

Web page host computer remote control

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1. Preparation before operation
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1. Preparation before operation

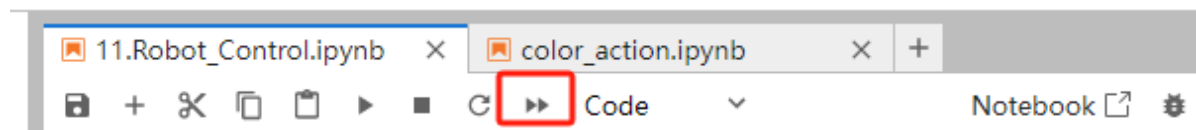
Please confirm that the computer and robot are connected to the same LAN. Open your computer browser, enter the robot's IP address in the URL bar: port number 8888, and open the Jupyter Lab web page.

Enter Jupyter Lab password: yahboom

Find the file path and double-click to open: muto/Samples/Control/11.Robot_Control.ipynb

2. Run the web page host computer program

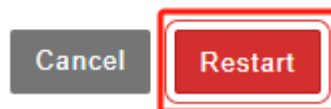
Click the Run button on the web page.



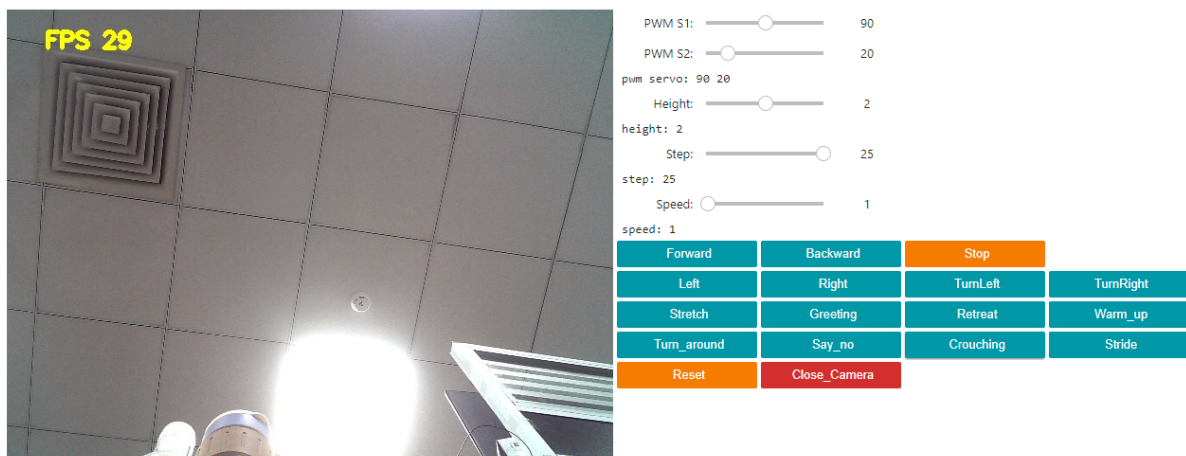
Click Restart when prompted.

Restart Kernel?

Do you want to restart the current kernel? All variables will be lost.



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



3. Introduction to web host computer functions

PWM S1: 90
PWM S2: 20
pwm servo: 90 20

Height: 2
height: 2

Step: 25
step: 25

Speed: 3
speed: 3

Forward	Backward	Stop	
Left	Right	TurnLeft	TurnRight
Stretch	Greeting	Retreat	Warm_up
Turn_around	Say_no	Crouching	Stride
Reset	Close_Camera		

Slider:

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