

示例3.3——百度语音识别与控制

功能2——本地语音输入，远程控制HiGo,语音提示状态

步骤1、安装功能包

```
cd gohi_ws/src
git clone https://github.com/DinnerHowe/simple_voice.git
git clone https://github.com/aniskoubaa/gaitech\_edu.git
```

步骤2、修改启动文件

```
cd ~/gohi_ws/src/simple_voice/launch
gedit warning_speaker.launch
```

//-----

修改启动文件warning_speaker.launch

```
<launch>
```

```
<arg name='words' default="请让一下，谢谢" />
```

```
<arg name='SpeakerSubTopic' default="Rog_result" />
```

```
<arg name="ResponseSensitivity" default="1.8"/>
```

```
<arg name="WorkSpaces" default="Xbot"/>
```

```
<include file="$(find simple_voice)/launch/simple_speaker.launch" />
```

```
<param name="ResponseSensitivity" value="$(arg ResponseSensitivity)" />
```

```
<param name="WorkSpaces" value="$(arg WorkSpaces)" />
```

```
<node pkg="simple_voice" type="node_main.py" name="warning2speaker" output="screen">
```

```
<param name='words' value="$(arg words)" type="str" />
```

```
<param name='SpeakerSubTopic' value="$(arg SpeakerSubTopic)" type="str" />
```

```
</node>
```

```
</launch>
```

----- //

步骤3、修改python脚本

修改程序node_main.py

//-----

```
def define(self):
```

```
self.say=rospy.Publisher('speak_string', String, queue_size=1)
```

```
if not rospy.has_param('~words'):
```

```
rospy.set_param('~words','请让一下，谢谢')
```

```
if not rospy.has_param('~SpeakerSubTopic'):
```

```
rospy.set_param('~SpeakerSubTopic', 'Rog_result')
```

```
#rospy.set_param('~SpeakerSubTopic', 'stop_flag')
```

```
self.words=rospy.get_param('~words')
```

```
self.topic=rospy.get_param('~SpeakerSubTopic')
```

```
self.commands = ['停止',
```

```
'前进',
```

```
'后退',
```

```
'左转',
```

```
'右转',
```

```
]
```

```
def talker(self,data):
```

```
# Get the motion command from the recognized phrase
```

```
command = data.data
```

```
if (command in self.commands):
```

```
if command == '前进':
```

```
self.say.publish(command)
```

```
elif command == '后退':
```

```
self.say.publish(command)
```

```
elif command == '左转':
```

```
self.say.publish(command)
```

```
elif command == '右转':
```

```
self.say.publish(command)
```

```
elif command == '停止':
```

```
self.say.publish(command)
```

```
else:  
pass
```

```
----- //
```

步骤4、

机器人端（SSH登录）：

```
## ssh gohi.local  
## roscore &  
## roslaunch gohi_hw gohi_hw.launch  
##roslaunch simple_voice warning_speaker.launch
```

PC端：

```
## 打开另一终端  
## roslaunch simple_voice simple_voice.launch
```