Patents

inventor:(Aliakbar AGHAMOHAMMADI)

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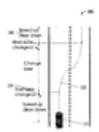
Systems and methods for mapping an environment

WO US CN • US9996944B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2016-07-06 • Filed 2016-09-16 • Granted 2018-06-12 • Published 2018-06-12

A method for mapping an environment by an electronic device is described. The method includes obtaining a set of sensor measurements. The method also includes determining a set of voxel occupancy probability distributions respectively corresponding to a set of voxels based on the set of sensor …

Motion planning and intention prediction for autonomous driving in highway …



WO US • US10345815B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2016-09-14 • Filed 2017-05-22 • Granted 2019-07-09 • Published 2019-07-09

Aspects of the disclosure are related to a method, apparatus, and system for planning a motion for a first vehicle, comprising: estimating past states of an observed second vehicle based on sensor inputs; predicting a future trajectory of the second vehicle based on the estimated past states;

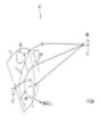
Object-focused active three-dimensional reconstruction

WO EP US CN *TW* • US10372968B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2016-01-22 • Filed 2016-06-24 • Granted 2019-08-06 • Published 2019-08-06

A method for guiding a robot equipped with a camera to facilitate three-dimensional (3D) reconstruction through sampling based planning includes recognizing and localizing an object in a two-dimensional (2D) image. The method also includes computing 3D depth maps for the localized object. A 3D …

Rapidly-exploring randomizing feedback-based motion planning



WO ~~EP~~ ~~US~~ CN JP *KR* ~~BR~~ **CA** *TW* • US20170165835A1 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-12-09 • Filed 2016-06-24 • Published 2017-06-15

A method of motion planning for an agent to reach a target includes determining a frontier region between a frontier at a current time and a frontier at a next time. Waypoints are sampled in the frontier region with a bias toward the target. A path to reach the target is selected based on a …

Simultaneous mapping and planning by a robot

WO EP US CN • US10093021B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-12-02 • Filed 2016-06-24 • Granted 2018-10-09 • Published 2018-10-09

A method substantially simultaneously plans a path and maps an environment by a robot. The method determines a mean of an occupancy level for a location in a map. The method also includes determining a probability distribution function (PDF) of the occupancy level. The method further includes …

Parallel belief space motion planner

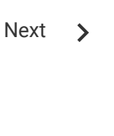
WO EP ~~US~~ CN • US20170004406A1 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-06-30 • Filed 2015-11-13 • Published 2017-01-05

A method for generating a movement policy includes determining a probability distribution function for multiples nodes of a roadmap and determining, in parallel, a cost and a collision probability for each edge of

the roadmap. The method also includes generating the movement policy based on the …

Holistic planning with multiple intentions for self-driving cars

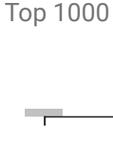


US • US10591920B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2017-05-24 • Filed 2017-05-24 • Granted 2020-03-17 • Published 2020-03-17

Aspects of the disclosure are related to a method, apparatus and system for joint motion planning and trajectory estimation, comprising: determining a cost function to describe system kinematics comprising trajectories, speeds, and accelerations of a host vehicle and of one or more other vehicles …

Stochastic map generation and bayesian update based on stereo vision



WO EP ~~US~~ CN *TW* • US20170161946A1 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-12-03 • Filed 2016-06-24 • Published 2017-06-08

A method for generating a map includes determining an occupancy level of each of multiple voxels. The method also includes determining a probability distribution function (PDF) of the occupancy level of each voxel. The method further includes performing an incremental Bayesian update on the PDF to …

Map generation based on raw stereo vision based measurements

WO EP ~~US~~ CN • US20170160747A1 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-12-04 • Filed 2016-06-24 • Published 2017-06-08

A method of calculating a most likely map based on batch data includes gathering a corpus of sensor measurements indexed by a location of a sensor throughout an environment to be mapped. The method also includes determining, after gathering the corpus of sensor measurements, a most likely …

Stochastic map-aware stereo vision sensor model

WO EP US CN KR *BR* • US10613546B2 • **Aliakbar AGHAMOHAMMADI** • Qualcomm Incorporated

Priority 2015-12-02 • Filed 2016-06-24 • Granted 2020-04-07 • Published 2020-04-07

A method for defining a sensor model includes determining a probability of obtaining a measurement from multiple potential causes in a field of view of a sensor modeled based on a stochastic map. The stochastic map includes a mean occupancy level for each voxel in the stochastic map and a variance …

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