

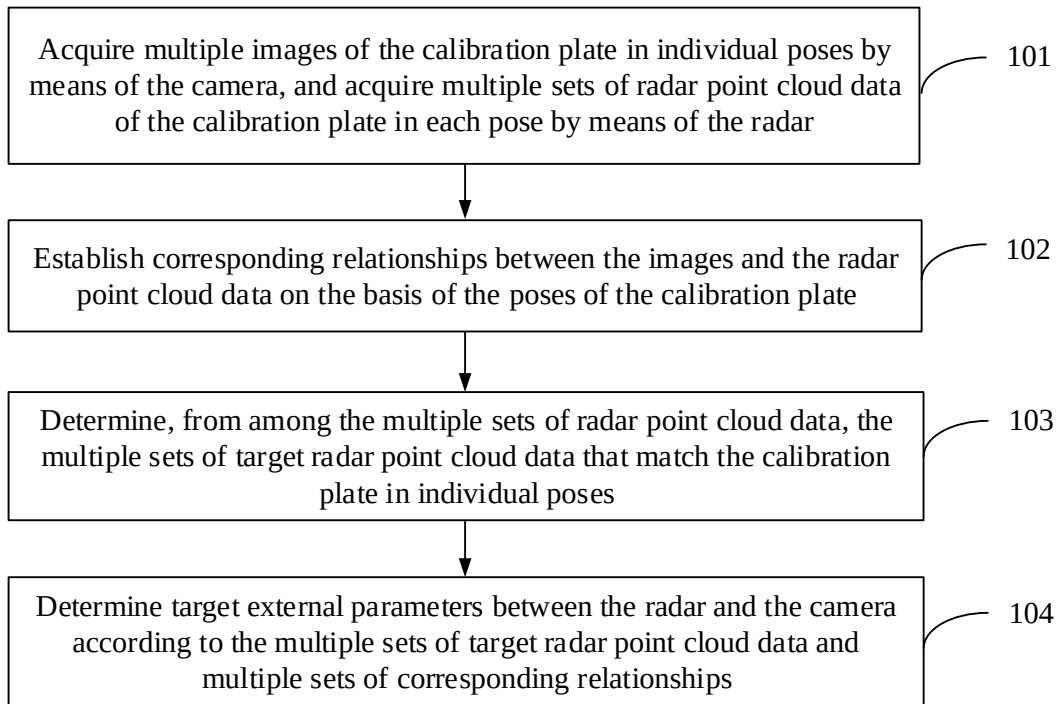


FIG. 1

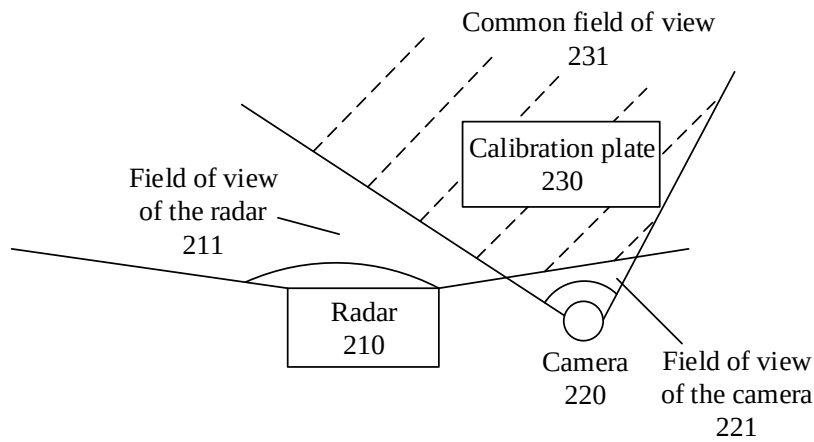


FIG. 2

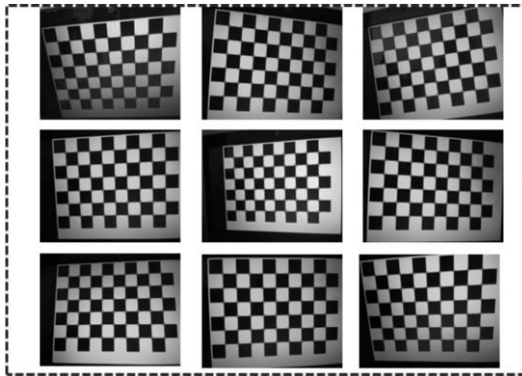


FIG. 3

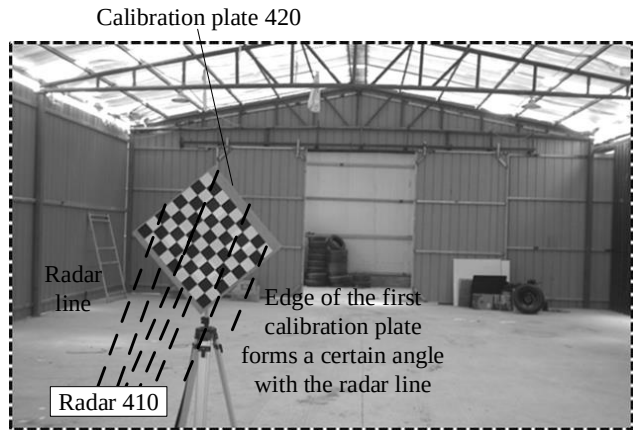


FIG. 4

Intrinsic parameter of the camera calibrated in advance is obtained, and an extrinsic parameter of the calibration plate in the respective position-orientations relative to the camera is respectively determined according to the intrinsic parameter of the camera and the plurality of images

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For the calibration plate in each of the respective position-orientations, a set of target radar point cloud data matched with the calibration plate in the position-orientation among the multiple sets of radar point cloud data is determined according to the extrinsic parameter of the calibration plate relative to the camera and an extrinsic parameter reference value between the radar and the camera

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FIG. 5

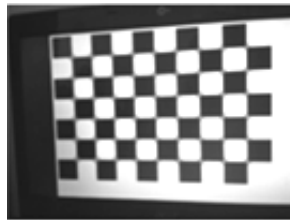


FIG. 6

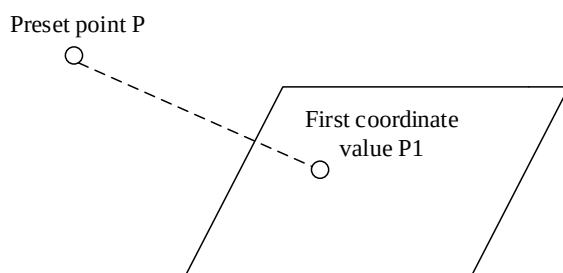


FIG. 7A

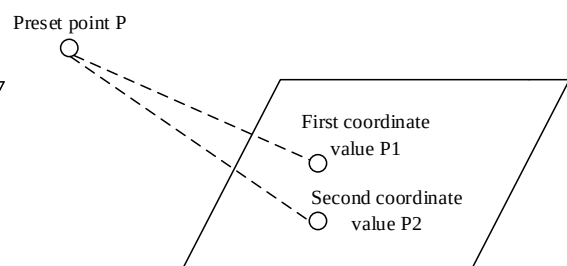


FIG. 7B

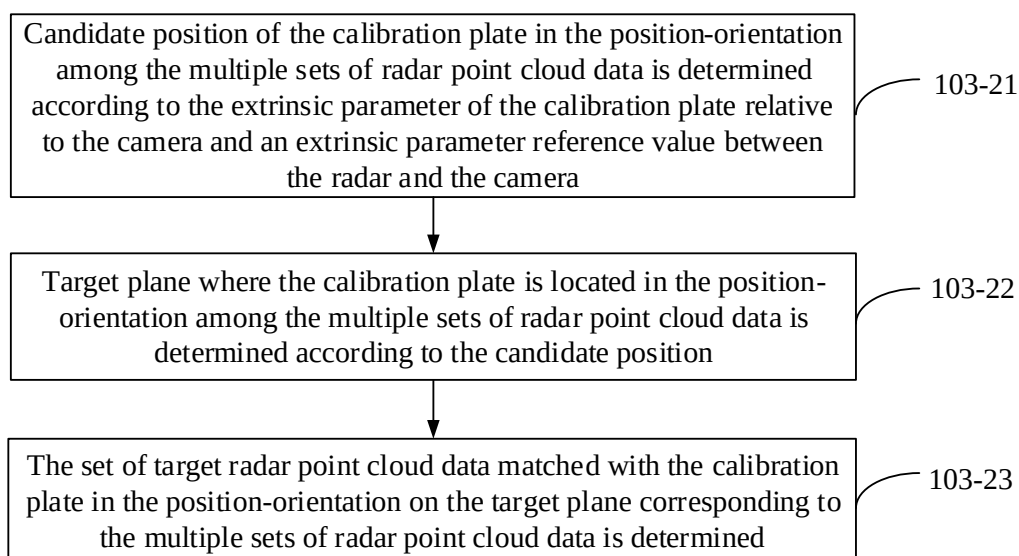


FIG. 8

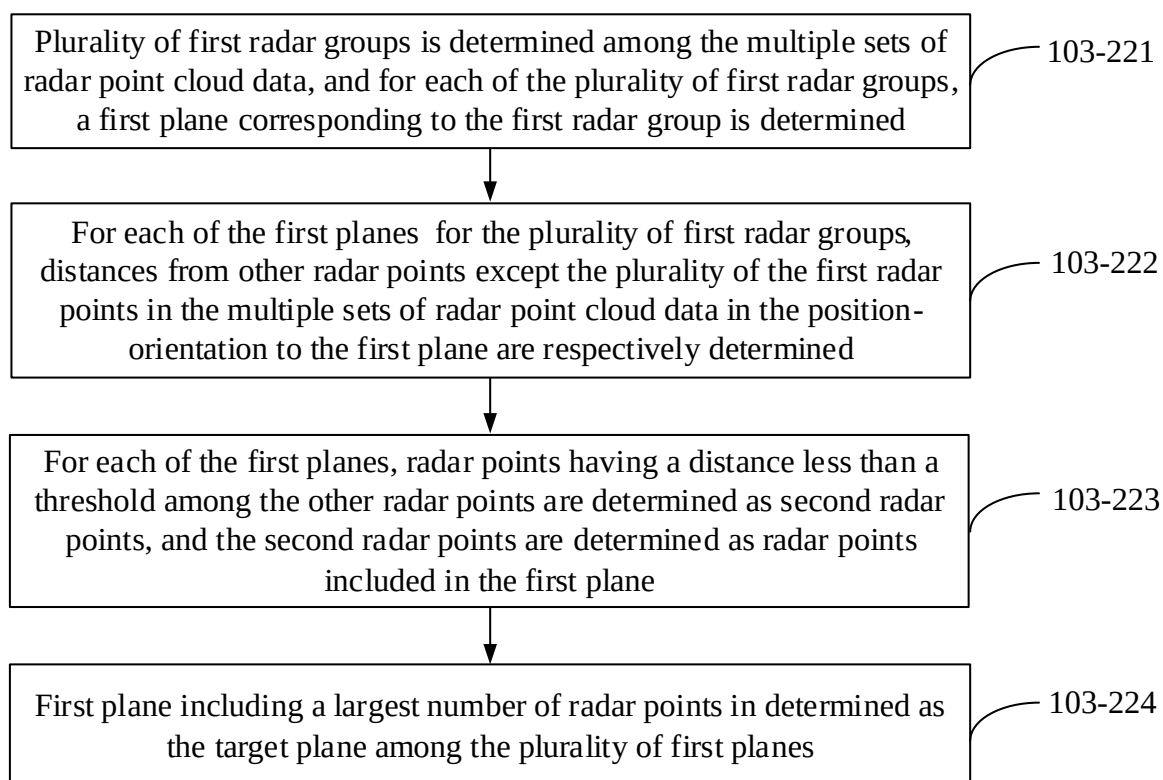


FIG. 9

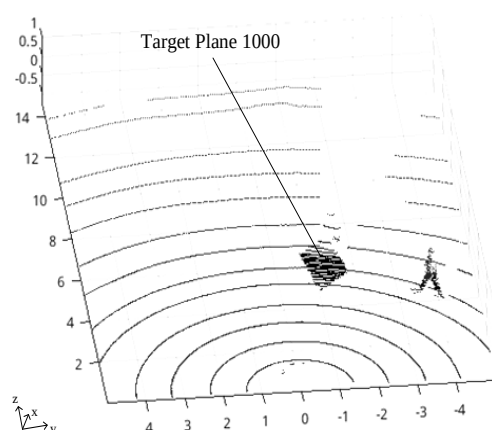


FIG. 10

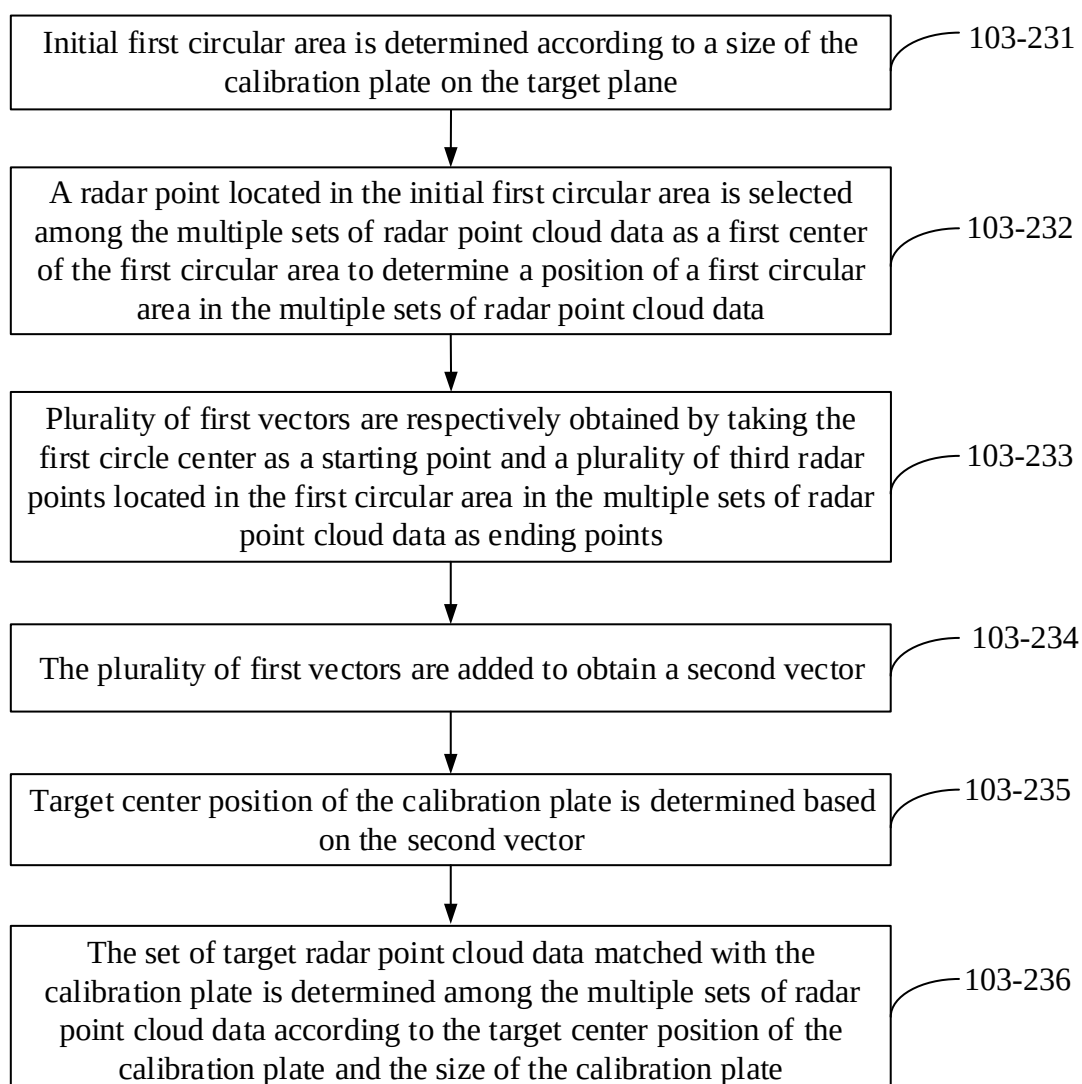


FIG. 11

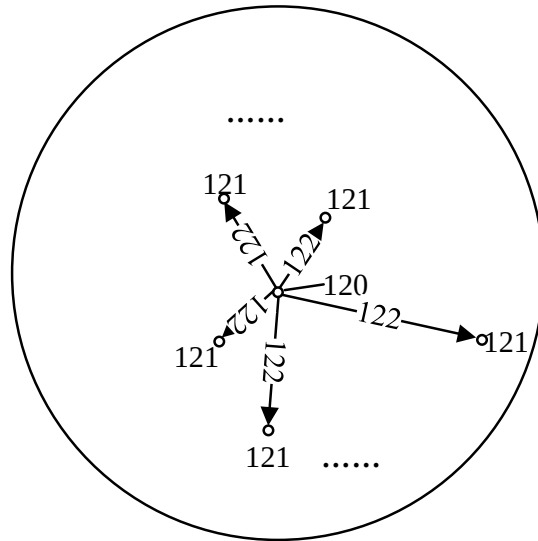


FIG. 12

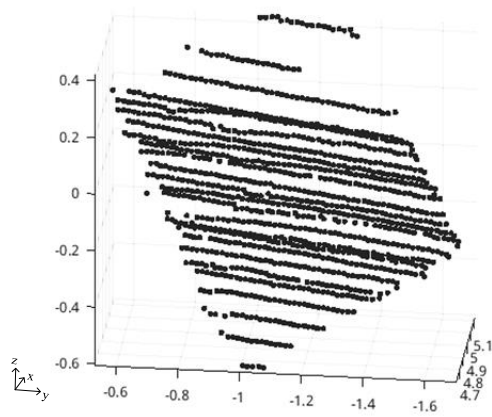


FIG. 13

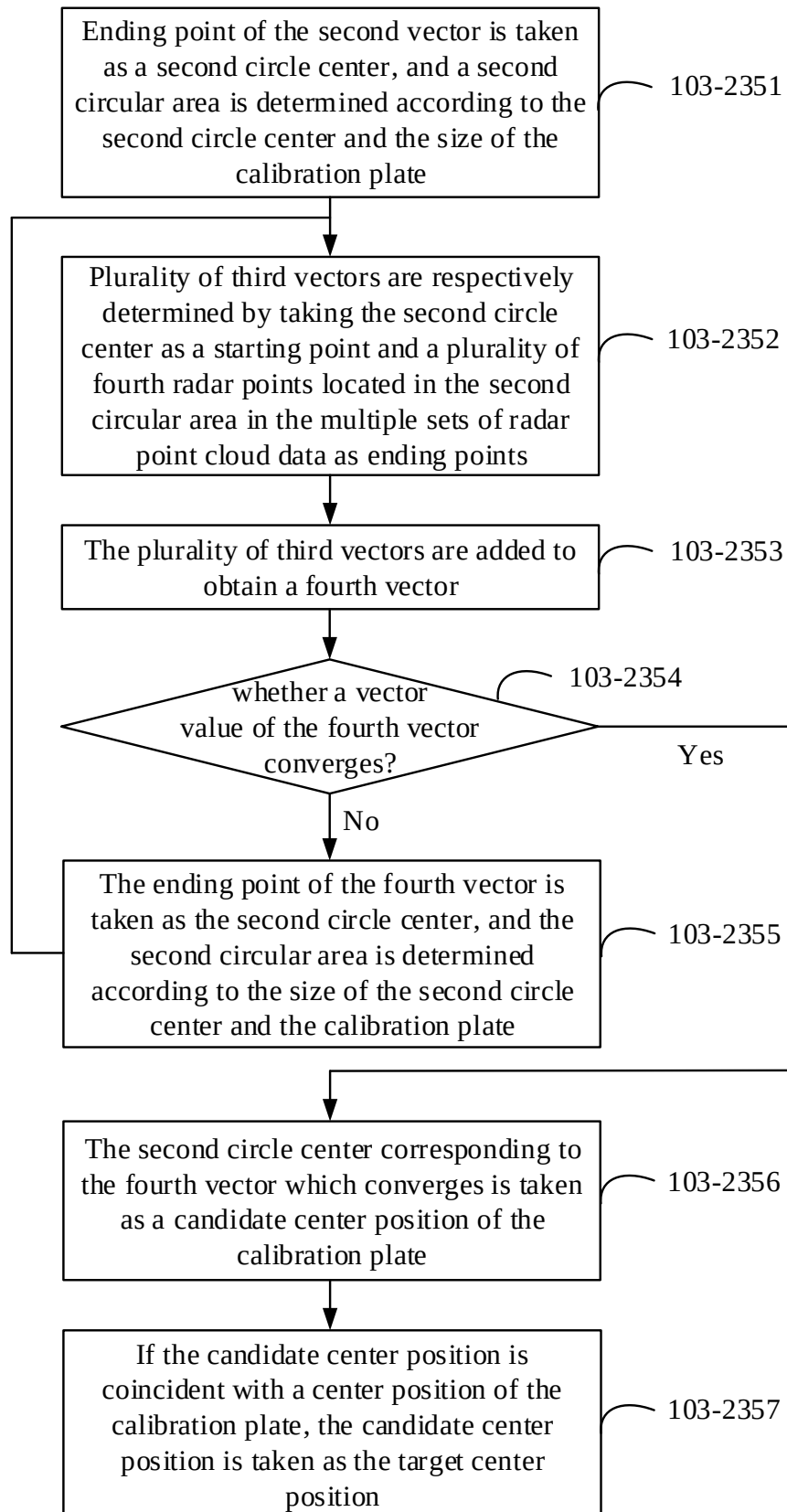


FIG. 14

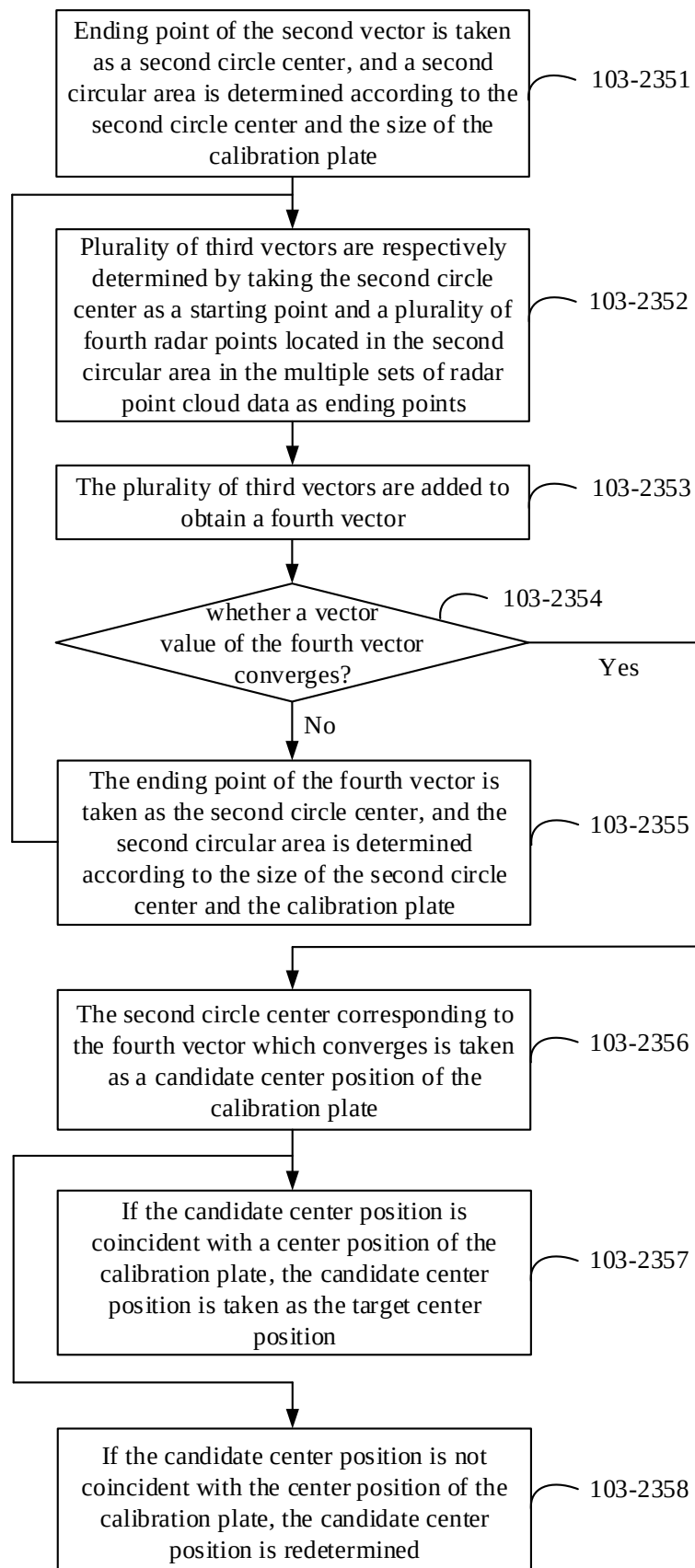


FIG. 15

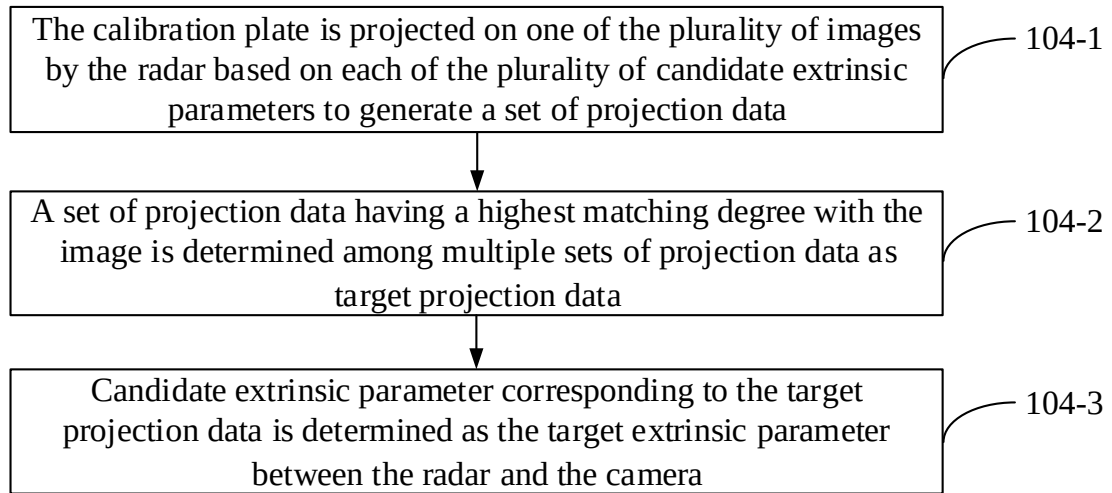


FIG. 16



FIG. 17A



FIG. 17B

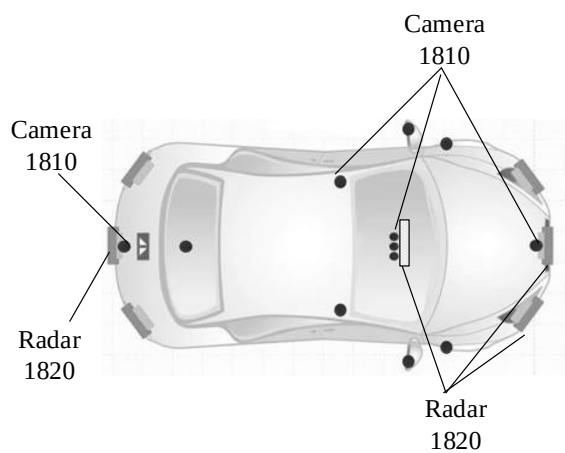


FIG. 18

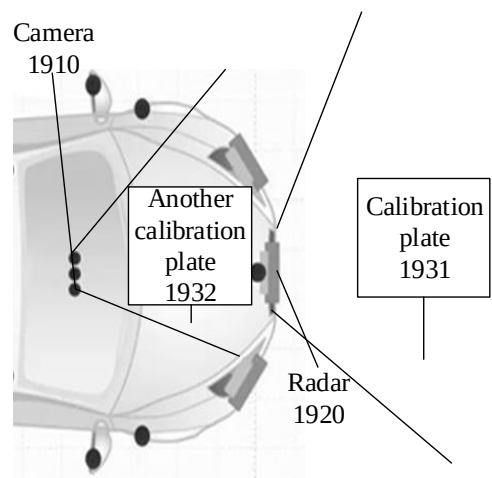


FIG. 19

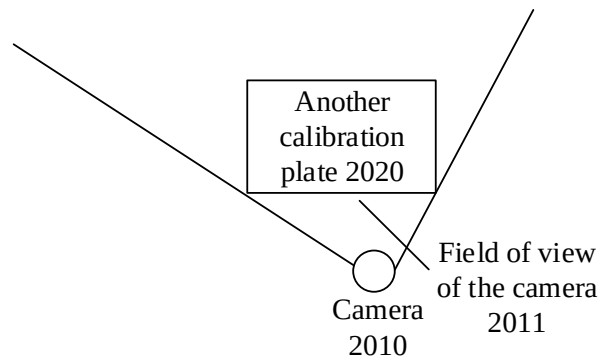


FIG. 20

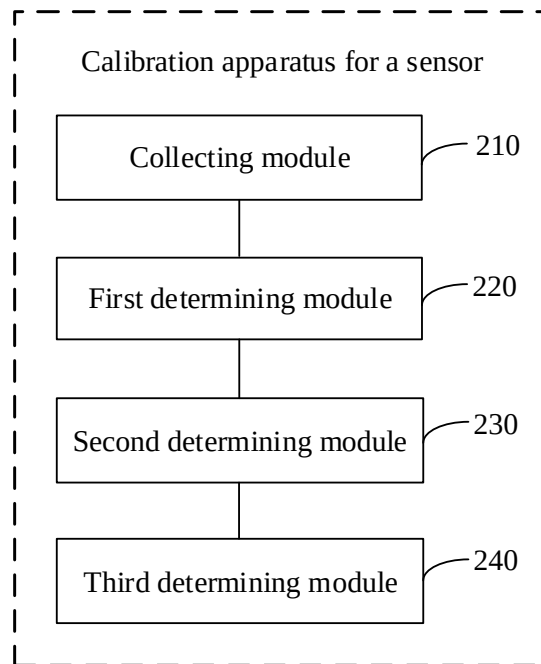


FIG. 21

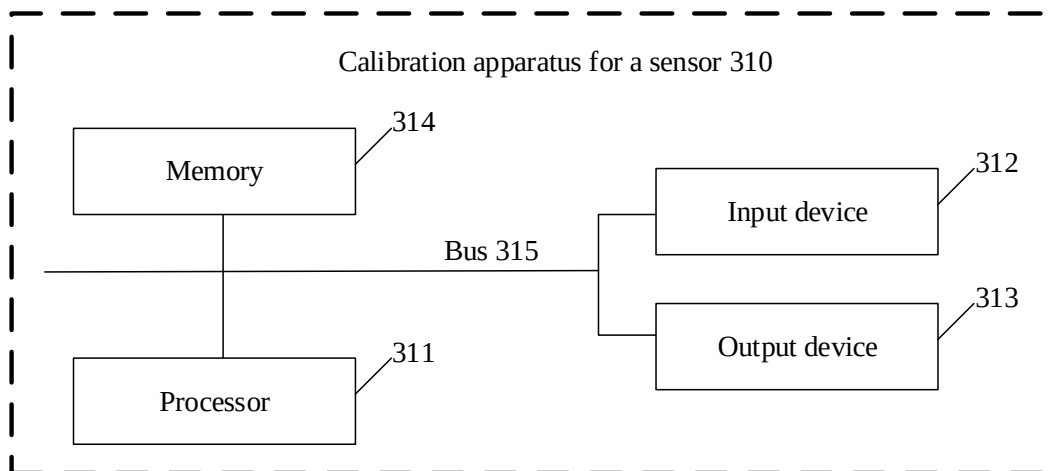


FIG. 22