Block Abnormal Height Sorting

Before starting this function, you need to close the large program and APP processes. If you need to restart the large program and APP later, start them from the terminal:

```
bash ~/dofbot_pro/APP_DOFBOT_PRO/start_app.sh
```

1. Function Description

After the program starts, place color blocks of the same color. The robotic arm will perform color recognition based on the set HSV values. After pressing the spacebar, the robotic arm will lower the gripper to grasp color blocks that exceed the height threshold; after placement is complete, it returns to the recognition posture.

2. Startup and Operation

2.1. Startup Commands

Enter the following commands in the terminal to start:

```
#Start camera:
ros2 launch orbbec_camera dabai_dcw2.launch.py
#Start underlying control:
ros2 run dofbot_pro_driver arm_driver
#Start inverse kinematics program:
ros2 run dofbot_pro_info kinemarics_dofbot
#Start color recognition program:
ros2 run dofbot_pro_color AnomalyHeightRemoval
#Start robotic arm grasping program:
ros2 run dofbot_pro_driver grasp
```

2.2. Operation Process

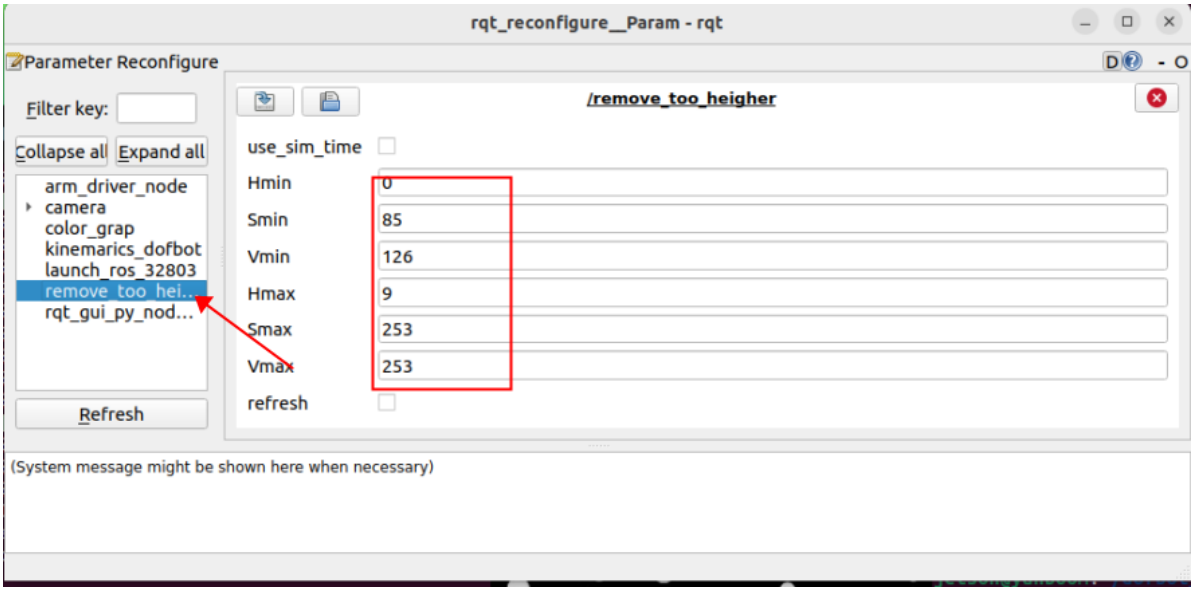
After starting in the terminal, place color blocks of different colors. The camera captures the image. Process the image with the following keys:

- [i] or [I]: Enter color recognition mode, directly load the HSV values calibrated by the program last time for recognition;
- [r] or [R]: Reset program parameters, enter color selection mode, use the mouse to select a certain area of the color block, obtain the HSV values of this area, release the mouse to enter color recognition mode
- Spacebar: Start grasping color blocks with abnormal height

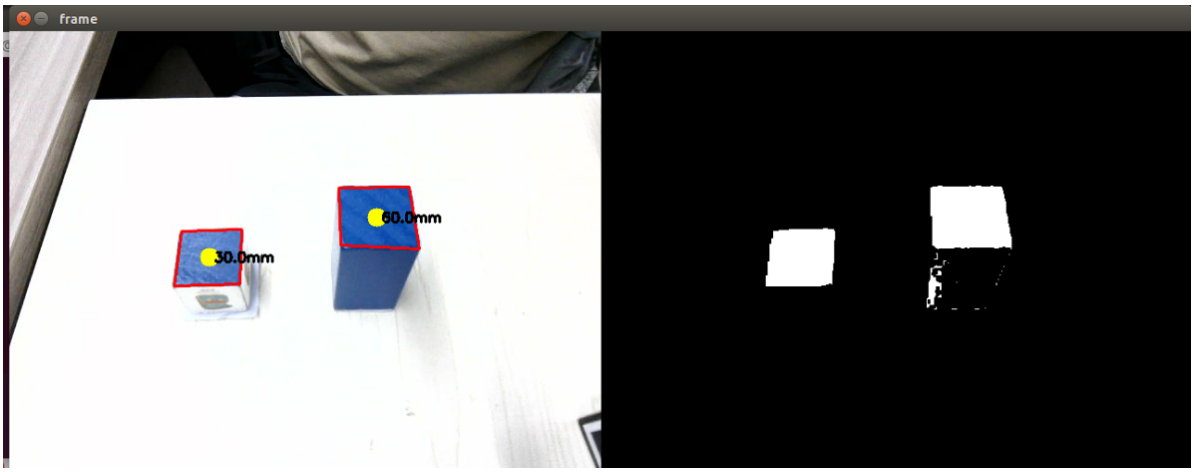
After entering color recognition mode, if the current HSV values still cannot filter out other colors, you can fine-tune the HSV values through the dynamic parameter tuner. Enter the following command in the terminal to start the dynamic parameter tuner:

```
rosrun rqt_reconfigure rqt_reconfigure
```

You can modify the HSV values through sliders

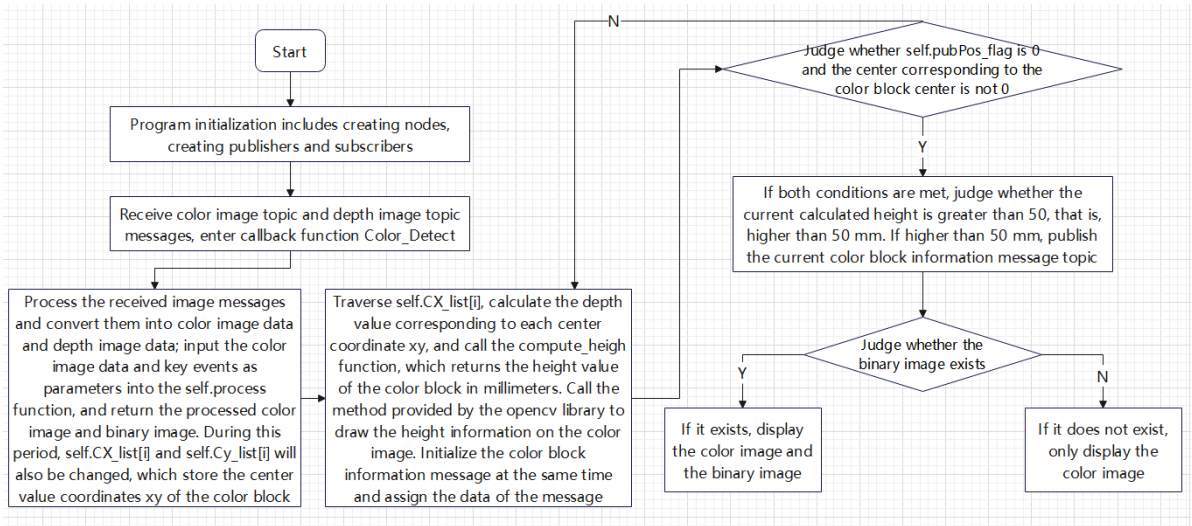


As shown in the figure below, when the left image (binary) only displays the uniquely recognized color, click the color image frame and press the spacebar, the robotic arm will lower the gripper to grasp color blocks with abnormal height.



3. Program Flowchart

AnomalyHeightRemoval.py



4. Core Code Analysis

4.1. AnomalyHeightRemoval.py

Code path:

```
/home/jetson/dofbot_pro_ws/src/dofbot_pro_color/dofbot_pro_color/AnomalyHeightRemoval.py
```

Import necessary libraries

```
import cv2
import rclpy
from rclpy.node import Node
import numpy as np
from message_filters import ApproximateTimeSynchronizer, Subscriber
from sensor_msgs.msg import Image
from std_msgs.msg import Float32, Bool
from cv_bridge import CvBridge
import cv2 as cv

import time
import math
import os
encoding = ['16UC1', '32FC1']
import tf_transformations as tf
import transforms3d as tfs

from dofbot_pro_color.height_measurement import *
from dofbot_pro_interface.msg import *
```

Program parameter initialization, create publishers, subscribers

```
def __init__(self):
    super().__init__('remove_too_heigher')
    self.declare_param()
    #Robotic arm color block recognition posture
    self.init_joints = [90.0, 120, 0.0, 0.0, 90, 90]
    #Create publisher for color block information
    self.pub_ColorInfo = self.create_publisher(AprilTagInfo, "PosInfo", 1)
    self.pubPoint = self.create_publisher(ArmJoint, "TargetAngle", 1)
    #Create subscriber for gesture recognition results
    self.grasp_status_sub = self.create_subscription(Bool, 'grasp_done',
self.GraspStatusCallback, 1)
    #Create two subscribers, subscribe to color image topic and depth image
topic
    self.depth_image_sub  = Subscriber(self, Image, "/camera/color/image_raw",
qos_profile=1)
    self.rgb_image_sub = Subscriber(self, Image, "/camera/depth/image_raw",
qos_profile=1)
    #Time-synchronize color and depth image subscription messages
     self.TimeSynchronizer = ApproximateTimeSynchronizer([self.depth_image_sub,
self.rgb_image_sub],queue_size=10,slop=0.5)
     self.TimeSynchronizer.registerCallback(self.Color_Detect)
    #Save xy coordinates of color block center
    self.y = 0 #320
```

```
    self.x = 0 #240
    #Create bridges for converting color and depth image topic message data to
image data
    self.rgb_bridge = CvBridge()
    self.depth_bridge = CvBridge()
    #Store x and y value lists of recognized color block center values
    self.CX_list = []
    self.CY_list = []
    #Initialize region coordinates
    self.Roi_init = ()
    #Initialize HSV values
    self.hsv_range = ()
    #Initialize recognized color block information, here representing color block
center x coordinate, center y coordinate and minimum enclosing circle radius r
    self.circle = (0, 0, 0)
    #Dynamic parameter adjustment flag, True means perform dynamic parameter
adjustment
    self.dyn_update = True
    #Mouse selection flag
    self.select_flags = False
    self.gTracker_state = False
    self.windows_name = 'frame'
    #Initialize state value
    self.Track_state = 'init'
    #Create color detection object
    self.color = color_detect()
    #Initialize row and column coordinates of region coordinates
    self.cols, self.rows = 0, 0
    #Initialize mouse selected xy coordinates
    self.Mouse_XY = (0, 0)
    #Default HSV threshold file path, this file stores the last saved HSV values
    self.hsv_text = rospkg.RosPack().get_path("dofbot_pro_color") +
"/scripts/colorHSV.text"
    #Load color HSV configuration file, configure dynamic parameter tuner
    Server(ColorHSVConfig, self.dynamic_reconfigure_callback)
    self.dyn_client = Client(nodeName, timeout=60)
    exit_code = os.system('rosservice call /camera/set_color_exposure  50')
    #Current recognized color block center xy coordinates and color block minimum
enclosing circle radius
    self.cx = 0
    self.cy = 0
    self.circle_r = 0
    #Flag for publishing color block information, True means color block
information can be published
    self.pubPos_flag = False
    #Initialize color block height value
    self.heigh = 0.0
    #Current robotic arm end position and pose
    self.CurEndPos = [-0.006,0.116261662208,0.0911289015753,-1.04719,-0.0,0.0]
    #Camera built-in parameters
    self.camera_info_K = [477.57421875, 0.0, 319.3820495605469, 0.0,
477.55718994140625, 238.64108276367188, 0.0, 0.0, 1.0]
    #Rotation transformation matrix between robotic arm end and camera, describes
relative position and pose between the two
    self.EndToCamMat =
np.array([[1.00000000e+00,0.00000000e+00,0.00000000e+00,0.00000000e+00],
                                  [0.00000000e+00,7.96326711e-04,9.99999683e-
01,-9.90000000e-02],
```

```
                                [0.00000000e+00,-9.99999683e-01,7.96326711e-
04,4.90000000e-02],

[0.00000000e+00,0.00000000e+00,0.00000000e+00,1.00000000e+00]])
```

Main image processing function Color_Detect

```
def Color_Detect(self,color_frame,depth_frame):
    #rgb_image
    #Receive color image topic message, convert message data to image data
    rgb_image = self.rgb_bridge.imgmsg_to_cv2(color_frame,'bgr8')
    result_image = np.copy(rgb_image)
    #depth_image
    #Receive depth image topic message, convert message data to image data
    depth_image = self.depth_bridge.imgmsg_to_cv2(depth_frame, encoding[1])
    frame = cv.resize(depth_image, (640, 480))
    depth_image_info = frame.astype(np.float32)
    action = cv.waitKey(10) & 0xFF
    result_image = cv.resize(result_image, (640, 480))
    #Pass the obtained color image as parameter to process, and also pass
keyboard event action
    result_frame, binary = self.process(result_image,action)
    print("self.CX_list: ",self.CX_list)
    print("self.CY_list: ",self.CY_list)
    #Traverse self.CX_list
    for i in range(len(self.CX_list)):
        cx = self.CX_list[i]
        cy = self.CY_list[i]
        #Calculate depth value corresponding to center coordinates
        dist = depth_image_info[cy,cx]/1000
        #Pass the obtained color block center value coordinates and center point
corresponding depth information to compute_heigh function, calculate color block
height value and perform method, convert unit from meters to millimeters
        heigh = round(self.compute_heigh(cx,cy,dist),2) *1000
        heigh_msg = str(heigh) + 'mm'
        #Call opencv's putText function to draw height information on color
image
        cv.putText(result_frame, heigh_msg, (cx+5, cy+5),
cv.FONT_HERSHEY_SIMPLEX, 0.5, (0, 0, 0), 2)
        #Create color block information message and assign values
        pos = AprilTagInfo()
        pos.x = cx
        pos.y = cy
        pos.z = dist
        #Determine if self.pubPos_flag is 0 and color block center corresponding
center is not 0
        if self.pubPos_flag == True and pos.z!=0:
            if i==len(self.CX_list) :
                self.pubPos_flag = False
            #If calculated value is greater than 50, that is height is higher
than 5 centimeters, then publish color block information topic message
            if heigh>50:
                self.pub_ColorInfo.publish(pos)
                self.pubPos_flag = False
    if len(binary) != 0: cv.imshow(self.windows_name, ManyImgs(1,
([result_frame, binary])))
    else:
```

```
        cv.imshow(self.windows_name, result_frame)
```

Image processing function self.process

```
def process(self, rgb_img, action):
    rgb_img = cv.resize(rgb_img, (640, 480))
    binary = []
    #Determine key press event, when spacebar is pressed, change information
publishing flag status, self.pubPos_flag True means information topic can be
published
    if action == 32: self.pubPos_flag = True
    #Determine key press event, when i or I is pressed, change state, switch to
recognition mode
    elif action == ord('i') or action == ord('I'): self.Track_state = "identify"
    #Determine key press event, when r or R is pressed, reset all parameters,
enter color selection mode
    elif action == ord('r') or action == ord('R'): self.Reset()
    #Determine state value, if it's init, it means initial state value, at this
time mouse can be used to select region
    if self.Track_state == 'init':
        cv.namedWindow(self.windows_name, cv.WINDOW_AUTOSIZE)
        #Select a region's color within the specified window
        cv.setMouseCallback(self.windows_name, self.onMouse, 0)
        #Determine color selection flag, true means color can be selected
        if self.select_flags == True:
            cv.line(rgb_img, self.cols, self.rows, (255, 0, 0), 2)
            cv.rectangle(rgb_img, self.cols, self.rows, (0, 255, 0), 2)
            #Determine if selected region exists
            if self.Roi_init[0] != self.Roi_init[2] and self.Roi_init[1] !=
self.Roi_init[3]:
                #Call Roi_hsv function in created color detection object
self.color, returns processed color image and HSV values
                rgb_img, self.hsv_range = self.color.Roi_hsv(rgb_img,
self.Roi_init)
                self.gTracker_state = True
                self.dyn_update = True
            else: self.Track_state = 'init'
    #Determine state value, if it's "identify", it means color recognition can be
performed
    elif self.Track_state == "identify":
        #Determine if HSV threshold file exists, if exists read values inside
and assign to hsv_range
        if os.path.exists(self.hsv_text): self.hsv_range =
read_HSV(self.hsv_text)
        #If not exists, change state to init for color selection
        else: self.Track_state = 'init'
    if self.Track_state != 'init':
        #Determine length of self.hsv_range value, that is determine if this
value exists, when length is not 0, enter color detection function
        if len(self.hsv_range) != 0:
            rgb_img, binary, self.CX_list,self.CY_list =
self.color.ShapeRecognition(rgb_img, self.hsv_range)
            #Determine dynamic parameter update flag, True means hsv_text file
can be updated and values on parameter server can be modified
            if self.dyn_update == True:
                write_HSV(self.hsv_text, self.hsv_range)
```

```
                params = {'Hmin': self.hsv_range[0][0], 'Hmax':
self.hsv_range[1][0],
                          'Smin': self.hsv_range[0][1], 'Smax':
self.hsv_range[1][1],
                          'Vmin': self.hsv_range[0][2], 'Vmax':
self.hsv_range[1][2]}
                self.dyn_client.update_configuration(params)
                self.dyn_update = False
    return rgb_img, binary
```

4.2. grasp.py

You can refer to section 4.2 [grasp.py] in tutorial [12. 3D Sorting and Grasping Course\1. AprilTag ID sorting].