



Robust Intersection Management for Connected Autonomous Vehicles

■ Goals

This thesis delves into the safety and performance challenges associated with implementing intersection of autonomous vehicles. It introduces a time and space aware technique designed to address these challenges by being robust against model mismatches, external disturbances, and nondeterministic delays in network and processing time.

■ Requirements

You should understand *Automatic control*, *Machine Learning*, *Automotive*.

Bibliography

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