

I1 🡺Data received from the laser

I2 🡺Data received from the camera

I3=O1🡺 Matched objects between laser and camera

I4=O2🡺Not matched objects

I5=I7=O3🡺 Paired objects between current frame and the last frame

I6=I8=O4🡺Not paired objects of the actual frame

O5🡺Fusion tracks prepared to send to a decision system