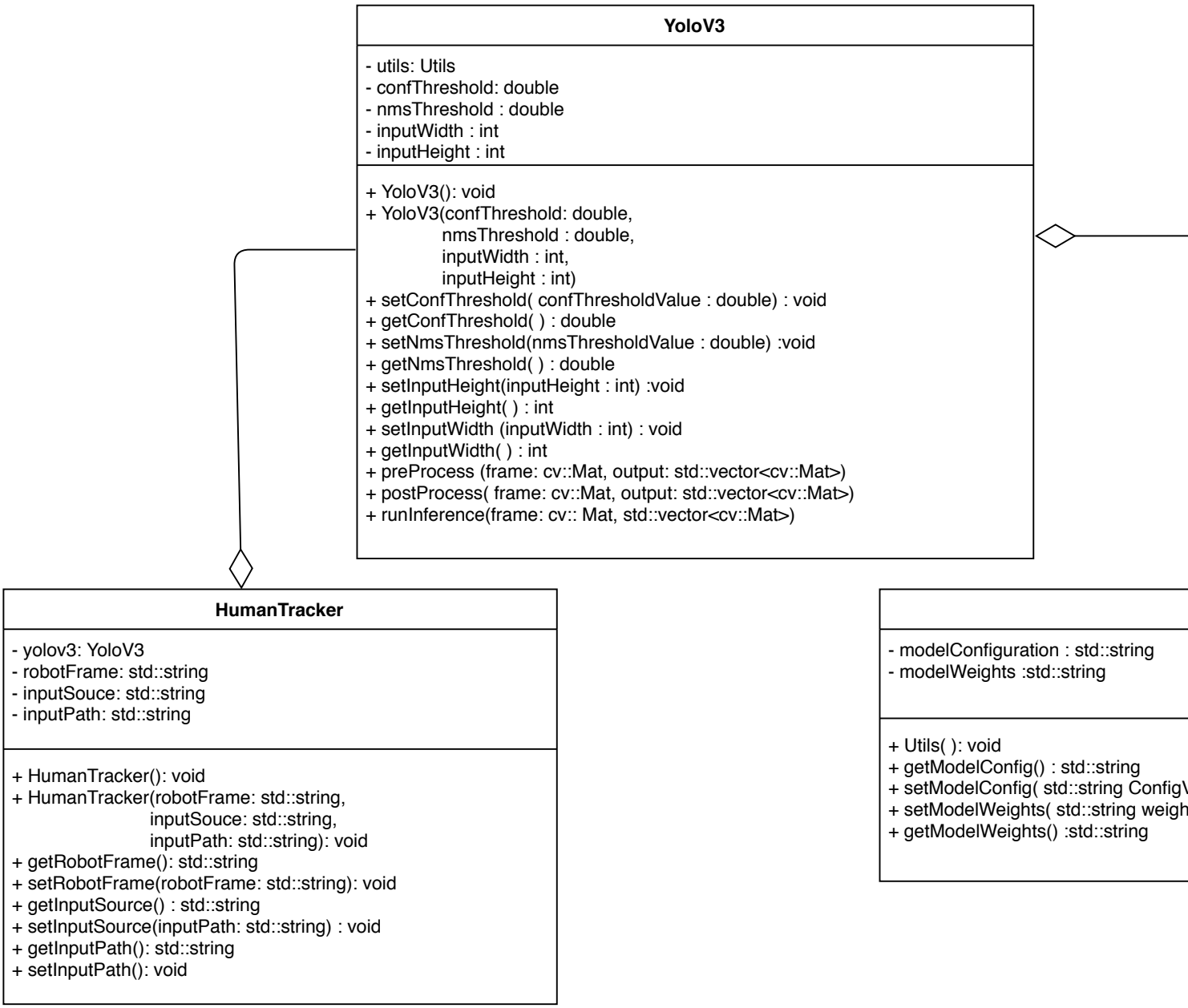
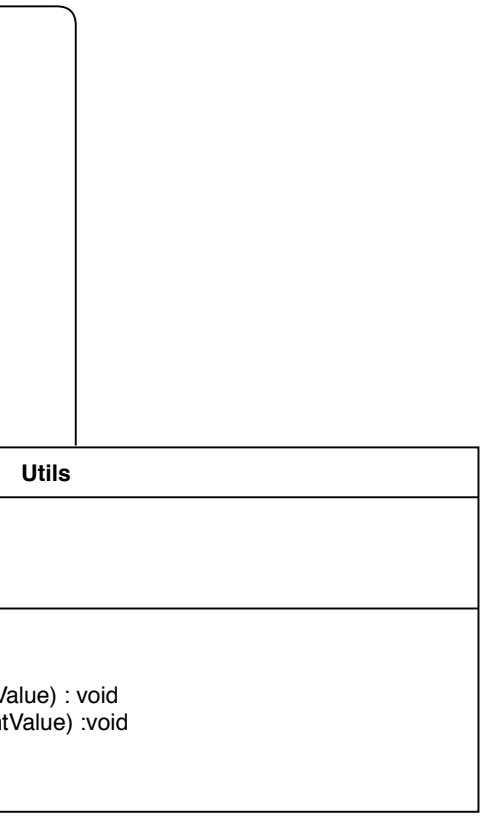

YoloV3
- utils: Utils
- confThreshold: double
- nmsThreshold : double
- inputWidth : int
- inputHeight : int
+ YoloV3(): void
+ YoloV3(confThreshold: double,
nmsThreshold : double,
inputWidth : int,
inputHeight : int)
+ setConfThreshold(confThresholdValue : double) : void
+ getConfThreshold( ) : double
+ setNmsThreshold(nmsThresholdValue : double) :void
+ getNmsThreshold( ) : double
+ setInputHeight(inputHeight : int) :void
+ getInputHeight( ) : int
+ setInputWidth (inputWidth : int) : void
+ getInputWidth( ) : int
+ preProcess (frame: cv::Mat, output: std::vector<cv::Mat>)
+ postProcess(frame: cv::Mat, output: std::vector<cv::Mat>)
+ runInference(frame: cv:: Mat, std::vector<cv::Mat>)
HumanTracker
- yolov3: YoloV3
- robotFrame: std::string
- inputSouce: std::string
- inputPath: std::string
+ HumanTracker(): void
+ HumanTracker(robotFrame: std::string,
inputSouce: std::string,
inputPath: std::string): void
+ getRobotFrame(): std::string
+ setRobotFrame(robotFrame: std::string): void
+ getInputSource() : std::string
+ setInputSource(inputPath: std::string) : void
+ getInputPath(): std::string
+ setInputPath(): void
- modelConfiguration : std::string
- modelWeights :std::string
+ Utils( ): void
+ getModelConfig() : std::string
+ setModelConfig(std::string Config
+ setModelWeights(std::string weigh
+ getModelWeights() :std::string


Utils
Value) : void
tValue) :void