Clear background detection algorithm

1.Use

Source code Launch file path:/OPT/ROS/noetic/share/opencv_apps/launch

Step 1: Start the camera

```
roslaunch dofbot_visual opencv_apps.launch img_flip:=false
```

- img_flip parameter: whether the image needs to be flipped horizontally, the default is false.

[usb_cam-test.launch] file opens the [web_video_server] node by default, and you can directly use the [IP:8080] web page to view images in real time.

Step 2: Start the corner detection function of Opencv_apps

```
roslaunch opencv_apps segment_objects.launch              # Clear background
detection algorithm
```

Each functional case will have a parameter [debug_view], Boolean type, whether to use Opencv to display images, which is displayed by default.

If no display is required, set it to [False], for example

```
roslaunch opencv_apps contour_moments.launch debug_view:=False
```

However, after starting this way, some cases cannot be displayed in other ways, because in the source code, some [Debug_view] are set to [FALSE], and the image processing will be turned off.

2.Display method

- rqt_image_view

Enter the following command to select the corresponding topic

```
rqt_image_view
```

- opencv

The system displays it by default, no need to do anything.

- Web viewing

(Same as under LAN) Enter IP+port in the browser, for example:

```
192.168.2.116:8080
```

Use your current virtual machine IP.

3. Effect display

By comparing the image, you can see that the background has been cleared.