21、Hough linear detection

21.1、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 hough_lines.launch                  # Hough linear detection
```

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.

21.2、 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.

21.3、Effect display

The lower the threshold, the more lines there are and the easier it is for the picture to freeze.


Hough Lines Demo
Thres: 50 + input
150