

A tracking control method for collision avoidance trajectory of autonomous vehicle based on multi-constraint MPC

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International journal of vehicle design

2021; 86(1/2/3/4):106-123

ARTICLE IDENTIFIERS

DOI: 10.1504/IJVD.2021.122255

PMID: unavailable

PMCID: not available

JOURNAL IDENTIFIERS

LCCN: not available

pISSN: 0143-3369

eISSN: 1741-5314

OCLC ID: not available

CONS ID: not available

US National Library of Medicine ID: not available

This article was identified from a query of the SafetyLit database.