4.Host computer control

1. Preparation

Please confirm that the computer and robot are connected to the same LAN. Open your computer browser, enter the robot's IP address and port number 8888, for example: for example: http://192.168.1.244:8888

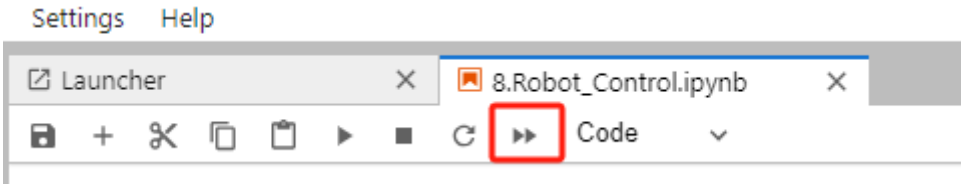
Open the Jupyter Lab web page.

password: **yahboom**

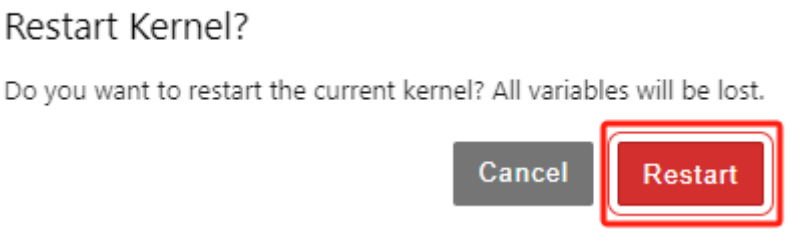
Find the file path and double-click to open: muto/Samples/Control/8.Robot_Control.ipynb

2. Run the web page host computer program

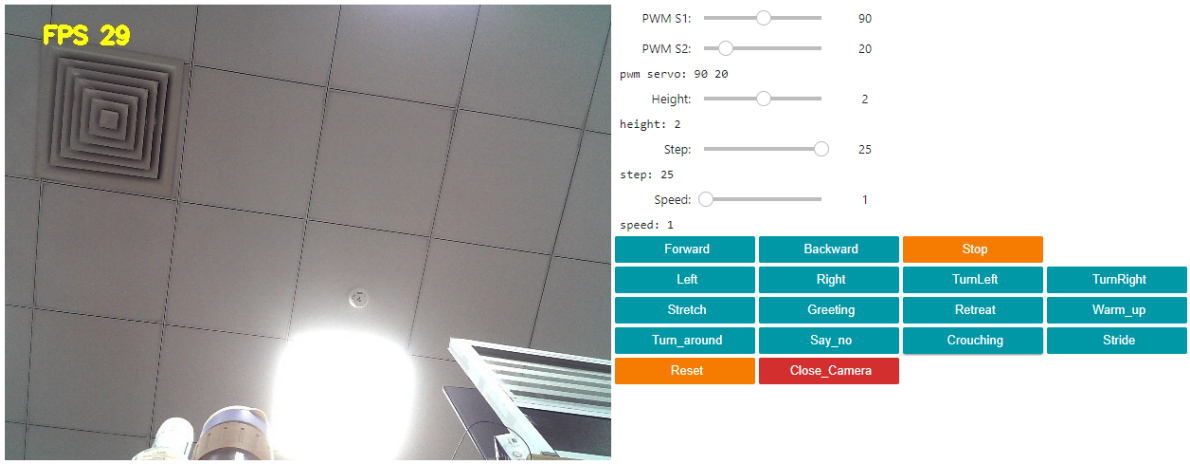
Click the Run button on the web page.



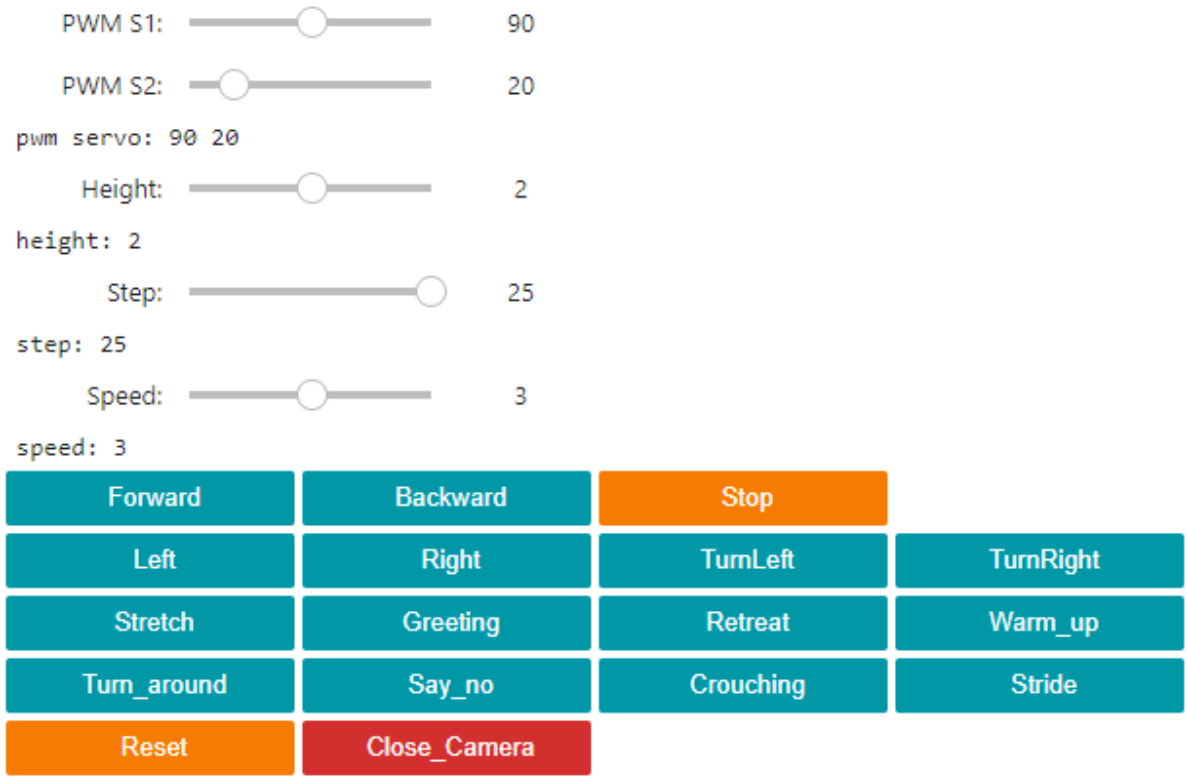
Click Restart when prompted.



Then page down to the end, where you can see the generated controls.



3. Introduction to web host computer functions



Slider:

PWM S1, PWM S2: Indicates the angle of the PWM servo gimbal that controls the robot. (RS version does not have PWM servo PTZ, please ignore)

Height: Control the height of the robot.

Step: Controls the robot's step width.

Speed: Control the robot's foot speed.

Button:

Forward: Control the robot to move forward.

Backward: Control the robot to move backward.

Stop: Control the robot to stop.

Left: Control the robot to move left.

Right: Control the robot to move right.

TurnLeft: Control the robot to turn left.

TurnRight: Control the robot to turn right.

Stretch: Control the robot to display stretching movements.

Greeting: Control the robot to show greeting actions.

Retreat: Control the robot to show fear and retreat.

Warm_up: Control the robot to perform warm-up squat movements.

Turn_around: Control the robot to rotate in circles.

Say_no: Control the robot to show the waving and saying no action.

Crouching: Control the robot to display the squatting movement.

Stride: Control the robot to show stride action.

Reset: Stops the robot and restores the default position.

Close_Camera: Close the camera thread. To prevent the program from occupying camera resources and causing other programs to be unable to run, please close the camera thread in time when you do not need to run this program.