**Estimating the driving state of Oncoming vehichles....**

2009, Trans. Point cloud, EKF,present a new approach for estimating the pose and the full motion state of detected vehicles, incuding v, a,yaw. Focus on oncoming traffic.估计yaw rate很关键，对向车行驶过弯道。

基于[1]提出的point cloud.EKF to relate the observations in the image to a 3-D obj movement. 主要探测目标是车，并根据车的运动局限使用了基于V和Yaw的circular path模型。主要贡献在于raw rate。

**Ego-Motion Estimation by Matching Dewarped Road Regions using stereo images,**

**2006, IEEE conference on Robotics and Automation**

首先使用stereo image将相对于路的静态区域找出来，这些区域可以认为是静态区域。然后提出了virtual projection plane (VPP) ，这种图等价于路的top view。Ego-motion可以通过匹配连续的路模型的VPP获得。此文使用vehicle-motion模型，并设计了匹配的方法，来确定ego-motion。

**Moving Object Detection in Real-Time Using Stereo from a Mobile platform,**

2015 unmanned systems,

Object detection algo, 两帧stereo image. 基于stereo matching和optical flow估计。提出了基于lucas-kanada paradigm算法的改进方案。在KITTI数据集上做了验证。总的来说是个优化。

**Detection of Independently moving objects through stereo vision and Ego-motion Extraction,**

2010, IEEE intelligent vehicles symposium,

A method to detect and localize independent moving obj. 主要研究Obstacle detection.

[3][4] rely on image motion estimation, through the computation of OF.

[6] estimate motion directly from the image, 但是仍然基于brightness constraint equation。Monocular method lack the exact knowledge of obj depth and can only determine the extract position of a given object up to a scale factor.

[11],[12], obstacle detection, in the field of ego-motion recovery and pathfinding[13],[14],[15].

提出了static/dynamic探测的方法。

**Robust real-time ego-motion from stereo images,**

MIT, Honda research institute,2003

没看懂干什么用的。。。。。。

**Real-Time vehicle Ego-Motion using stereo pairs and particle filters,**

2007,

直接从brightness of a steam of stereo pairs得到on-board camera position and orientation. 计算camera position和orientation的。

**Sensor Fusion for Accurate Ego-Motion Estimation in a Moving platform**,

Hindawi, 2015, ADAS Department, LG electronics,...

一个基于视觉的Ego-motion estimation method， 并且进行了多sensor的数据融合。用来Estimate the position of the sensor.

**Stereo Based Ego-Motion Estimation Using Pixel Tracking and Iterative Closest Point,**

6DoF ego-motion estimation, 基于一个假设，在连续的帧中有能够跟踪的明显的特征。视觉定位？解决自定位的问题。

**Object Motion Analysis and Prediction in Stereo Image Sequences,**

A combined approach that tracks the vehicle position and orientation over time based on a box model。与传统的CA模型，Curve radius预测模型不同，采用particle filter使结果更加精确。

是Barth2008的一个演进，之前用3D point clouds描述的3D模型，用EKF跟踪轨迹。之前这种方式采用CA模型，只适合1秒内的预测，不适用于几秒后的预测。这篇文章提供的方法可以用来预测目标几秒后的姿势和运动状态。

**Stereo Vision Motion Detection from a Moving Platform,**

澳大利亚人。

使用3D视差和OF划分和跟踪人。采用KF跟踪移动的人。

A Robust Method for Ego-Motion Estimation in Urban Environment using Stereo Camera,

视觉定位类的文章。

A Robust Approach For Ego-Motion Estimation Using a Mobile Stereo platform,

研究the motion of a camera. Daimler Chrysler AG, Research and Technology

A Robust Method for computing vehicle Ego-motion,

采用单摄计算车自身相对路的运动

Position Estimation in Ourdoor Environments using Pixel Tracking and Stereo vision,

2000 IEEE international conference on Robotics & Automation

自定位，Ego-Motion,