Contents

Acknowledgements III

Abstract IX

Kurzfassung XI

Nomenclature XIII

1. Introduction 1
- 1.1. Motivation . . . 1
  - 1.1.1. Automated Vehicles . . . 1
  - 1.1.2. Functional System Architecture . . . 3
  - 1.1.3. Environmental Perception . . . 6
- 1.2. State of the Art . . . 7
  - 1.2.1. Simultaneous Localization and Mapping . . . 9
  - 1.2.2. Movable Object Detection . . . 14
  - 1.2.3. Movable Object Tracking . . . 16
- 1.3. Contributions . . . 19
- 1.4. Overview . . . 21

2. Sensor Data Preprocessing 25
- 2.1. Introduction . . . 25
- 2.2. Vehicle Origin/Orientation correction . . . 27
- 2.3. Scan Undistortion . . . 29
- 2.4. Sensor Data Representation . . . 30
- 2.5. Ground Point Classification . . . 32
- 2.6. Object Segmentation . . . 36
- 2.7. Movable Object Detection . . . 40
- 2.8. Landmark Classification . . . 44
- 2.9. Road Area Identification . . . 45
- 2.10. Summary . . . 47

3. Volumetric Hybrid Map-based SLAM **49**
3.1. Introduction 49
3.2. Estimation technique 50
3.3. Motion Model 55
3.4. Environment Models 57
3.4.1. Grid Map 62
3.4.2. Feature Map 72
3.5. Proposal Distribution 76
3.5.1. Mathematical Formulation 77
3.5.2. Efficient Computation 81
3.5.3. Adaptive Selection 84
3.6. Summary 85

4. Geometric Model-based Tracking with Multiple Motion Models **87**
4.1. Introduction 87
4.2. Geometric Model-based Tracking 90
4.2.1. Geometric Shape Extraction 92
4.2.2. Geometric Shape Inference 95
4.3. Multiple Motion Models 99
4.3.1. Constant Velocity (CV) Model 100
4.3.2. Constant Acceleration (CA) Model 101
4.3.3. Coordinated Turn (CT) Model 102
4.4. Fuzzy Interacting Multiple Model Algorithm 103
4.4.1. Elemental Filter Design 103
4.4.2. Common State Vector 105
4.4.3. Hybrid Estimation Scheme 106
4.4.4. Fuzzy Inference System 111
4.5. Data Association 114
4.5.1. Validation Gating 115
4.5.2. Assignment method 116
4.6. Track Management 117
4.6.1. Life Cycle 118
4.6.2. Dynamic State 119
4.7. Summary 120

5. Evaluation **123**
5.1. Introduction 123
5.2. Localization and Mapping 124
5.2.1. Hybrid Map-based SLAM 124

5.2.2. Volumetric Hybrid Map-based SLAM 128
5.3. Target Tracking 137
5.3.1. Geometric Model-based Tracking 137
5.3.2. Multiple Motion Model-based Tracking 141
5.4. Runtime Analysis 151
5.5. Summary 154

6. Conclusion **155**
6.1. Summary 155
6.2. Outlook 157

A. Appendix **159**
A.1. Probability Theory 159
A.1.1. Conditional Probability 159
A.1.2. Product Rule 159
A.1.3. Sum Rule (Marginal Probability) 159
A.1.4. Total Probability Rule 160
A.1.5. Independence Rule 160
A.1.6. Bayes rule 160
A.1.7. Markov Assumption 161
A.2. Gaussian Distribution 161
A.2.1. Partitioned Gaussian Distribution 161
A.2.2. Linear Operation 162
A.2.3. Moments 162

List of Publications **165**

Bibliography **167**