What is claimed is:

1. An imaging positioning method, comprising:

performing a first inspection on an object by a first inspection system to generate a first inspection information;

determining at least one suspect position of the object according to the first inspection information;

conveying the object to a second inspection system by a conveying system, wherein the second inspection system is configured to generate a first imaging beam plane and a second imaging beam plane for inspecting the object, and a predetermined distance is provided between the first imaging beam plane and the second imaging beam plane;

locating the object on the first imaging beam plane, and performing a second inspection on the object by the second inspection system to generate a second inspection information;

determining at least one target position of the object according to the first inspection information and the second inspection information, wherein the target position is associated with the suspect position; and

controlling the conveying system to move the object from the first imaging beam plane to the second imaging beam plane according to the predetermined distance and a current coordinate information of the at least one target position, so that the at least one target position of the object is located on the second imaging beam plane, so as to perform a third inspection on the object by the second inspection system using the second imaging beam plane, wherein the current coordinate information is a coordinate information of the at least one target position after the second inspection is completed and before the conveying system moves the object from the first imaging beam plane to the second imaging beam plane.

2. The method according to claim 1, wherein the determining at least one suspect position of the object according to the first inspection information comprises:

generating a first image information of the object according to the first inspection information; and

determining the at least one suspect position of the object according to the first image information.

3. The method according to claim 2, further comprising: before determining the at least one target position of the object according to the first inspection information and the second inspection information,

generating a second image information of the object according to the second inspection information.

4. The method according to claim 3, wherein the determining at least one target position of the object according to the first inspection information and the second inspection information comprises:

determining a correlation between the first image information generated from the first inspection information and the second image information generated from the second inspection information according to the first image information and the second image information; and

determining the at least one target position of the object according to the at least one suspect position and the correlation.

5. The method according to any one of claims 1 to 4, further comprising:

determining the current coordinate information of the at least one target position according to a current position of the at least one target position relative to the first imaging beam plane and coordinates of the first imaging beam plane after the second inspection is completed and before the conveying system moves the object from the first imaging beam plane to the second imaging beam plane.

6. The method according to claim 5, wherein the controlling the conveying system to move the object from the first imaging beam plane to the second imaging beam plane according to the predetermined distance and a current coordinate information of the at least one target position comprises:

calculating a distance from the at least one target position to the second imaging beam plane according to the predetermined distance and the current coordinate information of the at least one target position; and

moving the object in a conveying direction by the calculated distance from the first imaging beam plane by the conveying system, so as to locate the at least one target position on the second imaging beam plane.

7. The method according to claim 6, wherein the at least one target position comprises one or more target positions, and the method comprises:

controlling the conveying system to move the object from the first imaging beam plane to the second imaging beam plane according to the predetermined distance and current coordinate information of each target position in the at least one target position, so that each target position is sequentially located on the second imaging beam plane to perform the third inspection.

8. The method according to any one of claims 1 to 4 and 6 to 7, wherein the coordinate information comprises a first-direction coordinate information and a second-direction coordinate information, and the controlling the conveying system to move the object from the first imaging beam plane to the second imaging beam plane according to the predetermined distance and a current coordinate information of the at least one target position comprises:

controlling an inspection component configured to form the second imaging beam plane to move in a first direction according to the first-direction coordinate information of the at least one target position; and

controlling the conveying system to move the object in a second direction according to the predetermined distance and the second-direction coordinate information of the at least one target position, so that the at least one target position is located on the second imaging beam plane, wherein the second direction is parallel to a conveying direction of the conveying system, and the first direction is perpendicular to the second direction.

9. The method according to claim 6 or 7, further comprising: after moving the object in the conveying direction by the calculated distance from the first imaging beam plane by the conveying system,

determining whether a conveying distance deviation in the conveying direction has occurred in the conveying system.

10. The method according to claim 9, further comprising:

in response to determining that a conveying distance deviation in the conveying direction has occurred in the conveying system, continuing to move the object by the conveying system according to the conveying distance deviation so that the at least one target position is located on the second imaging beam plane.

11. The method according to claim 9, wherein the conveying system comprises a conveyor belt for conveying the object, a driving roller for driving the conveyor belt to rotate, and a driven roller arranged downstream of the driving roller in the conveying direction and in frictional engagement with the conveyor belt, the method further comprising:

determining a rotation distance that the driving roller is required to rotate in order to move the conveyor belt by the calculated distance in the conveying direction; and

driving the driving roller to rotate according to the determined rotation distance so as to drive the conveyor belt to move in the conveying direction, wherein the conveying distance deviation is a difference between an actual distance the conveyor belt moves while the driving roller rotates by the calculated rotation distance and the calculated distance.

12. The method according to claim 11, wherein the conveying system further comprises a first encoder and a second encoder, the first encoder is disposed at the driving roller or at a motor for driving the driving roller to rotate so as to generate an encoded value corresponding to a rotation position of the driving roller or the motor, the second encoder is disposed at the driven roller so as to generate an encoded value corresponding to a rotation position of the driven roller, the method comprising:

acquiring a first initial encoded value from the first encoder indicating an initial position of the driving roller and a second initial encoded value from the second encoder indicating an initial position of the driven roller when the conveying system starts moving the object from the first imaging beam plane to the second imaging beam plane after the second inspection is completed;

calculating a first stop encoded value of the first encoder when the driving roller stops rotating after the conveyor belt has moved the calculated distance in the conveying direction, wherein the determining the rotation distance comprises calculating the first stop encoded value;

driving the driving roller to rotate so as to drive the conveyor belt and the driven roller to rotate until a current encoded value of the first encoder reaches the first stop encoded value, and acquiring a second stop encoded value of the second encoder indicating a stop position of the driven roller at that point; and

determining whether a conveying distance deviation of the conveyor belt has occurred according to the first initial encoded value, the second initial encoded value, the first stop encoded value, and the second stop encoded value.

13. The method according to claim 12, wherein the determining whether a conveying distance deviation of the conveyor belt has occurred according to the first initial encoded value, the second initial encoded value, the first stop encoded value, and the second stop encoded value comprises:

determining a first value representing a rotation distance of the driving roller according to the first initial encoded value and the first stop encoded value;

determining a second value representing a rotation distance of the driven roller according to the second initial encoded value and the second stop encoded value;

determining that no conveying distance deviation of the conveyor belt has occurred if the first value is equal to the second value; and

determining that a conveying distance deviation of the conveyor belt has occurred if the first value is not equal to the second value.

14. The method according to claim 12, further comprising:

adjusting a tension of the conveyor belt if it is determined that a conveying distance deviation of the conveyor belt has occurred.

15. The method according to any one of claims 1 to 14, wherein the first inspection system comprises a CT or DR inspection device, and the second inspection system comprises a DR inspection device for generating the first imaging beam plane and an XRD inspection device for generating the second imaging beam plane.

16. An imaging inspection system, comprising a first inspection system, a second inspection system, a conveying system, and a processor, wherein:

the first inspection system is configured to perform a first inspection on an object to generate a first inspection information;

the conveying system is configured to convey the object from the first inspection system to the second inspection system;

the second inspection system is configured to generate a first imaging beam plane and a second imaging beam plane for inspecting the object conveyed by the conveying system, so as to perform a second inspection on the object and generate a second inspection information when the object is located on the first imaging beam plane, and a predetermined distance is provided between the first imaging beam plane and the second imaging beam plane;

the processor is configured to:

determine at least one suspect position of the object according to the first inspection information;

determine at least one target position of the object according to the first inspection information and the second inspection information, wherein the target position is associated with the suspect position; and

control the conveying system to move the object from the first imaging beam plane to the second imaging beam plane according to the predetermined distance and a current coordinate information of the at least one target position, so that the at least one target position of the object is located on the second imaging beam plane; and

the second inspection system is further configured to perform a third inspection on the object when the at least one target position of the object is located on the second imaging beam plane, and the current coordinate information is a coordinate information of the at least one target position after the second inspection is completed and before the conveying system moves the object from the first imaging beam plane to the second imaging beam plane.

17. The imaging inspection system according to claim 16, wherein the processor is further configured to:

generate a first image information of the object according to the first inspection information; and

determine the at least one suspect position of the object according to the first image information.

18. The imaging inspection system according to claim 17, wherein the processor is further configured to generate a second image information of the object according to the second inspection information before determining the at least one target position of the object according to the first inspection information and the second inspection information.

19. The imaging inspection system according to claim 18, wherein the processor is further configured to:

determine a correlation between the first image information generated from the first inspection information and the second image information generated from the second inspection information according to the first image information and the second image

information; and

determine the at least one target position of the object according to the at least one suspect position and the correlation.

20. The imaging inspection system according to any one of claims 16 to 19, wherein the processor is further configured to:

determine the current coordinate information of the at least one target position according to a current position of the at least one target position relative to the first imaging beam plane and coordinates of the first imaging beam plane after the second inspection is completed and before the conveying system moves the object from the first imaging beam plane to the second imaging beam plane.