

Oriented object detection.md

Note: The environment has been set up. Simply follow the instructions to run the corresponding function commands to use it.

1. Orienting Objects: Images

Use yolo11n-obb.pt to predict images provided with the Ultralytics project.

Go to the code folder:

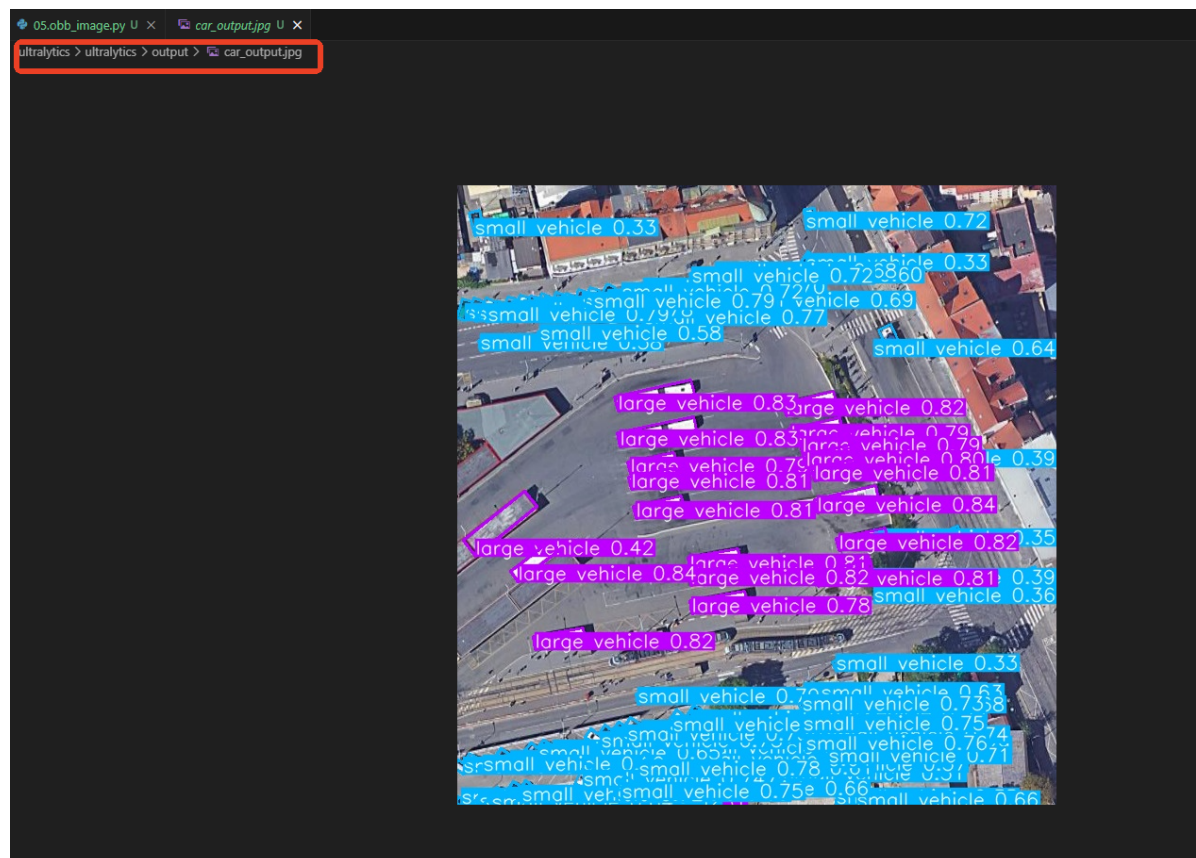
```
cd /home/sunrise/ultralytics/ultralytics/yahboom_demo
```

Run the code:

```
python3 05.obb_image.py
```

Preview

Yolo recognition output image location: /home/sunrise/ultralytics/ultralytics/output/



Sample code:

```
from ultralytics import YOLO

# Load a model
model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb.pt")
# model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb.onnx")
# model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb_ncnn_model")
```

```
# Run batched inference on a list of images
results = model("/home/sunrise/ultralytics/ultralytics/assets/car.jpg") #
return a list of Results objects

# Process results list
for result in results:
    boxes = result.boxes # Boxes object for bounding box outputs
    # masks = result.masks # Masks object for segmentation masks outputs
    # keypoints = result.keypoints # Keypoints object for pose outputs
    # probs = result.probs # Probs object for classification outputs
    obb = result.obb # Oriented boxes object for OBB outputs
    result.show() # display to screen

    result.save(filename="/home/sunrise/ultralytics/ultralytics/output/car_output.j
pg") # save to disk
```

2. Oriented Object Detection: Video

Use yolo11n-obb.pt to predict videos in the Ultralytics project (not included with Ultralytics).

Go to the code folder:

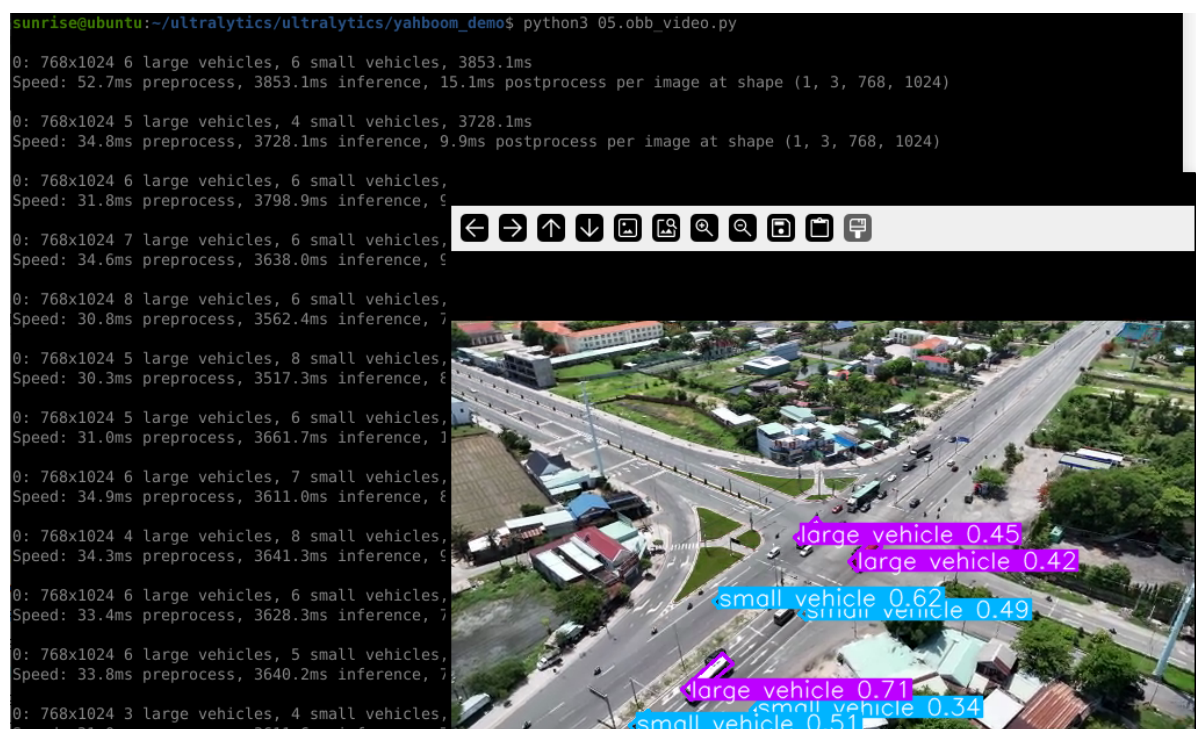
```
cd /home/sunrise/ultralytics/ultralytics/yahboom_demo
```

Run the code:

```
python3 05.obb_video.py
```

Preview

Yolo recognition output video location: /home/sunrise/ultralytics/ultralytics/output/



Sample code:

```

import cv2
from ultralytics import YOLO

# Load the YOLO model
model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb.pt")
# model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb.onnx")
# model = YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb_ncnn_model")

# Open the video file
video_path = "/home/sunrise/ultralytics/ultralytics/videos/street.mp4"
cap = cv2.VideoCapture(video_path)

# Get the video frame size and frame rate
frame_width = int(cap.get(cv2.CAP_PROP_FRAME_WIDTH))
frame_height = int(cap.get(cv2.CAP_PROP_FRAME_HEIGHT))
fps = int(cap.get(cv2.CAP_PROP_FPS))

# Define the codec and create a Videowriter object to output the processed video
output_path =
"/home/sunrise/ultralytics/ultralytics/output/05.street_output.mp4"
fourcc = cv2.VideoWriter_fourcc(*'mp4v') # You can use 'XVID' or 'mp4v'
depending on your platform
out = cv2.VideoWriter(output_path, fourcc, fps, (frame_width, frame_height))

# Loop through the video frames
while cap.isOpened():
    # Read a frame from the video
    success, frame = cap.read()

    if success:
        # Run YOLO inference on the frame
        results = model(frame)

        # Visualize the results on the frame
        annotated_frame = results[0].plot()

        # Write the annotated frame to the output video file
        out.write(annotated_frame)

        # Display the annotated frame
        cv2.imshow("YOLO Inference", cv2.resize(annotated_frame, (640, 480)))

        # Break the loop if 'q' is pressed
        if cv2.waitKey(1) & 0xFF == ord("q"):
            break
    else:
        # Break the loop if the end of the video is reached
        break

# Release the video capture and writer objects, and close the display window
cap.release()
out.release()
cv2.destroyAllWindows()

```

3. Directed Object Detection: Real-Time Detection

3.1. Launching the Camera

Launch the following program based on your camera model. In the terminal, enter:

```
#usb camera
ros2 launch usb_cam camera.launch.py
#nuwa camera
ros2 launch ascamera hp60c.launch.py
```

Open another terminal and navigate to the code folder:

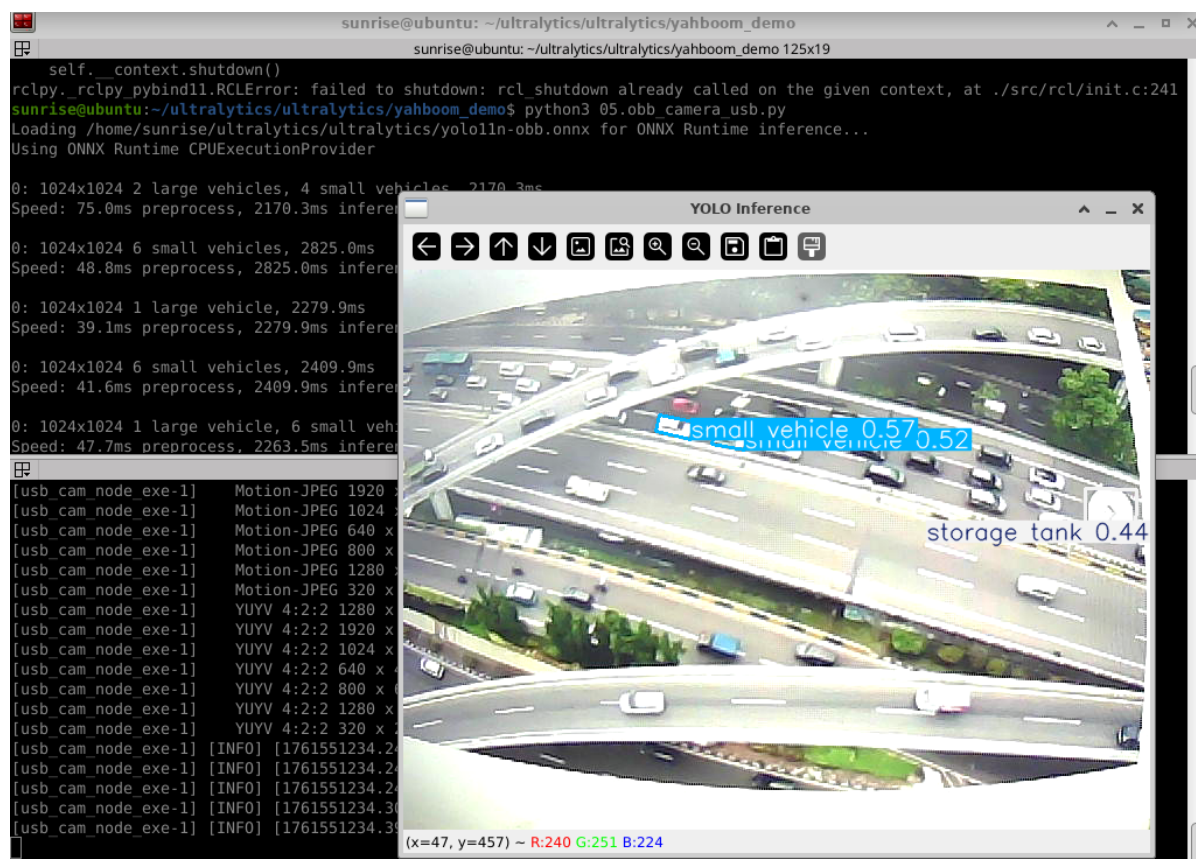
```
cd /home/sunrise/ultralytics/ultralytics/yahboom_demo
```

Run the code: Click the preview screen and press q to terminate the program!

```
python3 05.obb_camera_usb.py
```

Preview

Yolo recognition output video location: /home/sunrise/ultralytics/ultralytics/output/



Sample code:

```
#!/usr/bin/env python3
import rclpy
from rclpy.node import Node
from sensor_msgs.msg import Image, CompressedImage
from cv_bridge import CvBridge
```

```

import cv2
from ultralytics import YOLO
import os

class Image_detection(Node):
    def __init__(self):
        super().__init__('Image_detection')
        self.model = model =
YOLO("/home/sunrise/ultralytics/ultralytics/yolo11n-obb.pt")
        self.camera_type = os.getenv('CAMERA_TYPE', 'usb')
        self.bridge = CvBridge()
        if self.camera_type == 'usb':
            topic_name = '/usb_cam/image_raw'
        else:
            topic_name = '/ascamera_hp60c/camera_publisher/rgb0/image'

        self.subscription = self.create_subscription(Image, topic_name,
self.image_callback, 10)

        # Get the video frame size and frame rate
        frame_width = 640
        frame_height = 480
        fps = 15

        output_path =
"/home/sunrise/ultralytics/ultralytics/output/05.obb_camera_usb.mp4"
        fourcc = cv2.VideoWriter_fourcc(*'mp4v') # You can use 'XVID' or 'mp4v'
depending on your platform
        self.out = cv2.VideoWriter(output_path, fourcc, fps, (frame_width,
frame_height))

    def image_callback(self, msg):
        cv_image = self.bridge.imgmsg_to_cv2(msg, desired_encoding='bgr8')

        self.proecc(cv_image)

# Loop through the video frames
    def proecc(self, frame):
        # Run YOLO inference on the frame
        results = self.model(frame)

        # Visualize the results on the frame
        annotated_frame = results[0].plot()

        # Write the annotated frame to the output video file
        self.out.write(annotated_frame)

        # Display the annotated frame
        cv2.imshow("YOLO Inference", cv2.resize(annotated_frame, (640, 480)))

        # Break the loop if 'q' is pressed
        cv2.waitKey(1) & 0xFF == ord("q")

    def cancel(self):
        cv2.destroyAllWindows()
        self.out.release()

def main(args=None):

```

```
rclpy.init(args=args)
node = Image_detection()
try:
    rclpy.spin(node)
except KeyboardInterrupt:
    pass
finally:
    node.cancel()
    node.destroy_node()
    rclpy.shutdown()

if __name__ == '__main__':
    main()
```