

Target tracking algorithm

Locating objects in consecutive frames of a video is called tracking. In OpenCV, you can use traditional target tracking algorithms (such as mean tracking, Kalman filtering, etc.) Or target trackers based on deep learning (such as MOSSE, CSRT, etc.) for target tracking. Deep learning object trackers generally perform better in accuracy and robustness

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.

The `[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 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.

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

You can see an adjustable window appear on the screen, followed by a red frame.

