To connect Linux computer to Rehema Wifi network:

1. Go to Wifi dropdown in top right corner of screen
2. Connect to Hidden Wi-Fi Network…
3. Set Wi-Fi Security to WPA & WPA2 Personal
4. Network name: Rehema
5. Password: qazWSX11!!

To connect Linux computer to NAO6 robot:

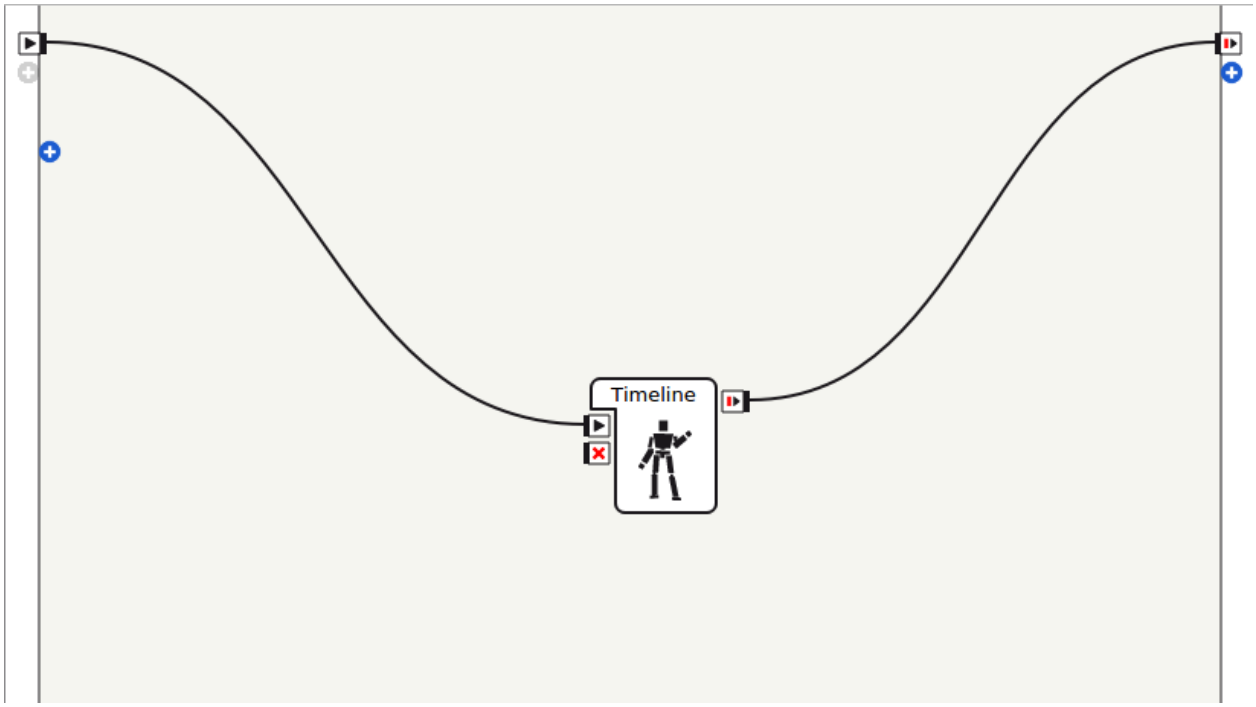
1. Download and Open Robot Settings
    a. In terminal, type “nautilus /opt”, which will open a folder in the file explorer
    b. Go to the Softbank Robotics -> Robot Settings -> bin
    c. Open the robot_settings file
2. Under the “Connect to a Robot” section, press Connect
3. Press the “Manually add a NAO” button
4. In the “Host / IP Address” field, the robot’s IP Address is 134.82.159.168

To connect NAO6 to Choregraphe:

1. Open Choregraphe, go to the top left, and press on  .
2. Tick the box “Use fixed IP/hostname”
3. Tap NAO’s power button to record the Wi-Fi IP address (should be 134.82.159.168)
4. Input NAO’s Wi-Fi IP address into Choregraphe
5. You are now connected to NAO through Choregraphe.

Creating Animations with Choregraphe:

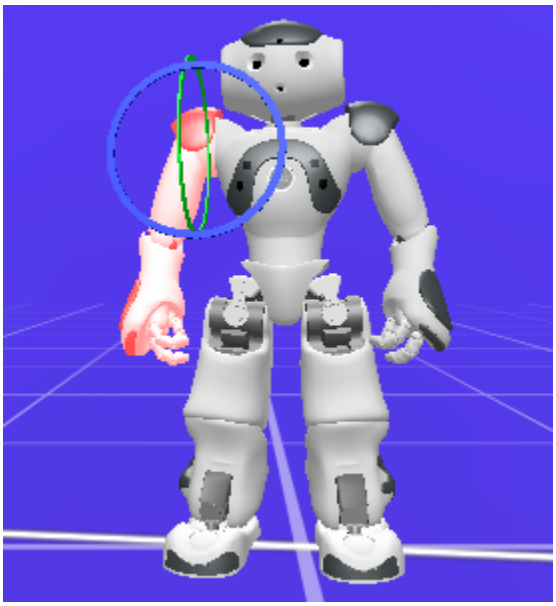
1. Open Choregraphe and connect to the robot
2. On the left side of the screen, in the Box libraries menu, go to Animation -> Creation and drag the Timeline box into the main working area.
3. Click and drag to connect the Timeline box to the onStart and onStopped boxes of the main working area.



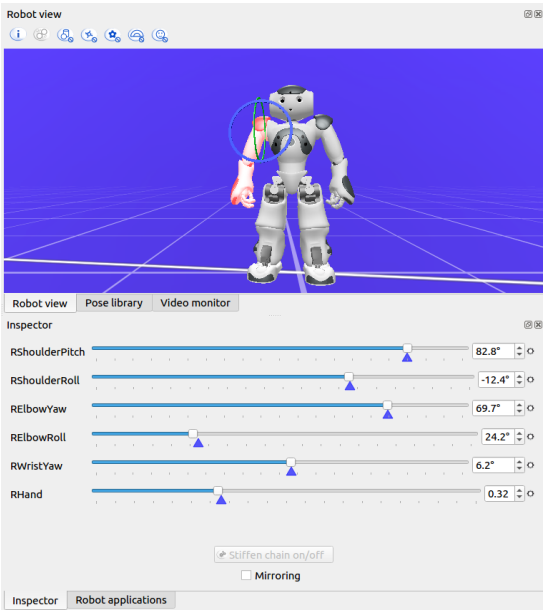
4. Double click on the Timeline box to enter the editor for the Timeline
5. At the top of the screen, click within the timeline as seen below to select a timestamp for which you want to change the robot's pose

6. You then have two options for how to move the joints of the robot:
    a. Using Choregraphe:

i. Using the Robot view on the right side of the screen, click on one of the limbs of the robot to bring up rotation wheels for that limb as seen below



ii. You can either use these rotation wheels to move the joints on the robot or you can go to the Inspector tab at the bottom of the Robot View window as shown below and change the rotation of each joint using the sliders.



b. Using the physical robot:

   i. At the top right of Choregraphe, press the Animation Mode button  to enter animation mode

   ii. Once in animation mode, on the physical robot, there are different triggers that will allow you to move each limb freely:

      1. To unstiffen the head, tap and hold on the middle sensor on the top of NAO's head
      2. To unstiffen the left arm, tap and hold on the touch sensor on the back of NAO's left arm
      3. To unstiffen the right arm, tap and hold on the touch sensor on the back of NAO's right arm
      4. To unstiffen the left leg, tap and hold on the touch sensor on the front of NAO's left foot
      5. To unstiffen the right leg, tap and hold on the touch sensor on the front of NAO's right foot

   iii. Once a limb is no longer stiff, you can move it freely to the desired position. Release the appropriate touch sensor to stiffen the joint and store the position

7. Click on a new point on the timeline and repeat steps 6 and 7 to make additional movements for the robot.

8. To run this animation, press the green play button  at the top of Choregraphe.