

The obstacles information in the paper: **Unified human intention recognition and heuristic-based trajectory generation for haptic teleoperation of non-holonomic vehicles.**

Case Index	Obstacles Vertexes	x/m	y/m	A/m <sup>2</sup>
1	1	[1.0536, 5.2076, 7.6904, 3.3020, 1.8175, 1.0536]	[-24.1302, -22.3107, -20.0148, -15.9654, -15.4096, -24.1302]	31.6629
	2	[15.1973, 8.3724, 10.1456, 10.6737, 14.9725, 17.8897, 15.1973]	[5.5654, 1.4575, -0.6598, -0.9698, -0.4894, 1.5285, 5.5654]	34.8589
	3	[20.9764, 21.0103, 17.1429, 13.5067, 20.9764]	[-21.79412, -17.7784, -16.4572, -17.4914, -21.7941]	19.4731
	4	[14.4173, 15.0592, 15.8862, 21.9707, 19.7812, 14.4173]	[20.1218, 11.9258, 11.5422, 12.9179, 19.4847, 20.1218]	47.2923
	5	[1.7098, 0.7440, 1.2033, 6.842, 1.7098]	[-2.0073, -6.6362, -8.5849, -4.5011, -2.0073]	19.5156
2	1	[-6.4966, -0.8523, 0.9215, -6.9614, -6.4966]	[-11.9662, -15.1626, -10.6640, -3.288, -11.9662]	48.0198
	2	[-9.9867, -14.5035, -13.1259, -7.3172, -9.9867]	[-9.9696, -16.8572, -16.3941, -11.6314, -9.9696]	14.8821
	3	[8.9452, 1.5260, -2.4718, 6.5177, 8.9452]	[17.1594, 16.9066, 15.1365, 11.7039, 17.1594]	34.7482
	4	[12.2310, 12.6312, 7.1529, 8.4657, 9.9534, 11.7380, 12.2310]	[-8.7432, -3.7511, -9.0493, -13.9231, -14.4430, -13.8416, -8.7432]	34.4228
	5	[-2.6756, 8.2349, 10.9122, -1.2384, -2.6756]	[-6.3222, -1.9116, -0.5478, 0.1463, -6.3222]	41.3321
3	1	[-1.1421, 4.4483, 0.3920, -4.4771, -1.1421]	[-4.6863, 4.2290, 4.0960, 1.2924, -4.6863]	34.9572
	2	[2.9514, 7.6192, 7.2038, -0.2625, -2.1547, -2.3113, 2.9514]	[3.2062, 6.1807, 7.9240, 5.5350, 4.9094, 4.3248, 3.2062]	22.0538
	3	[-19.7603, -15.4876, -14.3239, -16.8713, -21.3569, -19.7603]	[-17.7399, -16.4285, -14.1274, -7.2470, -8.6344, -17.7399]	48.9855
	4	[12.4822, 12.7795, 18.1074, 21.0550, 17.6340, 12.4822]	[-2.5500, -3.1202, -2.4008, 2.9780, 1.2265, -2.5500]	18.4821
	5	[-13.0089, -13.6610, -8.4055, -1.3161, -8.4509, -13.0089]	[9.0118, 5.7659, 4.3524, 7.8440, 9.4366, 9.0118]	38.6878