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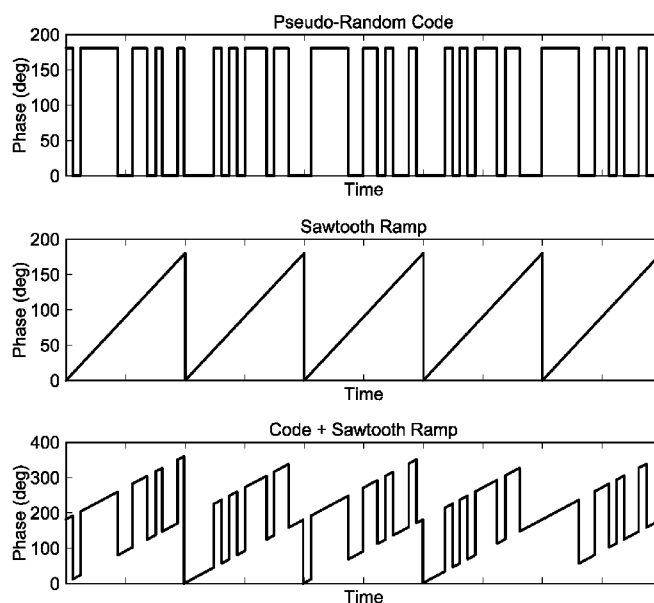


FIG. 7A

(57) Abstract: Systems and methods for detection of distances, velocities, and characteristics of a surface measured by a lidar sensor are described herein.



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PERCEPTION SYSTEMS FOR USE IN AUTONOMOUSLY CONTROLLING SYSTEMS

INCORPORATION BY REFERENCE TO ANY PRIORITY APPLICATIONS

[0001] Any and all applications for which a foreign or domestic priority claim is identified in the Application Data Sheet as filed with the present application are hereby incorporated by reference under 37 CFR 1.57.

[0002] This application claims priority benefit under 35 U.S.C. § 119(e) to U.S. Provisional Patent Application Serial No. 62/692,417 filed 29 June 2018 and entitled “PERCEPTION SYSTEMS FOR USE IN AUTONOMOUSLY CONTROLLING SYSTEMS”, and U.S. Provisional Patent Application Serial No. 62/850,933 filed 21 May 2019 and entitled “SYSTEMS AND METHODS FOR MEASURING CHARACTERISTICS OF AN OBJECT AT DISTANCE”, the entirety of each hereby expressly incorporated by reference herein.

BACKGROUND

Field

[0003] One technical field of the present disclosure is sensing systems, and more specifically, to perception systems for use in autonomously controlling systems.

Description of the Related Art

[0004] Autonomous systems require some sensing of their environment to provide information and feedback to the system. For example, many designs for autonomous vehicles use light imaging, detection, and ranging (“lidar”) to measure their surroundings, identify neighboring objects, and determine the location and velocity of said objects. However, current lidar devices have a range of problems including low accuracy, high cost, slow speed, and high interference from external sources. Thus, improved lidar devices are desirable not only in the field of autonomous systems, but also in other fields of measurement.

SUMMARY

[0005] The techniques described herein provide comprehensive sensing solutions for autonomy applications, such as computer-assisted driving of automobiles, and other sensing applications. These techniques can be applied in numerous technologies and systems, including, but not limited to, personal and commercial ground transportation, avionics,

robotics, industrial manufacturing, agriculture, mining, and mapping. The system may consist of a constellation, grouping, or collection of probes (including sensors or other input or sensing devices) to sense the environment and algorithms to interpret the data.

[0006] An example system is depicted in Figure 1, in the context of a perception system for an automobile 1 with a central unit 10 and a plurality of probes 20 connected to the central unit 10. Each of the probes 20 can include one or more sensors. This system combines a set of features, including but not limited to the following:

- **Multimodality.** Some or all of the sensors included in the constellation of sensors (sometimes called a super-sensor) contain multiple sensing modalities complementing and reinforcing each other, which may include, but are not limited to: lidar, radar, camera, gyroscope, kinematic and non-kinematic position sensors, kinematic and non-kinematic velocity sensors, global positioning systems (GPS), and ultrasonic sensors.

- **Concurrent.** The different sensing modalities can be deeply integrated into a single super-sensor, both at the hardware and the software levels. In some embodiments, concurrent sensing by each of one or more super-sensors, using the techniques described herein, may replace multimodality fusion (which may otherwise be required to combine or use simultaneously data obtained from multiple different sensors) to boost detection confidence (e.g., how confident the system is that it is detecting objects in an environment being sensed by the sensors) and measurement finesse.

- **Intelligent.** In some embodiments, the sensors intelligently allocate their resources according to the scene. For example, areas of higher importance, such as those in the direction of travel, may be prioritized in allocation of resources. In some embodiments, pre-processing algorithms interpret the data and optimize the sensor's configuration on-the-fly.

- **Flexible.** In some embodiments, probing and sensing are physically separated for better flexibility and reliability.

- **Centralized.** In some embodiments, a subset of or the entire constellation of sensors operates as a single system. Signals from some or all the probes and the sensing modalities may converge into one single representation of the environment, which is then used to perceive objects in the environment.

- **Perceptive.** In some embodiments, high level semantics accompany raw 3D maps for use in interpreting the environment. A dedicated computational engine may process the data through perception algorithms such as clustering, classification, and tracking.

- **Open.** In some embodiments, the perception system can allow for multiple, different algorithms to run thereon, such as those discussed herein and elsewhere.

[0007] Figure 2 depicts a block diagram of an example system. As shown, the central unit 10 can communicate with a probe 20 potentially having a variety of different sensors. The central unit 10 can include optics/electronics components that can receive optical or electronic signals from the probe 20 and provide initial processing of those signals. The optics/electronics components can also control the sensors, such as by providing instructions to measure in a particular way or in a particular area, or alternatively to provide necessary inputs such as a beam of light to optical sensors or power to electrical actuators. The central unit 10 can additionally include analog/digital converters to transform the signals from the sensors into digital form, and to transform digital instructions into analog inputs to drive various components at the probe 20. The analog/digital converters can communicate with a sensing engine, which can generate 3D maps and other representations of data received from the probes 20. The sensing engine can also generate digital instructions for the probes 20, which can then be converted to analog form by the converters. The central unit 10 can additionally include a perception engine that can provide a higher level analysis of the data provided by the probes 20. For example, the perception engine can use 3D maps and images generated by the sensing engine to identify other automobiles on a road, lane markings, pedestrians, and other features. These meaningful semantics can then be provided to other components, such as a separate route-planning system on an autonomous vehicle.

[0008] As noted above, the perception system can include a lidar sensor 100. A block diagram of a lidar subsystem, including a lidar sensor, is depicted in Figure 3. As shown, the lidar sensor can include a laser configured to output a beam of light. The laser can be, but is not limited to, a laser diode, quantum cascade laser, optical fiber laser, or distributed feedback laser. The laser can be connected or otherwise be in optical communication with optical fibers in the form of single-mode fibers, multimode fibers, tapered multimode fiber bundles, photonic crystal fibers, single mode fiber bundles, and photonic lantern multiplexers. Optical coupling in and out of the fiber can include a collimator in the case of a single fiber

output, or a lenslet array in the case of fiber bundles or photonic lanterns. Further, a beam emitted from the lidar sensor can be steered using electro-mechanical or electro-optical techniques. A rotatable mirror can optionally be used, having one or two axes of rotation and being controllable by a motor or other device. A rotatable polygonal mirror can also optionally be used for simultaneous 2-axis beam rastering. Using these fibers, fiber couplers (including dielectric mirrors, fiber coupler cubes, fiber-optic couplers, and metal-coated mirrors), waveguides, and/or other optical elements such as mirrors and lenses, the beam of light from a single laser can optionally be steered to the plurality of probes depicted in Figure 1, and similarly the reflected beams resulting from that beam of light and reflected to those probes can optionally be routed back to the same central unit 10 for processing. Thus, as shown, the central unit 10 can include a plurality of transceivers that communicate with various probes 20. Even further, multiple probes 20 can optionally be connected to a single transceiver, allowing for probe multiplexing signals collected simultaneously from different moments in time, different directions in space, and also from multiple probes.

[0009] A variety of different lidar systems can be used with the above-described systems. For example, a lidar sensor can include an optical sensor, a laser, at least one phase modulator, and a processor. The optical sensor can be configured to produce a signal based at least on receiving one or more beams of light. A laser can be configured to emit an initial beam of light, a first portion of that light being directed into the environment, and an internal portion being directed to the optical sensor. The optical sensor can be configured to receive both the internal portion and a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment. The phase modulator can be configured to modulate a phase of the first portion of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of the first portion of the initial beam of light prior to it being directed into the environment. The processor can be configured to receive signals from the optical sensor and to identify the first reflected beam of light as having resulted from the first portion of the initial beam of light based at least on detecting the unique code. The processor can be further configured to determine a distance to the first point of reflection based at least on the first reflected beam of light and the internal portion of the initial beam of light.

[0010] In a further embodiment, a lidar sensor can include an optical sensor, a laser, and a processor. The optical sensor can be configured to produce a signal based at least on receiving one or more beams of light. The laser can be configured to emit an initial beam of light, with a first portion of the initial beam of light being directed into the environment in a first direction, a second portion of the initial beam of light being directed into the environment in a second direction different from the first direction, and an internal portion of the initial beam of light being directed to the optical sensor. The optical sensor can be configured to receive each of the internal portion of the initial beam of light, a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment, and a second reflected beam of light resulting from the second portion of the initial beam of light being reflected at a second point of reflection in the environment. The processor can be configured to receive signals from the optical sensor and to identify the first reflected beam of light as having resulted from the first portion of the initial beam of light and the second reflected beam as having resulted from the second portion of the initial beam of light. The processor can further be configured to determine distances to the first and second points of reflection based at least on the first and second reflected beams of light and the internal portion of the initial beam of light. The time between direction of the first portion of the initial beam of light into the environment and reception of the first reflected beam of light by the optical sensor overlaps with the time between direction of the second portion of the initial beam of light into the environment and reception of the second reflected beam of light by the same optical sensor.

[0011] In a further embodiment, a lidar sensor can include an optical sensor, a laser, and a processor. The optical sensor can be configured to produce signals based at least on receiving one or more beams of light. The laser can be configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor. The optical sensor can be configured to receive both the internal portion of the initial beam of light and a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment. The processor can be configured to receive signals from the optical sensor and identify the first reflected beam of light as having resulted from the first portion of the initial beam of light based on the signals. The processor

can also be configured to determine a distance to the point of reflection based at least on the first reflected beam of light and the internal portion of the initial beam of light. Even further, the processor can be configured to determine a radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the first reflected beam of light and the internal portion of the initial beam of light. Even further, the lidar sensor can be configured to determine a lateral velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift of the first reflected beam of light and the determined radial velocity.

[0012] In a further embodiment, a lidar sensor can include a laser, a first fiber coupler, an optical synthesizer circuit, a transmitter, a receiver, a second fiber coupler, and an optical sensor. The laser can be configured to emit an initial beam of light, and the first fiber coupler can be in optical communication with the laser to receive and divide the initial beam of light into a transmitted portion and an internal portion. The optical synthesizer circuit can be in optical communication with the first fiber coupler to receive the transmitted portion of the initial beam of light from the first fiber coupler and to adjust the phase of the transmitted portion of the initial beam of light. The transmitter can be in optical communication with the optical synthesizer circuit to receive the transmitted portion with an adjusted phase from the optical synthesizer circuit and direct the transmitted portion into the environment. The receiver can be configured to receive the reflected beam of light from the environment resulting from the transmitted portion of the initial beam of light. The second fiber coupler can be in optical communication with the receiver and the first fiber coupler to combine the reflected beam of light and the internal portion of the initial beam of light into a combined beam of light. The optical sensor can be in optical communication with the second fiber coupler to receive the second beam of light.

[0013] In a further embodiment, a method of measuring distance can be provided. A beam of light can be split into a transmitted portion and an internal portion. The phase of the transmitted portion can be modulated over a period of time to embed a unique time-dependent code into the transmitted portion. The transmitted portion with the modulated phase can then be directed into the environment, and a reflected beam resulting from the transmitted portion being directed into the environment can be received. The reflected beam can be identified as resulting from the transmitted portion being directed into the environment at least by detecting

the unique code. A distance to a point of reflection can then be estimated using the reflected beam and the internal portion.

[0014] In a further embodiment, a method of simultaneously measuring multiple distances can be provided. A beam of light can be split into a first transmitted portion, a second transmitted portion, and an internal portion. The first and second transmitted portions can be directed into the environment in different directions. Reflected beams resulting from the first and second transmitted portions being directed into the environment can then be received at a single optical sensor. The reflected beams can be identified as resulting from the first and second transmitted portions being directed into the environment, and a distance to the points of reflection can be estimated using the reflected beams and the internal portion. The time between the directing of the first transmitted portion into the environment and receiving the reflected beam resulting from the first transmitted portion can overlap with the time between the directing of the second transmitted portion into the environment and receiving the reflected beam resulting from the second transmitted portion.

[0015] In a further embodiment, a method of operating a lidar sensor to measure a distance to an object and a velocity of the object can be provided. A beam of light can be split into a transmitted portion and an internal portion, and the transmitted portion can be directed into the environment. A reflected beam resulting from the transmitted portion being directed into the environment can be received. A distance to a point of reflection can be estimated using the reflected beam and the internal portion. Additionally, a radial velocity of the point of reflection relative to the lidar sensor can be estimated, based at least on a time derivative of a difference in phases of the light field between the reflected beam of light and the internal portion. Further, a lateral velocity of the point of reflection relative to the lidar sensor can be estimated based at least on a Doppler shift of the reflected beam and the determined radial velocity.

[0016] In a further embodiment, a lidar sensor can include an optical sensor, a laser, and a processor. The optical sensor can be configured to produce signals based at least on receiving one or more beams of light. The laser can be configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor. The optical sensor can also be configured to receive both the internal portion of the initial beam of light

and a reflected beam of light resulting from the first portion of the initial beam of light being reflected at a point of reflection in the environment. The processor can be configured to receive signals from the optical sensor and identify the reflected beam of light as having resulted from the first portion of the initial beam of light. The processor can be further configured to determine: a distance to the point of reflection based at least on the reflected beam of light and the internal portion of the initial beam of light, a radial velocity of the point of reflection relative to the lidar sensor, and a lateral velocity of the point of reflection relative to the lidar sensor based at least on a sidelobe width of the reflected beam.

[0017] In a further embodiment, a method of operating a lidar sensor to measure a distance to an object and a velocity of the object is provided. A beam of light can be split into a transmitted portion and an internal portion. The transmitted portion can be directed into the environment. A reflected beam, resulting from the transmitted portion being directed into the environment, can be received. The following features can then be determined: a distance to a point of reflection using the reflected beam and the internal portion, a radial velocity of the point of reflection relative to the lidar sensor, and a lateral velocity of the point of reflection relative to the lidar sensor based at least on a sidelobe width of the reflected beam.

[0018] In a further embodiment, a lidar sensor can include an optical sensor, a laser, and a processor. The optical sensor can be configured to produce signals based at least on receiving one or more beams of light. The laser can be configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor. The optical sensor can be configured to receive both the internal portion of the initial beam of light and a reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment. The processor can be configured to receive signals from the optical sensor and identify the reflected beam of light as having resulted from the first portion of the initial beam of light. The processor can be further configured to determine: a distance to the point of reflection based at least on the reflected beam of light and the internal portion of the initial beam of light, and one or more characteristics of a surface of an object at the point of reflection based at least on a spectral analysis of the reflected beam of light.

[0019] In a further embodiment, a method of operating a lidar sensor to measure a distance to an object and a velocity of the object can be provided. A beam of light can be split into a transmitted portion and an internal portion. The transmitted portion can be directed into the environment. A reflected beam, resulting from the transmitted portion being directed into the environment, can be received. The following features can then be determined: a distance to a point of reflection using the reflected beam and the internal portion, a radial velocity of the point of reflection relative to the lidar sensor, and one or more characteristics of a surface at the point of reflection based at least on a spectral analysis of the reflected beam.

BRIEF DESCRIPTION OF THE DRAWINGS

[0020] Further objects, features and advantages of the disclosure will become apparent from the following detailed description taken in conjunction with the accompanying figures showing illustrative embodiments, in which:

[0021] Figure 1 is a system diagram of an embodiment perception system.

[0022] Figure 2 is a block diagram of an embodiment perception system.

[0023] Figure 3 is a block diagram of an embodiment lidar system.

[0024] Figure 4A depicts a lidar system using direct detection.

[0025] Figure 4B depicts a lidar system using coherent detection.

[0026] Figures 5A-5H depict various lidar systems using coherent detection and superheterodyne techniques.

[0027] Figures 6A-6C depict various lidar systems using coherent detection and superhomodyne techniques.

[0028] Figures 7A and 7B depict codes that can be embedded into a phase of a beam of light.

[0029] Figure 8 depicts a computer system.

[0030] Figure 9 depicts a method for estimating a distance using a lidar sensor.

[0031] Figure 10 depicts a method for detecting multiple distances simultaneously.

[0032] Figure 11 depicts a method for measuring a distance, radial velocity, and lateral velocity.

[0033] Figures 12A-12C depict power spectra for different lateral velocities on a target towel.

[0034] Figure 13 depicts a computer-generated spectrum detecting a lateral velocity.

[0035] Figures 14A-14D depict power spectra for different target materials at a lateral velocity of 50 meters per second.

DETAILED DESCRIPTION

[0036] Figures 4A and 4B depict lidar systems using direct detection and coherent detection. Lidars detect objects by actively illuminating the environment and measuring the intensity of the light reflected by any encountered surfaces. Sensing techniques fall into two main camps: direct and coherent (sometimes called “indirect”). Direct detection techniques (depicted in Figure 4A) may measure the intensity of the reflected light directly with an optical sensor (such as a photodiode, photoreceiver, or photodetector). Coherent detection techniques (depicted in Figure 4B) may use an indirect method: mixing together the received light with part of the transmitted light on the optical sensor and measuring the interference between them with the optical sensor.

[0037] In some embodiments, coherent detection provides the following advantages over direct detection:

- **Noiseless signal amplification.** Direct and coherent detection often respond to background and electronic noise in very different ways. In direct detection, amplifying the signal often also amplifies the noise, without improving the signal-to-noise ratio (SNR). In contrast, coherent detection is often capable of amplifying the signal alone and improving the SNR.

- **Dynamic range.** Direct and coherent detection differ also by their dynamic range. In direct detection the signal is often directly proportional to the intensity of the received light and falls with the inverse of the squared distance of the object. In coherent detection the signal is often directly proportional to the amplitude of the received intensity and falls with only the inverse of the object’s distance.

[0038] Unlike some coherent detection technologies based on frequency modulation, some lidar systems described herein detect the range of objects by measuring the phase of the reflected light. They can potentially do so by solving one or more key problems that rendered coherent detection methods not applicable before: 1) the intrinsic ambiguity in mapping the phase of the light into distance; 2) the instability of the phase of the light upon

reflection from a rough surface; 3) the Doppler shift in the frequency of the light reflected by moving objects; 4) the narrow acceptance angle of the receiver; 5) the intrinsic indistinguishability of signals coming from different directions; 6) the laser's phase fluctuations due to noise.

[0039] (1) Phase ambiguity. The relative phase $\Delta\phi$ between the transmitted and the received waves (having a wavelength λ) is directly proportional to the round trip distance to the object $2L$:

$$\Delta\phi = \frac{4\pi}{\lambda} L$$

[0040] In principle L could be obtained by measuring $\Delta\phi$ and inverting this relationship. However, the phase increases by 360° degrees when the light travels through a distance equal to its wavelength (for example, approximately one micrometer). After that it wraps back to zero such that:

$$\Delta\phi = \frac{4\pi}{\lambda} (L \bmod \lambda)$$

[0041] The phase of the light has effectively only “short-term memory” of the distance traveled and by itself it could not be used to measure distances longer than the light’s wavelength.

[0042] (2) Phase instability. The phase of the light reflected by rough surfaces changes abruptly if the object moves under the illuminating light even slightly. That makes the phase measurement not practical in many situations.

[0043] (3) Doppler uncertainty. The velocity (v) of an object makes the frequency (f) of the reflected light increase or decrease depending on whether it’s leaving or approaching the receiver:

$$f_{Doppler} = \frac{v}{\lambda}$$

[0044] Because the frequency shift is unknown and can suddenly change as the lidar looks at different points in space, finding the signal and tracking its phase is challenging.

[0045] (4) Slow scanning. For the interference between the transmitted and the received light to generate a large signal, the two waves need to overlap sufficiently well on the optical sensor. In some coherent systems, this requirement may significantly limit the effective field of view of the receiver and consequently the beam scanning speed.

[0046] (5) Directional ambiguity. Some coherent lidars are not capable of distinguishing signals entering the optical sensor simultaneously from multiple directions. For the same reason, other lidars in the field of view can generate interference.

[0047] (6) Laser phase noise. In interferometric ranging the phase of the transmitted light is effectively the length used as a reference to measure other distances. The intrinsic instability of the laser frequency/phase or mechanical vibrations propagating through the transmitter can significantly affect the ranging accuracy/precision.

[0048] There are numerous possible approaches to and/or architectures for lidar systems that can address some or all of these problems. Figures 5A-5H depict lidar sensor systems that use superheterodyne coherent detection methods measuring the phase of an RF beatnote (although frequency ranges outside RF are also possible). In some embodiments, the techniques measure the phase between two coincident and spatially/temporally coherent laser beams. Factors like phase ambiguity, phase instability and Doppler uncertainty may affect both beams to the same extent and cancel out in a differential measurement. To do so, the beams need to be separable yet be precisely overlapped. This is discussed in more detail herein.

[0049] Figure 5A depicts a lidar sensor 100 including a laser 110. The laser 110 can optionally be part of a central unit 10, as described above. As further discussed above, the laser 110 can be separate from the other components depicted in Figure 5A. Even further, the laser 110 can optionally be shared between multiple lidar sensors, such that one laser 110 can potentially provide beams of light simultaneously to a plurality of lidar sensor arrangements as shown in Figure 3 (where the remaining components in Figure 5A can be provided separately to each transceiver). One or more fiber couplers can be used to propagate the beam of light from a single laser to multiple subsystems. However, in other embodiments each lidar sensor 100 can include a dedicated laser 110, as implied by the arrangement of components depicted in Figure 5A.

[0050] The initial beam of light from the laser 110 in Figure 5A can be split (for example, with one or more fiber couplers 170) into three separate portions. A first portion of the beam can be directed (for example with an optical fiber) to a first frequency shifter 140. The first frequency shifter 140 can be, for example, an electro-optical frequency shifter based on the Pockels effect or an acousto-optic frequency shifter. As shown, the first frequency shifter 140 can adjust or modulate the frequency of the first portion of the beam from a

frequency f_0 to another frequency f_0+f_1 . Although the frequency is depicted as being adjusted higher, the frequency can also be adjusted lower. More generally, the frequency can be adjusted to be a variety of different frequencies, optionally between zero and 10 GHz.

[0051] The first portion can then be directed to a first phase modulator 150. The first phase modulator 150 can be, but not limited to, a lithium niobate crystal or waveguide. The first phase modulator 150 can be configured to embed a code c_1 in the phase of the first beam of light over a period of time. As shown, the code can be substantially binary or quaternary, like a bar code. For example, the code can shift between a zero degree phase for a period of time and then to a 180 degree phase for a period of time, repeating that pattern for varying durations to generate the code. Even further, the code can optionally be random or pseudo-random and have a sufficient length to be considered unique. An example code is depicted in Figure 7A. However, other variations are possible. For example, the phase can optionally shift 90 degrees, 45 degrees, or 30 degrees. Further, the phase can be non-binary, including more than two possible phases.

[0052] A second portion of the beam of light from the laser 110 can be manipulated in a similar manner as the first portion, as depicted in Figure 5A. As shown, the second portion can be directed on an optical path different from the first portion, and can be adjusted by a second frequency shifter 141, adjusting the second portion to a frequency f_0+f_2 that can be optionally different from the first frequency, and a second phase modulator 151 that can be optionally configured to provide a similar but different code c_2 to the second portion such that the two codes are substantially orthogonal to each other. The first portion and the second portion can then be combined by a fiber coupler 171 and then jointly directed to a transmitter 120. In this manner, a combined beam can be generated having a frequency f_1-f_2 and a phase-modulated code c_1c_2 (a separate component having a frequency f_1+f_2 can be ignored for these purposes). In some embodiments the frequency f_1-f_2 can be between 0 to 10 GHz. This combined beam is generated by an optical synthesizer circuit 115, which can adjust the frequency and phase of portions of light prior to transmission into the environment. The optical synthesizer circuit 115 can optionally include components in addition to the frequency shifters 140, 141 and phase modulators 150, 151 such as collimators, mirrors, lenses, fiber couplers, delay lines, and other optical components that can prepare the beam for transmission. Further, although the first fiber coupler 170 is not depicted as being part of the optical synthesizer

circuit 115 in Figure 5A, it can optionally be considered to be part of the optical synthesizer circuit 115. For example, in another example of a lidar sensor in Figure 5B, the function of the fiber coupler 170A in Figure 5A is split into two fiber couplers 170B and 171B, only one of which being part of the optical synthesizer circuit 115.

[0053] The combined beam can then be directed into an environment by the transmitter 120. The transmitter 120 can optionally include various optical components such as one or more lenses, mirrors, collimators, or other devices. Further, the transmitter 120 can also optionally include adjustable components such that the first and second portions of the beam of light can be directed in a controllable direction. For example, the transmitter 120 can optionally have an angular range of at least 180 degrees, 90 degrees, or 45 degrees.

[0054] The combined beam directed into the environment can encounter an object causing a reflected beam that results from the first and second portions. This reflected beam can then be received by a receiver 130 and can be directed to an optical sensor 180. The optical sensor can also receive an internal portion of the initial beam of light from the laser 110. Thus, the optical sensor 180 can potentially derive information from the characteristics of the reflected beam and the characteristics of an interference between the reflected beam and the internal portion of the initial beam. The optical sensor 180 can then generate a signal indicative of the beams received and can provide that signal to a computer system 300 (depicted in Figure 8), and potentially through the system depicted in Figure 2, for further analysis. Such analysis can include steps such as identifying the codes c_1 and c_2 in the reflected beams to identify the time of transmission of said beams. A representation of the combined beam without the codes can also be synthesized electronically (digitally or in analog) by measuring and subtracting the phase of beatnotes of each of the reflected beams with the local oscillator, after appropriate decodings (such as removing the codes c_1 and c_2). The combined beam can also be synthesized by squaring the signal at the optical sensor 180, canceling out possible Doppler shifts induced by a moving object at the point of reflection. Further, comparing the phase of the received reflected beam to the beam that was transmitted can be used to determine (and then cancel) noise caused by instability in the laser 180, mechanical vibrations, and other effects.

[0055] Further variations on this system are also possible. For example, in some embodiments the transmitter 120 and receiver 130 can be combined into a transceiver with shared lenses, mirrors, or other components. Additionally, like the laser 110, the optical sensor

180 can also be part of the central unit 10, separate from the other components depicted in Figure 5A such as the optical synthesizer circuit 115, or be shared between multiple lidar sensors. Even further, parts of the optical synthesizer circuit 115 can be shared between multiple lidar sensors, such as by using a single frequency shifter 140/141 to generate a portion with a shifted frequency that can be used for multiple lidar sensors.

[0056] The use of the codes c_1 and c_2 can facilitate the identification of the combined beam among a variety of other combined beams (having different codes) that can be collected at a single optical sensor 180 shared amongst a plurality of lidar sensors 100A. Thus, for example, a lidar sensor could have two sets of components (such as two optical synthesizer circuits 115, frequency shifters 140, phase modulators 150, transmitters 120, and/or receivers 130) each using directing separate combined beams (which can be portions of the same initial beam from the laser 110) to measure distances in different directions simultaneously (such that the times of transmission into the environment and reception of a reflected beam for each set of components can overlap). It should also be noted that the codes can also facilitate the identification of reflected beams originating from the lidar sensors 100 as opposed to beams that might be emitted by other devices such as neighboring cars that might also include lidar sensors, such that the lidar sensors 100 can operate in the presence of large numbers of other lidar sensors.

[0057] The reflected beam can be used to measure a variety of features relating to an object at the point of reflection. For example, the reflected beam can indicate a distance L to the point of reflection using the phase of the received synthetic beam Φ_r relative to that of the transmitted synthetic beam Φ_t (along with the wavelength, Λ , of the synthetic beam):

$$L = \frac{\Lambda}{4\pi}(\Phi_t - \Phi_r)$$

[0058] The phase of the transmitted synthetic beam Φ_r can be estimated by measuring a phase of the beam prior to being directed into the environment. For example, the transmitter 120 can create a reflection that can also be received by the optical sensor 180 for measurement. Alternatively, a portion of the beam can be measured further upstream, prior to reaching the transmitter 120.

[0059] This analysis optionally can be done after an electronic representation of the beam without the codes has been generated. The ambiguity range (due to the repeating of the

phase) can be made arbitrarily large by choosing close enough frequency shifts f_1 and f_2 , leading to a synthetic wavelength (using the speed of light c):

$$\Lambda = \frac{c}{f_1 - f_2}$$

[0060] For example, the wavelength can be greater than 300 m for $f_1 - f_2$ less than 1 MHz. However, in some situations the frequency shift cannot easily be made small enough to yield a sufficiently large wavelength. Nevertheless, the resulting ambiguity from phase differences can be resolved by measuring the delay of the propagated code from transmission to reception, which can indicate a time-of-flight of the beam and thus a distance when compared with the speed of light. This code delay can provide a coarse measurement of the range, and the phase difference can provide a fine measurement of the last fraction of the distance. Combined, the coarse and the fine measurement can provide an accurate and unambiguous measurement of the distance. For example, the lidar sensor 100 can have an accuracy of 1 mm or better. Further, the lidar sensor 100 can measure to this accuracy at ranges of 10 meters, 50 meters, 100 meters, 200 meters, or 500 meters.

[0061] The reflected beam can also be used to measure a velocity of the point of reflection (for example, a velocity of an object when the point is on the object). The velocity of the point in a radial direction from the lidar sensor 100 can be determined by using a time derivative of the distance:

$$v_{\parallel} = \frac{\Lambda}{4\pi} \frac{d}{dt} (\phi_t - \phi_r)$$

[0062] This measurement can be facilitated using the code embedded in the beam, which allows continuous measurement, unlike other techniques that rely on discrete pulses.

[0063] The velocity of the point in a lateral direction, tangential to the line of sight of the lidar sensor 100, can also be determined. For example, a Doppler frequency shift can be measured from the reflected beam, indicating a total velocity when multiplied by the wavelength λ . This Doppler frequency shift can include not only a shift of the center of the reflected beam spectrum, but also a sidelobe frequency shift further discussed below. The radial velocity can then be subtracted to determine the lateral velocity:

$$v_{\perp} = \lambda f_{\text{Doppler}} - v_{\parallel}$$

[0064] Figure 13 depicts a computer-generated signal spectrum of the reflected beam using an analytical model of a lidar sensor described herein, with a point of reflection at

a distance of 10 meters and moving at a lateral velocity of 50.8 m/s. As shown, the spectrum substantially follows a $[\text{sinc}(\alpha x)]^2$ function, with the peaks and troughs in that function defining characteristic sidelobes. The sidelobes can repeat at a frequency, f_s , of approximately 5 kHz on either side of the central peak of the spectrum (and thus have a frequency width f_s). Features on the surface of the material at the point of reflection interacting with the beams being reflected can create these sidelobes in the reflected beam. The central peak of the spectrum can also blend together with these sidelobes in the presence of signal noise, essentially broadening the central peak. Thus, if the Doppler frequency is measured in an appropriate location, it can indicate the sum of the radial and lateral velocities as indicated above. However, the sidelobes width can also be used to determine the lateral velocity in other ways.

[0065] The frequency intervals, f_s , can be proportional to the lateral velocity of the point of reflection relative to the lidar sensor, v_p , divided by the diameter of the laser beam at point of reflection, D :

$$f_s = k \frac{v_p}{D}$$

with $k \approx 1$ being an empirical constant determined by experimental calibration.

[0066] The diameter of the laser beam at the point of reflection can be derived from the distance to the point of reflection by the following formula:

$$D = D_0 \sqrt{1 + \left(\frac{L}{z_R}\right)^2}$$

where D_0 is the laser beam waist diameter, z_R is the so-called Rayleigh range, and L is the distance to the point of reflection.

[0067] The velocity of the point of reflection can then be the sum of the lateral velocity of the object or material, $v_{\perp}$, plus the velocity of the point of reflection caused by rotation of the lidar sensor itself, v_l , such that the lateral velocity can be determined using the following:

$$v_{\perp} = \frac{D f_s}{k} - v_l$$

[0068] Thus, the lateral velocity of the object can be determined using the conformation of the spectrum of the reflected signal as shaped by these sidelobes. The distance to the point of reflection can be determined using the techniques described herein, or be

otherwise known. For a more specific example, the method shown in Figure 11 can be used, where the estimated distance is additionally used to estimate the lateral velocity. Further, the detection of the lateral velocity using the sidelobe frequency can optionally be used in combination with other techniques described herein such as the coded beams. Although the lateral velocity can also be measured without use of the coded beams, the coded beams can facilitate measurement of the lateral velocity. For example, the coded beams can assist in isolating a reflected beam from background radiation caused by other light sources in the environment that might introduce excessive noise that could prevent identification of the sidelobes in the spectrum of the reflected beam.

[0069] Figures 12A-12C depict actual power spectra of the reflected beam by frequency, against a cotton towel for a sample material, at different lateral velocities zero, four, and eight meters per second. These measurements were made using a lidar sensor rastering the surface of the target at a rate of 0 Hz, 100 Hz, and 200 Hz, respectively and at a distance of 6 meters from the towel, introducing a base relative lateral velocity of 0, 4, and 8 meters per second respectively (as indicated). Further, this data was generated using the coded beams and related techniques described herein. As shown, each spectrum includes a central peak at 100 MHz, which can optionally correspond to a synthetic beam as described above, or can alternatively correspond to the frequency of the emitted beam. The spectra additionally include sidelobes with peaks and troughs at intervals, f_s , on either side of the central peak. These sidelobes can be caused by features on the surface of the material at the point of reflection. Such features can also cause the central peak to blend together with nearby sidelobes, as can be seen particularly in Figure 12C.

[0070] However, due to noise in the data, the sidelobes can be difficult to identify in the data shown in Figures 12A-12C. It should be understood that the features to the side of the central peak in Figure 12A are not sidelobes caused by a lateral velocity, because this data was gathered at zero velocity. Instead, those bands are the result of noise in the data, computer processing, and other effects. Nevertheless, even if the sidelobes width cannot be easily or directly identified, its effects can also be seen in the expanding width of the central peak in the spectra, which can clearly be seen by comparing Figures 12A-12C. Thus, use of the sidelobe width to measure lateral velocity can come from either direct measurement of the sidelobe width, by measurement of the width of a central peak, or by similar analyses of the spectra.

[0071] The sidelobes, and thus the frequency width, f_s , can be identified using a variety of techniques. For example, in some embodiments a best-fit algorithm can be used to match an idealized spectrum to the spectrum of the reflected beam. Various aspects of the idealized spectrum, such as the sidelobe frequency, width, sidelobe amplitude, central peak amplitude, and other characteristics can then be adjusted to minimize differences between the two spectra (for example, using least-squares). The resulting sidelobe location in the idealized spectrum can then be used to determine the lateral velocity. Other best-fit techniques can also be used.

[0072] Similarly, a machine-learning algorithm can be developed to determine the sidelobe width from the spectrum of the reflected beam. A dataset of sample spectra with known sidelobe widths (or alternatively, known lateral velocities) can be generated and used to develop an algorithm that is directed toward using these techniques.

[0073] The reflected beam can also be used to measure a reflectivity of the object at the point of reflection. The amplitude of the reflected beam can indicate a reflectivity of the object when compared with experimental results at comparable distances, using look-up tables for example.

[0074] Further analysis of the power spectrum of the reflected beam can indicate additional characteristics of the surface at the point of reflection. Figures 14A-14D depict power spectra for various materials at a lateral velocity of 50 meters per second. As discussed above, the sidelobes can be caused by features on the surface at the point of reflection, and the form of the sidelobes can be affected by those features on the surface. For example, the sidelobes can include additional sidebands, which can be seen in the Signal Spectrum of Figure 13, showing periodic features within the sidelobes of the $[\text{sinc}(\alpha x)]^2$ function. The amplitude of these sidebands are generally proportional to the depth of the surface features. Thus, for example, a material with pits will have sidebands with a greater amplitude as the depth of the pits increases. Further, because the amplitude of the sidebands can add to the amplitude of the sidelobes, the amplitude of the sidelobes may also be proportional to the depth profile of the reflective surface. Thus, use of the sidelobes to determine information about the material can implicitly include use of the sidebands. Additional information about the material at the point of reflection can also be determined from a spectral analysis of the reflected beam, beyond just the lateral velocity or the depth of surface features. The features of the material determine the

shape of the spectrum, and each type of material can have different features. For example, a repeating pattern on the material can induce a repeating pattern in the spectrum of the reflected beam. Irregular profiles on the material can induce more complex spectra, but can still potentially include certain signatures characteristic to the material, such as multi-modal peaks, variations in slope, and other features.

[0075] It should be noted that these spectral analyses differ from spectral analyses that might detect a “color” of an object or some other chemical property of the object. The spectral analyses can be based on a fixed wavelength, instead of color analysis based on wavelength dependence upon reflection. Similarly, the spectral analyses can be done on a normalized spectrum (for example, arbitrarily centered about 0 kHz as shown in Figures 14A-14D). However, in some embodiments additional information such as “color” of objects can also be used.

[0076] As an example, the painted drywall material (whose generated spectrum is shown in Figure 14A) has a relatively smooth surface relative to the cotton towel (whose generated spectrum is shown in Figure 14B) or the wool fabric (in Figure 14D). As a result, the sideband amplitudes for the cotton towel and wool fabric have a higher amplitude, and thus additional features are more prominent in the spectra. The sideband amplitude and other features can be determined using best-fit or machine learning algorithms in a similar manner to those discussed above regarding the sidelobe width, to determine characteristics of the materials or the identity of the materials.

[0077] Even further, algorithms can be developed to use patterns in the spectrum of the reflected beam to identify the material. For example, a machine learning algorithm can be trained using data from various materials to identify the material based on the spectrum. Features including but not limited to the frequency spacing and amplitude of the sidebands can optionally be used. Techniques similar to those utilized in standard Fourier Transform InfraRed (FTIR) spectroscopy for chemical analysis can optionally be adapted for use in this context, as discussed in “Fourier Transform Infrared Spectroscopy”, Peter R. Griffiths, James A. de Haseth, John Wiley & Sons, 2007, Second Edition, which is incorporated by reference herein in its entirety.

[0078] As with the lateral velocity, the characteristics of the surface can also optionally be used in combination with other techniques described herein such as the coded

beams. Much like the lateral velocity, the surface characteristics can also be measured without using coded beams, but the coded beams are helpful to isolate the reflected beam from background radiation. Again, a method similar to that in Figure 11 can be used, where an additional step of estimating characteristics of the surface can be included, potentially using other information estimated from the beams.

[0079] Further variations on the design of the lidar sensor 100 are also possible, as shown by example in Figures 5B-5H, which can be similar to the embodiment in Figure 5A unless indicated to the contrary, with similar names and reference numbers indicating similar components. For example, as shown in Figure 5B, the lidar sensor 100B can include only one frequency shifter 140B (for instance an acousto-optic modulator, “AOM”, although other frequency shifters are also possible) and one phase modulator (depicted as an electro-optic modulator, “EOM”, although other phase modulators are also possible including, but not limited to dual-parallel Mach-Zehnder interferometers) 150B to adjust the frequency of a first portion of the initial beam of light and apply a code to each of the first and second portions of the initial beam of light emitted by the laser 110B. This initial beam of light can encounter a first fiber coupler 170B which can direct an internal portion of the beam toward an optical sensor 160B, and direct the remaining beam to an optical synthesizer circuit 115B. The optical synthesizer circuit 115B can include a second fiber coupler 171B, splitting first and second portions of the beam for transmission. The first portion can proceed directly to a frequency shifter 140B, then to a phase modulator 150B, and then to a transmitter 120B in substantially the same way as in Figure 5A. Distinct from Figure 5A, the embodiment in Figure 5B can include a first optical circulator 190B between the frequency shifter 140B and the phase modulator 150B, a second optical circulator 191B between the phase modulator and a third fiber coupler 172B, and a third optical circulator 192B between the third fiber coupler 172B and the transmitter 120B. However, the second portion can be directed from the second fiber coupler 171B to the second optical circulator 191B, such that it can then pass through the phase modulator 150B in reverse relative to the first portion. The second portion can then be directed by the first optical circulator 190B to an optional delay line 200B and then to the third fiber coupler 172B (where it can be combined with the first portion, the coupler serving as a combiner) to be transmitted with the first beam portion as in Figure 5A.

[0080] The code provided by the phase modulator 150B can be unique, such as with a pseudo-random code as described above (although different types of codes from spread spectrum theory can be used). This code can be sufficiently random such that a delay provided by the delay line 200B can shift the codes applied to the first and second portions of the beam of light sufficiently for the two codes to be substantially orthogonal to each other. Thus, the processing of signals from the lidar sensor 100B can be substantially the same as from the lidar sensor 100 of Figure 5A, with the exception that f_2 is zero. Nevertheless, f_1 can optionally be adjusted in a similar manner to achieve the desired ambiguity range for the measured distance as discussed above with respect to Figure 5A.

[0081] Figure 5B also depicts an embodiment where the transmitter 120B and the receiver 130B are combined into a single transceiver, with the third optical circulator 192B directing the reflected beam from the transceiver 120B/130B to a fourth fiber coupler 193B. The fourth fiber coupler 193B combines the reflected beam and the internal portion of the initial beam, and directs them to the optical sensor 160B.

[0082] Figure 5C depicts an embodiment lidar sensor 100C with similarities to both the lidar sensors 100A, 100B of Figures 5A and 5B. As shown, the optical synthesizer circuit 115C can include separate and independent paths for each of the first and second portions of the initial beam of light, as in Figure 5A. However, only one frequency shifter 140C is included, such that only one of the two portions has its frequency shifted, as in Figure 5B.

[0083] Figure 5D depicts an embodiment lidar sensor 100D substantially similar to the lidar sensor 100A in Figure 5A, with some minor differences. For example, a transceiver 120D/130D can replace the separate components in Figure 5A.

[0084] Figure 5E depicts an embodiment lidar sensor 100E substantially similar to the lidar sensor 100D in Figure 5D, but including only one frequency shifter 140E. As shown, the optical synthesizer circuit 115E can include a partially-reflective mirror 210E between the frequency shifter 140E and a first phase modulator 150E, such that a first portion of the initial beam can pass through these two components as in Figures 5A-5D. The second portion of the initial beam can be separated from the first portion here by the reflection at the in-line partial retroreflector 210E (which function as an in-line fiber coupler), instead of at a fiber-optic fiber coupler as depicted in the figures for the previous embodiments. The second portion can then pass through the frequency shifter 140E a second time, yielding a frequency $f_0 + 2f_m$ (with the

first portion's frequency at $f_0 + f_m$). The second portion can then be directed by the optical circulator 190E to a second phase modulator 151E to apply a code and pass the beam to a second fiber coupler 170E for recombination with the first portion prior to transmission.

[0085] Figure 5F depicts an embodiment lidar sensor 100F similar to the lidar sensor 100E in Figure 5E, but using only a single phase modulator 150F and a different method for separating the first and second portions of the initial beam. As shown, instead of a partially-reflective mirror between the frequency shifter 140F and the phase modulator 150F, a second fiber coupler 171F can be included, and a second optical circulator 191F can be provided between the phase modulator 150F and a fiber coupler 172F prior to the transceiver 120F/130F. Thus, the second portion of the initial beam can be separated at the second fiber coupler 171F, which can direct the second portion past the phase modulator 150F to the second optical circulator 191F. The second portion can then be directed in a reverse direction through the phase modulator 150F and the frequency shifter 140F (yielding a frequency of $f_0 + 2f_m$ as in Figure 5E). Finally, the first optical circulator 190F can direct the second portion through a delay line 200F prior to recombination with the first portion.

[0086] Figure 5G depicts an embodiment lidar sensor 100G similar to the lidar sensor 100E in Figure 5E, but providing both the first and second portions with the same code. As shown, a single phase modulator 150G can be provided downstream from the second fiber coupler 171G, between the fiber coupler and a second optical circulator 191G just before the transceiver 120G/130G, such that both portions receive the same code.

[0087] Figure 5H depicts an embodiment lidar sensor 100H that is further simplified to only include one frequency shifter 140H and one phase modulator 150H, with one portion of the initial beam of light remaining unshifted. Instead, the initial beam of light from the laser 110H is split only once at the first fiber coupler 170H, into a transmitted portion and an internal portion. The transmitted portion is directed to a frequency shifter 140H that, unlike the previously described embodiments, provides two superimposed frequency modulations onto the transmitted portion. As shown, frequencies of f_m and $f_m + \Delta f$ are used to shift the transmitted portion (starting with a frequency of f_0). Thus, a combined beam can then be generated having a frequency of Δf . The combined beam can then be directed to the phase modulator 150H, which applies a single code prior to passing the beam along toward the

transceiver 120H/130H. Thus, using a combined frequency Δf and a single code, the analysis of the reflected beam can be similar to those discussed above.

[0088] Thus, a variety of different lidar sensors are possible and other combinations and permutations of the embodiments described above will be understood to one of skill in the art as part of the disclosure herein.

[0089] In addition to the superheterodyne lidar sensors described above, superhomodyne lidar sensors can also be used to measure the phase of the reflected light from the direct current (“DC”) signal it generates on an optical sensor. Figures 6A-6C depict different lidar sensors using these techniques, with certain components being similar to those in Figures 5A-5H unless otherwise stated.

[0090] Figure 6A depicts a lidar sensor 100I with a layout and mode of operation substantially similar to the lidar sensor 100A in Figure 5A, but without frequency shifters. Additionally, the lidar sensor 100I can include phase modulators 150I, 151I that provide a different code c_1 to the first portion of the initial beam of light to be transmitted. As shown, the code c_1 can be the combination of a “bar code” (such as that described previously and shown as a pseudo-random noise code in Figure 7A) and a periodic pattern such as sawtooth phase modulation depicted in Figure 7A, yielding the combined code c_1 depicted in Figure 7A. Again, the codes c_1 and c_2 can be orthogonal to each other. Further variations on these codes are also possible. For example, the periodic pattern can be a linear sawtooth, quadratic sawtooth, cubic sawtooth, sinusoidal, or have some other profile.

[0091] After the combined signal with the codes c_1 and c_2 has been transmitted, reflected, and received, the codes can be used to identify the time of transmission of a received reflected beam. Similar analysis can also be applied to the received signal as in the superheterodyne process described above, such as Doppler frequency estimation and tracking, and comparing the phase of the received beam with the transmitted beam to reduce noise.

[0092] The reflected beam received by the lidar sensor in Figure 6A can also be used to measure a variety of features relating to an object at the point of reflection, as discussed in other embodiments above. However, there can be some differences.

[0093] For example, in the previously described method the distance can be determined using the difference in phases of the light fields of the transmitted and received reflected beams (after demodulating the received reflected beam to remove the codes).

Although that previously described method could also potentially be used in the system of Figure 6A, use of the periodicity of the sawtooth ramp code is described here. The relative phase Φ_r measured at the optical sensor 180I at time t is equal to the phase of the modulation ramp at a time $t-2L/c$:

$$\Phi_r(t) = \Phi_m(t - 2L/c)$$

where L is the distance to the object and c is the speed of light. The time of flight $2L/c$ and thus the distance LL can be derived by simply inverting the phase of the modulation ramp code Φ_m . Similarly, the radial velocity of the point of reflection can be computed using the difference in phases of the transmitted and received reflected beams after decoding. The lateral velocity can be computed using similar methods to those discussed above.

[0094] The reflected beam can also be used to measure a reflectivity of the object at the point of reflection. The quadrature amplitude of the DC signal resulting from the reflected beam at the optical sensor can be compared with experimental results at comparable distances, using look-up tables for example, to determine a reflectivity.

[0095] Further, reducing the slope of the sawtooth phase profile at the modulator allows mapping of the surface microscopic profile of the target object onto the measured phase of the light. Techniques for determining characteristics of the surface at the point of reflection discussed above can also be used with the superhomodyne arrangement.

[0096] Further variations on the design of the lidar sensor 100I are also possible, as shown in Figures 6B and 6C, which can be similar to the embodiment in Figure 6A unless indicated to the contrary, with similar names and reference numbers indicating similar components. For example, as shown in Figure 6B, the lidar sensor 100J can include only one phase modulator 150J. A first portion of the initial beam of light can pass through the phase modulator 150J, and three optical circulators 190J, 191J, 192J, as in Figure 6A. A second portion of the initial beam of light can be directed through the phase modulator 150J in a reverse direction and then directed through an optional delay line 200J using the first optical circulator 190J. This delay can lead the second portion to have a code that is orthogonal to the first portion's code when they are recombined. It should be noted that this lidar 100J is substantially similar to the lidar 100B depicted in Figure 5B (without a frequency shifter). The phase modulation provided by the phase modulator 150J can optionally include a pseudo-random binary code combined with a parabolic sawtooth pattern, as depicted in Figure 7B.

[0097] Figure 6C depicts an embodiment lidar sensor 100K similar to the lidar sensor 100I in Figure 6A, with some minor differences. For example, a transceiver 120K/130K can replace the separate components in Figure 6A.

[0098] As in the superheterodyne examples depicted in Figures 5A-5H, additional variations on the superhomodyne lidar sensors can also be provided. For example, the first portion and second portion can be separated using fiber-optic fiber couplers or partially-reflective in-line retroreflectors. These can be routed along separate paths or can be combined in a single path. They can also optionally be provided with the same code.

[0099] Figures 9-11 depict various methods for measuring distances, which can be optionally implemented using the systems described above. As shown in Figure 9, an initial beam (such as a beam generated from a laser 110) can be split into a transmitted portion and an internal portion. The transmitted portion can have its phase modulated to embed a unique code (as discussed above) prior to being directed into the environment. The received reflected beam resulting from the transmitted portion can then be identified by detecting the unique code. The distance to a point of reflection can then be estimated using the reflected beam and the internal portion.

[0100] The method depicted in Figure 10 is substantially similar to that in Figure 9, but shows that two separate transmitted portions can be used to detect distances simultaneously. The method depicted in Figure 11 is also similar to that in Figures 9 and 10, but shows that multiple values can be estimated, such as the radial and lateral velocities, in addition to the distance.

[0101] According to one embodiment, the techniques described herein (such as for measuring distances, velocities, and surface characteristics) are implemented by at least one computing device. The techniques may be implemented in whole or in part using a combination of at least one server computer and/or other computing devices that are coupled using a network, such as a packet data network. The computing devices may be hard-wired to perform the techniques, or may include digital electronic devices such as at least one application-specific integrated circuit (ASIC) or field programmable gate array (FPGA) that is persistently programmed to perform the techniques, or may include at least one general purpose hardware processor programmed to perform the techniques pursuant to program instructions in firmware, memory, other storage, or a combination. Such computing devices may also combine custom

hard-wired logic, ASICs, or FPGAs with custom programming to accomplish the described techniques. The computing devices may be server computers, workstations, personal computers, portable computer systems, handheld devices, mobile computing devices, wearable devices, body mounted or implantable devices, smartphones, smart appliances, internetworking devices, autonomous or semi-autonomous devices such as robots or unmanned ground or aerial vehicles, any other electronic device that incorporates hard-wired and/or program logic to implement the described techniques, one or more virtual computing machines or instances in a data center, and/or a network of server computers and/or personal computers.

[0102] Figure 8 is a block diagram that illustrates an example computer system with which an embodiment may be implemented. In the example of FIG. 3, a computer system 300 and instructions for implementing the disclosed technologies in hardware, software, or a combination of hardware and software, are represented schematically, for example as boxes and circles, at the same level of detail that is commonly used by persons of ordinary skill in the art to which this disclosure pertains for communicating about computer architecture and computer systems implementations.

[0103] Computer system 300 includes an input/output (I/O) subsystem 302 which may include a bus and/or other communication mechanism(s) for communicating information and/or instructions between the components of the computer system 300 over electronic signal paths. The I/O subsystem 302 may include an I/O controller, a memory controller and at least one I/O port. The electronic signal paths are represented schematically in the drawings, for example as lines, unidirectional arrows, or bidirectional arrows.

[0104] At least one hardware processor 304 is coupled to I/O subsystem 302 for processing information and instructions. Hardware processor 304 may include, for example, a general-purpose microprocessor or microcontroller and/or a special-purpose microprocessor such as an embedded system or a graphics processing unit (GPU) or a digital signal processor or ARM processor. Processor 304 may comprise an integrated arithmetic logic unit (ALU) or may be coupled to a separate ALU.

[0105] Computer system 300 includes one or more units of memory 306, such as a main memory, which is coupled to I/O subsystem 302 for electronically digitally storing data and instructions to be executed by processor 304. Memory 306 may include volatile memory

such as various forms of random-access memory (RAM) or other dynamic storage device. Memory 306 also may be used for storing temporary variables or other intermediate information during execution of instructions to be executed by processor 304. Such instructions, when stored in non-transitory computer-readable storage media accessible to processor 304, can render computer system 300 into a special-purpose machine that is customized to perform the operations specified in the instructions.

[0106] Computer system 300 further includes non-volatile memory such as read only memory (ROM) 308 or other static storage device coupled to I/O subsystem 302 for storing information and instructions for processor 304. The ROM 308 may include various forms of programmable ROM (PROM) such as erasable PROM (EPROM) or electrically erasable PROM (EEPROM). A unit of persistent storage 310 may include various forms of non-volatile RAM (NVRAM), such as FLASH memory, or solid-state storage, magnetic disk or optical disk such as CD-ROM or DVD-ROM, and may be coupled to I/O subsystem 302 for storing information and instructions. Storage 310 is an example of a non-transitory computer-readable medium that may be used to store instructions and data which when executed by the processor 304 cause performing computer-implemented methods to execute the techniques herein.

[0107] The instructions in memory 306, ROM 308 or storage 310 may comprise one or more sets of instructions that are organized as modules, methods, objects, functions, routines, or calls. The instructions may be organized as one or more computer programs, operating system services, or application programs including mobile apps. The instructions may comprise an operating system and/or system software; one or more libraries to support multimedia, programming or other functions; data protocol instructions or stacks to implement TCP/IP, HTTP or other communication protocols; file format processing instructions to parse or render files coded using HTML, XML, JPEG, MPEG or PNG; user interface instructions to render or interpret commands for a graphical user interface (GUI), command-line interface or text user interface; application software such as an office suite, internet access applications, design and manufacturing applications, graphics applications, audio applications, software engineering applications, educational applications, games or miscellaneous applications. The instructions may implement a web server, web application server or web client. The instructions may be organized as a presentation layer, application layer and data storage layer

such as a relational database system using structured query language (SQL) or no SQL, an object store, a graph database, a flat file system or other data storage.

[0108] Computer system 300 may be coupled via I/O subsystem 302 to at least one output device 312. In one embodiment, output device 312 is a digital computer display. Examples of a display that may be used in various embodiments include a touch screen display or a light-emitting diode (LED) display or a liquid crystal display (LCD) or an e-paper display. Computer system 300 may include other type(s) of output devices 312, alternatively or in addition to a display device. Examples of other output devices 312 include printers, ticket printers, plotters, projectors, sound cards or video cards, speakers, buzzers or piezoelectric devices or other audible devices, lamps or LED or LCD indicators, haptic devices, actuators or servos.

[0109] At least one input device 314 is coupled to I/O subsystem 302 for communicating signals, data, command selections or gestures to processor 304. Examples of input devices 314 include the optical sensors and other sensors described herein, and potentially other devices such as touch screens, microphones, still and video digital cameras, alphanumeric and other keys, keypads, keyboards, graphics tablets, image scanners, joysticks, clocks, switches, buttons, dials, slides, and/or various types of sensors such as force sensors, motion sensors, heat sensors, accelerometers, gyroscopes, and inertial measurement unit (IMU) sensors and/or various types of transceivers such as wireless, such as cellular or Wi-Fi, radio frequency (RF) or infrared (IR) transceivers and Global Positioning System (GPS) transceivers.

[0110] Another type of input device is a control device 316, which may perform cursor control or other automated control functions such as navigation in a graphical interface on a display screen, alternatively or in addition to input functions. Control device 316 may be a touchpad, a mouse, a trackball, or cursor direction keys for communicating direction information and command selections to processor 304 and for controlling cursor movement on display 312. The input device may have at least two degrees of freedom in two axes, a first axis (e.g., x) and a second axis (e.g., y), that allows the device to specify positions in a plane. Another type of input device is a wired, wireless, or optical control device such as a joystick, wand, console, steering wheel, pedal, gearshift mechanism or other type of control device. An

input device 314 may include a combination of multiple different input devices, such as a video camera and a depth sensor.

[0111] In another embodiment, computer system 300 may comprise an internet of things (IoT) device in which one or more of the output device 312, input device 314, and control device 316 are omitted. Or, in such an embodiment, the input device 314 may comprise one or more cameras, motion detectors, thermometers, microphones, seismic detectors, other sensors or detectors, measurement devices or encoders and the output device 312 may comprise a special-purpose display such as a single-line LED or LCD display, one or more indicators, a display panel, a meter, a valve, a solenoid, an actuator or a servo.

[0112] When computer system 300 is a mobile computing device, input device 314 may comprise a global positioning system (GPS) receiver coupled to a GPS module that is capable of triangulating to a plurality of GPS satellites, determining and generating geo-location or position data such as latitude-longitude values for a geophysical location of the computer system 300. Output device 312 may include hardware, software, firmware and interfaces for generating position reporting packets, notifications, pulse or heartbeat signals, or other recurring data transmissions that specify a position of the computer system 300, alone or in combination with other application-specific data, directed toward host 324 or server 330.

[0113] Computer system 300 may implement the techniques described herein using customized hard-wired logic, at least one ASIC or FPGA, firmware and/or program instructions or logic which when loaded and used or executed in combination with the computer system causes or programs the computer system to operate as a special-purpose machine. According to one embodiment, the techniques herein are performed by computer system 300 in response to processor 304 executing at least one sequence of at least one instruction contained in main memory 306. Such instructions may be read into main memory 306 from another storage medium, such as storage 310. Execution of the sequences of instructions contained in main memory 306 causes processor 304 to perform the process steps described herein. In alternative embodiments, hard-wired circuitry may be used in place of or in combination with software instructions.

[0114] The term “storage media” as used herein refers to any non-transitory media that store data and/or instructions that cause a machine to operation in a specific fashion. Such storage media may comprise non-volatile media and/or volatile media. Non-volatile media

includes, for example, optical or magnetic disks, such as storage 310. Volatile media includes dynamic memory, such as memory 306. Common forms of storage media include, for example, a hard disk, solid state drive, flash drive, magnetic data storage medium, any optical or physical data storage medium, memory chip, or the like.

[0115] Storage media is distinct from but may be used in conjunction with transmission media. Transmission media participates in transferring information between storage media. For example, transmission media includes coaxial cables, copper wire and fiber optics, including the wires that comprise a bus of I/O subsystem 302. Transmission media can also take the form of acoustic or light waves, such as those generated during radio-wave and infra-red data communications.

[0116] Various forms of media may be involved in carrying at least one sequence of at least one instruction to processor 304 for execution. For example, the instructions may initially be carried on a magnetic disk or solid-state drive of a remote computer. The remote computer can load the instructions into its dynamic memory and send the instructions over a communication link such as a fiber optic or coaxial cable or telephone line using a modem. A modem or router local to computer system 300 can receive the data on the communication link and convert the data to a format that can be read by computer system 300. For instance, a receiver such as a radio frequency antenna or an infrared detector can receive the data carried in a wireless or optical signal and appropriate circuitry can provide the data to I/O subsystem 302 such as place the data on a bus. I/O subsystem 302 carries the data to memory 306, from which processor 304 retrieves and executes the instructions. The instructions received by memory 306 may optionally be stored on storage 310 either before or after execution by processor 304.

[0117] Computer system 300 also includes a communication interface 318 coupled to bus 302. Communication interface 318 provides a two-way data communication coupling to network link(s) 320 that are directly or indirectly connected to at least one communication networks, such as a network 322 or a public or private cloud on the Internet. For example, communication interface 318 may be an Ethernet networking interface, integrated-services digital network (ISDN) card, cable modem, satellite modem, or a modem to provide a data communication connection to a corresponding type of communications line, for example an Ethernet cable or a metal cable of any kind or a fiber-optic line or a telephone line. Network

322 broadly represents a local area network (LAN), wide-area network (WAN), campus network, internetwork or any combination thereof. Communication interface 318 may comprise a LAN card to provide a data communication connection to a compatible LAN, or a cellular radiotelephone interface that is wired to send or receive cellular data according to cellular radiotelephone wireless networking standards, or a satellite radio interface that is wired to send or receive digital data according to satellite wireless networking standards. In any such implementation, communication interface 318 sends and receives electrical, electromagnetic or optical signals over signal paths that carry digital data streams representing various types of information.

[0118] Network link 320 typically provides electrical, electromagnetic, or optical data communication directly or through at least one network to other data devices, using, for example, satellite, cellular, Wi-Fi, or BLUETOOTH technology. For example, network link 320 may provide a connection through a network 322 to a host computer 324.

[0119] Furthermore, network link 320 may provide a connection through network 322 or to other computing devices via internetworking devices and/or computers that are operated by an Internet Service Provider (ISP) 326. ISP 326 provides data communication services through a world-wide packet data communication network represented as internet 328. A server computer 330 may be coupled to internet 328. Server 330 broadly represents any computer, data center, virtual machine or virtual computing instance with or without a hypervisor, or computer executing a containerized program system such as DOCKER or KUBERNETES. Server 330 may represent an electronic digital service that is implemented using more than one computer or instance and that is accessed and used by transmitting web services requests, uniform resource locator (URL) strings with parameters in HTTP payloads, API calls, app services calls, or other service calls. Computer system 300 and server 330 may form elements of a distributed computing system that includes other computers, a processing cluster, server farm or other organization of computers that cooperate to perform tasks or execute applications or services. Server 330 may comprise one or more sets of instructions that are organized as modules, methods, objects, functions, routines, or calls. The instructions may be organized as one or more computer programs, operating system services, or application programs including mobile apps. The instructions may comprise an operating system and/or system software; one or more libraries to support multimedia, programming or other functions;

data protocol instructions or stacks to implement TCP/IP, HTTP or other communication protocols; file format processing instructions to parse or render files coded using HTML, XML, JPEG, MPEG or PNG; user interface instructions to render or interpret commands for a graphical user interface (GUI), command-line interface or text user interface; application software such as an office suite, internet access applications, design and manufacturing applications, graphics applications, audio applications, software engineering applications, educational applications, games or miscellaneous applications. Server 330 may comprise a web application server that hosts a presentation layer, application layer and data storage layer such as a relational database system using structured query language (SQL) or no SQL, an object store, a graph database, a flat file system or other data storage.

[0120] Computer system 300 can send messages and receive data and instructions, including program code, through the network(s), network link 320 and communication interface 318. In the Internet example, a server 330 might transmit a requested code for an application program through Internet 328, ISP 326, local network 322 and communication interface 318. The received code may be executed by processor 304 as it is received, and/or stored in storage 310, or other non-volatile storage for later execution.

[0121] The execution of instructions as described in this section may implement a process in the form of an instance of a computer program that is being executed, and consisting of program code and its current activity. Depending on the operating system (OS), a process may be made up of multiple threads of execution that execute instructions concurrently. In this context, a computer program is a passive collection of instructions, while a process may be the actual execution of those instructions. Several processes may be associated with the same program; for example, opening up several instances of the same program often means more than one process is being executed. Multitasking may be implemented to allow multiple processes to share processor 304. While each processor 304 or core of the processor executes a single task at a time, computer system 300 may be programmed to implement multitasking to allow each processor to switch between tasks that are being executed without having to wait for each task to finish. In an embodiment, switches may be performed when tasks perform input/output operations, when a task indicates that it can be switched, or on hardware interrupts. Time-sharing may be implemented to allow fast response for interactive user applications by rapidly performing context switches to provide the appearance of concurrent

execution of multiple processes simultaneously. In an embodiment, for security and reliability, an operating system may prevent direct communication between independent processes, providing strictly mediated and controlled inter-process communication functionality.

[0122] Some additional example embodiments are described in view of the following clauses:

Clause 1. A lidar sensor comprising:

- an optical sensor configured to produce signals based at least on receiving one or more beams of light;

- a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor, wherein the optical sensor is configured to receive both the internal portion of the initial beam of light and a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment;

- a processor configured to:

- receive signals from the optical sensor;

- identify the first reflected beam of light as having resulted from the first portion of the initial beam of light;

- determine a distance to the point of reflection based at least on the first reflected beam of light and the internal portion of the initial beam of light;

- determine a radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the first reflected beam of light and the internal portion of the initial beam of light; and

- determine a lateral velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift of the first reflected beam of light and the determined radial velocity.

Clause 2. The lidar sensor of clause 1, further comprising an phase modulator configured to modulate a phase of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of

the first portion of the initial beam of light prior to it being directed into the environment.

Clause 3. The lidar sensor of clause 2, wherein the determined distance is based at least on a time of return of the first reflected beam of light using at least the unique code.

Clause 4. The lidar sensor of clause 1, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

Clause 5. The lidar sensor of clause 4, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

Clause 6. A lidar sensor comprising:

- a laser configured to emit an initial beam of light;

- a first fiber coupler in optical communication with the laser to receive and divide the initial beam of light into a transmitted portion and an internal portion;

- an optical synthesizer circuit in optical communication with the first fiber coupler to receive the transmitted portion of the initial beam of light from the first fiber coupler and to adjust a phase of the transmitted portion of the initial beam of light;

- a transmitter in optical communication with the optical synthesizer circuit to receive the transmitted portion with an adjusted phase from the optical synthesizer circuit and direct the transmitted portion into the environment;

- a receiver configured to receive a reflected beam of light from the environment resulting from the transmitted portion of the initial beam of light;

- a second fiber coupler in optical communication with the receiver and the first fiber coupler to combine the reflected beam of light and the internal portion of the initial beam of light into a combined beam of light; and

- an optical sensor in optical communication with the second fiber coupler to receive the second beam of light.

Clause 7. The lidar sensor of clause 6, wherein the transmitter and receiver are a single transceiver.

Clause 8. The lidar sensor of clause 6, wherein the optical synthesizer circuit comprises one or more phase modulators, the phase modulators being configured to embed a

unique code into a modulated phase of the transmitted portion of the initial beam of light.

Clause 9. The lidar sensor of clause 8, wherein the one or more phase modulators are also configured to embed a periodic pattern combined with the unique code into the modulated phase of the transmitted portion of the initial beam of light.

Clause 10. The lidar sensor of clause 6, wherein the optical synthesizer circuit further comprises at least two different optical paths and is configured to separate the transmitted portion of the initial beam of light into a first portion and a second portion along the at least two different optical paths and recombine the first portion and second portion prior to being received by the transmitter.

Clause 11. The lidar sensor of clause 10, wherein the optical synthesizer circuit comprises a third fiber coupler configured to separate the transmitted portion of the initial beam of light into the first portion and the second portion, and a fourth fiber coupler configured to recombine the first portion and the second portion prior to being received by the transmitter.

Clause 12. The lidar sensor of clause 10, wherein the optical synthesizer circuit comprises one or more phase modulators configured to embed different unique codes into modulated phases of each of the first portion and the second portion prior to being recombined.

Clause 13. The lidar sensor of clause 6, wherein the optical synthesizer circuit comprises a frequency shifter configured to adjust a frequency of the transmitted portion of the initial beam of light prior to being directed into the environment.

Clause 14. The lidar sensor of clause 6, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

Clause 15. The lidar sensor of clause 14, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

Clause 16. A method of operating a lidar sensor to measure a distance to an object and a velocity of the object, the method comprising:

- splitting a beam of light into a transmitted portion and an internal portion;
- directing the transmitted portion into the environment;

receiving a reflected beam resulting from the transmitted portion being directed into the environment;

estimating a distance to a point of reflection using the reflected beam and the internal portion;

estimating a radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the reflected beam of light and the internal portion; and

estimating a lateral velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift of the reflected beam and the determined radial velocity.

Clause 17. The method of clause 16, further comprising modulating a phase of the transmitted portion over a period of time with a unique code to embed the unique code into a modulated phase of the transmitted portion prior to it being directed into the environment.

Clause 18. The method of clause 17, wherein the estimated distance is determined based at least on a time of return of the reflected beam using at least the unique code.

WHAT IS CLAIMED IS:

1. A lidar sensor comprising:

an optical sensor configured to produce signals based at least on receiving one or more beams of light;

a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor, wherein the optical sensor is configured to receive both the internal portion of the initial beam of light and a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment;

at least one phase modulator configured to modulate a phase of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of the first portion of the initial beam of light prior to it being directed into the environment; and

a processor configured to receive signals from the optical sensor and to identify the first reflected beam of light as having resulted from the first portion of the initial beam of light based at least on detecting the unique code and further configured to determine a distance to the first point of reflection based at least on the first reflected beam of light and the internal portion of the initial beam of light.

2. The lidar sensor of Claim 1, wherein a second portion of the initial beam of light is also directed into the environment in a direction different from the first portion of the initial beam of light, and the optical sensor is configured to receive a second reflected beam of light resulting from the second portion of the initial beam of light being reflected at a second point of reflection in the environment, the lidar sensor further comprising:

a second phase modulator configured to modulate a phase of the second portion of the initial beam of light over a period of time with a second unique code to embed the second unique code in its modulated phase prior to the second portion of the initial beam of light being directed into the environment, such that the second unique code is different from the first unique code,

wherein the processor is configured to identify a second reflected beam of light as having resulted from the second portion of the initial beam of light based at least on

detecting the second unique code and further configured to determine a distance to the second point of reflection based at least on the second reflected beam of light and the internal portion of the initial beam of light, and

wherein the time between direction of the first portion of the initial beam of light into the environment and reception of the first reflected beam of light by the optical sensor overlaps with the time between direction of the second portion of the initial beam of light into the environment and reception of the second reflected beam of light by the optical sensor.

3. The lidar sensor of any of Claims 1-2, wherein the processor is configured to determine the distance to the first point of reflection based on at least a relative phase between the first reflected beam of light and the internal portion of the initial beam of light.

4. The lidar sensor of any of Claims 1-3, wherein the processor is configured to determine the distance to the first point of reflection based on at least a time of return of the first reflected beam of light using at least the unique code.

5. The lidar sensor of any of Claims 1-4, further comprising an optical frequency shifter configured to shift a frequency of the first portion of the initial beam of light prior to it being directed into the environment.

6. The lidar sensor of any of Claims 1-5, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

7. The lidar sensor of Claim 6, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

8. The lidar sensor of any of Claims 1-7, wherein the at least one phase modulator is additionally configured to modulate a phase of the first portion of the initial beam of light over a period of time with a periodic pattern to embed the periodic pattern, combined with the unique code, into the modulated phase of the first portion of the initial beam of light prior to it being directed into the environment.

9. The lidar sensor of any of Claims 1-8, wherein the lidar sensor further comprises:

an optical element dividing the first portion into two parts; and

a fiber coupler recombining the two parts prior to the first portion being directed into the environment.

10. The lidar sensor of Claim 9, further comprising at least two optical paths, the first part being directed along a first path and the second part being directed along a second path different from the first path, wherein the two parts each pass through the at least one optical modulator such that each part receives a different unique code.

11. The lidar sensor of Claim 10, wherein the at least one phase modulator comprises two phase modulators, and each part is modulated by a different phase modulator.

12. The lidar sensor of any of Claims 9-11, further comprising at least one optical frequency shifter configured to shift a frequency of the two parts such that each part has a different frequency prior to being recombined.

13. A lidar sensor comprising:

an optical sensor configured to produce signals based at least on receiving one or more beams of light;

a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment in a first direction, a second portion of the initial beam of light being directed into the environment in a second direction different from the first direction, and an internal portion of the initial beam of light being directed to the optical sensor, wherein the same optical sensor is configured to receive each of the internal portion of the initial beam of light, a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment, and a second reflected beam of light resulting from the second portion of the initial beam of light being reflected at a second point of reflection in the environment;

a processor configured to receive signals from the optical sensor and to identify the first reflected beam of light as having resulted from the first portion of the initial beam of light and the second reflected beam as having resulted from the second portion of the initial beam of light, and further configured to determine distances to the first and second points of reflection based at least on the first and second reflected beams of light and the internal portion of the initial beam of light;

wherein the time between direction of the first portion of the initial beam of light into the environment and reception of the first reflected beam of light by the optical sensor overlaps with the time between direction of the second portion of the

initial beam of light into the environment and reception of the second reflected beam of light by the same optical sensor.

14. The lidar sensor of Claim 13, further comprising:

one or more phase modulators configured to modulate a phase of each of the first and second portions of the initial beam of light over a period of time with different unique codes, to embed the unique codes in their modulated phases, prior to being directed into the environment, and

wherein the processor is configured to identify the reflected beams of light as having resulted from the portions of the initial beam of light based at least on detecting the unique codes.

15. The lidar sensor of Claim 14, wherein the one or more phase modulators are additionally configured to modulate a phase of each of the first and second portions of the initial beam of light over a period of time with a periodic pattern to embed the periodic pattern combined with the unique codes, into the modulated phases of the first and second portions of the initial beam of light prior to them being directed into the environment.

16. The lidar sensor of any of Claims 13-15, wherein the processor is configured to determine the distances to the first and second points of reflection based on at least a relative phase between the first and second reflected beams of light and the internal portion of the initial beam of light.

17. The lidar sensor of any of Claims 13-16, wherein the processor is configured to determine the distances to the first and second points of reflection based on at least times of return of the first and second reflected beams of light using at least the unique code.

18. The lidar sensor of any of Claims 13-17, further comprising one or more optical frequency shifters configured to shift frequencies of the first and second portions of the initial beam of light prior to them being directed into the environment.

19. The lidar sensor of any of Claims 13-18, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

20. The lidar sensor of Claim 19, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

21. A method of measuring distance comprising:

splitting a beam of light into a transmitted portion and an internal portion;

modulating a phase of the transmitted portion of the beam of light over a period of time to embed a unique code into a modulated phase of the transmitted portion;

directing the transmitted portion with the modulated phase into the environment;

receiving a reflected beam resulting from the transmitted portion being directed into the environment;

identifying the reflected beam as resulting from the transmitted portion being directed into the environment at least by detecting the unique code; and

estimating a distance to a point of reflection using the reflected beam and the internal portion.

22. The method of Claim 21, wherein the unique code is a pseudo-random code.

23. The method of any of Claims 21-22, further comprising modulating a phase of the transmitted portion of the beam of light over a period of time to embed a periodic pattern combined with the unique code into a modulated phase of the transmitted portion.

24. The method of any of Claims 21-23, further comprising:

splitting the transmitted portion into a first transmitted portion and a second transmitted portion and wherein the step of modulating further comprises modulating phases of the first and second portions over a period of time to embed different unique codes into the modulated phases of the first and second portions; and

combining the first and second transmitted portions with the modulated phases prior to directing the transmitted portion into the environment.

25. The method of any of Claims 21-24, further comprising modulating a frequency of the transmitted portion of the beam of light, and wherein the step of directing comprises directing the transmitted portion with the modulated phase and frequency into the environment.

26. A method of simultaneously measuring multiple distances comprising:

splitting a beam of light into a first transmitted portion, a second transmitted portion, and an internal portion;

directing the first and second transmitted portions into the environment in different directions;

receiving reflected beams resulting from the first and second transmitted portions being directed into the environment at a single optical sensor;

identifying the reflected beams as resulting from the first and second transmitted portions being directed into the environment; and

estimating a distance to points of reflection using the reflected beams and the internal portion,

wherein the time between the directing of the first transmitted portion into the environment and receiving the reflected beam resulting from the first transmitted portion overlaps with the time between the directing of the second transmitted portion into the environment and receiving the reflected beam resulting from the second transmitted portion.

27. The method of Claim 26, further comprising modulating phases of the first and second transmitted portions of the beam of light over a period of time to embed different unique codes into a modulated phase of each of the first and second transmitted portions.

28. The method of Claim 27, wherein the unique codes are pseudo-random codes.

29. The method of any of Claims 27-28, further comprising modulating phases of the first and second transmitted portions of the beam of light over a period of time to embed a periodic pattern combined with the unique codes into the modulated phases of the first and second transmitted portions.

30. The method of any of Claims 26-29, further comprising modulating frequencies of the first and second transmitted portions of the beam of light, and wherein the step of directing comprises directing the transmitted portion with the modulated phases and frequencies into the environment.

31. A lidar sensor comprising:

an optical sensor configured to produce signals based at least on receiving one or more beams of light;

a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor, wherein the optical sensor is configured to receive both the internal portion of the initial beam of light and a first reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment;

a processor configured to:

- receive signals from the optical sensor;
- identify the first reflected beam of light as having resulted from the first portion of the initial beam of light;
- determine a distance to the point of reflection based at least on the first reflected beam of light and the internal portion of the initial beam of light;
- determine a radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the first reflected beam of light and the internal portion of the initial beam of light; and
- determine a lateral velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift of the first reflected beam of light and the determined radial velocity.

32. The lidar sensor of Claim 31, further comprising an phase modulator configured to modulate a phase of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of the first portion of the initial beam of light prior to it being directed into the environment.

33. The lidar sensor of Claim 32, wherein the determined distance is based at least on a time of return of the first reflected beam of light using at least the unique code.

34. The lidar sensor of any of Claims 31-33, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

35. The lidar sensor of 34, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

36. A lidar sensor comprising:

- a laser configured to emit an initial beam of light;
- a first fiber coupler in optical communication with the laser to receive and divide the initial beam of light into a transmitted portion and an internal portion;
- an optical synthesizer circuit in optical communication with the first fiber coupler to receive the transmitted portion of the initial beam of light from the first fiber coupler and to adjust a phase of the transmitted portion of the initial beam of light;
- a transmitter in optical communication with the optical synthesizer circuit to receive the transmitted portion with an adjusted phase from the optical synthesizer circuit and direct the transmitted portion into the environment;

a receiver configured to receive a reflected beam of light from the environment resulting from the transmitted portion of the initial beam of light;

a second fiber coupler in optical communication with the receiver and the first fiber coupler to combine the reflected beam of light and the internal portion of the initial beam of light into a combined beam of light; and

an optical sensor in optical communication with the second fiber coupler to receive the second beam of light.

37. The lidar sensor of Claim 36, wherein the transmitter and receiver are a single transceiver.

38. The lidar sensor of any of Claims 36-37, wherein the optical synthesizer circuit comprises one or more phase modulators, the phase modulators being configured to embed a unique code into a modulated phase of the transmitted portion of the initial beam of light.

39. The lidar sensor of Claim 38, wherein the one or more phase modulators are also configured to embed a periodic pattern combined with the unique code into the modulated phase of the transmitted portion of the initial beam of light.

40. The lidar sensor of any of Claims 36-39, wherein the optical synthesizer circuit further comprises at least two different optical paths and is configured to separate the transmitted portion of the initial beam of light into a first portion and a second portion along the at least two different optical paths and recombine the first portion and second portion prior to being received by the transmitter.

41. The lidar sensor of Claim 40, wherein the optical synthesizer circuit comprises a third fiber coupler configured to separate the transmitted portion of the initial beam of light into the first portion and the second portion, and a fourth fiber coupler configured to recombine the first portion and the second portion prior to being received by the transmitter.

42. The lidar sensor of any of Claims 40-41, wherein the optical synthesizer circuit comprises one or more phase modulators configured to embed different unique codes into modulated phases of each of the first portion and the second portion prior to being recombined.

43. The lidar sensor of any of Claims 36-42, wherein the optical synthesizer circuit comprises a frequency shifter configured to adjust a frequency of the transmitted portion of the initial beam of light prior to being directed into the environment.

44. The lidar sensor of any of Claims 36-43, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

45. The lidar sensor of Claim 44, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

46. A method of operating a lidar sensor to measure a distance to an object and a velocity of the object, the method comprising:

splitting a beam of light into a transmitted portion and an internal portion;

directing the transmitted portion into the environment;

receiving a reflected beam resulting from the transmitted portion being directed into the environment;

estimating a distance to a point of reflection using the reflected beam and the internal portion;

estimating a radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the reflected beam of light and the internal portion; and

estimating a lateral velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift of the reflected beam and the determined radial velocity.

47. The method of Claim 46, further comprising modulating a phase of the transmitted portion over a period of time with a unique code to embed the unique code into a modulated phase of the transmitted portion prior to it being directed into the environment.

48. The method of Claim 47, wherein the estimated distance is determined based at least on a time of return of the reflected beam using at least the unique code.

49. A lidar sensor comprising:

an optical sensor configured to produce signals based at least on receiving one or more beams of light;

a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor, wherein the optical sensor is configured to receive both the internal portion of the initial beam of light and a reflected

beam of light resulting from the first portion of the initial beam of light being reflected at a point of reflection in the environment; and

a processor configured to:

receive signals from the optical sensor;

identify the reflected beam of light as having resulted from the first portion of the initial beam of light;

determine a distance to the point of reflection based at least on the reflected beam of light and the internal portion of the initial beam of light;

determine a radial velocity of the point of reflection relative to the lidar sensor; and

determine a lateral velocity of the point of reflection relative to the lidar sensor based at least on a sidelobe width of the reflected beam.

50. The lidar sensor of Claim 49, further comprising a phase modulator configured to modulate a phase of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of the first portion of the initial beam of light prior to it being directed into the environment.

51. The lidar sensor of Claim 50, wherein the determined distance is based at least on a time of return of the reflected beam of light using at least the unique code.

52. The lidar sensor of any of Claims 49-51, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

53. The lidar sensor of Claim 52, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

54. The lidar sensor of any of Claims 49-53, wherein the processor is configured to determine the lateral velocity of the point of reflection relative to the lidar sensor based at least on the determined radial velocity.

55. The lidar sensor of any of Claims 49-54, wherein the processor is configured to determine the lateral velocity of the point of reflection relative to the lidar sensor based at least on the determined distance.

56. The lidar sensor of any of Claims 49-55, wherein the processor is configured to determine the radial velocity of the point of reflection relative to the lidar sensor based at least on a Doppler shift.

57. The lidar sensor of any of Claims 49-56, wherein the processor is configured to determine the radial velocity of the point of reflection relative to the lidar sensor based at least on a time derivative of a difference in phases of the light field between the reflected beam of light and the internal portion of the initial beam of light.

58. The lidar sensor of any of Claims 49-57, wherein the processor is configured to determine the sidelobe width using at least a best-fit algorithm.

59. The lidar sensor of any of Claims 49-58, wherein the processor is configured to determine the sidelobe width using at least a machine-learning algorithm.

60. The lidar sensor of any of Claims 49-59, wherein the processor is configured to determine one or more characteristics of a surface of an object at the point of reflection based at least on a spectral analysis of the reflected beam of light.

61. A method of operating a lidar sensor to measure a distance to an object and a velocity of the object, the method comprising:

splitting a beam of light into a transmitted portion and an internal portion;

directing the transmitted portion into the environment;

receiving a reflected beam resulting from the transmitted portion being directed into the environment;

determining a distance to a point of reflection using the reflected beam and the internal portion;

determining a radial velocity of the point of reflection relative to the lidar sensor; and

determining a lateral velocity of the point of reflection relative to the lidar sensor based at least on a sidelobe width of the reflected beam.

62. The method of claim 61, further comprising modulating a phase of the transmitted portion over a period of time with a unique code to embed the unique code into a modulated phase of the transmitted portion prior to it being directed into the environment.

63. The method of claim 62, wherein the distance is determined based at least on a time of return of the reflected beam using at least the unique code.

64. The method of any of Claim 61-63, wherein the lateral velocity of the point of reflection relative to the lidar sensor is determined based at least on the determined radial velocity.

65. The method of any of Claims 61-64, wherein the lateral velocity of the point of reflection relative to the lidar sensor is determined based at least on the determined distance.

66. The method of any of Claims 61-65, wherein the radial velocity of the point of reflection relative to the lidar sensor is determined based at least on a Doppler shift.

67. The method of any of Claims 61-66, wherein the radial velocity of the point of reflection relative to the lidar sensor is determined based at least on a time derivative of a difference in phases of the light field between the reflected beam and the internal portion of the beam of light.

68. The method of any of Claims 61-67, wherein the sidelobe width is determined using at least a best-fit algorithm.

69. The method of any of Claims 61-68, wherein the sidelobe width is determined using at least a machine-learning algorithm.

70. The method of any of Claim 61-69, further comprising the step of determining one or more characteristics of a surface at the point of reflection based at least on a spectral analysis of the reflected beam.

71. A lidar sensor comprising:

- an optical sensor configured to produce signals based at least on receiving one or more beams of light;

- a laser configured to emit an initial beam of light, a first portion of the initial beam of light being directed into the environment and an internal portion of the initial beam of light being directed to the optical sensor, wherein the optical sensor is configured to receive both the internal portion of the initial beam of light and a reflected beam of light resulting from the first portion of the initial beam of light being reflected at a first point of reflection in the environment; and

- a processor configured to:

- receive signals from the optical sensor;

- identify the reflected beam of light as having resulted from the first portion of the initial beam of light;

- determine a distance to the point of reflection based at least on the reflected beam of light and the internal portion of the initial beam of light; and

determine one or more characteristics of a surface of an object at the point of reflection based at least on a spectral analysis of the reflected beam of light.

72. The lidar sensor of Claim 71, further comprising a phase modulator configured to modulate a phase of the first portion of the initial beam of light over a period of time with a unique code to embed the unique code into a modulated phase of the first portion of the initial beam of light prior to it being directed into the environment.

73. The lidar sensor of Claim 72, wherein the determined distance is based at least on a time of return of the reflected beam of light using at least the unique code.

74. The lidar sensor of any of Claims 71-73, wherein the lidar sensor is configured to accurately determine distances over 10 meters.

75. The lidar sensor of Claim 74, wherein the lidar sensor is configured to accurately determine distances over 100 meters.

76. The lidar sensor of any of Claims 71-75, wherein the processor is configured to determine a roughness of the surface based at least on an amplitude of sidelobes of the reflected beam.

77. The lidar sensor of any of Claims 71-76, wherein the processor is configured to determine a material of the object based on the spectral analysis of the reflected beam.

78. The lidar sensor of Claim 77, wherein the processor is configured to use a machine learning algorithm to determine the material.

79. The lidar sensor of any of Claims 77-78, wherein the processor is configured to use a combination of relative frequency spacing and amplitude of sidelobes of the reflected beam of light to determine the material.

80. The lidar sensor of any of Claims 77-79, wherein the processor is configured to identify patterns in a spectrum of the reflected beam of light to determine the material.

81. The lidar sensor of any of Claims 71-80, wherein the spectral analysis comprises an analysis of patterns in a spectrum of the reflected beam of light.

82. A method of operating a lidar sensor to measure a distance to an object and a velocity of the object, the method comprising:

splitting a beam of light into a transmitted portion and an internal portion;
directing the transmitted portion into the environment;

receiving a reflected beam resulting from the transmitted portion being directed into the environment;

determining a distance to a point of reflection using the reflected beam and the internal portion;

determining a radial velocity of the point of reflection relative to the lidar sensor; and

determining one or more characteristics of a surface at the point of reflection based at least on a spectral analysis of the reflected beam.

83. The method of Claim 82, further comprising modulating a phase of the transmitted portion over a period of time with a unique code to embed the unique code into a modulated phase of the transmitted portion prior to it being directed into the environment.

84. The method of any of Claims 82-83, wherein the distance is determined based at least on a time of return of the reflected beam using at least the unique code.

85. The method of any of Claims 82-84, wherein the one or more characteristics comprises a roughness of the surface, and the roughness is determined based at least on an amplitude of sidelobes of the reflected beam.

86. The method of any of Claims 82-85, wherein the one or more characteristics comprises a material of the surface.

87. The method of Claim 86, wherein the material is determined based at least on a spectral analysis of the reflected beam using machine learning.

88. The method of any of Claims 86-87, wherein the material is determined based at least on a combination of relative frequency spacing and amplitude of sidelobes of the reflected beam.

89. The method of any of Claims 86-88, wherein the material is determined based at least on patterns in a spectrum of the reflected beam.

90. The method of any of Claims 82-89, wherein the spectral analysis comprises an analysis of patterns in a spectrum of the reflected beam of light.

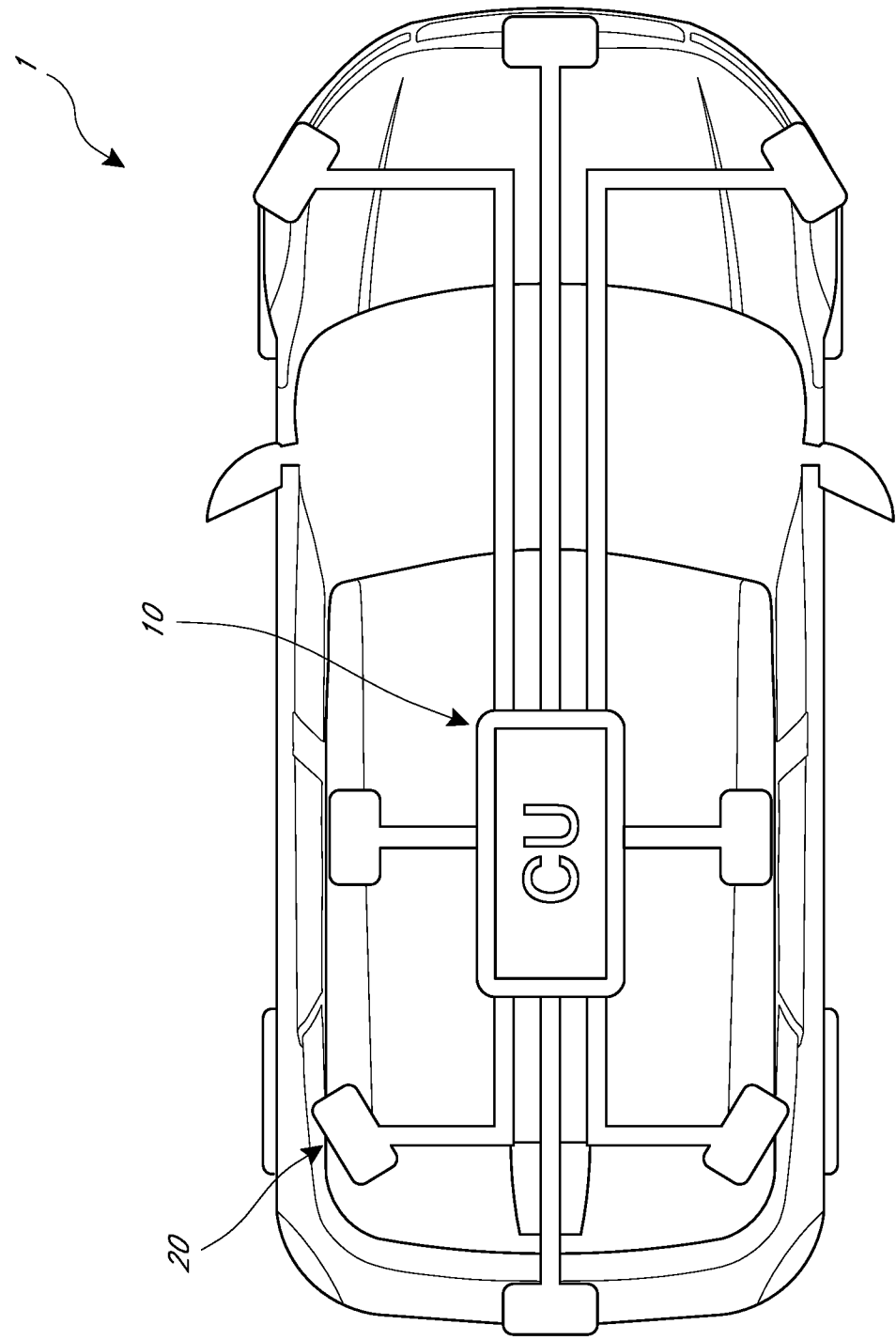
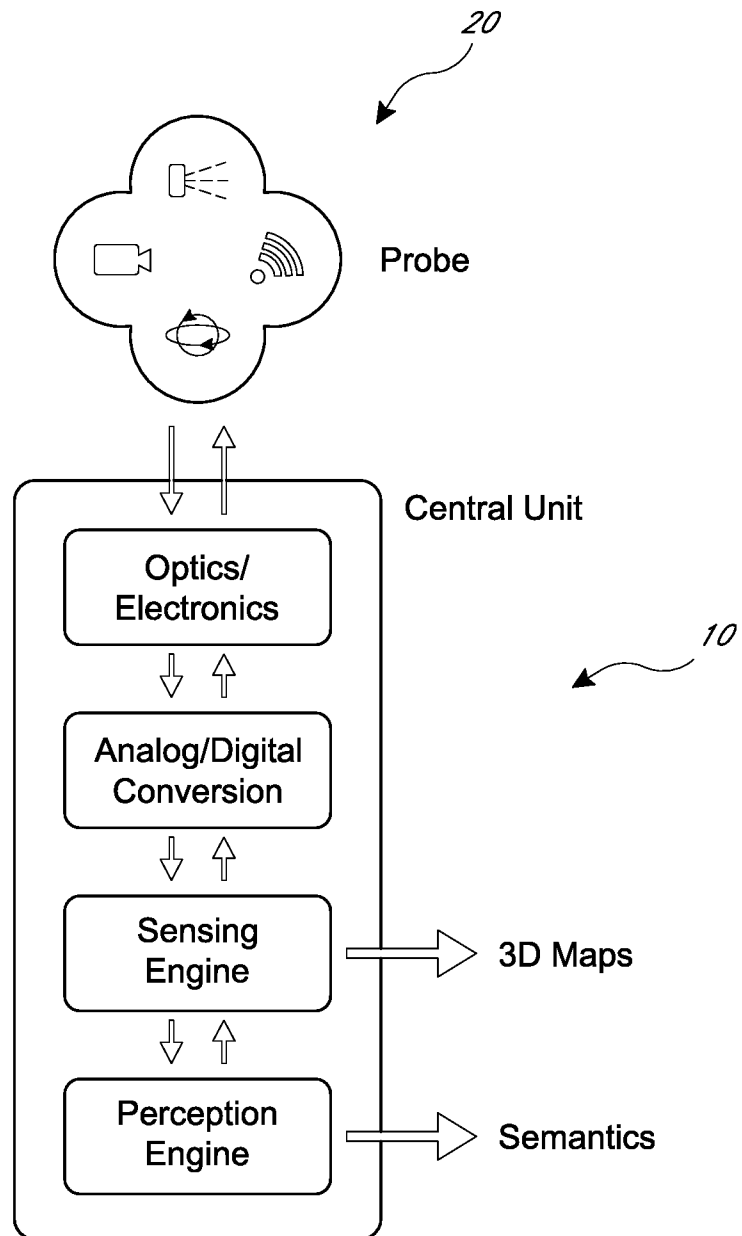
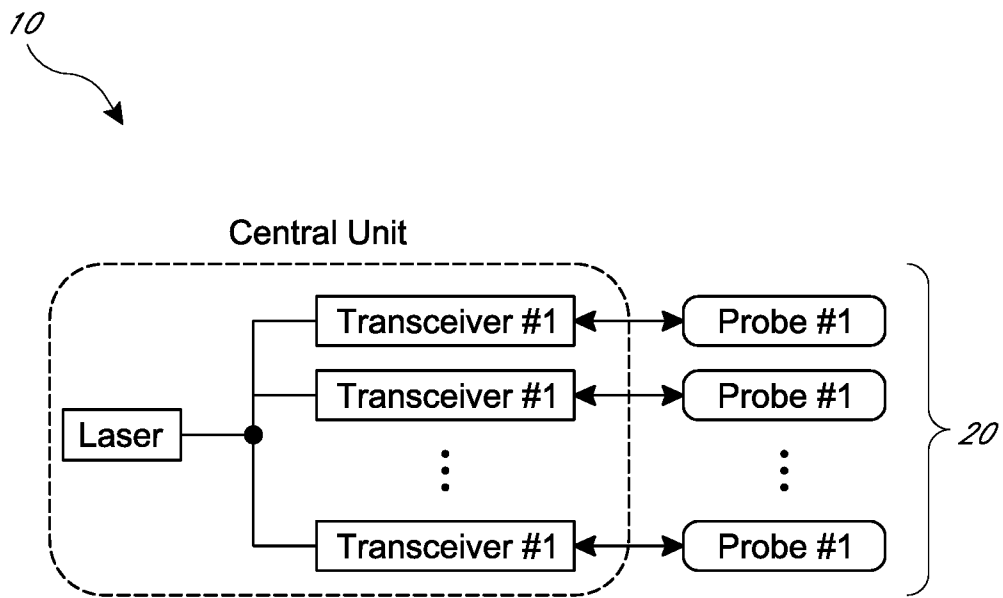


FIG. 1

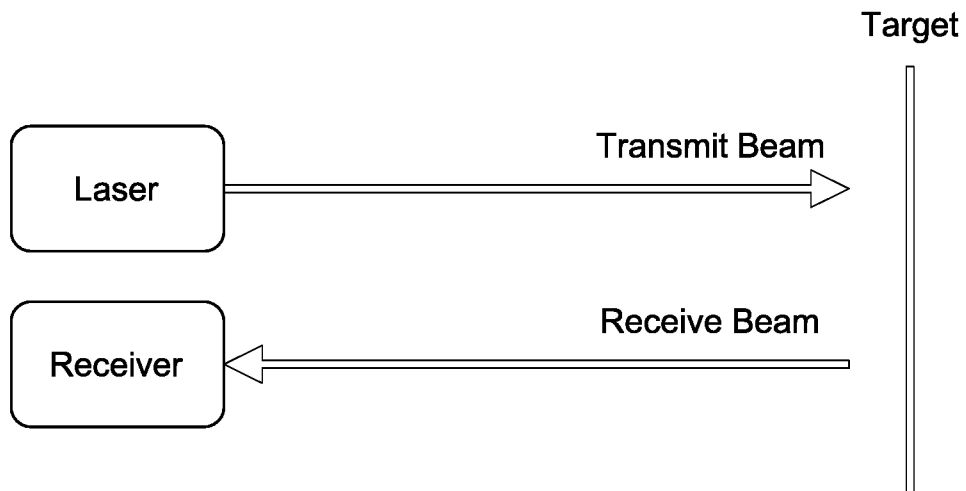
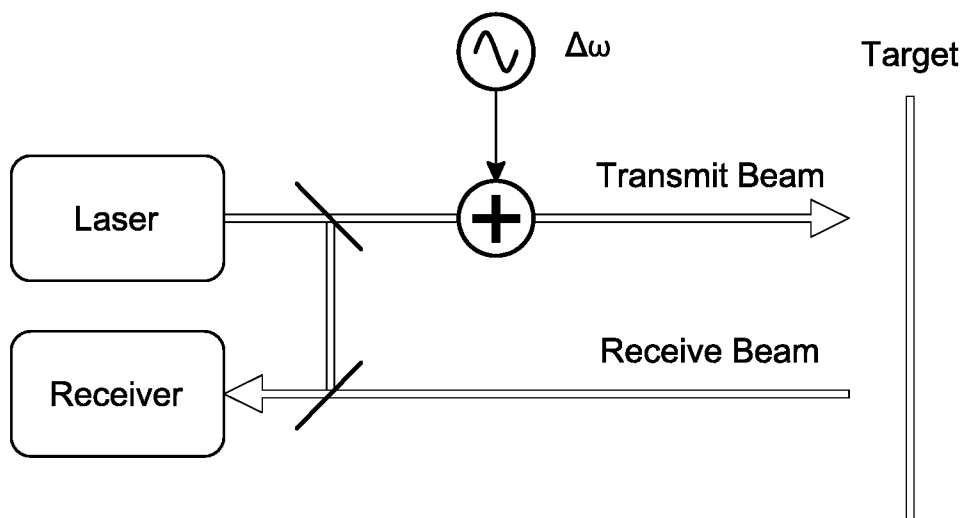
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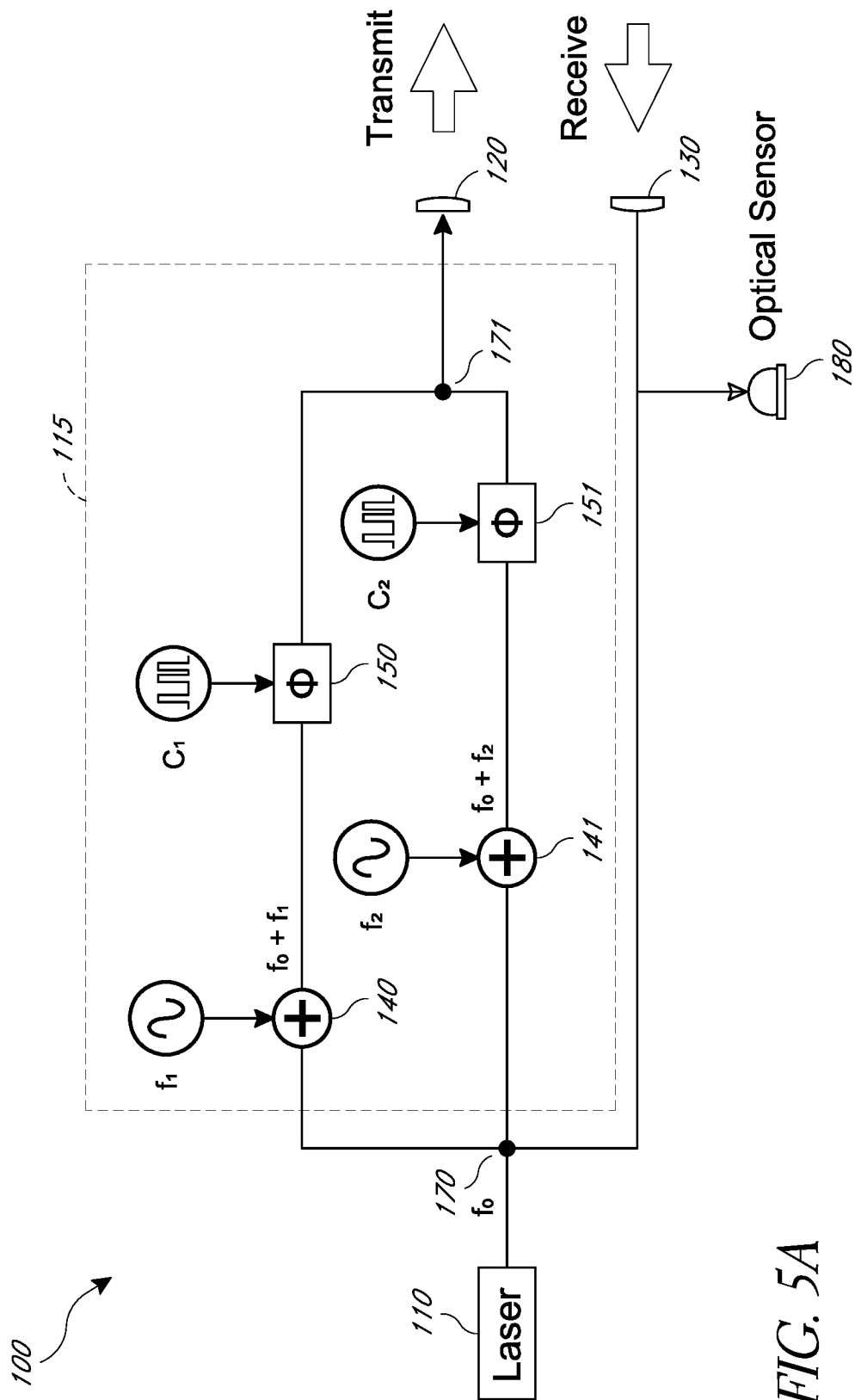
*FIG. 2*

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*FIG. 3*

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*FIG. 4A**FIG. 4B*



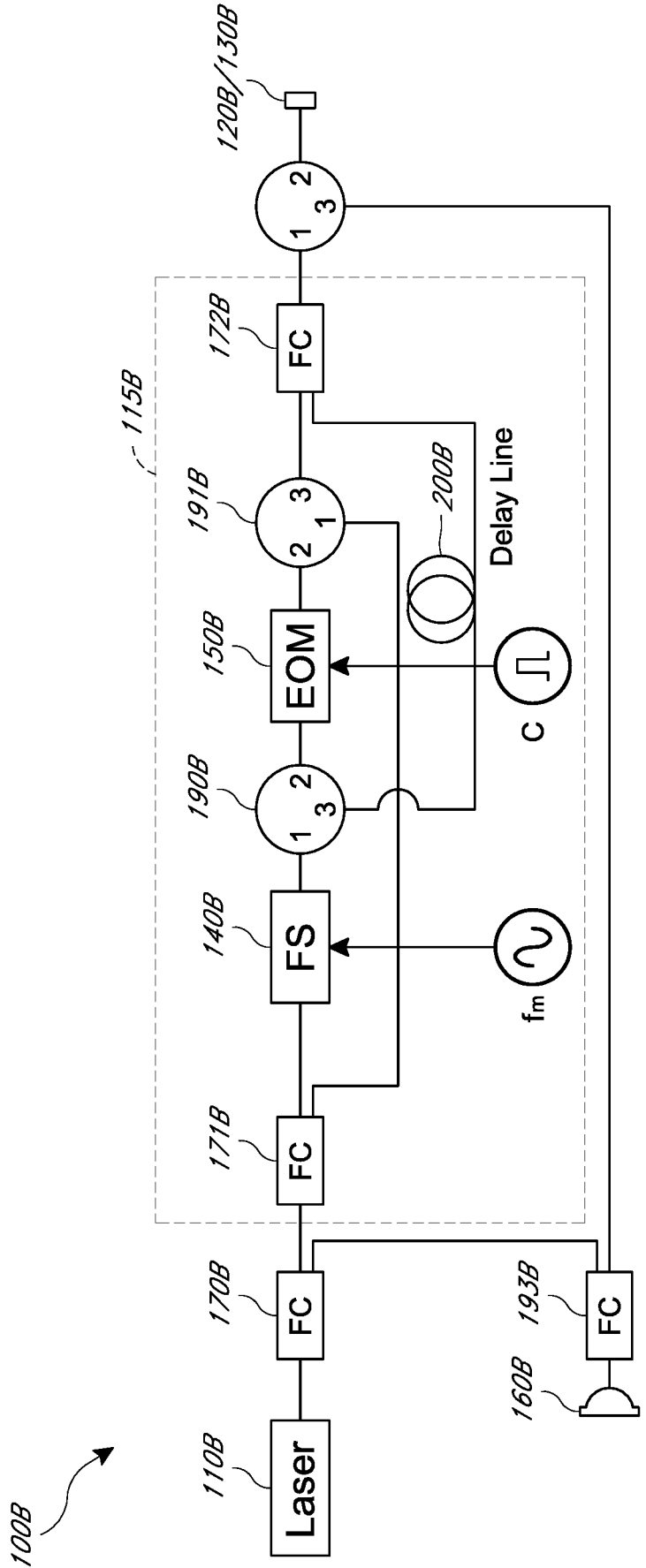
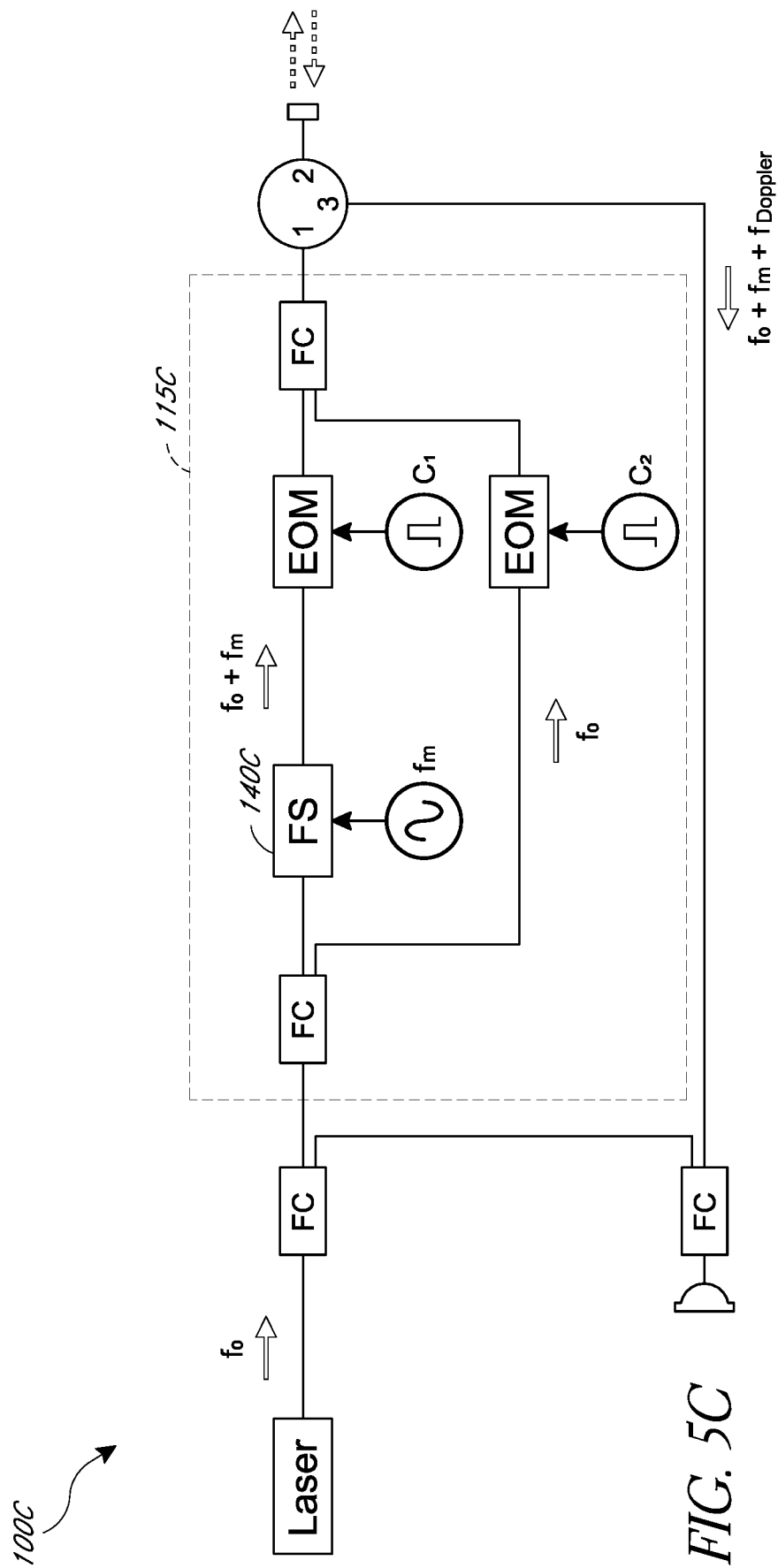
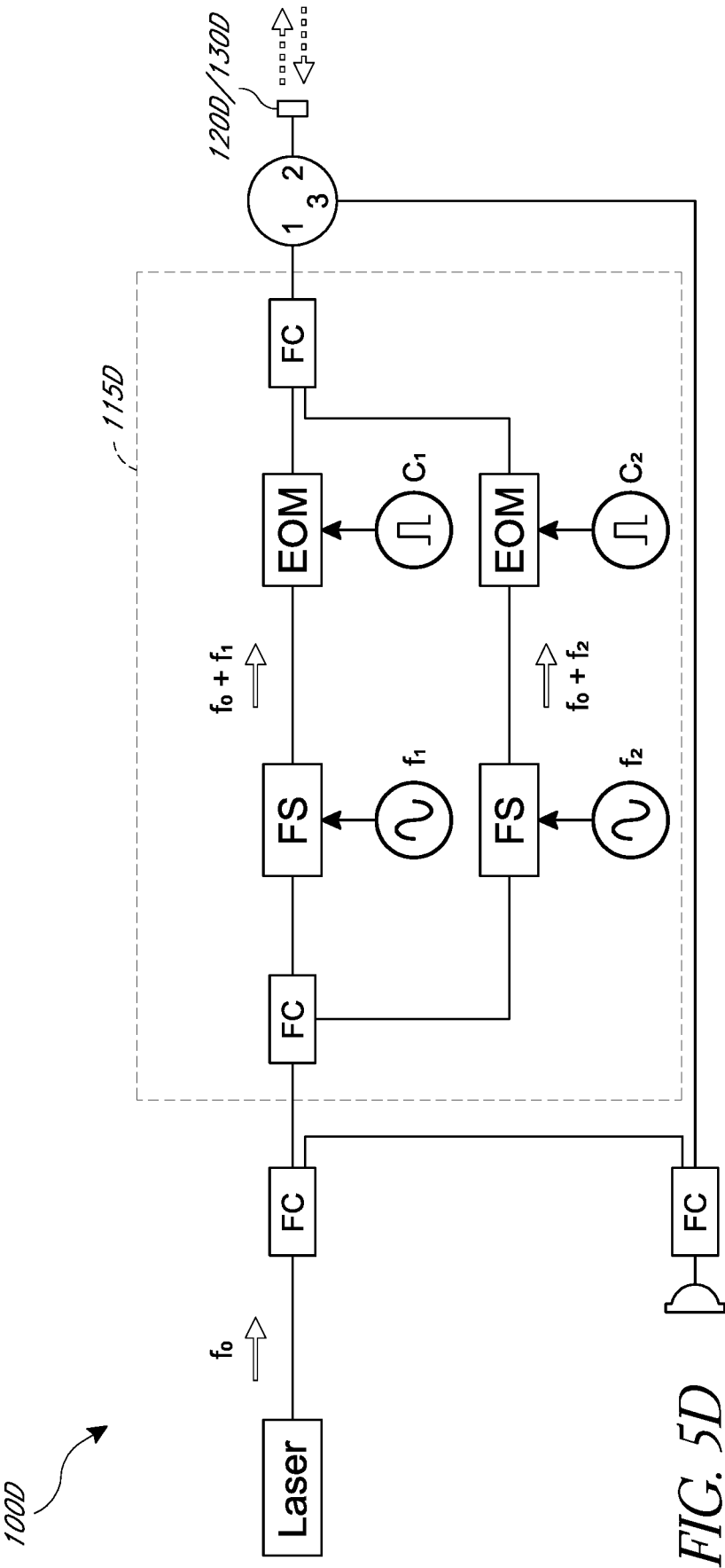
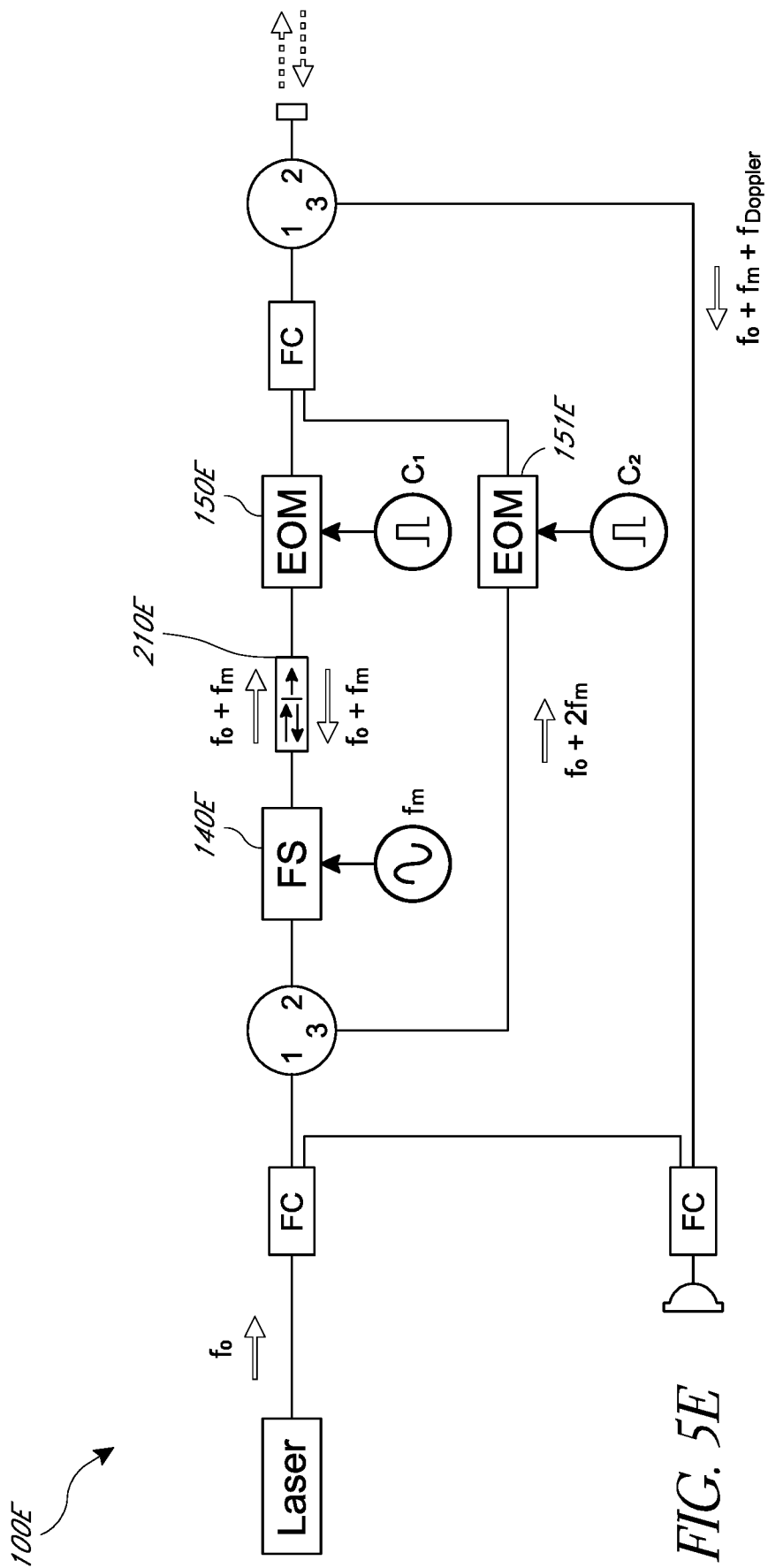


FIG. 5B





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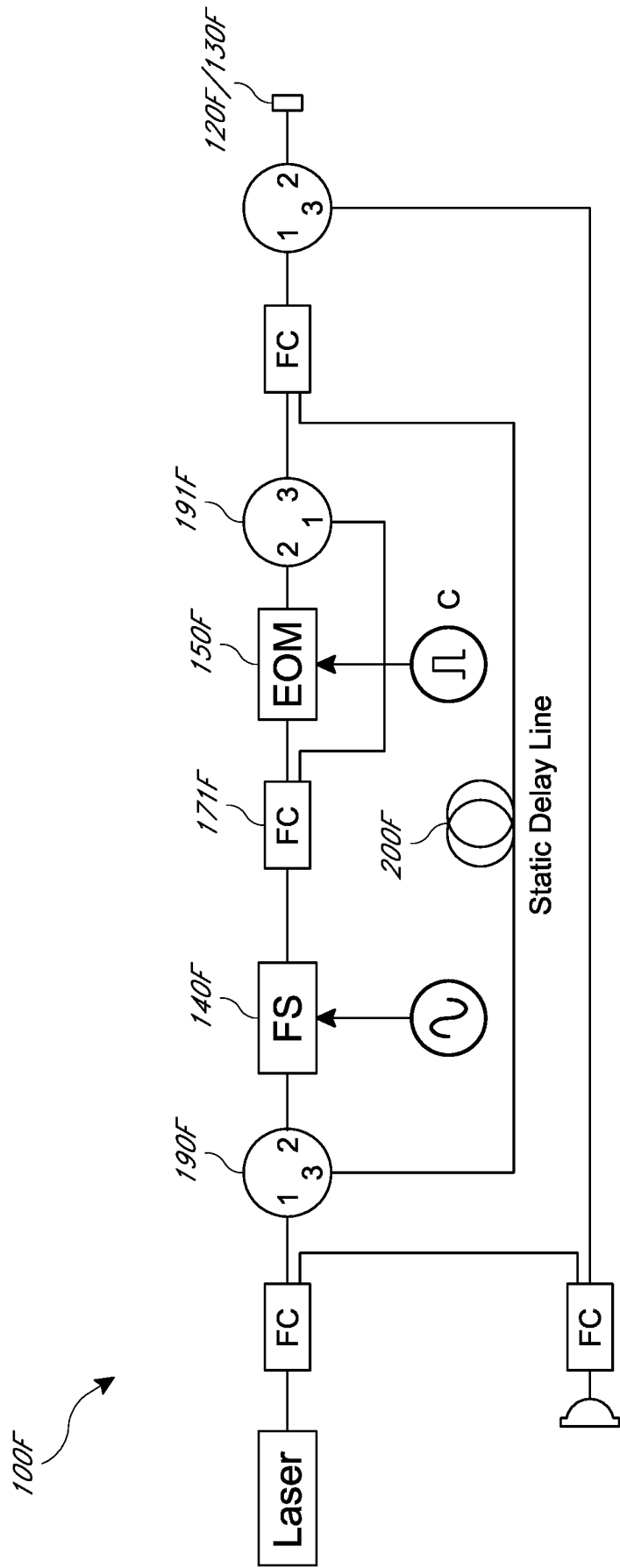


FIG. 5F

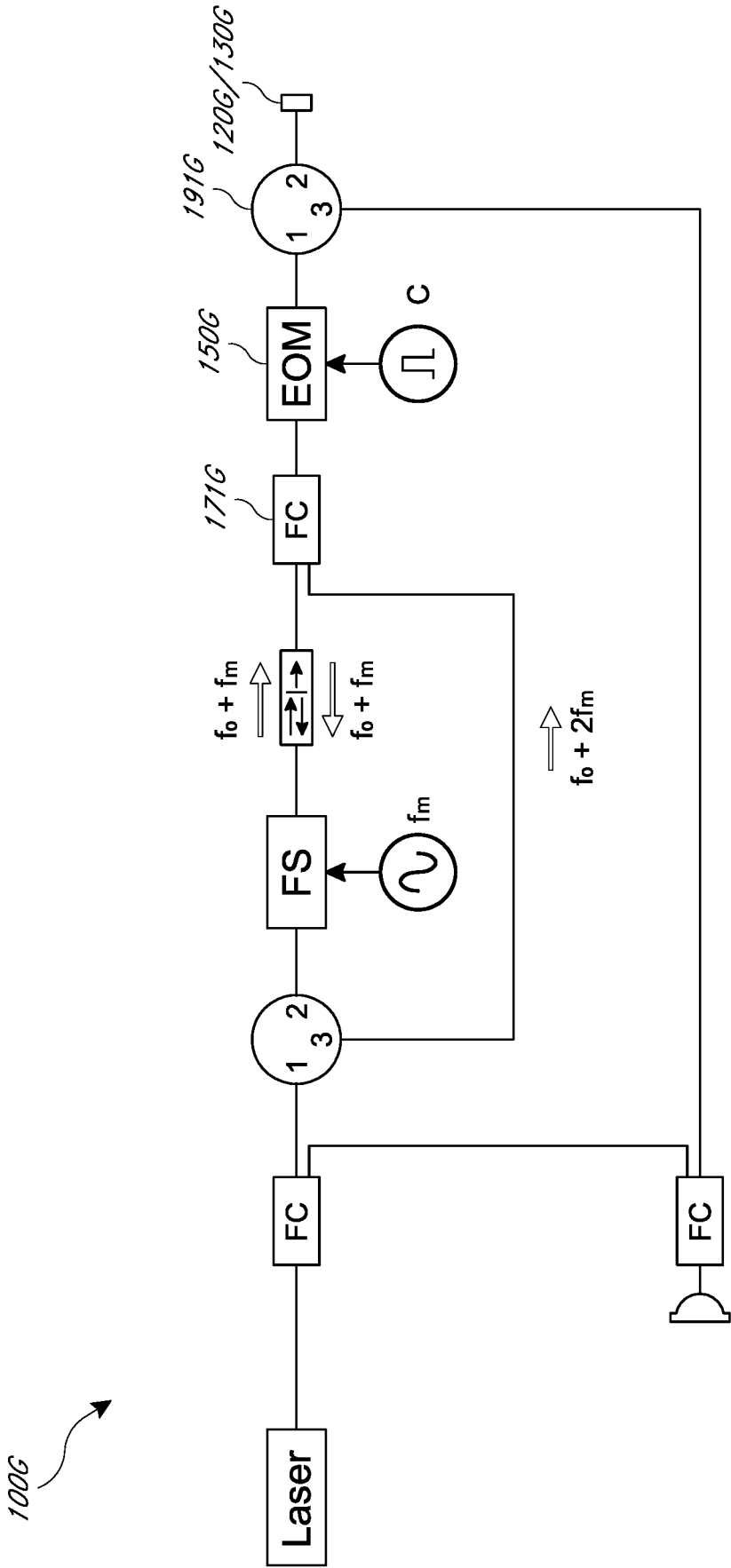


FIG. 5G

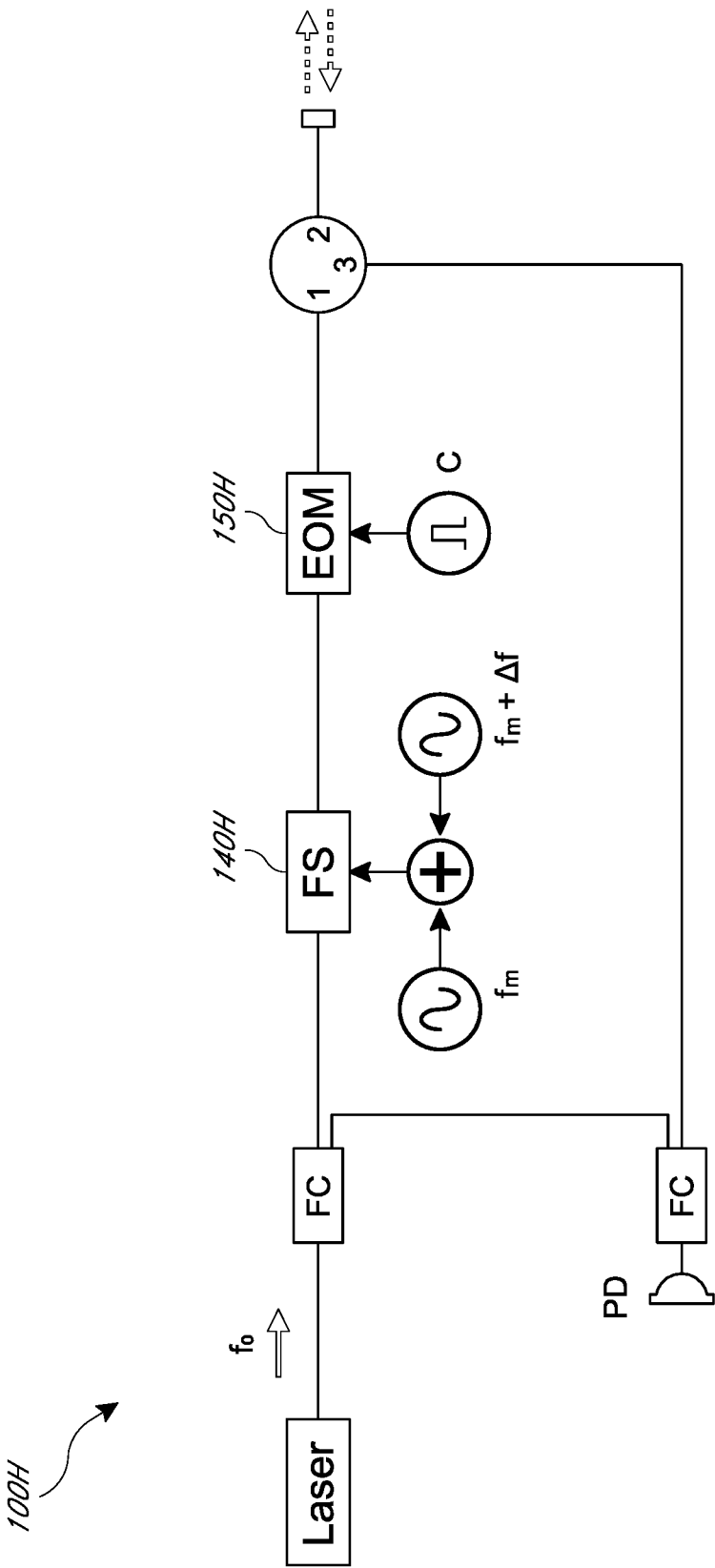


FIG. 5H

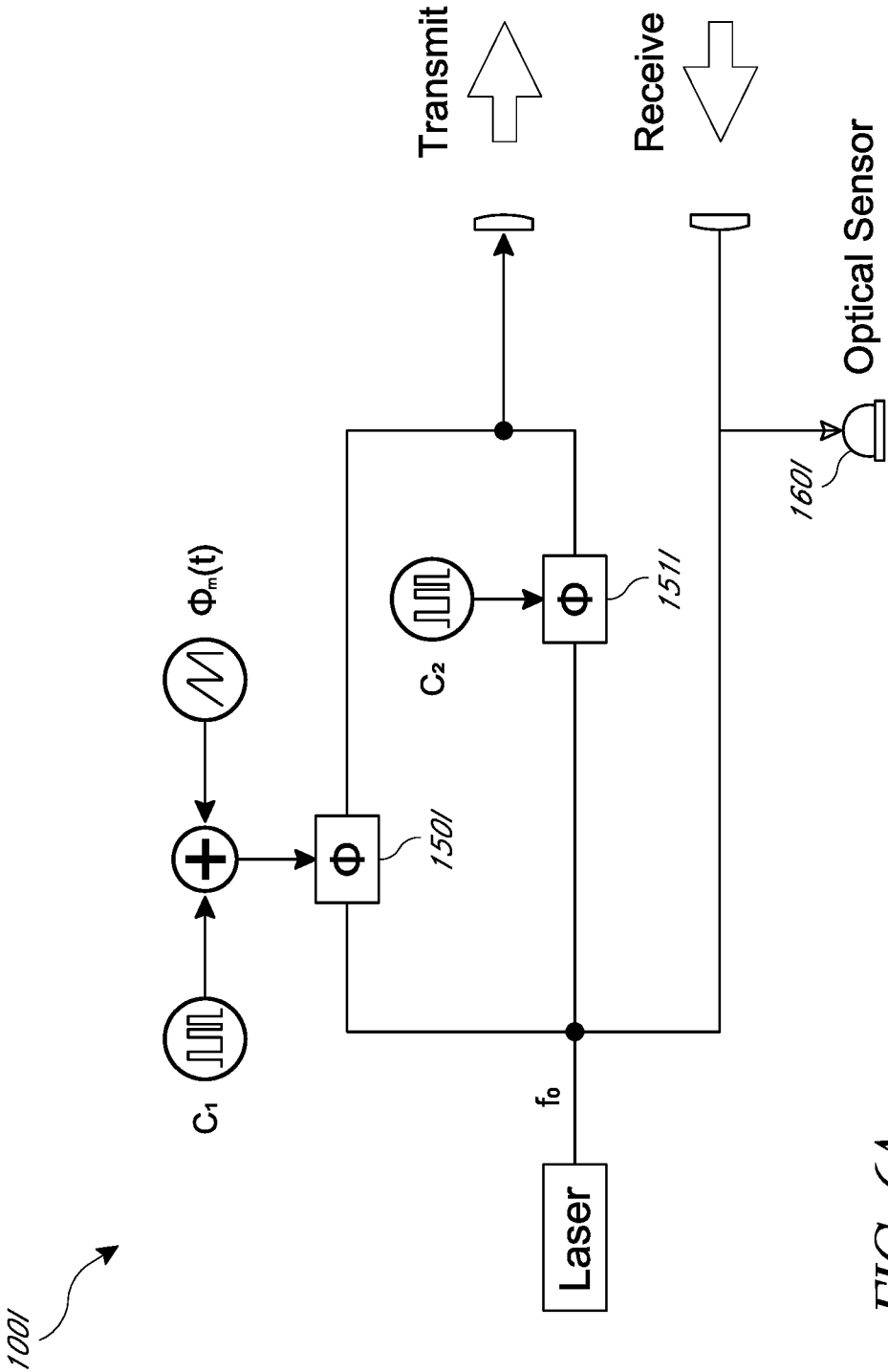
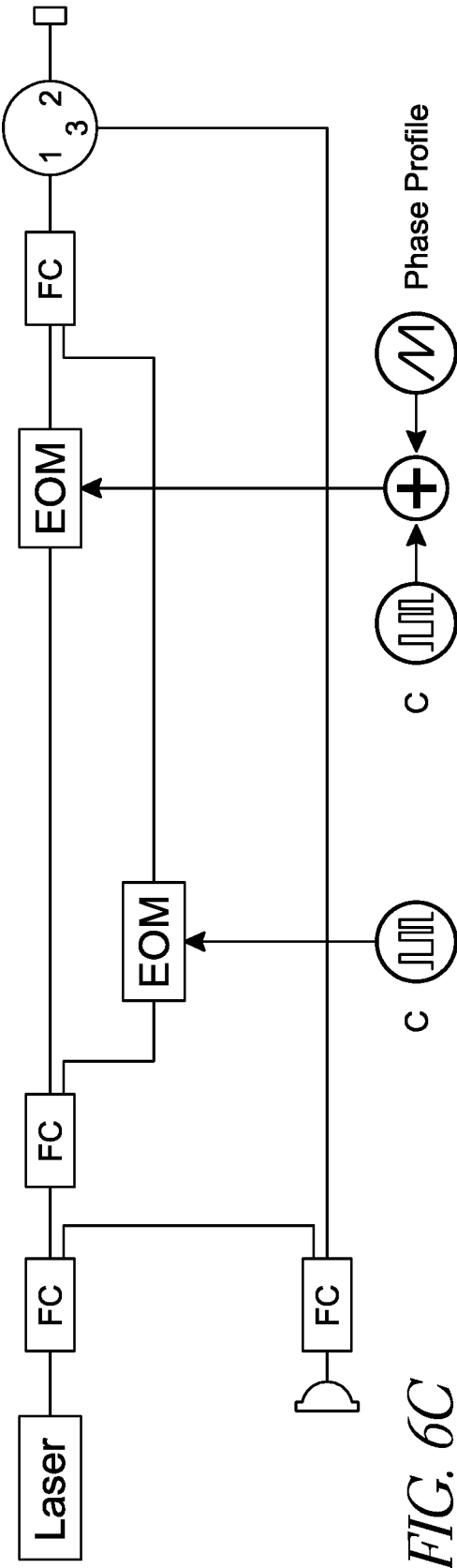
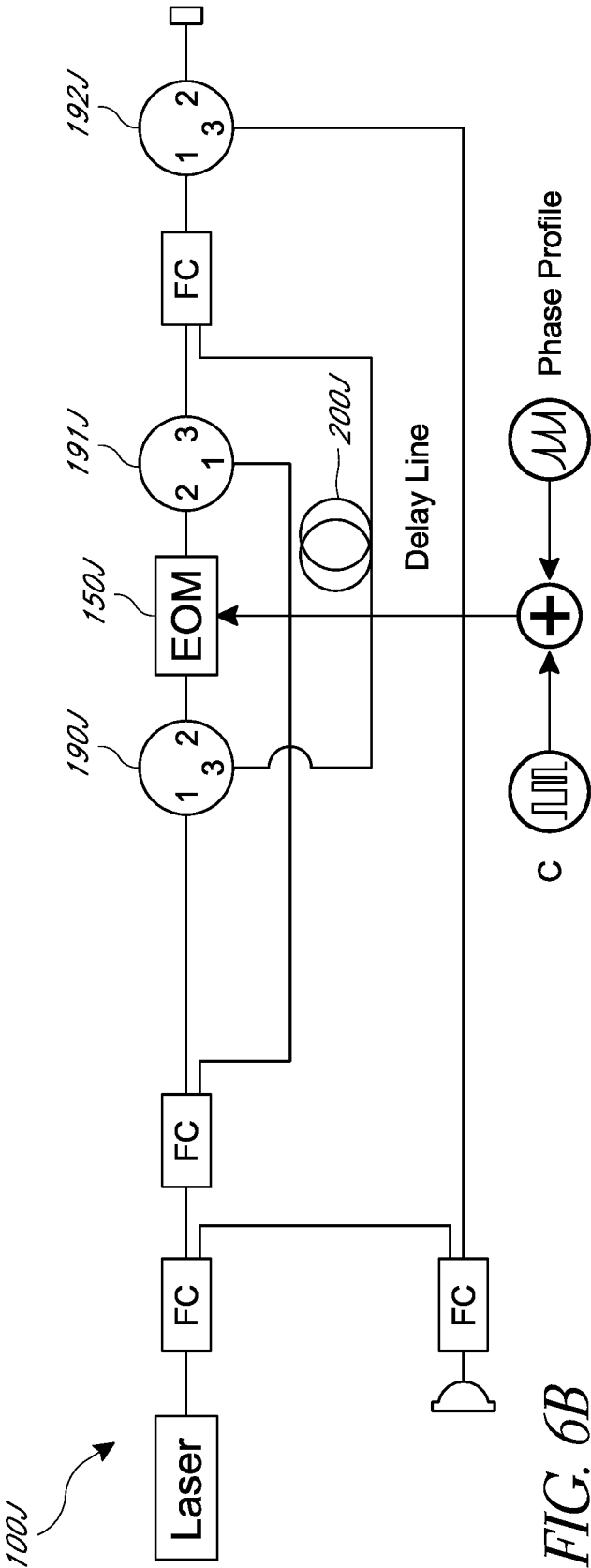
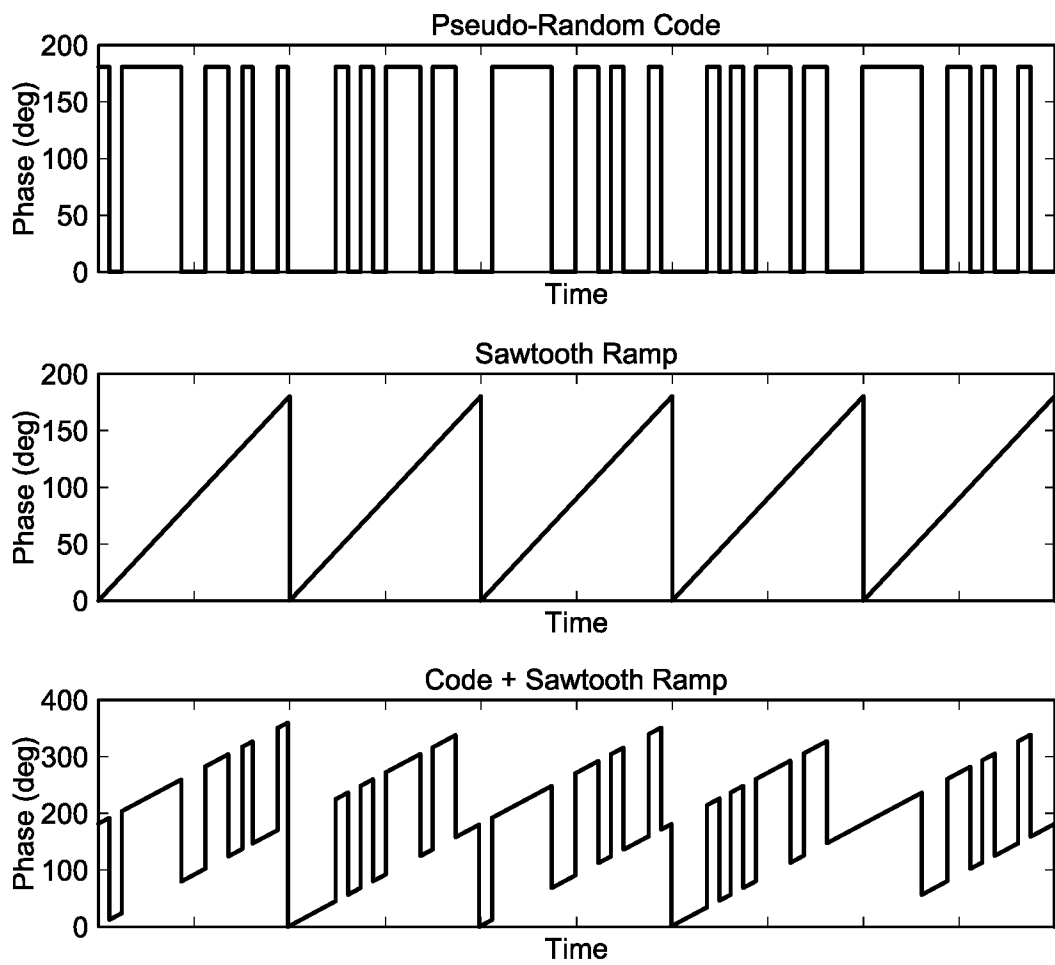


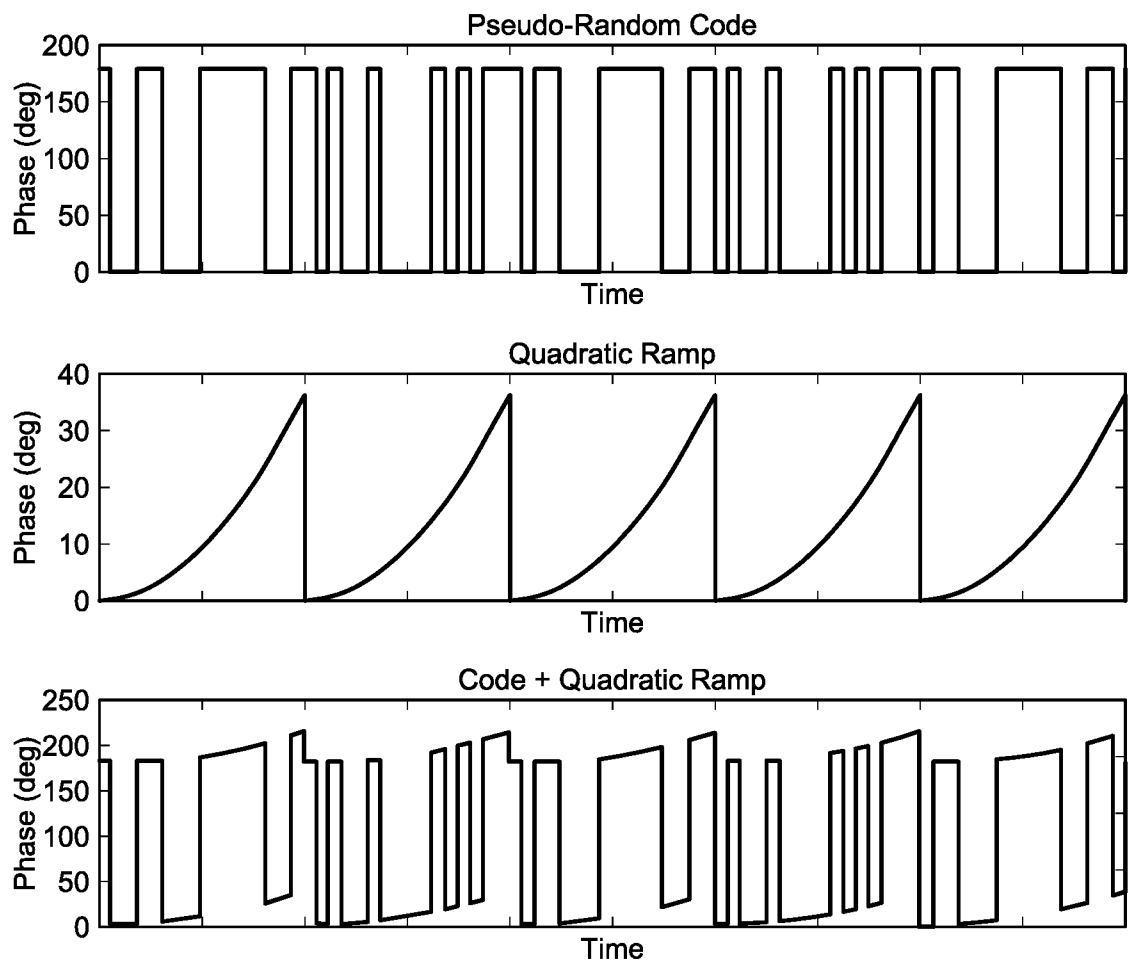
FIG. 6A



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*FIG. 7A*

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*FIG. 7B*

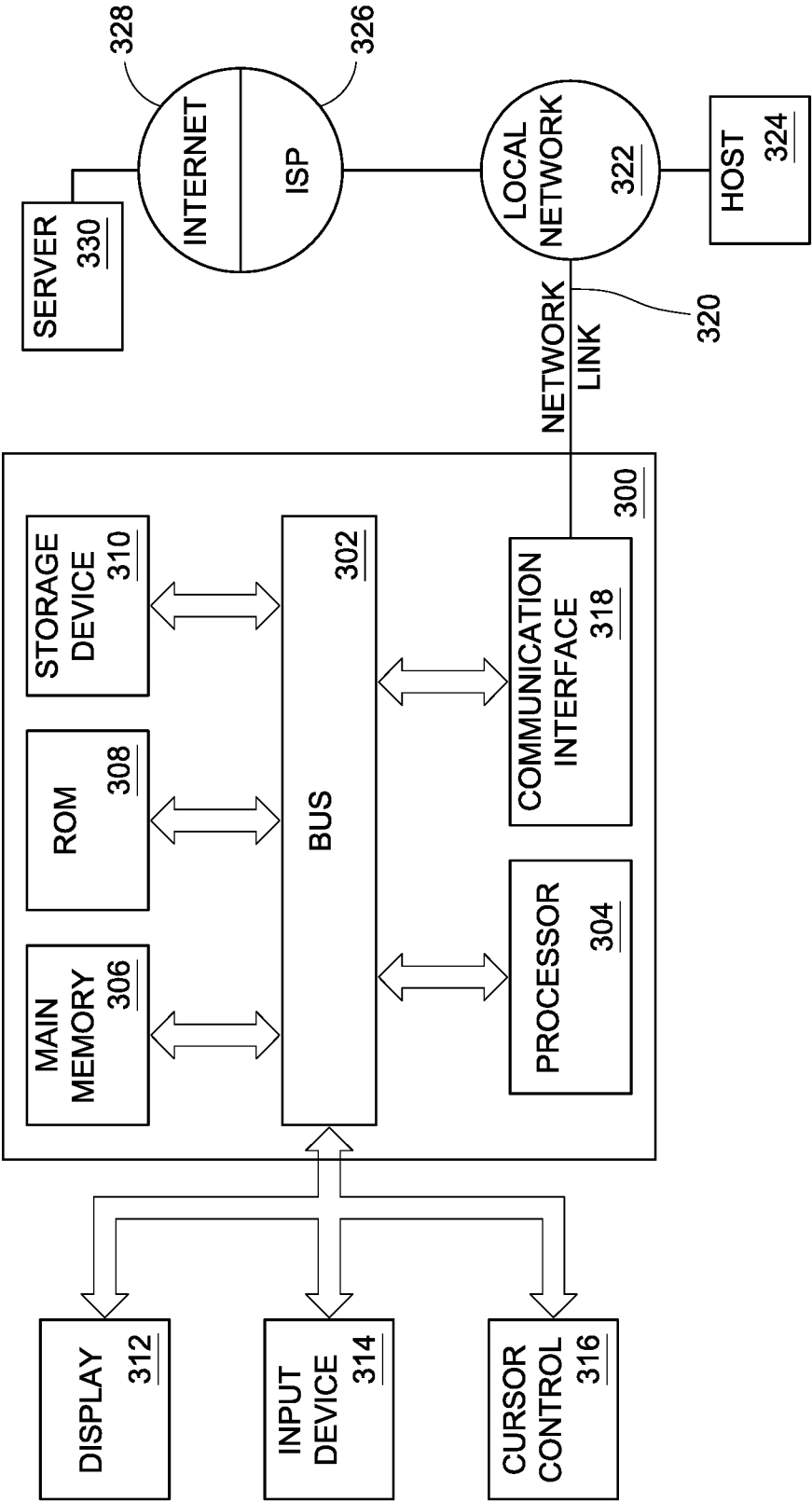
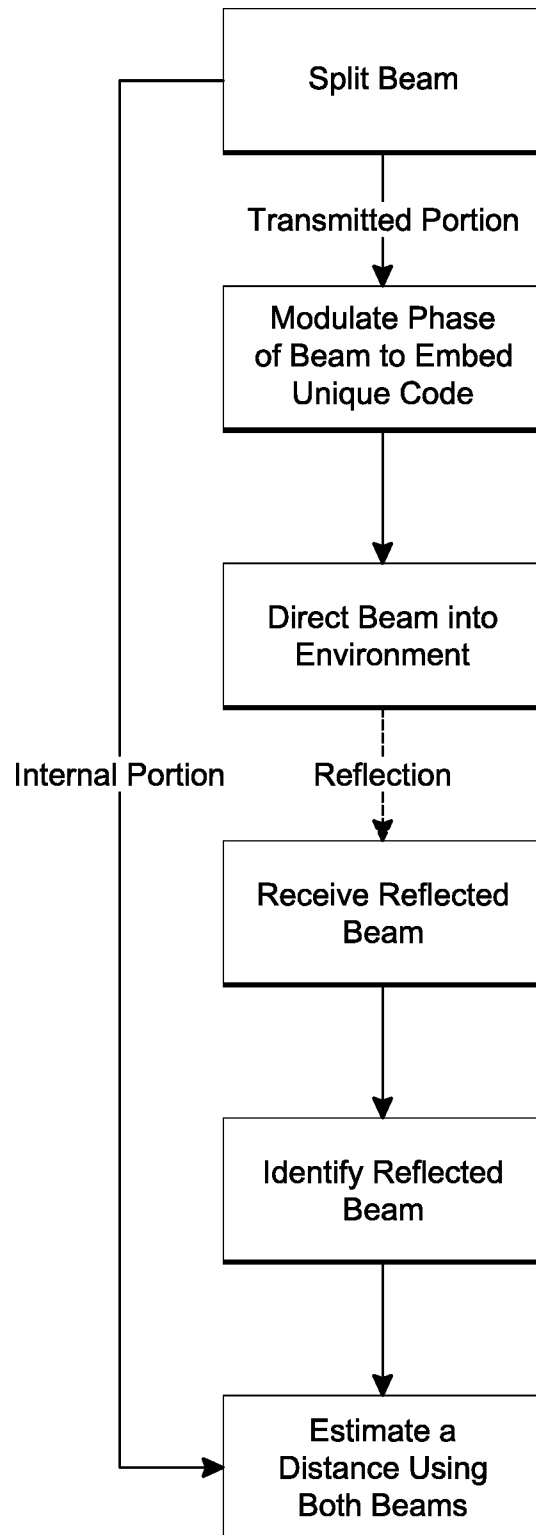
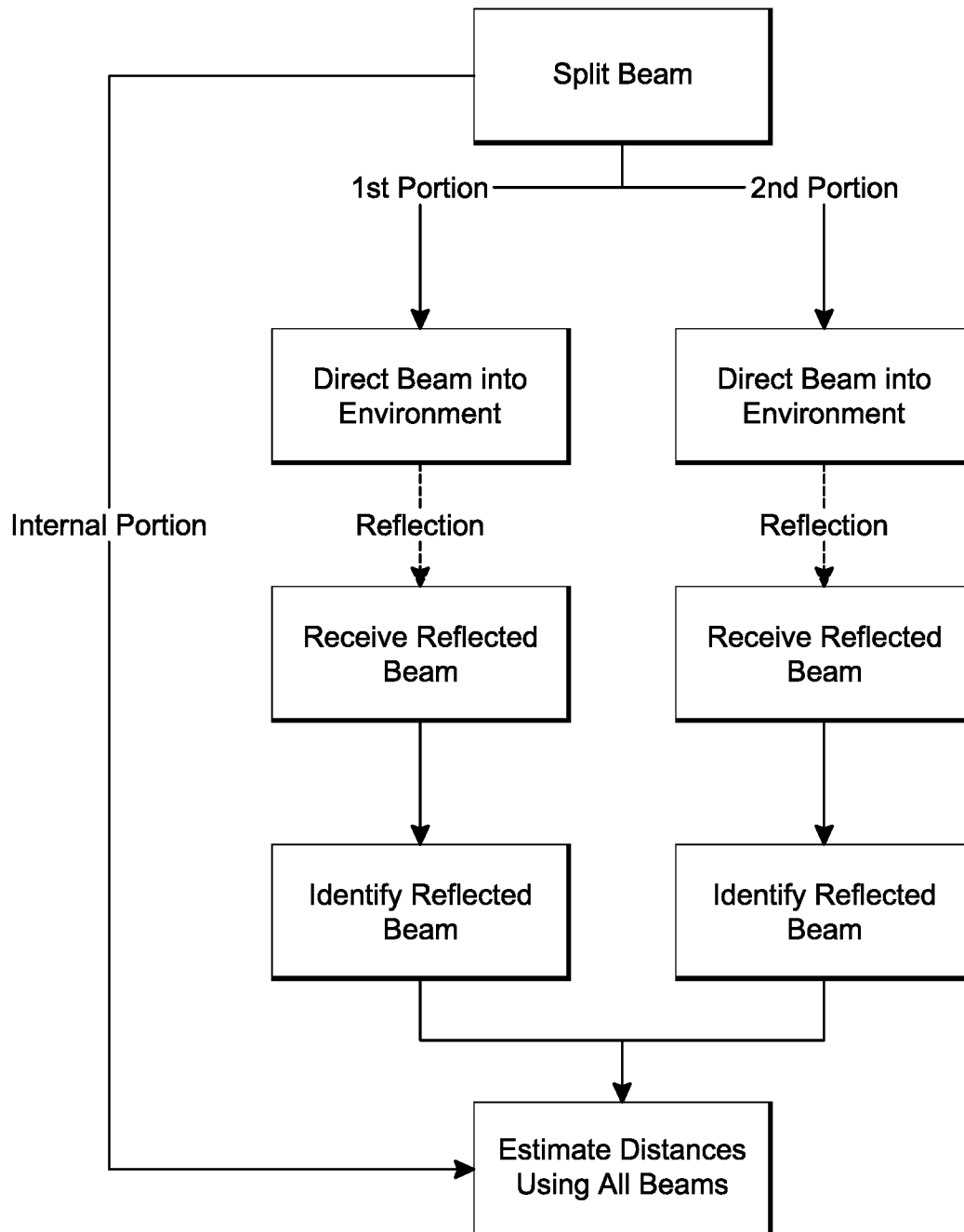


FIG. 8

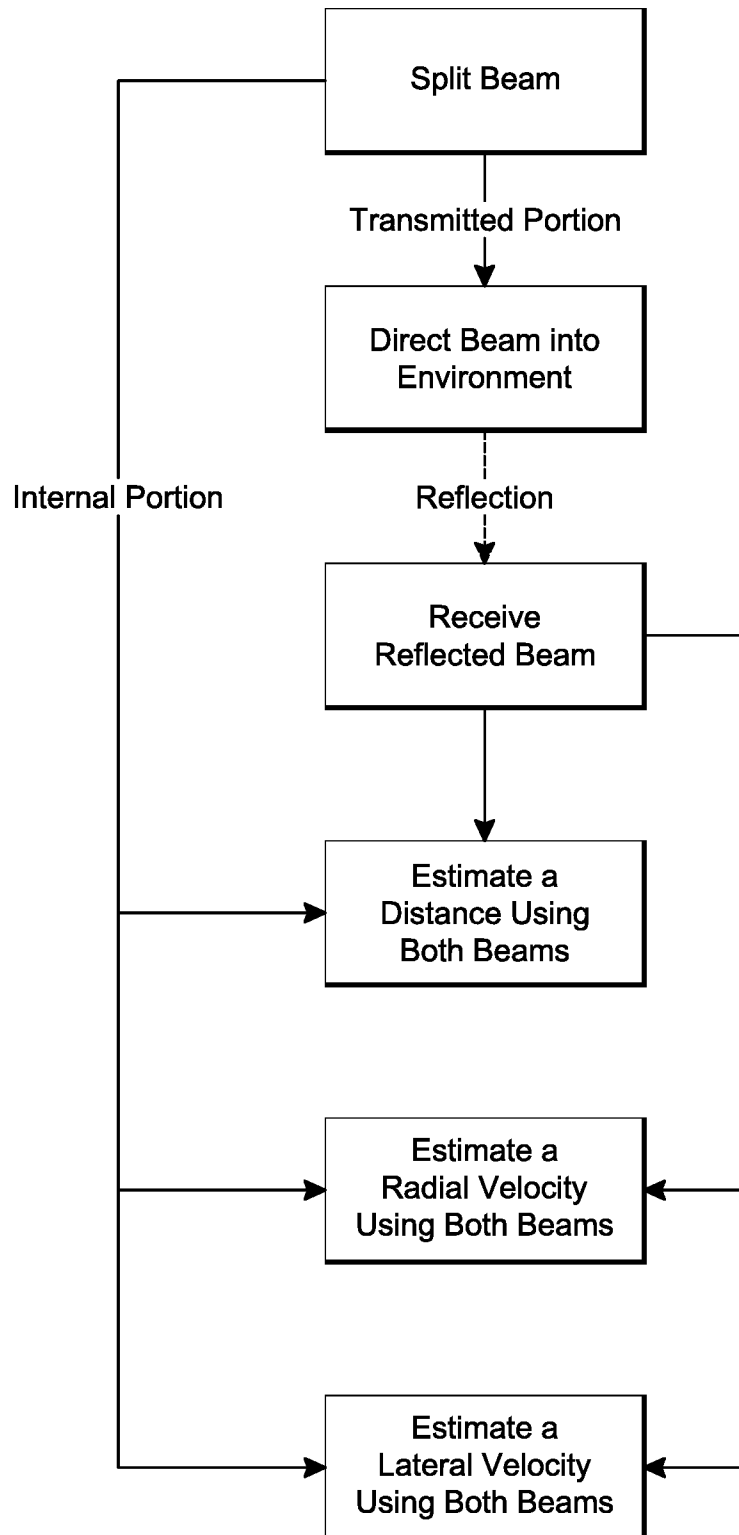
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*FIG. 9*

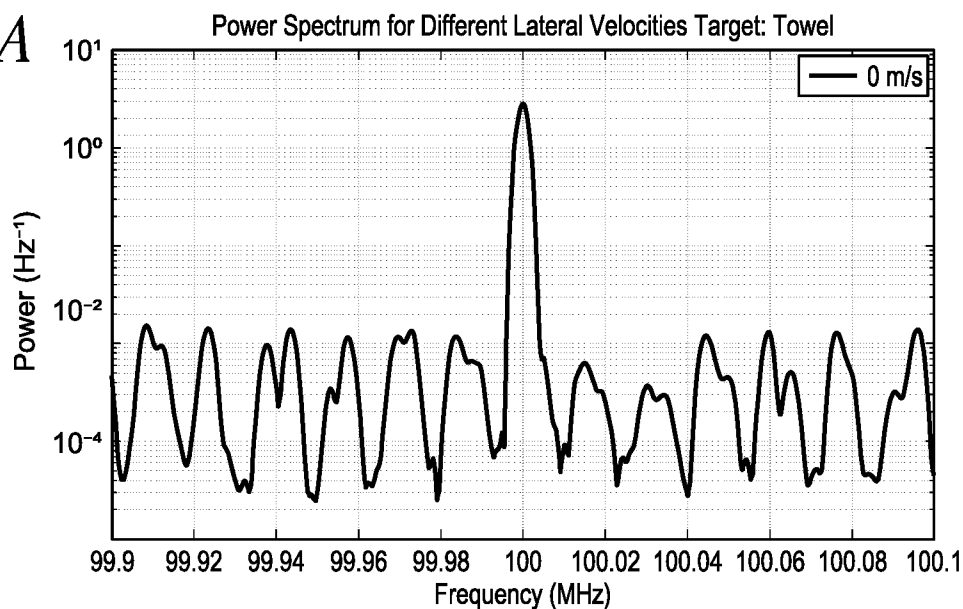
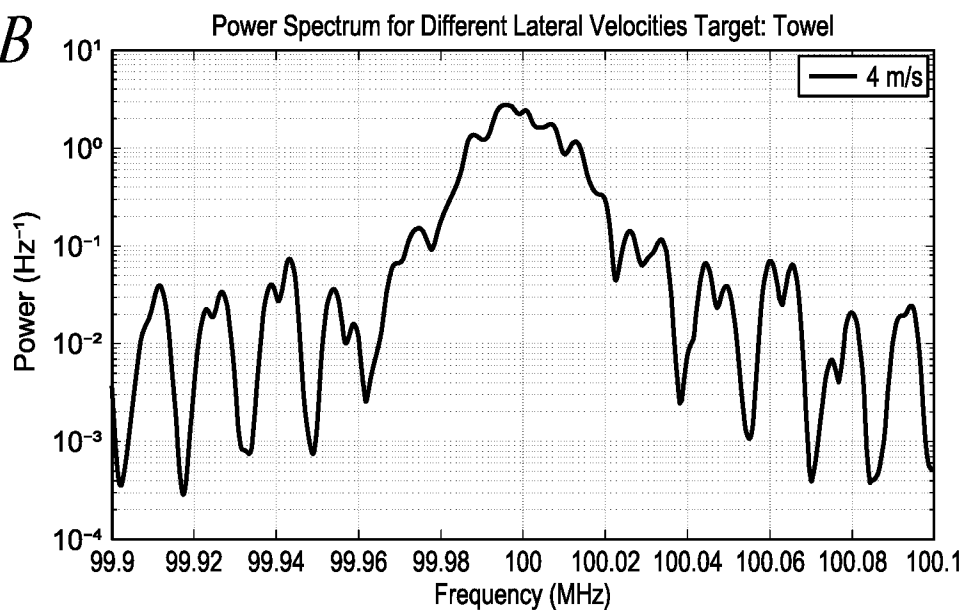
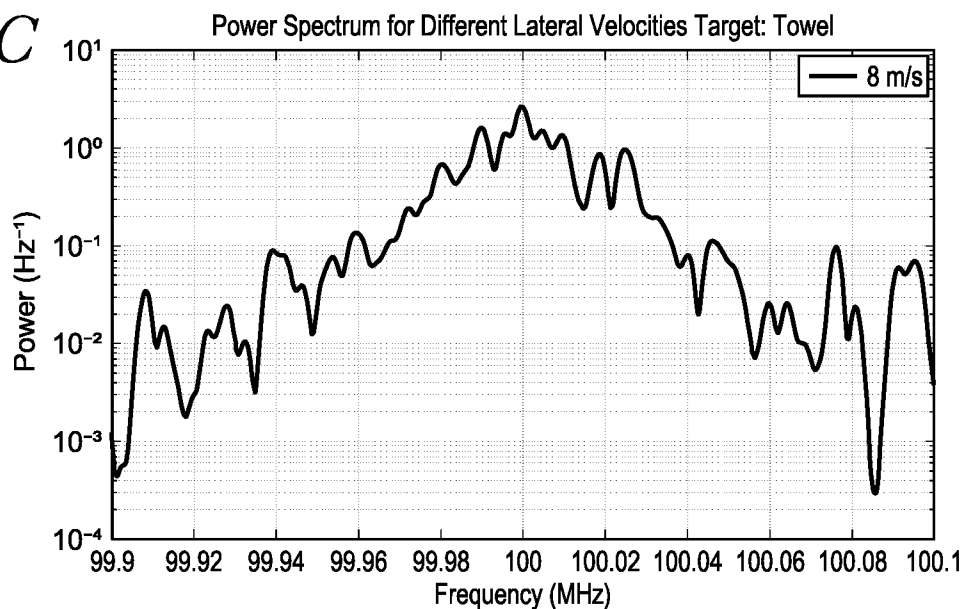
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*FIG. 10*

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*FIG. 11*

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FIG. 12A*FIG. 12B**FIG. 12C*

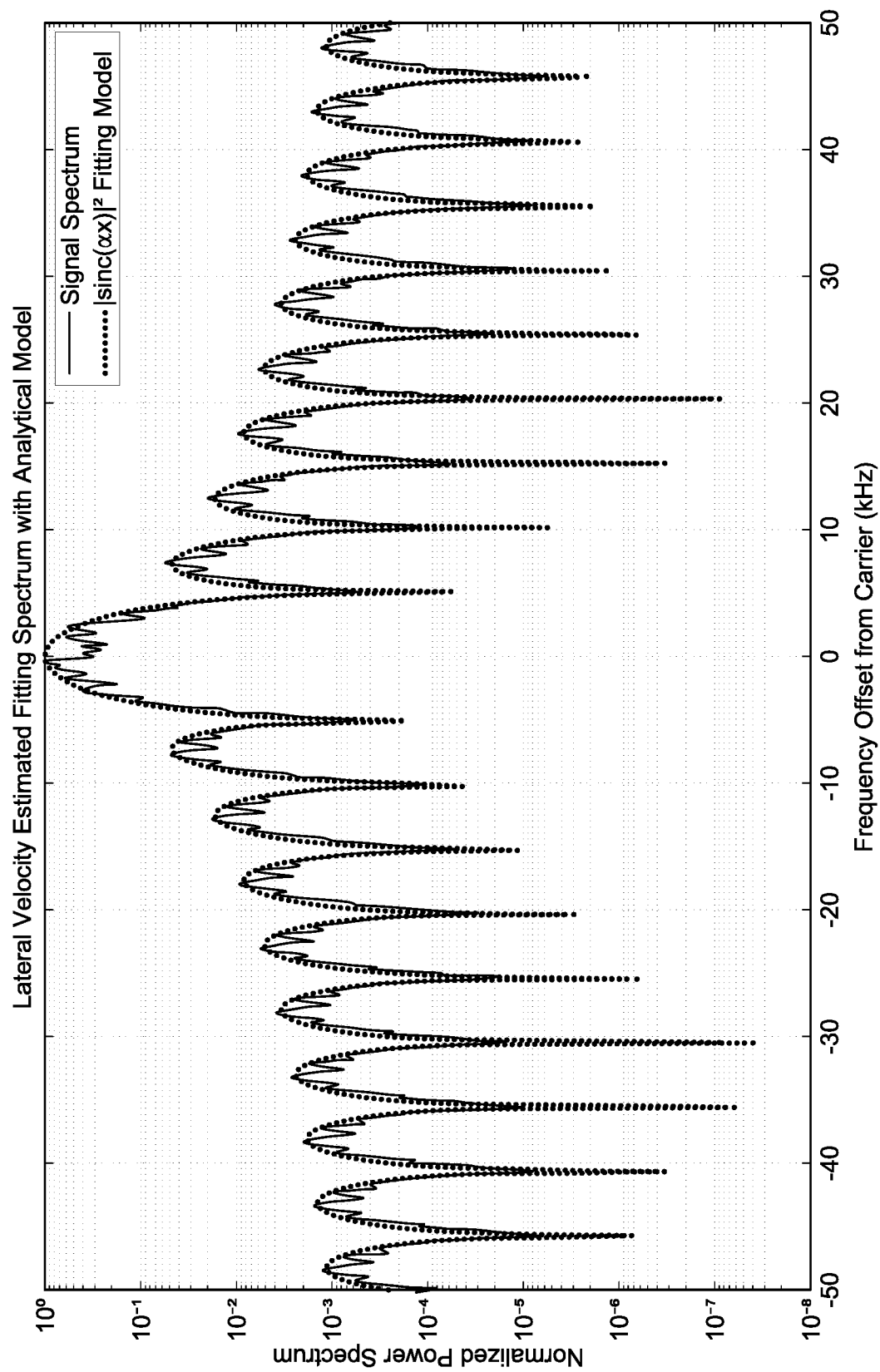


FIG. 13

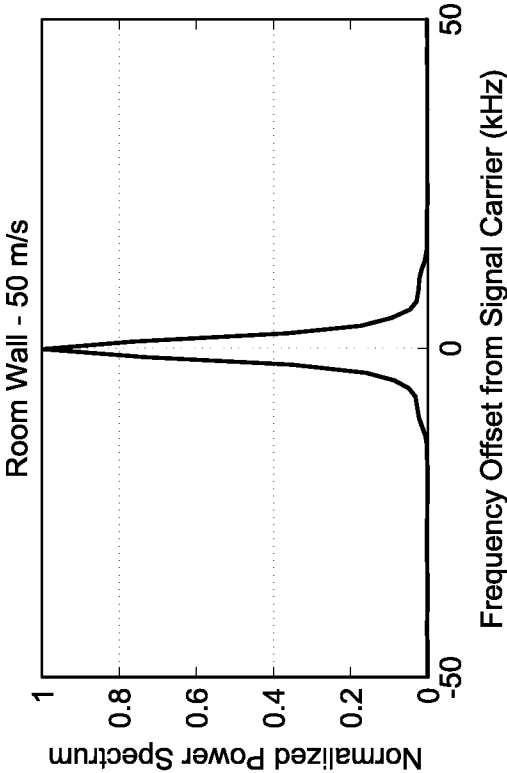


FIG. 14A

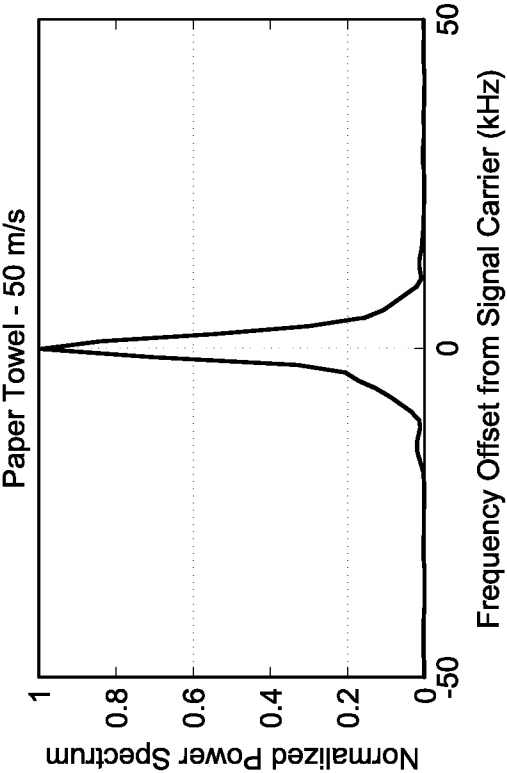


FIG. 14C

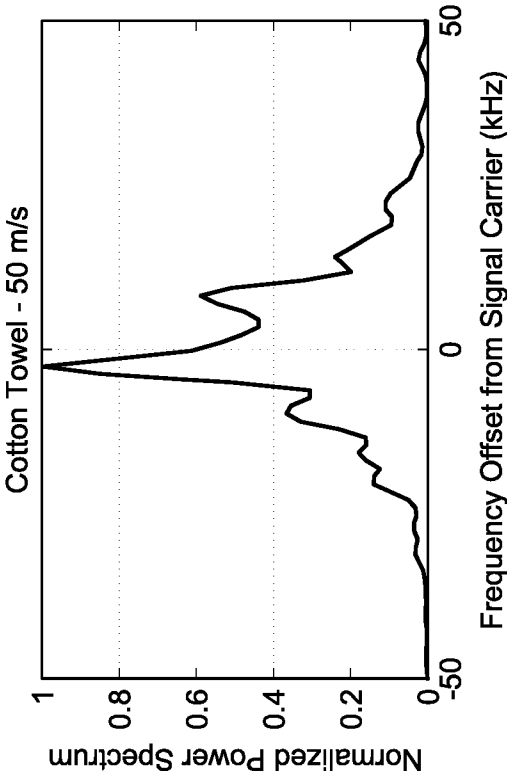


FIG. 14B

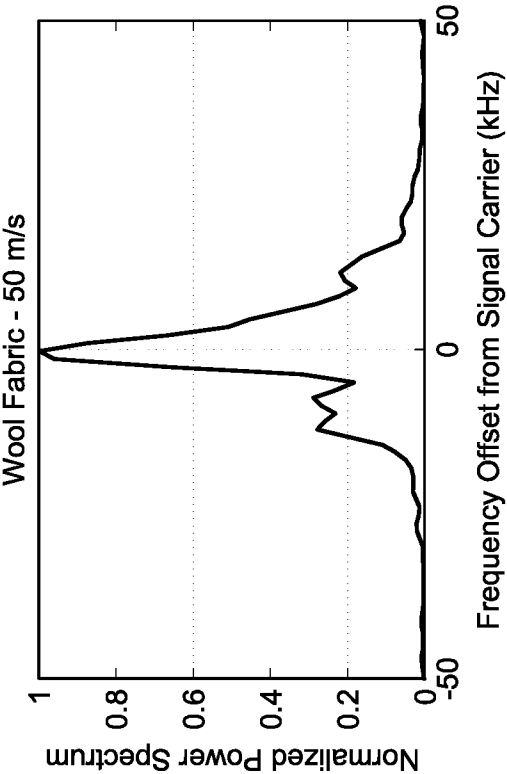


FIG. 14D

INTERNATIONAL SEARCH REPORT

International application No
PCT/US2019/037640

A. CLASSIFICATION OF SUBJECT MATTER INV. G01S17/32 G01S7/491 G01S7/48 G01S7/481 G01S17/36 ADD.		
According to International Patent Classification (IPC) or to both national classification and IPC		
B. FIELDS SEARCHED		
Minimum documentation searched (classification system followed by classification symbols) G01S		
Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched		
Electronic data base consulted during the international search (name of data base and, where practicable, search terms used) EPO-Internal, WPI Data		
C. DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	US 6 580 497 B1 (ASAKA KIMIO [JP] ET AL) 17 June 2003 (2003-06-17)	1,3-7, 21-25
Y	columns 12-19	8-12
Y	US 2017/214746 A1 (ZETTLER THOMAS [DE] ET AL) 27 July 2017 (2017-07-27) paragraphs [0053] - [0056]	8-12
X	WO 2017/216581 A1 (FRAUNHOFER UK RES LTD [GB]) 21 December 2017 (2017-12-21)	1,3-7, 21-25
Y	columns 9-30	8-12
A	EP 2 963 445 A2 (ADVANCED SCIENT CONCEPTS INC [US]) 6 January 2016 (2016-01-06) paragraphs [0011] - [0045]	1,3-12
	- / - -	
☒ Further documents are listed in the continuation of Box C. ☒ See patent family annex.		
* Special categories of cited documents : "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent but published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed "T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family		
Date of the actual completion of the international search 16 September 2019		Date of mailing of the international search report 20/11/2019
Name and mailing address of the ISA/ European Patent Office, P.B. 5818 Patentlaan 2 NL - 2280 HV Rijswijk Tel. (+31-70) 340-2040, Fax: (+31-70) 340-3016		Authorized officer Damp, Stephan

INTERNATIONAL SEARCH REPORT

International application No

PCT/US2019/037640

C(Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
A	US 2017/329010 A1 (WARKE NIRMAL C [US] ET AL) 16 November 2017 (2017-11-16) paragraphs [0019] - [0030] -----	1,3-12, 21-25
A	EP 2 626 722 A1 (SICK AG [DE]) 14 August 2013 (2013-08-14) the whole document -----	1,3-12, 21-25

INTERNATIONAL SEARCH REPORT

International application No.
PCT/US2019/037640

Box No. II Observations where certain claims were found unsearchable (Continuation of item 2 of first sheet)

This international search report has not been established in respect of certain claims under Article 17(2)(a) for the following reasons:

1. ☐ Claims Nos.:
because they relate to subject matter not required to be searched by this Authority, namely:
2. ☐ Claims Nos.:
because they relate to parts of the international application that do not comply with the prescribed requirements to such an extent that no meaningful international search can be carried out, specifically:
3. ☐ Claims Nos.:
because they are dependent claims and are not drafted in accordance with the second and third sentences of Rule 6.4(a).

Box No. III Observations where unity of invention is lacking (Continuation of item 3 of first sheet)

This International Searching Authority found multiple inventions in this international application, as follows:

see additional sheet

1. ☐ As all required additional search fees were timely paid by the applicant, this international search report covers all searchable claims.
2. ☐ As all searchable claims could be searched without effort justifying an additional fees, this Authority did not invite payment of additional fees.
3. ☐ As only some of the required additional search fees were timely paid by the applicant, this international search report covers only those claims for which fees were paid, specifically claims Nos.:
4. ☒ No required additional search fees were timely paid by the applicant. Consequently, this international search report is restricted to the invention first mentioned in the claims; it is covered by claims Nos.:

1, 3-12, 21-25

Remark on Protest

- ☐ The additional search fees were accompanied by the applicant's protest and, where applicable, the payment of a protest fee.
- ☐ The additional search fees were accompanied by the applicant's protest but the applicable protest fee was not paid within the time limit specified in the invitation.
- ☐ No protest accompanied the payment of additional search fees.

FURTHER INFORMATION CONTINUED FROM PCT/ISA/ 210

This International Searching Authority found multiple (groups of) inventions in this international application, as follows:

1. claims: 1, 3-12, 21-25

A lidar sensor with a light beam which is phase modulated by a periodic pattern combined with a unique code.

2. claims: 2, 13-20, 26-30

A lidar sensor with coed light beam and overlapping light flight times.

3. claims: 31-35, 46-48

A lidar sensor, where the velocity is determined from a time derivative and from a Doppler shift.

4. claims: 36-45

A lidar sensor, where different light components are guided by fiber couplers.

5. claims: 49-70

A lidar sensor, where a lateral target velocity is derived from a sidelobe width.

6. claims: 71-90

A lidar sensor, where the target surface characteristics is determined by spectral analysis.

INTERNATIONAL SEARCH REPORT

Information on patent family members

International application No

PCT/US2019/037640

Patent document cited in search report	Publication date	Patent family member(s)	Publication date
US 6580497	B1	17-06-2003	EP 1055941 A2 29-11-2000
		US 6580497 B1	17-06-2003
US 2017214746	A1	27-07-2017	DE 102016101041 A1 27-07-2017
		US 2017214746 A1	27-07-2017
WO 2017216581	A1	21-12-2017	NONE
EP 2963445	A2	06-01-2016	EP 2963445 A2 06-01-2016
		JP 6502196 B2	17-04-2019
		JP 2016014665 A	28-01-2016
		US 2016003946 A1	07-01-2016
US 2017329010	A1	16-11-2017	NONE
EP 2626722	A1	14-08-2013	EP 2626722 A1 14-08-2013
		JP 2013160769 A	19-08-2013