Lane

+int polyOrder

+std::string colour

+std::vector<double> polyCoeff +cv::Point startCoordinates

+cv..Point startCoordinates

+bool status

LaneDetectionModule

-yellowMinx : cv::Scalar -yellowMax : cv::Scalar -grayscaleMin : int -grayscaleMax : int -videoName : std::string

+LaneDetectionModule()

+~LaneDetectionModule()

+undistortImage(const cv::Mat& src , cv::Mat& dst) : void

+thresholdImageY(const cv::Mat& src , cv::Mat& dst) : void

+thresholdImageW(const cv::Mat& src , cv::Mat& dst) : void

+extractROI(const cv::Mat& src , cv::Mat& dst) : void

+extractLanes(const cv::Mat& src , Lane& lane1 , Lane& lane2 , int curveFlag) : void

+getDriveHeading(Lane& lane1 , Lane& lane2) : double

+displayOutput(const cv::Mat& src , Lane& lane1 , Lane& lane2 , double heading) : void

+detectLane(std::string videoName) : bool

+getYellowMax(): cv::Scalar +getYellowMin(): cv::Scalar

+setYellowMax(cv::Scalar value) : void

+setYellowMin(cv::Scalar value) : void

+setGrayScaleMin(int value) : void +setGrayScaleMax(int value) : void

+getGrayScaleMin(): int +getGrayScaleMax(): int