upon the previous driving history of a vehicle operator, which may indicate that the vehicle operator has an increased risk of an accident in low light environments. In the example, the determination may compare the expected performance of the various autonomous operation features against the expected performance of the vehicle operator, which may cause the server **140** or controller **204** to determine an optimal feature use level that includes more autonomous operation feature use than would otherwise be determined to be optimal. As a related example, the server **140** or the controller **204** may not determine the optimal use level based upon the previous driving history of the vehicle operator from the previous example, which may result in a determination of an optimal feature use level that includes less use of autonomous operation features than in the preceding example.

The determined optimal use level may be used to further determine an autonomous (and/or semi-autonomous) operation feature use suggestion. The use suggestion may include one or more settings relating to autonomous operation features, enabling or disabling particular autonomous operation features, using specific versions of autonomous operation features, resuming manual operation of the vehicle, temporarily ceasing autonomous and/or manual operation of the vehicle, and/or similar changes to the use and configuration of the autonomous operation features in operating the vehicle **108**. It should be noted that the determined use suggestion may include changes to the use of autonomous operation features, use of additional autonomous operation features, and/or use of fewer autonomous operation features.

At block **1110**, the suggested optimal use levels of autonomous (and/or semi-autonomous) operation features determined at block **1108** is compared against the actual autonomous operation feature use levels determined at block **1102**. When the suggested and optimal feature use levels are determined to be different, the server **140** or the controller **204** causes a suggestion of autonomous operation feature use to be presented to the vehicle operator at block **1112**. In some embodiments, the suggestion may not be presented when the difference between the optimal use level and the actual use level is below a predetermined threshold. For example, the server **140** may determine not to present the suggested autonomous operation use to the vehicle operator where the difference would only result in a risk reduction equivalent to a monetary value below five cents.

The suggestion presented at block **1112** may be presented using a display within the vehicle **108**, a mobile device **110**, or other means, including visual and/or audible notifications. The suggestion may include a recommendation that the vehicle operator enable or use one or more additional autonomous (and/or semi-autonomous) operation feature, that the vehicle operator change the settings or configuration for one or more autonomous (and/or semi-autonomous) operation features, that the vehicle operator disable or discontinue use of one or more autonomous (and/or semi-autonomous) operation features, and/or related changes that may be made to the use of the autonomous (and/or semi-autonomous) operation features. The suggestion may further include one or more reasons for making a change to the autonomous operation feature use, such as an indication of a reduction in risk, a percentage reduction in the probability of a collision, an increase in a probability of completing the trip without incident, a reduction in a premium or other policy charge, a reduction in a rate, an increase in a coverage amount, an increase in a coverage type, a reduction in a deductible, and/or related information to induce the vehicle operator to change the autonomous operation feature use. For example, a suggestion presented to the vehicle operator may indicate that updating to a newer software version of an autonomous operation feature would result in a decrease of a certain amount in a vehicle insurance premium. In some embodiments, the vehicle operator may make a selection upon presentation of the suggestion, which selection may cause the use levels of one or more of the autonomous operation features to be adjusted (e.g., to match the one or more optimal use levels). In other embodiments, the vehicle operator may otherwise adjust or control the use levels, as discussed above. A change or adjustment to the use, configuration, or settings of the autonomous operation features may further cause a change or adjustment to costs or coverage associated with a vehicle insurance policy, as discussed above.

After a suggestion has been presented at block **1112** or when the suggested optimal feature use is determined to be insufficiently different from the actual feature use at block **1110**, the server **140** or the controller **204** determine whether vehicle operation is ongoing at block **1114**. When operation is ongoing, the method **1100** may repeat the steps of blocks **1102-1112**. In some embodiments, the method **1100** may repeat only when a predetermine period of time (e.g., 5 minutes, 15 minutes) has passed, when vehicle operating conditions have sufficiently changed (e.g., upon exiting a highway, entering fog, sunset, etc.), and/or when a sufficient change in the recommendation has occurred (e.g., risk level, monetary incentive, feature use level recommendation, etc.). When the operation of the vehicle **108** is complete, the method **1100** may terminate. In some embodiments, however, the method **1100** may be implemented either before or after vehicle operation, in which case the actual autonomous (and/or semi-autonomous) operation feature use determined in block **1102** may be based upon the settings of the autonomous operation features that had been previously used, the settings that would be applied if the vehicle were to be used at that time, or the default settings.

Exemplary Warning Method

In addition to monitoring use of autonomous operation features to present feedback regarding autonomous (and/or semi-autonomous) operation feature use to vehicle operators, some embodiments may determine elevated risk levels and present warnings to the vehicle operator. In some embodiments, this may include warnings regarding situations where no changes to the optimal autonomous operation feature use level would be suggested, but where an increased risk nonetheless exists. For example, communication data regarding recent snowfall may be combined with sensor data

indicating a high frequency of slipping wheels to determine a high risk of an accident exists at the current speed on a snow-covered road. The vehicle operator might then respond by reducing the speed of the vehicle, resuming manual control of the vehicle, and/or selecting an alternate route using major thoroughfares that are clear of snow. Such responses may further cause an adjustment in a cost or coverage level associated with a vehicle insurance policy.

FIG. **12** illustrates an exemplary autonomous (and/or semi-autonomous) operation feature monitoring and alert method **1200**. The method **1200** may be performed by the controller **204** or the server **140** at any time while the vehicle **108** is in operation. During implementation of the method **1200**, the controller **204** or server **140** may determine the use of the autonomous operation features at block **1202**. This may include current use of versions, configurations, or settings related to the autonomous operation features. As discussed above, the controller **204** or server **140** may further receive sensor data and communication data, respectively, at blocks **1204** and **1206**. The sensor data may be received from sensors **120** disposed within the vehicle **108**, and the communication data may include information regarding the vehicle environment (including information regarding the rate of incidents in similar conditions or locations based on historical data). This information may be used at block **1208** to determine the risk associated with operation of the vehicle under the conditions. As above, the sensor data, communication data, and the determination of risk may either include or exclude information regarding one or more vehicle operators (e.g., the physical, mental, and/or emotional state of the vehicle operator).

At block **1208**, the server **140** or the controller **204** may determine a risk level associated with the operation of the vehicle under the current conditions. This may include a determination of the risk associated with the autonomous (and/or semi-autonomous) vehicle operation features then in use, or it may include a determination of the risk associated with various configurations or settings of autonomous operation features as discussed above with respect to method **1100**. In some embodiments, the determination may not include information regarding one or more vehicle operators. The server **140** or controller **204** may determine one total risk level or a plurality of risk levels associated with vehicle operation at block **1208**. For example, separate risk levels may be determined for different types of potential incidents (e.g., collisions with other vehicles, loss of control or traction, collisions with pedestrians, collisions with stationary obstructions, etc.).

At block **1210**, the server **140** or the controller **204** may compare the determined risk level against a warning threshold risk level. In some embodiments, the difference between the determined risk level and a risk level associated with an optimal autonomous (and/or semi-autonomous) operation feature use level (as discussed above with respect to method **1100**) may be compared against the warning threshold, and the warning threshold may be set at a level such that a warning is triggered only when the additional risk from suboptimal autonomous (and/or semi-autonomous) operation feature use, configuration, and/or settings exceeds a certain level. In further embodiments, the risk level may be compared against a plurality of predetermined warning thresholds, and the warning presented to the vehicle operator may be determined based upon the highest warning threshold exceeded by the risk level.

When the risk level is determined to exceed the warning threshold at block **1210**, the controller **204** or server **140** may cause a warning to be presented to the vehicle operator at block **1212**. The warning presented at block **1212** may be presented using a display within the vehicle **108**, a mobile device **110**, or other means, including visual, audible, and/or haptic notifications. The warning may specify one or more causes of the elevated risk (e.g., weather, speed, hardware malfunctions, etc.). Alternatively, the warning may simply alter the vehicle operator to an elevated risk level. In some embodiments, the vehicle operator may make a selection upon presentation of the alert, which selection may cause the use, configuration, or settings of one or more of the autonomous (and/or semi-autonomous) operation features to be adjusted (e.g., the vehicle operator may resume full control of operation, the vehicle operator may cede control of operation to the autonomous (and/or semi-autonomous) operation features, etc.). In other embodiments, the vehicle operator may otherwise adjust or control the use levels, as discussed above. A change or adjustment to the use, configuration, or settings of the autonomous operation features may further cause a change or adjustment to costs or coverage associated with a vehicle insurance policy, as discussed above.

After the warning has been presented at block **1212** or when the risk level is determined to be below the risk threshold at block **1210**, the server **140** or the controller **204** determine whether vehicle operation is ongoing at block **1214**. When operation is ongoing, the method **1200** may repeat the steps of blocks **1202-1212**. When the operation of the vehicle **108** is complete, the method **1200** may terminate.

Exemplary Fault Determination Method

In some embodiments, the system **100** may be used to determine or allocate fault upon the occurrence of an accident or other collision involving the vehicle **108**. Information regarding the operation of the vehicle **108** may be recorded and stored during operation, which may then be used to determine the cause of a collision or accident automatically upon receiving an indication of the occurrence of such. Fault may be allocated to either the vehicle operator, one or more autonomous operation features, or a third party (e.g., another motorist or autonomous vehicle). Such allocation of fault may be further used to adjust one or more of an insurance policy premium, a risk level, a rate category, a penalty, or a discount relating to a vehicle insurance policy. In some embodiments, the allocation of fault may also be used to determine whether to cancel an insurance policy, adjust a deductible, adjust a policy limit, and/or determine a payment associated with the collision or accident. Where an autonomous operation feature is determined to be wholly or partially responsible for the accident, the risk levels or risk profile associated with that autonomous operation feature may be revised, such that the risk levels or risk profile of other autonomous vehicles using the feature may also be adjusted.

FIG. **13** illustrates an exemplary fault determination method **1300** for determining fault following an accident based upon sensor data and communication data. Upon receiving an indication of an accident at block **1302**, the method **1300** may receive sensor data and communication data at block **1304** and may further receive information regarding the operation of one or more autonomous (and/or semi-autonomous) operation features at block **1306**. In some embodiments, this information may be used to make a preliminary determination of whether a third party is at fault at block **1308**, in which case there may be no fault allocated to the vehicle operator and/or autonomous (and/or semi-autonomous) operating features. If a third party was not at fault or if the vehicle **108** had the last chance to avoid the accident, the method **1300** may then determine and allocate

fault between the vehicle operator and one or more autonomous (and/or semi-autonomous) operation features in blocks **1314-1324**. The determination of fault may further be used to determine and/or adjust a coverage level at block **1326**, such as a deductible level or a policy status.

The determination process of method **1300** may depend upon whether the vehicle **108** is operated in a fully autonomous, partially autonomous, or manual operation mode at the time of the accident. In some embodiments, the server **140** may determine and/or allocate fault without human involvement. In other embodiments, the server **140** may present relevant information and/or a determination of fault to a reviewer (e.g., a claims adjuster or other specialist) for verification or further analysis. In such embodiments, the presented information may include summaries or detailed reports of sensor data and/or communication data, including still images or video recordings from the sensors **120** within the vehicle **108** or other sensors at the location of the accident (e.g., sensors disposed within other vehicles involved in or near the accident site, sensors disposed within infrastructure elements, etc.). The method **1300** may be implemented by the mobile device **110**, the on-board computer **114**, the server **140**, and/or some combination of these components.

At block **1302**, the server **140** may receive an indication of an accident involving the vehicle **108**. The server **140** or controller **204** may generate this indication automatically based on sensor data, or it may be initiated manually by a vehicle operator or another person following the accident. However the indication is received, it may cause the method **1300** to proceed to the one or more determinations of fault.

At block **1304**, the server **140** may receive sensor data from the one or more sensors **120** within the vehicle **108** and/or communication data from the communication component **122** and/or the communication unit **220**. In addition, the server **140** may receive additional information from external sources, including sensor data from other vehicles or infrastructure, communication information from other vehicles or infrastructure, and/or communication information from third-party sources. For example, additional information may be obtained from other autonomous vehicles involved in the accident or near the accident. As discussed above, the server **140** may additionally receive control decision data regarding the control decisions generated by one or more of the autonomous operation features of the vehicle **108**. In some embodiments, the sensor and/or communication data may be stored in the database **146** or in the program memory **160** or **208**, and/or in the RAM **164** or **212** during ordinary operation of the vehicle **108**, from which the data may be retrieved or accessed by the server **140**. Additionally, or alternatively, the sensor and/or communication data may be stored in another memory or database communicatively connected to the network **130**. In some embodiments, a back-up of the sensor and/or communication data may be stored within a memory (not shown) that may be designed to withstand the forces and temperatures frequently associated with a vehicular collision.

At block **1306**, the server **140** may further receive information regarding the operation of the autonomous (and/or semi-autonomous) operation features in the vehicle **108**. This information may include information regarding use, configuration, and settings of the features concurrent with the accident. In some embodiments, the information may further include information regarding control signals or outputs from the autonomous operation features to control the vehicle **108**. This may be useful, for example, in determining whether the autonomous operation feature failed to take appropriate control actions or whether the control signals were not implemented or were ineffective in controlling the vehicle **108** (e.g., such as may occur when on ice or when a defect prevents an electromechanical control from properly functioning). In some embodiments, autonomous operation feature data may be available for additional vehicles involved in the accident, which may be accessed or obtained by the server **140**. As above, the autonomous operation feature data may be recorded during ordinary operation of the vehicle **108** and accessed or obtained by the server **140** upon receipt of the indication of the accident.

At block **1308**, the server **140** may determine whether a third party is at fault for the accident based upon the sensor data, communication data, and/or autonomous (and/or semi-autonomous) operation feature data received in blocks **1304** and **1306**. Determining fault may generally include determining one or more of the following: a point of impact on the vehicle **108**, a point of impact on one or more additional vehicles, a velocity of the vehicle **108**, a velocity of one or more additional vehicles, a movement of the vehicle **108**, a movement of one or more additional vehicles, a location of one or more obstructions, a movement of one or more obstructions, a location of one or more pedestrians, a movement of one or more pedestrians, a measure of road surface integrity, a measure of road surface friction, a location of one or more traffic signs or signals (e.g., yield signs, stop signs, traffic lights, etc.), an indication of the state of one or more traffic signs or signals, a control signal generated by one or more autonomous operation features of the vehicle **108**, and/or a control signal generated by one or more autonomous operation features of one or more additional vehicles. Based upon the above-mentioned factors, the server **140** may determine whether the vehicle **108** (including the vehicle operator and/or the autonomous operation features) caused the accident or whether a third party (including other autonomous vehicles, other vehicle operators, pedestrians, etc.) caused the accident.

For purposes of determining fault at block **1310**, in some embodiments the server **140** may include unavoidable accidents as being the fault of a third party (e.g., a bridge collapse, an animal suddenly darting into the path of a vehicle, etc.). Additionally, or alternatively, physical defects in the autonomous vehicle **108** or the physical components of the autonomous operation features (e.g., the sensors **120**, the on-board computer **114**, or connections within the vehicle **108**) may be determined by the server **140** as being the fault of a third party (e.g., the vehicle maker, the original equipment manufacturer, or the installer).

When the accident is determined at block **1310** to have been caused by a third party, the server **140** may then determine whether the vehicle **108** or the vehicle operator had a chance to avoid the accident that was not taken at block **1312**. For example, the vehicle operator may have been able to avoid a collision by braking or swerving but for inattentiveness at the time of the accident. Where no such chance for the vehicle operator or the autonomous operation features to avoid the accident is determined to have existed at block **1312**, the fault determination method **1300** may terminate. Where such a chance to avoid the accident is determined to have existed at block **1312**, the method **1300** may continue to allocate a portion of the fault between the vehicle operator and the autonomous operation features.

At block **1314**, the server **140** may determine the operating control status of the vehicle **108** at the time of the accident based upon the received autonomous (and/or semi-autonomous) operation feature data regarding the use, configuration, and settings of the features. The vehicle **108** may

be determined to have been either manually, fully autonomously, or partially autonomously operated at the time of the accident. Based upon the determination, the allocation of fault will be determined differently. Of course, any allocation of fault to a third party above at block **1310** may decrease the total fault to be allocated between the vehicle operator and the one or more autonomous operation features.

Where it is determined at block **1314** that the vehicle **108** was operating entirely manually without any autonomous operation features at the time of the accident, the fault may be allocated entirely to the vehicle operator. In such case, the server **140** may adjust (or cause to be adjusted) the risk or rate profile associated with the vehicle operator at block **1322** in a manner similar to the adjustment that is typically made when a vehicle operator of a non-autonomous vehicle is determined to be at fault for an accident.

Where it is determined at block **1314** that the vehicle **108** was operating in a fully autonomous mode at the time of the accident, the fault will usually be assigned entirely to one or more autonomous operation features. There are some situations, however, where the autonomous operation feature may recognize a situation where autonomous operation is no longer feasible due to conditions in the vehicle's environment (e.g., fog, manual traffic direction, etc.). When it is determined that the vehicle **108** was operating as a fully autonomous vehicle at block **1314**, therefore, the server **140** may determine whether the one or more autonomous operation features attempted to return control of the vehicle to the vehicle operator prior to the accident at block **1318**. Because such attempts may require the vehicle operator to be alert and capable of receiving control from the autonomous operation features, an adequate period of time for transition may be required. Thus, when it is determined at block **1320** that the autonomous operation features did not attempt to return control of the vehicle **108** to the vehicle operator or failed to provide sufficient time to transfer control, the server **140** may allocate fault for the accident to the one or more autonomous operation features and adjust the risk levels and/or risk profiles associated with the one or more autonomous operation features at block **1324**. When it is instead determined that the autonomous operation features attempted to return control of the vehicle **108** to the vehicle operation with adequate time for transferring control at block **1320**, the server **140** may allocate fault to the vehicle operator, and the vehicle operator's risk or rate profile may be adjusted at block **1322**. In some embodiments, the server **140** may allocate some portion of the fault to each of the vehicle operator and the autonomous operation features where an attempt to return control of the vehicle **108** to the vehicle operator was made, notwithstanding vehicle operator inattention.

Where it is determined at block **1314** that the vehicle **108** was operating in a partially autonomous mode at the time of the accident, the server **140** determines an allocation of fault between the vehicle operator and one or more autonomous operation features at block **1316**. This determination may include determining which autonomous operation features were in use at the time of the accident, the settings of those autonomous operation features, and whether the vehicle operator overrode the operation of the autonomous operation features. For example, the server **140** may determine that an autonomous operation feature such as adaptive cruise control without lane centering to be fully or primarily responsible for an accident caused by the vehicle **108** striking another vehicle directly ahead in the same lane. In contrast, the server **140** may determine the vehicle operator to be fully or primarily at fault when the same adaptive cruise control without lane centering was engaged when the vehicle **108** struck another vehicle in an adjacent lane. Upon determining the allocation of fault at block **1316**, the server **140** may adjust the vehicle operator and/or autonomous operation feature risk levels accordingly in blocks **1322** and/or **1324**, respectively. In some embodiments, the use of autonomous operation features may be considered in reducing the adjustment to the vehicle operator risk or rate profile, thereby mediating the impact of the accident on the rates or premiums associated with vehicle insurance for the vehicle operator.

At block **1326** the method **1300** may further utilize the fault determinations for underwriting and/or claim administration, in addition to or as an alternative to adjusting one or more risk levels associated with the vehicle operator or the autonomous operation features. The server **140** may further determine and/or adjust one or more coverage levels associated with an insurance policy covering the vehicle **108** based upon the allocation of fault between the vehicle operator and the autonomous operation features. For example, coverage levels may increase or decrease as the portion of the fault allocated to the autonomous operation feature increases or decreases. In some embodiments, the coverage level may be associated with the accident, such as a deductible, an estimate of a cost to repair or replace the vehicle, an estimate of a cost to repair or replace other property, and/or other payments or adjustments to payments associated with damage or injuries arising from the specific accident. In further embodiments, the coverage level may be associated with a general aspect of the insurance policy, such as a type of coverage, a maximum payment with respect to one or more types of coverage, a maximum payment per person, and/or a maximum total payment per accident. For example, where an autonomous operation feature is determined to be at fault at blocks **1314-1324**, a deductible associated with the insurance policy may be reduced or eliminated with respect to the accident. Where both the vehicle operator and an autonomous operation feature are determined to be partially at fault, the coverage level may be determined or adjusted based upon the portion of the fault allocated to each, either directly proportionally or otherwise. For example, the deductible for an accident caused in equal part by the vehicle operator and one or more autonomous operation features may be reduced by some amount (e.g., 25%, 50%, 75%). As a further example, some or all of the maximum coverage limits associated with the insurance policy may be increased (e.g., 25% increase in liability coverage, 50% increase in collision coverage, etc.).

In some embodiments, the determination and/or adjustment of the coverage levels may include a determination of ongoing coverage levels or coverage status. The server **140** may determine whether to cancel or decline to renew a policy based upon the allocation of fault and/or received information regarding the accident. For example, when the vehicle operator is determined to be wholly at fault or to be above a fault proportion threshold (e.g., the vehicle operator is responsible for 80% of the fault allocated), the server **140** may determine to cancel the policy in accordance with its terms. Alternatively, the server **140** may determine to require or exclude certain types or levels of coverage, either generally or in a manner dependent upon the settings or configuration of one or more of the autonomous operation features. For example, when the vehicle operator is determined to be above a fault proportion threshold, the server **140** may limit renewal options to exclude collision coverage or limit the maximum policy limit of collision coverage. In

some embodiments, coverage may further be limited or cancelled based upon the use of specific autonomous operation features, such as where an autonomous operation feature is determined to be wholly or partially at fault. Determinations regarding coverage levels or coverage status may be further based upon information regarding the vehicle and/or the vehicle operator, such as information regarding previous accidents and/or the vehicle operator's history of use of autonomous operation features (including settings used). Further embodiments may require or exclude coverage (or levels of coverage) based upon future use of autonomous operation features. For example, following an accident caused by the vehicle operator driving at night, the server **140** may determine to cancel coverage for future claims arising from manual operation of the vehicle by the vehicle operator at night. Thus, the coverage may only extend to operation of the vehicle during daylight hours or autonomous operation of the vehicle at night.

In some embodiments, the server **140** may cause one or more of the adjustments to the insurance policy to be presented to the vehicle operator or other customer. The customer may be presented with one or more options relating to adjustments to the policy (e.g., options to either agree to use autonomous operation features with certain settings or to forego a type of coverage). Where the vehicle operator declines all presented options, the server **140** may cancel or decline to renew the policy. As with determination of fault, in some embodiments, determinations of adjustments or cancellation may be presented to a reviewer (e.g., a claims adjuster or other specialist) for verification or further analysis prior to becoming effective.

Once the server **140** has assigned fault, adjusted the vehicle operator's risk or rate profile and/or one or more of the autonomous (and/or semi-autonomous) operation feature risk levels or profiles, and determined or adjusted one or more coverage levels associated with the vehicle insurance policy, the fault determination method **1300** may terminate. The adjusted risk levels or profiles may be used to adjust a premium, surcharge, penalty, rate, or other cost associated with a vehicle insurance policy for the vehicle **108** and/or the vehicle operator.

In some embodiments, the fault determination method **1300** may be implemented after payment has been made on claims relating to the accident. Because the sensor, communication, and autonomous operation feature data may be stored for later use, as discussed above, payment may be made shortly after occurrence of the accident. Determination of fault may then be made or verified at a later date. For example, operating data concerning an accident may be stored for later use following the accident, but payment of claims based upon a vehicle insurance policy covering the vehicle may be made before a determination of fault. Alternatively, or additionally, the fault determination method **1300** may be used to preliminarily determine fault immediately or shortly after the occurrence of an accident, and payment of claims may be made based upon such preliminary determination. Review and assessment of the preliminary determination may be completed at a later time, thereby allowing faster processing of claims.

Autonomous Vehicle Insurance Policies

The disclosure herein relates to insurance policies for vehicles with autonomous operation features. Accordingly, as used herein, the term "vehicle" may refer to any of a number of motorized transportation devices. A vehicle may be a car, truck, bus, train, boat, plane, motorcycle, snowmobile, other personal transport devices, etc. Also as used herein, an "autonomous operation feature" of a vehicle means a hardware or software component or system operating within the vehicle to control an aspect of vehicle operation without direct input from a vehicle operator once the autonomous operation feature is enabled or engaged. Autonomous operation features may include semi-autonomous operation features configured to control a part of the operation of the vehicle while the vehicle operator control other aspects of the operation of the vehicle. The term "autonomous vehicle" means a vehicle including at least one autonomous operation feature, including semi-autonomous vehicles. A "fully autonomous vehicle" means a vehicle with one or more autonomous operation features capable of operating the vehicle in the absence of or without operating input from a vehicle operator. Operating input from a vehicle operator excludes selection of a destination or selection of settings relating to the one or more autonomous operation features.

Additionally, the term "insurance policy" or "vehicle insurance policy," as used herein, generally refers to a contract between an insurer and an insured. In exchange for payments from the insured, the insurer pays for damages to the insured which are caused by covered perils, acts, or events as specified by the language of the insurance policy. The payments from the insured are generally referred to as "premiums," and typically are paid by or on behalf of the insured upon purchase of the insurance policy or over time at periodic intervals. Although insurance policy premiums are typically associated with an insurance policy covering a specified period of time, they may likewise be associated with other measures of a duration of an insurance policy, such as a specified distance traveled or a specified number of trips. The amount of the damages payment is generally referred to as a "coverage amount" or a "face amount" of the insurance policy. An insurance policy may remain (or have a status or state of) "in-force" while premium payments are made during the term or length of coverage of the policy as indicated in the policy. An insurance policy may "lapse" (or have a status or state of "lapsed"), for example, when the parameters of the insurance policy have expired, when premium payments are not being paid, when a cash value of a policy falls below an amount specified in the policy, or if the insured or the insurer cancels the policy.

The terms "insurer," "insuring party," and "insurance provider" are used interchangeably herein to generally refer to a party or entity (e.g., a business or other organizational entity) that provides insurance products, e.g., by offering and issuing insurance policies. Typically, but not necessarily, an insurance provider may be an insurance company. The terms "insured," "insured party," "policyholder," and "customer" are used interchangeably herein to refer to a person, party, or entity (e.g., a business or other organizational entity) that is covered by the insurance policy, e.g., whose insured article or entity is covered by the policy. Typically, a person or customer (or an agent of the person or customer) of an insurance provider fills out an application for an insurance policy. In some cases, the data for an application may be automatically determined or already associated with a potential customer. The application may undergo underwriting to assess the eligibility of the party and/or desired insured article or entity to be covered by the insurance policy, and, in some cases, to determine any specific terms or conditions that are to be associated with the insurance policy, e.g., amount of the premium, riders or exclusions, waivers, and the like. Upon approval by underwriting, acceptance of the applicant to the terms or conditions, and payment of the initial premium, the insurance policy may be in-force, (i.e., the policyholder is enrolled).

Although the exemplary embodiments discussed herein relate to automobile insurance policies, it should be appreciated that an insurance provider may offer or provide one or more different types of insurance policies. Other types of insurance policies may include, for example, commercial automobile insurance, inland marine and mobile property insurance, ocean marine insurance, boat insurance, motorcycle insurance, farm vehicle insurance, aircraft or aviation insurance, and other types of insurance products.

Analyzing Effectiveness of Technology & Functionality

In one aspect, the present embodiments may provide a system and method for estimating the effectiveness of one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment on reducing a likelihood, and/or severity, of a vehicle accident, such as depicted in FIG. **14** (discussed further below). The system and method, for each autonomous or semi-autonomous vehicle technology or functionality that is analyzed, may evaluate or utilize the effect or impact of one or more accident-related factors or elements on the effectiveness of the respective autonomous or semi-autonomous vehicle technology or functionality. The analysis or evaluation may determine the impact of each factor or element on how well an autonomous or semi-autonomous vehicle technology or functionality actually performs under certain conditions (such as driving, vehicle, and/or road conditions; accident or vehicle type; and/or other factors).

A. Technologies and Functionalities

Noted above, a system and method may analyze and/or evaluate the effectiveness of autonomous or semi-autonomous vehicle technology, functionality, systems, and/or equipment. Individual technologies, functionalities, systems, and/or pieces of equipment may be evaluated that are related to: (1) fully autonomous (or driverless) vehicles; (2) limited driver control; (3) automatic or automated steering, acceleration, and/or braking; (4) blind spot monitoring; (5) collision warning; (6) adaptive cruise control; (7) parking assistance; (8) driver acuity or alertness monitoring; (9) pedestrian detection; (10) software security for smart vehicles; (11) theft prevention; (12) artificial intelligence upgrades or updates; (13) GPS functionality; (14) vehicle-to-vehicle wireless communication; (15) vehicle-to-infrastructure one or two-way wireless communication; and/or other technology and functionality, including that discussed elsewhere herein. Each technology or functionality, and/or the accident avoidance and/or mitigation effectiveness thereof, may be analyzed individually and/or in combination with one or more other technologies or functionalities.

B. Factors or Elements Impacting Effectiveness

The analysis and/or evaluation of the effectiveness of each technology or functionality may determine an impact of one or more factors or elements that may degrade the performance of each autonomous or semi-autonomous vehicle technology or functionality. For instance, each factor or element may lower or limit the effectiveness of an autonomous or semi-autonomous vehicle technology or functionality with respect to accident avoidance and/or limiting the severity of vehicle accidents. The factors or elements may be analyzed individually and/or in combination with one or more other factors or elements.

Mentioned above, accident-related or other factors, elements, and/or conditions may impact the effectiveness of an autonomous or semi-autonomous vehicle technology or functionality. The factors, elements, and/or conditions that may be evaluated may include: (1) point of vehicle impact during a vehicle accident; (2) type of road that an accident occurs on; (3) time of day that an accident occurs at; (4) weather conditions associated with an accident; (5) type of trip during which the accident occurred (short, long, etc.); (6) vehicle style for the vehicle(s) involved in an accident; (7) whether the vehicles involved in the accident were equipped with vehicle-to-vehicle wireless communication functionality; (8) whether the vehicle(s) involved in the accident were equipped with vehicle-to-infrastructure or infrastructure-to-vehicle wireless communication functionality; and/or other factors, elements, and/or conditions associated with, or impacting, individual vehicle accidents.

An evaluation of the foregoing factors, elements, and/or conditions with respect to multiple vehicle accidents involving vehicles having one or more autonomous or semi-autonomous vehicle technologies or functionalities may indicate or suggest: (a) an overall effectiveness for each individual autonomous or semi-autonomous vehicle technology or functionality, and/or (b) the impact (whether negative or positive) of each factor or element (type of road; type of vehicle; time of day; weather conditions; type of vehicle crash, i.e., point of impact; etc.) on the effectiveness of each autonomous or semi-autonomous vehicle technology, functionality, and/or associated equipment. After which, insurance premiums, rates, discounts, rewards, points, and/or other insurance-related items for vehicles having one or more autonomous or semi-autonomous vehicle technologies or functionalities may be generated, adjusted, and/or updated.

C. Applying Driver Characteristics to Auto Insurance

Characteristics and/or driving behaviors of individual drivers or customers may also be used to estimate, generate, and/or adjust insurance premiums, rates, discounts, rewards, and/or other insurance-related items for vehicles having one or more autonomous or semi-autonomous vehicle technologies or functionalities. Driver characteristics and/or driver behavior, as well as driver location or home address, may be compared, or analyzed in conjunction, with the factors or elements that may impact the accident avoidance or mitigation effectiveness of each autonomous or semi-autonomous vehicle technology or functionality.

For instance, a driver or insured may mainly drive on the highway, during daylight hours, and/or primarily for short commutes to and from work. The driver or insured's vehicle may have certain autonomous or semi-autonomous vehicle technologies or functionalities that have been established to decrease the likelihood of an accident, the severity of any accident, and/or otherwise increase safety or vehicle performance during highway, daylight, and/or short commute driving. If so, the insurance rate, premium, discount, and/or another insurance-related item for the driver or insured may be adjusted in accordance with the estimated lower risk (of accident, and/or severe accident).

As one example, the impact of one factor (point of vehicle impact) on the effectiveness of accident avoidance and/or mitigation for an autonomous or semi-autonomous vehicle technology or functionality may be determined. For instance, the impact of head-on collisions on the accident avoidance and/or mitigation effectiveness of automatic braking and/or automatic steering functionality may be analyzed. Also analyzed may be the effect of point of vehicle impact on the accident avoidance and/or mitigation effectiveness of automatic acceleration functionality. The impact of point of vehicle impact on the accident avoidance and/or mitigation effectiveness of other autonomous or semi-autonomous technologies and/or functionalities, including those discussed elsewhere herein, may additionally or alternatively be evaluated.

As another example, the impact of another factor (vehicle size or type) on the effectiveness of accident avoidance and/or mitigation for an autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment may be determined. For instance, the impact of the vehicle being a compact car, mid-sized car, truck, SUV (sport utility vehicle), etc. on the accident avoidance and/or mitigation effectiveness for blind spot monitoring functionality and/or driver acuity monitoring functionality may be analyzed. The impact of vehicle size or type on the accident avoidance and/or mitigation effectiveness of other autonomous or semi-autonomous technologies and/or functionalities, including those discussed elsewhere herein, may additionally or alternatively be evaluated.

As a further example, the impact of another factor (type of road) on the effectiveness of accident avoidance and/or mitigation for an autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment may be determined. For instance, the impact of the type of road (whether a freeway, highway, toll way, rural road or two-lane state or county highway, and/or downtown or city street) on the accident avoidance and/or mitigation effectiveness for adaptive cruise control functionality and/or vehicle-to-vehicle functionality may be analyzed. The impact of type of road on the accident avoidance and/or mitigation effectiveness of other autonomous or semi-autonomous technologies and/or functionalities, including those discussed elsewhere herein, may additionally or alternatively be evaluated.

Additionally, the amount of time or percentage of vehicle usage that an autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment is used by the driver or vehicle operator may be determined from sensor or smart vehicle data. Technology usage information gathered or collected may be used to generate, update, and/or adjust insurance policies, premiums, rates, discounts, rewards, points, programs, and/or other insurance-related items.

D. Exemplary System Overview

At a broad level, the methods and systems described herein may be viewed as combining information regarding autonomous (and/or semi-autonomous) vehicle operation technology with information regarding environmental or usage elements to evaluate one or more autonomous (and/or semi-autonomous) operation features, determine one or more risk factors for the autonomous (and/or semi-autonomous) operation features, and determine vehicle insurance premiums based upon the risk factors. In some embodiments, the autonomous operation features may include an autonomous driving software package or artificial intelligence for operating an automobile. Evaluation of the autonomous operation features may include evaluating both software and hardware associated with the features in a test environment, as well as evaluating actual loss experience associated with vehicles using the features in ordinary operation (i.e., operation not in a test environment). The risk factors may be associated with the relative ability of the autonomous operation features to make control decisions that avoid accidents and other collisions. The risk factors may be included in determining insurance policy premiums, which may in some embodiments include other factors relevant to the determination of the total risk associated with one or more types of insurance coverage for an autonomous vehicle.

FIG. **14** illustrates a high-level flow diagram of an exemplary autonomous (and/or semi-autonomous) automobile insurance pricing system. Information regarding one or more autonomous operation feature technologies is collected, accessed, or otherwise received at block **1402**. Such information may relate to one or more of the following technologies: a fully autonomous (driverless) vehicle operating technology, a limited driver control technology, an automatic steering technology, an automatic acceleration and/or braking technology, a blind spot monitoring and/or other information augmenting technology, a collision and/or other warning technology, an adaptive cruise control technology, a parking assist technology, and/or other autonomous operation technologies (including those described elsewhere herein or later developed). The autonomous operation feature technologies of block **1402** may be associated with one or more environmental or usage elements, information regarding which may be collected, accessed, or otherwise received at block **1404**. Such information may relate to one or more of the following elements: a point of impact between the autonomous automobile and another object (e.g., another vehicle, an infrastructure component, or another moving or fixed object within the autonomous automobile's environment), a type of road (e.g., a limited access highway, a residential neighborhood street, or a main thoroughfare), a time of day and/or date (e.g., rush hour, weekend, or holiday), a weather condition (e.g., light levels, cloud cover, precipitation, temperature, wind, or ground cover such as ice or snow), a type and/or purpose of vehicle trip (e.g., commuting, interstate travel, or leisure), a vehicle style and/or type, a vehicle-to-vehicle communication, or a vehicle-to-infrastructure communication. The information regarding the elements in block **1404** may be further associated with the information regarding the technology in block **1402**. Some technologies may be adapted to utilize information regarding some elements, and some elements may be more relevant to some technologies than to others.

The information regarding the technologies and elements may then be used in evaluating the performance of the autonomous (and/or semi-autonomous) operation features. The performance or sophistication of the autonomous operating features (e.g., autonomous driving software or artificial intelligence) may be determined within a test environment at block **1406**, as described above. The evaluation may include a variety of combinations of technologies and elements, and one or more risk levels or risk profiles may be determined as part of or based upon the evaluation. In some embodiments, the evaluation may include testing the autonomous operation features on a test track or other test facility by installing the features within a test automobile. The test performance may then be supplemented or compared with actual loss experience information relating to the autonomous operating features in actual driving situations recorded at block **1408**. The recorded actual loss experience from block **1408** and/or the evaluated test performance from block **1406** may be used to determine a relative or total risk factor for the autonomous operation features based upon the observed or expected ability of the autonomous operation features to make driving decisions for the autonomous automobile and avoid crashes, collisions, or other losses at block **1410**. Based upon the risk factor determined at block **1410**, one or more premiums or components of premiums for an automobile insurance policy may be determined at block **1412**, as discussed above. These premiums make take into account the risks associated with autonomous operation features or combinations of features, as well as expected environmental or usage conditions, factors, or levels. The premiums determined at block **1412** may then be presented to a customer or potential customer for review, selection, or acceptance and purchase.

Exemplary Methods of Evaluating Impact on Effectiveness

In one aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include: (a) evaluating, via a processor, a vehicle accident avoidance and/or mitigation effectiveness of, and/or associated with, an autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment under real-world driving conditions, the real-world driving conditions including one or more conditions that effect or impact the likelihood, and/or severity, of a vehicle accident or collision; (b) updating, adjusting, and/or generating an auto insurance policy, premium, rate, and/or discount, via the processor, based upon the accident avoidance and/or mitigation effectiveness of the autonomous or semi-autonomous vehicle technology, functionality, system, or equipment for a vehicle equipped with the autonomous or semi-autonomous vehicle feature, technology, system, and/or piece of equipment; (c) presenting (all or a portion of) the updated, adjusted, and/or generated auto insurance policy, premium, rate, and/or discount to an insured, driver, or owner of the vehicle equipped with the autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment for their review, approval, and/or modification on a display screen associated with a computing device; (d) receiving, via the processor, an approval of and/or modification to the auto insurance policy, premium, rate, and/or discount from the insured, driver, or owner of the vehicle equipped with the autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment; and/or (e) updating an auto insurance policy, premium, rate, and/or discount for, and/or then adjusting appropriate amounts to be charged to, the insured, driver, or owner of the vehicle equipped with the autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment based upon the information received from the insured, driver, or owner of the vehicle equipped with the autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment.

The step of (a) evaluating, via the processor, an accident avoidance or mitigation effectiveness of, or associated with, an autonomous or semi-autonomous vehicle technology, functionality, system, or piece of equipment under real-world driving conditions may include: (i) analysis of a plurality of vehicle accidents involving one or more vehicles having the autonomous or semi-autonomous vehicle technology, functionality, system, or piece of equipment, and/or (ii) testing vehicles equipped with the autonomous or semi-autonomous vehicle technology, functionality, system, and/or piece of equipment under real-world conditions and gathering data. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include: (1) updating, adjusting, and/or generating an auto insurance policy, premium, rate, and/or discount, via a processor, based upon and/or taking into consideration: (a) one or more autonomous or semi-autonomous vehicle features, technologies, systems, and/or pieces of equipment; (b) conditions and/or factors impacting the effectiveness of each autonomous or semi-autonomous vehicle feature, technology, system, and/or piece of equipment with respect to accident avoidance and/or mitigation; (c) driver or insured actual characteristics or driving behavior, and/or geographical location associated with the driver, insured, or vehicle; and/or (d) driver or insured actual usage of the one or more autonomous or semi-autonomous vehicle features, technologies, systems, and/or pieces of equipment; (2) presenting on a display (such on a display of a computing device associated with the driver or insured, or a sales agent), all or a portion of, the updated, adjusted, and/or generated auto insurance policy, premium, rate, and/or discount for the driver's or insured's review, approval, and/or modification; (3) receiving and/or accepting the approval and/or modification via wireless communication from the computing device associated with the driver or insured at the processor; and/or (4) processing, handling, and/or updating the auto insurance policy accordingly and/or billing the driver or insured appropriately (via the processor) for the updated or new auto insurance coverage.

The one or more autonomous or semi-autonomous vehicle features, technologies, systems, and/or pieces of equipment may be or include an updated or revised version of computer or processing instructions related to the one or more autonomous or semi-autonomous vehicle features, technologies, systems, and/or pieces of equipment. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

Exemplary Methods of Applying Auto Insurance Risk Factors

In another aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include: (i) estimating a risk factor associated with auto insurance, via a processor, based upon (1) one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment; and/or (2) one or more accident-related conditions or factors that impact the effectiveness of the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment, individually and/or as a group or collectively; (ii) generating, updating, and/or adjusting an auto insurance policy, premium, rate, and/or discount, via the processor, based upon the (a) risk factor associated with auto insurance estimated, and/or (b) actual driving characteristics and/or behaviors (such as typical driving patterns/paths/routes, geographical location, type of trips usually taken, etc.) of a driver, an insured, or an owner of a vehicle with having the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment; (iii) presenting (all or a portion of) the auto insurance policy, premium, rate, and/or discount generated, updated, and/or adjusted, under the direction and/or control of the processor, on a display of a computing device (such as a mobile device associated with the driver, insured, or vehicle owner or an insurance representative) for their review, approval, and/or modification; (iv) receiving, at the processor, such as via wireless communication from the computing device, the auto insurance policy, premium, rate, and/or discount approved by the driver, insured, or vehicle owner; and/or (v) processing, handling, and/or updating the new auto insurance policy, premium, rate, and/or discount via the processor such that the customer (driver, insured, vehicle owner or operator) is billed appropriately for the amount of auto insurance coverage agreed upon or purchased.

An amount or percentage of driving time that the driver or insured uses the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, or pieces of equipment while driving the vehicle may be used to update, adjust, and/or generate the insurance policy,

premium, rate, and/or discount. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include: (1) applying an accident risk factor associated with one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment to an auto insurance policy, premium, rate, discount, reward, etc. for a driver or insured's vehicle having, or equipped with, the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment (via a processor), the risk factor being generated from evaluation of one or more driving and/or accident-related conditions impacting an effectiveness of the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment with respect to accident avoidance and/or mitigation; (2) presenting (under the direction and/or control of the processor) on a display of a computing device (such as a mobile device associated with the driver or insured, or a sales agent) (all and/or portions of) the auto insurance policy, premium, rate, discount, reward, etc. to which the accident risk factor was applied for the driver's or insured's review, approval, and/or modification; (3) receiving and/or accepting the approved and/or modified auto insurance policy, premium, rate, discount, reward, etc. at the processor (such as via wireless communication from the computing device); and/or (4) processing, handling, and/or updating (via the processor) the auto insurance policy for the driver's or insured's vehicle having, or equipped with, the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment accordingly based upon the information received to bill the customer (e.g., driver, insured, or vehicle owner/operator) an appropriate amount for the amount of auto insurance coverage purchased and/or agreed to. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

Exemplary Methods of Evaluating Artificial Intelligence

In another aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include (1) determining, via a processor, the automobile accident avoidance and/or mitigation related effectiveness associated with, or for, a revision or update of computer or processor instructions that direct and/or control one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment (and that may be stored on a non-transitory computer readable media or medium), the effectiveness determination taking into consideration: (a) actual vehicle accident information for accidents involving vehicles equipped with the revision or update of the computer or processor instructions that direct and/or control the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment; and/or (b) physical testing of vehicles equipped with the revision or update of the computer or processor instructions that direct and/or control the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment. The method may also include (2) updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount for a vehicle equipped with the revision or update of computer or processor instructions that direct and/or control the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

In another aspect, a computer-implemented method of updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount may be provided. The method may include: (1) testing an upgrade or update to computer or processor instructions that direct and/or control one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment (and that are stored on a non-transitory computer readable media or medium); (2) determining an increase in accident avoidance or mitigation effectiveness based upon the upgraded or updated computer or processor instructions that direct and/or control the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment; and/or (3) updating, adjusting, and/or generating an insurance policy, premium, rate, and/or discount for a vehicle equipped with the upgraded or updated computer or processor instructions that direct and/or control the one or more autonomous or semi-autonomous vehicle technologies, functionalities, systems, and/or pieces of equipment based upon the increase in accident avoidance or mitigation effectiveness determined. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

Additional Exemplary Methods

In one aspect, a computer-implemented method of evaluating risk of autonomous or semi-autonomous vehicle technology may be provided. The method may include (1) generating, via one or more processors, a virtual test scenario, the virtual test scenario including one or more accident-related factors or conditions; (2) applying, via the one or more processors, the virtual test scenario to a package of computer instructions that instruct a vehicle processor to perform an autonomous or semi-autonomous functionality; (3) analyzing, via the one or more processors, a performance of the autonomous or semi-autonomous functionality under virtual conditions associated with the virtual test scenario; (4) determining, via the one or more processors, an insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the package of computer instructions that instruct the vehicle processor to perform the autonomous or semi-autonomous functionality; and/or (5) generating, updating, or adjusting, via the one or more processors, a premium, rate, discount, reward, or other insurance item associated with an insurance policy for an autonomous or semi-autonomous vehicle employing the package of computer instructions that instruct the vehicle processor to perform the autonomous or semi-autonomous functionality based upon the insurance-based risk of, or associated with, the package of computer instructions. The method may include additional, fewer, or alternate actions, including those discussed elsewhere herein.

For instance, the one or more accident-related factors or conditions of the virtual test scenario may include road, construction, traffic, other vehicle, and/or weather factors or conditions. The virtual test scenario may include a virtual simulation of virtual traffic traveling on a virtual road, and each virtual vehicle traveling on a virtual route at a virtual speed. Determining, via the one or more processors, the insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the package of computer instructions may include determining whether the package of computer instructions made a correct or proper decision given the

road, construction, traffic, other vehicle, and/or weather conditions of the virtual test scenario.

In another aspect, a computer-implemented method of evaluating risk of autonomous or semi-autonomous vehicle technology may be provided. The method may include (1) collecting or receiving, via one or more processors, a virtual log of actual or real-world driving performance of autonomous or semi-autonomous functionality from a vehicle (or smart vehicle controller); (2) determining, via the one or more processors, an insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the autonomous or semi-autonomous functionality from analysis of the virtual log of actual or real-world driving performance of the autonomous or semi-autonomous functionality, respectively; and/or (3) generating, updating, or adjusting, via the one or more processors, a premium, rate, discount, reward, or other insurance item associated with an insurance policy for an autonomous or semi-autonomous vehicle employing the autonomous or semi-autonomous functionality based upon the insurance-based risk of, or associated with, the autonomous or semi-autonomous functionality. The method may include additional, less, or alternate functionality, including that discussed elsewhere herein.

For instance, determining, via the one or more processors, the insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the autonomous or semi-autonomous functionality from analysis of the virtual log of actual or real-world driving performance may include analysis of: (1) decisions that the autonomous or semi-autonomous functionality, or associated computer instructions, made; and/or (2) the environment and/or operating conditions (e.g., road, construction, traffic, and/or weather conditions) under which the decisions were made. Additionally or alternatively, determining, via the one or more processors, the insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the autonomous or semi-autonomous functionality from analysis of the virtual log of actual or real-world driving performance may include analysis of: (1) evasive maneuvers that the autonomous or semi-autonomous functionality, or associated computer instructions, made (or directed the vehicle to perform); and/or (2) the environment and/or operating conditions (e.g., road, construction, traffic, and/or weather conditions) under which the evasive maneuvers were made. Further, determining, via the one or more processors, the insurance-based risk (e.g., a risk of a vehicle accident) of, or associated with, the autonomous or semi-autonomous functionality from analysis of the virtual log of actual or real-world driving performance may include analysis of (1) how the autonomous or semi-autonomous functionality, or associated computer instructions, respond to other drivers on the road maneuvering or changing speed; and/or (2) grading, rating, or otherwise evaluating the responsiveness of the autonomous or semi-autonomous functionality, or associated computer instructions, to other drivers' driving behavior.

In another aspect, a computer-implemented method of evaluating risk of autonomous or semi-autonomous vehicle technology and/or adjusting autonomous or semi-autonomous vehicle technology may be provided. The method may include (1) determining, via one or more processors, an optimum setting for an autonomous or semi-autonomous vehicle technology; (2) detecting, via the one or more processors, that an actual setting for an autonomous or semi-autonomous vehicle system of a vehicle is different than the optimum setting for the autonomous or semi-autonomous vehicle technology; (3) generating a recommendation, via the one or more processors, to change the actual setting for the autonomous or semi-autonomous vehicle system to the optimum setting; and/or (4) causing the recommendation, via the one or more processors, to be presented to a driver of the vehicle having the autonomous or semi-autonomous vehicle system to facilitate the driver changing the actual setting to the optimum setting (or otherwise accepting, or being notified of, an automatic change to the optimum setting). The method may include additional, less, or alternate functionality, including that discussed elsewhere herein.

For instance, the method may include generating or adjusting, via the one or more processors, a premium, rate, discount, or reward of an auto insurance policy for the vehicle based upon the vehicle having or being equipped with the recommendation functionality associated with recommending optimum settings, and/or a percentage of the driver accepting the recommendations provided. The optimum setting that is determined may be determined based upon a setting for the autonomous or semi-autonomous vehicle technology that reduces a likelihood of the vehicle employing the technology having, or being involved in, a vehicle accident or collision. Additionally or alternatively, the optimum setting that is determined may be determined based upon risk associated with the autonomous or semi-autonomous vehicle technology.

In another aspect, a computer-implemented method of determining accident fault may be provided. The method may include (1) receiving or collecting, at or via a remote server (or processor) associated with an insurance provider, performance data associated with autonomous or semi-autonomous vehicle technology for an insured vehicle involved in a vehicle accident, the insured vehicle being insured by an insurance policy issued by the insurance provider; (2) analyzing, at or via the remote server, the performance data received; (3) determining, at or via the remote server, from analysis of the performance data: (a) a first percentage of fault of the vehicle accident for the autonomous or semi-autonomous vehicle technology of the insured vehicle in operation at a time of the vehicle accident; and/or (b) a second percentage of fault of the vehicle accident for an insured driver who was driving the insured vehicle during the vehicle accident; and/or (4) adjusting or updating, at or via the remote server, a premium, rate, discount, or reward of the insurance policy covering the insured vehicle based upon the first and second percentages of fault that are assigned to the insured vehicle and insured driver, respectively, from the analysis of the performance data. The method may include additional, less, or alternate functionality, including that discussed elsewhere herein.

For instance, the method may include further determining, at or via the remote server, from analysis of the performance data: (c) a third percentage of fault of the accident for other vehicles or drivers involved in and/or causing the vehicle accident. The method may include handling, at or via the remote server, an insurance claim for the vehicle accident submitted by the insured using, or based upon, the performance data received associated with the autonomous or semi-autonomous vehicle functionality exhibited during the vehicle accident.

The method may include changing, at or via the remote server, policy coverages (and/or premiums, rates, discounts, etc.) for the insured or the insured vehicle using, or based upon, the performance data received associated with the autonomous or semi-autonomous vehicle functionality exhibited during the vehicle accident. Additionally or alternatively, the method may include changing, at or via the remote server, liability limits or coverages (and/or premi-

ums, rates, discounts, etc.) for the insured or the insured vehicle using, or based upon, the performance data received associated with the autonomous or semi-autonomous vehicle functionality exhibited during the vehicle accident.

Exemplary Computer System for Fault Determination

In one aspect, a computer system for determining fault relating to a vehicle crash may be provided. The computer system may include one or more processors or transceivers configured to: (1) receive vehicle operating data for a vehicle having one or more autonomous operation features for controlling the vehicle, the vehicle operating data being generated and transmitted by an on-board computer or mobile device using wireless communication or data transmission, the vehicle operating data includes: (i) telematics data indicating vehicle operation before and/or during a vehicle crash, including vehicle speed, heading, acceleration, and/or braking; (ii) sensor data from one or more vehicle-mounted sensors associated with the one or more autonomous operation features, the sensor data also indicating a configuration or setting of each autonomous operation feature before and/or during the vehicle crash; and/or (iii) a recorded log of operating data that includes (a) information regarding decisions made by the one or more autonomous operation features, and/or (b) commands sent from the on-board computer to control components to operate the vehicle, before and/or during the vehicle crash; (2) receive an indication of an accident involving the vehicle having one or more autonomous operation features for controlling the vehicle, or otherwise determine that the vehicle has been involved in an accident based upon processor analysis of the (i) telematics data, (ii) sensor data, and/or (iii) recorded log received; and/or (3) determine an allocation of fault for the accident for the one or more autonomous operation features based, at least in part, upon the received (i) telematics data, (ii) sensor data, and/or (iii) recorded log to facilitate vehicle crash reconstruction, such as generating a virtual or computer animated reconstruction of the vehicle crash and/or crash timeline of events.

The one or more processors may analyze the vehicle operating data received to determine an extent of vehicle damage, and/or cost to repair or replace the damage, the vehicle operating data including video, image, and/or audio data. Determining an allocation of fault for the accident for the one or more autonomous operation features may include the one or more processors analyzing data generated by the vehicle-mounted sensors or cameras depicting a vehicle environment, and/or data from the sensors regarding the response of the vehicle to its environment prior to, and/or during, the vehicle crash. Additionally or alternatively, determining an allocation of fault for the accident for the one or more autonomous operation features may include the one or more processors analyzing wireless communications or data transmissions to and from the vehicle, including vehicle-to-vehicle or infrastructure-to-vehicle wireless communications.

The one or more vehicle-mounted sensors may include one or more of a GPS unit, a radar unit, a LIDAR unit, an ultrasonic sensor, an infrared sensor, a camera, an accelerometer, a tachometer, or a speedometer, and may include at least one sensor configured to actively or passively scan the vehicle environment for obstacles, including other vehicles, buildings, and pedestrians. The one or more vehicle-mounted sensors may include three or more of an ignition sensor, an odometer, a system clock, a speedometer, a tachometer, an accelerometer, a gyroscope, a compass, a geolocation or GPS unit, a camera, and a distance sensor.

The one or more processors may be configured to: determine an allocation of fault for the accident based, at least in part, upon whether or not the vehicle was being operated (before or during the vehicle crash) in accordance with optimal use levels (or settings) for a variety of combinations of configurations and settings associated with autonomous operation features based upon road, weather, or traffic conditions at the time of, or prior to, the vehicle crash, the optimal use levels (or settings) being associated with a lowest risk of vehicle crash given the road, weather, or traffic conditions.

The one or more processors may be configured to: (i) determine an optimal use level for a variety of combinations of configurations and settings associated with autonomous operation features based upon current road, weather, or traffic conditions; (ii) compare the optimal use level with a current actual use level for the variety of combinations of configurations and settings associated with autonomous operation features; and/or (iii) if the optimal use level differs from the current actual use level, generate and transmit an electronic notification to the vehicle or vehicle operator's mobile device recommending that the optimal use level be used.

Determining the allocation of fault may include determining, by a processor, a point of impact on the vehicle, and/or an indication of a state of one or more traffic signals before or during the vehicle crash. The one or more processors may be configured to: receive data indicating engagement of the one or more autonomous operation features before the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include the one or more processors analyzing whether the autonomous operation feature failed to take appropriate control actions and/or whether the control signals were ineffective in controlling the vehicle immediately prior to the vehicle crash.

The one or more processors may be configured to receive data indicating engagement or disengagement of the one or more autonomous operation features before the vehicle crash; and determining the allocation of fault for the vehicle crash may include the one or more processors analyzing whether the vehicle had a chance, opportunity, or time to take action to avoid the accident but that action was not taken. The one or more processors and transceivers may be configured to receive data indicating engagement or disengagement of the one or more autonomous operation features before the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include the one or more processors determining that autonomous operation of the vehicle prior to the vehicle crash was no longer feasible due to conditions in the vehicle's environment. Additionally or alternatively, the one or more processors and/or transceivers may be configured to receive data indicating engagement of the one or more autonomous operation features before (and/or during) the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include the one or more processors determining whether the one or more autonomous operation features attempted to return control of the vehicle to the vehicle operator prior to (or during) the vehicle crash, and whether or not an adequate period of time for transition of vehicle control was available prior to the vehicle crash. The computer system may include additional, less, or alternate functionality, including that discussed elsewhere herein.

Exemplary Computer-Implemented Method for Determining Fault

In another aspect, a computer-implemented method for determining fault relating to a vehicle crash may be pro-

vided. The method may include (1) receiving, via one or more processors or an associated transceiver, vehicle operating data for a vehicle having one or more autonomous operation features for controlling the vehicle, the vehicle operating data being generated and transmitted by an on-board computer or mobile device using wireless communication or data transmission. The vehicle operating data may include: (i) telematics data indicating vehicle operation before and during a vehicle crash, including vehicle speed, heading, acceleration, and/or braking; (ii) sensor data from one or more vehicle-mounted sensors associated with the one or more autonomous operation features, the sensor data also indicating a configuration or setting of each autonomous operation feature before, and during, the vehicle crash; and/or (iii) a recorded log of operating data that includes information regarding decisions made by the one or more autonomous operation features, and/or commands sent from the on-board computer to control components to operate the vehicle, before and/or during the vehicle crash. The method may include (2) receiving, via the one or more processors or associated transceiver, an indication of an accident involving the vehicle having one or more autonomous operation features for controlling the vehicle, or otherwise determining, via the one or more processors, that the vehicle has been involved in an accident based upon processor analysis of the (i) telematics data, (ii) sensor data, and/or (iii) recorded log received; and/or (3) determining, by the one or more processors, an allocation of fault for the accident for the one or more autonomous operation features based, at least in part, upon the received (i) telematics data, (ii) sensor data, and/or (iii) recorded log to facilitate vehicle crash reconstruction.

The one or more processors may analyze the vehicle operating data received to determine an extent of vehicle damage, and/or a cost to repair or replace the damage, the vehicle operating data including video and/or image data. Determining, by the one or more processors, an allocation of fault for the accident for the one or more autonomous operation features may include processor analysis of data generated by the vehicle-mounted sensors and/or cameras depicting a vehicle environment, and/or data from the sensors regarding the response of the vehicle to its environment. Additionally, or alternatively, determining, by the one or more processors, an allocation of fault for the accident for the one or more autonomous operation features may include processor analysis of wireless communications or data transmissions to and from the vehicle, including vehicle-to-vehicle or infrastructure-to-vehicle wireless communications.

The one or more vehicle-mounted sensors may include one or more of a GPS unit, a radar unit, a LIDAR unit, an ultrasonic sensor, an infrared sensor, a camera, an accelerometer, a tachometer, or a speedometer, and may include at least one sensor configured to actively or passively scan the vehicle environment for obstacles, including other vehicles, buildings, and pedestrians. The one or more vehicle-mounted sensors may include three or more of the following: an ignition sensor, an odometer, a system clock, a speedometer, a tachometer, an accelerometer, a gyroscope, a compass, a geolocation or GPS unit, a camera, or a distance sensor.

Determining, by the one or more processors, an allocation of fault for the accident based, at least in part, upon whether or not the vehicle was being operated (before and/or during the vehicle crash) in accordance with optimal use levels (or settings) for a variety of combinations of configurations and settings associated with autonomous operation features based upon road, weather, or traffic conditions at the time of, or prior to, the vehicle crash, the optimal use levels (or settings) being associated with a lowest risk of vehicle crash given the current road, weather, or traffic conditions.

The method may include (1) determining, by the one or more processors, an optimal use level for a variety of combinations of configurations and settings associated with autonomous operation features based upon current road, weather, or traffic conditions; (2) comparing the optimal use level with a current actual use level for the variety of combinations of configurations and settings associated with autonomous operation features; and/or (3) if the optimal use level differs from the actual use level, generating and transmitting a notification to the vehicle or vehicle operator's mobile device recommending that the optimal use level be used.

Determining the allocation of fault may include determining, by a processor, a point of impact on the vehicle, and/or an indication of a state of one or more traffic signals before or during the vehicle crash. The method may include receiving, at the one or more processors, data indicating engagement of the one or more autonomous operation features before the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include performing, at the one or more processors, processor analysis of whether the autonomous operation feature failed to take appropriate control actions, and/or whether the control signals were ineffective in controlling the vehicle. The method may include receiving, at the one or more processors, data indicating engagement or disengagement of the one or more autonomous operation features before and/or during the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include performing, at the one or more processors, processor analysis of whether the vehicle had a chance or the time to take action to avoid the accident but that action was not taken.

The method may include receiving, at the one or more processors, data indicating engagement or disengagement of the one or more autonomous operation features before the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include performing, at the one or more processors, processor analysis indicating that autonomous operation was no longer feasible due to conditions in the vehicle's environment. Additionally or alternatively, the method may include receiving, at the one or more processors, data indicating engagement of the one or more autonomous operation features before and/or during the vehicle crash; and/or determining the allocation of fault for the vehicle crash may include performing, at the one or more processors, processor analysis that determines whether the one or more autonomous operation features attempted to return control of the vehicle to the vehicle operator prior to the vehicle crash, and/or whether or not an adequate period of time for transition of control of the vehicle was available prior to the vehicle crash.

The method may include additional, less, or alternate actions, including those discussed elsewhere herein. The method may be implemented via one or more local or remote processors and transceivers, and/or via computer-executable instructions stored on non-transitory computer-readable medium or media.

While the preferred embodiments of the invention have been described, it should be understood that the invention is not so limited and modifications may be made without departing from the invention. The scope of the invention is defined by the appended claims, and all devices that come within the meaning of the claims, either literally or by equivalence, are intended to be embraced therein.

It is therefore intended that the foregoing detailed description be regarded as illustrative rather than limiting, and that it be understood that it is the following claims, including all equivalents, that are intended to define the spirit and scope of this invention.

OTHER MATTERS

Although the text herein sets forth a detailed description of numerous different embodiments, it should be understood that the legal scope of the invention is defined by the words of the claims set forth at the end of this patent. The detailed description is to be construed as exemplary only and does not describe every possible embodiment, as describing every possible embodiment would be impractical, if not impossible. One could implement numerous alternate embodiments, using either current technology or technology developed after the filing date of this patent, which would still fall within the scope of the claims.

It should also be understood that, unless a term is expressly defined in this patent using the sentence "As used herein, the term '_____' is hereby defined to mean . . . " or a similar sentence, there is no intent to limit the meaning of that term, either expressly or by implication, beyond its plain or ordinary meaning, and such term should not be interpreted to be limited in scope based upon any statement made in any section of this patent (other than the language of the claims). To the extent that any term recited in the claims at the end of this disclosure is referred to in this disclosure in a manner consistent with a single meaning, that is done for sake of clarity only so as to not confuse the reader, and it is not intended that such claim term be limited, by implication or otherwise, to that single meaning. Finally, unless a claim element is defined by reciting the word "means" and a function without the recital of any structure, it is not intended that the scope of any claim element be interpreted based upon the application of 35 U.S.C. § 112(f).

Throughout this specification, plural instances may implement components, operations, or structures described as a single instance. Although individual operations of one or more methods are illustrated and described as separate operations, one or more of the individual operations may be performed concurrently, and nothing requires that the operations be performed in the order illustrated. Structures and functionality presented as separate components in example configurations may be implemented as a combined structure or component. Similarly, structures and functionality presented as a single component may be implemented as separate components. These and other variations, modifications, additions, and improvements fall within the scope of the subject matter herein.

Additionally, certain embodiments are described herein as including logic or a number of routines, subroutines, applications, or instructions. These may constitute either software (code embodied on a non-transitory, tangible machine-readable medium) or hardware. In hardware, the routines, etc., are tangible units capable of performing certain operations and may be configured or arranged in a certain manner. In example embodiments, one or more computer systems (e.g., a standalone, client or server computer system) or one or more hardware modules of a computer system (e.g., a processor or a group of processors) may be configured by software (e.g., an application or application portion) as a hardware module that operates to perform certain operations as described herein.

In various embodiments, a hardware module may be implemented mechanically or electronically. For example, a hardware module may comprise dedicated circuitry or logic that is permanently configured (e.g., as a special-purpose processor, such as a field programmable gate array (FPGA) or an application-specific integrated circuit (ASIC) to perform certain operations. A hardware module may also comprise programmable logic or circuitry (e.g., as encompassed within a general-purpose processor or other programmable processor) that is temporarily configured by software to perform certain operations. It will be appreciated that the decision to implement a hardware module mechanically, in dedicated and permanently configured circuitry, or in temporarily configured circuitry (e.g., configured by software) may be driven by cost and time considerations.

Accordingly, the term "hardware" should be understood to encompass a tangible entity, be that an entity that is physically constructed, permanently configured (e.g., hardwired), or temporarily configured (e.g., programmed) to operate in a certain manner or to perform certain operations described herein. Considering embodiments in which hardware is temporarily configured (e.g., programmed), the hardware need not be configured or instantiated at any one instance in time. Software may accordingly configure a processor, for example, to constitute a particular hardware module at one instance of time and to constitute a different hardware module at a different instance of time. Hardware elements can provide information to, and receive information from, other hardware elements. Accordingly, the described hardware may be regarded as being communicatively coupled.

The various operations of example methods described herein may be performed, at least partially, by one or more processors that are temporarily configured (e.g., by software) or permanently configured to perform the relevant operations. Whether temporarily or permanently configured, such processors may constitute processor-implemented modules that operate to perform one or more operations or functions. The modules referred to herein may, in some example embodiments, comprise processor-implemented modules. Similarly, the methods or routines described herein may be at least partially processor-implemented. The performance of certain of the operations may be distributed among the one or more processors, not only residing within a single machine, but deployed across a number of machines. In some example embodiments, the processor or processors may be located in a single location (e.g., within a home environment, an office environment or as a server farm), while in other embodiments the processors may be distributed across a number of locations.

Unless specifically stated otherwise, discussions herein using words such as "processing," "computing," "calculating," "determining," "presenting," "displaying," or the like may refer to actions or processes of a machine (e.g., a computer) that manipulates or transforms data represented as physical (e.g., electronic, magnetic, or optical) quantities within one or more memories (e.g., volatile memory, non-volatile memory, or a combination thereof), registers, or other machine components that receive, store, transmit, or display information. As used herein any reference to "one embodiment" or "an embodiment" means that a particular element, feature, structure, or characteristic described in connection with the embodiment may be included in at least one embodiment. The appearances of the phrase "in one embodiment" in various places in the specification are not necessarily all referring to the same embodiment. Some embodiments may be described using the expression "coupled" and "connected" along with their derivatives. For example, some embodiments may be described using the

term "coupled" to indicate that two or more elements are in direct physical or electrical contact. The term "coupled," however, may also mean that two or more elements are not in direct contact with each other, but yet still co-operate or interact with each other. The embodiments are not limited in this context.

As used herein, the terms "comprises," "comprising," "includes," "including," "has," "having" or any other variation thereof, are intended to cover a non-exclusive inclusion. For example, a process, method, article, or apparatus that comprises a list of elements is not necessarily limited to only those elements but may include other elements not expressly listed or inherent to such process, method, article, or apparatus. Further, unless expressly stated to the contrary, "or" refers to an inclusive or and not to an exclusive or. In addition, use of the "a" or "an" are employed to describe elements and components of the embodiments herein. This is done merely for convenience and to give a general sense of the description. In this description, and the claims that follow, the singular also includes the plural unless it is obvious that it is meant otherwise. This detailed description is to be construed as exemplary only and does not describe every possible embodiment, as describing every possible embodiment would be impractical, if not impossible. One could implement numerous alternate embodiments, using either current technology or technology developed after the filing date of this application.

Upon reading this disclosure, those of skill in the art will appreciate still additional alternative structural and functional designs for system and a method for assigning mobile device data to a vehicle through the disclosed principles herein. Thus, while particular embodiments and applications have been illustrated and described, it is to be understood that the disclosed embodiments are not limited to the precise construction and components disclosed herein. Various modifications, changes and variations, which will be apparent to those skilled in the art, may be made in the arrangement, operation and details of the method and apparatus disclosed herein without departing from the spirit and scope defined in the appended claims.

The particular features, structures, or characteristics of any specific embodiment may be combined in any suitable manner and in any suitable combination with one or more other embodiments, including the use of selected features without corresponding use of other features. In addition, many modifications may be made to adapt a particular application, situation or material to the essential scope and spirit of the present invention. It is to be understood that other variations and modifications of the embodiments of the present invention described and illustrated herein are possible in light of the teachings herein and are to be considered part of the spirit and scope of the present invention.

What is claimed is:

1. A computer system for reconstructing a vehicle crash, the computer system comprising one or more processors, one or more transceivers coupled to the one or more processors, and one or more program memories coupled to the one or more processors and storing executable instructions that cause the one or more processors to:

receive vehicle operating data for a vehicle having one or more autonomous operation features for controlling the vehicle, the vehicle operating data being generated and transmitted by an on-board computer or mobile device using wireless communication or data transmission, wherein the vehicle operating data includes:

(i) sensor data from one or more vehicle-mounted sensors associated with the one or more autonomous operation features, the sensor data also indicating a configuration or setting of each autonomous operation feature before and during the vehicle crash; and

(ii) a recorded log of decisions made by the one or more autonomous operation features, and commands sent from the on-board computer to control components to operate the vehicle, before and during the vehicle crash;

receive an indication of an accident involving the vehicle, or otherwise determine that the vehicle has been involved in the accident based upon processor analysis of the (i) sensor data and (ii) recorded log received;

generate a crash reconstruction representing a sequence of events involved in the accident by automatically determining, for each of a plurality of times in the sequence of events, each of the following: (i) a location of the vehicle based upon the sensor data, (ii) a location of an obstruction involved in the accident based upon the sensor data, and (iii) a movement of the vehicle based upon the decisions in the recorded log;

determine an allocation of fault for the accident for each of the one or more autonomous operation features based at least in part upon the crash reconstruction; and

cause one or more of the following actions to be performed based upon the determined total risk level: adjust an insurance policy associated with the vehicle, determine a coverage level associated with the insurance policy, present information regarding the determined total risk level to a reviewer via a display of a reviewer computing device to verify the determined total risk level, or present the determination to a customer via a display of a customer computing device for review of an adjustment to the insurance policy associated with the vehicle.

2. The computer system of claim **1**, wherein the one or more processors analyze the vehicle operating data received to determine an extent of vehicle damage, or a cost to repair the damage or replace part or all of the vehicle, the vehicle operating data including video or image data.

3. The computer system of claim **1**, wherein determining an allocation of fault for the accident for the one or more autonomous operation features further includes the one or more processors analyzing data generated by the vehicle-mounted sensors or cameras depicting a vehicle environment and data from the sensors regarding the response of the vehicle to its environment prior to, or during, the vehicle crash.

4. The computer system of claim **1**, wherein determining an allocation of fault for the accident for the one or more autonomous operation features further includes the one or more processors analyzing wireless communications or data transmissions to and from the vehicle, including vehicle-to-vehicle or infrastructure-to-vehicle communications.

5. The computer system of claim **1**, wherein the one or more vehicle-mounted sensors include one or more of a GPS (Global Positioning System) unit, a radar unit, a LIDAR unit, an ultrasonic sensor, an infrared sensor, a camera, an accelerometer, a tachometer, or a speedometer, and at least one sensor is configured to actively or passively scan a vehicle environment of the vehicle for obstacles, including other vehicles, buildings, and pedestrians.

6. The computer system of claim **1**, wherein the one or more vehicle-mounted sensors include one or more of an ignition sensor, an odometer, a system clock, a speedometer, a tachometer, an accelerometer, a gyroscope, a compass, a geolocation or GPS unit, a camera, or a distance sensor.

7. The computer system of claim 1, the one or more processors further configured to:

determine an allocation of fault for the accident based, at least in part, upon whether or not the vehicle was being operated in accordance with optimal use levels for a variety of combinations of configurations and settings associated with the one or more autonomous operation features based upon road, weather, or traffic conditions at the time of, or prior to, the vehicle crash, the optimal use levels being associated with a lowest risk of vehicle crash.

8. The computer system of claim 1, the one or more processors further configured to:

determine an optimal use level for a variety of combinations of configurations and settings associated with the one or more autonomous operation features based upon current road, weather, or traffic conditions;

compare the optimal use level with a current actual use level for the variety of combinations of configurations and settings associated with the one or more autonomous operation features; and

if the optimal use level differs from the current actual use level, generate and transmit an electronic notification to the vehicle or vehicle operator's mobile device recommending that the optimal use level be used.

9. The computer system of claim 1, wherein determining the allocation of fault further includes determining, by a processor, a point of impact on the vehicle, or an indication of a state of one or more traffic signals before, or during, the vehicle crash.

10. The computer system of claim 1, the one or more processors further configured to receive data indicating engagement of at least one of the one or more autonomous operation features before the vehicle crash; and

determining the allocation of fault for the vehicle crash includes the one or more processors analyzing whether the autonomous operation feature failed to take appropriate control actions or whether control signals were ineffective in controlling the vehicle immediately prior to the vehicle crash.

11. The computer system of claim 1, the one or more processors further configured to receive data indicating engagement or disengagement of the one or more autonomous operation features before the vehicle crash; and

wherein determining the allocation of fault for the vehicle crash includes the one or more processors analyzing whether the vehicle had time to take action to avoid the accident but that action was not taken.

12. The computer system of claim 1, the one or more processors and transceivers further configured to receive data indicating engagement or disengagement of the one or more autonomous operation features before the vehicle crash; and

wherein determining the allocation of fault for the vehicle crash includes the one or more processors determining that autonomous operation of the vehicle prior to the vehicle crash was no longer feasible due to conditions in a vehicle environment of the vehicle.

13. The computer system of claim 1, the one or more processors and transceivers configured to receive data indicating engagement of the one or more autonomous operation features before the vehicle crash; and

wherein determining the allocation of fault for the vehicle crash includes the one or more processors determining whether the one or more autonomous operation features attempted to return control of the vehicle to the vehicle operator prior to the vehicle crash and whether or not an adequate period of time for transition was available prior to the vehicle crash.

14. The computer system of claim 1, wherein the vehicle operating data received via wireless communication further includes telematics data indicating vehicle operation before and during a vehicle crash, including vehicle speed, heading, acceleration, and braking; and

the one or more processors are configured to (1) determine that the vehicle has been involved in the accident based upon processor analysis of the (i) sensor data, (ii) recorded log received, and (iii) telematics data; and (2) determine an allocation of fault for the accident for the one or more autonomous operation features based at least in part upon the received (i) sensor data, (ii) recorded log received, and (iii) telematics data.

15. A computer-implemented method for reconstructing a vehicle crash, comprising:

receiving, via one or more processors or an associated transceiver, vehicle operating data for a vehicle having one or more autonomous operation features for controlling the vehicle, the vehicle operating data being generated and transmitted by an on-board computer or mobile device using wireless communication or data transmission, wherein the vehicle operating data includes:

(i) sensor data from one or more vehicle-mounted sensors associated with the one or more autonomous operation features, the sensor data also indicating a configuration or setting of each autonomous operation feature before and during the vehicle crash; and

(ii) a recorded log of decisions made by the one or more autonomous operation features, and commands sent from the on-board computer to control components to operate the vehicle, before and during the vehicle crash;

receiving, via the one or more processors or associated transceiver, an indication of an accident involving the vehicle, or otherwise determining, via the one or more processors, that the vehicle has been involved in the accident based upon processor analysis of the (i) sensor data, and (ii) recorded log received;

generating, by the one or more processors, a crash reconstruction representing a sequence of events involved in the accident by automatically determining, for each of a plurality of times in the sequence of events, each of the following: (i) a location of the vehicle based upon the sensor data, (ii) a location of an obstruction involved in the accident based upon the sensor data, and (iii) a movement of the vehicle based upon the decisions in the recorded log;

determining, by the one or more processors, an allocation of fault for each of the accident for the one or more autonomous operation features based at least in part upon the crash reconstruction; and

causing, by the one or more processors, one or more of the following actions to be performed based upon the determined total risk level: adjust an insurance policy associated with the vehicle, determine a coverage level associated with the insurance policy, present information regarding the determined total risk level to a reviewer via a display of a reviewer computing device to verify the determined total risk level, or present the determination to a customer via a display of a customer computing device for review of an adjustment to the insurance policy associated with the vehicle.

16. The computer-implemented method of claim **15**, wherein, the one or more processors analyze the vehicle operating data received to determine an extent of vehicle damage, or cost to repair the damage or replace part or all of the vehicle, the vehicle operating data including video or image data.

17. The computer-implemented method of claim **15**, wherein determining, by the one or more processors, an allocation of fault for the accident for the one or more autonomous operation features further includes processor analysis of data generated by the vehicle-mounted sensors or cameras depicting a vehicle environment and data from the sensors regarding the response of the vehicle to its environment prior to, and during, the vehicle crash.

18. The computer-implemented method of claim **15**, wherein determining, by the one or more processors, an allocation of fault for the accident for the one or more autonomous operation features further includes processor analysis of wireless communications or data transmissions to and from the vehicle, including vehicle-to-vehicle or infrastructure-to-vehicle communications.

19. The computer-implemented method of claim **15**, the method comprising:

determining, by the one or more processors, an allocation of fault for the accident based, at least in part, upon whether or not the vehicle being operated in accordance with optimal use levels for a variety of combinations of configurations and settings associated with the one or more autonomous operation features based upon road, weather, or traffic conditions at the time of, or prior to, the vehicle crash, the optimal use levels being associated with a lowest risk of vehicle crash.

20. The computer-implemented method of claim **15**, the method comprising:

determining, by the one or more processors, an optimal use level for a variety of combinations of configurations and settings associated with the one or more autonomous operation features based upon current road, weather, or traffic conditions;

comparing the optimal use level with a current actual use level for the variety of combinations of configurations and settings associated with the one or more autonomous operation features; and if the optimal use level differs from the current actual use level, generating and transmitting a notification to the vehicle or vehicle operator's mobile device recommending that the optimal use level be used.

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