

## 一、硬件连接

舵机安装时需要注意,将控制脑袋左右转动的舵机连接到5号PWM引脚上。如果想控制脑袋上下运动,则将控制上下移动的舵机连接到 arduino Mega2560 扩展板的6号pwm引脚上。然后注意给舵机加上合适的电压,保证舵机可以正常工作。

## 二、更新代码并运行启动人脸跟踪

更新人脸跟踪代码并运行可分两种方法,第一种方法简单,直接执行脚本即可。第二种方法是分步执行的,较为复杂。

介绍第一种方法:

1. 执行执行 update\_and\_launch.bash 脚本即可,执行脚本命令如下:

`./update_and_launch.bash`

```
corvin@Robot:~$ ./update_and_launch.bash
remote: Counting objects: 5, done
remote: Finding sources: 100% (4/4)
remote: Total 4 (delta 1), reused 4 (delta 1)
Unpacking objects: 100% (4/4), done.
From ssh://corvin.cn:29418/face_tracker
 * branch          kinetic-devel -> FETCH_HEAD
  b8c5ad9..d1524ab kinetic-devel -> origin/kinetic-devel
Updating b8c5ad9..d1524ab
Fast-forward
 setup.bash => scripts/setup.bash | 0
 scripts/update_and_launch.bash | 9 ++++++++
 2 files changed, 9 insertions(+)
 rename setup.bash => scripts/setup.bash (100%)
 create mode 100755 scripts/update_and_launch.bash
Base path: /home/corvin/face_tracker/ros_code
Source space: /home/corvin/face_tracker/ros_code/src
Build space: /home/corvin/face_tracker/ros_code/build
Devel space: /home/corvin/face_tracker/ros_code/devel
Install space: /home/corvin/face_tracker/ros_code/install
####
#### Running command: "make cmake_check_build_system" in "/home/corvin/face_
####
####
#### Running command: "make -j4 -l4" in "/home/corvin/face_tracker/ros_code/
####
[ 0%] Built target std_msgs_generate_messages_py
[ 0%] Built target std_msgs_generate_messages_eus
[ 0%] Built target std_msgs_generate_messages_nodejs
[ 0%] Built target std_msgs_generate_messages_lisp
[ 0%] Built target _arduino_servo_connect_generate_messages_check_deps_Servo
[ 0%] Built target _arduino_servo_connect_generate_messages_check_deps_Servo
[ 0%] Built target std_msgs_generate_messages_cpp
[ 25%] Built target arduino_servo_connect_generate_messages_eus
[ 41%] Built target arduino_servo_connect_generate_messages_nodejs
[ 66%] Built target arduino_servo_connect_generate_messages_py
[ 83%] Built target arduino_servo_connect_generate_messages_lisp
[100%] Built target arduino_servo_connect_generate_messages_cpp
[100%] Built target arduino_servo_connect_generate_messages
```

## 介绍第二种方法：

2. 打开 terminator 终端，首先第一步进入到人脸跟踪源码 face\_tracker 目录下：

```
cd face_tracker
```

3. 从 ROS 小课堂服务器上拉取最新的代码，更新代码命令如下：

```
git pull origin kinetic-devel
```

4. 接下来进入 ros 工作区目录并重新编译人脸跟踪源码，执行命令如下：

```
cd ros_code&&catkin_make
```

5. 配置工作环境变量：

```
source devel/setup.bash
```

6. 执行人脸跟踪命令如下：

```
roslaunch face_tracker_bringup face_tracker_bringup.launch
```