Static path planning

Exit

s_{Ref}^1
s_{Ref}^2
s_{Ref}^3

Entrance

Feature points

Expected velocity

Entrance　Exit

Dynamic optimal tracking

Offline training

Model

V^π

$\bar{\pi} > \pi$

Policy

Value

J

Code Deployment

AI

Online application

Selecting

s_{Ref}^1
s_{Ref}^2
s_{Ref}^3

Value

J_1
J_2
J_3

Tracking

s_{Ref}^2

Policy

Safety shield

Whole space　u^*

u^{safe}
Safe Space

u^{safe}