WE CLAIM:

1. A system for determining a trajectory for a vehicle, comprising:

at least one storage medium including a set of instructions; and

at least one processor configured to communicate with the at least one storage medium, wherein when executing the set of instructions, the at least one processor is directed to:

obtain status information of a vehicle;

determine one or more original trajectories from a current location of the vehicle to a destination based on the status information of the vehicle;

determine one or more candidate trajectories from the one or more original trajectories;

extract feature vectors from the one or more candidate trajectories, each feature vector corresponding to a candidate trajectory and including a speed of the vehicle and a similarity for the candidate trajectory between a current moment T+1 and a previous moment T; and

determine a target trajectory from the one or more candidate trajectories based on a trajectory evaluation model and the feature vectors for the one or more candidate trajectories.

2. The system of claim 1, wherein the status information of the vehicle includes at least one of:

a driving direction of the vehicle,

the speed of the vehicle,

an accelerated speed of the vehicle,

a wheel base of the vehicle, or

a front wheel steering angle of the vehicle.

3. The system of claim 1, wherein to determine the one or more original

trajectories, the at least one processor is further directed to:

determine one or more sub-target locations related to the destination; and

determine the one or more original trajectories based, at least in part, on the one or more sub-target locations.

4. The system of claim 1, wherein to determine the one or more candidate trajectories from the one or more original trajectories, the at least one processor is further directed to:

determine one or more obstacles in a grid map;

perform a collision detection between the one or more original trajectories and the one or more obstacles; and

determine the one or more candidate trajectories from the one or more original trajectories based on the collision detection.

5. The system of claim 1, wherein to determine the target trajectory from the candidate trajectories based on the trajectory evaluation model, the at least one processor is further directed to:

extract one or more features with respect to the one or more candidate trajectories;

evaluate the one or more candidate trajectories based on the one or more features and the trajectory evaluation model; and

determine the target trajectory based on the trajectory evaluation model.

6. The system of claim 1, wherein the at least one processor is further directed to:

obtain a plurality of sample trajectories;

determine training data based on the plurality of sample trajectories; and

determine the trajectory evaluation model based on the training data.

7. The system of claim 6, wherein to determine the training data based on the plurality of sample trajectories, the at least one processor is further directed to:

extract one or more sample features with respect to the plurality of sample trajectories and a sample evaluation result associated with each of the plurality of sample trajectories; and

determine the one or more sample features and the corresponding sample evaluation results as the training data.

8. The system of claim 7, wherein the one or more sample features include at least one of:

a sample starting location,

a sample destination,

a sample speed of a vehicle,

a sample accelerated speed of a vehicle, or

a sample curvature.

9. The system of claim 1, wherein the at least one processor is further directed to:

determine a speed planning strategy based on the target trajectory.

10. A method implemented on a computer device having a processor, a storage medium, and a communication platform connected to a network, the method comprising:

obtaining, by the processor, status information of a vehicle;

determining, by the processor, one or more original trajectories from a current location of the vehicle to a destination based on the status information of the vehicle;

determining, by the processor, one or more candidate trajectories from the one or more original trajectories based on result of a collision detection test;

extracting, by the processor, feature vectors from the one or more candidate trajectories, each feature vector corresponding to a candidate trajectory and including a speed of the vehicle and a similarity for the candidate trajectory between a current moment T+1 and a previous moment T; and

determining, by the processor, a target trajectory from the one or more candidate trajectories based on a trajectory evaluation model and the feature vectors for the one or more available trajectories.

11. The method of claim 10, wherein the status information of the vehicle includes at least one of:

a driving direction of the vehicle,

the speed of the vehicle,

an accelerated speed of the vehicle,

a wheel base of the vehicle, or

a front wheel steering angle of the vehicle.

12. The method of claim 10, wherein the determining the one or more original trajectories comprises:

determining one or more sub-target locations related to the destination; and

determining the one or more original trajectories based, at least in part, on the one or more sub-target locations.

13. The method of claim 10, wherein the determining the one or more candidate trajectories comprises:

determining one or more obstacles in a grid map;

performing a collision detection between the one or more original trajectories and the one or more obstacles; and

determining the one or more candidate trajectories from the one or more original trajectories based on the collision detection.

14. The method of claim 10, wherein the determining the target trajectory from the one or more candidate trajectories comprises:

extracting one or more features with respect to the one or more candidate trajectories;

evaluating the one or more candidate trajectories based on the one or more features and the trajectory evaluation model; and

determining the target trajectory based on the trajectory evaluation model.

15. The method of claim 10, further comprising:

obtaining a plurality of sample trajectories;

determining training data based on the plurality of sample trajectories; and

determining the trajectory evaluation model based on the training data.

16. The method of claim 15, wherein the determining training data based on the plurality of sample trajectories comprises:

extracting one or more sample features with respect to the plurality of sample trajectories and a sample evaluation result associated with each of the plurality of sample trajectories; and

determining the one or more sample features and the corresponding sample evaluation results as the training data.

17. The method of claim 10, wherein the one or more sample features include at least one of:

a sample starting location,

a sample destination,

a sample speed of a vehicle,

a sample accelerated speed of a vehicle, or

a sample curvature of a sample trajectory.

18. The method of claim 10, further comprising:

determining a speed planning strategy based on the target trajectory.

19. A system, comprising:

a status information obtaining module, configured to obtain status information of a vehicle;

a trajectory generation module, configured to determine one or more original trajectories from a current location of the vehicle to a destination based on the status information of the vehicle;

a candidate trajectory determination module, configured to determine one or more candidate trajectories from the one or more original trajectories;

a feature extraction unit, configured to extract feature vectors form the one or more candidate trajectories, each feature vector corresponding to a candidate trajectory and including a speed of the vehicle and a similarity for the candidate trajectory between a current moment T+1 and a previous moment T; and

a target trajectory determination module, configured to determine a target trajectory from the one or more candidate trajectories based on a trajectory evaluation model and the feature vectors for the one or more candidate trajectories.

20. A non-transitory computer readable medium, comprising at least one set of instructions for determining a trajectory for a vehicle, wherein when executed by at least one processor of an electronic terminal, the at least one

set of instructions directs the at least one processor to perform acts of:

obtaining status information of a vehicle;

determining one or more original trajectories from a current location of the vehicle to a destination based on the status information of the vehicle;

determining one or more candidate trajectories from the one or more original trajectories;

extracting feature vectors form the one or more candidate trajectories, each feature vector corresponding to a candidate trajectory and including a speed of the vehicle and a similarity for the candidate trajectory between a current moment T+1 and a previous moment T; and

determining a target trajectory from the one or more candidate trajectories based on a trajectory evaluation model and the feature vectors for the one or more candidate trajectories.