High Level Controller

The high level controller (HLC) is based on the NUCs. Its purpose is to plan trajectories for one vehicle. In networked trajectory planning, multiple HLCs are involved. Each HLC is responsible for the trajectory of one vehicle.

The HLC is not part of the infrastructure software, but has to use the interfaces of the lab. We recommend to use MATLAB, but you can use any language. We describe example HLCs in the example section.