

# Common Problems and Solutions

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## 1. How is Jetcobot powered?

Answer: The robot arm is powered by a DC 12V 5A power adapter, the Jetson Orin NX/Nano motherboard is powered by a DC 19V 2.37A power adapter, and the Jetson Nano motherboard is powered by a DC 5V 4A power adapter. Since all three power adapters are DC interfaces, in order to avoid burning the device due to incorrect insertion, please carefully check the power supply voltage of the power adapter before inserting the power adapter.

## 2. How does Jetcobot access data in Docker through JupyterLab?

Answer: Open the browser, then enter the IP address of Jetcobot: 8889, and then press Enter to enter.

## 3. Why do you need to close the APP control program? What impact does it have on program development?

Answer: In order to experience the convenience of the control program, the robot automatically runs the APP and wireless handle control program when it is turned on. Before running the development routine, in order to avoid the routine calling resource failure or interference, you need to close the APP control program first. If you do not use APP control for a long time, you can permanently close the APP control program according to the tutorial.

## 4. What does the environment variable MY\_SERIAL mean?

Answer: MY\_SERIAL represents the serial port symbol, which points to "/dev/ttyUSB0" by default. If you need to modify it, please edit the .bashrc file in the /root directory in the Docker container, find export MY\_SERIAL="/dev/ttyUSB0", save it after modification, and restart the terminal to take effect. If it is the Jetson Nano system version, you need to modify the .bashrc file in the jetson user directory.

## 5. Use the **send\_coords** function to control the movement of the robot arm coordinates. What should I do if the robot arm does not execute the command?

Answer: The robot arm coordinates have a certain limit range. If it exceeds the control range or the position is unreachable, the robot arm automatically ignores the command and does not execute the action. For the input coordinate range of the robot arm, please refer to the instructions in [Control Robot Arm Course-Sending Data].