

5. Face Recognition

5.1. 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 commodity 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 capabilities of the framework.
- Free and open source: framework and solution under Apache2.0, fully extensible and customizable.

5.2, Face Recognition

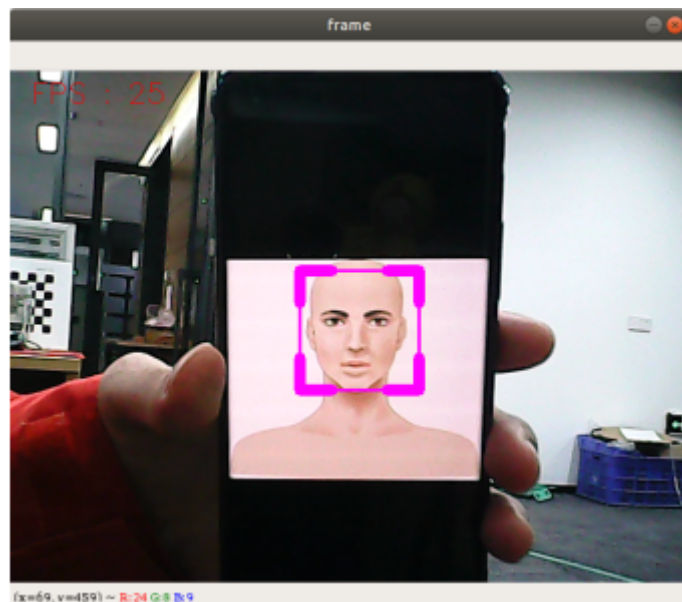
5.2.1, Startup

Terminal input,

Please do this step before running the program

```
sudo supervisorctl stop ChassisServer #Shut down 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
```

```
roslaunch yahboom_navrobo_mediapipe 05_FaceEyeDetection.launch # Face recognition
```



5.2.2, Source code

Source code location: /home/yahboom/YBAMR-COBOT-EDU-00001/src/yahboom_navrobo_mediapipe/scripts/05_FaceEyeDetection.py

```
#!/usr/bin/env python3
# encoding: utf-8
import time
import rospy
import rospkg
import cv2 as cv
from cv_bridge import CvBridge
from sensor_msgs.msg import CompressedImage, Image

class FaceEyeDetection:
    def __init__(self):
        self.bridge = CvBridge()

        rospy.init_node("FaceEyeDetection", anonymous=False)
        self.eyeDetect = cv.CascadeClassifier(
            rospkg.RosPack().get_path("dofbot_mediapipe") +
            "/scripts/file/haarcascade_eye.xml")
        self.faceDetect = cv.CascadeClassifier(
            rospkg.RosPack().get_path("dofbot_mediapipe") +
            "/scripts/file/haarcascade_frontalface_default.xml")
        self.pub_rgb = rospy.Publisher("/FaceEyeDetection/image", Image,
            queue_size=1)
        rospy.on_shutdown(self.cancel)

    def cancel(self):
        self.pub_rgb.unregister()

    def face(self, frame):
        gray = cv.cvtColor(frame, cv.COLOR_BGR2GRAY)
        faces = self.faceDetect.detectMultiScale(gray, 1.3)
        for face in faces: frame = self.faceDraw(frame, face)
        return frame

    def eye(self, frame):
        gray = cv.cvtColor(frame, cv.COLOR_BGR2GRAY)
```

```

        eyes = self.eyeDetect.detectMultiScale(gray, 1.3)
        for eye in eyes:
            cv.circle(frame, (int(eye[0] + eye[2] / 2), int(eye[1] + eye[3] /
2)), (int(eye[3] / 2)), (0, 0, 255), 2)
        return frame

def faceDraw(self, frame, bbox, l=30, t=10):
    x, y, w, h = bbox
    x1, y1 = x + w, y + h
    cv.rectangle(frame, (x, y), (x + w, y + h), (255, 0, 255), 2)
    # Top left x,y
    cv.line(frame, (x, y), (x + l, y), (255, 0, 255), t)
    cv.line(frame, (x, y), (x, y + l), (255, 0, 255), t)
    # Top right x1,y
    cv.line(frame, (x1, y), (x1 - l, y), (255, 0, 255), t)
    cv.line(frame, (x1, y), (x1, y + l), (255, 0, 255), t)
    # Bottom left x1,y1
    cv.line(frame, (x, y1), (x + l, y1), (255, 0, 255), t)
    cv.line(frame, (x, y1), (x, y1 - l), (255, 0, 255), t)
    # Bottom right x1,y1
    cv.line(frame, (x1, y1), (x1 - l, y1), (255, 0, 255), t)
    cv.line(frame, (x1, y1), (x1, y1 - l), (255, 0, 255), t)
    return frame

def pub_img(self, frame):
    self.pub_rgb.publish(self.bridge.cv2_to_imgmsg(frame, "bgr8"))

if __name__ == '__main__':
    capture = cv.VideoCapture(6)
    capture.set(6, cv.VideoWriter_fourcc(*'XVID'))
    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, content_index = 0, 0, 0
    dat_file = "./file/shape_predictor_68_face_landmarks.dat"
    face_eye_detection = FaceEyeDetection()
    content = ["face", "eye", "face_eye"]
    while capture.isOpened():
        ret, frame = capture.read()
        # frame = cv.flip(frame, 1)
        action = cv.waitKey(1) & 0xFF
        if action == ord("f") or action == ord("F"):
            content_index += 1
            if content_index >= len(content): content_index = 0
            if content[content_index] == "face": frame =
face_eye_detection.face(frame)
            elif content[content_index] == "eye": frame =
face_eye_detection.eye(frame)
            else: frame = face_eye_detection.eye(face_eye_detection.face(frame))
            if action == ord('q') or action == 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, 0.9, (0, 0,
255), 1)
        cv.imshow('frame', frame)

```

```
face_eye_detection.pub_img(frame)
capture.release()
cv.destroyAllWindows()
```