

# First-time use instructions

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1. The product is equipped with multiple power adapters with the same interface type but different voltages. To avoid burning the device due to wrong insertion, please check and confirm before powering on the device.
2. The robotic arm will automatically stand up after powering on. Please place the robotic arm in an area with enough space before powering on.
3. Jetson Orin NX and Jetson Orin Nano use the Docker image environment. Before running the program, you need to enter the Docker environment first and then run the program. Jetson Nano uses the native environment and can run the program directly in the terminal.
4. Jetson Orin NX/Orin Nano uses the Docker image environment, while Jetson Nano uses the motherboard native system image environment. The factory images of the two have been compatible in code, and the types are distinguished by the system version, so that each can execute the required content.
5. Jetson Nano's moveit course needs to be run in a virtual machine.
6. The default jupyterlab port number for Jetson Orin NX and Jetson Orin Nano motherboards is 8889, and the default port number for Jetson Nano is 8888.
7. If you do not need to start the APP control program automatically at startup, you can enter the command 'sudo systemctl disable yahboom\_app.service' to permanently shut down the APP and handle control programs. The next time you start the computer, the APP and handle control programs will not be automatically started.
8. If you do not need to start docker and JupyterLab automatically at startup, you can enter the command 'sudo systemctl disable yahboom\_docker.service' to permanently shut down the docker container and JupyterLab. The next time you start the computer, the docker container and JupyterLab will not be automatically started.