18、Feature point tracking

18.1、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 goodfeature_track.launch            # Feature point tracking
```

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.

18.2、Display method

- rqt_image_view

Enter the following command and select the corresponding topic

```
rqt_image_view
```

- opencv

The system displays it by default and no processing is required.

18.3、Effect display

You can see an adjustable window appearing on the screen, and object feature points appearing at the same time.


Image
Max corners
75