示例4——语音控制机械臂

1、启动机械臂

roslaunch pxpincher_launch pxp.launch

2、启动语音播音

 roslaunch simple_voice arm_speaker.launch

PC端：
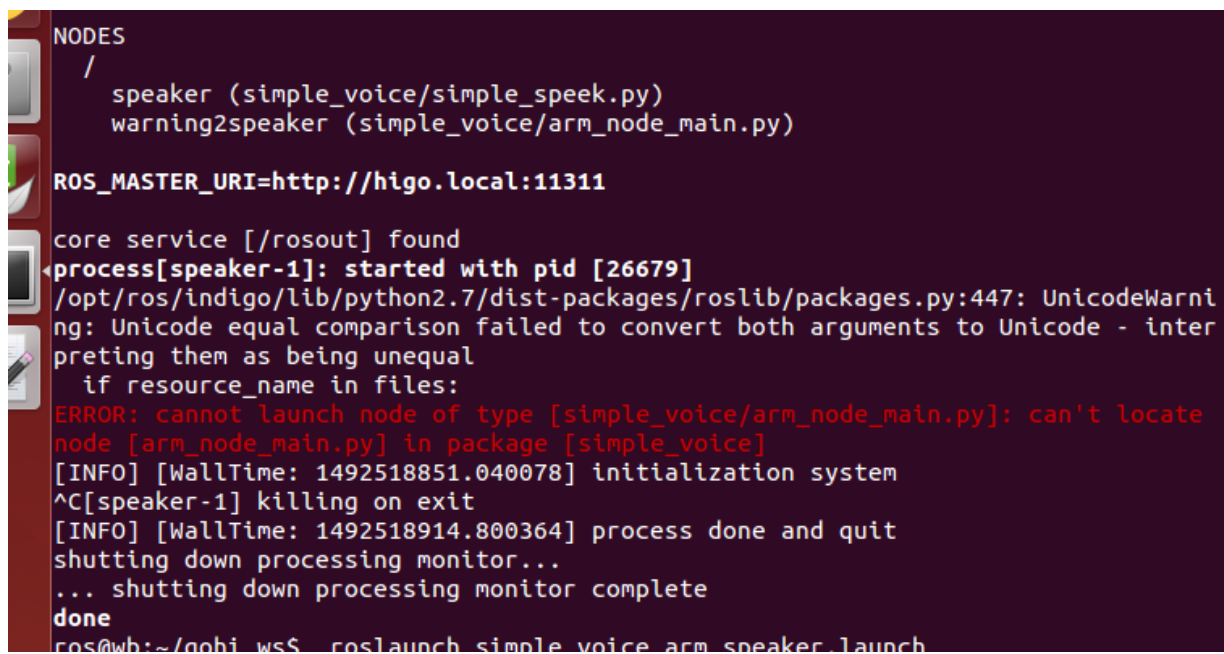
3、启动动作

rosrun pxpincher_lib pxpincher_test

机器人端（SSH登录）：

4、启动 语音识别

roslaunch simple_voice simple_voice_default.launch

```
NODES
  /
    speaker (simple_voice/simple_speek.py)
    warning2speaker (simple_voice/arm_node_main.py)

ROS_MASTER_URI=http://higo.local:11311

core service [/rosout] found
process[speaker-1]: started with pid [26679]
/opt/ros/indigo/lib/python2.7/dist-packages/roslib/packages.py:447: UnicodeWarni
ng: Unicode equal comparison failed to convert both arguments to Unicode - inter
preting them as being unequal
  if resource_name in files:
ERROR: cannot launch node of type [simple_voice/arm_node_main.py]: can't locate
node [arm_node_main.py] in package [simple_voice]
[INFO] [WallTime: 1492518851.040078] initialization system
^C[speaker-1] killing on exit
[INFO] [WallTime: 1492518914.800364] process done and quit
shutting down processing monitor...
... shutting down processing monitor complete
done
ros@wb:~/gobi_ws$ roslaunch simple_voice arm_speaker.launch
```

解决方式：修改py文件权限，作为可执行文件