



Raspberry Pi catkin_ws/ catkin workspace. Holds catkin packages for mmm_control basic control of robot i2c.py Arduino_ROS_bridge.py writeData(noun, mp3 files verb) **ROS loop** sends commands to Arduino via I2C subscribe to "joint command" topic thingy and relays that audio.py readData() play sounds from the speaker! to Arduino reads data from Arduino via I2C returns a list of integers. publish joint states to ROS topic /joint_states



