

Abstract

The invention relates to a method for creating a probabilistic free space map with static (2a, 2b, 3) and
5 dynamic objects (V1-V7), having the following steps:

- retrieving (S1) static objects (2a, 2b, 3) as well as a perception area polygon (WP) from an existing environment model;
- collecting (S2) predicted trajectories (T1, T2) of
10 dynamic objects (V1-V7);
- merging (S3) the static objects (2a, 2b, 3) of the perception area polygon (WP) and the predicted trajectories (T1, T2) in a first free space map;
- fixing (S4) a maximum prediction time;
- 15 - fixing (S5) prediction time steps;
- fixing (S6) a current prediction time and setting this current prediction time to the value 0 in order to fix the start of a fixed prediction time period;
- fixing (S7) confidence regions (K) around the static
20 (2a, 2b, 3) and dynamic objects (V1-V7);
- fixing (S8) at least one uncertain region (U) around at least one static (2a, 2b, 3) or dynamic object (V1-V7);
- producing (S9) a first probabilistic free space map
25 for the current prediction time;
- producing (S10) at least one further free space map for at least one prediction time step;
- evaluating (S11) the produced free space maps.

30 (Fig. 1)