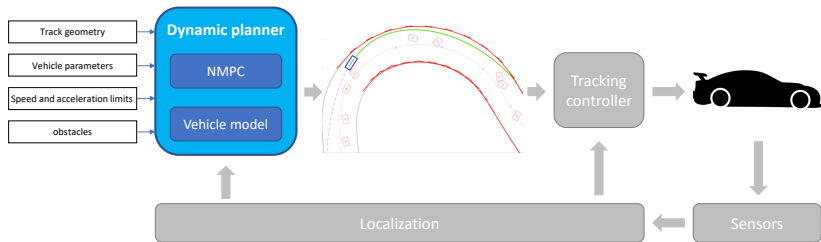


# Dynamic trajectory planning for autonomous racing

Autonomous driving at high speeds with moving obstacles requires continuous re-planning. Considering the kinematic and dynamic constraints of the vehicle is essential for obtaining a feasible path and velocity profile.



## Features and objectives

- Maximizing track progress while considering constraints and avoiding obstacles
- Using techniques from nonlinear model predictive control (NMPC)
- Real-time capable implementation