

Threshold image processing

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.

[`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 threshold.launch                                # Threshold image  
processing
```

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 may not be displayed in other ways, because in the source code, some [`debug_view`] is set to [`False`], which will turn off image processing.

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 LAN) Enter IP+port in the browser, for example.

```
192.168.2.116:8080
```

For specific IP, use your current virtual machine IP.

3. Effect display

The picture below is the threshold transformation diagram after processing.

