Connect to ROS-WiFi cam module agent

1. Open the agent

If you are using the factory virtual machine system, you can enter in the terminal:

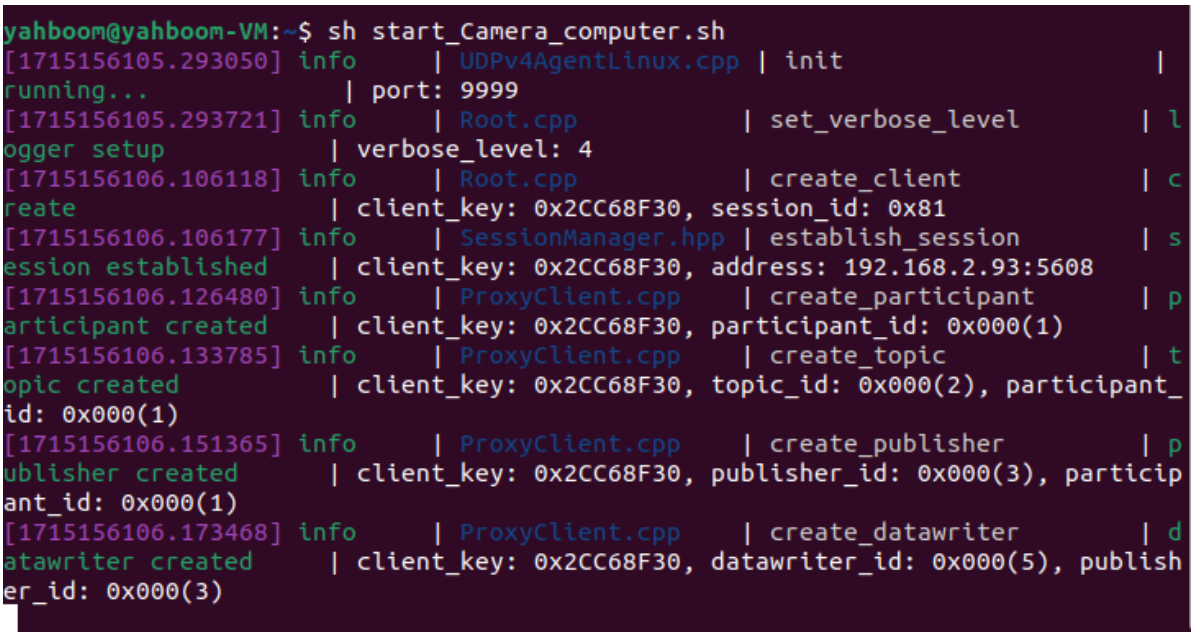
```
sh ~/start_Camera_computer.sh
```

If you are using a third-party virtual machine system, you need to install the docker development environment first, and open the terminal to enter:

```
docker run -it --rm -v /dev:/dev -v /dev/shm:/dev/shm --privileged --net=host
microros/micro-ros-agent:humble udp4 --port 9999 -v4
```

2. Connect to the agent

After the previous tutorials are configured and confirmed,
turn on the power switch of the car to automatically connect to the agent. The connection is successful as shown in the figure below

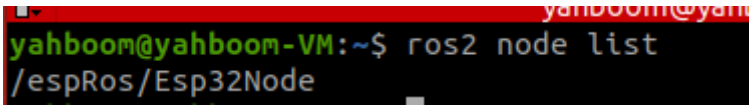


Note: If the connection is not successful, please check and confirm whether the ROS-wifi image transmission module can be connected to the local area network normally and whether the proxy IP address corresponds.

3. Test ROS node

Open the ROS2 terminal environment and enter the following command to view the node name of /espRos/Esp32Node

```
ros2 node list
```

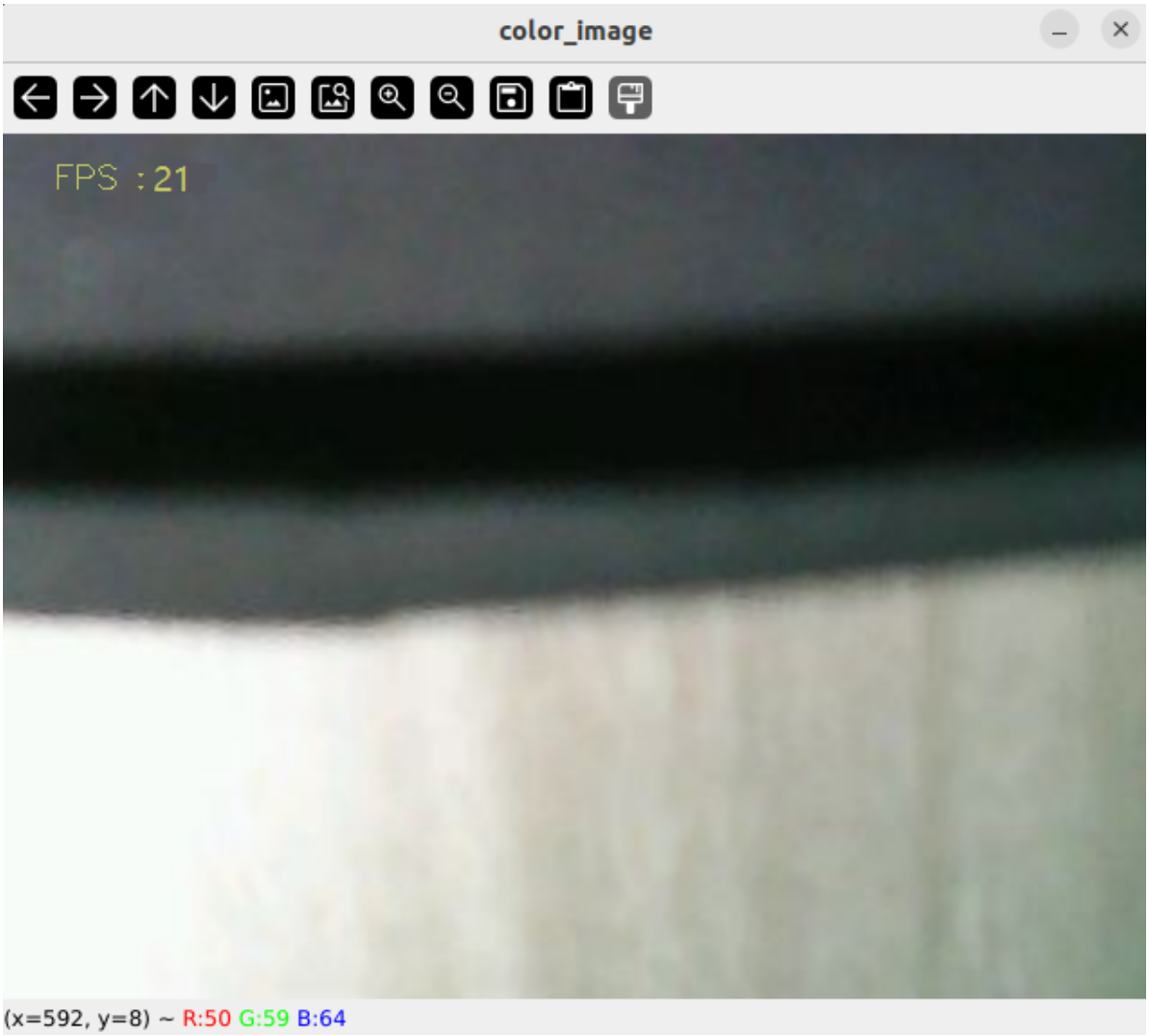


If the /espRos/Esp32Node node cannot be searched, please check and confirm that the ROS DOMAIN ID of the .bashrc file on the virtual machine/computer must be 20. The ROS DOMAIN ID of the micros car must also be 20, otherwise the car cannot perform AI vision gameplay.

4. View the camera screen

1. Open the terminal of the factory virtual machine system and enter

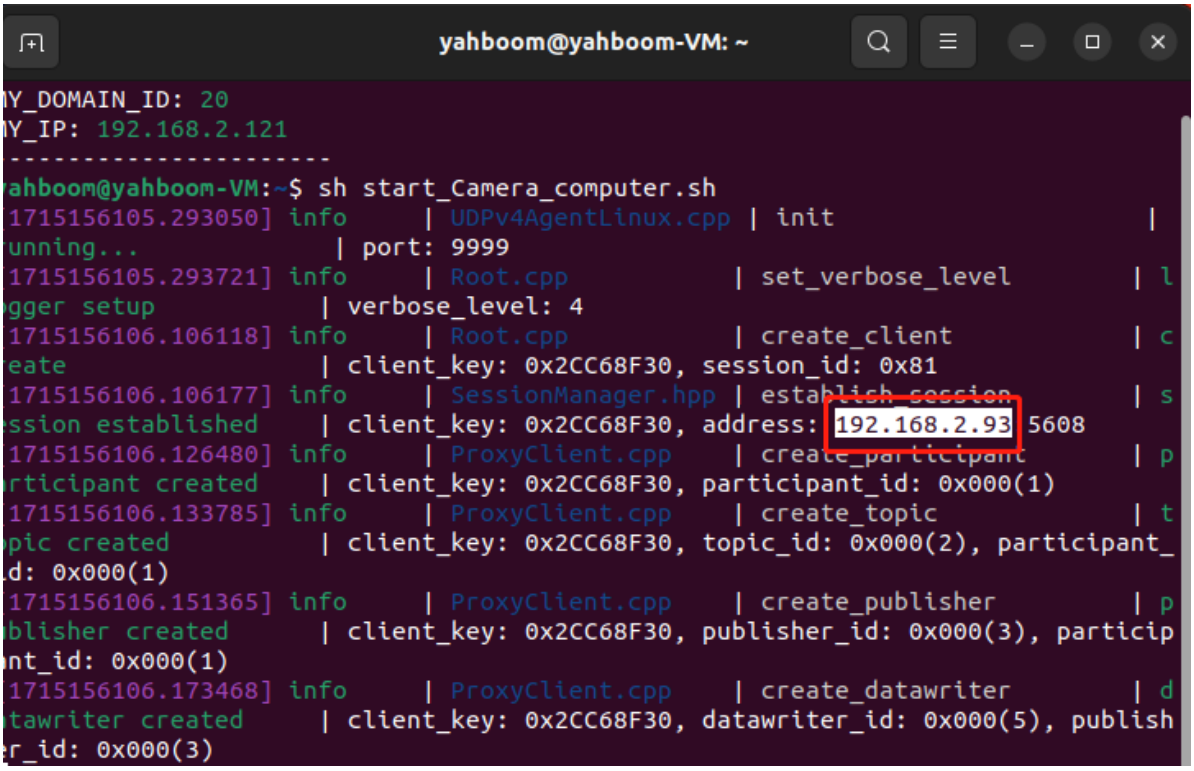
```
ros2 run yahboom_esp32_camera sub_img
```



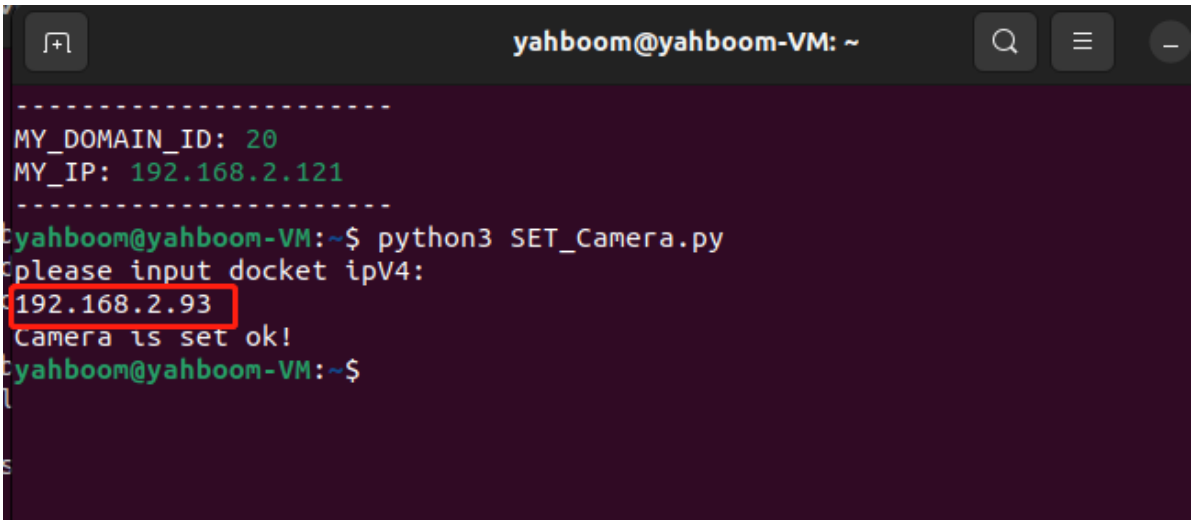
2. If the camera is inverted, open a new terminal and enter

```
python3 ~/SET_Camera.py
```

Then enter the IP address connected to the ROS-wifi image transmission module, and you can view it in the terminal connected to the ROS-wifi image transmission module agent



According to the ip found Enter the IP address in the terminal and press Enter



The image will be restored

If it is a third-party system, you need to transplant it yourself according to the function package of yahboomcar_ws.