

# HONDA



## PERSONALIZATION & HMI

ON THE NEXT PAGES YOU CAN SEE SUMMARIES OF THE FOLLOWING PATENTS  
IN THE RESEARCH FIELD PERSONALIZATION & HMI:

EP3081447

INTELLIGENT GAP SETTING FOR ADAPTIVE CRUISE CONTROL

EP2865576

COMPOSITE CONFIDENCE ESTIMATION FOR PREDICTIVE  
DRIVER ASSISTANT SYSTEMS

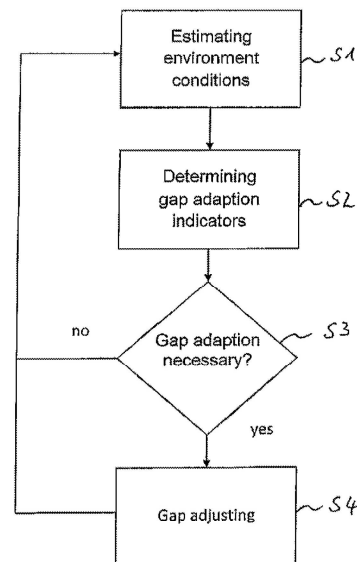
**Intelligent gap setting for adaptive cruise control  
EP3081447 B1**

<p><b>Current assignees</b> HONDA RESEARCH INSTITUTE EUROPE*</p> <p><b>Inventors</b> REBHAN SVEN KLEINEHAGENBROCK MARCUS</p> <p><b>Filing date:</b> 2015-04-14</p> <p><b>Granting Date:</b> 2020-07-01</p>	<p><b>IPC - International classification</b> B60R-021/0132    B60W-030/16*    G08G-001/16</p> <p><b>CPC - Cooperative classification</b> B60W-030/16*    B60W-2530/14    B60W-2540/04 B60W-2540/215    B60W-2550/00    B60W-2550/10 B60W-2550/12    B60W-2550/14    B60W-2550/146 B60W-2550/148    B60W-2550/302    B60W-2550/308 B60W-2550/408    B60W-2552/00    B60W-2552/30 B60W-2552/40    B60W-2554/00    B60W-2554/801 B60W-2554/804    B60W-2555/00    B60W-2555/20 B60W-2556/65    B60W-2750/308    B60W-2754/30</p>
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<b>Family</b>					
JP6812109	B2	JP2016199252	A		
EP3081447	B1	US20160304092	A1		
US9969393	B2	EP3081447	A1		

(EP3081447)

The present invention relates to a method for assisting a driver in driving a vehicle, in which sensor data are produced by at least one sensor (2, 3) physically sensing the environment of a host vehicle (E) and/or by obtaining data conveying information about the environment of a host vehicle (E), an object (A) in a path of the host vehicle (E) is detected based on the sensor data, a distance between the host vehicle (E) and the detected object (A) is controlled based on a preset gap (t GAP ), environmental conditions of the host vehicle (E) are estimated (S1) based on the sensor data, gap adaption indicators associated to the estimated environmental conditions are determined (S2), wherein each of the gap adaption indicators indicates an extension or a reduction of the preset gap (t GAP ) and the preset gap (t GAP ) is adjusted (S4) based on the gap adaption indicators.



**Composite confidence estimation for predictive driver assistant systems**

**EP2865576 B1**

<p><b>Current assignees</b> HONDA RESEARCH INSTITUTE EUROPE*</p>		<p><b>IPC - International classification</b></p>		
<p><b>Inventors</b> SCHMÜDDERICH JENS</p>		B60R-021/0132	B60W-030/08	B60W-030/14
<p><b>Filing date:</b> 2013-10-22</p>		B60W-030/18	B60W-040/04	B60W-050/00*
<p><b>Granting Date:</b> 2018-07-04</p>		G01S-013/93	G06K-009/00	G06K-009/62
		G06N-005/04	G08G-001/16*	
		<p><b>CPC - Cooperative classification</b></p>		
		B60W-030/08	B60W-030/14	B60W-030/16
		B60W-030/18/163	B60W-040/04	B60W-050/00/97*
		B60W-2050/0022	B60W-2550/20	B60W-2554/00
		B60W-2556/20	G06K-009/00/805	G06K-009/62/92
		G06N-005/04		
		<p><b>PCL - US patent classification</b></p>		
		<b>PCLO:</b>	701093000*	
		<b>PCLX:</b>	701001000	

<b>Family</b>				
JP6544908	B2	EP2865576	A1	
EP2865576	B1	JP2015082324	A	
US9308919	B2	US20150112571	A1	

(EP2865576)

The invention relates to a driving assistance system (100) including a prediction subsystem (110) in a vehicle. According to a method aspect of the invention, the method comprises the steps of accepting a set of basic environment representations (120); allocating a set of basic confidence estimates (122); associating weights to the basic confidence estimates (122); calculating (128) a weighted composite confidence estimate for a composite environment representation; and providing the weighted composite confidence estimate as input for an evaluation of a prediction (130, 132) based on the composite environment representation.

