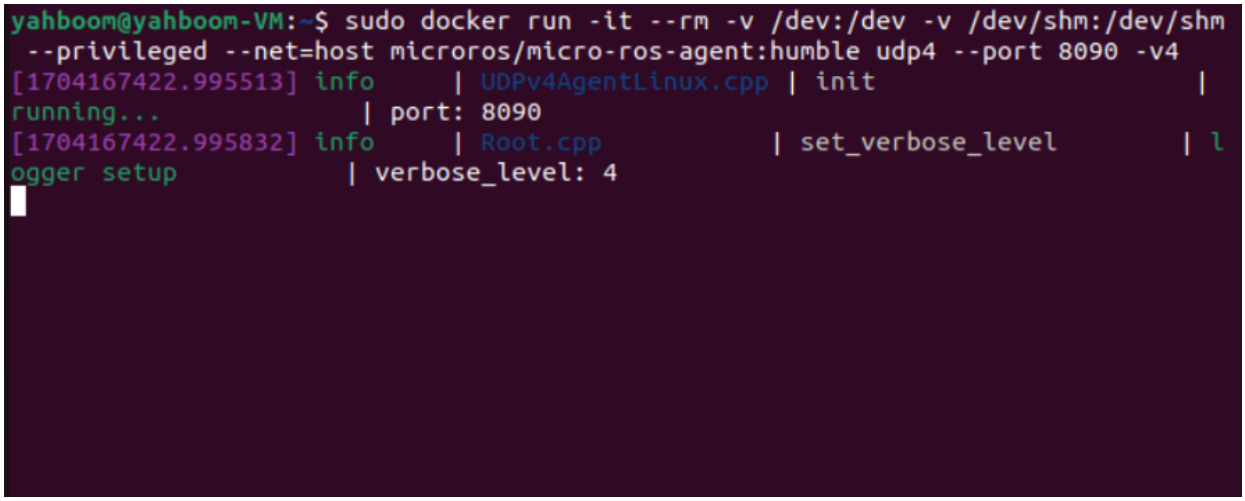
VM handle remote control

Note: The virtual machine needs to be in the same LAN as the car, and the ROS_DOMAIN_ID needs to be consistent. You can check [Must read before use] to set the IP and ROS_DOMAIN_ID on the board.

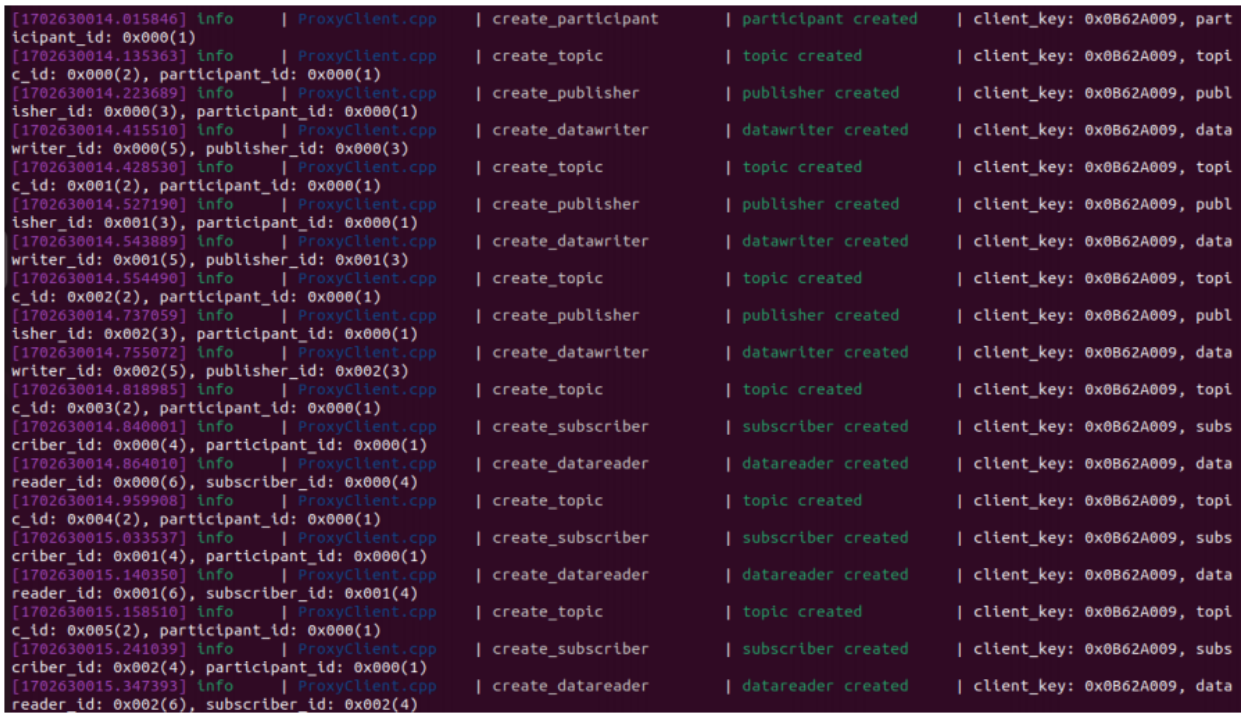
1. Start and connect to the agent

Taking the supporting virtual machine as an example, enter the following command to start the agent:

```
sudo docker run -it --rm -v /dev:/dev -v /dev/shm:/dev/shm --privileged --
net=host microros/micro-ros-agent:humble udp4 --port 8090 -v4
```



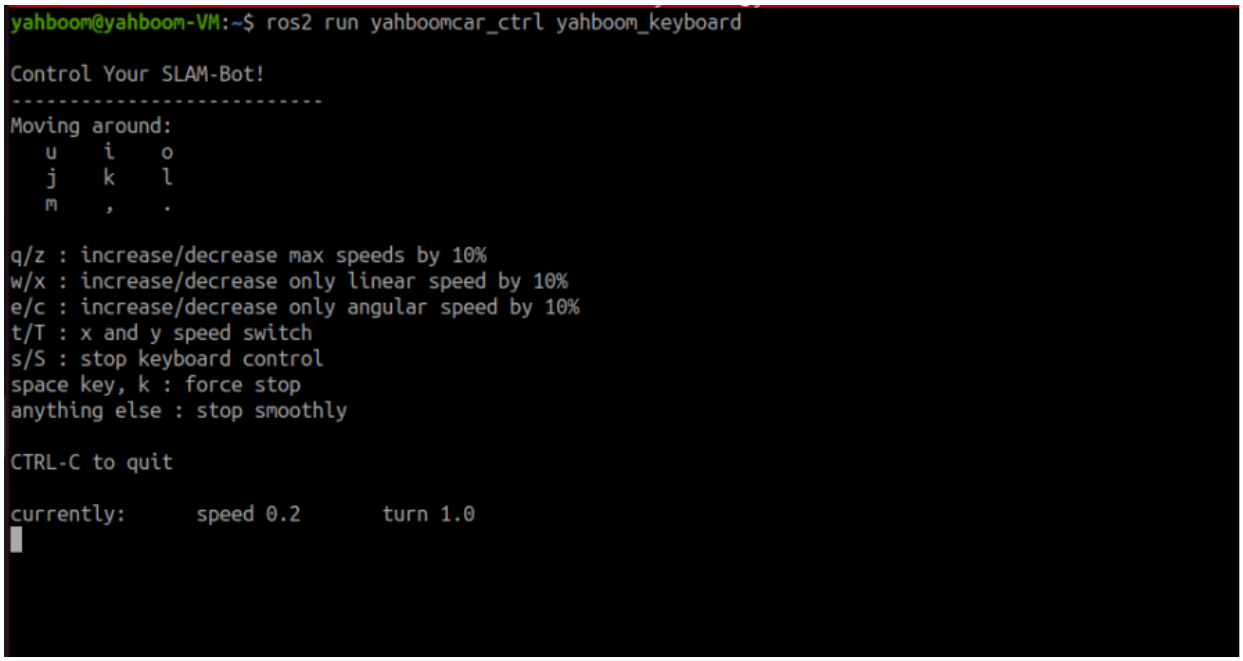
Then, turn on the car switch and wait for the car to connect to the agent. The connection is successful, as shown in the figure below.



2. Start the keyboard control program

Take the supporting virtual machine as an example, enter in the terminal,

```
ros2 run yahboomcar_ctrl yahboom_keyboard
```



Then, according to the instructions below, press the corresponding button to control the movement of the car.

【i】: Go forward 【,】: move back

【l】: Right rotation 【j】: left rotation

【u】: Turn left 【o】: Turn right

【m】: Reverse left 【.】: Reverse right