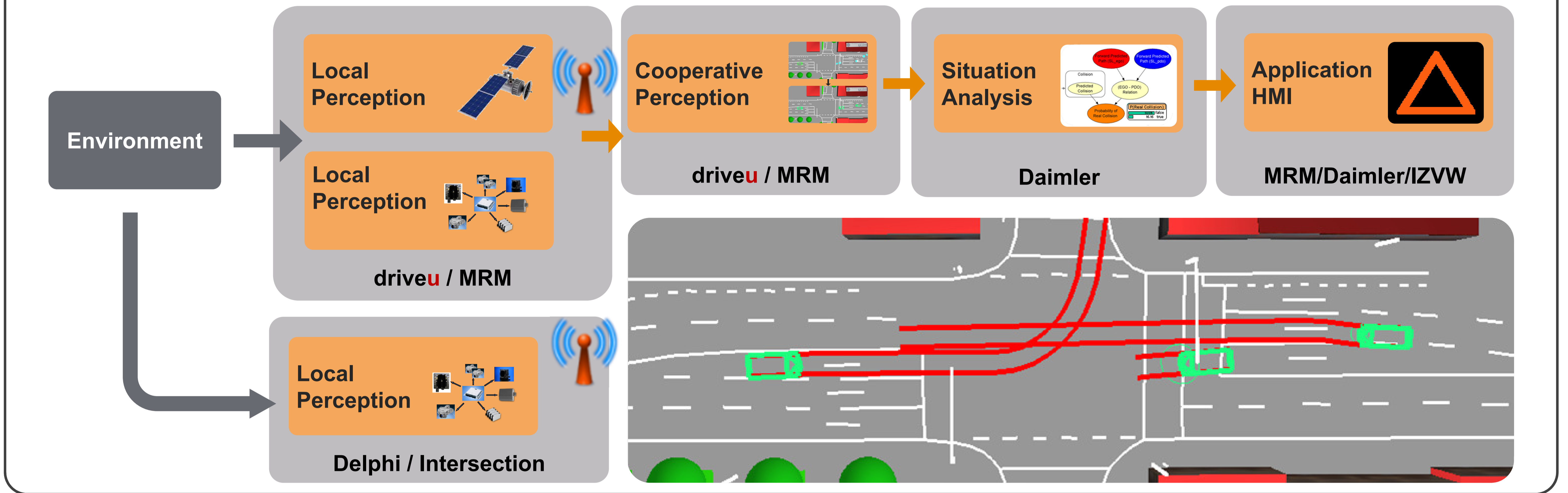


Demonstration I (driveu, Delphi, Daimler)

FORSCHUNGSINITIATIVE
K O - F A S

Project Ko-PER

Ko-PER Assistance: Schematic Overview



Ko-PER Team I Vehicles

driveu The vehicle is equipped with localization, perception and communication subsystems. It computes a local and cooperative fusion result which is input to the on-board situation analysis and HMI modules.

Delphi The Delphi vehicle is equipped with location and perception sensors, a local fusion module and the communication hardware. It transmits its perception results to other vehicles but features no cooperative safety function of its own.

Daimler The vehicle is equipped with localization and communication units. It receives perception results from the intersection and other vehicles and incorporates the cooperative fusion as well as the situation analysis and safety functions developed in Ko-PER.



Left-Turn and Crossing Maneuver with Occlusion

