OpenCV Learning Notes

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# 1. Introduction

reference book:

Learning OpenCV (Computer Vision in C++ with the OpenCV Library)

Get OpenCV source code:

git clone <https://github.com/Itseez/opencv.git>

# 2. Introduction to OpenCV 2.x

tip: OpenCV function live with namespace called cv.

## (1) Read Image and Show In a Window:

Mat img = **imread**( argv[1], -1 );

if( img.empty() ) return -1;

**namedWindow**( "Example2", WINDOW\_AUTOSIZE );

**imshow**( "Example2", img );

waitKey( 0 );

**destroyWindow**( "Example2" );

## (2) Read Video and Display In a Window:

cv::namedWindow( "Example3", cv::WINDOW\_AUTOSIZE );

cv::**VideoCapture** cap;

cap.open( string(argv[1]) );

**cv::Mat frame**;

while( 1 ) {

**cap >> frame**;

if( !frame.data ) break; // Ran out of film

cv::imshow( "Example3", frame );

if( cv::waitKey(33) >= 0 ) break;

}

get video properties:

int frame\_numbers = (int) g\_cap.get(cv::CAP\_PROP\_FRAME\_COUNT);

int frame\_width = (int) g\_cap.get(cv::CAP\_PROP\_FRAME\_WIDTH);

int frame\_height = (int) g\_cap.get(cv::CAP\_PROP\_FRAME\_HEIGHT);

## (3) Process Image Example:

Gaussian Blur One Image

cv::Mat out;

// Do the smoothing

// Could use GaussianBlur(), blur(), medianBlur() or bilateralFilter().

cv::**GaussianBlur**(frame, out, cv::Size(5, 5), 3, 3);

cv::**GaussianBlur**(out, out, cv::Size(5, 5), 3, 3);

cv::imshow("Example2\_4", out);

Gaussian Blur and Downsample:

cv::pyrDown( img, img2);

Canny Edge Detector:

cv::Canny( img\_gry, img\_cny, 10, 100, 3, true );

Access several pixel / modify pixel:

cv::Vec3b intensity = frame.at< cv::Vec3b >(y, x);

uchar blue = intensity.val[0]; // We could write img\_rgb.at< cv::Vec3b >(x,y)[0]

uchar green = intensity.val[1];

uchar red = intensity.val[2];

# 3. Getting to Know OpenCV

## (1) Overview of Basic Type

a. Point

two kinds of point: two dimensional and three dimensional

cv::Point2i

cv::Point3i

dot product and cross product:

cv::Point3i p0(1, 2, 3);

cv::Point3i p1(4, 5, 6);

float x = p0.dot(p1);

cv::Point3i cy(p0.cross(p1));

### b.Scalar

The class cv::Scalar is really a four-dimensional point class.

### c. Size

The size classes are, in practice, similar to the corresponding point classes, and can be cast to and from

them. The primary difference between the two is that the point class’ data members are named x and y,

while the corresponding data members in the size classes are named width and height

Value constructors cv::Size2f sz( w, h );

Member access sz.width; sz.height;

Compute area sz.area();

### d. Rect

The rectangle classes include the members x and y of the point class (representing the upper-left corner of the rectangle) and the members width and height of the size class (representing the extent of the rectangle). The rectangle classes, however, do not inherit from the point or size classes, and so in general they do not inherit operators from them.

Value constructors cv::Rect( x, y, w, h );

Construct from origin and size cv::Rect( p, sz );

Construct from two corners cv::Rect( p1, p2 );

Member access r.x; r.y; r.width; r.height;

Compute area r.area();

Extract upper-left corner r.tl();

Extract lower-right corner r.lr;

Determine if point p is inside of rectangle r r.contains( p );

e. RotatedRect

The cv::RotatedRect class is one of the few classes in the C++ OpenCV interface that is not a

template underneath. It is a container, which holds a cv::Point2f called center, a cv::Size2f

called size, and one additional float called angle, with the latter representing the rotation of the

rectangle around center. One very important difference between cv::RotatedRect and cv::Rect

is the convention that a cv::RotatedRect is located in “space” relative to its center, while the

cv::Rect is located relative to its upper-left corner.

### e. The Fixed Matrix Classes

The fixed matrix classes are for matrices whose dimensions are known at compile time (hence “fixed”). As

a result, all memory for their data is allocated on the stack, which means that they allocate and clean up

quickly. Operations on them are fast and there are specially optimized implementations for small matrices

(2*-by-*2, 3*-by-*3, etc.). The