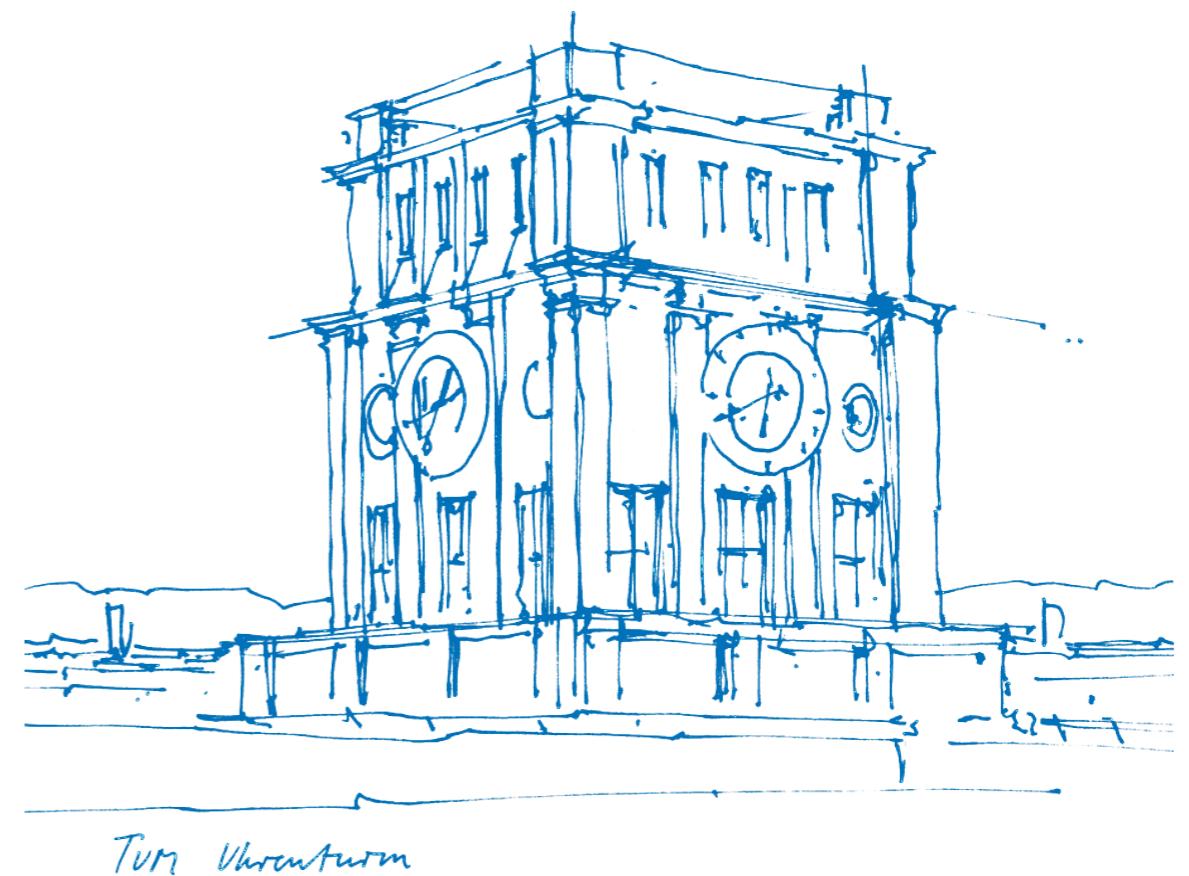


Team Parking - Status Week 8

Daniel Svendsen

Fortiss - From sensors to driving functions

27.06.2019



Status

- Set goals for Sprint 3 - deadline 18. July
- Sensor fusion - Kalman Filter
- Path Planning

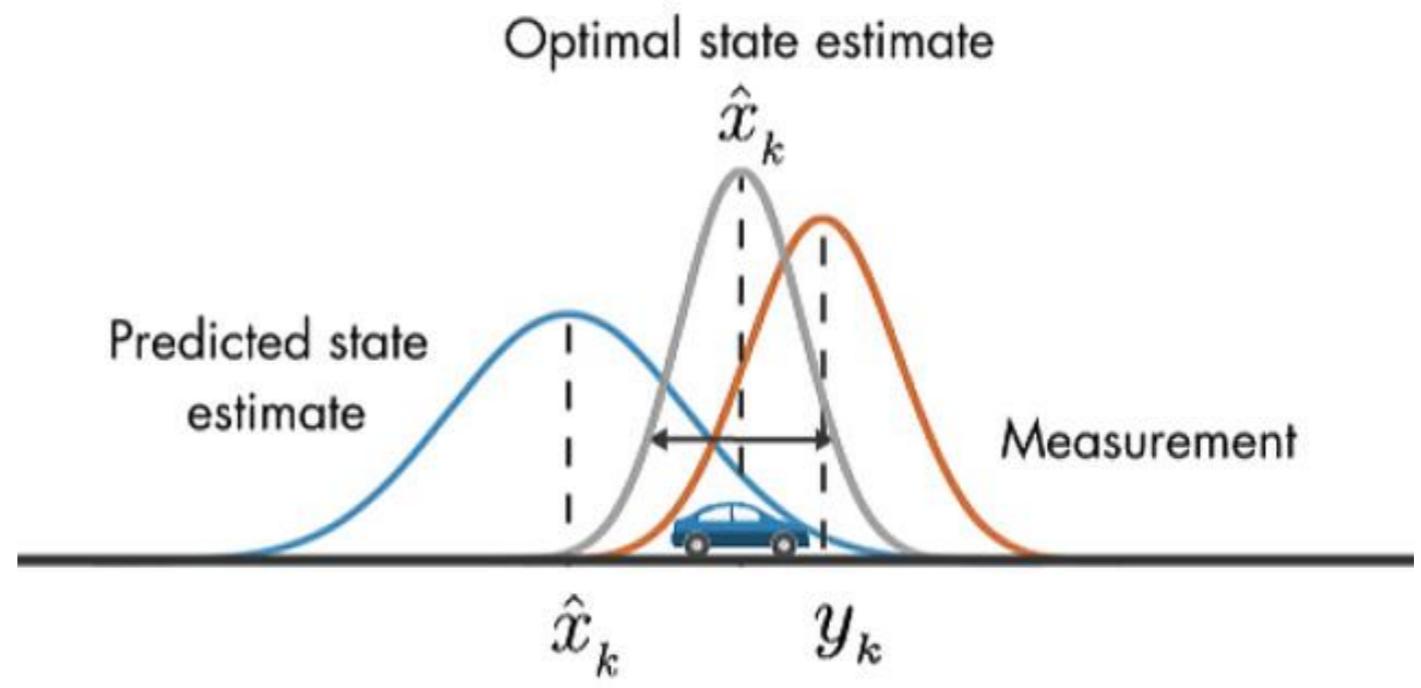
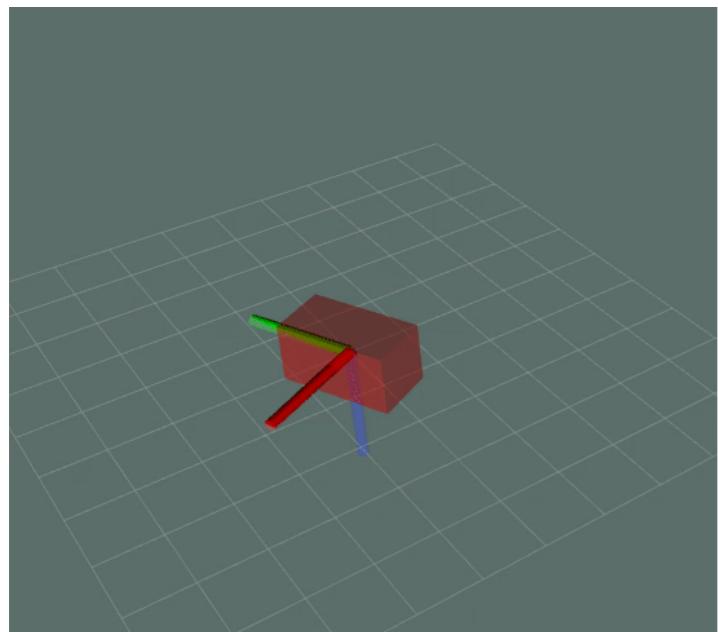


Last Wednesday



Sensor fusion - Kalman Filter

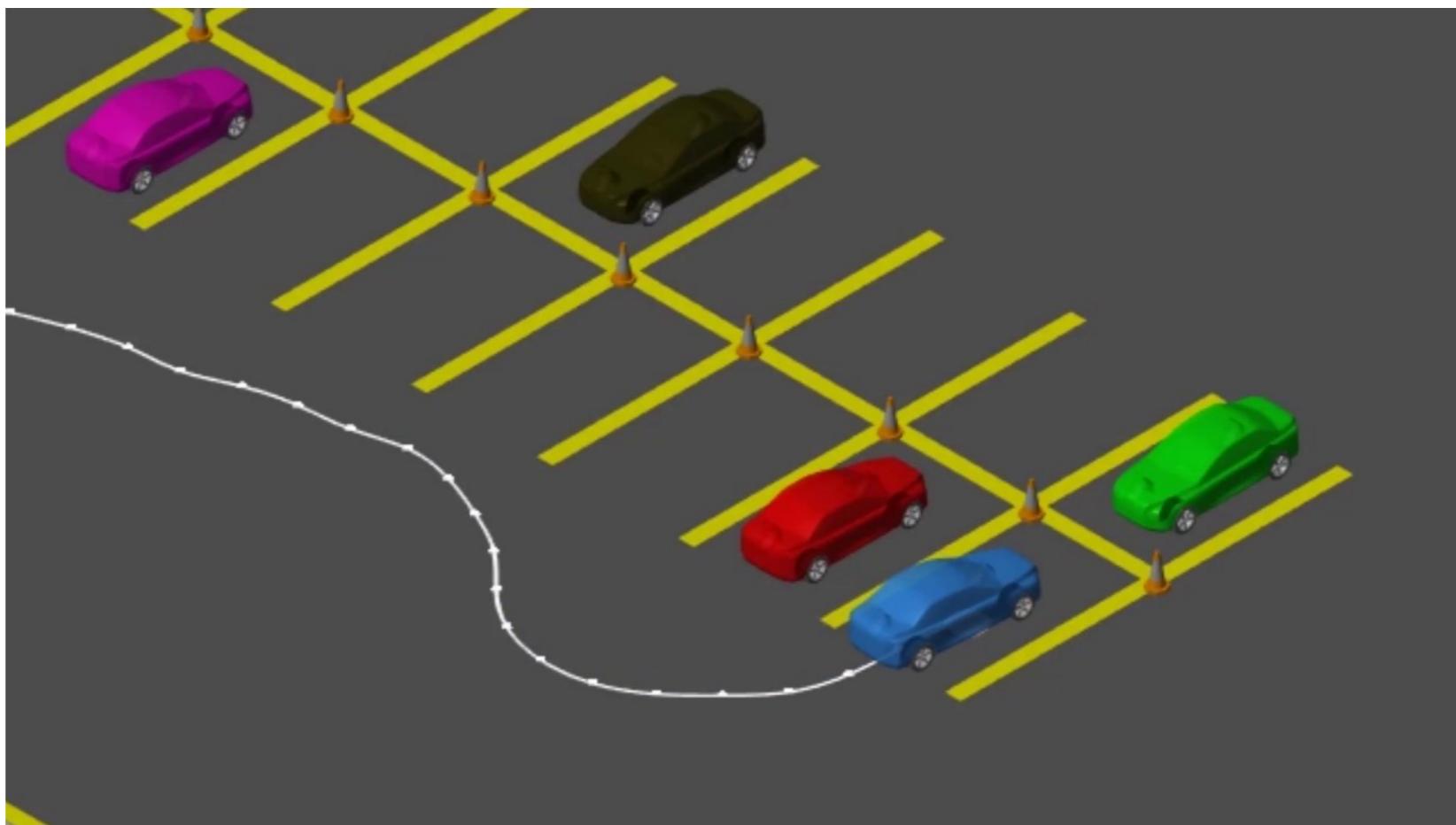
- LIDAR, IMU and Wheel Odometry



<https://www.mathworks.com/videos/understanding-kalman-filters-part-3-optimal-state-estimator--1490710645421.html>

Path Planning

- Work in progress. Tested internally
- To Do: Test on the Rover.



Future plans

- ✳ Implement and integrate sensor data
- ✳ Fuse to achieve smooth driving
- ✳ For final demo. Keep it simle, manually select the goal position
- ✳ Sketch out an architecture that unifies our parking application with the platooning AF3-model.