



(51) International Patent Classification:
G05D 1/02 (2006.01)

(21) International Application Number:
PCT/CN2018/108356

(22) International Filing Date:
28 September 2018 (28.09.2018)

(25) Filing Language: English

(26) Publication Language: English

(71) Applicants: **BAIDU.COM TIMES TECHNOLOGY (BEIJING) CO., LTD.** [CN/CN]; 2/F A2 Zhongguancun Software Park 17th Building, No. 8, Dongbeiwang West Road, Haidian District, Beijing 100080 (CN). **BAIDU USA LLC** [US/US]; 1195 Bordeaux Dr., Sunnyvale, CA 94089 (US).

(72) Inventors: **ZHU, Fan**; 1195 Bordeaux Dr., Sunnyvale, CA 94089 (US). **MA, Lin**; 2/F A2 Zhongguancun Software

Park 17th Building, No.8, Dongbeiwang West Road, Haidian District, Beijing 100080 (CN).

(74) Agent: **INSIGHT INTELLECTUAL PROPERTY LIMITED**; 19 A, Tower A, InDo Building, No. 48A Zhichun Road, Haidian District, Beijing 100098 (CN).

(81) Designated States (*unless otherwise indicated, for every kind of national protection available*): AE, AG, AL, AM, AO, AT, AU, AZ, BA, BB, BG, BH, BN, BR, BW, BY, BZ, CA, CH, CL, CN, CO, CR, CU, CZ, DE, DJ, DK, DM, DO, DZ, EC, EE, EG, ES, FI, GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IR, IS, JO, JP, KE, KG, KH, KN, KP, KR, KW, KZ, LA, LC, LK, LR, LS, LU, LY, MA, MD, ME, MG, MK, MN, MW, MX, MY, MZ, NA, NG, NI, NO, NZ, OM, PA, PE, PG, PH, PL, PT, QA, RO, RS, RU, RW, SA, SC, SD, SE, SG, SK, SL, SM, ST, SV, SY, TH, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, ZA, ZM, ZW.

(54) Title: A PEDESTRIAN INTERACTION SYSTEM FOR LOW SPEED SCENES FOR AUTONOMOUS VEHICLES

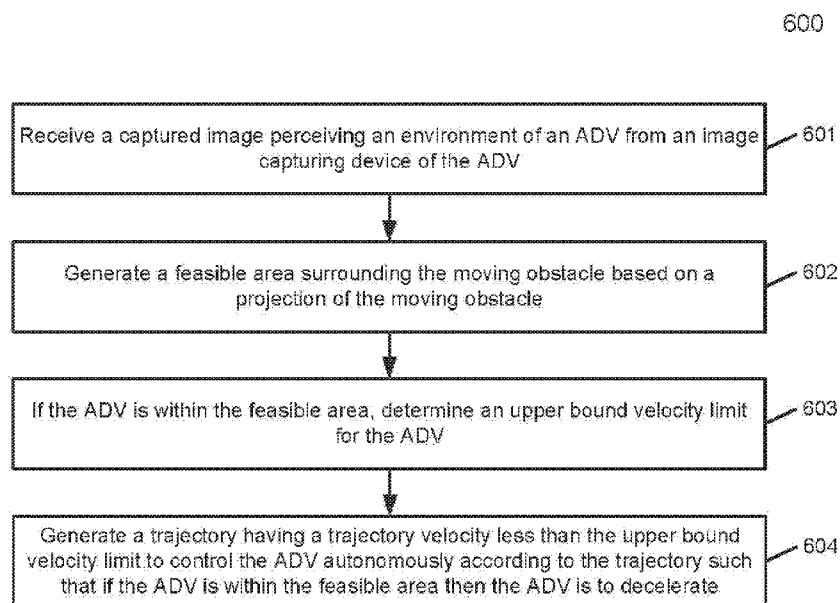


FIG. 6

(57) Abstract: A method, a non-transitory machine-readable medium and a data processing system for an autonomous driving vehicle. The system receives a captured image perceiving an environment of an ADV from an image capturing device of the ADV (601), where the captured image identifies an obstacle in motion near the ADV. The system generates a feasible area surrounding the moving obstacle based on a projection of the moving obstacle (602). If the ADV is within the feasible area, the system determines an upper bound velocity limit for the ADV (603). The system generates a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate (604).

(84) Designated States (*unless otherwise indicated, for every kind of regional protection available*): ARIPO (BW, GH, GM, KE, LR, LS, MW, MZ, NA, RW, SD, SL, ST, SZ, TZ, UG, ZM, ZW), Eurasian (AM, AZ, BY, KG, KZ, RU, TJ, TM), European (AL, AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR, HU, IE, IS, IT, LT, LU, LV, MC, MK, MT, NL, NO, PL, PT, RO, RS, SE, SI, SK, SM, TR), OAPI (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, KM, ML, MR, NE, SN, TD, TG).

Published:

— *with international search report (Art. 21(3))*

A PEDESTRIAN INTERACTION SYSTEM FOR LOW SPEED SCENES FOR AUTONOMOUS VEHICLES

TECHNICAL FIELD

[0001] Embodiments of the present disclosure relate generally to operating autonomous vehicles. More particularly, embodiments of the disclosure relate to a pedestrian interaction system for low speed scenes for autonomous driving vehicles (ADV).

BACKGROUND

[0002] Vehicles operating in an autonomous mode (e.g., driverless) can relieve occupants, especially the driver, from some driving-related responsibilities. When operating in an autonomous mode, the vehicle can navigate to various locations using onboard sensors, allowing the vehicle to travel with minimal human interaction or in some cases without any passengers.

[0003] When operating an autonomous mode, interaction strategies for autonomous driving vehicles on urban roads may not be suitable for vehicles driven in low speed scenarios. Locations for such low speed scenarios may include a parking lot, driveways, and campus land for universities, colleges, and institutional buildings. While on campus roadways, autonomous driving vehicles are expected to interact with pedestrian more than on urban roads.

SUMMARY

[0004] In a first aspect, the present disclosure provides a computer-implemented method for an autonomous driving vehicle (ADV), the method including: receiving a captured image perceiving an environment of an ADV from an image capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV; generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle; if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV; and generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

[0005] In a second aspect, the present disclosure provides a non-transitory machine-readable medium having instructions stored therein, which when executed by a processor, cause the processor to perform operations, the operations including: receiving a captured image perceiving an environment of an ADV from an image capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV; generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle; if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV; and generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

[0006] In a third aspect, the present disclosure provides a data processing system, including a processor; and a memory coupled to the processor to store instructions, which when executed by the processor, cause the processor to perform operations, the operations including: receiving a

captured image perceiving an environment of an ADV from an image capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV, generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle, if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV, and generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

BRIEF DESCRIPTION OF THE DRAWINGS

[0007] Embodiments of the disclosure are illustrated by way of example and not limitation in the figures of the accompanying drawings in which like references indicate similar elements.

[0008] Figure 1 is a block diagram illustrating a networked system according to one embodiment.

[0009] Figure 2 is a block diagram illustrating an example of a sensor and control system using by an autonomous vehicle according to one embodiment.

[0010] Figures 3A-3B are block diagrams illustrating examples of a perception and planning system used by an autonomous vehicle according to some embodiments.

[0011] Figure 4 is a block diagram illustrating an example of a velocity limiter module according to one embodiment.

[0012] Figure 5 is a block diagram illustrating an example of a campus scene according to one embodiment.

[0013] Figure 6 is a flow diagram illustrating a method according to one embodiment.

[0014] Figure 7 is a block diagram illustrating a data processing system according to one embodiment.

DETAILED DESCRIPTION

[0015] Various embodiments and aspects of the disclosures will be described with reference to details discussed below, and the accompanying drawings will illustrate the various embodiments. The following description and drawings are illustrative of the disclosure and are not to be construed as limiting the disclosure. Numerous specific details are described to provide a thorough understanding of various embodiments of the present disclosure. However, in certain instances, well-known or conventional details are not described in order to provide a concise discussion of embodiments of the present disclosures.

[0016] Reference in the specification to “one embodiment” or “an embodiment” means that a particular feature, structure, or characteristic described in conjunction with the embodiment can be included in at least one embodiment of the disclosure. The appearances of the phrase “in one embodiment” in various places in the specification do not necessarily all refer to the same embodiment.

[0017] Embodiments of the disclosures disclose a vehicle-pedestrian interaction system for low speed scenes for an autonomous vehicle. According to one aspect, a system receives a captured image perceiving an environment of an ADV from an image capturing device of the ADV, where the captured image identifies an obstacle in motion near the ADV. The system generates a feasible area surrounding the moving obstacle based on a projection of the moving obstacle. If the ADV is within the feasible area, the system determines an upper bound velocity

limit for the ADV. The system generates a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

[0018] In one embodiment, the generated feasible area includes a center location determined based on a location and/or a velocity direction of the moving obstacle for time T , and a radius determined based on a speed of the moving obstacle. In another embodiment, a location of the projection of the moving obstacle is determined based on a location of the moving obstacle and the ADV, e.g., at a perpendicular intersection point (e.g., 90 degrees angle) between a moving direction of the ADV and the moving obstacle. In another embodiment, the upper bound velocity limit is determined based on a distance between the ADV and the projection of the moving obstacle at a current time.

[0019] In another embodiment, the upper bound velocity limit or velocity limit (v_{limit}) for the ADV at time T is $v_0 e^{\frac{-\alpha}{d}}$, where v_0 is a current velocity of the ADV, α is an attenuation rate and d is the distance between the ADV and the projection of the moving obstacle at a current time. In another embodiment, time T can be determined by: $T = \frac{v_{bound}}{acc_{max}} + k$, where v_{bound} is a maximum velocity of the ADV or a maximum velocity determined by a roadway of the ADV, acc_{max} is a maximum acceleration of the ADV, and k is a constant. In one embodiment, the moving obstacle is a pedestrian.

[0020] Figure 1 is a block diagram illustrating an autonomous vehicle network configuration according to one embodiment of the disclosure. Referring to Figure 1, network configuration 100 includes autonomous vehicle 101 that may be communicatively coupled to one or more servers 103-104 over a network 102. Although there is one autonomous vehicle shown, multiple autonomous vehicles can be coupled to each other and/or coupled to servers 103-104 over

network 102. Network 102 may be any type of networks such as a local area network (LAN), a wide area network (WAN) such as the Internet, a cellular network, a satellite network, or a combination thereof, wired or wireless. Server(s) 103-104 may be any kind of servers or a cluster of servers, such as Web or cloud servers, application servers, backend servers, or a combination thereof. Servers 103-104 may be data analytics servers, content servers, traffic information servers, map and point of interest (MPOI) servers, or location servers, etc.

[0021] An autonomous vehicle refers to a vehicle that can be configured to in an autonomous mode in which the vehicle navigates through an environment with little or no input from a driver. Such an autonomous vehicle can include a sensor system having one or more sensors that are configured to detect information about the environment in which the vehicle operates. The vehicle and its associated controller(s) use the detected information to navigate through the environment. Autonomous vehicle 101 can operate in a manual mode, a full autonomous mode, or a partial autonomous mode.

[0022] In one embodiment, autonomous vehicle 101 includes, but is not limited to, perception and planning system 110, vehicle control system 111, wireless communication system 112, user interface system 113, and sensor system 115. Autonomous vehicle 101 may further include certain common components included in ordinary vehicles, such as, an engine, wheels, steering wheel, transmission, etc., which may be controlled by vehicle control system 111 and/or perception and planning system 110 using a variety of communication signals and/or commands, such as, for example, acceleration signals or commands, deceleration signals or commands, steering signals or commands, braking signals or commands, etc.

[0023] Components 110-115 may be communicatively coupled to each other via an interconnect, a bus, a network, or a combination thereof. For example, components 110-115 may

be communicatively coupled to each other via a controller area network (CAN) bus. A CAN bus is a vehicle communication standard designed to allow microcontrollers and devices to communicate with each other in applications without a host computer. It is a message-based protocol, designed originally for multiplex electrical wiring within automobiles, but is also used in many other contexts.

[0024] Referring now to Figure 2, in one embodiment, sensor system 115 includes, but it is not limited to, one or more cameras 211, global positioning system (GPS) unit 212, inertial measurement unit (IMU) 213, radar unit 214, and a light detection and range (LIDAR) unit 215. GPS system 212 may include a transceiver operable to provide information regarding the position of the autonomous vehicle. IMU unit 213 may sense position and orientation changes of the autonomous vehicle based on inertial acceleration. Radar unit 214 may represent a system that utilizes radio signals to sense objects within the local environment of the autonomous vehicle. In some embodiments, in addition to sensing objects, radar unit 214 may additionally sense the speed and/or heading of the objects. LIDAR unit 215 may sense objects in the environment in which the autonomous vehicle is located using lasers. LIDAR unit 215 could include one or more laser sources, a laser scanner, and one or more detectors, among other system components. Cameras 211 may include one or more devices to capture images of the environment surrounding the autonomous vehicle. Cameras 211 may be stationary cameras and/or PTZ (pan-tilt-zoom) cameras. A camera may be mechanically movable, for example, by mounting the camera on a rotating and/or tilting a platform.

[0025] Sensor system 115 may further include other sensors, such as, a sonar sensor, an infrared sensor, a steering sensor, a throttle sensor, a braking sensor, and an audio sensor (e.g., microphone). An audio sensor may be configured to capture sound from the environment

surrounding the autonomous vehicle. A steering sensor (e.g., electric power steering (EPS)) may be configured to sense the steering angle of a steering wheel, wheels of the vehicle, or a combination thereof. A throttle sensor and a braking sensor sense the throttle position and braking position of the vehicle, respectively. In some situations, a throttle sensor and a braking sensor may be integrated as an integrated throttle/braking sensor.

[0026] Vehicle control system 111 can include, but is not limited to, steering unit 201, throttle unit 202 (also referred to as an acceleration unit), and braking unit 203. Steering unit 201 is to adjust the direction or heading of the vehicle. Throttle unit 202 is to control the speed of the motor or engine that in turn controls the speed and acceleration of the vehicle. Braking unit 203 is to decelerate the vehicle by providing friction to slow the wheels or tires of the vehicle. Note that the components as shown in Figure 2 may be implemented in hardware, software, or a combination thereof.

[0027] Referring back to Figure 1, wireless communication system 112 is to allow communication between autonomous vehicle 101 and external systems, such as devices, sensors, other vehicles, etc. For example, wireless communication system 112 can wirelessly communicate with one or more devices directly or via a communication network, such as servers 103-104 over network 102. Wireless communication system 112 can use any cellular communication network or a wireless local area network (WLAN), e.g., using WiFi to communicate with another component or system. Wireless communication system 112 could communicate directly with a device (e.g., a mobile device of a passenger, a display device, a speaker within vehicle 101), for example, using an infrared link, Bluetooth, etc. User interface system 113 may be part of peripheral devices implemented within vehicle 101 including, for example, a keyboard, a touch screen display device, a microphone, and a speaker, etc.

[0028] Some or all of the functions of autonomous vehicle 101 may be controlled or managed by perception and planning system 110, especially when operating in an autonomous driving mode. Perception and planning system 110 includes the necessary hardware (e.g., processor(s), memory, storage) and software (e.g., operating system, planning and routing programs) to receive information from sensor system 115, control system 111, wireless communication system 112, and/or user interface system 113, process the received information, plan a route or path from a starting point to a destination point, and then drive vehicle 101 based on the planning and control information. Alternatively, perception and planning system 110 may be integrated with vehicle control system 111.

[0029] For example, a user as a passenger may specify a starting location and a destination of a trip, for example, via a user interface. Perception and planning system 110 obtains the trip related data. For example, perception and planning system 110 may obtain location and route information from an MPOI server, which may be a part of servers 103-104. The location server provides location services and the MPOI server provides map services and the POIs of certain locations. Alternatively, such location and MPOI information may be cached locally in a persistent storage device of perception and planning system 110.

[0030] While autonomous vehicle 101 is moving along the route, perception and planning system 110 may also obtain real-time traffic information from a traffic information system or server (TIS). Note that servers 103-104 may be operated by a third party entity. Alternatively, the functionalities of servers 103-104 may be integrated with perception and planning system 110. Based on the real-time traffic information, MPOI information, and location information, as well as real-time local environment data detected or sensed by sensor system 115 (e.g., obstacles, objects, nearby vehicles), perception and planning system 110 can plan an optimal route and

drive vehicle 101, for example, via control system 111, according to the planned route to reach the specified destination safely and efficiently.

[0031] Server 103 may be a data analytics system to perform data analytics services for a variety of clients. In one embodiment, data analytics system 103 includes data collector 121 and machine learning engine 122. Data collector 121 collects driving statistics 123 from a variety of vehicles, either autonomous vehicles or regular vehicles driven by human drivers. Driving statistics 123 include information indicating the driving commands (e.g., throttle, brake, steering commands) issued and responses of the vehicles (e.g., speeds, accelerations, decelerations, directions) captured by sensors of the vehicles at different points in time. Driving statistics 123 may further include information describing the driving environments at different points in time, such as, for example, routes (including starting and destination locations), MPOIs, road conditions, weather conditions, etc.

[0032] Based on driving statistics 123, machine learning engine 122 generates or trains a set of rules, algorithms, and/or models 124 for a variety of purposes. In one embodiment, for example, algorithms/model 124 may include one or more machine learning models and/or image segmentation models to detect objects such as pedestrians and to identify information about these objects. The machine learning models can be trained and uploaded onto the ADVs to be used for autonomous driving by the ADVs, in real-time. Algorithms/model 124 may include algorithms/models to determine velocity limits to be used by the ADVs.

[0033] Figures 3A and 3B are block diagrams illustrating an example of a perception and planning system used with an autonomous vehicle according to one embodiment. System 300 may be implemented as a part of autonomous vehicle 101 of Figure 1 including, but is not limited to, perception and planning system 110, control system 111, and sensor system 115.

Referring to Figures 3A-3B, perception and planning system 110 includes, but is not limited to, localization module 301, perception module 302, prediction module 303, decision module 304, planning module 305, control module 306, routing/sampling module 307, and velocity limiter module 308.

[0034] Some or all of modules 301-308 may be implemented in software, hardware, or a combination thereof. For example, these modules may be installed in persistent storage device 352, loaded into memory 351, and executed by one or more processors (not shown). Note that some or all of these modules may be communicatively coupled to or integrated with some or all modules of vehicle control system 111 of Figure 2. Some of modules 301-308 may be integrated together as an integrated module. For example, velocity limiter module 308 and planning module 305 may be integrated as a single module.

[0035] Localization module 301 determines a current location of autonomous vehicle 300 (e.g., leveraging GPS unit 212) and manages any data related to a trip or route of a user. Localization module 301 (also referred to as a map and route module) manages any data related to a trip or route of a user. A user may log in and specify a starting location and a destination of a trip, for example, via a user interface. Localization module 301 communicates with other components of autonomous vehicle 300, such as map and route information 311, to obtain the trip related data. For example, localization module 301 may obtain location and route information from a location server and a map and POI (MPOI) server. A location server provides location services and an MPOI server provides map services and the POIs of certain locations, which may be cached as part of map and route information 311. While autonomous vehicle 300 is moving along the route, localization module 301 may also obtain real-time traffic information from a traffic information system or server.

[0036] Based on the sensor data provided by sensor system 115 and localization information obtained by localization module 301, a perception of the surrounding environment is determined by perception module 302. The perception information may represent what an ordinary driver would perceive surrounding a vehicle in which the driver is driving. The perception can include the lane configuration (e.g., straight or curve lanes), traffic light signals, a relative position of another vehicle, a pedestrian, a building, crosswalk, or other traffic related signs (e.g., stop signs, yield signs), etc., for example, in a form of an object. The lane configuration includes information describing a lane or lanes, such as, for example, a shape of the lane (e.g., straight or curvature), a width of the lane, how many lanes in a road, one-way or two-way lane, merging or splitting lanes, exiting lane, etc.

[0037] Perception module 302 may include a computer vision system or functionalities of a computer vision system to process and analyze images captured by one or more cameras in order to identify objects and/or features in the environment of autonomous vehicle. The objects can include traffic signals, road way boundaries, other vehicles, pedestrians, and/or obstacles, etc. The computer vision system may use an object recognition algorithm, video tracking, and other computer vision techniques. In some embodiments, the computer vision system can map an environment, track objects, and estimate the speed of objects, etc. Perception module 302 can also detect objects based on other sensors data provided by other sensors such as a radar and/or LIDAR.

[0038] For each of the objects, prediction module 303 predicts how the object will behave under the circumstances. The prediction is performed based on the perception data perceiving the driving environment at the point in time in view of a set of map/route information 311 and traffic rules 312. For example, if the object is a vehicle at an opposing direction and the current driving

environment includes an intersection, prediction module 303 will predict whether the vehicle will likely move straight forward or make a turn. If the perception data indicates that the intersection has no traffic light, prediction module 303 may predict that the vehicle may have to fully stop prior to enter the intersection. If the perception data indicates that the vehicle is currently at a left-turn only lane or a right-turn only lane, prediction module 303 may predict that the vehicle will more likely make a left turn or right turn respectively.

[0039] For each of the objects, decision module 304 makes a decision regarding how to handle the object. For example, for a particular object (e.g., another vehicle in a crossing route) as well as its metadata describing the object (e.g., a speed, direction, turning angle), decision module 304 decides how to encounter the object (e.g., overtake, yield, stop, pass). Decision module 304 may make such decisions according to a set of rules such as traffic rules or driving rules 312, which may be stored in persistent storage device 352.

[0040] Routing module 307 is configured to provide one or more routes or paths from a starting point to a destination point. For a given trip from a start location to a destination location, for example, received from a user, routing module 307 obtains route and map information 311 and determines all possible routes or paths from the starting location to reach the destination location. Routing module 307 may generate a reference line in a form of a topographic map for each of the routes it determines from the starting location to reach the destination location. A reference line refers to an ideal route or path without any interference from others such as other vehicles, obstacles, or traffic condition. That is, if there is no other vehicle, pedestrians, or obstacles on the road, an ADV should exactly or closely follows the reference line. The topographic maps are then provided to decision module 304 and/or planning module 305. Decision module 304 and/or planning module 305 examine all of the possible routes to select

and modify one of the most optimal routes in view of other data provided by other modules such as traffic conditions from localization module 301, driving environment perceived by perception module 302, and traffic condition predicted by prediction module 303. The actual path or route for controlling the ADV may be close to or different from the reference line provided by routing module 307 dependent upon the specific driving environment at the point in time.

[0041] Based on a decision for each of the objects perceived, planning module 305 plans a path or route for the autonomous vehicle, as well as driving parameters (e.g., distance, speed, and/or turning angle). That is, for a given object, decision module 304 decides what to do with the object, while planning module 305 determines how to do it. For example, for a given object, decision module 304 may decide to pass the object, while planning module 305 may determine whether to pass on the left side or right side of the object. Planning and control data is generated by planning module 305 including information describing how vehicle 300 would move in a next moving cycle (e.g., next route/path segment). For example, the planning and control data may instruct vehicle 300 to move 10 meters at a speed of 30 mile per hour (mph), then change to a right lane at the speed of 25 mph.

[0042] Based on the planning and control data, control module 306 controls and drives the autonomous vehicle, by sending proper commands or signals to vehicle control system 111, according to a route or path defined by the planning and control data. The planning and control data include sufficient information to drive the vehicle from a first point to a second point of a route or path using appropriate vehicle settings or driving parameters (e.g., throttle, braking, and turning commands) at different points in time along the path or route.

[0043] In one embodiment, the planning phase is performed in a number of planning cycles, also referred to as command cycles, such as, for example, in every time interval of 100

milliseconds (ms). For each of the planning cycles or command cycles, one or more control commands will be issued based on the planning and control data. That is, for every 100 ms, planning module 305 plans a next route segment or path segment, for example, including a target position and the time required for the ADV to reach the target position. Alternatively, planning module 305 may further specify the specific speed, direction, and/or steering angle, etc. In one embodiment, planning module 305 plans a route segment or path segment for the next predetermined period of time such as 5 seconds. For each planning cycle, planning module 305 plans a target position for the current cycle (e.g., next 5 seconds) based on a target position planned in a previous cycle. Control module 306 then generates one or more control commands (e.g., throttle, brake, steering control commands) based on the planning and control data of the current cycle.

[0044] Note that decision module 304 and planning module 305 may be integrated as an integrated module. Decision module 304/planning module 305 may include a navigation system or functionalities of a navigation system to determine a driving path for the autonomous vehicle. For example, the navigation system may determine a series of speeds and directional headings to effect movement of the autonomous vehicle along a path that substantially avoids perceived obstacles while generally advancing the autonomous vehicle along a roadway-based path leading to an ultimate destination. The destination may be set according to user inputs via user interface system 113. The navigation system may update the driving path dynamically while the autonomous vehicle is in operation. The navigation system can incorporate data from a GPS system and one or more maps so as to determine the driving path for the autonomous vehicle.

[0045] Decision module 304/planning module 305 may further include a collision avoidance system or functionalities of a collision avoidance system to identify, evaluate, and avoid or

otherwise negotiate potential obstacles in the environment of the autonomous vehicle. For example, the collision avoidance system may effect changes in the navigation of the autonomous vehicle by operating one or more subsystems in control system 111 to undertake swerving maneuvers, turning maneuvers, braking maneuvers, etc. The collision avoidance system may automatically determine feasible obstacle avoidance maneuvers on the basis of surrounding traffic patterns, road conditions, etc. The collision avoidance system may be configured such that a swerving maneuver is not undertaken when other sensor systems detect vehicles, construction barriers, etc. in the region adjacent the autonomous vehicle that would be swerved into. The collision avoidance system may automatically select the maneuver that is both available and maximizes safety of occupants of the autonomous vehicle. The collision avoidance system may select an avoidance maneuver predicted to cause the least amount of acceleration in a passenger cabin of the autonomous vehicle.

[0046] Figure 4 is a block diagram illustrating an example of a velocity limiter module according to one embodiment. Referring to Figure 4, velocity limiter module 308 can determine upper bound velocity limits for an ADV based on one or more feasible areas (e.g., cautionary areas) surrounding one or more pedestrians. Velocity limiter module 308 can then generate a driving trajectory for the ADV based on the upper bound velocity limits such that if the ADV is within the feasible area the ADV is to decelerate. In one embodiment, velocity limiter module 308 includes image receiver/pre-processor module 401, feasible area generator module 403, velocity limit determiner module 405, and trajectory generator module 407. Image receiver/pre-processor module 401 can receive an image captured by an image capturing device (e.g., one or more cameras) of the ADV. Image receiver/pre-processor module 401 can also pre-process the images. Pre-processing can include, but is not limited to, adjusting an exposure control, a gain

control, a tone mapping, white balancing, and demosaic & bilateral filtering to be applied to the image. Pre-processing the images prepares the images to better identify objects (e.g., pedestrians) in the images with varying time of day and weather conditions. For example, at night time, there should be a higher amount of light exposure in an image than at day time, such that objects can be better identified. Another example of pre-processing includes scaling and/or cropping the images to a standard image size, such that different cameras having different settings can be used for the image capturing device. Feasible area generator module 403 can generate a feasible area for each detected object (e.g., pedestrian). The feasible area is a cautionary area that indicates that ADVs within the feasible area should proceed with caution, e.g., ADVs should reduce vehicle speed based on a predetermined speed limit, capture images at a higher frame rate per second, and/or brake to stop, etc. Velocity limit determiner module 403 can determine a velocity limit for a given object/obstacle (e.g., pedestrian) according to a velocity limit model (as part of velocity limit models 313 of Figure 3A). Trajectory generator module 405 can generate a trajectory based on any determined velocity limit to control the ADV so to limit the velocity of the ADV near pedestrians.

[0047] Figure 5 is a block diagram illustrating an example of a campus scene according to one embodiment. Referring to Figure 5, in one embodiment, scene 500 includes both object 501 (e.g., pedestrian) and ADV 101 in motion. Scene 500 may represent a low speed zone on a university campus or any low speed area. When ADV 101 initially enters or is within the low speed zone (as determined by map and route information 311), ADV 101 is to enable/activate velocity limiter module 308. Similarly when ADV 101 exits or is outside of the low speed zone (as determined by map and route information 311), ADV 101 can disable/de-activate velocity limiter module 308.

[0048] While in the low speed zone, in one embodiment, an image receiver module, such as image receiver/pre-processor module 401 of velocity limiter module 308 of Figure 4, receives an image from an image sensor of the ADV. Image receiver 401 may process the image to identify a number of obstacles or objects near ADV 101. For example, ADV 101 may identify pedestrian 501 as an obstacle in motion. Image receiver 401 may receive subsequent image frames and detect, via a machine learning model or image segmentation model a direction, a speed, and/or an orientation of pedestrian 501. In another embodiment, velocity limiter module 308 may receive from a perception module, such as perception module 302 of Figure 3A, pedestrian information (e.g., direction, speed, and orientation) for pedestrian 501.

[0049] Based on the pedestrian/obstacle information, a feasible area generator module, such as module 403 of Figure 4, then generates feasible area 505 for pedestrian 501 to be used for ADV-pedestrian interactions. For example, if ADV 101 is within feasible area 505 then a velocity limit determiner module, such as module 405 of Figure 4, can determine an upper bound velocity limit to be applied to ADV 101. In one embodiment, a projection (e.g., projection 507) of the moving obstacle is determined to be a perpendicular point of intersection for a current location of pedestrian 501, e.g., (x_0, y_0) , and ADV 101. In one embodiment, the velocity limit may be determined based on a distance (e.g., distance d) between ADV 101 and the projection of pedestrian 501 (e.g., projection 507). Additionally, a new feasible area may be generated and a new velocity limit may be determined if ADV 101 determines that pedestrian 501 is to change its course of motion or stops moving. Note that the shape of the feasible area is not limited to a circular shape, and it can be other shapes such as an elliptical shape or a rectangular shape, etc.

[0050] Based on the velocity limit, a trajectory generator module, such as module 407 of Figure 4, can then generate a trajectory with a velocity less than the velocity limit. The velocity

limit in effect can causes ADV 101 to keep a safe distance from pedestrian 501, e.g., ADV 101 would decelerate according to a distance between ADV 101 and pedestrian 501 as ADV 101 approaches pedestrian 501 or a speed of ADV 101 is to taper to a velocity limit if ADV 101 simply passes by pedestrian 501. Although Figure 5 only shows one pedestrian 501 for the purpose of illustration, multiple pedestrians can be detected and multiple feasible areas can be generated. In this case, based on the multiple feasible areas, a lowest velocity limit can be used to generate the trajectory.

[0051] To generate a feasible area, in one embodiment, a size and a center point of the feasible area is determined according to an orientation (and/or velocity direction) and speed of pedestrian 501. In one embodiment, feasible area 505 can be a circular shape. Feasible area 505 may have a circular radius proportion to a speed of pedestrian 501. In one embodiment, the radius is linearly proportional to the speed of pedestrian 501, e.g., $radius \propto pv$, where p is a constant and v is the speed of pedestrian 501. In another embodiment, feasible area can be an oval shape or an elliptical shape.

[0052] For feasible area 505, center point 503 can be determined as: $center(x, y) = f(\theta) + (x_0, y_0)$, where θ is a velocity direction of pedestrian 501 and (x_0, y_0) is a current positional coordinate of pedestrian 501. Here, $f(\theta)$ can be a prediction for subsequent motions of pedestrian 501 as it moves away from its current coordinates, e.g., a projection of the pedestrian. In one embodiment, center point 503 for feasible area 505 is determined for pedestrian 501 at time T , where T is $\frac{v_{bound}}{acc_{max}} + k$, v_{bound} is a maximum velocity of ADV 101 or a maximum velocity determined by a roadway of the ADV in the low speed zone, acc_{max} is a maximum acceleration or deceleration (e.g., brake) of the ADV, and k is a constant. In one embodiment, based on the

directional velocity θ for the time interval T , $f(\theta)$ can be determined as $T * \theta$ and the center point 503 can then be determined according to the equation: $center(x, y) = f(\theta) + (x_0, y_0)$.

[0053] A velocity limit at time T would then be determined based on equation: $v_{limit} = v_0 e^{\frac{-\alpha}{d}}$, where v_0 is a current velocity of ADV 101, α is an attenuation rate, and d is a distance between the ADV and projection 507 of the moving obstacle at a current time. In one embodiment, projection 507 is located at a perpendicular intersection between a current location of pedestrian 501, e.g., (x_0, y_0) , and ADV 101. The attenuation rate can be used to adjust how quickly the velocity limit changes with respect to distance d . In one embodiment, α is a constant value (e.g., >1) or a value preconfigured by a user of ADV 101. Once the velocity limit is determined, the velocity limit can be applied to a trajectory, which is generated by a trajectory generator module, such as module 407 of Figure 4, to limit a velocity of the trajectory such that a speed of the trajectory is to taper to v_{limit} .

[0054] Figure 6 is a flow diagram illustrating a method according to one embodiment. Processing 600 may be performed by processing logic which may include software, hardware, or a combination thereof. For example, process 600 may be performed by velocity limiter module 308 of Figure 3A. Referring to Figure 6, at block 601, processing logic receives a captured image perceiving an environment of an ADV from an image capturing device of the ADV, where the captured image identifies an obstacle in motion near the ADV. At block 602, processing logic generates a feasible area surrounding the moving obstacle based on a projection of the moving obstacle. At block 603, if the ADV is within the feasible area, processing logic determines an upper bound velocity limit for the ADV. At block 604, processing logic generates a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV

autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

[0055] In one embodiment, the generated feasible area includes a center location determined based on a velocity direction of the moving obstacle for time T , and a radius determined based on a speed of the moving obstacle. In another embodiment, a location of the projection of the moving obstacle is determined based on a current location of the moving obstacle and a velocity direction of the moving obstacle. In another embodiment, the location of the projection of the moving obstacle is determined as a perpendicular point of intersection between the moving obstacle and the ADV (see e.g., Figure 5). In another embodiment, the upper bound velocity limit is determined based on a distance between the ADV and the projection of the moving obstacle at a current time.

[0056] In another embodiment, the upper bound velocity limit or velocity limit (v_{limit}) for the ADV at time T is $v_0 e^{\frac{-\alpha}{d}}$, where v_0 is a current velocity of the ADV, α is an attenuation rate and d is the distance between the ADV and the projection of the moving obstacle at a current time. In another embodiment, time T can be determined by: $T = \frac{v_{bound}}{acc_{max}} + k$, where v_{bound} is a maximum velocity of the ADV or a maximum velocity determined by a roadway of the ADV, acc_{max} is a maximum acceleration of the ADV, and k is a constant. In one embodiment, the moving obstacle is a pedestrian.

[0057] Note that some or all of the components as shown and described above may be implemented in software, hardware, or a combination thereof. For example, such components can be implemented as software installed and stored in a persistent storage device, which can be loaded and executed in a memory by a processor (not shown) to carry out the processes or operations described throughout this application. Alternatively, such components can be

implemented as executable code programmed or embedded into dedicated hardware such as an integrated circuit (e.g., an application specific IC or ASIC), a digital signal processor (DSP), or a field programmable gate array (FPGA), which can be accessed via a corresponding driver and/or operating system from an application. Furthermore, such components can be implemented as specific hardware logic in a processor or processor core as part of an instruction set accessible by a software component via one or more specific instructions.

[0058] Figure 7 is a block diagram illustrating an example of a data processing system which may be used with one embodiment of the disclosure. For example, system 1500 may represent any of data processing systems described above performing any of the processes or methods described above, such as, for example, perception and planning system 110 or servers 103-104 of Figure 1. System 1500 can include many different components. These components can be implemented as integrated circuits (ICs), portions thereof, discrete electronic devices, or other modules adapted to a circuit board such as a motherboard or add-in card of the computer system, or as components otherwise incorporated within a chassis of the computer system.

[0059] Note also that system 1500 is intended to show a high level view of many components of the computer system. However, it is to be understood that additional components may be present in certain implementations and furthermore, different arrangement of the components shown may occur in other implementations. System 1500 may represent a desktop, a laptop, a tablet, a server, a mobile phone, a media player, a personal digital assistant (PDA), a Smartwatch, a personal communicator, a gaming device, a network router or hub, a wireless access point (AP) or repeater, a set-top box, or a combination thereof. Further, while only a single machine or system is illustrated, the term “machine” or “system” shall also be taken to

include any collection of machines or systems that individually or jointly execute a set (or multiple sets) of instructions to perform any one or more of the methodologies discussed herein.

[0060] In one embodiment, system 1500 includes processor 1501, memory 1503, and devices 1505-1508 connected via a bus or an interconnect 1510. Processor 1501 may represent a single processor or multiple processors with a single processor core or multiple processor cores included therein. Processor 1501 may represent one or more general-purpose processors such as a microprocessor, a central processing unit (CPU), or the like. More particularly, processor 1501 may be a complex instruction set computing (CISC) microprocessor, reduced instruction set computing (RISC) microprocessor, very long instruction word (VLIW) microprocessor, or processor implementing other instruction sets, or processors implementing a combination of instruction sets. Processor 1501 may also be one or more special-purpose processors such as an application specific integrated circuit (ASIC), a cellular or baseband processor, a field programmable gate array (FPGA), a digital signal processor (DSP), a network processor, a graphics processor, a communications processor, a cryptographic processor, a co-processor, an embedded processor, or any other type of logic capable of processing instructions.

[0061] Processor 1501, which may be a low power multi-core processor socket such as an ultra-low voltage processor, may act as a main processing unit and central hub for communication with the various components of the system. Such processor can be implemented as a system on chip (SoC). Processor 1501 is configured to execute instructions for performing the operations and steps discussed herein. System 1500 may further include a graphics interface that communicates with optional graphics subsystem 1504, which may include a display controller, a graphics processor, and/or a display device.

[0062] Processor 1501 may communicate with memory 1503, which in one embodiment can be implemented via multiple memory devices to provide for a given amount of system memory. Memory 1503 may include one or more volatile storage (or memory) devices such as random access memory (RAM), dynamic RAM (DRAM), synchronous DRAM (SDRAM), static RAM (SRAM), or other types of storage devices. Memory 1503 may store information including sequences of instructions that are executed by processor 1501, or any other device. For example, executable code and/or data of a variety of operating systems, device drivers, firmware (e.g., input output basic system or BIOS), and/or applications can be loaded in memory 1503 and executed by processor 1501. An operating system can be any kind of operating systems, such as, for example, Robot Operating System (ROS), Windows® operating system from Microsoft®, Mac OS®/iOS® from Apple, Android® from Google®, LINUX, UNIX, or other real-time or embedded operating systems.

[0063] System 1500 may further include IO devices such as devices 1505-1508, including network interface device(s) 1505, optional input device(s) 1506, and other optional IO device(s) 1507. Network interface device 1505 may include a wireless transceiver and/or a network interface card (NIC). The wireless transceiver may be a WiFi transceiver, an infrared transceiver, a Bluetooth transceiver, a WiMax transceiver, a wireless cellular telephony transceiver, a satellite transceiver (e.g., a global positioning system (GPS) transceiver), or other radio frequency (RF) transceivers, or a combination thereof. The NIC may be an Ethernet card.

[0064] Input device(s) 1506 may include a mouse, a touch pad, a touch sensitive screen (which may be integrated with display device 1504), a pointer device such as a stylus, and/or a keyboard (e.g., physical keyboard or a virtual keyboard displayed as part of a touch sensitive screen). For example, input device 1506 may include a touch screen controller coupled to a

touch screen. The touch screen and touch screen controller can, for example, detect contact and movement or break thereof using any of a plurality of touch sensitivity technologies, including but not limited to capacitive, resistive, infrared, and surface acoustic wave technologies, as well as other proximity sensor arrays or other elements for determining one or more points of contact with the touch screen.

[0065] IO devices 1507 may include an audio device. An audio device may include a speaker and/or a microphone to facilitate voice-enabled functions, such as voice recognition, voice replication, digital recording, and/or telephony functions. Other IO devices 1507 may further include universal serial bus (USB) port(s), parallel port(s), serial port(s), a printer, a network interface, a bus bridge (e.g., a PCI-PCI bridge), sensor(s) (e.g., a motion sensor such as an accelerometer, gyroscope, a magnetometer, a light sensor, compass, a proximity sensor, etc.), or a combination thereof. Devices 1507 may further include an imaging processing subsystem (e.g., a camera), which may include an optical sensor, such as a charged coupled device (CCD) or a complementary metal-oxide semiconductor (CMOS) optical sensor, utilized to facilitate camera functions, such as recording photographs and video clips. Certain sensors may be coupled to interconnect 1510 via a sensor hub (not shown), while other devices such as a keyboard or thermal sensor may be controlled by an embedded controller (not shown), dependent upon the specific configuration or design of system 1500.

[0066] To provide for persistent storage of information such as data, applications, one or more operating systems and so forth, a mass storage (not shown) may also couple to processor 1501. In various embodiments, to enable a thinner and lighter system design as well as to improve system responsiveness, this mass storage may be implemented via a solid state device (SSD). However in other embodiments, the mass storage may primarily be implemented using a

hard disk drive (HDD) with a smaller amount of SSD storage to act as a SSD cache to enable non-volatile storage of context state and other such information during power down events so that a fast power up can occur on re-initiation of system activities. Also a flash device may be coupled to processor 1501, e.g., via a serial peripheral interface (SPI). This flash device may provide for non-volatile storage of system software, including BIOS as well as other firmware of the system.

[0067] Storage device 1508 may include computer-accessible storage medium 1509 (also known as a machine-readable storage medium or a computer-readable medium) on which is stored one or more sets of instructions or software (e.g., module, unit, and/or logic 1528) embodying any one or more of the methodologies or functions described herein. Processing module/unit/logic 1528 may represent any of the components described above, such as, for example, velocity limiter module 308 of Figure 3A. Processing module/unit/logic 1528 may also reside, completely or at least partially, within memory 1503 and/or within processor 1501 during execution thereof by data processing system 1500, memory 1503 and processor 1501 also constituting machine-accessible storage media. Processing module/unit/logic 1528 may further be transmitted or received over a network via network interface device 1505.

[0068] Computer-readable storage medium 1509 may also be used to store the some software functionalities described above persistently. While computer-readable storage medium 1509 is shown in an exemplary embodiment to be a single medium, the term “computer-readable storage medium” should be taken to include a single medium or multiple media (e.g., a centralized or distributed database, and/or associated caches and servers) that store the one or more sets of instructions. The terms “computer-readable storage medium” shall also be taken to include any medium that is capable of storing or encoding a set of instructions for execution by the machine

and that cause the machine to perform any one or more of the methodologies of the present disclosure. The term “computer-readable storage medium” shall accordingly be taken to include, but not be limited to, solid-state memories, and optical and magnetic media, or any other non-transitory machine-readable medium.

[0069] Processing module/unit/logic 1528, components and other features described herein can be implemented as discrete hardware components or integrated in the functionality of hardware components such as ASICS, FPGAs, DSPs or similar devices. In addition, processing module/unit/logic 1528 can be implemented as firmware or functional circuitry within hardware devices. Further, processing module/unit/logic 1528 can be implemented in any combination hardware devices and software components.

[0070] Note that while system 1500 is illustrated with various components of a data processing system, it is not intended to represent any particular architecture or manner of interconnecting the components; as such details are not germane to embodiments of the present disclosure. It will also be appreciated that network computers, handheld computers, mobile phones, servers, and/or other data processing systems which have fewer components or perhaps more components may also be used with embodiments of the disclosure.

[0071] Some portions of the preceding detailed descriptions have been presented in terms of algorithms and symbolic representations of operations on data bits within a computer memory. These algorithmic descriptions and representations are the ways used by those skilled in the data processing arts to most effectively convey the substance of their work to others skilled in the art. An algorithm is here, and generally, conceived to be a self-consistent sequence of operations leading to a desired result. The operations are those requiring physical manipulations of physical quantities.

[0072] It should be borne in mind, however, that all of these and similar terms are to be associated with the appropriate physical quantities and are merely convenient labels applied to these quantities. Unless specifically stated otherwise as apparent from the above discussion, it is appreciated that throughout the description, discussions utilizing terms such as those set forth in the claims below, refer to the action and processes of a computer system, or similar electronic computing device, that manipulates and transforms data represented as physical (electronic) quantities within the computer system's registers and memories into other data similarly represented as physical quantities within the computer system memories or registers or other such information storage, transmission or display devices.

[0073] Embodiments of the disclosure also relate to an apparatus for performing the operations herein. Such a computer program is stored in a non-transitory computer readable medium. A machine-readable medium includes any mechanism for storing information in a form readable by a machine (e.g., a computer). For example, a machine-readable (e.g., computer-readable) medium includes a machine (e.g., a computer) readable storage medium (e.g., read only memory ("ROM"), random access memory ("RAM"), magnetic disk storage media, optical storage media, flash memory devices).

[0074] The processes or methods depicted in the preceding figures may be performed by processing logic that comprises hardware (e.g. circuitry, dedicated logic, etc.), software (e.g., embodied on a non-transitory computer readable medium), or a combination of both. Although the processes or methods are described above in terms of some sequential operations, it should be appreciated that some of the operations described may be performed in a different order. Moreover, some operations may be performed in parallel rather than sequentially.

[0075] Embodiments of the present disclosure are not described with reference to any particular programming language. It will be appreciated that a variety of programming languages may be used to implement the teachings of embodiments of the disclosure as described herein.

[0076] In the foregoing specification, embodiments of the disclosure have been described with reference to specific exemplary embodiments thereof. It will be evident that various modifications may be made thereto without departing from the broader spirit and scope of the disclosure as set forth in the following claims. The specification and drawings are, accordingly, to be regarded in an illustrative sense rather than a restrictive sense.

CLAIMS

What is claimed is:

1. A computer-implemented method for an autonomous driving vehicle (ADV), the method comprising:
 - receiving a captured image perceiving an environment of an ADV from an image capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV;
 - generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle;
 - if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV; and
 - generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.
2. The method of claim 1, wherein the generated feasible area includes a center location determined based on a velocity direction of the moving obstacle for time T , and a radius determined based on a speed of the moving obstacle.
3. The method of claim 2, wherein a location of the projection of the moving obstacle is determined based on a current location of the moving obstacle and the ADV.
4. The method of claim 3, wherein the upper bound velocity limit is determined based on a distance between the ADV and the projection of the moving obstacle at a current time.

5. The method of claim 3, wherein the velocity limit (v_{limit}) is $v_0 e^{\frac{-\alpha}{d}}$, wherein v_0 is a current velocity of the ADV, α is an attenuation rate and d is the distance between the ADV and the projection of the moving obstacle at a current time.

6. The method of claim 3, wherein time T is $\frac{v_{bound}}{acc_{max}} + k$, wherein v_{bound} is a maximum velocity of the ADV or a maximum velocity determined by a roadway of the ADV, acc_{max} is a maximum acceleration of the ADV, and k is a constant.

7. The method of claim 1, wherein the moving obstacle is a pedestrian.

8. A non-transitory machine-readable medium having instructions stored therein, which when executed by a processor, cause the processor to perform operations, the operations comprising:

receiving a captured image perceiving an environment of an ADV from an image

capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV;

generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle;

if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV; and

generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

9. The non-transitory machine-readable medium of claim 8, wherein the generated feasible area includes a center location determined based on a velocity direction of the moving obstacle for time T , and a radius determined based on a speed of the moving obstacle.
10. The non-transitory machine-readable medium of claim 9, wherein a location of the projection of the moving obstacle is determined based on a current location of the moving obstacle and the ADV.
11. The non-transitory machine-readable medium of claim 10, wherein the upper bound velocity limit is determined based on a distance between the ADV and the projection of the moving obstacle at time T .
12. The non-transitory machine-readable medium of claim 10, wherein the velocity limit (v_{limit}) is $v_0 e^{\frac{-\alpha}{d}}$, wherein v_0 is a current velocity of the ADV, α is an attenuation rate and d is the distance between the ADV and the projection of the moving obstacle at a current time.
13. The non-transitory machine-readable medium of claim 10, wherein time T is $\frac{v_{bound}}{acc_{max}} + k$, wherein v_{bound} is a maximum velocity of the ADV or a maximum velocity determined by a roadway of the ADV, acc_{max} is a maximum acceleration of the ADV, and k is a constant.
14. The non-transitory machine-readable medium of claim 8, wherein the moving obstacle is a pedestrian.
15. A data processing system, comprising:
a processor; and
a memory coupled to the processor to store instructions, which when executed by the processor, cause the processor to perform operations, the operations including:

receiving a captured image perceiving an environment of an ADV from an image capturing device of the ADV, wherein the captured image identifies an obstacle in motion near the ADV,

generating a feasible area surrounding the moving obstacle based on a projection of the moving obstacle,

if the ADV is within the feasible area, determining an upper bound velocity limit for the ADV, and

generating a trajectory having a trajectory velocity less than the upper bound velocity limit to control the ADV autonomously according to the trajectory such that if the ADV is within the feasible area the ADV is to decelerate.

16. The system of claim 15, wherein the generated feasible area includes a center location determined based on a velocity direction of the moving obstacle for time T , and a radius determined based on a speed of the moving obstacle.

17. The system of claim 16, wherein a location of the projection of the moving obstacle is determined based on a current location of the moving obstacle and the ADV.

18. The system of claim 17, wherein the upper bound velocity limit is determined based on a distance between the ADV and the projection of the moving obstacle at a current time.

19. The system of claim 17, wherein the velocity limit (v_{limit}) is $v_0 e^{\frac{-\alpha}{d}}$, wherein v_0 is a current velocity of the ADV, α is an attenuation rate and d is the distance between the ADV and the projection of the moving obstacle at a current time.

20. The system of claim 17, wherein time T is $\frac{v_{bound}}{acc_{max}} + k$, wherein v_{bound} is a maximum velocity of the ADV or a maximum velocity determined by a roadway of the ADV, acc_{max} is a maximum acceleration of the ADV, and k is a constant.
21. The system of claim 15, wherein the moving obstacle is a pedestrian.

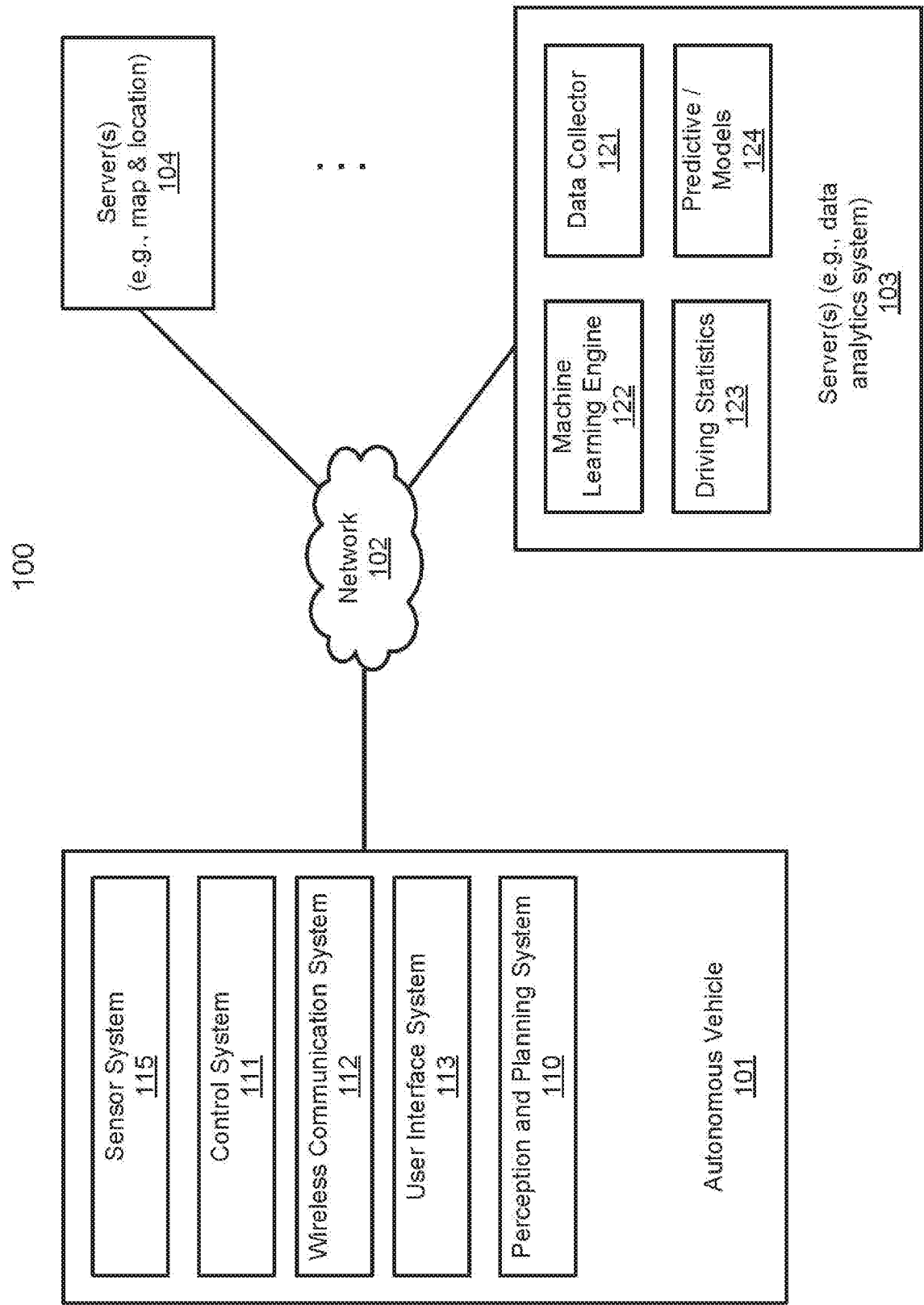


FIG. 1

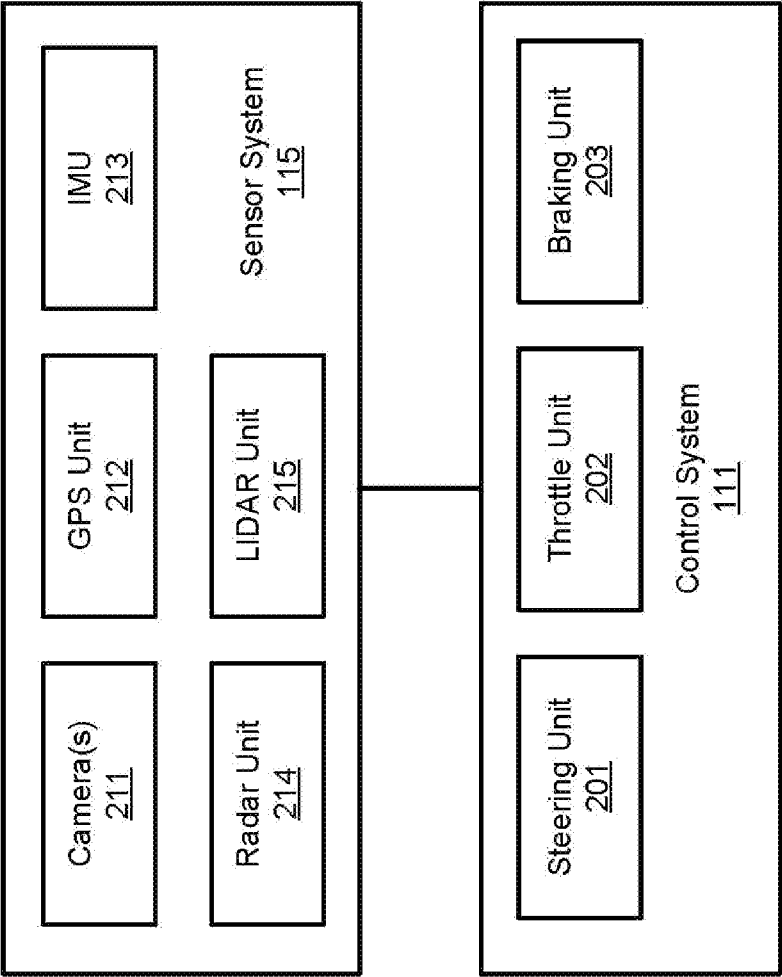


FIG. 2

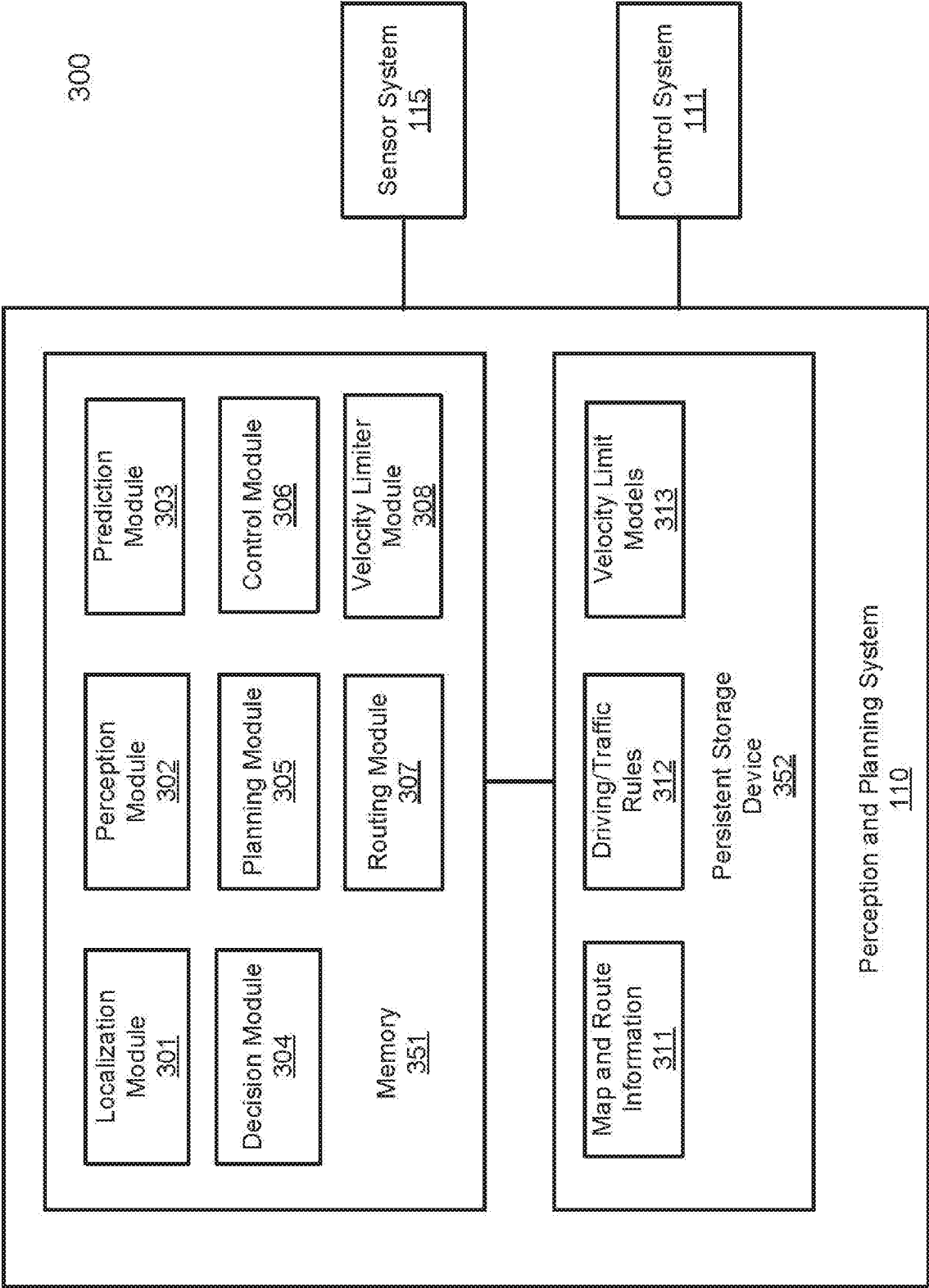


FIG. 3A

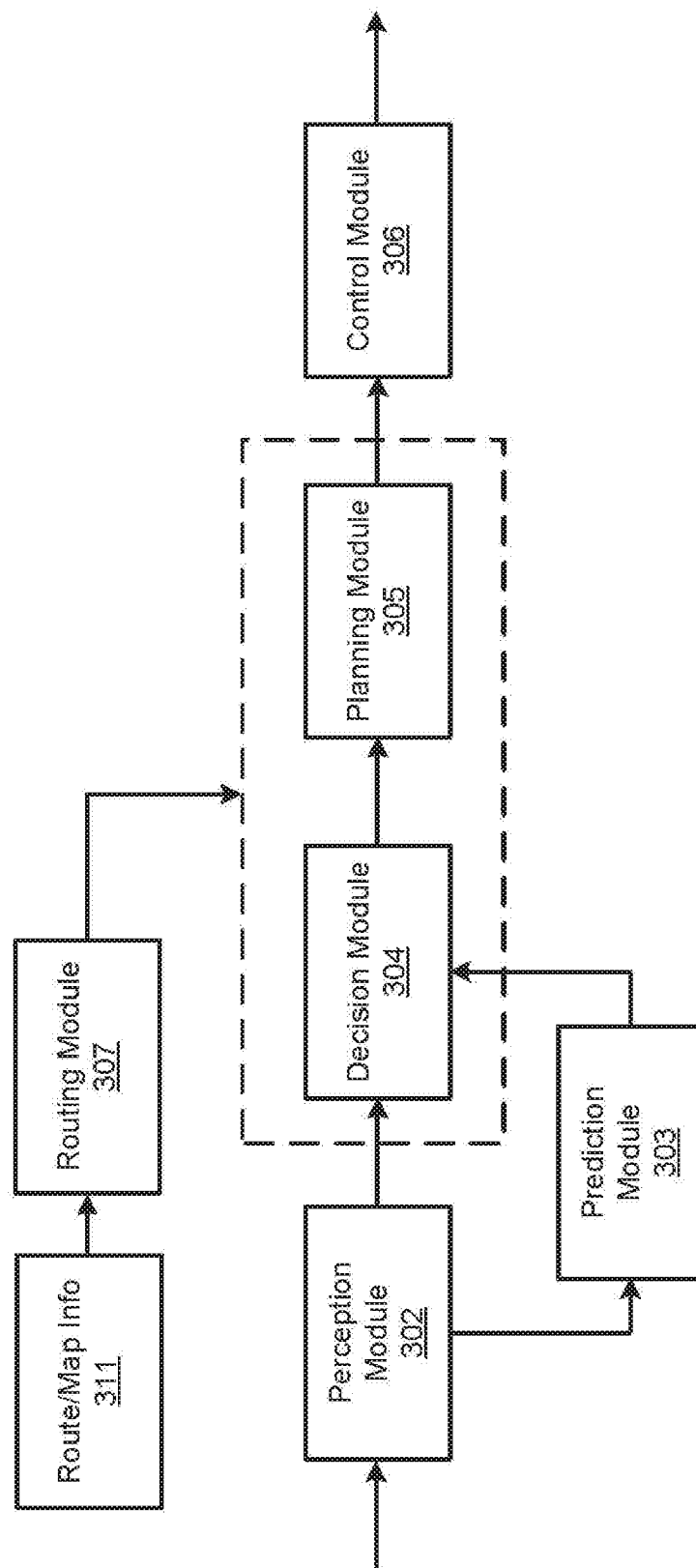


FIG. 3B

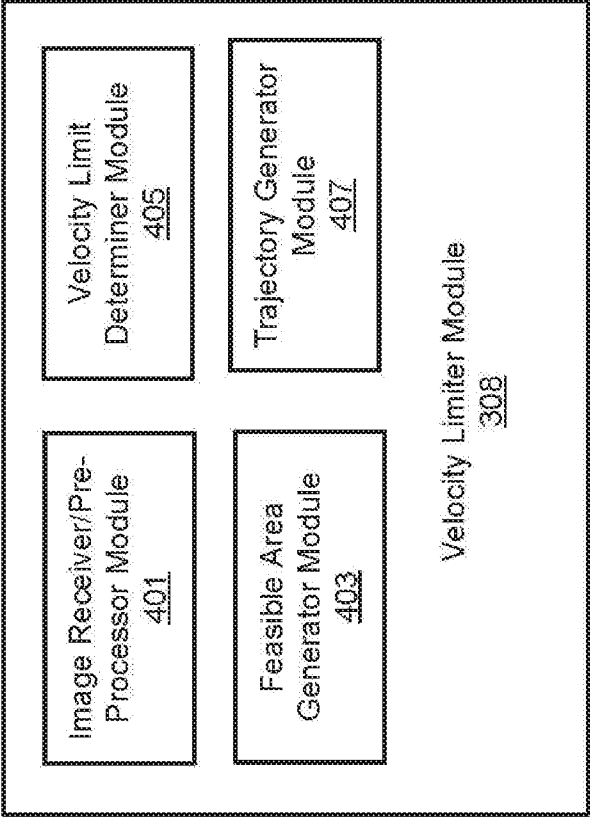


FIG. 4

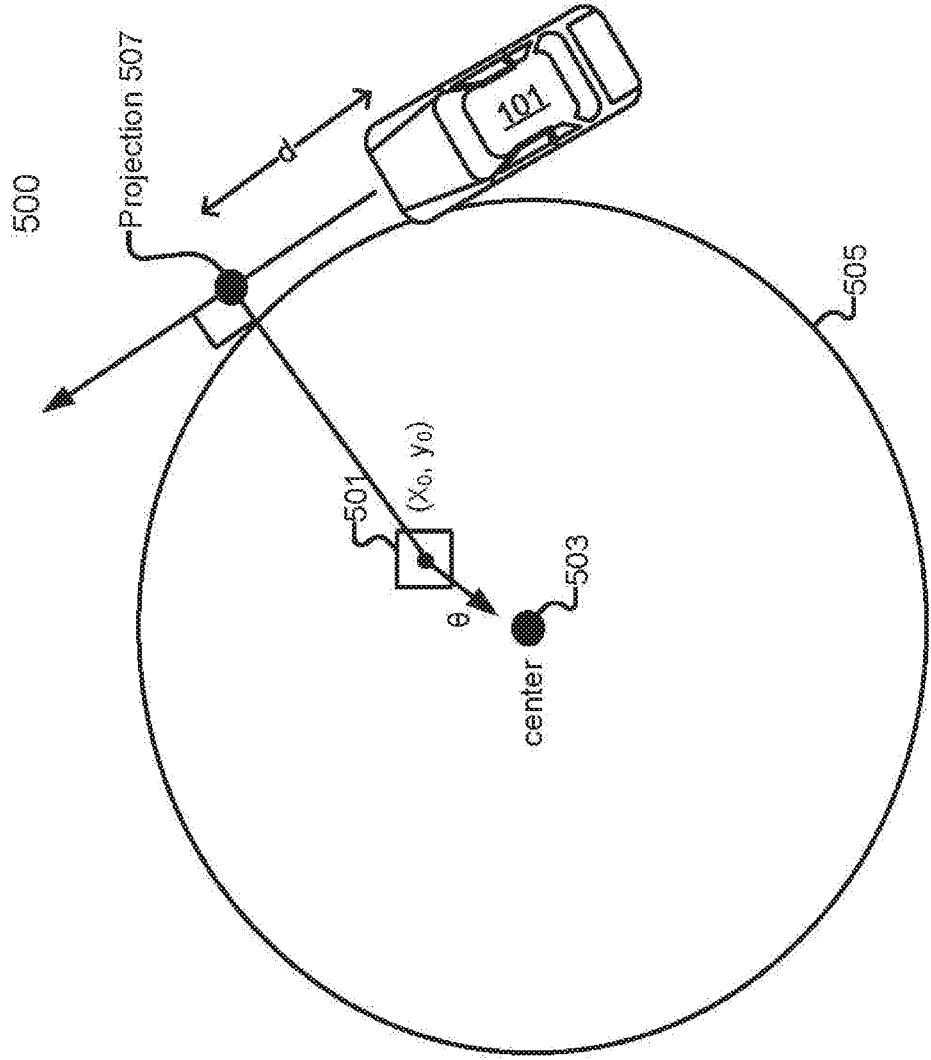


FIG. 5

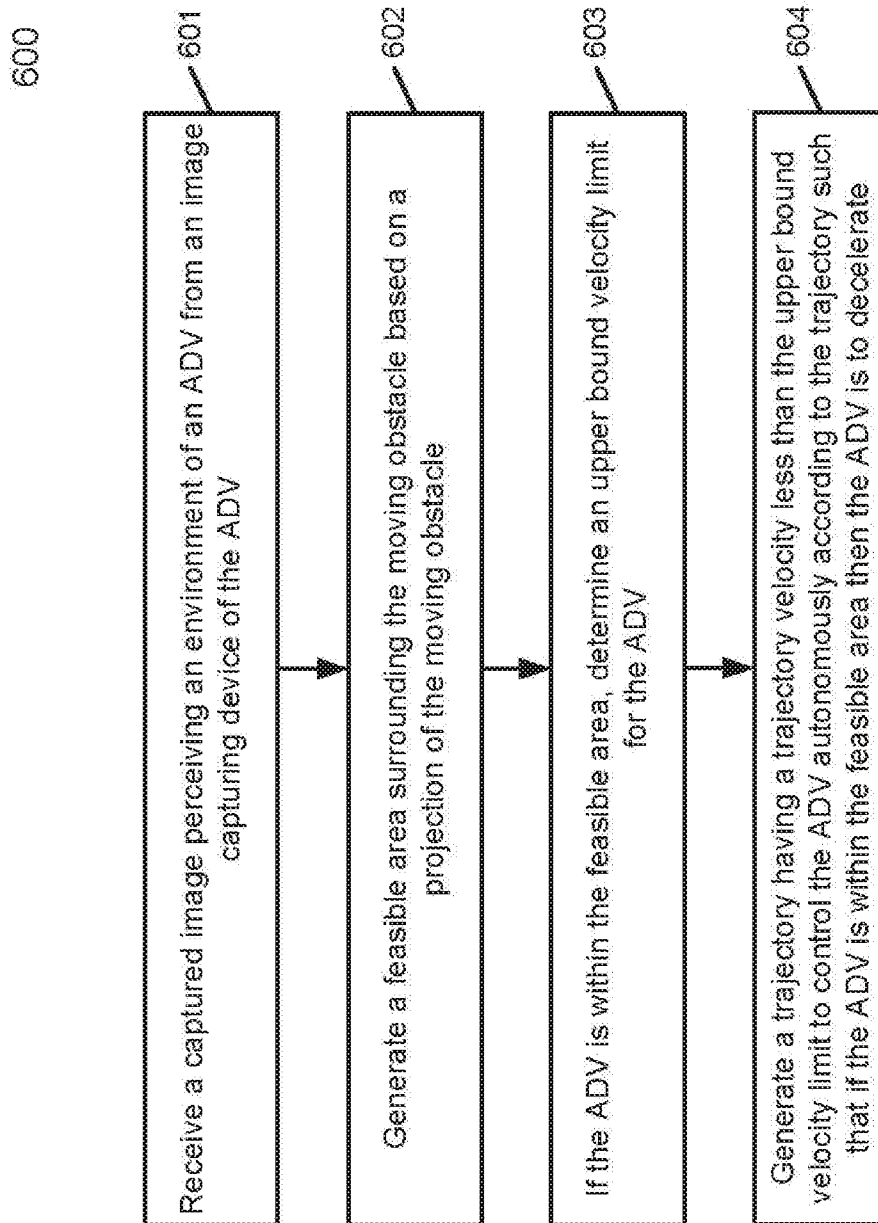


FIG. 6

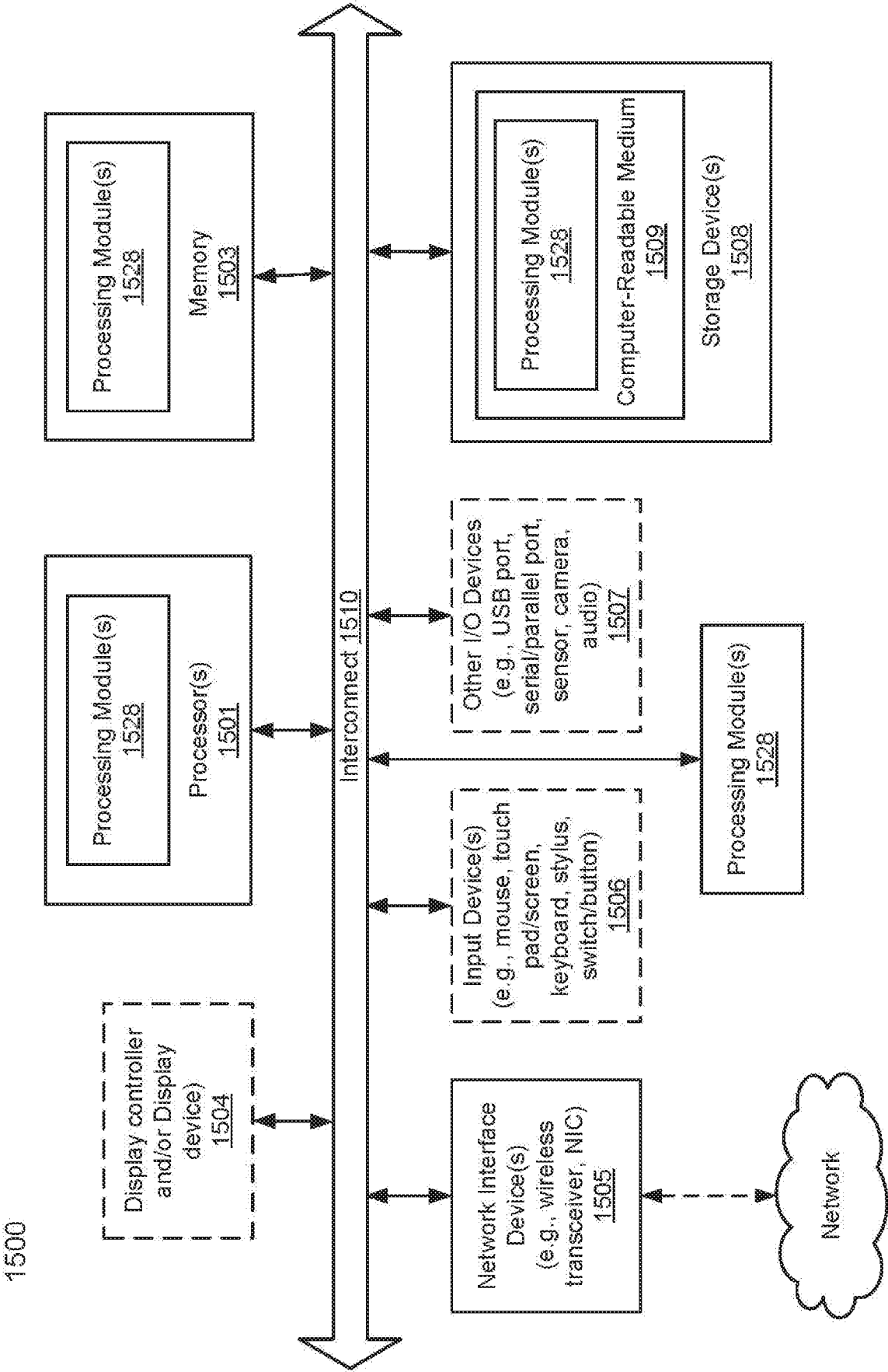


FIG. 7

INTERNATIONAL SEARCH REPORT

International application No.

PCT/CN2018/108356

A. CLASSIFICATION OF SUBJECT MATTER

G05D 1/02(2006.01)i

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

G05D; G08G; B60W; B60R

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

CNABS;TWTEXT;CNTXT;VEN;CJFD:unmanned,autonomous,driving,car,vehicle,aeroplane,airplane,robot,UAV,ADV, obstacle+,pedestrian+,collision,avoid+,path,rout,plan+,surroud+,around+,peripheral,nearby,area,zone,district,decelerat+,brak+, stop+,project+,location,position,distance,velocity,speed,orientation,direction

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	US 20170183003 A1 (MAZDA MOTOR) 29 June 2017 (2017-06-29) claims 1-2, description, paragraphs [0001]-[0004], [0028]-[0050], figures 1-11	1, 7-8, 14-15, 21
Y	US 20170183003 A1 (MAZDA MOTOR) 29 June 2017 (2017-06-29) claims 1-2, description, paragraphs [0001]-[0004], [0028]-[0050], figures 1-11	2-4, 9-11, 16-18
Y	JP 2006039698 A (DENSO CORP) 09 February 2006 (2006-02-09) claims 1 and 3, description, paragraphs [0044] - [0046] and [0059] - [0062], figures 7 and 10.	2-4, 9-11, 16-18
Y	CN 106338996 A (SHANGHAI WUJING INTELLIGENT SCIENCE & TECH CO LTD) 18 January 2017 (2017-01-18) description, paragraphs [0108] to [0113], figure 7	3, 4, 10, 11, 17, 18
A	US 2011213513 A1 (NADERHIRN MICHAEL) 01 September 2011 (2011-09-01) the whole document	1-21
A	EP 3101641 A1 (TOYOTA MOTOR CO LTD) 07 December 2016 (2016-12-07) the whole document	1-21
A	US 2017315559 A1 (SHARP KK) 02 November 2017 (2017-11-02) the whole document	1-21

☐ Further documents are listed in the continuation of Box C.
 ☒ See patent family annex.

* Special categories of cited documents:

“A” document defining the general state of the art which is not considered to be of particular relevance

“E” earlier application or patent but published on or after the international filing date

“L” document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified)

“O” document referring to an oral disclosure, use, exhibition or other means

“P” document published prior to the international filing date but later than the priority date claimed

“T” later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention

“X” document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone

“Y” document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art

“&” document member of the same patent family

Date of the actual completion of the international search

27 November 2018

Date of mailing of the international search report

24 January 2019

Name and mailing address of the ISA/CN

STATE INTELLECTUAL PROPERTY OFFICE OF THE
P.R.CHINA
6, Xitucheng Rd., Jimen Bridge, Haidian District, Beijing
100088
China

Authorized officer

LIU,Nan

Facsimile No. (86-10)62019451

Telephone No. 86-010-62085796

INTERNATIONAL SEARCH REPORT
Information on patent family members

International application No.

PCT/CN2018/108356

Patent document cited in search report			Publication date (day/month/year)	Patent family member(s)			Publication date (day/month/year)
US	20170183003	A1	29 June 2017	JP	6354746	B2	11 July 2018
				JP	2017117157	A	29 June 2017
				US	9896097	B2	20 February 2018
				CN	107021052	A	08 August 2017
JP	2006039698	A	09 February 2006	JP	6315055	B2	25 April 2018
CN	106338996	A	18 January 2017	None			
US	2011213513	A1	01 September 2011	WO	2009040064	A1	02 April 2009
				EP	2193414	A1	09 June 2010
				US	8467953	B2	18 June 2013
				AT	505798	B1	15 December 2011
				EP	2193414	B8	25 April 2018
				AT	505798	A1	15 April 2009
				EP	2193414	B1	21 March 2018
EP	3101641	A1	07 December 2016	KR	101824803	B1	14 March 2018
				CA	2932089	C	19 June 2018
				US	9849876	B2	26 December 2017
				CN	106240560	A	21 December 2016
				BR	102016012783	A2	24 January 2017
				RU	2016121640	A	06 December 2017
				RU	2666071	C2	05 September 2018
				IN	201614018760	A	09 December 2016
				JP	2017004106	A	05 January 2017
				KR	20160143543	A	14 December 2016
				CA	2932089	A1	05 December 2016
				US	2016355181	A1	08 December 2016
US	2017315559	A1	02 November 2017	WO	2016076148	A1	19 May 2016
				JP	2016095703	A	26 May 2016
				US	10108200	B2	23 October 2018