Advanced perception:
tracking of a moving person

Olivier Aycard
Professor
Grenoble INP - PHELMA
GIPSA Lab
https://www.gipsa-lab.grenoble-inp.fr/user/olivier.aycard
olivier.aycard@grenoble-inp.fr

Advanced follow me behavior (perception part: 1/2)

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
   - In a real environment, there is always several persons present
   - What happen with the green marker ?
   - If you move robair only using the green marker, is robair still following you ?

Advanced follow me behavior (perception part: 2/2)

4. Ask to a second person to move in front of robair while you are not moving
   - In a real environment, there is always several persons present
   - What happen with the green marker ?
   - If you move robair only using the green marker, is robair still following you ?

5. Why do we need to track the followed moving person ?
6. Have a look on datmo course: tracking part (from slide 28);

Advanced follow me behavior (perception part: 2/2)

7. In datmo_node.cpp:
   1. Modify « update » and introduce the variable « tracking_mode »;
   2. Implement « track_a_moving_person » in datmo.cpp.