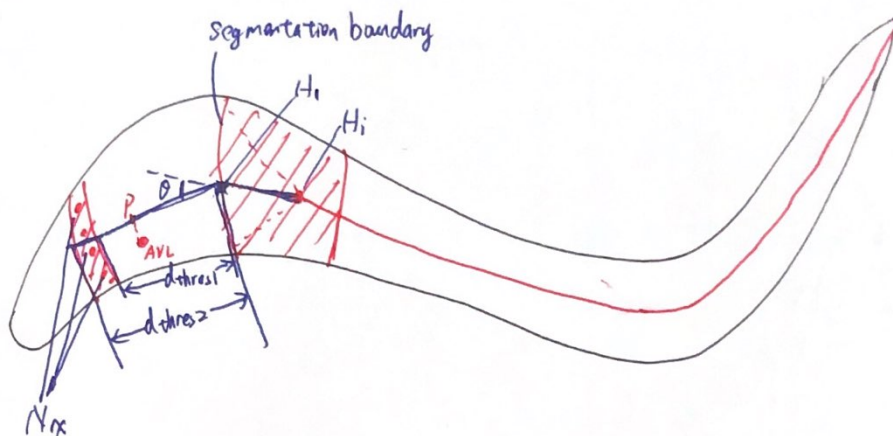


Track AVL



$$\frac{\overrightarrow{N_x P}}{P H_1} = \lambda. \quad H_1 = \text{midpoint of segmentation boundary.}$$

$$H_i = \text{first point (index=i) on the correct centerline.}$$

$$\textcircled{1} \quad \langle \overrightarrow{H_i H_1}, \overrightarrow{H_i N_x} \rangle < \theta_{\text{thres}}$$

$$\textcircled{2} \quad d_{\text{thres1}} < |\overrightarrow{H_1 N_x}| < d_{\text{thres2}}$$

$$\textcircled{3} \quad \min_x |\overrightarrow{H_1 N_x}| \text{ or } \max_x |\overrightarrow{H_1 N_x}| \text{ or } \min_x \langle \overrightarrow{H_i H_1}, \overrightarrow{H_i N_x} \rangle \text{ or } \max_x \langle \overrightarrow{H_i H_1}, \overrightarrow{H_i N_x} \rangle$$

$$\textcircled{4} \quad \frac{\overrightarrow{N_x P}}{P H_1} = \lambda \Rightarrow P = \frac{N_x + \lambda H_1}{1 + \lambda}$$

$$\textcircled{5} \quad \text{anchor} \leftarrow P, \quad \text{single track AVL.}$$

$$201210-F_2 \text{ 参考值: } i=3, \theta_{\text{thres}}=80^\circ, d_{\text{thres}}=[90, 210], \lambda=0.45$$