

laneDetector
<ul style="list-style-type: none">- orgImg: Mat- undImg: Mat- pplmg: Mat- grayImg: Mat- edgeImg: Mat- roiImg: Mat- cameraMatrix: Mat- distCoeff: Mat- lines: vector<vector<double>>- leftLines: vector<vector<double>>- rightLines: vector<vector<double>>- leftLane: vector<double>- rightLane: vector<double>- vanishingPt: vector<double>
<ul style="list-style-type: none">+ undistortImage(Mat orgImg, Mat cameraMatrix, Mat distCoeff): Mat+ preprocessImage(Mat undImg): Mat+ grayImage(Mat pplmg): Mat+ detectEdges(Mat grayImg): Mat+ extractROI(Mat edgeImg): Mat+ perspectiveTransform(Mat roiImg): Mat+ detectLanes(Mat roiImg): vector<vector<double>>+ sortLanes(vector<vector<double>>): void+ computeFitLine(vector<vector<double>> leftLines, vector<vector<double>> rightLines): void+ projectNormalView(vector<double> leftLane, vector<double> rightLane): Mat+ augmentLane(vector<double> leftLane, vector<double> rightLane): Mat+ predictTurn(vector<double> leftLane, vector<double> rightLane): void