

The dataset is divided into 2 parts:

1. The raw, unfiltered data, as directly generated by the automated vehicle recognition software of TNO (<https://www.tno.nl/en/focus-areas/defence-safety-security/roadmaps/information-sensor-systems/wide-area-motion-imagery-wami/>)
This database is set up as a structure, in which each vehicle has its own entry. For each vehicle the following data is recorded in the different columns:
 - Datenum: actual time of measurement
 - xx: x-coordinate
 - yy: y-coordinate
 - l: length of the vehicle
 - w: width of the vehicle
 - bbox: boundary box of vehicle recognition
2. The processed and filtered data, as used for research
This database is set up as a structure, in which each vehicle has its own entry. For each vehicle the following data is recorded in the different columns:
 - id: vehicle id
 - t: time step, relative to start of measurement
 - x: x-coördiate - unsmoothed
 - y: y-coördiate - unsmoothed
 - l: length of the vehicle
 - w: width of the vehicle
 - x_sm: x-coördiate - smoothed
 - y_sm: y-coördiate - smoothed
 - dir: driving direction, relative to direction of the motorway
 - v_cal: vehicle's speed
 - a_cal: vehicle's acceleration rate
 - lanes: lane in which the vehicle drivers (-1 = ramp lane, 1 = right lane, 2 = 2nd lane from the right, 3 = 3rd lane from the right)
 - zone: zone in which vehicle drives (zone relative to ramp: 1 = before, 2 = at, 3 = after)
 - lane_adj: the adjacent lanes to current lane (left column: lane on the left, right column: lane on the right. Value = 0 if there is no lane)