Developement of an autonomous driving environment model visualization based on object list level

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***Abstract*— This electronic document is a live template. The various components of your paper [title, text, heads, etc.] are already defined on the style sheet, as illustrated by the portions given in this document.**

I. INTRODUCTION

II. RELATED WORKS

IEEE Fabio Reway Test Method for Measuring the Simulation-to-Reality Gap of Camera-based Object Detection Algorithms for Autonomous Driving

III. MATERIALS AND METHODS

Kleines Intro was jetzt kommt

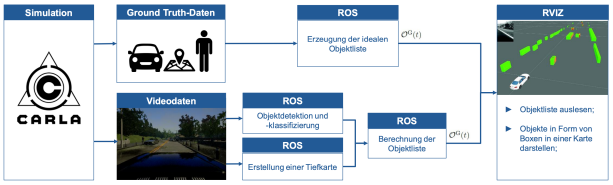

Fig. 1. Ueberblick

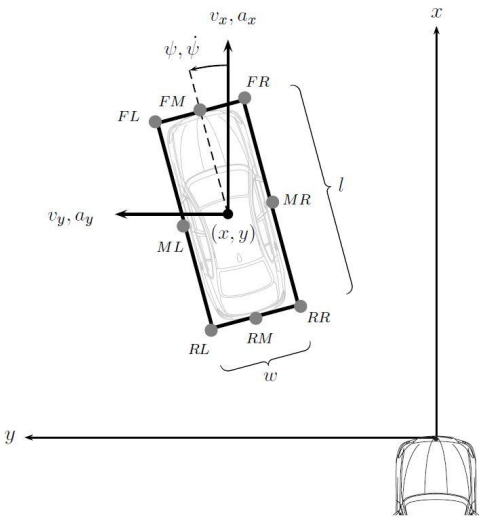

Fig. 2. Fahrzeugkoordinatensystem

A. Creating simulation scenario

- Welcher Simulator wurde verwendet
- Welches Szenario (NCAP)
- Szenario beschreiben

B. Creating objects list of ground-truth data (TP1

- Erstellung Objektliste
- Objektliste anhand Attribut-Vektor beschreiben
- Ros-System beschreiben
- Feature Vektor Ermittlung

C. Evaluation of video data (TP2)

- Detektion Objekte (Yolo)
- Tracking Objekte (Tracker)
- Gleichung zur Berechnung von zB Geschwindigkeit, Beschleunigung
- Ermittlung Classification / prop mov / prop exis

D. Visualization of object lists(TP3)

- subscription der Objektlisten
- Auswertung der Objektlisten,Marker Array, Tf Transform,

E. Evaluation of object lists(TP3)

- Objektlisten in BagFiles aufnehmen
- Geo und Time mapping
- Berechnung von iOu etc. verweis auf VerÃ¶ffentlichung von Fabio

IV. RESULTS

Ergebnisse des Projekts:

- Funktioniert die Auswertung
- Wie gut sind die Kamerawerte im Vergleich zu Groundtruth Werte
- sind die Werte represenativ

V. CONCLUSIONS

APPENDIX

ACKNOWLEDGMENT

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REFERENCES

[1] F. Reway, W. Huber, and E. P. Ribeiro, "Test methodology for vision-based adas algorithms with an automotive camera-in-the-loop," in *2018 IEEE International Conference on Vehicular Electronics and Safety (ICVES)*, Sep. 2018, pp. 1–7.