

ABSTRACT

The present disclosure provides a method and apparatus for controlling a vehicle, an electronic device, a computer readable storage medium, a computer program product and an unmanned vehicle, relates to the field of artificial intelligence technology such as data processing, trajectory planning and autonomous driving, and can be applied in autonomous driving scenarios. A specification implementation of the method includes: simulating and deducing, based on current state information between a target vehicle and a traffic participant of the target vehicle, an interaction process between the target vehicle and the traffic participant to obtain an initial part of a cooperative game tree, where a root node in the initial part corresponds to the current state information; updating, in response to there being a target leaf node that is capable of being expanded to obtain a target child node in the initial part, respective nodes on a deduction path from the root node to the target child node based on a path parameter of an updated predicted trajectory obtained by processing a predicted trajectory from the root node to the target child node using an iterative linear quadratic regulator algorithm, to obtain a complete cooperative game tree including the initial part and the target child node; and determining a first control instruction of the target vehicle using the complete cooperative game tree, to control the target vehicle using the first control instruction. Accordingly, not only can the decision-making efficiency in the vehicle control process be improved, but also the trajectory planning can be performed more smoothly and with higher quality, thereby improving the control quality of the vehicle.

Figure 2.