Cooperative Perception
Project Context and Objectives

Project Goals

- Establish / improve preventive safety in longitudinal and intersection traffic
- Work towards virtually complete dynamic representation of traffic environment; integrate perception of adjacent vehicles and intersection
- Thus overcome blocked views, compensate for driver’s inattentiveness
- Early inspire driver’s mindfulness in case of emerging hazards
- Use novel HMI approaches based on driver information and last resort warnings
- Employ concurrence of diversely equipped test vehicles and intersection(s)

Vehicle Type A
- Self-Localization Unit
- Communication Unit
- Perception System
- Assistance Function(s)

Vehicle Type B
- Self-Localization Unit
- Communication Unit
- Assistance Function(s)

Vehicle Type C
- Self-Localization Unit
- Communication Unit
- Perception System

Example scenarios selected for today’s live demonstrations

Team 1
- Crossing with obscured view
- American style left turn with hidden contraflow

Team 2
- Cooperative pedestrian protection (with Ko-TAG)
- Cooperative bicyclist protection (with Ko-TAG)
- Left turn assistance to protect VRUs

Team 3
- Turning with circumspection