

METHOD FOR REPRESENTING A HARMONIZED OBSCURED AREA OF AN
ENVIRONMENT OF A MOBILE PLATFORM

The present invention relates to a method for representing an
5 obscured area of an environment of a mobile platform, the area
obscured in respect to object areas of a first and a second imaging
device of the mobile platform.

A mobile platform may be an at least partially automated system,
10 which is mobile, as e.g. an at least partially automated vehicle,
and/or a vehicle including a driver assistance system.

Such a vehicle may include a driver assistance system for
visualization of a surrounding environment of the vehicle. This
15 driver assistance system may be referred to as a
surround-view-system and usually comprises one or more imaging
devices, as for instance cameras or video systems, which may be
mounted at the vehicle e.g. on top of the vehicle, wherein each
imaging device may provide a different viewing area or allows a
20 different viewing angle in respect to the environment. That means
the object area of the different imaging devices is different,
wherein an object area is an area an imaging device is able to
capture images of objects, which are physically located within
that area.

25 Because of physical and optical restrictions, such imaging
devices typically have a "blind spot"-area, which means that
there are areas of the environment, which are obscured in respect
to actual images of such imaging devices. For instance, this may
30 be the area from the ground underneath the mobile platform, as
e.g. the ground underneath a vehicle hidden by the vehicle itself.

There may be differences of the optical properties between raw
images taken by different imaging devices directed to different
35 parts of the environment, even in areas where both object areas
overlap. Composing images for presenting obscured areas, based
on such images of different imaging devices with different
optical properties of the compost sections, each section

originating from different imaging devices degrades the overall visual quality of the compost image.

The area underneath the bonnet of a vehicle is of special
5 importance because of the usage of such images of the obscured area for parking or off-road conditions. The differences in the optical properties of images of different imaging devices around the mobile platform may be related to brightness differences, color differences in respect the used imaging devices including
10 quality issues of the generated images, as well as the environmental conditions as e.g. shadows or other issues, which may disrupt or annoy a combination of such images.

Accordingly, the present invention is directed to a method for
15 representing an obscured area of an environment of a mobile platform, a surround-view-system, a mobile platform, a computer program, and a computer-readable storage medium as described in the independent claims.

20 Advantageous modifications of the invention are stated in the dependent claims. All combinations of at least two of the features disclosed in the description, the claims, and the figures fall within the scope of the invention. In order to avoid repetition, features disclosed in accordance with the method shall also apply
25 and be claimable in accordance with mentioned systems.

Steps of the method are presented in an order to explain the method, but the method should not be understood as to be restricted to this order, as any expert will understand, that the objective of the invention can be achieved using different
30 orders.

Aspects of the present invention are based on the inside, that an obscured area of the mobile platform, like a vehicle, may be composed and in this way representing an obscured area by image
35 data achieved at a prior time step by the imaging device taking images, when the actual obscured area was visible. That means an area obscured at a second time step may have been visible in the object area of an imaging device at a first time step, because

of the movement of the mobile platform including the imaging devices between the first and second time step.

5 An aspect of the present invention provides a method for representing an obscured area of an environment of a mobile platform in respect to an object area of a first and a second imaging device of the mobile platform.

10 In a step of the method, a delta-area is determined, being the difference of a second obscured area of the environment and a first obscured area of the environment. The second obscured area is obscured in respect to the object area of the first and second imaging device at a second time step. In addition the first obscured area of the environment is obscured in respect to the
15 object area of the first and second imaging device at a first time step.

In another step, a first overlap-image and a second overlap-image is determined, being an overlap of an image of the first imaging
20 device respectively of an image of the second imaging device with the delta-area, wherein both images are taken at the first time step.

In another step, a difference of an optical property of the images
25 of the first and the second imaging device is determined.

In another step, the difference of the optical property within at least one of the overlap-images is harmonized.

30 Such an obscured area results from the physical limitation of an individual imaging device to generate images representing the complete environment of a mobile platform. In addition, even if more than one imaging device is used, each imaging device pointing into different directions in respect to the mobile platform,
35 there might be areas of the environment, which are obscured areas in respect to object area of the imaging devices.

The object area of the imaging device is the area where the imaging device is able to generate images of objects in that area.

In this context, the mobile platform includes an at least partially automated system in respect to at least partially automated functionality, but a mobile platform also includes vehicles and other mobile machines, including driver assistance systems. Further examples of mobile platforms may be driver assistance systems utilizing multiple sensors, mobile multi-sensor robots like e.g. robotic vacuum cleaner, or robotic lawn mower, a multi-sensor surveillance system, a manufacturing machine, a personal assistant or an access control system. Each one of these systems may be fully or partially automated systems.

According to one aspect, the method of harmonizing at least the second obscured area includes a method of compensating the optical distortion of the raw images of the imaging devices, which may originate from the optical system used by the mentioned imaging devices.

Optical properties of images may be typically represented by a color and/or brightness of an individual pixel of the image. Beside this optical properties of the smallest unit of an image there may be also optical properties related to groups of pixels like structures or shadow areas.

Harmonizing of these optical properties may relate to a continuously and smooth transition from an optical property at one site of an image having a first optical property to another site of the image having a second optical property. There is a huge variety of techniques to harmonize images. Examples for harmonizing may be harmonizing within the second overlap area, harmonizing with respect to different directions, harmonizing in respect to an identified gradient inside or outside of the obscured area and so on.

Using such a method of composing sections of images of different imaging devices enable to represent obscured areas, even if that

area within an actual image of the used imaging devices of the mobile platform is outside of their object area. By harmonizing sections of the representation of an obscured area, which is composed by sections of images of at least two imaging devices of that obscured area, at a point in time when the area was not obscured in respect to the used imaging devices, improves the quality of the representation of that area.

The optical property difference of the images of the first and the second imaging devices may be determined using areas of the images appropriate for the goal of a smooth transition of optical properties and the selection of that areas may also take into account a smooth transition within images of the environment actually taken by the imaging devices. Visualizing of such a composed and harmonize representation of the obscured area, for instance on a screen inside of a vehicle, may give a pleasant picture to a passenger or driver of the vehicle, without annoying harsh contrasts within that picture representing the obscured area. By this the representation of the obscured area, especially beneath the bonnet area of the vehicle is improved.

In another aspect, the difference of the optical property is determined by comparing an optical property of at least a first reference area within the image of the first imaging device and at least a second reference area within the image of the second imaging device.

Referencing the optical properties to areas of images outside of the obscured area gives the advantage, that the representation of the obscured area is automatically adapted to the actual object area of the used imaging devices.

In another aspect, the first reference area and the second reference area is chosen from an object area of the first imaging device and respectively the second imaging device, where both object areas overlap.

Determining the difference of the optical properties of the images, of the at least two imaging devices from object areas of these devices which overlap, results in a good description of the optical properties of the two images. This may determine the
5 difference of the optical properties at that site, where a harsh contrast of combined images may be annoying, because at that site the two images of the different imaging devices adjoin each other.

10 In another aspect, the difference of the optical properties of the images of the first and the second imaging device is determined by averaging the optical properties within the reference area. This may improve the accuracy of the determination of the difference.

15 In another aspect, the reference areas are from the same size and overlap each other in the corresponding object area of the environment.

20 According to a further aspect, the described method for representing an obscured area of an environment may be performed multiple times using different reference areas. Differences of optical properties are characterized, with reference to different directions of the environment, wherein the harmonization within at least one of the overlap-images is
25 performed accordingly, taking into account optical property differences in respect to different directions.

30 According to a further aspect, the first and/or the second overlap-image is harmonized in respect to an optical property gradient defined by the difference of the optical properties and a length related to the obscured area.

To define such a gradient based on the determined difference of the optical properties a related length may be for instance a
35 borderline of the obscured area like the front borderline or a site borderline at it may be the full line or parts of the line.

According to one aspect, harmonizing of the second obscured area may include harmonizing the second overlap-image by adjusting the pixels of the second overlap-image adjacent to the border between the first overlap-image and the second overlap-image according to the determined optical property of the first imaging device.

Starting at the borderline of the first overlap-image and the second overlap-image each of the pixel of the second overlap-image, which are arranged in parallel to a front side borderline of the second obscured area are linearly adjusted in respect to their optical property in such a way, that the pixel at the side border of the second obscured area are adopted to the optical property of the second image device. All the pixels in between are respectively adapted according to the resulting gradient.

The remaining area of the second overlap-image may be adapted to the particular property of the second imaging device.

That means that there is a smooth transition within the at least one overlap-image for harmonization. The gradient may be calculated taking into account the absolute value of the difference of the optical properties of the images of the first and the second imaging device and the distance, which is defined for instance as explained above by half of a length of the obscured area.

According to a further aspect, the harmonization of the first or second overlap-image includes adjusting an optical property value of each pixel of the first or second overlap-image corresponding to the value and a direction of the gradient. The adjusting of the optical property value of each pixel can be calculated using a linear formula 1:

$$OP = (1 - t) \cdot OP2 + (t \cdot OP1) \quad (1)$$

Where OP stands for the optical property a pixel is adjusted to having a distance of $1-t$ from determined $OP1$, or a distance of t to the site of the determined $OP2$. $OP2$ and $OP1$ stands for the

optical properties of the images of the first and the second imaging devices at the respective sites.

5 The advantage of adjusting the optical property value of each pixel of the overlap-images corresponding to the gradient in respect to the strength and direction, based on differences of optical properties from reference areas outside of the obscured area, is a smooth transition of the optical properties, wherein the transition may fit to the optical properties of the actual
10 object area representing the environment of the mobile platform.

According to a further aspect, the optical property value is the brightness value and/or the color value.

15 As explained above the optical property of an individual pixel may be given by a brightness value and a color value. The color value depends on the used color model and typically includes three values for three colors. Harmonization of the brightness or the individual colors may be done with different techniques, but
20 using formula 1 for harmonization is an easy and quick way with small effort and good results. That means every individual color may be harmonized in the same way as the brightness by adjusting the pixel linearly using the determined gradient as described.

25 According to a further aspect, the delta-area is determined using motion data of the movable platform.

The obscured area may be the area not being part of the object area of at least two imaging devices for instance at a point in
30 time of a first time step. If the mobile platform is moving, the obscured area is moving too and is defined in the same way as explained at a second time step. After defining an obscured area at a first time step the location data of the environment may be updated for a second time step using motion data of the mobile
35 platform. To determine motion data of the mobile platform, for instance ego motion data or data from the controller area network bus (CAN) may be used, for determining the delta-area. A

controller area network bus data includes e.g. steering and speed data, ego motion relates to motion data determined from images.

A movement vector may be defined to transfer the obscured area at the first time step to the obscured area at the second time step, if the movement vector gives the distance and direction of the movement between the two time steps.

According to a further aspect, the first imaging device points into the front direction of the mobile platform and the second imaging device at least partially point into the direction of the motion of the mobile platform.

If the second imaging device at least partially point into the direction of the motion of the platform the image of the second imaging device at a first time step overlaps with the actual obscured area and that image may provide the overlap area needed for representing the obscured area.

According to a further aspect, the second obscured area is represented by the harmonized second overlap-image, the first overlap-image, and a section of a representation of the first obscured area.

If the mobile platform is moving straight, there is no need for harmonizing a representation of the obscured area, because the obscured area may be updated by image data of an image device directed into the front of the mobile platform.

If the mobile platform turns in a different direction, for updating the obscured area image data are needed, which originate from a different imaging device.

For complete updated representation of the obscured area a section of the prior obscured area, a section of an image of a first imaging device, which is directed to the front of the mobile platform, and a section, meaning the second overlap region, of an image of the second imaging device are needed. This second overlap region is harmonized as described above to adapt to the

other sections and the actual images of the at least two imaging devices.

A further aspect of the method is schematic shown below:

5 Image Data i from front, right and left side of the mobile platform: i_f, i_r, i_l at a point in time t ; and a point in time $t-1$: $i_f[t-1], i_r[t-1], i_l[t-1]$ are provided by four raw surround cam images; and also an image Patch of the obscured area at a time $t-1$: $g[t-1]$;
10 Brightness and/or color harmonization for a projected surface is applied using motion data mv_x, mv_y of the mobile platform;

A patch is transformed using: $g[x,y,t] = g[x+mv_x, y+mv_y, t-1]$,
15 where a motion vector is within an image patch;
A patch is transformed using: $g[x,y,t] = i_f, i_r, i_l, i_r[x+mv_x, y+mv_y, t-1]$, where motion vector is out of image patch using the motion data mv_x, mv_y

20 A further aspect of the method is schematic shown by the steps of:

- Vehicle ON
- Surround View System ON
- Continuously Capture Live Camera Data from Multiple Cameras
- 25 - Preserve the Previous Frame data from Multiple Cameras
- Monitor the Ego motion Info from Vehicle
- Harmonize the Image from previously stored Raw data
- Construct the Historical Ground plane View
- Render the Brightness Corrected Blind spot Ground plane

30 A mobile platform may include four imaging devices pointing into different directions to cover the complete environment of the mobile platform but excluding the obscured area beneath the mobile platform. For parking purpose or outdoor activities, it
35 may be helpful for a driver of a vehicle to have access to a representation of that hidden obscured area.

According to a further aspect, the representation of the obscured area is stored in between power cycles of the vehicle. This may provide information about the obscured area of e.g. a vehicle in a parking position from a prior journey to support the departure
5 from the parking position.

According to a further aspect, the representation of the obscured area shown on a screen of the movable platform. This representation as a picture on a screen may support a driver for
10 parking or outdoor activities.

A further aspect of the invention relates to a device, which is arranged to perform a method according to method described above. Such a device enables an easy accessible and transportable way
15 to perform the method.

A further aspect of the invention relates to a computer program comprising instructions, which, when the program is executed by a computer, cause the computer to carry out the method described
20 above.

A further aspect of the invention relates to a computer-readable storage medium on which the above-mentioned computer program is stored.
25

Reference will now be made in detail to exemplary embodiments of the present invention, examples of which are illustrated in the accompanying figures.

30 Fig. 1 shows a top-down view to a mobile platform turning to the left including a first and second obscured area;

Fig. 2 shows a vehicle including a screen and a surround-view-system; and
35

Fig. 3 shows the steps for representing an obscured area of an environment.

The figures are merely schematic representations and serve only to illustrate the invention. Advantages and features of the present invention, and implementation methods thereof will be clarified through following embodiments described with reference to the accompanying figures. The present invention may, however, be embodied in different forms and should not be construed as limited to the embodiments set forth herein.

A shape, a size, a ratio, an angle, and a number disclosed in the drawings for describing embodiments of the present invention are merely an example, and thus, the present invention is not limited to the illustrated details. The terms of a singular form may include plural forms unless referred to the contrary. In construing an element, the element is construed as including an error range although there is no explicit description.

It will be understood that, although the terms "first", "second", etc. may be used herein to describe various elements, these elements should not be limited by these terms. These terms are used only to distinguish one element from another. For example, a first element could be termed a second element, and, similarly, a second element could be termed a first element, without departing from the scope of the present invention. The embodiments of the present invention may be carried out independently from each other, or may be carried out together in co-dependent relationship.

Figure 1 shows a top-down view of an obscured area 20a related to a mobile platform at a first time step as defined above on a ground plane. The mobile platform may include a driver assistance system and/or surround-view system. In this exemplary embodiment, the mobile platform includes at least four imaging devices directed to four different directions in respect to the mobile platform, to enable obtaining a surround view of the current environment of the mobile platform. The imaging devices are arranged in such a way, that an object area F in front of the mobile platform is covered by an imaging device directed to the front of the mobile platform. An object area B in the rear area of the mobile platform is covered by an imaging device directed

to the rear of the mobile platform. An object area L respectively an object area R correspond to a left respectively right object area of the mobile platform, which are covered by corresponding imaging devices directed to the left respectively to the right side of the mobile platform.

The object areas of their respective imaging devices may overlap but for representing the environment, the mentioned areas F, B, L and R are defined resulting in borderlines 11, 12, 13, 14 between those areas as shown in figure 1.

Because of a movement of the mobile platform e.g. to the left a transformation of the first obscured area 20a to a second obscured area 20b results as shown figure 1. This is because the imaging devices are moving together with the mobile platform resulting in new object areas of each individual imaging device defining the corresponding second obscured area 20b.

For updating a given representation of the first obscured area 20a after the mobile platform has moved to a new position and resulting in a second obscured area 20b, the representation of the second obscured area 20b may be assembled from three sections A, B and C as shown in figure 1.

In a step S1, a delta-area A-B is determined. The delta area A-B is the difference of the second obscured area 20b of the environment, which is obscured in respect to the object area of the first imaging device F and the area of the second imaging device L at a second time step and a first obscured area 20a of the environment in respect to the object area of the first imaging device F and the second imaging device L at a first time step.

In a step S2 a first overlap-image A and a second overlap-image B is determined, being an overlap of an image of the first imaging device respectively an overlap of an image of the second imaging device with the delta-area A-B, wherein both images are taken at the first time step. The image of the first imaging device is an image of the object area F of the front imaging device and the

image of the second imaging device is an image of the object area L of the left imaging device of the mobile platform. The section for defining the first overlap area A and the second overlap area B is defined by the overlap of the two images with the delta-area A-B, being the sum of the two overlap areas A, B.

The optical properties of the first overlap area A and the still remaining obscured section C of the representation of the first obscured area 20a may be already adapted with respect to each other, because the image data for the representation of the first obscured area 20a may be based on images from the imaging device directed to the front object area F of the mobile platform.

The optical properties of the second overlap area B, being the overlap of the image of the second imaging device directed to the left object area L of the mobile platform may be different from the optical properties of the image of the first imaging device directed to the front object area of the mobile platform.

In a step S3, a difference of an optical property of the images of the first and the second imaging device is determined.

In particular, this difference of the optical property may be identified by comparing an optical property of at least a first reference area Rf within the image of the first imaging device F and at least a second reference area Rs within the image of the second image-taking device L.

In particular, the at least first reference area Rf and the at least second reference area Rs are areas of the environment, were the object areas of both imaging devices overlap Rf-Rs. That means, that for instance at a borderline 11, where the object area of the first imaging device, in this example the imaging device directed to the front object area F, and the object area of the second imaging device, in this example the imaging device, which is directed to the left object area L, both overlap. For representing the environment there is a borderline defined for

instance line 11, where the images of those object areas are adjacent to each other.

This reference area may be at any distance and site from the first obscured area 20a, for instance directly adjacent to the first obscured area 20a at the borderline 11.

In particular, the difference of the optical properties of the images of the first and the second imaging device may be determined by averaging the optical properties within the first Rf and the second reference area Rs for determining the difference of the optical properties of the image of the first imaging device and the image of the second imaging device.

Particularly the two reference areas Rf, Rs are from the same size and overlap each other in the corresponding object area of the environment.

The second overlap-image B is harmonized in respect to an optical property gradient, which is defined by the difference of the optical properties as described above and a length relative to the first obscured area. In particular, this length may be half of the distance from the front of the obscured area to the rear of the obscured area.

In particular, the harmonization of the second overlap-image includes adjusting an optical property value of each pixel of the second overlap-image corresponding to the value and a direction of the gradient. That means that each image pixel of the second overlap-image is adopted in respect to its optical property correspondingly to the distance from the point within the overlap area, where the difference of the brightness was determined up to the middle of the obscured area, starting with the determined value referenced to the optical property of the image of the front imaging device up to the value of the determined optical property of the left imaging device.

Starting at the borderline 11 of the first overlap-image A and the second overlap-image B each of the pixel of the second

overlap-image B, which are arranged in parallel to a front side
borderline of the second obscured area 20b are linearly adjusted
in respect to their optical property in such a way, that the pixel
at the side border of the second obscured area are adopted to the
5 optical property of the second image device. All the pixels in
between are respectively adapted according to the resulting
gradient. The adjusting of the optical property value of each
pixel can be calculated using a linear formula 1:

$$OP = (1 - t) \cdot OP2 + (t \cdot OP1)$$

10 Where t is a typical distance in respect to OP1 and OP2 as
described above.

Where OP1 and OP2 are the optical properties of the first Rf and
the second reference area Rs. The remaining area of the second
15 overlap-image may be adapted to the particular property of the
second imaging device.

That means that there is a smooth transition within the at least
one overlap-image for harmonization.

20

Figure 2 schematically shows a vehicle 200 including a screen 220
and a surround-view-system.

Figure 3 schematically shows the method including steps S1 to S4
25 as described above.

5 Claims

1. A method for representing an obscured area (20a, 20b) of an environment of a mobile platform (200) in respect to an object area of a first and a second imaging device of the mobile platform
10 (200), the method comprising:

 determining a delta-area (A, B) (S1), being the difference of a second obscured area (20b) of the environment, which is obscured in respect to the object area of the first and second imaging device at a second time step and a first obscured area
15 (20a) of the environment, which is obscured in respect to the object area of the first and second imaging device at a first time step;

 determining a first overlap-image (A) and a second overlap-image (B) (S2), being an overlap of an image of the first
20 imaging device respectively of an image of the second imaging device with the delta-area (A, B), wherein both images are taken at the first time step;

 determining a difference of an optical property (S3) of the images of the first and the second imaging device;

25 harmonizing the difference of the optical property (S4) within at least one of the overlap-images (A, B).

2. The method according to claim 1, wherein the difference of the optical property is determined by comparing an optical
30 property of at least a first reference area (Rf) within the image of the first imaging device and at least a second reference area (Rs) within the image of the second imaging device.

3. The method according to claim 2, wherein the at least first reference area (Rf) and the at least second reference area (Rs)
35 are areas of the environment, where the object areas of both imaging devices overlap.

4. The method according to any one of the preceding claims, wherein the first (A) and/or the second overlap-image (B) is harmonized in respect to an optical property gradient defined by the difference of the optical properties and a length related to the first obscured area (20a).

5. The method according to claim 4, wherein the harmonization of the first (20a) or second overlap-image (20b) includes adjusting an optical property value of each pixel of the first (20a) or second overlap-image (20b) corresponding to the value and a direction of the gradient.

6. The method according to one of the preceding claims, wherein the optical property value is the brightness value and/or the color value.

7. The method according to one of the preceding claims, wherein the delta-area (A, B) is determined using motion data of the mobile platform (200).

8. The method according to any one of the preceding claims, wherein the first imaging device points into the front direction of the mobile platform (200) and the second imaging device at least partially point into the direction of the motion of the mobile platform.

9. The method according to any one of the preceding claims, wherein the second obscured area (20b) is represented by the harmonized second overlap-image (B), the first overlap-image (A) and a section of a representation of the first obscured area (C).

10. The method according to claim 9, wherein the representation of the second obscured area (B) is stored in between power cycles of the vehicle.

11. The method according to any one of the preceding claims, wherein the representation of the second obscured area (B) is shown on a screen (220) of the mobile platform (200).

12. A surround-view-system (210), arranged to perform the method according to one of the claims 1 to 11.

5 13. A mobile platform (200), preferably a vehicle (200), including a screen (220) for visualizing a representation of the obscured area (20a, 20b), and a surround-view-system (210) according to claim 12.

10 14. A computer program comprising instructions, which, when a computer executes the program, cause the computer to carry out the method according to claims 1 to 11.

15 15. A computer-readable storage medium on which the computer program according to claim 14 is stored.

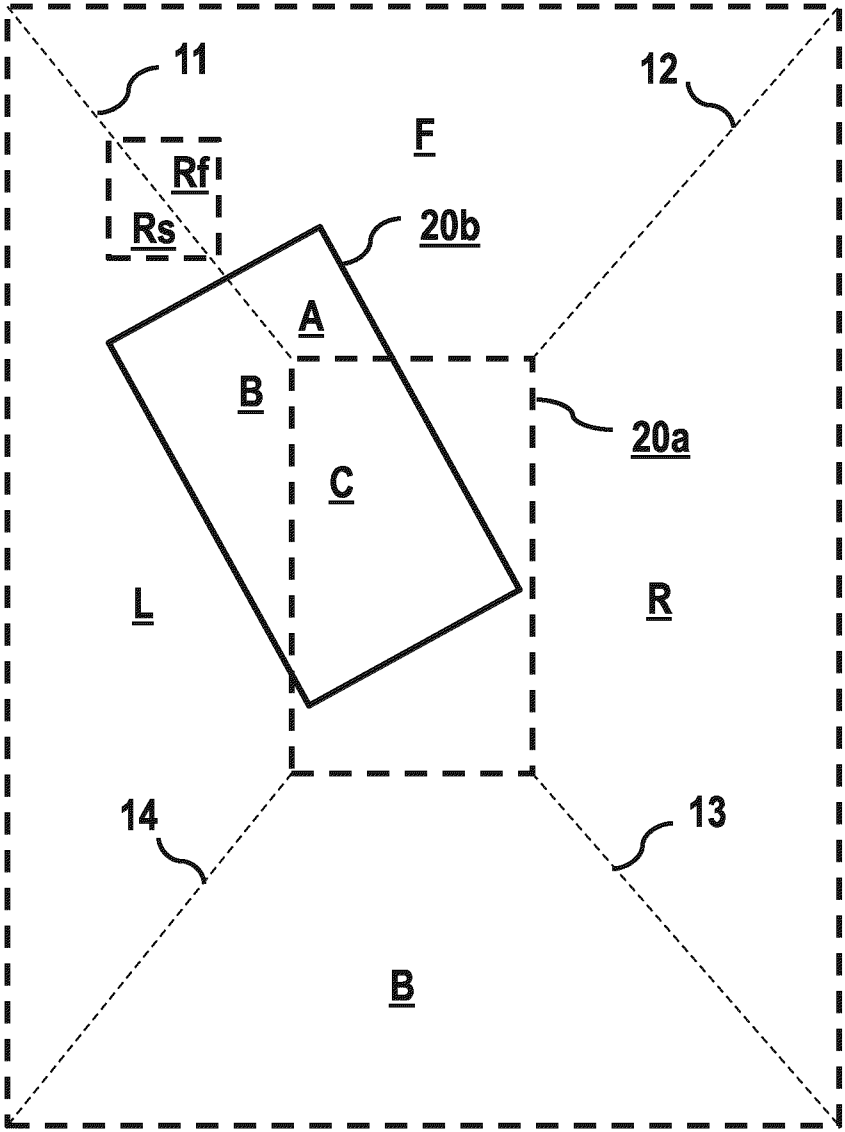


Fig. 1

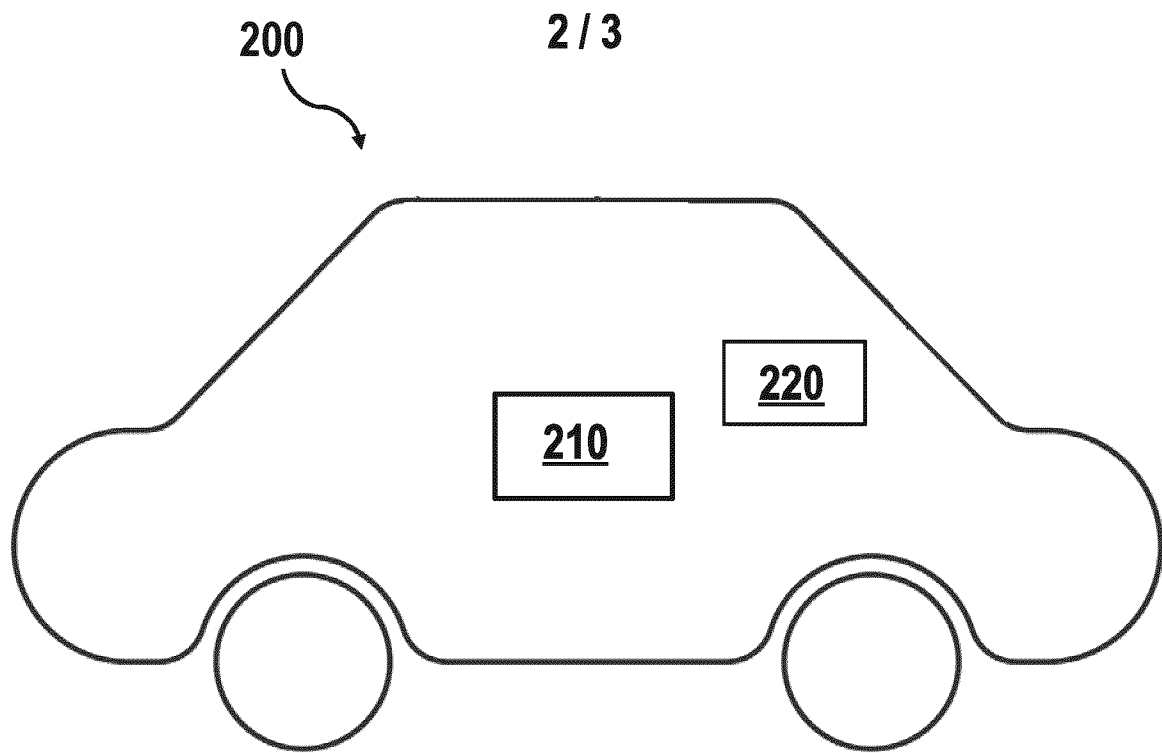


Fig. 2

3 / 3

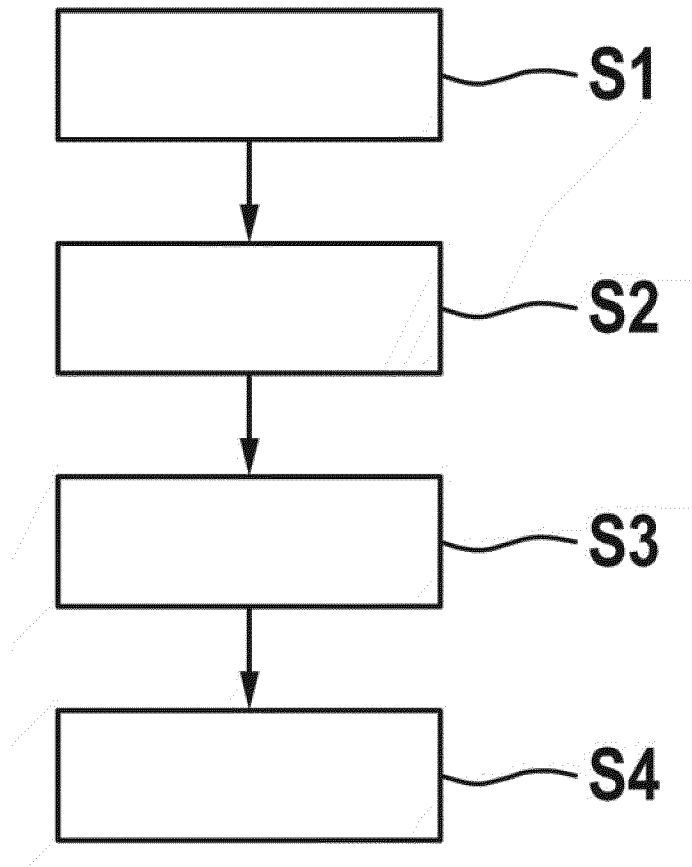


Fig. 3

INTERNATIONAL SEARCH REPORT

International application No
PCT/EP2020/064016

A. CLASSIFICATION OF SUBJECT MATTER
INV. H04N7/18 B60R1/00 G06T3/40
ADD.

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)
H04N B60R G06T

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

EPO-Internal, WPI Data

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	GB 2 559 758 A (JAGUAR LAND ROVER LTD [GB]) 22 August 2018 (2018-08-22) abstract figures 3,5,6,9 page 1, lines 13-22 page 1, line 35 - page 2, line 6 page 14, line 16 - page 15, line 27 page 17, line 26 - page 18, line 4 page 22, line 22 - page 30, line 29 page 26, lines 26-34	1-15
A	US 6 813 391 B1 (UYTTENDAELE MATTHEW T [US] ET AL) 2 November 2004 (2004-11-02) abstract figure 2 column 7, line 6 - line 49 ----- -/-	2,3



Further documents are listed in the continuation of Box C.



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Date of the actual completion of the international search

16 June 2020

Date of mailing of the international search report

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INTERNATIONAL SEARCH REPORT

International application No
PCT/EP2020/064016

C(Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
A	JP 2015 222934 A (CALSONIC KANSEI CORP) 10 December 2015 (2015-12-10) abstract figures 3-8 -----	1-15

INTERNATIONAL SEARCH REPORT

Information on patent family members

International application No

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