Enter the robot's docker container

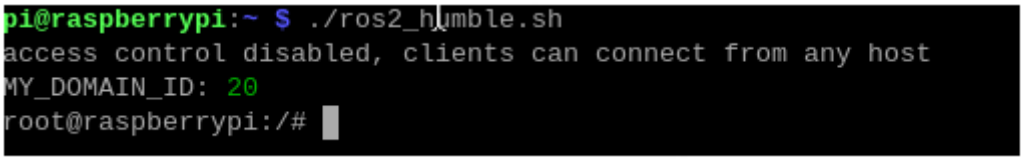
Note: The ROS_DOMAIN_ID of the Raspberry Pi and the microROS control board need to be consistent. You can check **[MicroROS Control Board Parameter Configuration]** to set the microROS control board ROS_DOMAIN_ID. Check the tutorial **[Connect MicroROS Agent]** to determine whether the IDs are consistent.

1、Enter the robot docker

Taking the supporting Raspberry Pi as an example, enter the following command to enter the docker container.

```
./ros2_humble.sh
```

When the following interface appears, you have entered docker successfully. Now you can control the car through commands.



It should be noted that this ID needs to be consistent with the ID configured in the MicroROS control board parameters in the previous section, so that synchronous communication can be performed to control the car. Enter the following command to test whether communication is successful.

```
ros2 node list
```

2、Enter the same docker from multiple terminals

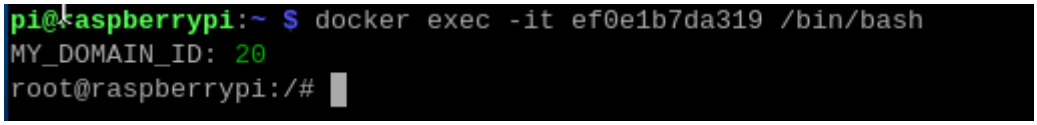
Reopen a new terminal in the Raspberry Pi and enter the command.

```
docker ps -a
```

You can see the ID number you used to enter docker and the docker version.

You can enter the same docker based on this ID number. Note that the ID number is different every time you enter the docker. Enter the command.

```
docker exec -it ef0e1b7da319 /bin/bash
```



When this screen appears, we have entered the same docker.