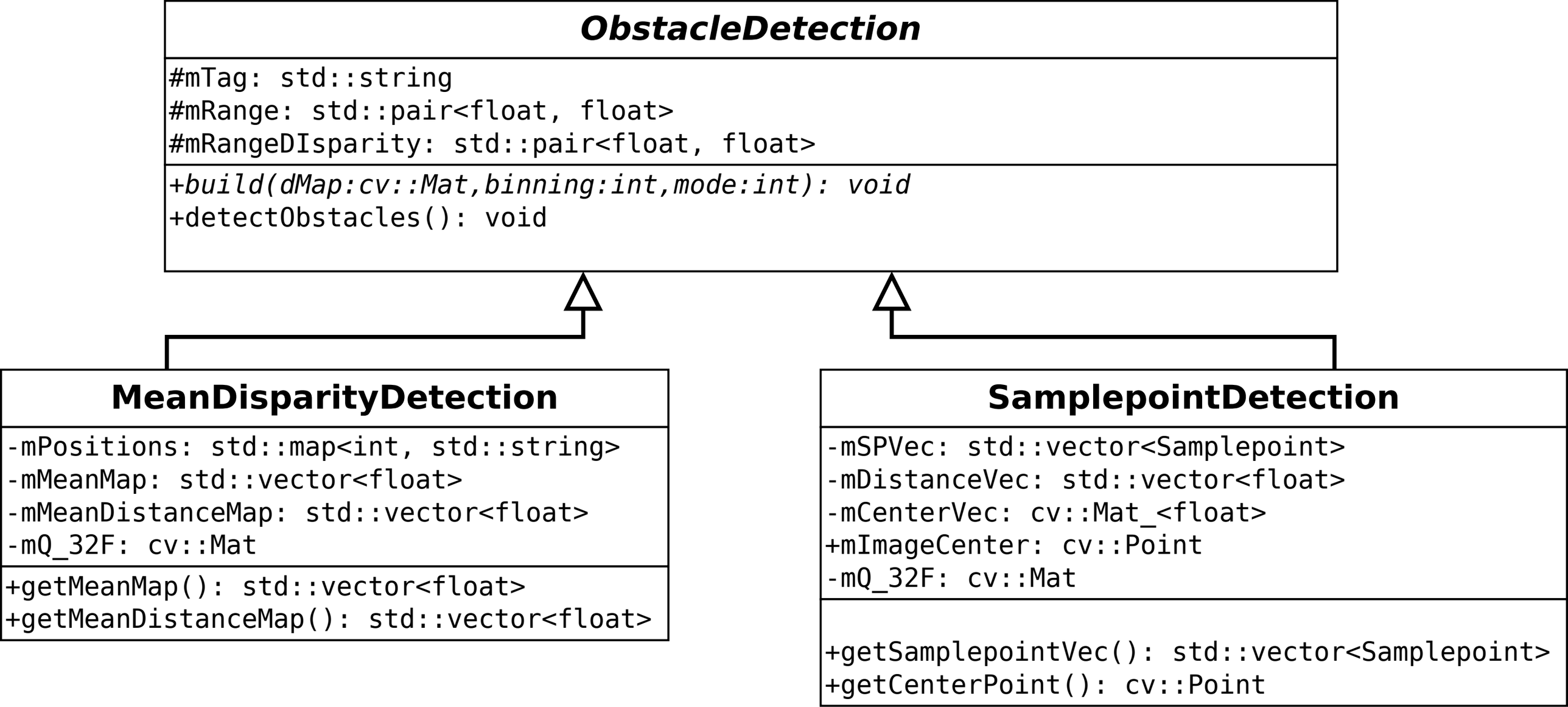
ObstacleDetection
#mTag: std::string
#mRange: std::pair<float, float>
#mRangeDIsparity: std::pair<float, float>
+build(dMap:cv::Mat,binning:int,mode:int): void
+detectObstacles(): void
MeanDisparityDetection
-mPositions: std::map<int, std::string>
-mMeanMap: std::vector<float>
-mMeanDistanceMap: std::vector<float>
-mQ_32F: cv::Mat
+getMeanMap(): std::vector<float>
+getMeanDistanceMap(): std::vector<float>
SamplepointDetection
-mSPVec: std::vector<Samplepoint>
-mDistanceVec: std::vector<float>
-mCenterVec: cv::Mat_<float>
+mImageCenter: cv::Point
-mQ_32F: cv::Mat
+getSamplepointVec(): std::vector<Samplepoint>
+getCenterPoint(): cv::Point