```
                    ( Subscribe LIDAR )
                             |
                             v
                    [  MTT processed  ]
                             |
                             v
                          /     \
                        /  Search  \
              Not Found/  for the    \ Found
         +-----------/   same id in   \------------+
         |           \   Candidates    /           |
         |            \    Vector     /            |
         v              \           /              v
```

Create New Candidate:

- id
- distance to LIDAR straight line
- candidate right world coordenate
- candidate left world coordenate
- candidate right image point
- candidate left image point
- image
- classification

Refresh Known Candidate:

- distance to LIDAR straight line
- candidate right world coordenate
- candidate left world coordenate

velocity ≠ 0
and Classification
Non-Pedestrian

width
> 1m

Yes

Yes

Classification: Unknown

Mark for
deletion