

Handle remote control robot arm

1. Hardware connection

1. Make sure that the USB wireless handle receiver has been inserted into the USB port of the motherboard before turning on the computer.



USB无线
手柄接收器

2. Install the battery of the wireless handle and turn the power switch of the wireless handle to [ON].



2. Start the handle program

Before starting the handle control program, you need to make sure that the APP control program is closed, otherwise it will cause interference.

Run the handle control program

```
ros2 launch jetcobot_ctr1 yahboom_joy.launch.py
```

```
jetson@yahboom: ~  
[System Information]  
ROS: humble  
DOMAIN_ID: 98  
IP_Address_1: 192.168.2.80  
IP_Address_2: 192.168.2.114  
jetson@yahboom:~$ ros2 launch jetcobot_ctrl yahboom_joy.launch.py  
[INFO] [launch]: All log files can be found below /home/jetson/.ros/log/2025-05-07-11-39-38-104159-yahboom-25501  
[INFO] [launch]: Default logging verbosity is set to INFO  
[INFO] [joy_node-1]: process started with pid [25539]  
[INFO] [yahboom_joy-2]: process started with pid [25542]  
[joy_node-1] [INFO] [1746589178.949105195] [joy_node]: No haptic (rumble) available, skipping initialization  
[joy_node-1] [INFO] [1746589178.949429069] [joy_node]: Opened joystick: Controller. deadzone: 0.050000
```

3. Key operation

Press the [START] key to activate the handle.

You can now start controlling the robot arm. The key 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 A controls joint 7 (gripper), X B controls joint 6.
- ⑤: L1 controls the robot arm speed to increase, L2 controls the robot arm speed to decrease.
- ⑥: R1 controls the gripper to clamp immediately, and R2 controls the gripper to release immediately.
- ⑦: [SELECT] button controls the arm joint angle to return to the initial position.

[START] activates the handle.

[MODE] mode switch, do not press this button.

Note: When the wireless handle is idle for a few minutes, it will automatically enter the sleep state. At this time, you need to press the [START] button to activate the handle before you can control the arm.