

AI Encyclopedia-Problem Solving Expert

Before running the function, you need to close the App and large programs. For the closing method, refer to [4. Preparation] - [1. Manage APP control services].

1. Function Description

After the program starts, ask the large model for the answer to a question. After thinking, the large model will reply with the answer to the question, and the program will control the robotic arm to point to that answer.

2. Startup

Taking the text version as an example, users with Jetson-Nano mainboard version need to enter the docker container first and then input the following command. Users with Orin mainboard can directly open the terminal and input the following command:

```
ros2 launch largemodel largemodel_control.launch.py text_chat_mode:=True
```

Then open a second terminal and input the following command:

```
ros2 run text_chat text_chat
```

Then input "What is the correct answer to this question?" in the text_chat terminal and press Enter; if it's the voice version, wake up the voice module and directly say to the voice module "What is the correct answer to this question?", then wait for the large model to think and reply, as shown in the figure below:

[illegible]

Then the robotic arm will point to answer B:



The question is:

which of the following words can be used to describe spring ()

- | | |
|---------|---------|
| A. Hot | B. Warm |
| C. Cold | D. Cool |

3. Task Planning

1. Call seehat() to check the question;
2. Reply with the answer to the question;
3. Find the answer option on the desktop;
4. Call the point_to() function to point to that answer option