

3. USB wireless handle + mobile phone screen remote control tutorial

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3.1. Open steps

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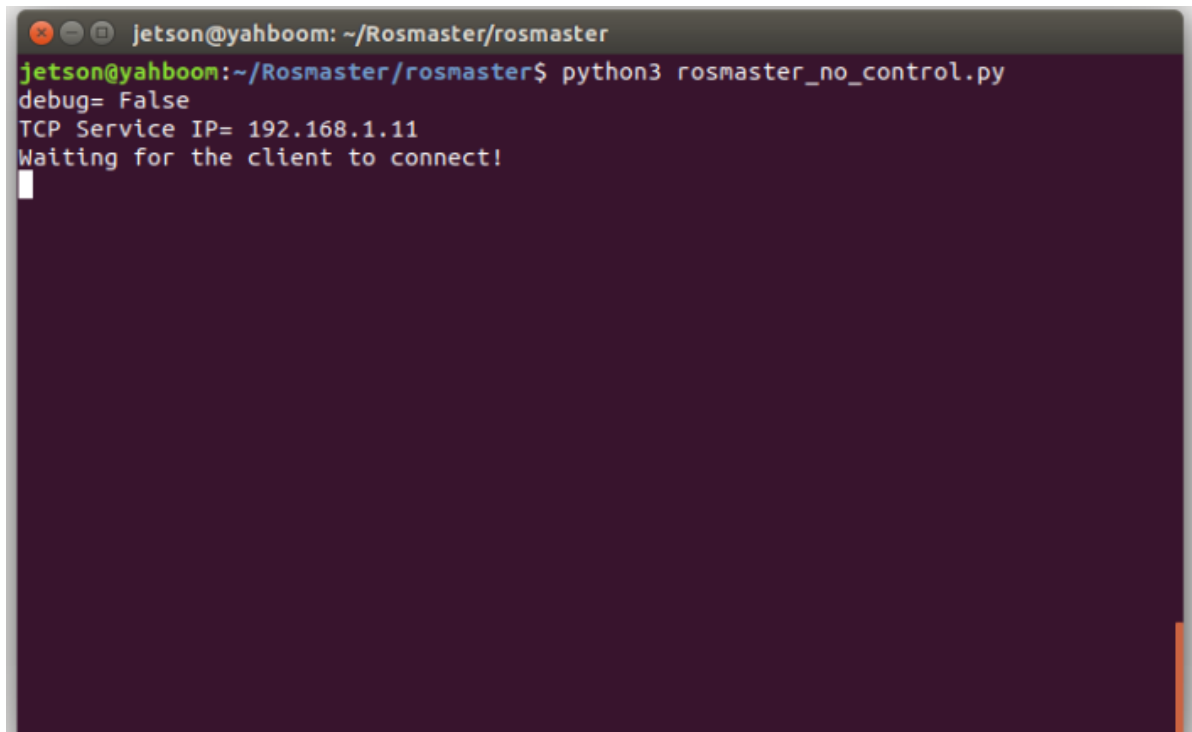
- After booting into the program, first close the large program, you can refer to the second section of "05. ROSMASTER Basic Control Tutorial" "2. Turn off the self-starting large program".
- Open a terminal, type,

```
roslaunch yahboomcar_bringup bringup.launch #launch chassis + remote control
```

- Open another terminal and enter

```
cd ~/rosmaster/rosmaster
```

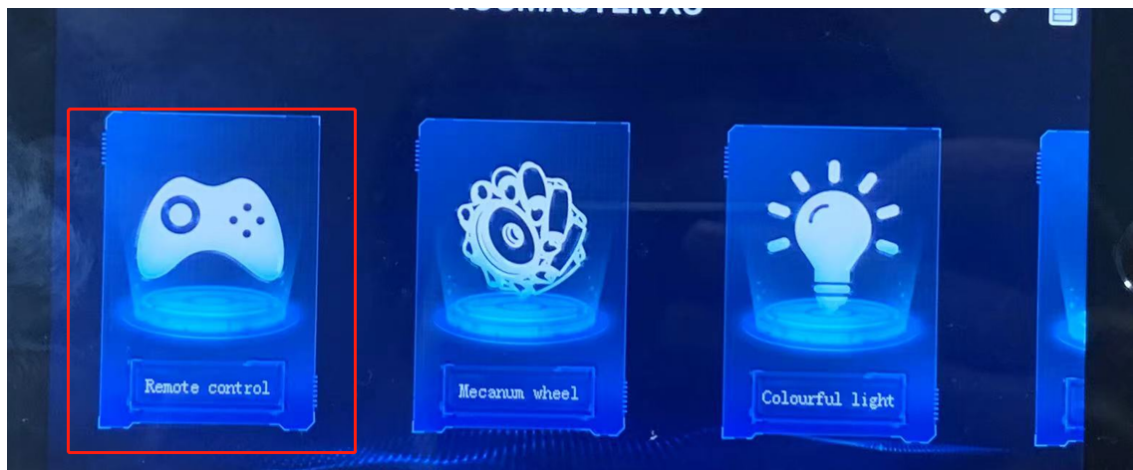
```
python3 rosmasetr_no_control.py
```

A terminal window screenshot with a dark purple background. The prompt is 'jetson@yahboom: ~/Rosmaster/rosmaster'. The command 'python3 rosmasetr_no_control.py' has been executed. The output shows 'debug= False', 'TCP Service IP= 192.168.1.11', and 'Waiting for the client to connect!'. A white cursor is visible on the line following the last message.

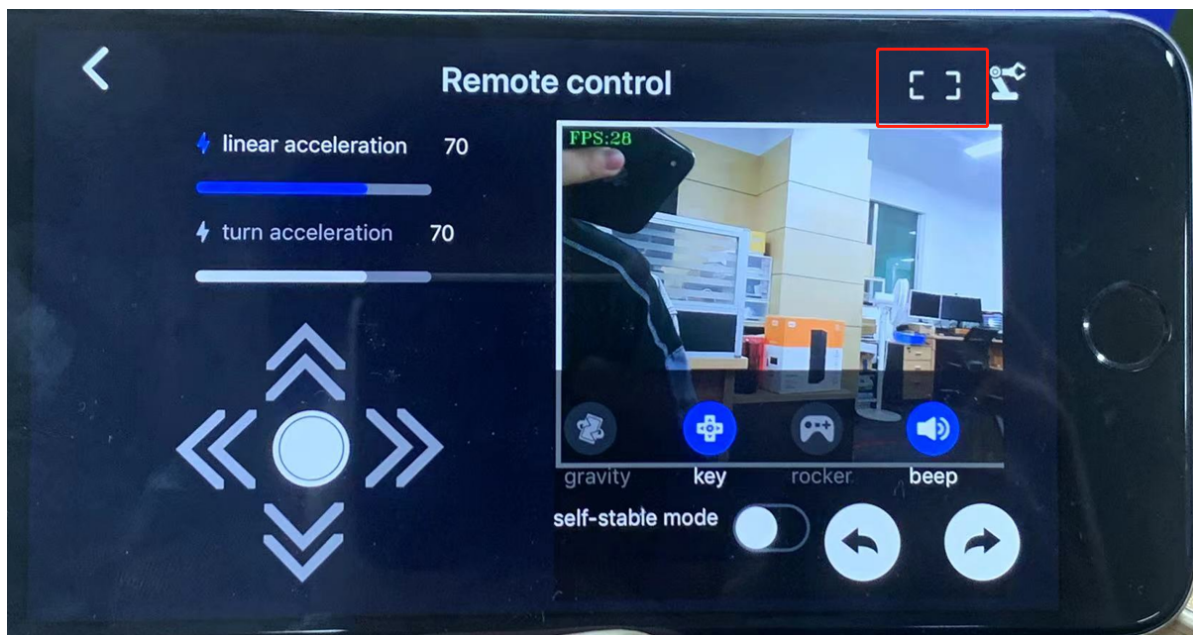
```
jetson@yahboom: ~/Rosmaster/rosmaster
jetson@yahboom:~/Rosmaster/rosmaster$ python3 rosmasetr_no_control.py
debug= False
TCP Service IP= 192.168.1.11
Waiting for the client to connect!
█
```

- Refer to the "Mobile APP Remote Control Tutorial" in "03. Mobile Phone Remote Control Tutorial", connect the mobile phone to the rosmaster, and then you can see the screen transmitted by the rosmaster on the mobile phone screen.

[Click here to enter the control screen](#)



Click here for full screen viewing,



- Fix the phone on the handle, press the start button on the handle, and you can control it after you hear a beep.