

USB Handle Control

Start USB Handle Control Program

The robotic arm factory image is configured to start the handle control function together with the app control service at boot, and can be directly connected for control.

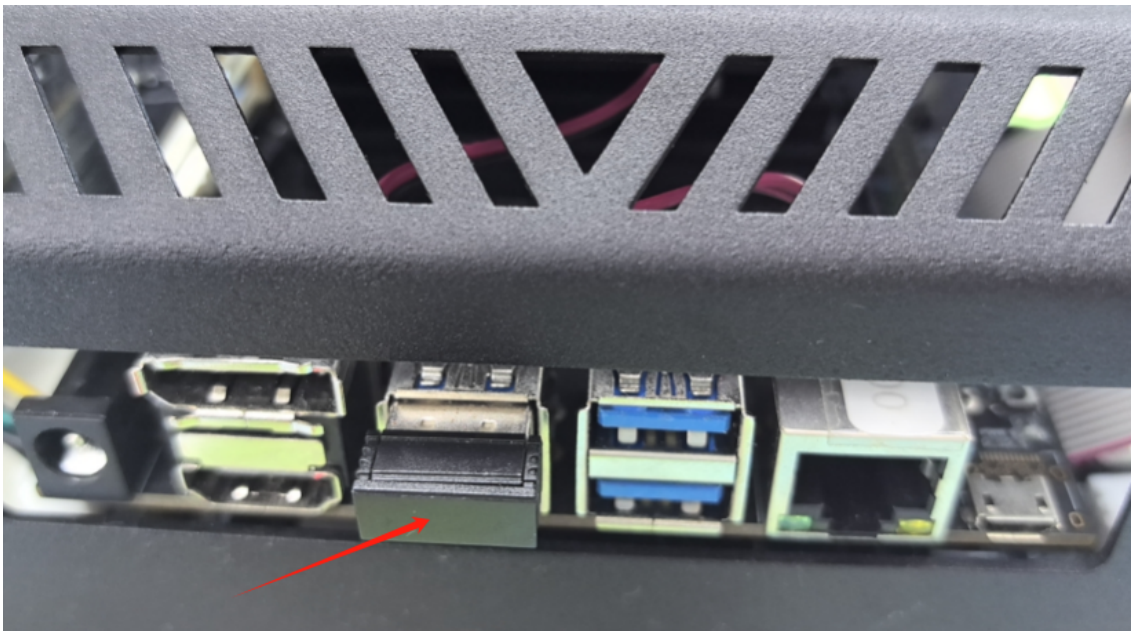
If you have closed the app auto-start service, you can also start the USB handle control program through the following command.

Open the system terminal and enter the following command

```
python3 /home/jetson/dofbot_pro/APP_DOFBOT_PRO/joystick.py
```

Connect USB Handle

1. Confirm that the USB wireless handle receiver is inserted into the USB port of the motherboard before booting.



2. Install the wireless handle battery.



3. Turn the wireless handle power switch to [ON].



4. Press the [START] key once to activate the handle. After successful connection, press the [START] key again, and the buzzer will beep once.
5. At this point, you can start controlling the robotic arm.

USB Handle Button Functions

The button functions are shown in the figure below:



- ①: Up and down control joint 2, left and right control joint 1.
 - ②: Up and down control joint 3, left and right have no function.
 - ③: Up and down control joint 4, left and right control joint 5.
 - ④: Y and A control joint 6 (gripper), X and B have no function.
 - ⑤: L1 controls robotic arm speed increase, L2 controls robotic arm speed decrease.
 - ⑥: R1 controls gripper to grab 3cm building blocks, R2 controls gripper to release.
 - ⑦: [SELECT] controls robotic arm joint angles to return to initial position.
- [START] activates the handle, buzzer beeps.
- [MODE] mode switch, please do not press this button.

Note: When the wireless handle is idle for a few minutes, it will automatically enter sleep mode. At this time, you need to press the [START] key to activate the handle. After hearing the buzzer beep, you can start controlling the robotic arm.