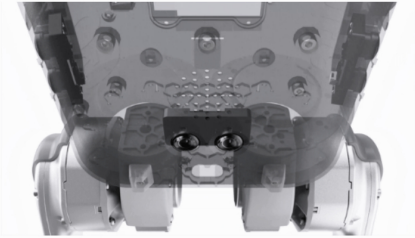


GO1 QUADRUPED TUTORIALS



This package supplies Sphinx-based tutorial content to assist you with setting up and operating your **GO1** quadruped robot. The tutorials topics are listed in the left column, and presented in the suggested reading order.

KEY FEATURES

- Fastest running speed of 4.7m/s (10.5mph, close to the speed of professional long-distance runners)
- ISS intelligent accompanying system, patented wireless vector positioning and control technology
- v555 super sense system, 5 groups of fisheye binocular depth perception + fisheye AI perception + 3 groups of ultrasonic
- Built-in super AI computing power with 16-core top CPU + GPU (384Core, 1.5TFLOPS)

Warning

These tutorials assume that you are comfortable working with ROS. We recommend starting with our [ROS tutorial](#) if you are not familiar with ROS already.

Simulation is a logical place for most users to start, as this is universally applicable; understanding how to effectively operate GO1 in simulation is valuable whether you are in the testing phase with software you intend to ultimately deploy on a real GO1, or you do not have one and are simply exploring the platform's capabilities.

Navigation is a follow-on to what is learned in the simulation tutorial, as navigation and map-making may be run in the simulated environment. However, this content is applicable to both the simulator and the real platform, if equipped with a laser scanner or lidar.

The remainder of the subjects are more applicable to the real robot, and have to do with configuring, using, and maintaining the platform. If you are a lab administrator rather than direct platform user, you may wish to skip the introductory chapters and jump straight to these ones.

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