

# Overall detection

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## 1、 Introduction

- MediaPipe is an open source data stream processing machine learning application development framework developed by Google. It is a graph-based data processing pipeline for building and using multiple forms of data sources, such as video, audio, sensor data, and any time series data. MediaPipe is cross-platform and can run on embedded platforms (Raspberry Pi, etc.), mobile devices (iOS and Android), workstations and servers, and supports mobile GPU acceleration.

MediaPipe provides cross-platform, customizable ML solutions for real-time and streaming media. The core framework of MediaPipe is implemented in C++ and provides support for languages such as Java and Objective C. The main concepts of MediaPipe include Packet, Stream, Calculator, Graph and Subgraph.

Features of MediaPipe :

- End-to-end acceleration: Built-in fast ML inference and processing accelerates even on commodity hardware.
- Build once, deploy anywhere: Unified solutions for Android, iOS, desktop/cloud, web and IoT.
- Ready-to-use solutions: Cutting-edge ML solutions that showcase the full capabilities of the framework.
- Free and open source: frameworks and solutions under Apache2.0, fully extensible and customizable.

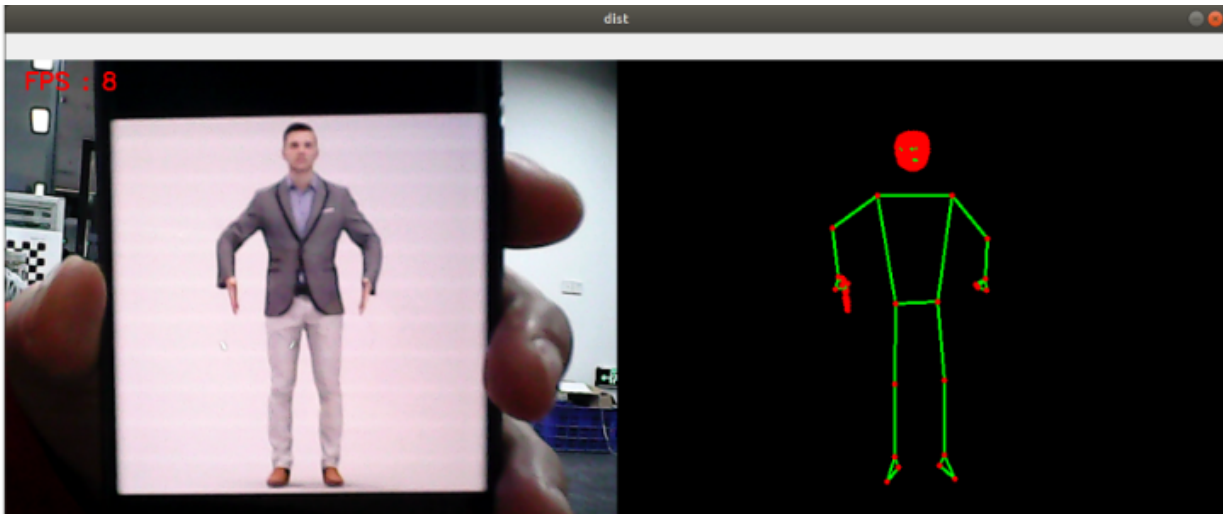
## 2、 Overall inspection

Combined with the contents of the previous two sections, this routine implements the function of detecting both palms and human bodies.

### 2.1、 run command

After entering the docker container, enter the following command in the terminal.

```
ros2 run yahboomcar_mediapipe 03_Holistic
```



## 2.2. Source code

After entering the docker container, the location of the source code of this function is as follows.

```
/root/yahboomcar_ws/src/yahboomcar_mediapipe/yahboomcar_mediapipe/03_Holistic .py
```

```
#!/usr/bin/env python3
# encoding: utf-8
import time
import rospy
import cv2 as cv
import numpy as np
import mediapipe as mp
from geometry_msgs.msg import Point
from yahboomcar_msgs.msg import PointArray

class Holistic:
    def __init__(self, staticMode=False, landmarks=True, detectionCon=0.5,
trackingCon=0.5):
        self.mpHolistic = mp.solutions.holistic
        self.mpFaceMesh = mp.solutions.face_mesh
        self.mpHands = mp.solutions.hands
        self.mpPose = mp.solutions.pose
        self.mpDraw = mp.solutions.drawing_utils
        self.mpholistic = self.mpHolistic.Holistic(
            static_image_mode=staticMode,
            smooth_landmarks=landmarks,
            min_detection_confidence=detectionCon,
            min_tracking_confidence=trackingCon)
        self.pub_point = rospy.Publisher('/mediapipe/points', PointArray,
queue_size=1000)
        self.lmDrawSpec = mp.solutions.drawing_utils.DrawingSpec(color=(0, 0, 255),
thickness=-1, circle_radius=3)
```

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        self.drawSpec = mp.solutions.drawing_utils.DrawingSpec(color=(0, 255, 0),
thickness=2, circle_radius=2)

    def findHolistic(self, frame, draw=True):
        pointArray = PointArray()
        img = np.zeros(frame.shape, np.uint8)
        img_RGB = cv.cvtColor(frame, cv.COLOR_BGR2RGB)
        self.results = self.mpholistic.process(img_RGB)
        if self.results.face_landmarks:
            if draw: self.mpDraw.draw_landmarks(frame, self.results.face_landmarks,
self.mpFaceMesh.FACEMESH_CONTOURS, self.lmDrawSpec, self.drawSpec)
            self.mpDraw.draw_landmarks(img, self.results.face_landmarks,
self.mpFaceMesh.FACEMESH_CONTOURS, self.lmDrawSpec, self.drawSpec)
            for id, lm in enumerate(self.results.face_landmarks.landmark):
                point = Point()
                point.x, point.y, point.z = lm.x, lm.y, lm.z
                pointArray.points.append(point)
        if self.results.pose_landmarks:
            if draw: self.mpDraw.draw_landmarks(frame, self.results.pose_landmarks,
self.mpPose.POSE_CONNECTIONS, self.lmDrawSpec, self.drawSpec)
            self.mpDraw.draw_landmarks(img, self.results.pose_landmarks,
self.mpPose.POSE_CONNECTIONS, self.lmDrawSpec, self.drawSpec)
            for id, lm in enumerate(self.results.pose_landmarks.landmark):
                point = Point()
                point.x, point.y, point.z = lm.x, lm.y, lm.z
                pointArray.points.append(point)
        if self.results.left_hand_landmarks:
            if draw: self.mpDraw.draw_landmarks(frame,
self.results.left_hand_landmarks, self.mpHands.HAND_CONNECTIONS, self.lmDrawSpec,
self.drawSpec)
            self.mpDraw.draw_landmarks(img, self.results.left_hand_landmarks,
self.mpHands.HAND_CONNECTIONS, self.lmDrawSpec, self.drawSpec)
            for id, lm in enumerate(self.results.left_hand_landmarks.landmark):
                point = Point()
                point.x, point.y, point.z = lm.x, lm.y, lm.z
                pointArray.points.append(point)
        if self.results.right_hand_landmarks:
            if draw: self.mpDraw.draw_landmarks(frame,
self.results.right_hand_landmarks, self.mpHands.HAND_CONNECTIONS, self.lmDrawSpec,
self.drawSpec)
            self.mpDraw.draw_landmarks(img, self.results.right_hand_landmarks,
self.mpHands.HAND_CONNECTIONS, self.lmDrawSpec, self.drawSpec)
            for id, lm in enumerate(self.results.right_hand_landmarks.landmark):
                point = Point()
                point.x, point.y, point.z = lm.x, lm.y, lm.z
                pointArray.points.append(point)
        self.pub_point.publish(pointArray)
        return frame, img

    def frame_combine(self, frame, src):
        if len(frame.shape) == 3:
            frameH, frameW = frame.shape[:2]

```

```

        srcH, srcW = src.shape[:2]
        dst = np.zeros((max(frameH, srcH), frameW + srcW, 3), np.uint8)
        dst[:, :frameW] = frame[:, :]
        dst[:, frameW:] = src[:, :]
    else:
        src = cv.cvtColor(src, cv.COLOR_BGR2GRAY)
        frameH, frameW = frame.shape[:2]
        imgH, imgW = src.shape[:2]
        dst = np.zeros((frameH, frameW + imgW), np.uint8)
        dst[:, :frameW] = frame[:, :]
        dst[:, frameW:] = src[:, :]
    return dst

if __name__ == '__main__':
    rospy.init_node('Holistic', anonymous=True)
    capture = cv.VideoCapture(0)
    capture.set(6, cv.VideoWriter_fourcc('M', 'J', 'P', 'G'))
    capture.set(cv.CAP_PROP_FRAME_WIDTH, 640)
    capture.set(cv.CAP_PROP_FRAME_HEIGHT, 480)
    print("capture get FPS : ", capture.get(cv.CAP_PROP_FPS))
    pTime = cTime = 0
    holistic = Holistic()
    while capture.isOpened():
        ret, frame = capture.read()
        # frame = cv.flip(frame, 1)
        frame, img = holistic.findHolistic(frame, draw=False)
        if cv.waitKey(1) & 0xFF == ord('q'): break
        cTime = time.time()
        fps = 1 / (cTime - pTime)
        pTime = cTime
        text = "FPS : " + str(int(fps))
        cv.putText(frame, text, (20, 30), cv.FONT_HERSHEY_SIMPLEX, 0.8, (0, 0, 255),
2)

        dist = holistic.frame_combine(frame, img)
        cv.imshow('dist', dist)
        # cv.imshow('frame', frame)
        # cv.imshow('img', img)
    capture.release()
    cv.destroyAllWindows()

```

