

Optimal Trajectories for Highly Automated Driving

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Abstract : In this contribution two approaches for calculating optimal trajectories for highly automated vehicles are presented and compared. The first one is based on a non-linear vehicle model, used for evaluation. The second one is based on a simplified model and can be implemented on a current ECU. In usual driving situations both approaches show very similar results.

Keywords : trajectory planning, direct method, indirect method, highly automated driving

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