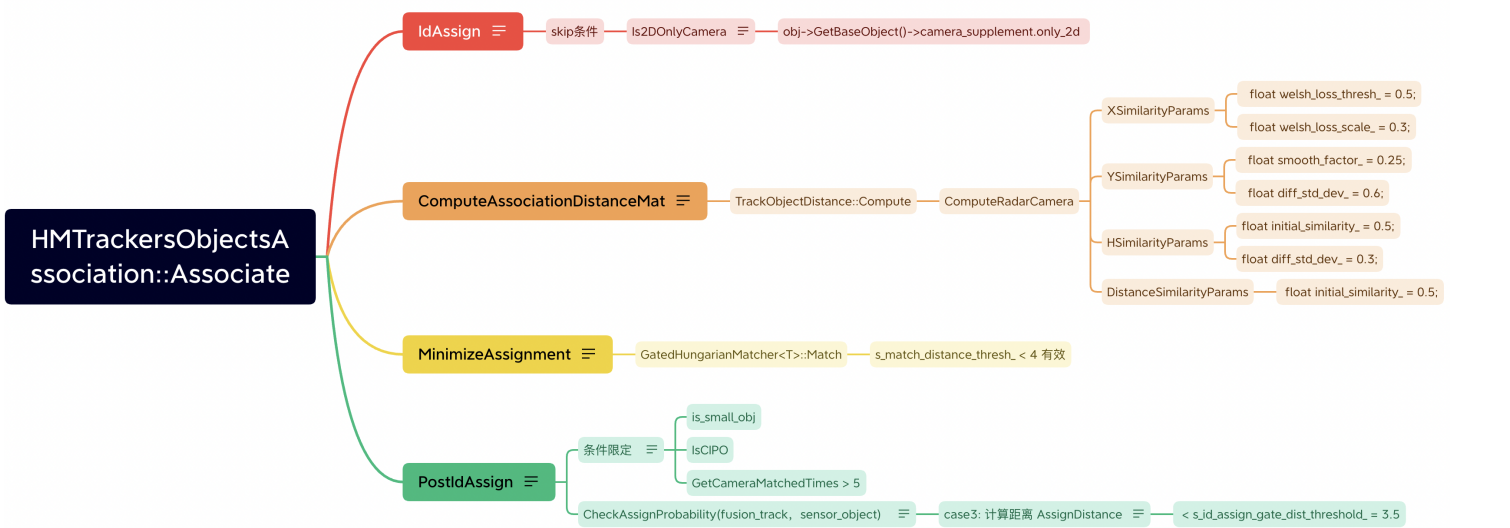


camera与radar关联

@顾恺琦

整体流程



1	应用场景	参数/假设名称	取值	位置	含义
2	Urban	Is2DOnlyCamera		IdAssign	camera报出的障碍物只有2d信息
3		float welsh_loss_thresh_ = 0.5; float welsh_loss_scale_ = 0.3; float scale_positive_max_p_ = 0.9; float scale_positive_th_p_ = 0.5;		ComputeAssociationDistanceMat	XSimilarityParams $e^{-\left(\frac{x_{diff}-x_{th}}{x_{scale}}\right)^2}$
4		float smooth_factor_ = 0.25; float diff_std_dev_ = 0.6; float bounded_scale_positive_max_p_ = 0.9; float bounded_scale_positive_min_p_ = 0.4;			YSimilarityParams $1 - ChiSquare\left(-\frac{diff}{\sigma^2}\right)$
5		float initial_similarity_ = 0.5; float diff_std_dev_ = 0.3; float scale_positive_max_p_ = 0.9; (调整为0.8) float scale_positive_th_p_ = 0.5;			HSimilarityParams $1 - ChiSquare\left(-\frac{diff}{\sigma^2}\right)$
6		float initial_similarity_ = 0.5; float scale_positive_max_p_ = 0.9; float scale_positive_th_p_ = 0.5;			DistanceSimilarityParams
7		float initial_similarity_ = 0.5; float distance_std_scale = 0.05; float measurement_std = 1; float welsh_loss_scale_ = 0.3; float scale_positive_max_p_ = 0.8; float scale_positive_th_p_ = 0.5;			RearDistanceSimilarityParams (仅后向角雷达开启)

8	<div>float welsh_loss_thresh_ = 0.6; float welsh_loss_scale_ = 0.2; float sigmoid_thresh_ = 25; float sigmoid_scale_ = -0.5; float bounded_scale_ = 0.5; float bounded_scale_positive_max_p_ = 0.5; float scale_positive_th_p_ = 0.0;</div>			<div>VelocitySimilarityParams (仅后向角雷达开启)</div>
9	<div>vc_similarity2distance_penalize_thresh_</div>	<div>0.1</div>		<div>根据融合相似性计算radar-camera距离 distance_thresh_ * (1 - similarity) / (1 - vc_similarity2distance_penalize_thresh_)</div>
10	<div>s_association_center_dist_threshold_</div>	<div>30</div>		
11				
12	<div>s_match_distance_thresh_</div>	<div>4</div>	<div>MinimizeAssignment</div>	<div>hm关联阈值</div>
13	<div>is_small_obj</div>	<div>if</div>	<div>PostIdAssign</div>	<div>条件限定</div>
14	<div>IsCIPO</div>	<div>if</div>		<div>条件限定</div>
15	<div>GetCameraMatchedTimes</div>	<div>5</div>		<div>条件限定 GetCameraMatchedTimes &gt; 5</div>
16	<div>s_id_assign_gate_dist_threshold_</div>	<div>3.5</div>		<div>CheckAssignProbability</div>
17	<div>s_camera_matched_times_threshold_</div>	<div>3</div>		
18				
19				

