

# Standing angle adjustment

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## Quick use

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### 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.



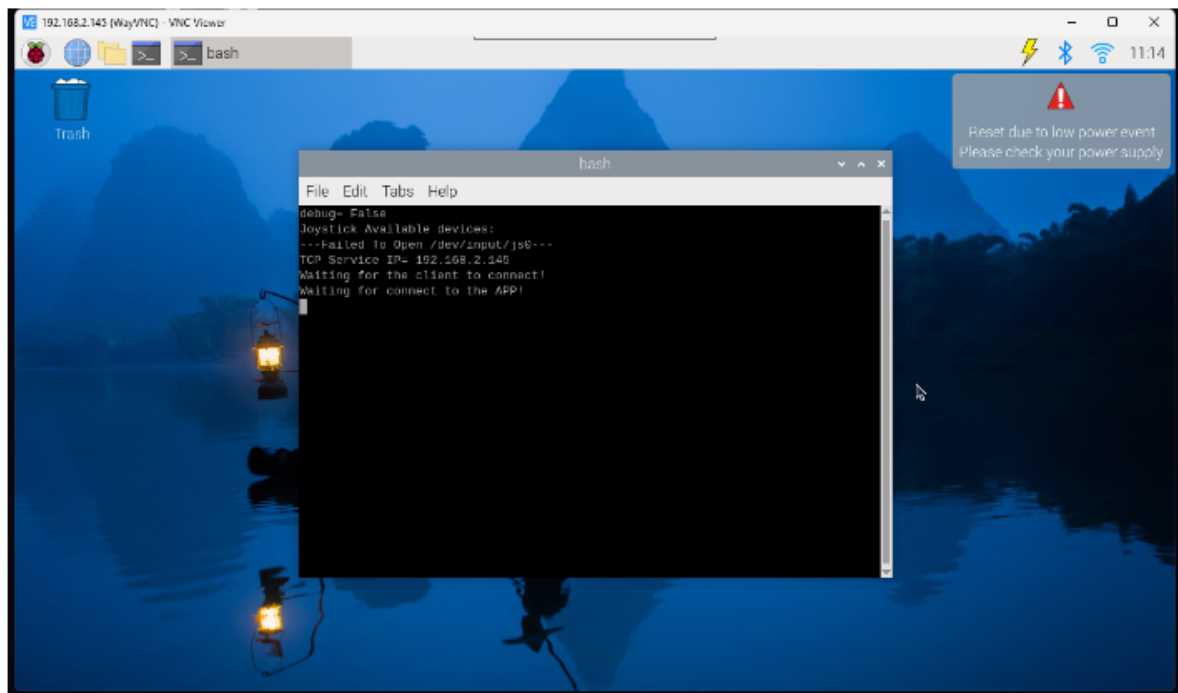
Enter the command in the terminal to start the chassis task.

```
sudo systemctl restart YahboomStart.service
```

```
pi@yahboom:~$  
pi@yahboom:~$  
pi@yahboom:~$  
pi@yahboom:~$  
pi@yahboom:~$ sudo systemctl restart YahboomStart.service
```

### 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
```





```
pi@yahboom:~/cartographer_ws2$ ros2 launch yahboom_set_height yahboomSetHeightLaunch.launch.py xGoHeight:=95 attitude_p:=0 move_x:=0 move_y:=0
[INFO] [launch]: All log files can be found below /home/pi/.ros/log/2023-08-03-20-36-43-673626-yahboom-36098
[INFO] [launch]: Default logging verbosity is set to INFO
<launch.substitutions.launch_configuration.LaunchConfiguration object at 0xffffb1575d90>
[INFO] [yahboom_set_height-1]: process started with pid [36256]
[yahboom_set_height-1] [INFO] [1691066208.277122393] [yahboom_set_height]: xGoHeight_value: 95!
[yahboom_set_height-1] [INFO] [1691066208.283611943] [yahboom_set_height]: attitude_p_value: 0!
[yahboom_set_height-1] [INFO] [1691066208.289951800] [yahboom_set_height]: move_x_value: 0!
[yahboom_set_height-1] [INFO] [1691066208.295725362] [yahboom_set_height]: move_y_value: 0!
[yahboom_set_height-1] 95
[yahboom_set_height-1] 0
[yahboom_set_height-1] 0
[yahboom_set_height-1] 0
```

**Set the parameter `attitude_p` to different values**, the standing angle of the mechanical dog will be different.

Note: The mechanical dog will start walking when `move_x` is greater than 0, please pay attention to safety when using it.