# Poppy Generation Robots Replayer

## Application installation

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# 1. Installation of the Poppy program

## 1.1. Flashing an eMMC card

To prepare a new eMMC card for Poppy Humanoid, flash an eMMC card with the last version of Poppy Humanoid, and then connect on your robot by typing in a terminal:

```
ssh poppy@poppy.local
password : poppy
```

## 1.2. Pypot configuration

Modify the Poppy Humanoid configuration, if not already done, in the file:
*/usr/local/lib/python2.7/dist-packages/poppy_humanoid/poppy_humanoid.py*

Change :
```
        for m in robot.motors:
            m.goto_behavior = 'minjerk'
```
in :
```
        for m in robot.motors:
            m.goto_behavior = 'dummy'
```

## 1.3. Loading the Poppy program

Download the Poppy program source code:
*https://github.com/generationrobots-lab/Poppy_GRR*

- Modify the file **serverPoppy/CONFIG.json** to configure the application according to your robot. The "value" field for each parameter must be modified:
    - **poppyName** : corresponds to the robot name. By default, its name is *poppy.*.
    - **kinectName** : corresponds to the Kinect server name if it exists. If no Kinect exists, put '*none'*
    - **wrists** : put to *True* if articulated wrists are on the robot, *False* if not.
    - **ScreenOn** : activates the screen or not. put to *False* if no screen is connected.
    - **fullScreen** : activates the fullscreen mode if put to *True*.
    - **Volume** : configures the volume of the robot voice. the value is comprised between *0 and 1*.
    - **internet** : set to *True* if the robot is connected to the internet.
    - **creature** : nature of the robot : *humanoid* or *torso*.
    - **nb_demo** : if kinect exists, number of repetitions by the robot before repetitions by the person alone.
    - **seuil_bien** : if kinect exists, threshold to determine if the exercise has been correctly reproduced or not.

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- **seuil_nul** : if kinect exists, low threshold to determine if the exercise has been badly reproduced or not.
- **first** : activates beginner mode. It plays full session first before the patient do the exercises.

The robot is then ready to use. The only thing left to do is to execute the Poppy server by typing:

*python serverPoppy/poppyserver.py*

The web interface can now connect to the robot.

# 2.  Web interface installation

## 2.1.  Loading the web interface

The web interface can be downloaded as the Poppy program. Its repertory is *poppyApp*.

Put the repertory */poppyApp/* in:
- using WAMP (windows): *C:/wamp/www/*
- using LAMP (linux): */var/www/html/*

## 2.2.  Configuration

Then, the file */poppyApp/core/database/connect.php* must be modified: to the lines 12 and 13, put your login of your database.

Next, modify the file */poppyApp/JS/functions.js* : replace at the line 7 the "poppyName", and put the name of your Poppy (by defaut poppy.local) or its IP address.

Finally, import the database ProjetKERAAL from the file *ProjetKERAAL.sql*, in the page *http://localhost/phpmyadmin*.

## 2.3.  Executing

Note : if you are using Windows, please download and install first Bonjour software.

After launching your server (Apache…), open the web interface by typing the following URL : http://localhost/poppyApp/poppyGRR.php.