

ABSTRACT

Aspects concern a method for correcting position estimates of a movable object. According to various embodiments, the method comprises establishing (1001) a hidden Markov model, HMM, instance for a movable object and, for positioning times of a sequence of positioning times, receiving (1002) a position estimate from a positioning device of the movable object for a respective positioning time, determining (1003) a set of candidate path segments for the positioning time, determining (1004) likelihoods for the candidate path segments to correspond to the position estimate by application of the Viterbi algorithm to the HMM instance, expanding (1005) the HMM instance by the determined likelihoods for the candidate path segments for the positioning time and determining (1006) a corrected position estimate from a candidate path segment of the set of candidate path segments with the highest likelihood.

FIG. 10