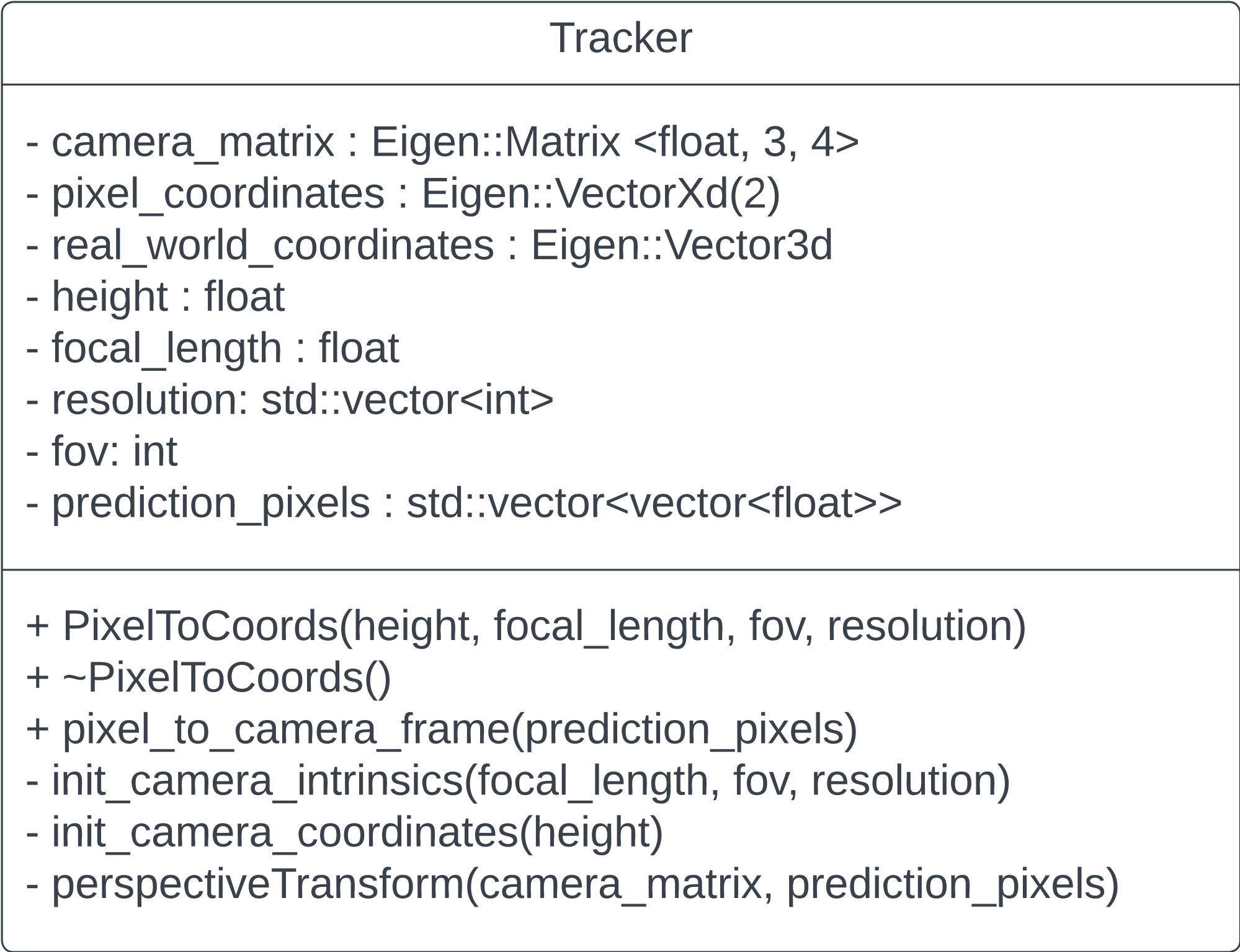
Tracker
- camera_matrix : Eigen::Matrix <float, 3, 4>
- pixel_coordinates : Eigen::VectorXd(2)
- real_world_coordinates : Eigen::Vector3d
- height : float
- focal_length : float
- resolution: std::vector<int>
- fov: int
- prediction_pixels : std::vector<vector<float>>
+ PixelToCoords(height, focal_length, fov, resolution)
+ ~PixelToCoords()
+ pixel_to_camera_frame(prediction_pixels)
- init_camera_intrinsics(focal_length, fov, resolution)
- init_camera_coordinates(height)
- perspectiveTransform(camera_matrix, prediction_pixels)