

3.Overall inspection

Note: There are related running codes on Raspberry Pi and Jetson nano, but due to differences in motherboard performance, the running may not be as smooth. The supporting virtual machine also has the operating environment and programs installed. If the experience on the motherboard is not good, you can remove the camera, plug it into the virtual machine, and connect the camera device to the virtual machine to run the corresponding program on the virtual machine.

3.1. 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 solution 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.

3.2.MediaPipe Hands

Refer to the content of Section 1 Hand Detection [1.2] and will not go into details here.

3.3.MediaPipe Pose

Refer to the content of Section 1 Hand Detection [2.2] and will not go into details here.

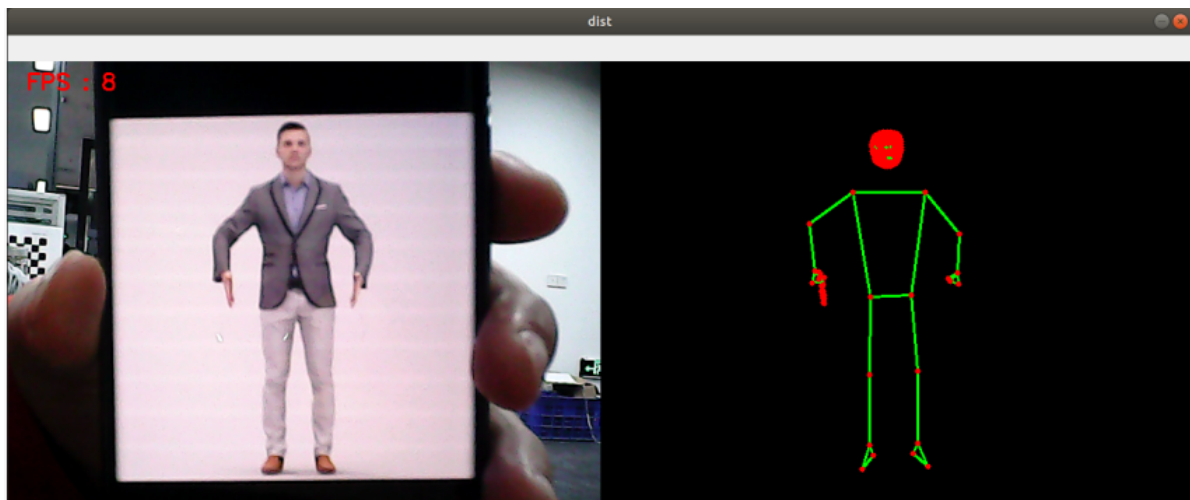
3.4. Overall detection

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

3.4.1. Start up

Terminal input,

```
roscore
roslaunch dofbot_mediapipe 03_Holistic.py
```



3.4.2. Source code

Source code location: /home/jetson/dofbot_ws/src/dofbot_mediapipe/scripts/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()

```