Table of Contents

• WillyWRT

. Speech recognition	. 2
. Flow	
Velcome	
roject Willy	
History of Willy	
• Project Willy	
• Publicity	
• Sponsors	
Setting started	
Development Guide	
• Driving Willy	
• Documentation	
uild of Willy	
• Design history	
• Requirements	
Design reference	
Physical build	
• Hardware	
obotic Operating System	
• Introduction to ROS	
• ROS Tutorials	
• Multi master	
rchitecture	
Software Architecture	
Hardware Architecture	
ROS topic design	
lardware nodes	
• sensor node	
• si node	
• power node	

Components

- ROS master
- · New ROS master on Lubuntu
- Brain
- Sonar
- Lidar
- Localization and navigation
- Motor controller
- Joystick
- Social interaction
- Speech
- Speech recognition

Radeffect App

• Radeffect App

Lessons learned

- · Todo & Advice
- Lessons Learned

Archive

- Previous Groups
- Research Archive
- Skylab Architecture
- Skylab

1. Speech recognition

Listening to speech is located on the SI node and is done with a Python script. The script is published at the Github location: https://github.com/Windesheim-Willy/speech_recognition/blob/master/start_recognition.py . Two essential services are used:

- Speech recognition (speech to text conversion) of Google through the use the module speech_recognition
- Fuzzy logic search option through the use of the module fuzzywuzzy

2. Flow

The general flow in the script is as follows:

• The neccesary modules are imported

- The hit ratio used for fuzzy logic resemblance is set
- Two topics are set for publishing
- Speech is captured through the microphone
- Speech is transferred to Google for translation in clear text in Dutch
- Text is published on topic /interaction/clear_text
- Text is compared with fuzzy logic to keywords, when hit the number 1 is published on topic /interaction/is_active