

Title (en)
METHOD, COMPUTER-IMPLEMENTED TOOL, VEHICLE CONTROL UNIT, AND VEHICLE FOR LOCATING OBSTACLES IN VEHICLE ROADWAY REGIONS, WHICH ARE CHARACTERIZED BY LANDMARKS

Title (de)
VERFAHREN, COMPUTER-IMPLEMENTIERTES WERKZEUG, FAHRZEUG-STEUERUNGSEINHEIT UND FAHRZEUG ZUM VERORTEN VON HINDERNISOBJEKTEN IN LANDMARKENGEKENNZEICHNETEN FAHRSTRECKENBEREICHEN VON FAHRZEUGEN

Title (fr)
PROCÉDÉ, OUTIL MIS EN OEUVRE PAR ORDINATEUR, UNITÉ DE COMMANDE DE VÉHICULE, ET VÉHICULE POUR LOCALISER DES OBSTACLES DANS DES RÉGIONS DE CHAUSSÉE DE VÉHICULE, QUI SONT CARACTÉRISÉS PAR DES POINTS DE REPÈRE

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Abstract (en)
[origin: WO2022028848A1] The aim of the invention is to locate obstacles in vehicle roadway regions, which are characterized by landmarks, without needing to precisely locate the obstacles nor attempt a coordinate transformation required for this purpose in a known manner. This is achieved in that by (i) associating (DAZ) sensor measurement data (SMD1, SMD2), which is detected by at least one sensor (SS) of a vehicle sensor system (FZS) and belongs to sensor measurement objects (SMOLM/ SMOHO) and by means of which the landmarks (LM) and the obstacle (HO) can be represented, with stored landmark reference data (LM-RD) and by (ii) ascertaining a sensor detection-specific locating distance (VOD) between a sensor measurement object (SMOHO) with unassociated sensor measurement data (SMD2) and a landmark (LM) with associated sensor measurement data (SMD1,az) on the basis of the associated and unassociated sensor measurement data (SMD1,az, SMD2) in that pieces of sensor detection-specific information (IFses) contained in said sensor measurement data relating to the locating distance (VOD) to be ascertained are put into a relationship with one another, an obstacle (HO) in a vehicle (FZ) roadway region (FSB), which is characterized by landmarks, is located or the position thereof is determined (VO, VOIF) on a roadway (FS) of the roadway region (FSB) constituting an obstacle to the vehicle (FZ) if the sensor measurement object (SMOHO) with unassociated sensor measurement data (SMD2) on the roadway (FS) can be correlated at least on the basis of the ascertained sensor detection-specific locating distance (VOD).

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