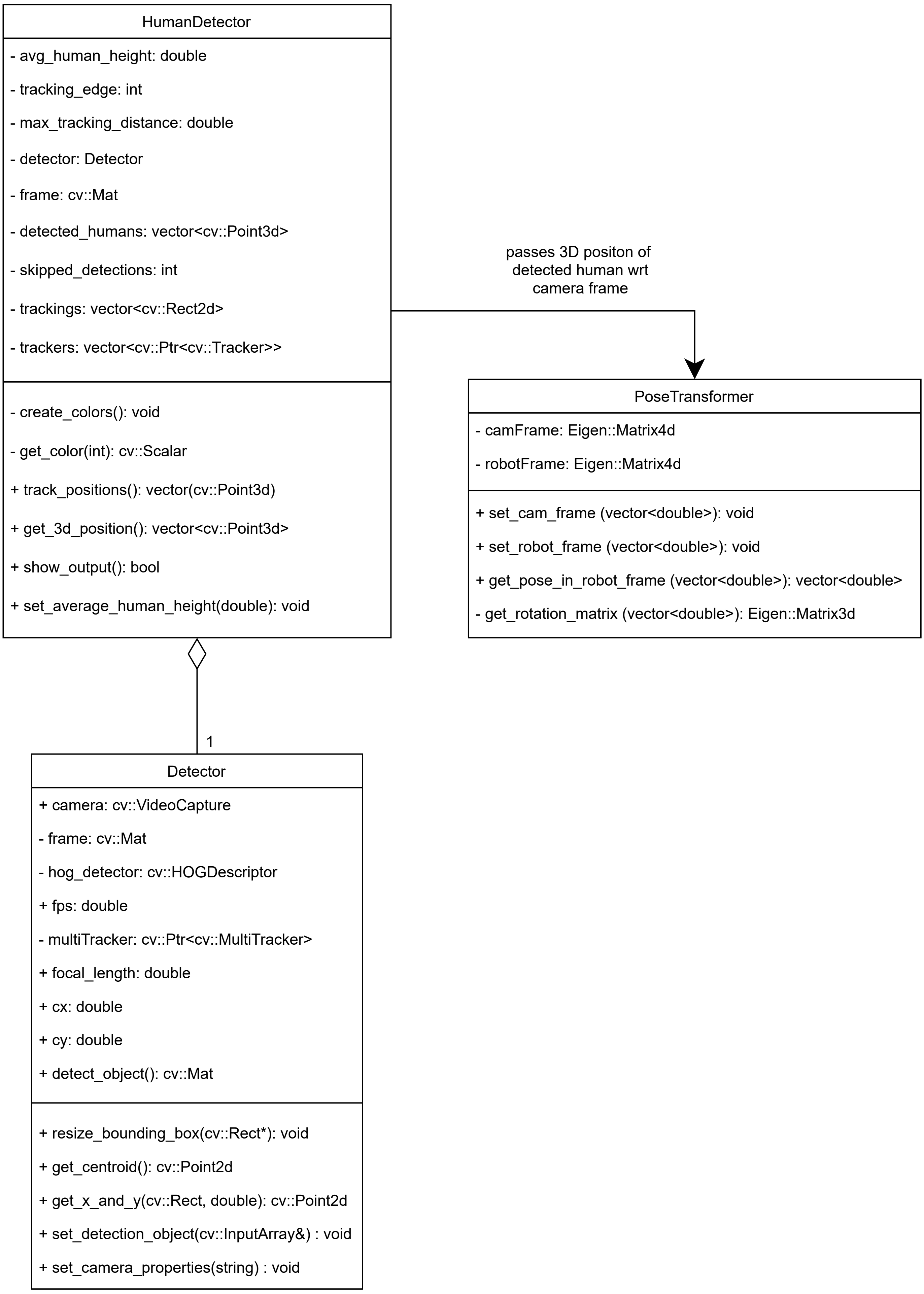
HumanDetector
- avg_human_height: double
- tracking_edge: int
- max_tracking_distance: double
- detector: Detector
- frame: cv::Mat
- detected_humans: vector<cv::Point3d>
- skipped_detections: int
- trackings: vector<cv::Rect2d>
- trackers: vector<cv::Ptr<cv::Tracker>>
- create_colors(): void
- get_color(int): cv::Scalar
+ track_positions(): vector(cv::Point3d)
+ get_3d_position(): vector<cv::Point3d>
+ show_output(): bool
+ set_average_human_height(double): void
passes 3D positon of detected human wrt camera frame
PoseTransformer
- camFrame: Eigen::Matrix4d
- robotFrame: Eigen::Matrix4d
+ set_cam_frame (vector<double>): void
+ set_robot_frame (vector<double>): void
+ get_pose_in_robot_frame (vector<double>): vector<double>
- get_rotation_matrix (vector<double>): Eigen::Matrix3d
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Detector
+ camera: cv::VideoCapture
- frame: cv::Mat
- hog_detector: cv::HOGDescriptor
+ fps: double
- multiTracker: cv::Ptr<cv::MultiTracker>
+ focal_length: double
+ cx: double
+ cy: double
+ detect_object(): cv::Mat
+ resize_bounding_box(cv::Rect*): void
+ get_centroid(): cv::Point2d
+ get_x_and_y(cv::Rect, double): cv::Point2d
+ set_detection_object(cv::InputArray&) : void
+ set_camera_properties(string) : void