Voice control mechanical dog action group

Quick use

1. Power on DOGZILLA

First, we turn on the switching power supply of the mechanical dog and start the mechanical dog



After starting, we can view the IP address on the small screen of the robot dog.

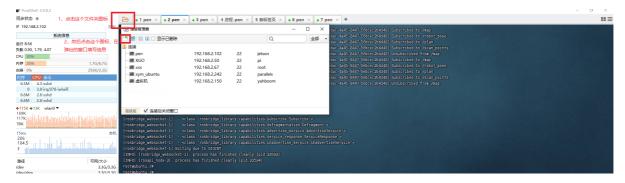
2. Start DOGZILLA chassis

PI4 version steps:

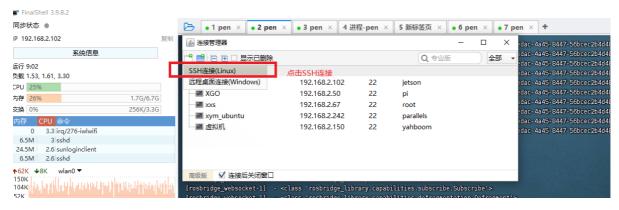
Then use the ssh terminal to connect to the robot dog.

Note: The IP address used when writing this tutorial: 192.168.2.102 User name: pi Password: yahboom The actual IP address shall prevail when used.

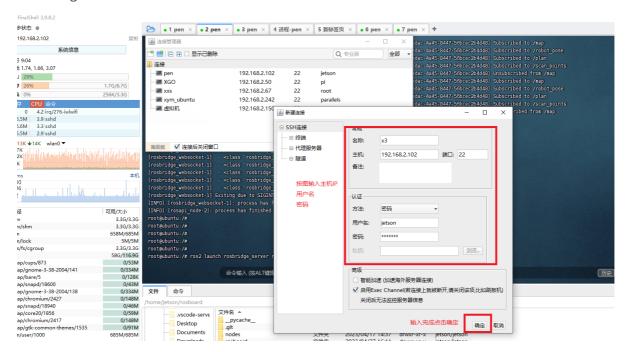
Open the shell tool. The shell tool I use here is FinalShell. Enter username, password, port, connection name and other information.



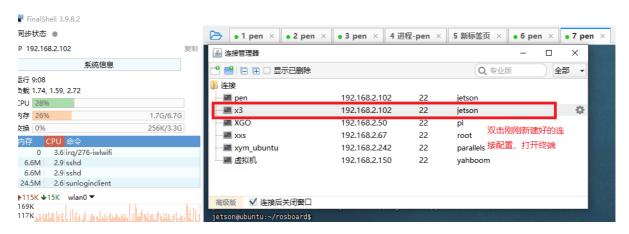
Select ssh connection to create a new ssh connection



Here the username is pi, the password is yahboom, and the ip address is the IP address of the real robot dog.



Select the ssh connection you just created here.

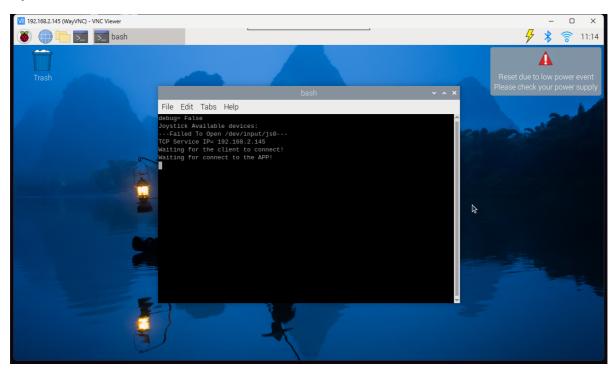


Enter the command in the terminal to start the chassis task.

```
pl@yahboom:~$
pi@yahboom:~$
pi@yahboom:~$
pi@yahboom:~$
pi@yahboom:~$
pi@yahboom:~$
```

PI5 version steps:

After the mechanical dog is started, use the vnc software to remotely connect to the mechanical dog through the IP address on the OLED (**For specific steps, please see "Remote Login Operation"**).



Then ctrl+c closes the large program and enter the following command to enter docker:

./run_humble.sh

```
TCP Service IP= 192.168.2.145
Waiting for the client to connect!
Waiting for connect to the APP!
^CKeyboardInterrupt
2024-04-28T10:17:27Z
----program end----
pi@raspberrypi:~ $ ./run_humble.sh
access control disabled, clients can connect from any host
root@raspberrypi:/#
```

Then enter the following commands in the docker terminal to start the car radar, imu, and mechanical dog joint status nodes.

ros2 launch bringup Navigation_bringup.launch.py

```
File Edit Tabs Help
at 0x7fff363522f0>
[yahboomcar_joint_state-3] [13.16, 45.61, 1.34, 10.1, 44.36, -1.09, 10.1, 51.85]
2.55, 6.53, 51.22, -0.36]
[yahboomcar_joint_state-3] [-0.17585449218750002, -0.13996582031250002, -9.72702
63671875, -1.0365853658536586, -0.426829268292683, -0.6097560975609757, 0.010487
360583411322, -0.02726797640323639, 5.983139933268229]
[yahboomcar_joint_state-3] *********;
                                ********* <rclpy.timer.Timer object
at 0x7fff363522f0>
[yahboomcar_joint_state-3] [13.16, 45.61, 1.34, 10.1, 44.36, -1.09, 10.1, 51.85,
2.55, 6.53, 51.22, -0.36]
[yahboomcar_joint_state-3] ###################
[yahboomcar_joint_state-3] [-0.14475097656250002, -0.131591796875, -9.7401855468
75, -1.0975609756097562, -0.3658536585365854, -0.6097560975609757, 0.01022947788
9007993, -0.02749979310565525, 5.983139933268229]
                                        *** <rclpy.timer.Timer object
[yahboomcar_joint_state-3] ***
at 0x7fff363522f0>
[yahboomcar_joint_state-3] [13.16, 45.61, 1.34, 10.1, 44.36, -1.09, 10.1, 51.85,
2.55, 6.53, 51.22, -0.36]
yahboomcar_joint_state-3] #################
```

3. Start the program of voice control action group

The steps are the same for PI4 and PI5 versions:

Open another shell or docker terminal and enter the following command in the terminal:

Note: This terminal is used to open the remote connection to the mechanical dog.

```
#pi4
cd ~/cartographer_ws2
source install/setup.bash
ros2 run voice_xgo_ctrl_run voice_xgo_ctrl_action

#pi5
cd yahbomcar_ws/
source install/setup.bash
ros2 run voice_xgo_ctrl_run voice_xgo_ctrl_action
```

```
pi@yahboom:~$

pi@yahboom:~$ cd cartographer_ws2/

pi@yahboom:~/cartographer_ws2$ source install/setup.bash

pi@yahboom:~/cartographer_ws2$

pi@yahboom:~/cartographer_ws2$ ros2 run voice_xgo_ctrl_run voice_xgo_ctrl_action

Speech Serial Opened! Baudrate=115200
```

Then he said to the mechanical dog: "Hello, Xiaoya".

The robot dog will respond: "Yes."

Then say to the mechanical dog: "Command 1" or "Command 2" etc.

Voice commands include: Command 1 to Command 10. The mechanical dog recognizes the voice command and will perform corresponding actions.

Note: After the mechanical dog is awakened by voice, it does not need to be awakened again within 20 seconds.	