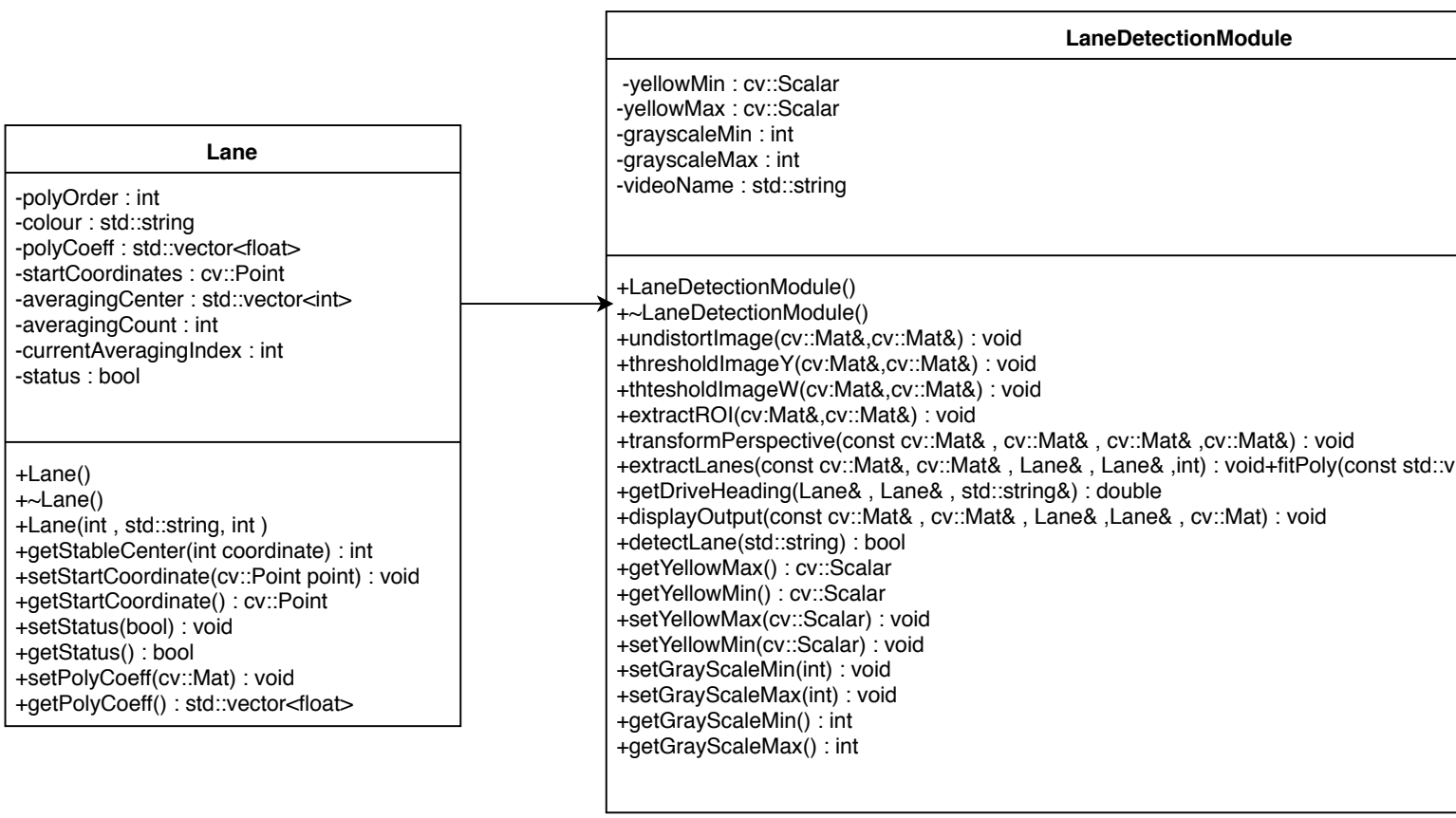
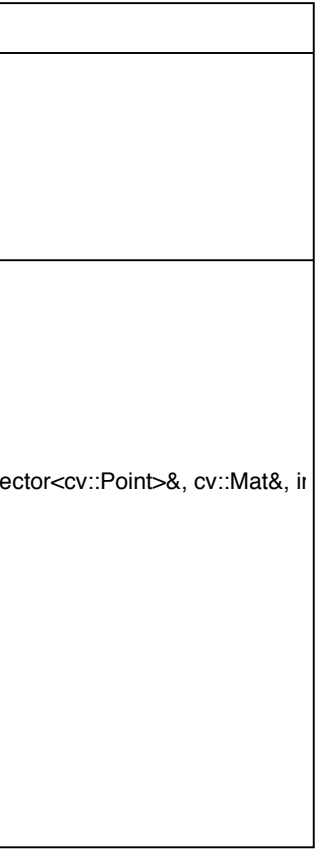

Lane
-polyOrder : int
-colour : std::string
-polyCoeff : std::vector<float>
-startCoordinates : cv::Point
-averagingCenter : std::vector<int>
-averagingCount : int
-currentAveragingIndex : int
-status : bool
+Lane()
+~Lane()
+Lane(int , std::string, int )
+getStableCenter(int coordinate) : int
+setStartCoordinate(cv::Point point) : void
+getStartCoordinate() : cv::Point
+setStatus(bool) : void
+getStatus() : bool
+setPolyCoeff(cv::Mat) : void
+getPolyCoeff() : std::vector<float>
LaneDetectionModule
-yellowMin : cv::Scalar
-yellowMax : cv::Scalar
-grayscaleMin : int
-grayscaleMax : int
-videoName : std::string
+LaneDetectionModule()
+~LaneDetectionModule()
+undistortImage(cv::Mat&,cv::Mat&) : void
+thresholdImageY(cv:Mat&,cv::Mat&) : void
+thteshold ImageW(cv:Mat&,cv::Mat&) : void
+extractROI(cv:Mat&,cv::Mat&) : void
+transformPerspective(const cv::Mat& , cv::Mat& , cv::Mat& ,cv::Mat&) : void
+extractLanes(const cv::Mat&, cv::Mat& , Lane& , Lane& ,int) : void+fitPoly(const std::v
+getDriveHeading(Lane& , Lane& , std::string&) : double
+displayOutput(const cv::Mat& , cv::Mat& , Lane& ,Lane& , cv::Mat) : void
+detectLane(std::string) : bool
+getYellowMax() : cv::Scalar
+getYellowMin() : cv::Scalar
+setYellowMax(cv::Scalar) : void
+setYellowMin(cv::Scalar) : void
+setGrayScaleMin(int) : void
+setGrayScaleMax(int) : void
+getGrayScaleMin() : int
+getGrayScaleMax() : int


ector<cv::Point>&, cv::Mat&, ir