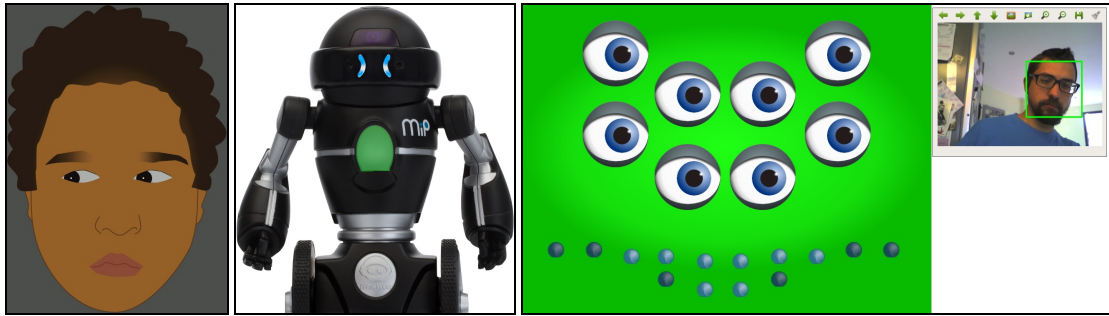


rosavatar



This package renders virtual faces that can be controlled with ROS topics.

Parameters

- `~eyes_folder` [std::string, default:""] Folder where the different images can be found. Leave empty for the default face.

Subscriptions

- `~iris_position` [geometry_msgs/Point] Output topic, containing the normalized coordinates of
- `~mouth_vol` [std_msgs/Float64] Mouth volume, that will turn LEDS on/off. Will be clamped between 0 and 1.
- `~state` [std_msgs/String] State. Sad if nobody around, normal otherwise.

Publications

- `~eyes` [sensors_msgs/Image] Generated avatar image.

Example launch files

Mouse control

This creates a small window in which the user can orientate the look of the robot. It makes the default avatar look in the direction of the mouse.

```
$ roslaunch rosavatar face_control.launch
```

To test the volume meter made by the mouth leds, you can play a song, or run:

```
$ speaker-test -t wav
```

Face control

This makes the default avatar look in the direction of any detected face. Otherwise, the avatar turns sleepy.

```
$ roslaunch rosavatar face_control.launch
```

To test the volume meter made by the mouth leds, you can play a song, or run:

```
$ speaker-test -t wav
```

Depends on [cv_camera](#). To install:

```
1 $ git clone https://github.com/OTL/cv_camera
2 $ catkin_make --only-pkg-with-deps rosavatar cv_camera
```

Licence

LGPL v3 (GNU Lesser General Public License version 3). See LICENCE.