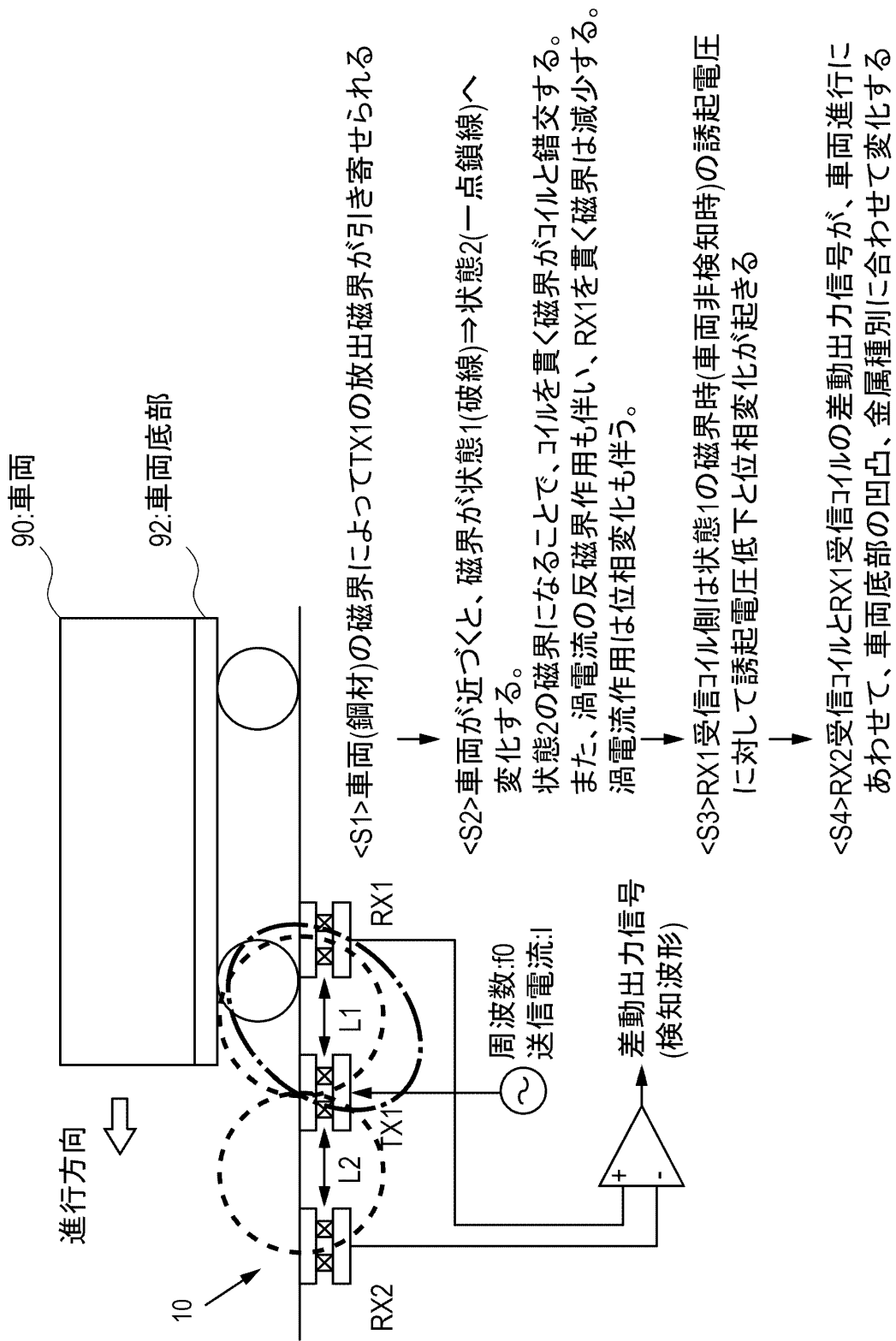


[図1]



[図2]

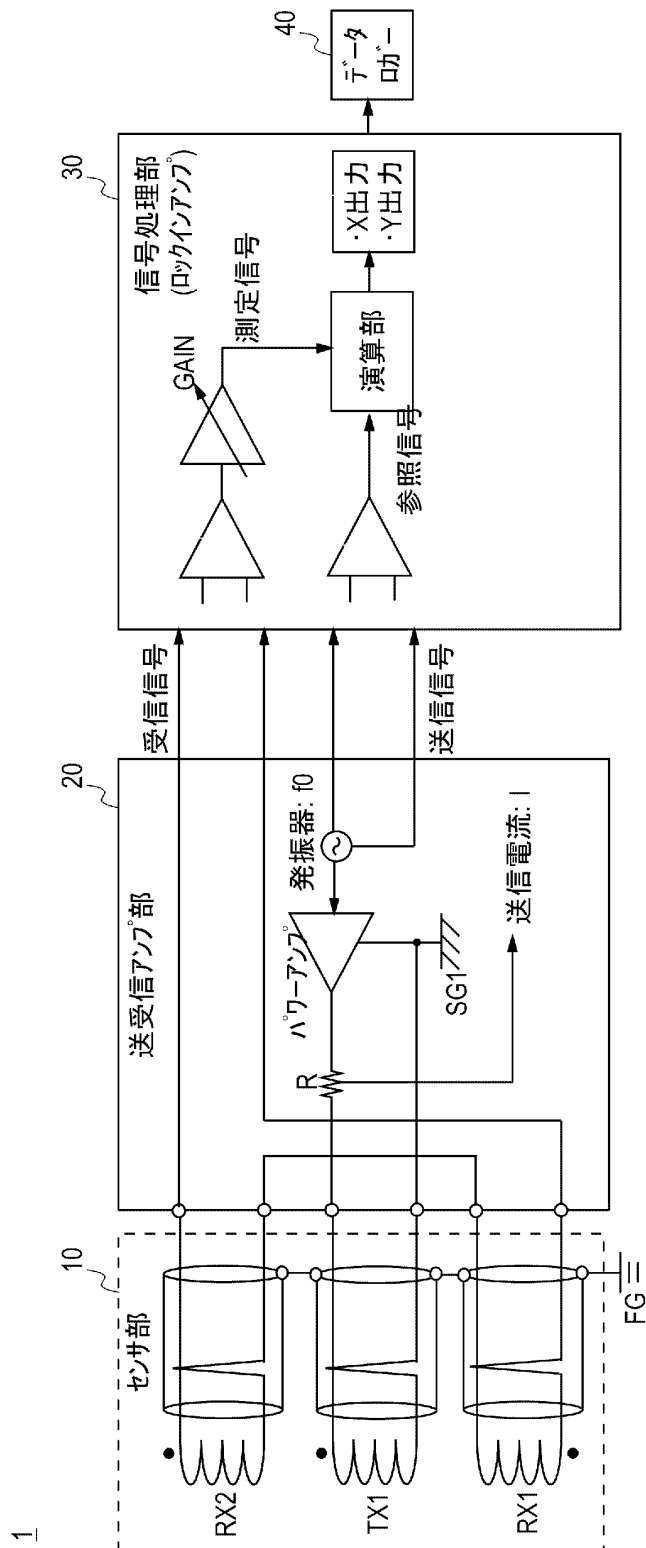
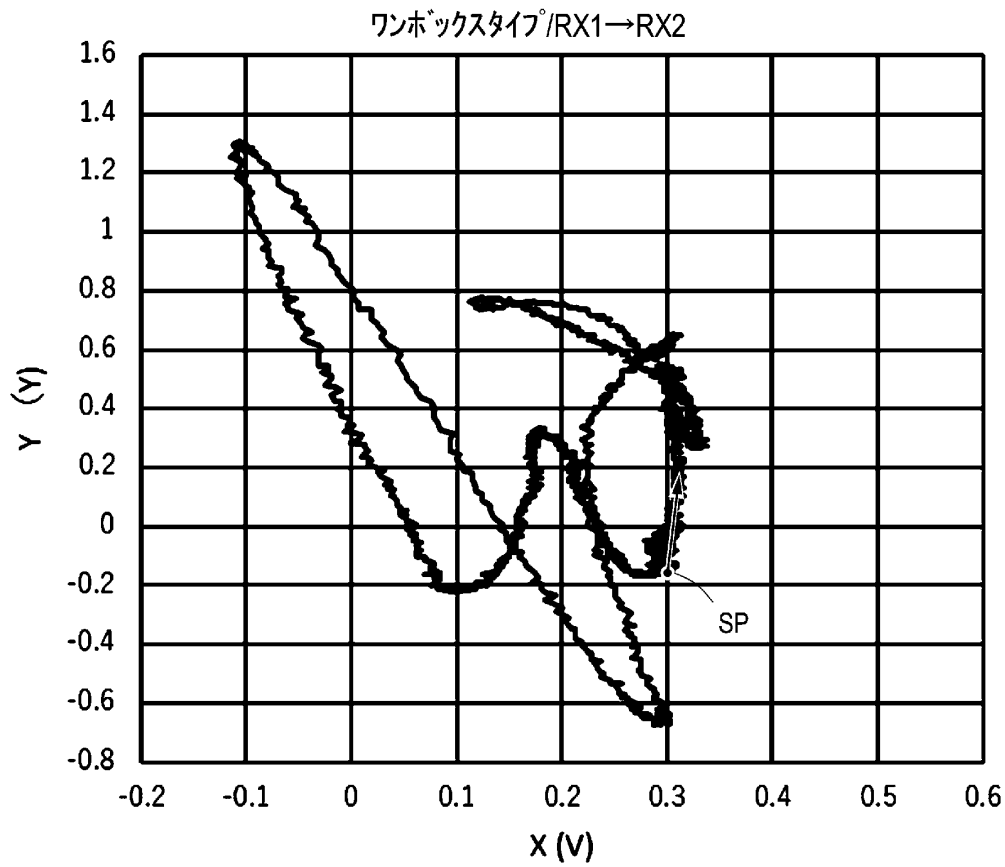


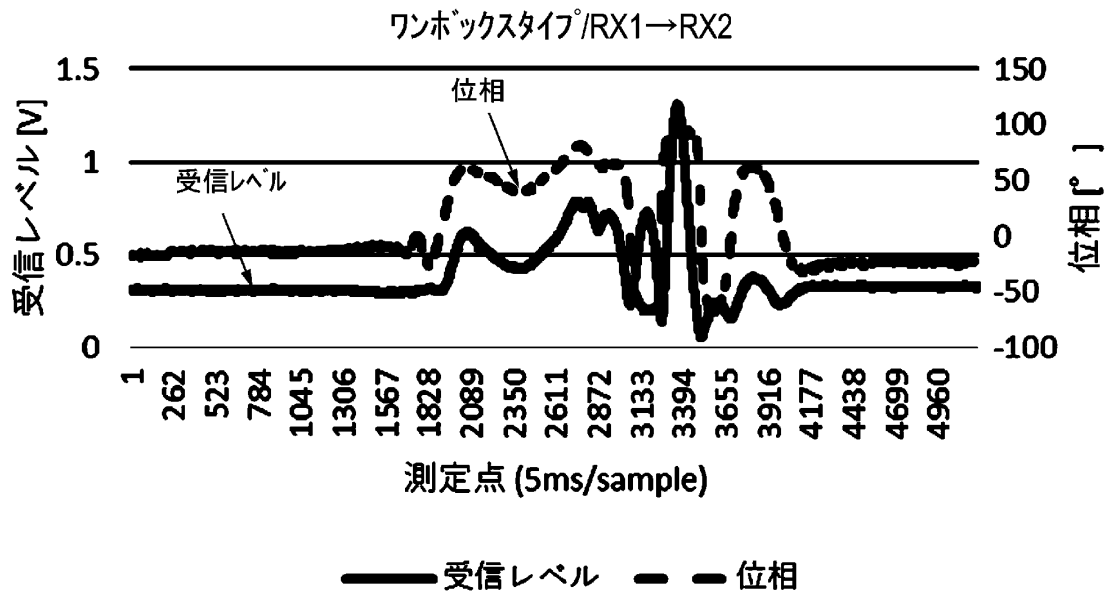
Figure 1 illustrates the configuration and operation of a vehicle-to-vehicle communication system. The top part shows four states of a vehicle (90) relative to a road and the locations of sensors (RX1, RX2) and a transmitter (TX1). The states are: <状態1:車両非検知状態A>, <状態2:車両検知状態A>, <状態3:車両検知状態B>, and <状態4:車両非検知状態B>.

The bottom part shows the signal processing flow. It starts with a transmitted signal (TX1) and a received signal (RX1/RX2). These are converted into X-Y coordinates. The received signal is then processed to determine the vehicle's position (R0, R1, R2) and the angle of arrival (theta 1, theta 2, theta 3). The final output is a trajectory plot showing the vehicle's path (A1, A2, A3) and the predicted trajectory (X, Y) based on the received signal.

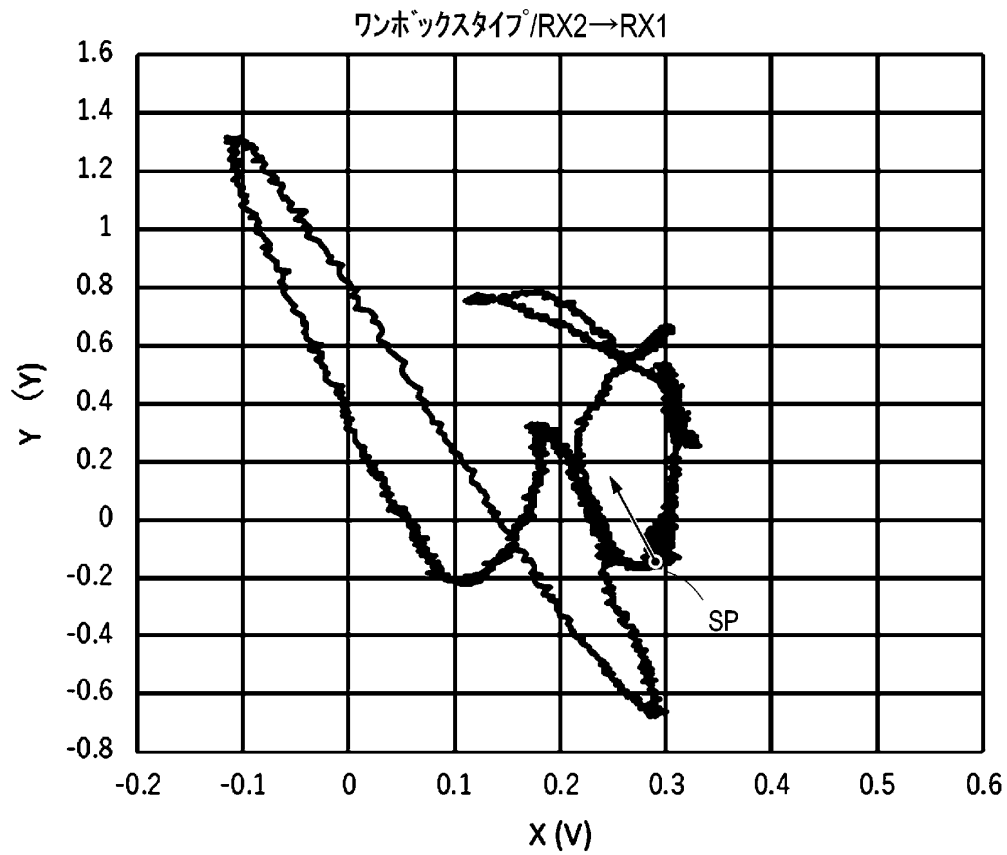
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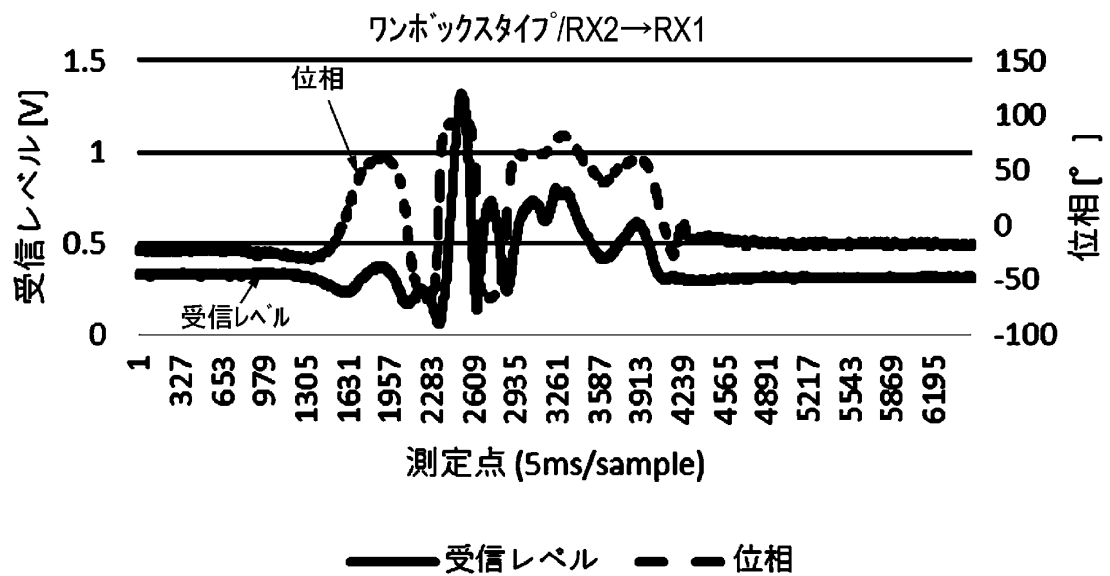
[図5]



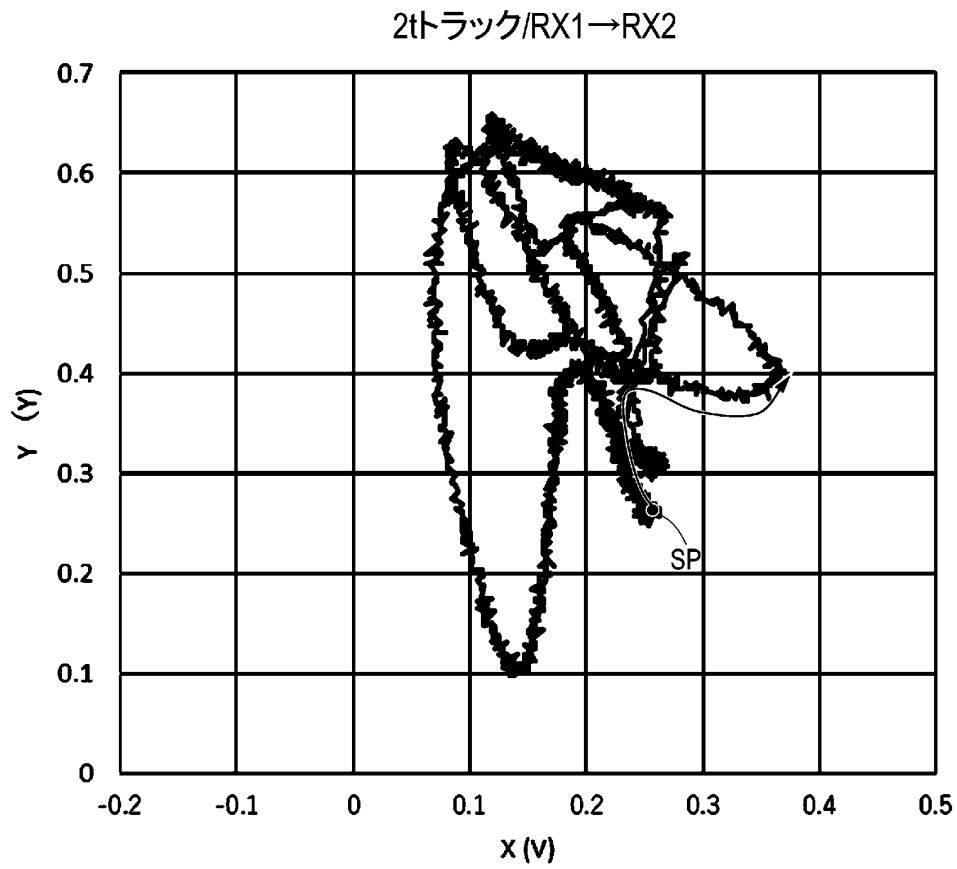
[図6]



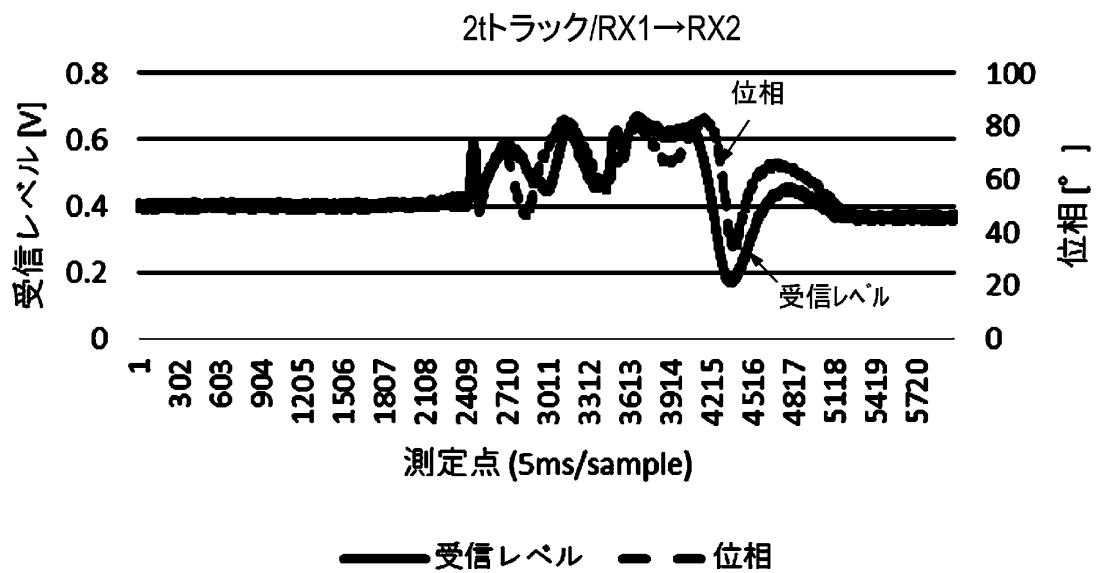
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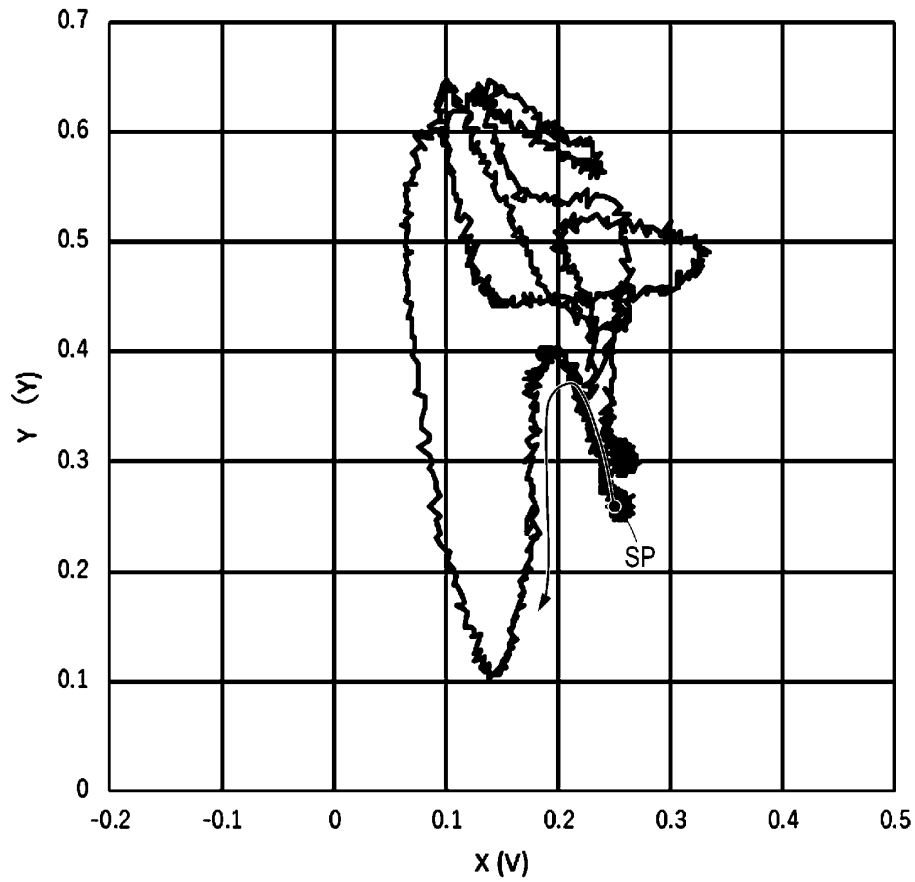
[図8]



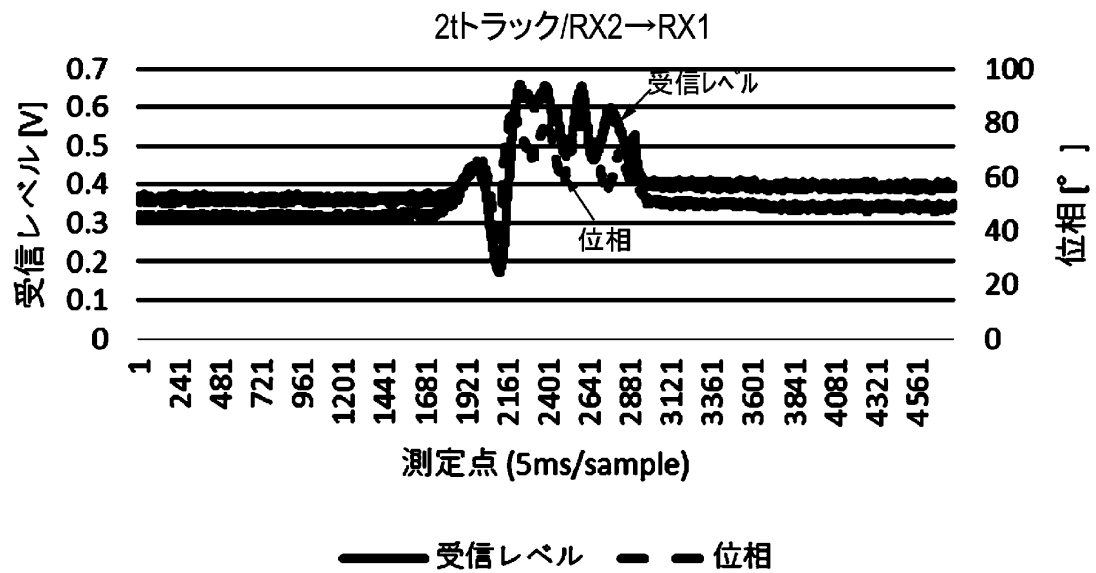
[図9]



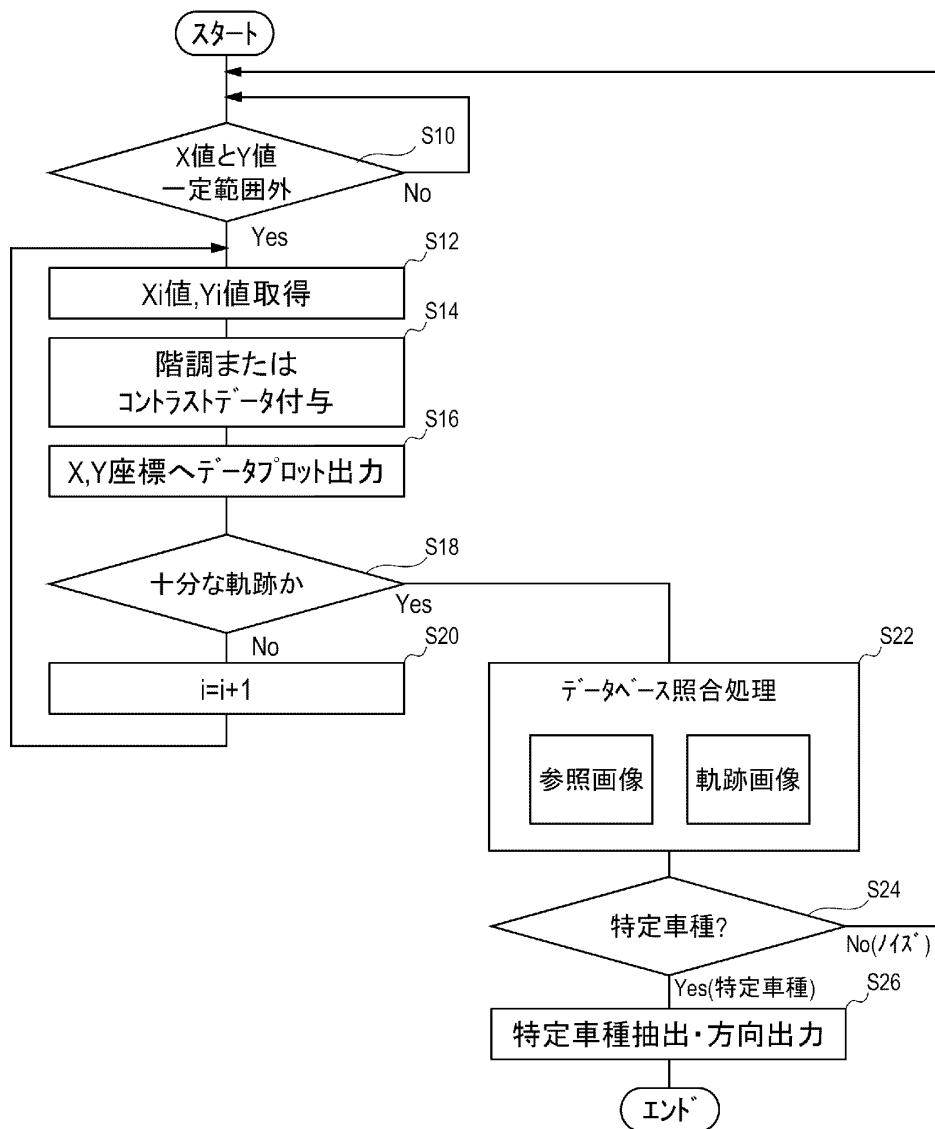
[図10]



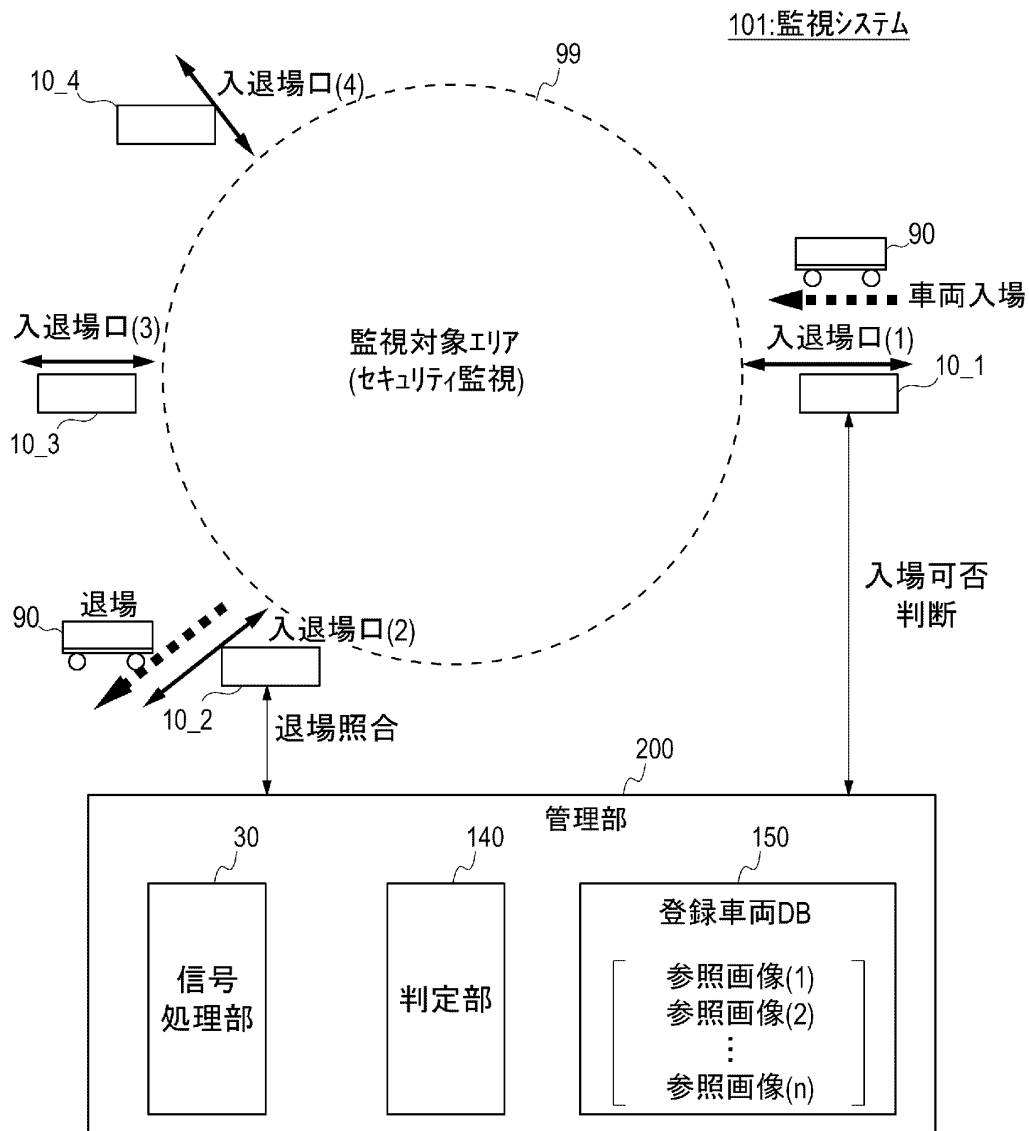
[図11]



[図12]



[図13]



[図14]

