

Table of Contents

| | |
|---------------------------|---|
| 1. Driving of willy | 2 |
| 1.1. Stop Willy | 3 |

Welcome

Project Willy

- [History of Willy](#)
- [Project Willy](#)
- [Publicity](#)
- [Sponsors](#)

Getting started

- [Development Guide](#)
- [Driving Willy](#)
- [Documentation](#)

Build of Willy

- [Design history](#)
- [Requirements](#)
- [Design reference](#)
- [Physical build](#)
- [Hardware](#)

Robotic Operating System

- [Introduction to ROS](#)
- [ROS Tutorials](#)
- [Multi master](#)

Architecture

- [Software Architecture](#)
- [Hardware Architecture](#)
- [ROS topic design](#)

Hardware nodes

- [sensor node](#)
- [si node](#)
- [power node](#)
- [WillyWRT](#)

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. Driving of willy

1. Deploy the brakes

Normally a wheelchair has brakes. The brakes of Willy have been removed.

2. Deploy the emergency stop

3. Turn the power on

Do it in the following order:

- Start the OpenWRT PI
- Start the Notebook
- Start the Sensor and SI PI.

4. Undeploy the emergency stop



By default the **brain** will takeover the control. Make sure to move Willy to a safe place with the controller first.

1.1. Stop Willy

1. **Deploy the emergency stop**
2. **Shutdown all raspberry PI's from the notebook**
 - a. Open the terminal on the notebook

```
sh /opt/willy/components/ansible/shutdown-pi.sh
```

Fill in the password of the PI's

1. **Shutdown the notebook**
2. **Turn of the power**