

Follow me behavior (detection part) tests

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Follow me behavior (perception part): tests

1. Offline tests
2. Tests on robair

Follow me behavior (perception part): offline tests

- Open 5 terminals:
 1. Roscore
 2. Rosrun *follow_me detection_node*;
 3. Rosbag play *data_file*.bag: to play a saved file;
 - Use a rosbag in `~/catkin_ws/data_for_labs/detection`
 4. Rosrun *follow_me robot_moving_node*;
 - The laser data are only processed when the robot does not move;
 - This is automatically taken into account by the node *robot_moving_node*;
 - **You do not have to take care about this issue.**
 5. Rviz: the vizualization tool of ROS.
 - To have a graphical display of the processing;

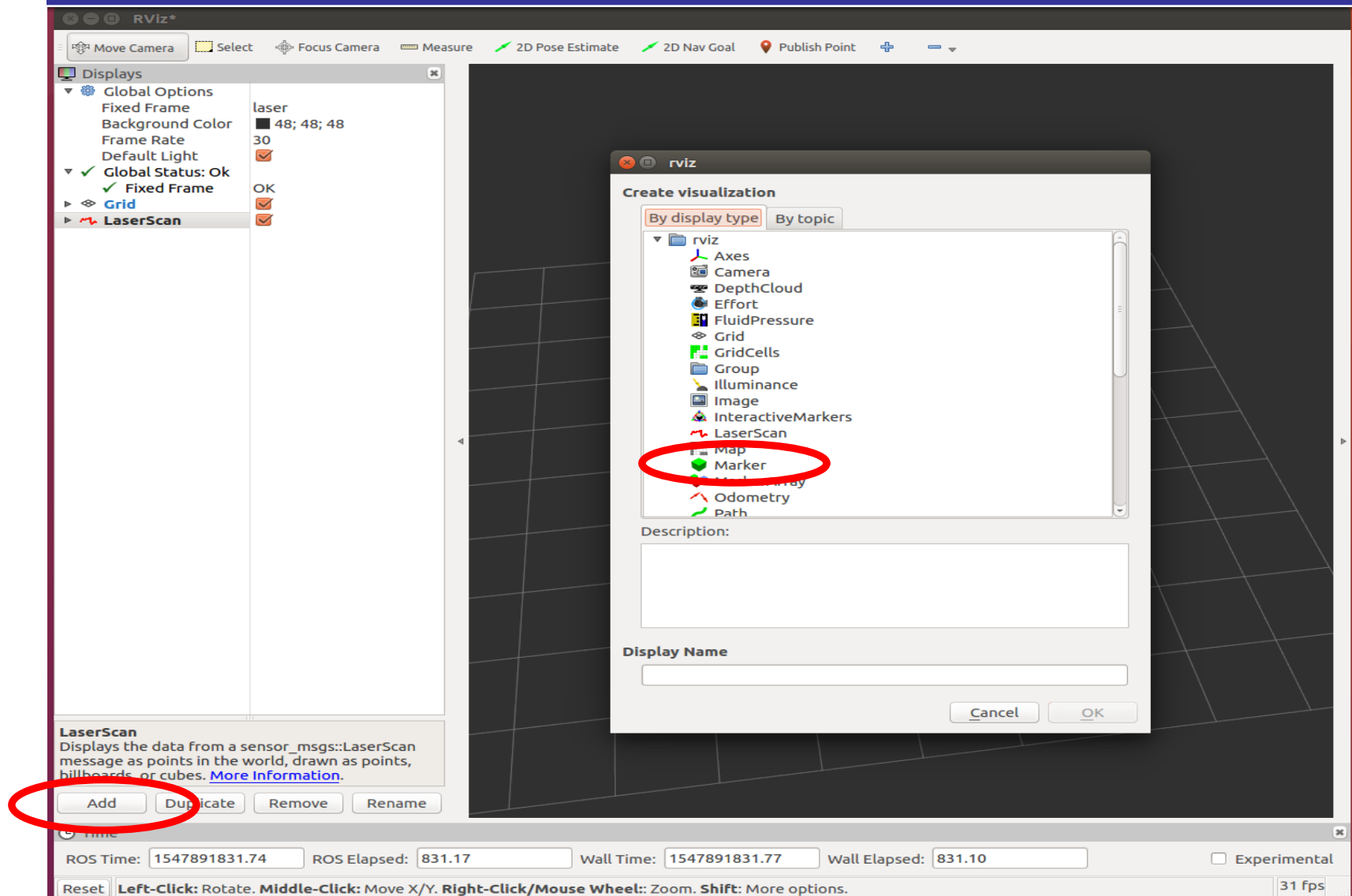
Follow me behavior (perception part): tests

1. Offline tests
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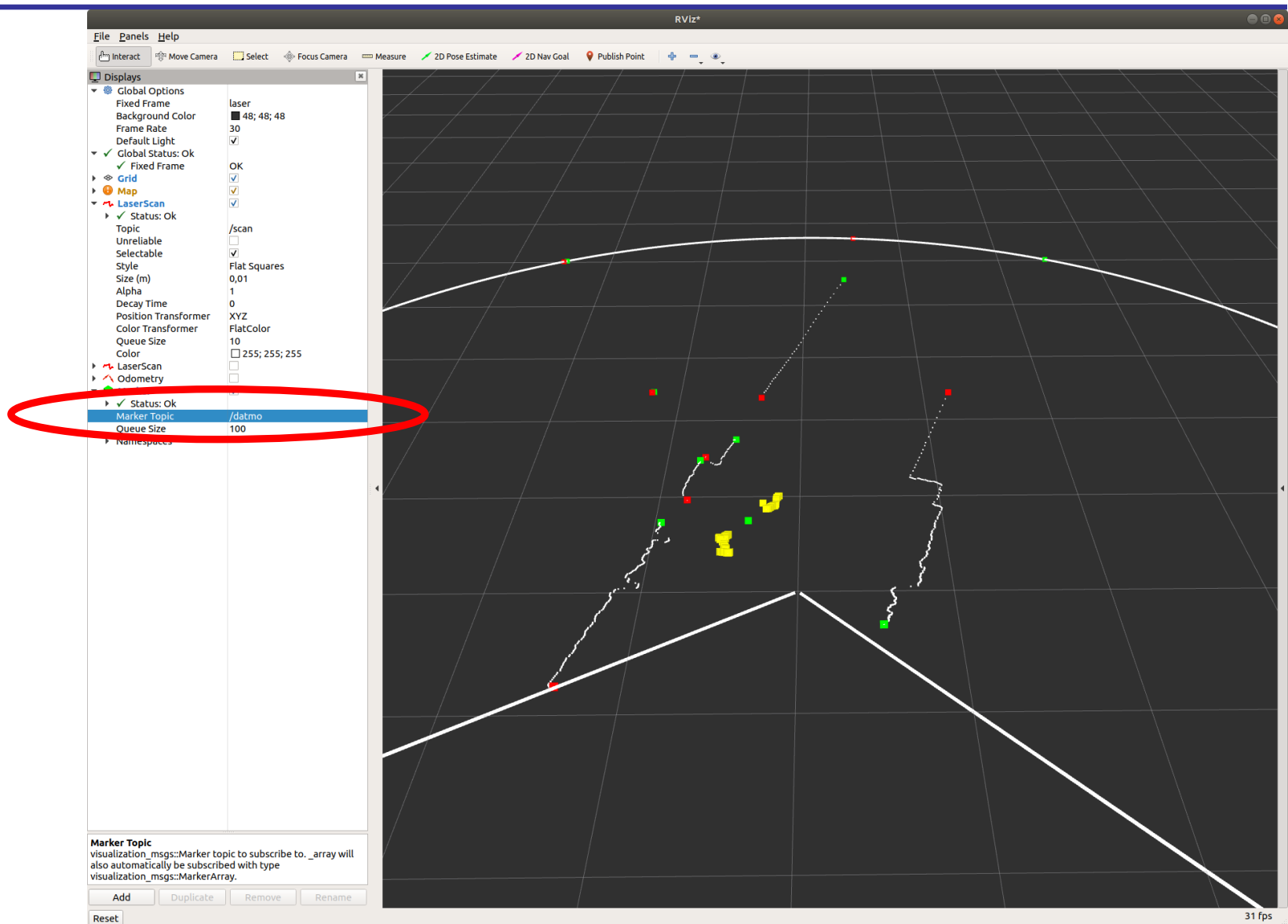
Follow me behavior (perception part): tests on robair(1/4)

- Open 3 terminals:
 1. Rosrun follow_me *datmo_node*;
 2. Rosrun follow_me *robot_moving_node*;
 - The laser data are only processed when the robot does not move;
 - This is automatically taken into account by the node *robot_moving_node*;
 - You do not have to take care about this issue.
 3. Rviz: the vizualization tool of ROS.
 - To have a graphical display of the processing;
 - See screenshots on next slides

Follow me behavior (perception part): tests on robair (2/4)



Follow me behavior (perception part): tests on robair (3/4)



Follow me behavior (perception part): tests on robair (4/4)

1. Move in front of robair and check that you are detected;
2. Open a new terminal:
 - Rosrun teleoperation teleoperation_node.py;
 - **Only** using the green marker in the middle of your 2 legs, rotate robair so that it is facing you;
3. **Only** using the green marker in the middle of your 2 legs, move robair so that it stays close to you;
4. Ask to a second person to move in front of robair while you are not moving
 - What happen with the green marker ?
 - If you move robair **only** using the green marker, is robair still following you ?