

5、ROS+OpenCV application

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5.1、Overview

5.2、Usage

5.2.1、Start up

5.2.2、Display method

5.2.3、Effect show

5.3、Node

5.3.1、Edge detection algorithm

5.3.2、Contour moment

5.3.3、Face recognition

5.1、Overview

wiki: http://wiki.ros.org/opencv_apps

Source code: [https://github.com/ros-perception/opencv_apps.git]

opencv_apps provides various nodes that run internally OpenCV's functionalities and publish the result as ROS topics. With opencv_apps, you can skip writing OpenCV application codes for a lot of its functionalities by simply running a launch file that corresponds to OpenCV's functionality you want.

Contents

1. Introduction, usage
2. Edge Detection Nodes
 1. edge_detection
 2. hough_lines
 3. hough_circles
3. Structural Analysis Nodes
 1. find_contours
 2. convex_hull
 3. general_contours
 4. contour_moments
4. People/Face Detection Nodes
 1. face_detection
 2. face_recognition
 3. people_detect
5. Motion Analysis Nodes
 1. goodfeature_track
 2. camshift
 3. fback_flow
 4. lk_flow
 5. phase_corr
 6. simple_flow
6. Object Segmentation Nodes
 1. segment_objects
 2. watershed_segmentation
7. Image Filter Nodes
 1. rgb_color_filter
 2. hls_color_filter
 3. hsv_color_filter
8. Simple Image Processing Nodes
 1. adding_images

5.2、 Usage

5.2.1、 Start up

Step 1: Start the camera

```
roslaunch transbot_visual opencv_apps.launch camDevice:=USBCam
```

Step 2: Start the function of Opencv_apps

```
roslaunch opencv_apps face_recognition.launch           # Face recognition
roslaunch opencv_apps corner_harris.launch             # harris corner
detection
roslaunch opencv_apps camshift.launch                   # Target tracking
algorithm
roslaunch opencv_apps contour_moments.launch            # Contour moment
roslaunch opencv_apps convex_hull.launch                # Polygon outline
roslaunch opencv_apps discrete_fourier_transform.launch # Discrete Fourier
Transform Algorithm
roslaunch opencv_apps edge_detection.launch             # Edge detection
algorithm
roslaunch opencv_apps face_detection.launch             # Face detection
algorithm
roslaunch opencv_apps fback_flow.launch                 # Optical flow
detection algorithm
```

roslaunch opencv_apps find_contours.launch	# Contour detection
roslaunch opencv_apps general_contours.launch	# General contour
detection	
roslaunch opencv_apps goodfeature_track.launch	# Feature point
tracking	
roslaunch opencv_apps hls_color_filter.launch	# HLS color filter
roslaunch opencv_apps hough_circles.launch	# Hough circle
detection	
roslaunch opencv_apps hough_lines.launch	# Hough line detection
roslaunch opencv_apps hsv_color_filter.launch	# HSV color filter
roslaunch opencv_apps lk_flow.launch	# LK optical flow
algorithm	
roslaunch opencv_apps people_detect.launch	# Human detection
algorithm	
roslaunch opencv_apps phase_corr.launch	# Phase correlation
displacement detection	
roslaunch opencv_apps pyramids.launch	# Image pyramid
sampling algorithm	
roslaunch opencv_apps rgb_color_filter.launch	# RGB color filtering
roslaunch opencv_apps segment_objects.launch	# Clear background
detection algorithm	
roslaunch opencv_apps simple_flow.launch	# Simplified optical
flow algorithm	
roslaunch opencv_apps smoothing.launch	# Simple filter
roslaunch opencv_apps threshold.launch	# Threshold image
processing	
roslaunch opencv_apps watershed_segmentation.launch	# Watershed
segmentation algorithm	

Almost every function case will have a parameter [debug_view], boolean type, whether to use OpenCV to display the picture, it is displayed by default.

If you don't need to display it, set it to [False], for example

```
roslaunch opencv_apps contour_moments.launch debug_view:=False
```

5.2.2. Display method

- rqt_image_view

Enter the following command to select the corresponding topic

```
rqt_image_view
```

- opencv

The system displays it by default.

- Web view

(At the same LAN) Enter IP+port in the browser, for example:

```
192.168.2.102:8080
```

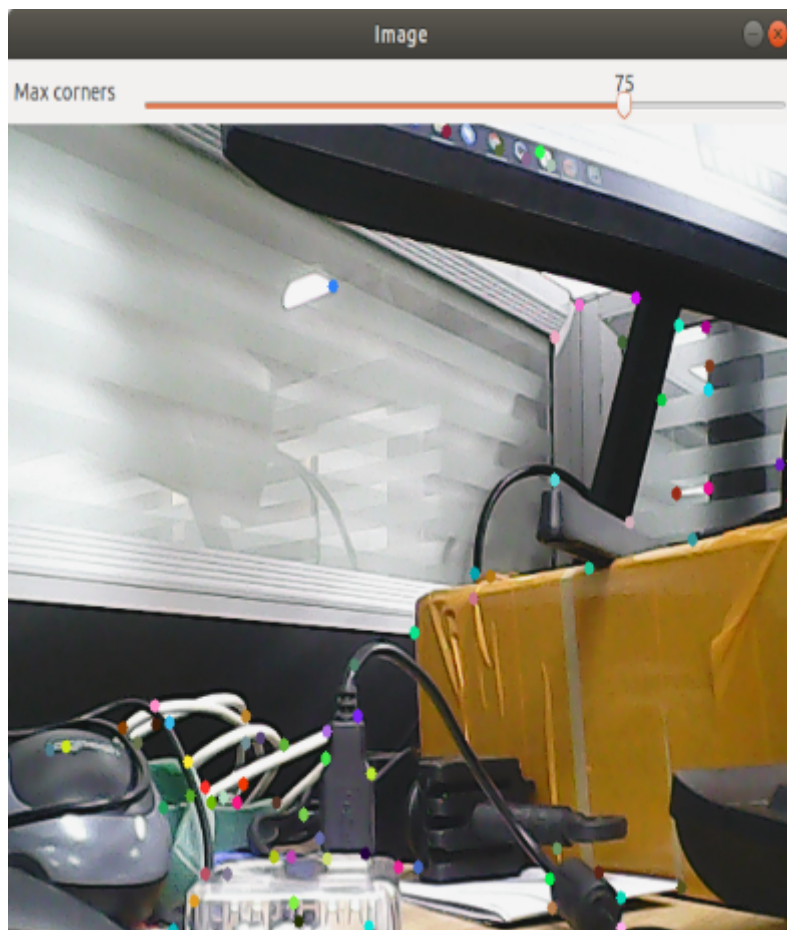
5.2.3, Effect show

- Optical flow detection algorithm

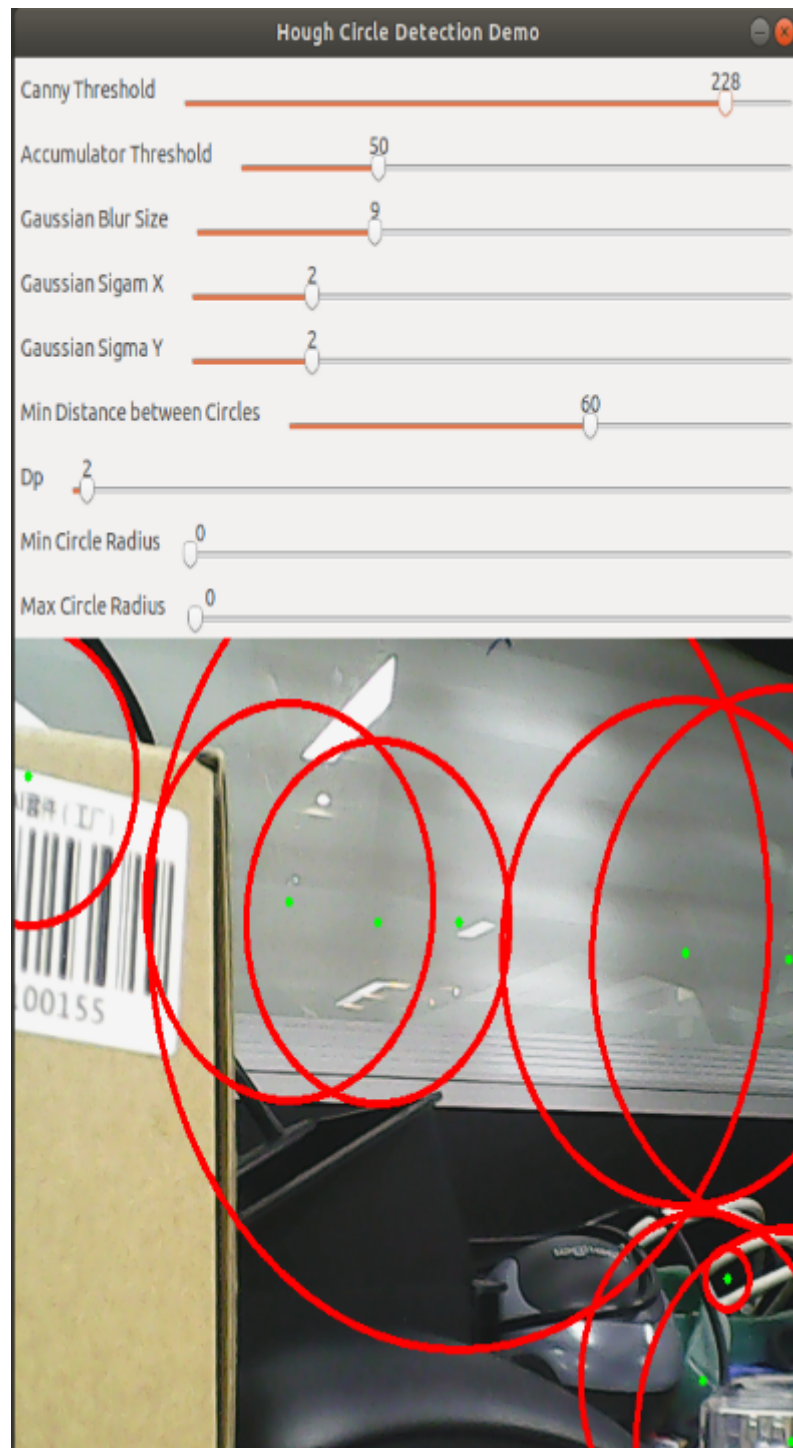
Move the screen and observe the phenomenon.



- Feature point tracking

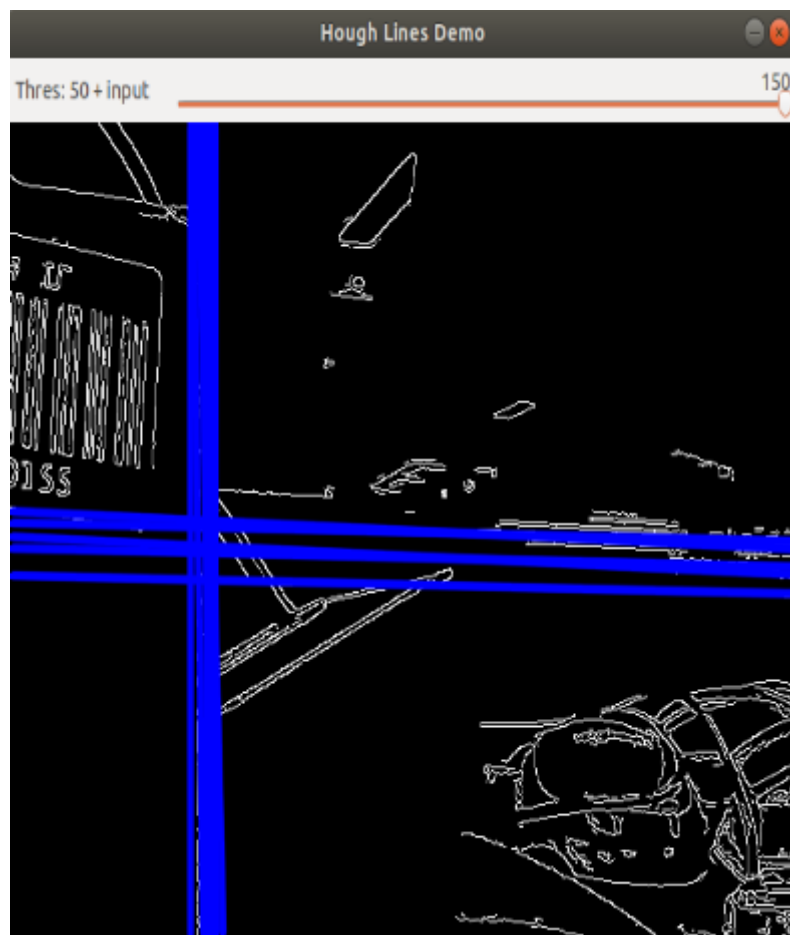


- Hough circle detection



- Hough line detection

The lower the threshold, the more lines there are, and the more easily the picture gets stuck.



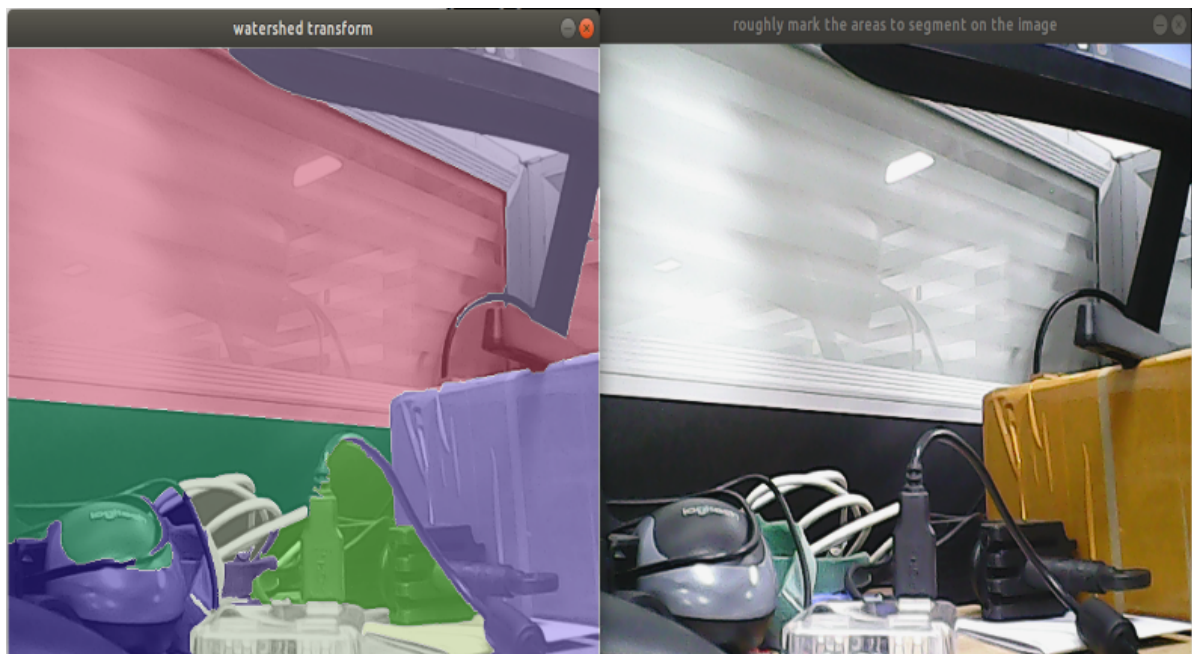
- Phase correlation displacement detection

The faster the camera moves, the larger the radius of the circle.



- Watershed segmentation algorithm

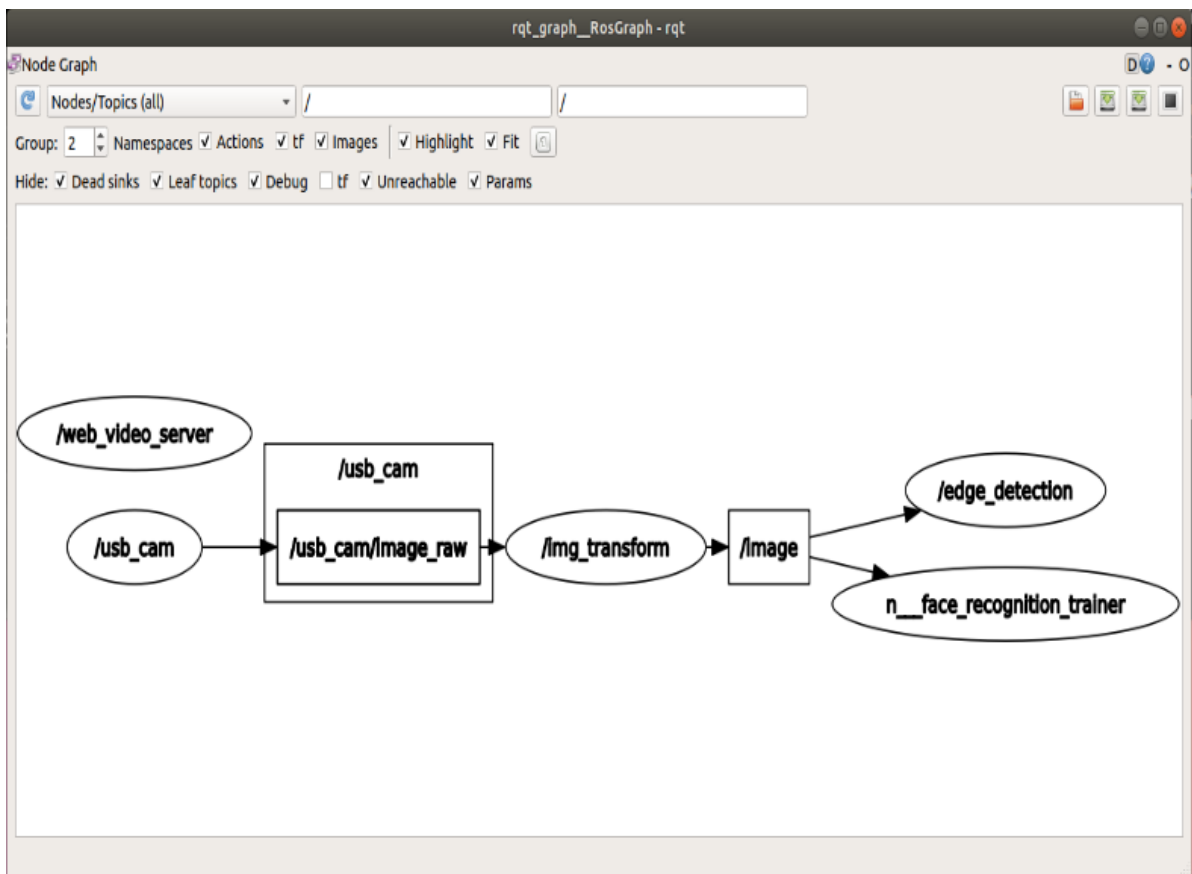
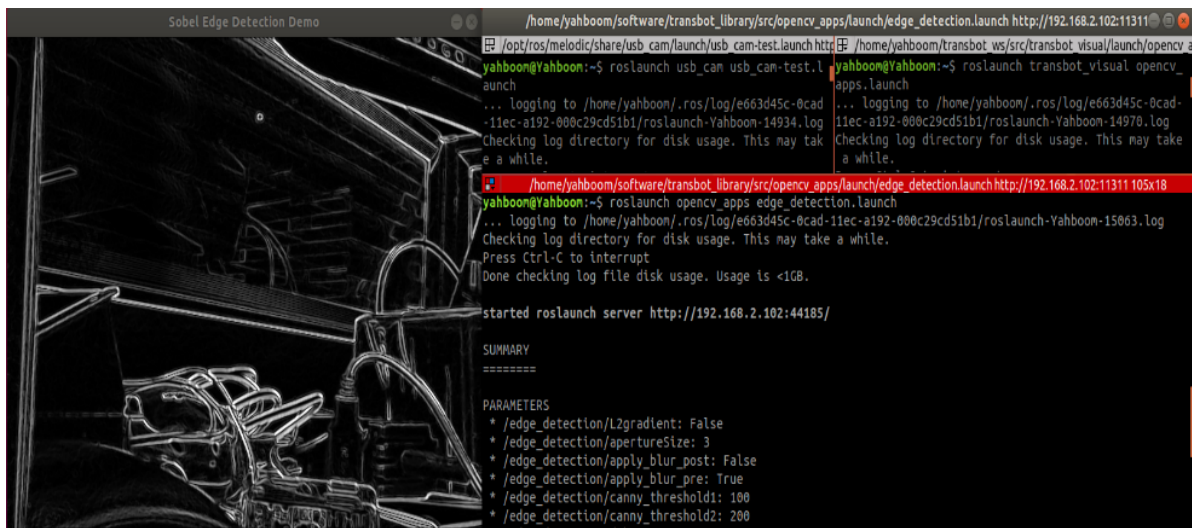
Use the mouse to select different objects, the system automatically distinguishes them.



5.3、Node

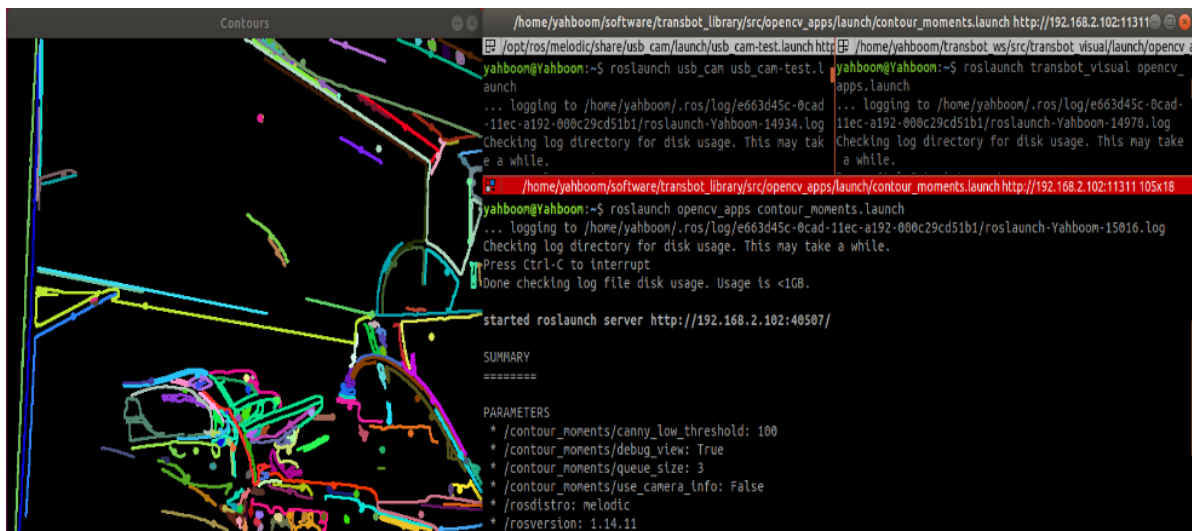
5.3.1、Edge detection algorithm

Parameter	Type	Default	Analyze
~use_camera_info	bool	true	Subscribe to the topic [camera_info] to get the default coordinate system ID, otherwise use the image information directly.
~debug_view	bool	false	Whether to create a window to display the node image
~edge_type	int	0	Specify the edge detection method: 0: Sobel operator, 1: Laplacian operator, 2: Canny edge detection
~canny_threshold1	int	100	Specify the second canny threshold
~canny_threshold2	int	200	Specify the first canny threshold
~apertureSize	int	3	The aperture size of the Sobel operator.
~apply_blur_pre	bool	True	Whether to apply blur() to the input image
~postBlurSize	double	3.2	Input image aperture size
~apply_blur_post	bool	False	Whether to apply GaussianBlur() to the input image
~L2gradient	bool	False	Parameters of canny
~queue_size	int	3	Queue size



5.3.2, Contour moment

Parameter	Type	Default	Analyze
<code>~use_camera_info</code>	bool	true	Subscribe to the topic [camera_info] to get the default coordinate system ID, otherwise use the image information directly.
<code>~debug_view</code>	bool	false	Whether to create a window to display the node image
<code>~canny_low_threshold</code>	int	0	Canny edge detection low threshold
<code>~queue_size</code>	int	3	Queue size



5.3.3、Face recognition

Parameter	Type	Default	Analyze
~approximate_sync	bool	false	Subscribe to the topic [camera_info] to get the default coordinate system ID, otherwise use the image information directly.
~queue_size	int	100	Queue size for subscribed topics
~model_method	string	"eigen"	Face recognition method: "eigen", "fisher" or "LBPH"
~use_saved_data	bool	true	Load training data from the ~data_dir path
~save_train_data	bool	true	Save the training data to the ~data_dir path for retraining
~data_dir	string	"~/opencv_apps/face_data"	保存训练数据路径
~face_model_width	int	190	Train the width of the face image
~face_model_height	int	90	Training the height of the face image
~face_padding	double	0.1	Fill ratio of each face
~model_num_components	int	0	The number of components of the face recognizer model (0 is considered unlimited)
~model_threshold	double	8000.0	Face recognition model threshold
~lbph_radius	int	1	Radius parameter (only applicable to LBPH method)

Parameter	Type	Default	Analyze
~lbph_neighbors	int	8	Neighborhood parameters (only applicable to LBPH method)
~lbph_grid_x	int	8	Grid x parameters (only applicable to LBPH method)
~lbph_grid_y	int	8	Grid y parameter (only applicable to LBPH method)
~queue_size	int	100	Image subscriber queue size

Steps:

1. First, after the colon in the figure below, enter the character's name: Yahboom
2. Confirm name: y
3. Then place the face in the center of the image and click OK.
4. Cycle to add a photo: y, click to confirm.
5. To end the picture collection, enter: n and click to confirm.
6. Close the launch file and restart.

If you need to enter the recognition, cycle 1~5 in turn until all the recognition personnel are entered, and then perform step 6.

```

face_recognition_trainer.py
Please input your name and press Enter: Yahboom
Your name is Yahboom. Correct? [y/n]: y
Please stand at the center of the camera and press Enter:
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: y
taking picture...
One more picture? [y/n]: 

```

Step 3: Ensure that the face can be recognized



Recognition effect

