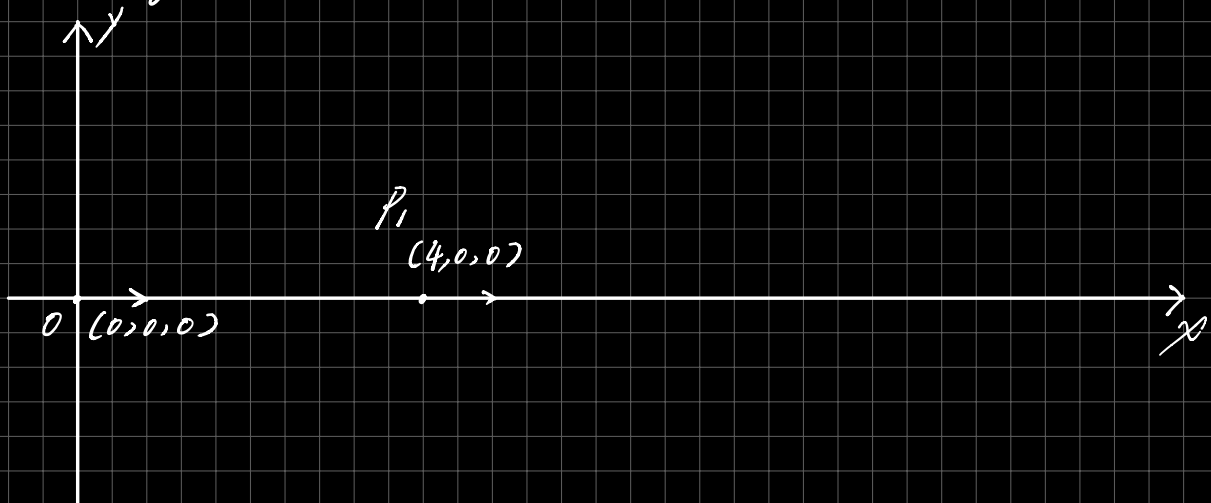
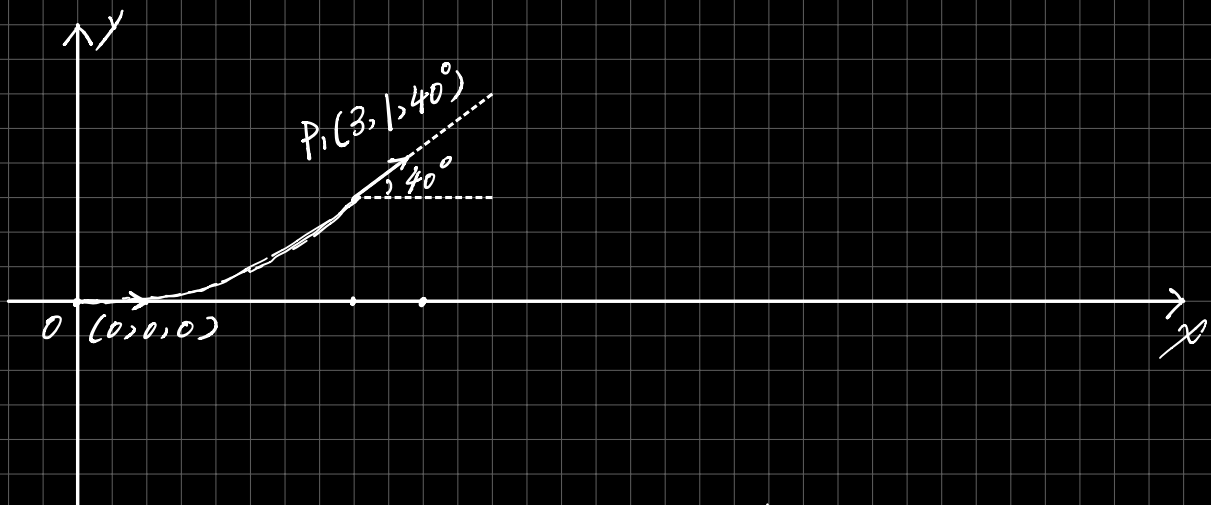


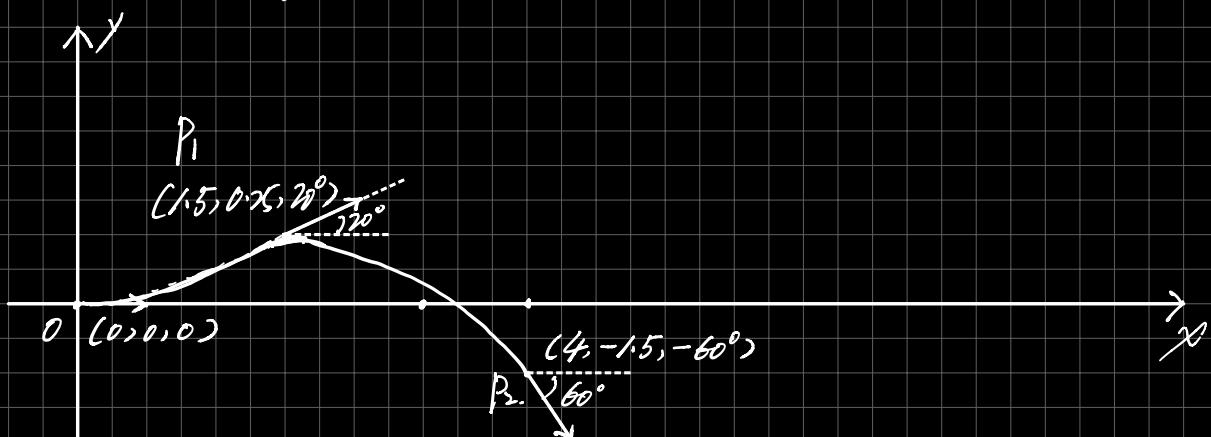
① straight



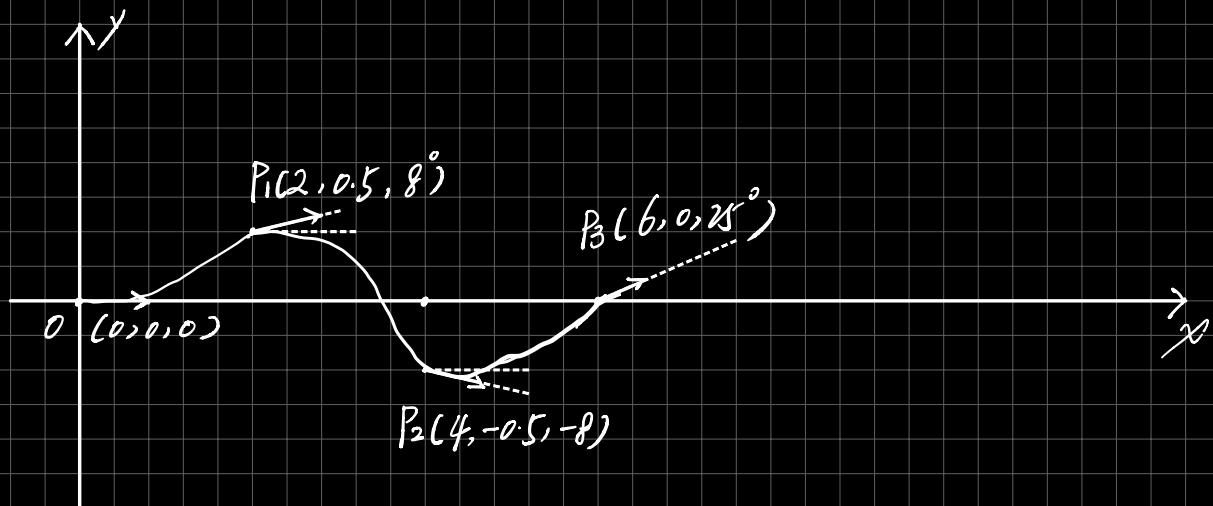
② turning 1. yam! one turning to left or right.



③ two turning 1. yam! combine two turnings.



④ Sturnning 1. gaml: S turning.



Each one has a reflection version about x axis.
You could change the coordinates of the control points. This set of parameters is working at:

$\lambda \approx 5$ velocity_fwd ≈ 0.3

feat-traj-reg-thresh ≈ 3

There may be 0~5 localizations. Sometimes track is lost.