FAQ analysis

1. What is the difference between Muto robot S1 version and S2 version?

Answer: The S1 version uses the PS2 controller control method. After successful installation, you can use the PS2 controller to control it without programming. The S2 version uses a jetson nano or Raspberry Pi master controller and supports Python programming control.

2. What should I do if the camera cannot read the data?

Answer: Confirm that there is no problem with the hardware connection. Please exit the program, re-plug and unplug the device USB cable, and check whether there is a /dev/video0 device number. If not, please restart the system.

3. How is the robot powered?

Answer: The car is equipped with a battery pack at the factory. Connect the T-shaped interface of the battery pack to the battery interface of the expansion board through an adapter cable. Turn on the main power switch. The expansion board integrates a voltage conversion chip for use by various devices.

4. Which functions on the expansion board are managed by the microcontroller?

Answer: The parts managed by the microcontroller on the expansion board include: status indicators, buzzers, attitude sensors, RESET keys, PWM servo interfaces, serial servo interfaces, etc.

5. Why should we close the APP control program? What impact does it have on program development?

Answer: In order to experience the convenience of the control program, the robot automatically runs the APP control program when it is turned on, but it will occupy resources such as the camera and serial port. Before actually developing the routine, you need to close the APP control program to avoid the routine calling resources such as cameras and serial ports and reporting errors. If you do not use APP control for a long time, you can permanently close the APP control program according to the tutorial.

6. What should I do if one of the legs does not touch the ground when the robot returns to rest?

Answer: Please connect to the APP control software, find the robot calibration, and follow the calibration steps to recalibrate the servos on the robot legs.

7. What should I do if I still give priority to connecting to the WiFi signal at home after turning on the hotspot mode?

Answer：Since both hotspot mode and connecting to WiFi signals use WiFi devices, they have startup priority. Please set the priority in hotspot mode to be higher than the WiFi signal at home, so that the hotspot will be transmitted first.

8. What should I do if the color recognition or color tracking function is not accurate??

Answer：Because there may be certain differences in the color of the object, and different usage environments and different lighting brightness will also produce differences. Please follow the HSV calibration tutorial and update the calibrated HSV data to the corresponding routine after calibration.

9. The robot automatically squats down and simultaneously emits a "di-di-di-di" whistle alarm. What should I do?

Answer：This state is the low voltage protection state of the robot. Please turn off the power and charge the robot in time.

10. What is the status meaning of the indicator light on the robot expansion board?

Answer：POWER indicator light: Indicates the power supply status of the robot. It is normally on and off when it is abnormal. MCU indicator light: Indicates the operating status of the microcontroller. It flashes twice every 3 seconds in the normal state. It flashes continuously when the battery is low. If it is always on or off, it indicates that the microcontroller is operating abnormally.