

iri_people_tracking_mht (ROS package) [{#mainpage}](#)

Description

ROS wrapper of the [people_tracking_mht](#) C++ driver library, located within this package.

Dependencies

This node has the following dependencies:

- ROS
 - tf
 - nav_msgs
 - visualization_msgs
- IRI-ROS
 - [iri_base_algorithm](#)
 - [iri_perception_msgs](#)
- IRI
 - [iriutils](#)
 - [people_tracking_mht](#)

Install

Install its dependencies:

- ROS dependencies can be installed with `sudo apt install ros- $\$ROS_DISTR0$ -dependency-name`
- IRI-ROS dependencies normally need to be cloned and compiled in an active ROS workspace, as explained in their README file.
- IRI dependencies are normally need to be cloned, compiled and installed, as explained in their README file.

This package, as well as all IRI dependencies, can be installed by cloning the repository inside the active workspace:

```
roscd
cd ../src
git clone https://gitlab.iri.upc.edu/labrobotica/ros/perception/iri_people_tracking_mht.
```

However, this package is normally used as part of a wider installation (i.e. a robot, an experiment or a demonstration) which will normally include a complete `roinstall` file to be used with the [wstool](#) tool.

How to use it

Example of use playing a rosbag, running the node, along with other nodes (laser_people_detection, laser_people_map_filter, map_server, static_transform_publisher) and showing tracked person on Rviz and reconfigurable parameters on rqt_reconfigure.

```
roslaunch iri_people_tracking_mht test.launch
```

