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                           Interaction, Uncertain Prediction and Uncertain Perception

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   Soggetti                Mechanical engineering & materials

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   Sommario/riassunto      This work presents a behavior planning algorithm for automated
                           driving in urban environments with an uncertain and dynamic nature.
                           The algorithm allows to consider the prediction uncertainty (e.g.
                           different intentions), perception uncertainty (e.g. occlusions) as well as
                           the uncertain interactive behavior of the other agents explicitly.
                           Simulating the most likely future scenarios allows to find an optimal
                           policy online that enables non-conservative planning under
                           uncertainty.