15、Optical flow detection algorithm

15.1、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 parameters: 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 fback_flow.launch                  # Optical flow 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 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.

15.2、Display method

- rqt_image_view

Enter the following command to select the corresponding topic

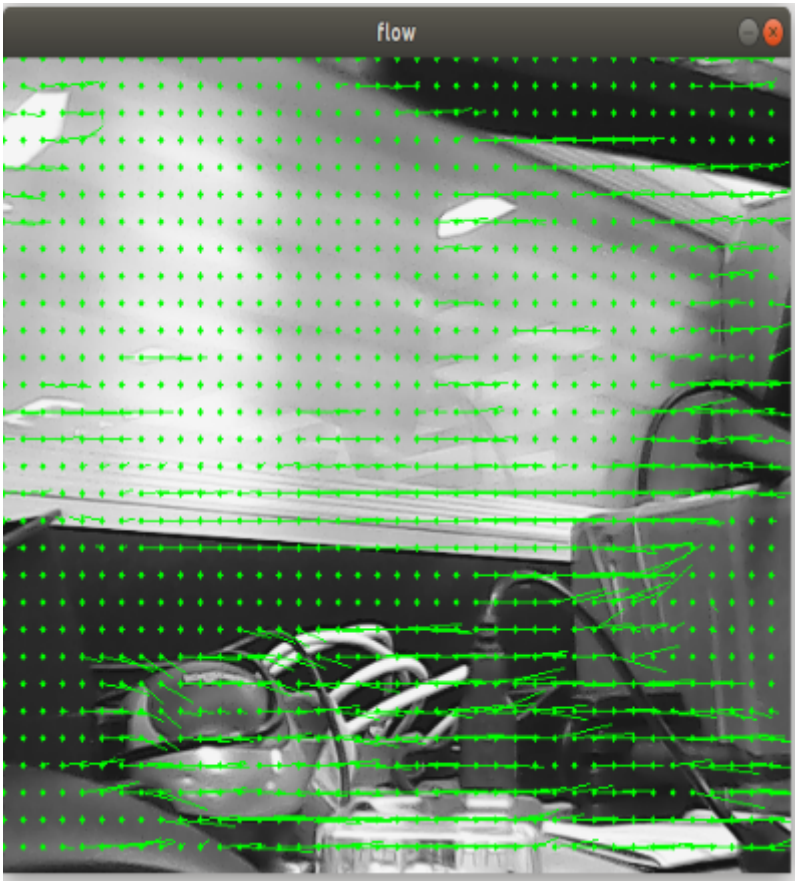
```
rqt_image_view
```

- opencv

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

15.3、Effect display

Move the screen and observe the phenomenon.


flow