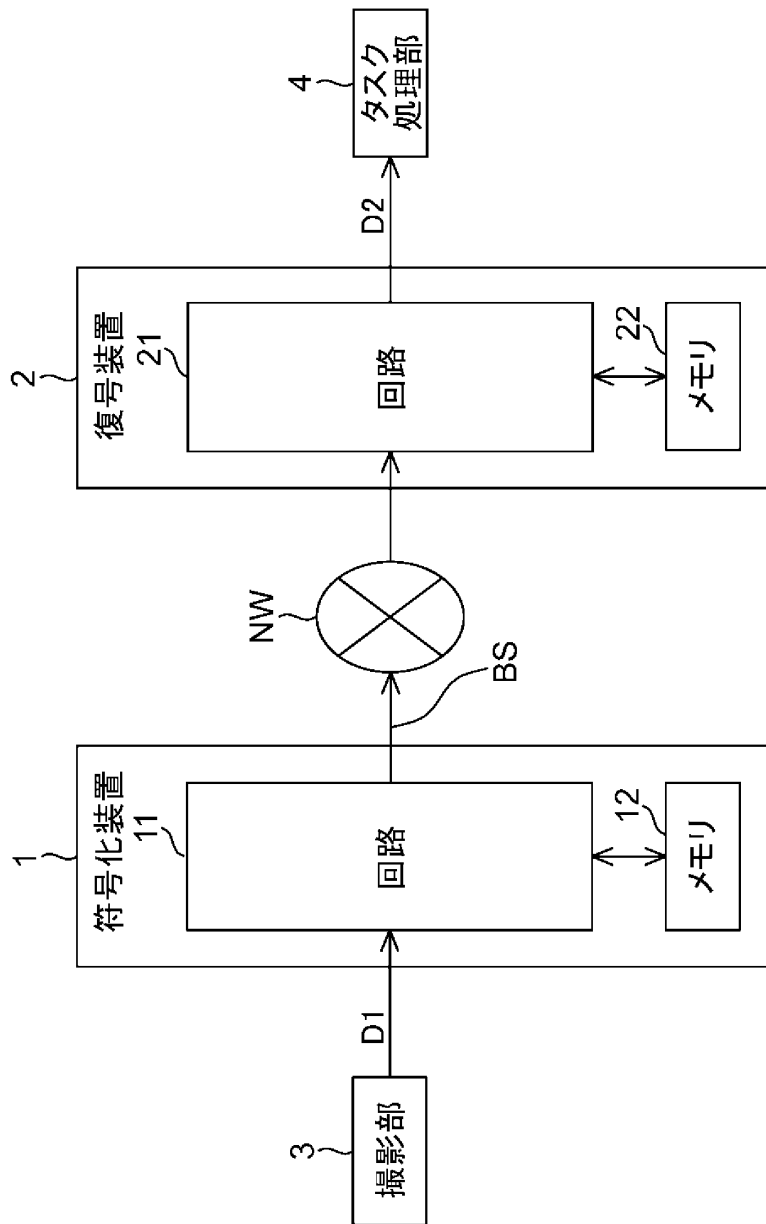
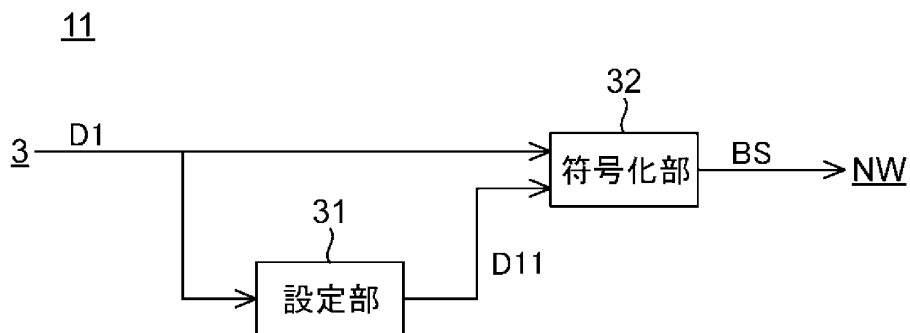


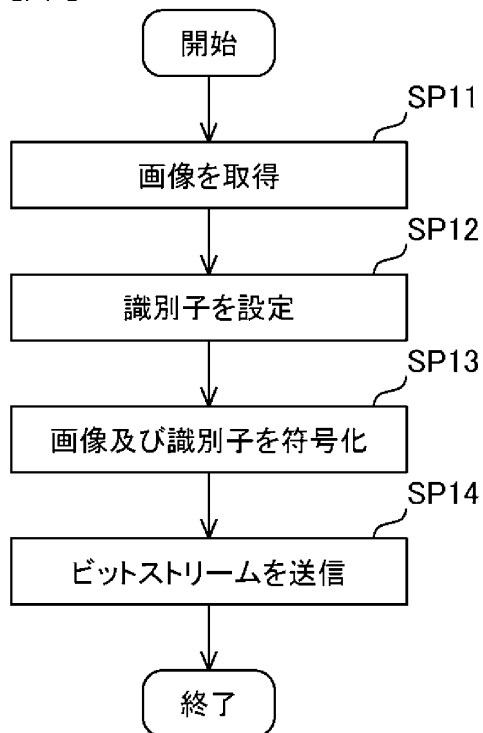
[図1]



[図2]



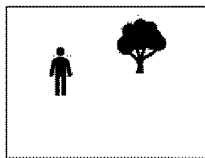
[図3]



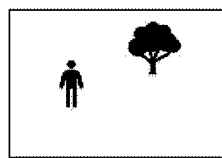
[図4]

タスク処理: ヒューマンビジョン

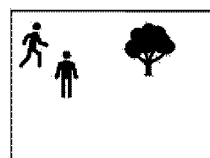
(適切)

T₀

(適切)

T₁

(適切)

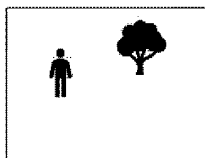
T₂

→ 時間

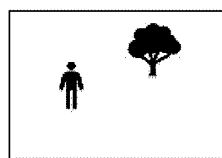
[図5]

タスク処理: オブジェクト検出

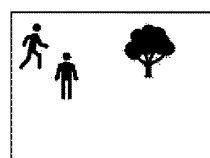
(適切)

T₀

(不適切)

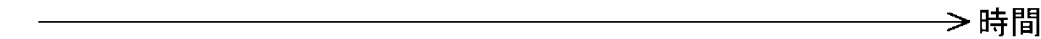
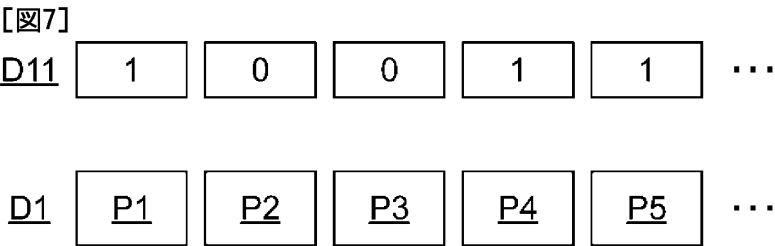
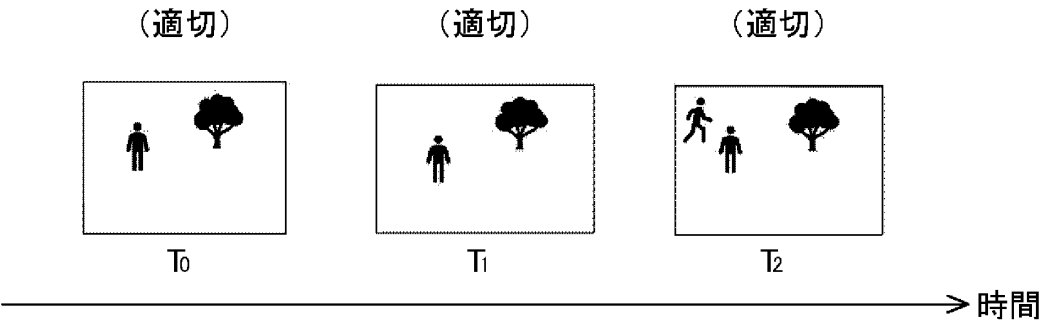
T₁

(適切)

T₂

→ 時間

[図6]
タスク処理:オブジェクト追跡



[図8]

sub_function(payloadSize){	識別子
...	
frame_for_inference	u(1)
...	
}	

[図9]

frame_for_inference

(A)

1	適切
0	不適切

frame_for_inference

(B)

1	適切
0	指定なし

[図10]

sub_function(payloadSize){	識別子
...	
frame_not_for_inference	u(1)
...	
}	

[図11]

frame_not_for_inference

(A)

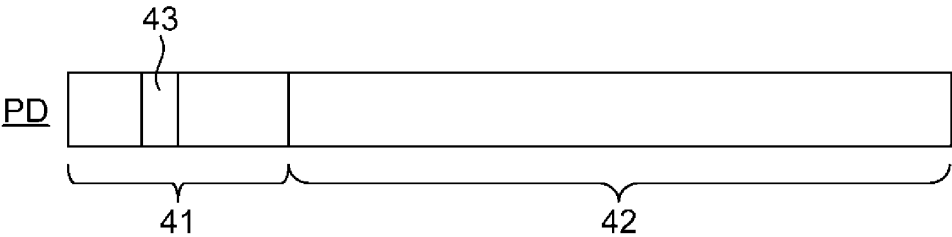
1	不適切
0	適切

frame_not_for_inference

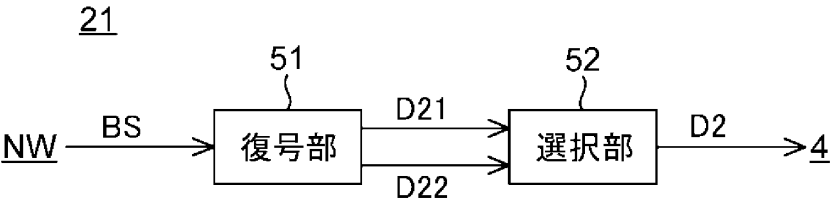
(B)

1	不適切
0	指定なし

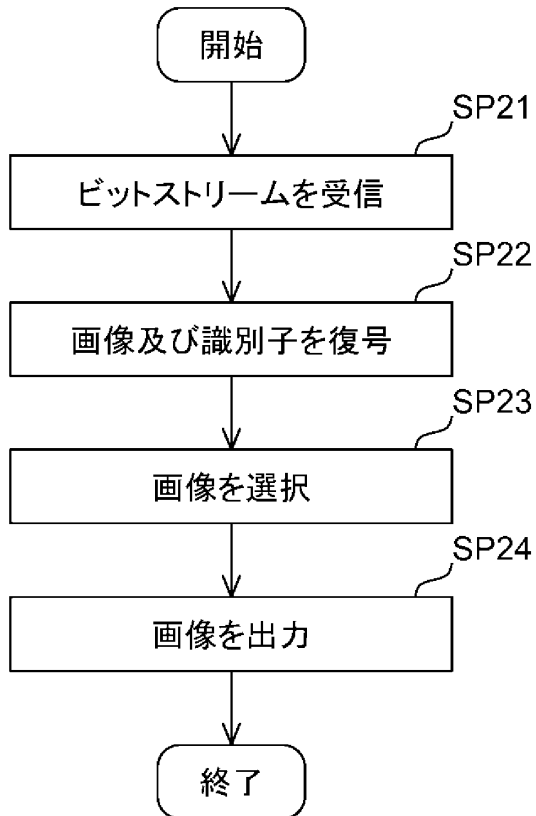
[図12]



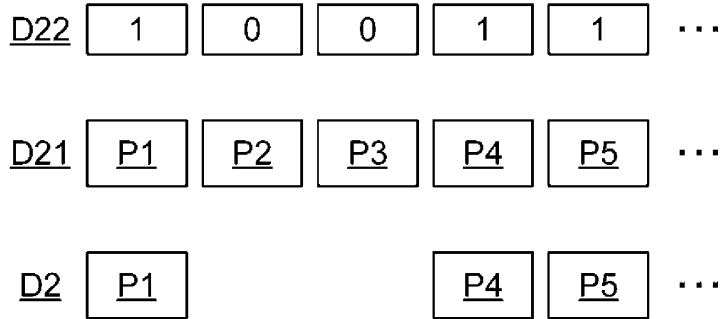
[図13]



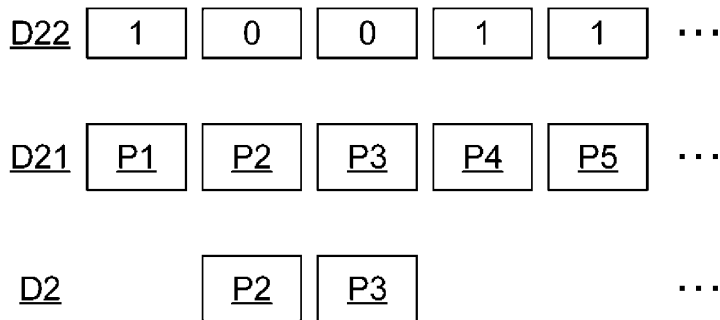
[図14]



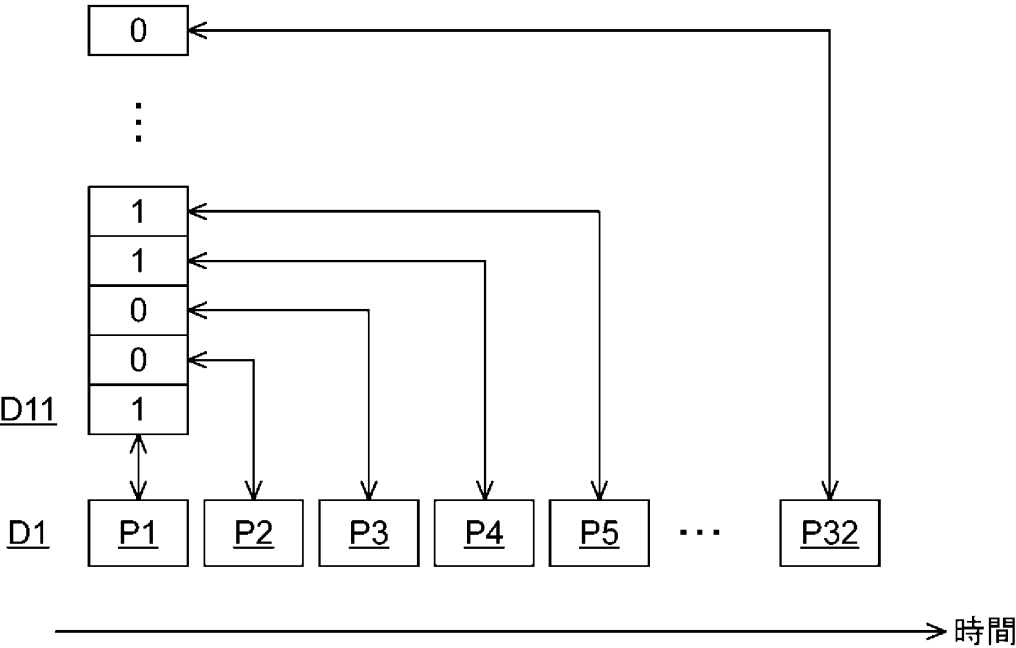
[図15]



[図16]



[図17]



[図18]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
frame_for_inference[i]	u(1)
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図19]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
image_identifier[i]	ue(v)
frame_for_inference[i]	u(1)
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図20]

frame_for_inference

(A)	1	適切
	0	不適切
	×	指定なし

frame_for_inference

(B)	1	適切
	0	指定なし
	×	指定なし

[図21]

frame_not_for_inference

(A)	1	不適切
	0	適切
	×	指定なし

frame_not_for_inference

(B)	1	不適切
	0	指定なし
	×	指定なし

[図22]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
frame_for_inference_present_flag[i]	u(1)
if(frame_for_inference_present_flag[i]){	
frame_for_inference[i]	u(1)
}	
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

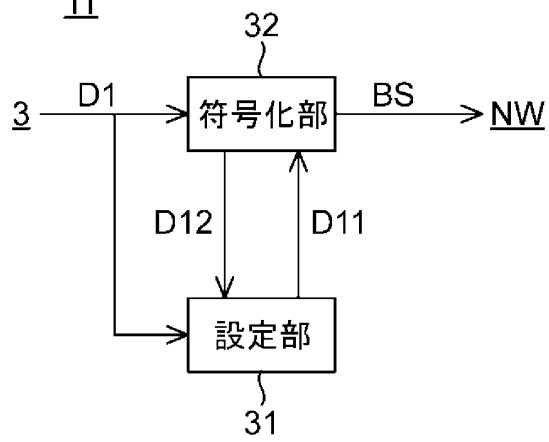
[図23]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
frame_for_inference_present_flag[i]	u(1)
if(frame_for_inference_present_flag[i]){	
image_identifier[i]	ue(v)
frame_for_inference[i]	u(1)
}	
}	
while(!byte_aligned())	
reserved zero bit/*equal to 0*/	u(1)
...	
}	

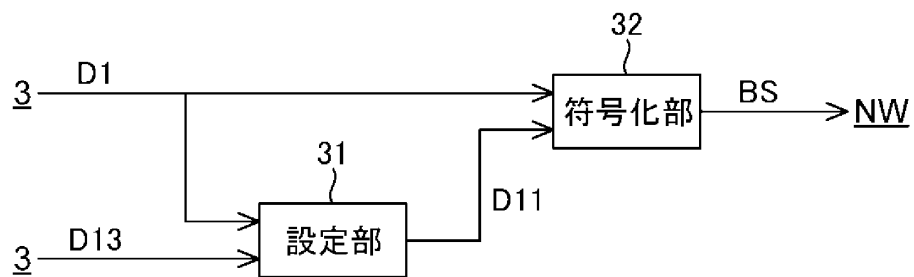
[図24]

sub_function(payloadSize){	識別子
...	
vision_task	st(v)
...	
}	

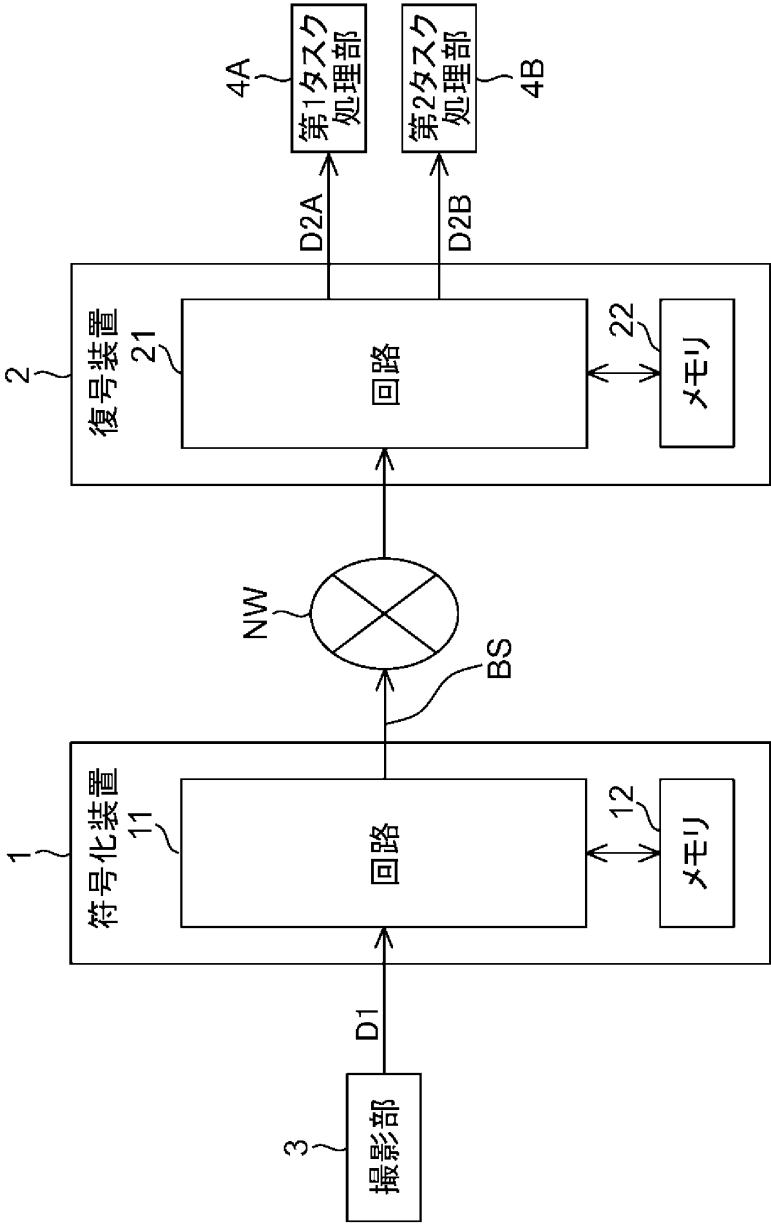
[図25]

11

[図26]

11

[図27]

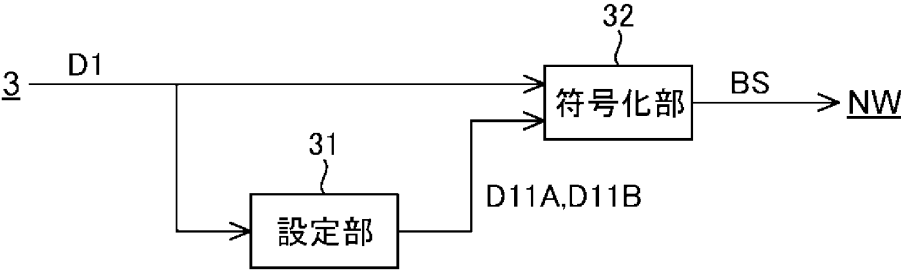


[図28]

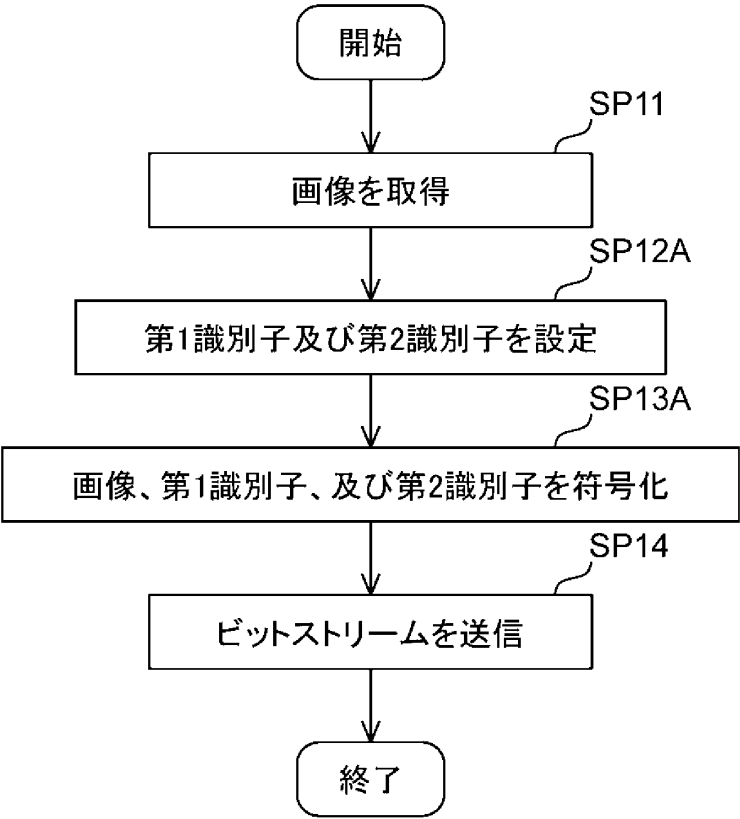
60

第1タスク処理	オブジェクト検出
第2タスク処理	ヒューマンビジョン

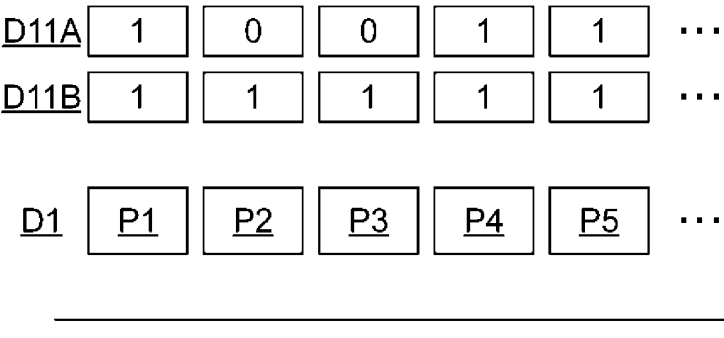
[図29]
11

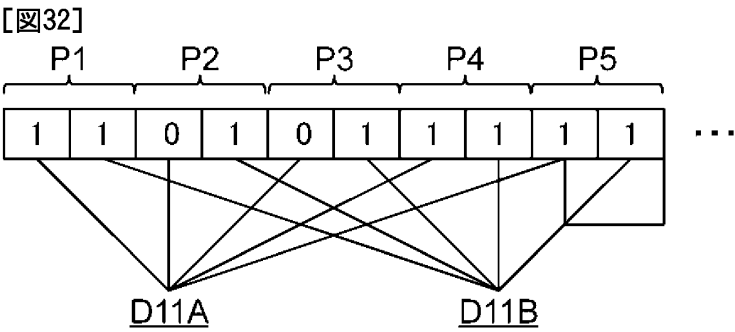


[図30]



[図31]





[図33A]

sub_function(payloadSize){	識別子
...	
num_vision_task_minus1	u(3)
for(i=0;i<num_vision_task_minus1+1;i++){	
frame_for_inference[i]	u(1)
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図33B]

sub_function(payloadSize){	識別子
...	
frame_for_inference[0]	u(1)
frame_for_inference[1]	u(1)
frame_for_inference[2]	u(1)
...	
}	

[図34A]

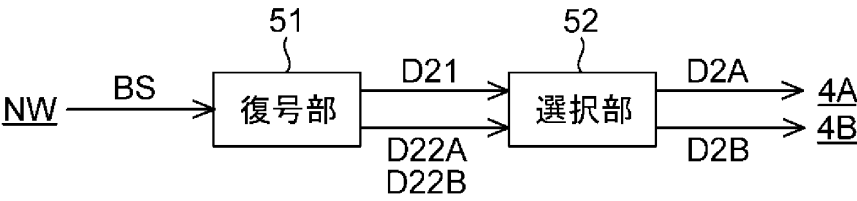
sub_function(payloadSize){	識別子
...	
num_vision_task_minus1	u(3)
for(i=0;i<num_vision_task_minus1+1;i++){	
frame_not_for_inference[i]	u(1)
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図34B]

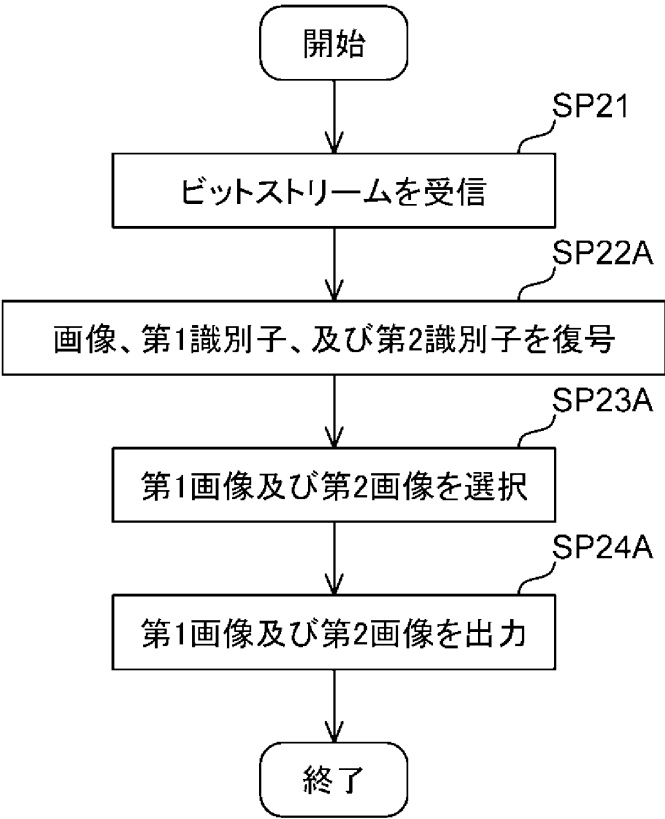
sub_function(payloadSize){	識別子
...	
frame_not_for_inference[0]	u(1)
frame_not_for_inference[1]	u(1)
frame_not_for_inference[2]	u(1)
...	
}	

[図35]

21



[図36]



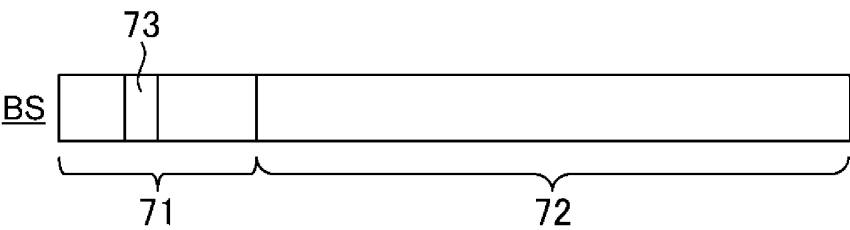
時間

時間

[図40]

sub_function(payloadSize){	識別子
...	
num_identifier_minus1	u(3)
for(i=0;i<num_identifier_minus1+1;i++){	
vision_task[i]	st(v)
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図41]



[図42]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
num_vision_task_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
for(j=0;j<num_vision_task_minus1+1;j++){	
frame_for_inference[i][j]	u(1)
}	
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図43]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
num_vision_task_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
image_identifier[i]	ue(v)
for(j=0;j<num_vision_task_minus1+1;j++){	
frame_for_inference[i][j]	u(1)
}	
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図44]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
frame_for_inference_present_flag[i]	u(1)
if(frame_for_inference_present_flag[i]){	
num_vision_task_minus1	ue(v)
for(j=0;j<num_vision_task_minus1+1;j++){	
frame_for_inference[i][j]	u(1)
}	
}	
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	

[図45]

sub_function(payloadSize){	識別子
...	
num_frames_minus1	ue(v)
for(i=0;i<num_frames_minus1+1;i++){	
frame_for_inference_present_flag[i]	u(1)
if(frame_for_inference_present_flag[i]){	
image_identifier[i]	ue(v)
num_vision_task_minus1	ue(v)
for(j=0;j<num_vision_task_minus1+1;j++){	
frame_for_inference[i][j]	u(1)
}	
}	
}	
while(!byte_aligned())	
reserved_zero_bit/*equal to 0*/	u(1)
...	
}	