

## 9. Finger Control

### 9.1. 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 used to build data sources in various forms, 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 packets, streams, calculators, graphs, and subgraphs.

Features of MediaPipe:

- End-to-end acceleration: built-in fast ML inference and processing can be accelerated even on ordinary hardware.
- Build once, deploy anywhere anytime: unified solution for Android, iOS, desktop/cloud, web and IoT.
- Ready-to-use solution: cutting-edge ML solution that demonstrates the full functionality of the framework.
- Free and open source: framework and solution under Apache2.0, fully extensible and customizable.

### 9.2, Finger control

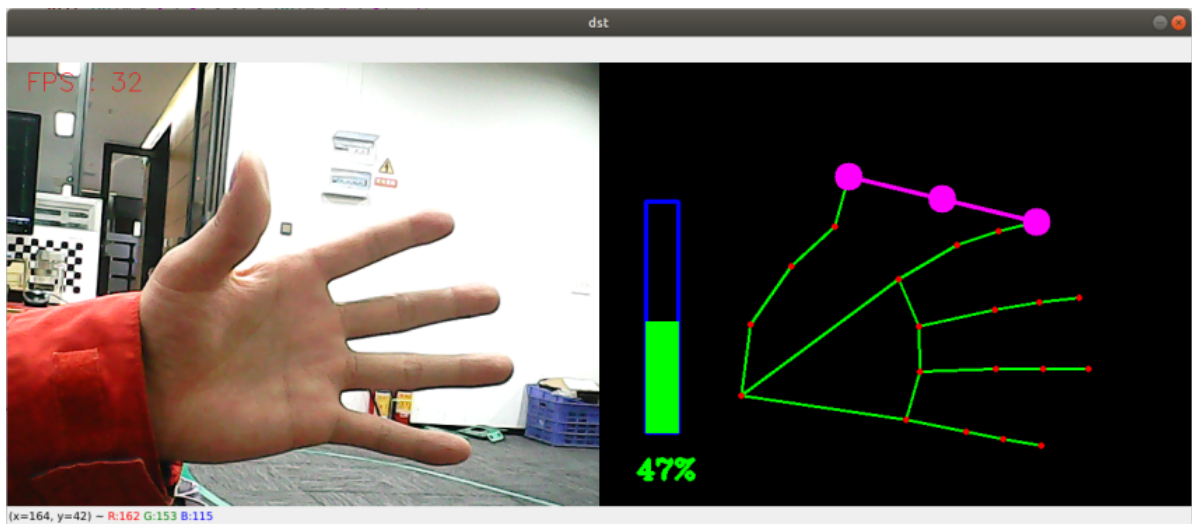
Click the [f key] to switch the recognition effect, and the distance between the thumb and index finger (open/close) can control the effect of the image.

#### 9.2.1, Startup

**Please do this step before running the program**

```
sudo supervisorctl stop ChassisServer #Stop the self-starting chassis service
#Indoor version of NAVROBO-astra_pro2 camera executes this command
/home/yahboom/YBAMR-COBOT-EDU-00001/start/OBColorViewer #Release color stream
video100
#[info][722318][Pipeline.cpp:251] Start streams done!
#[info][722318][Pipeline.cpp:234] Pipeline start done!
#[warning][722318][Pipeline.cpp:327] wait for frame timeout, you can try to
increase the wait time! current timeout=100
```

```
cd /home/yahboom/YBAMR-COBOT-EDU-00001/src/yahboom_navrobo_mediapipe/scripts #
Enter the source code directory
python3 10_HandCtrl.py # Finger control
```



## 9.2.2, Source code

Source code location: /home/yahboom/YBAMR-COBOT-EDU-00001/src/yahboom\_navrobo\_mediapipe/scripts/10\_HandCtrl.py

```
#!/usr/bin/env python3
# encoding: utf-8
import math
import time
import cv2 as cv
import numpy as np
import mediapipe as mp

pTime = cTime = volPer = value = index = 0
effect = ["color", "thresh", "blur", "hue", "enhance"]
volBar = 400
class handDetector:
    def __init__(self, mode=False, maxHands=2, detectorCon=0.5, trackCon=0.5):
        self.tipIds = [4, 8, 12, 16, 20]
        self.mpHand = mp.solutions.hands
        self.mpDraw = mp.solutions.drawing_utils
        self.hands = self.mpHand.Hands(
            static_image_mode=mode,
            max_num_hands=maxHands,
            min_detection_confidence=detectorCon,
            min_tracking_confidence=trackCon
        )
        self.lmDrawSpec = mp.solutions.drawing_utils.DrawingSpec(color=(0, 0, 255), thickness=-1, circle_radius=15)
        self.drawSpec = mp.solutions.drawing_utils.DrawingSpec(color=(0, 255, 0), thickness=10, circle_radius=10)

    def get_dist(self, point1, point2):
        x1, y1 = point1
        x2, y2 = point2
        return abs(math.sqrt(math.pow(abs(y1 - y2), 2) + math.pow(abs(x1 - x2), 2)))

    def calc_angle(self, pt1, pt2, pt3):
        point1 = self.lmList[pt1][1], self.lmList[pt1][2]
        point2 = self.lmList[pt2][1], self.lmList[pt2][2]
        point3 = self.lmList[pt3][1], self.lmList[pt3][2]
```

```

a = self.get_dist(point1, point2)
b = self.get_dist(point2, point3)
c = self.get_dist(point1, point3)
try:
    radian = math.acos((math.pow(a, 2) + math.pow(b, 2) - math.pow(c,
2)) / (2 * a * b))
    angle = radian / math.pi * 180
except:
    angle = 0
return abs(angle)

def findHands(self, frame, draw=True):
    img = np.zeros(frame.shape, np.uint8)
    img_RGB = cv.cvtColor(frame, cv.COLOR_BGR2RGB)
    self.results = self.hands.process(img_RGB)
    if self.results.multi_hand_landmarks:
        for handLms in self.results.multi_hand_landmarks:
            if draw: self.mpDraw.draw_landmarks(img, handLms,
self.mpHand.HAND_CONNECTIONS)
    return img

def findPosition(self, frame, draw=True):
    self.lmList = []
    if self.results.multi_hand_landmarks:
        for id, lm in
enumerate(self.results.multi_hand_landmarks[0].landmark):
            # print(id,lm)
            h, w, c = frame.shape
            cx, cy = int(lm.x * w), int(lm.y * h)
            # print(id, lm.x, lm.y, lm.z)
            self.lmList.append([id, cx, cy])
            if draw: cv.circle(frame, (cx, cy), 15, (0, 0, 255), cv.FILLED)
    return self.lmList

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__':
    capture = cv.VideoCapture(6)
    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))
    hand_detector = handDetector()

```

```

while capture.isOpened():
    ret, frame = capture.read()
    action = cv.waitKey(1) & 0xFF
    # frame = cv.flip(frame, 1)
    img = hand_detector.findHands(frame)
    lmList = hand_detector.findPosition(frame, draw=False)
    if len(lmList) != 0:
        angle = hand_detector.calc_angle(4, 0, 8)
        x1, y1 = lmList[4][1], lmList[4][2]
        x2, y2 = lmList[8][1], lmList[8][2]
        cx, cy = (x1 + x2) // 2, (y1 + y2) // 2
        cv.circle(img, (x1, y1), 15, (255, 0, 255), cv.FILLED)
        cv.circle(img, (x2, y2), 15, (255, 0, 255), cv.FILLED)
        cv.line(img, (x1, y1), (x2, y2), (255, 0, 255), 3)
        cv.circle(img, (cx, cy), 15, (255, 0, 255), cv.FILLED)
        if angle <= 10: cv.circle(img, (cx, cy), 15, (0, 255, 0), cv.FILLED)
        volBar = np.interp(angle, [0, 70], [400, 150])
        volPer = np.interp(angle, [0, 70], [0, 100])
        value = np.interp(angle, [0, 70], [0, 255])
        # print("angle: {},value: {}".format(angle, value))
    # 进行阈值二值化操作, 大于阈值value的, 使用255表示, 小于阈值value的, 使用0表示
    if effect[index]=="thresh":
        gray = cv.cvtColor(frame, cv.COLOR_BGR2GRAY)
        frame = cv.threshold(gray, value, 255, cv.THRESH_BINARY)[1]
    # 进行高斯滤波,(21, 21)表示高斯矩阵的长与宽都是21, 标准差取value
    elif effect[index]=="blur":
        frame = cv.GaussianBlur(frame, (21, 21), np.interp(value, [0, 255],
[0, 11]))
    # 色彩空间的转化,HSV转换为BGR
    elif effect[index]=="hue":
        frame = cv.cvtColor(frame, cv.COLOR_BGR2HSV)
        frame[:, :, 0] += int(value)
        frame = cv.cvtColor(frame, cv.COLOR_HSV2BGR)
    # 调节对比度
    elif effect[index]=="enhance":
        enh_val = value / 40
        clahe = cv.createCLAHE(clipLimit=enh_val, tileGridSize=(8, 8))
        lab = cv.cvtColor(frame, cv.COLOR_BGR2LAB)
        lab[:, :, 0] = clahe.apply(lab[:, :, 0])
        frame = cv.cvtColor(lab, cv.COLOR_LAB2BGR)
    if action == ord('q'): break
    if action == ord('f'):
        index += 1
        if index >= len(effect): index = 0
    cTime = time.time()
    fps = 1 / (cTime - pTime)
    pTime = cTime
    text = "FPS : " + str(int(fps))
    cv.rectangle(img, (50, 150), (85, 400), (255, 0, 0), 3)
    cv.rectangle(img, (50, int(volBar)), (85, 400), (0, 255, 0), cv.FILLED)
    cv.putText(img, f'{int(volPer)}%', (40, 450), cv.FONT_HERSHEY_COMPLEX,
1, (0, 255, 0), 3)
    cv.putText(frame, text, (20, 30), cv.FONT_HERSHEY_SIMPLEX, 0.9, (0, 0,
255), 1)
    dst = hand_detector.frame_combine(frame, img)
    cv.imshow('dst', dst)
    # cv.imshow('frame', frame)
    # cv.imshow('img', img)

```

```
capture.release()  
cv.destroyAllWindows()
```