

com._604robotics.robot2012.vision

Class Target

java.lang.Object
com._604robotics.robot2012.vision.Target

```
public class Target
extends Object
```

Represents a target.

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Field Summary

Fields	
Modifier and Type	Field and Description
double	angle This is the angle of the target, relative to the camera.
double	angle_uncertainty This is the uncertainty of the angle of the target.
double	x x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera.
double	x_uncertainty These are the uncertainties of the x, y, and z positions of the target.
double	y x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera.
double	y_uncertainty These are the uncertainties of the x, y, and z positions of the target.
double	z x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera.
double	z_uncertainty These are the uncertainties of the x, y, and z positions of the target.

Constructor Summary

Constructors	
Constructor and Description	
Target()	
Target (double x, double y, double z, double angle)	
Target (double x, double y, double z, double x_uncertainty, double y_uncertainty, double z_uncertainty, double angle, double angle_uncertainty)	
Target (Point3d point, double angle)	

Method Summary

Methods	
Modifier and Type	Method and Description
String	toString()
Methods inherited from class java.lang.Object	
clone, equals, finalize, getClass, hashCode, notify, notifyAll, wait, wait, wait	

Field Detail

angle

```
public double angle
```

This is the angle of the target, relative to the camera.

(angle)
.....(Target)
...../
...../
...../
.../ - - - - - |> (Camera)
.../
../
./
/
/
this value is expressed in radians.

angle_uncertainty

```
public double angle_uncertainty
```

This is the uncertainty of the angle of the target. This is interpreted as a plus or minus to the angle. Again, this is expressed in radians

x

```
public double x
```

x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera. y will be positive when the target appears to be above of the center of the camera. z will always be negative (see [Wikipedia: Right-hand rule](#)). As the absolute value of z increases, so does the distance from the camera to the target. To determine the approximate accuracy of these values, check [x, y, z]_accuracy. The units of these measures are in inches.

y

```
public double y
```

x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera. y will be positive when the target appears to be above of the center of the camera. z will always be negative (see [Wikipedia: Right-hand rule](#)). As the absolute value of z increases, so does the distance from the camera to the target. To determine the approximate accuracy of these values, check [x, y, z]_accuracy. The units of these measures are in inches.

z

```
public double z
```

x, y, and z represent the 3-d position of the target x will be positive when the target appears to be right of the center of the camera. y will be positive when the target appears to be above of the center of the camera. z will always be negative (see [Wikipedia: Right-hand rule](#)). As the absolute value of z increases, so does the distance from the camera to the target. To determine the approximate accuracy of these values, check [x, y, z]_accuracy. The units of these measures are in inches.

x_uncertainty

```
public double x_uncertainty
```

These are the uncertainties of the x, y, and z positions of the target. These are interpreted as pluses and minuses to the x, y, and z values. Again, these are in inches.

y_uncertainty

```
public double y_uncertainty
```

These are the uncertainties of the x, y, and z positions of the target. These are interpreted as pluses and minuses to the x, y, and z values. Again, these are in inches.

z_uncertainty

```
public double z_uncertainty
```

These are the uncertainties of the x, y, and z positions of the target. These are interpreted as pluses and minuses to the x, y, and z values. Again, these are in inches.

Constructor Detail

Target

```
public Target(double x,
              double y,
              double z,
              double angle)
```

Parameters:

- x -
- y -
- z -
- angle -

Target

```
public Target(double x,
              double y,
              double z,
              double x_uncertainty,
              double y_uncertainty,
              double z_uncertainty,
              double angle,
              double angle_uncertainty)
```

Parameters:

- x -
- y -
- z -
- x_uncertainty -
- y_uncertainty -
- z_uncertainty -
- angle -
- angle_uncertainty -

Target

```
public Target(Point3d point,
              double angle)
```

Parameters:

- point -
- angle -

Target

```
public Target()
```

Method Detail

toString

```
public String toString()
```

Overrides:

- toString in class `Object`

