

32、Watershed segmentation algorithm

32.1、Use

Source code launch file path: ~/jetcobot_ws/src/opencv_apps/launch

Step 1: Start the camera

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

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

Step 2: Start the corner detection function of Opencv_apps

```
roslaunch opencv_apps camshift.launch                # target tracking  
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 in this way, some cases cannot be displayed in other ways, because in the source code, some [debug_view] is set to [False], which will turn off image processing.

32.2、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.

32.3、Effect display method

Use the mouse to select different objects and the system will automatically distinguish them.

