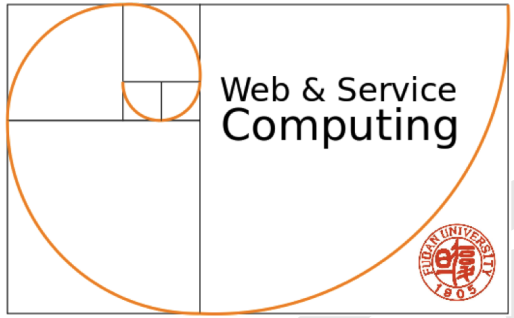

A Priority-Based Policy for Autonomous Intersection Control

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May 5, 2019

Table of Contents

Introduction

- something

Table of Contents

Related Work

1. something

Table of Contents

Background

Point1 the point 1 is

Table of Contents

Motivation

Definition

Block Title

Something in block

Find highest priority request

Algorithm 1: Find highest priority request

Input:
The hashmap to find vehicles in a lane, *l2v*;
The hashmap from vehicle to its request, *v2m*;
Output:
Highest priority request, *request*;
Function

```
    nearest vins ← empty
    foreach lane in the keyset of l2v do
        v ← null
        foreach vin in l2v[lane] do
            v ← nearest vin in this lane
        end
        nearest vins ← nearest vins ∪ v
    end
    if nearest vins is empty then
        return null
    end
    foreach vin in nearest vins do
        request ← highest priority request
    end
    foreach vin in nearest vins do
        if request is not v2m[vin] then
            set v2m[vin]'s priority as twice
        end
    end
end
```

Demo

Something description

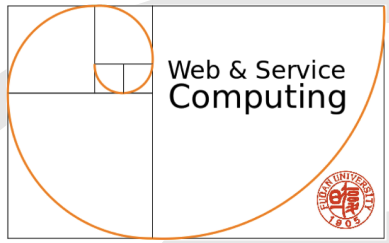

Figure: Caption here

Experiments

Table: average passing using for different policy

Passing Time(s) / Policy / Sim Time(s)	FCFS Policy	Priority-based Policy
50	10.24	9.96
100	14.98	13.56
150	18.83	15.46
200	19.34	15.38
250	21.23	17.86
300	22.65	20.05

Analysis

Table of Contents

Conclusion and Future work

Future work

Table of Contents

Thanks Q&A