Getting Started

Preparation

After checking that the USB device is connected correctly, check the power adapter interface of the motherboard and the robot arm, then plug them into the power interface of the motherboard and the robot arm respectively, and wait for the robot arm system to start, which takes about 1 minute. After the system starts, the robot arm will initialize and stand upright.

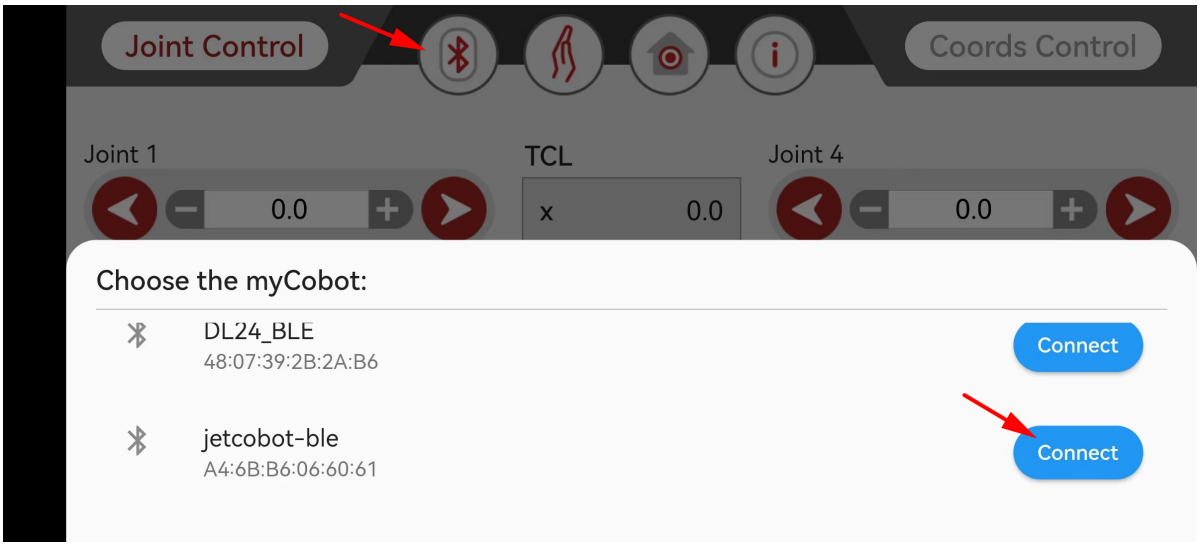
APP remote control

1. Download APP

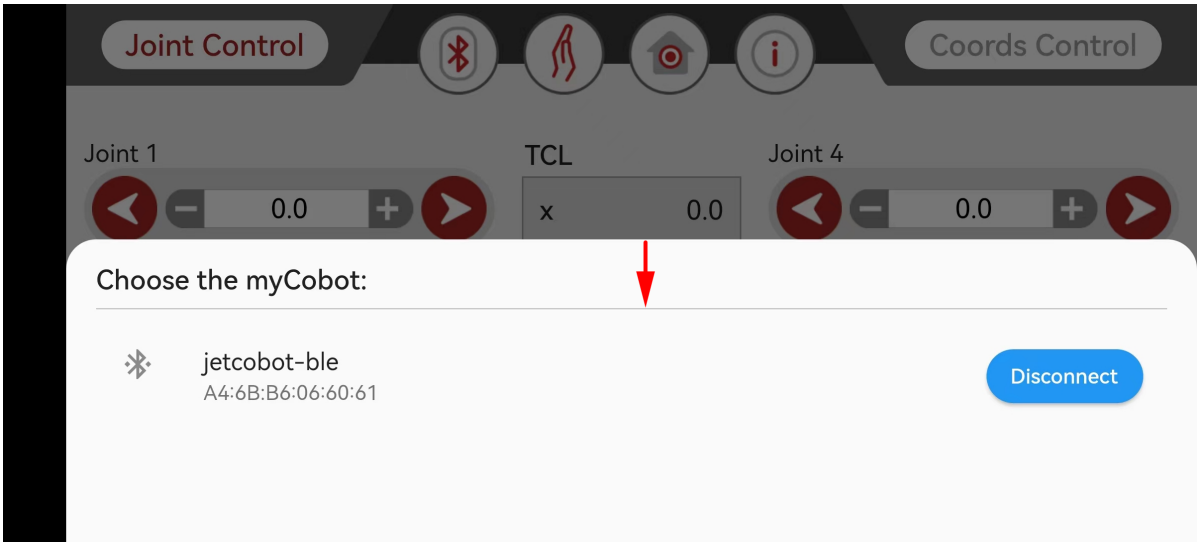
If you are an Android user, go to [Google Play Store] and search for mycobot to download the APP. Or scan the QR code below to download the APP file. IOS users are not supported yet.

2. Bluetooth connection interface

Click the Bluetooth icon in the middle, then select the Bluetooth device name [jetcobot-ble], and click [Connect].

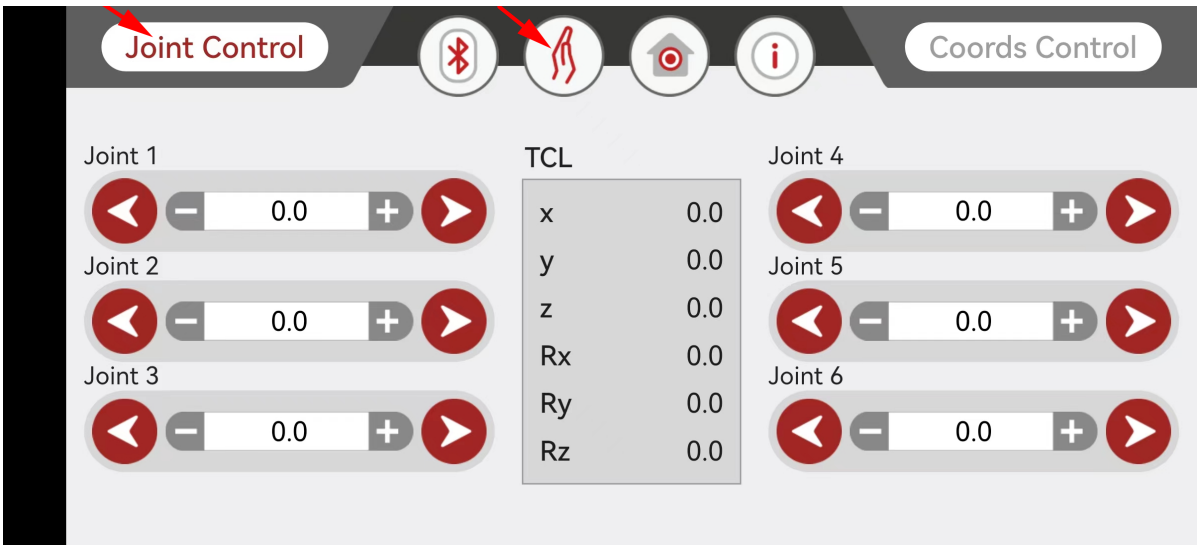


After the connection is successful, the status will change to [Disconnect]. Scroll down the Bluetooth interface to return to the control interface.



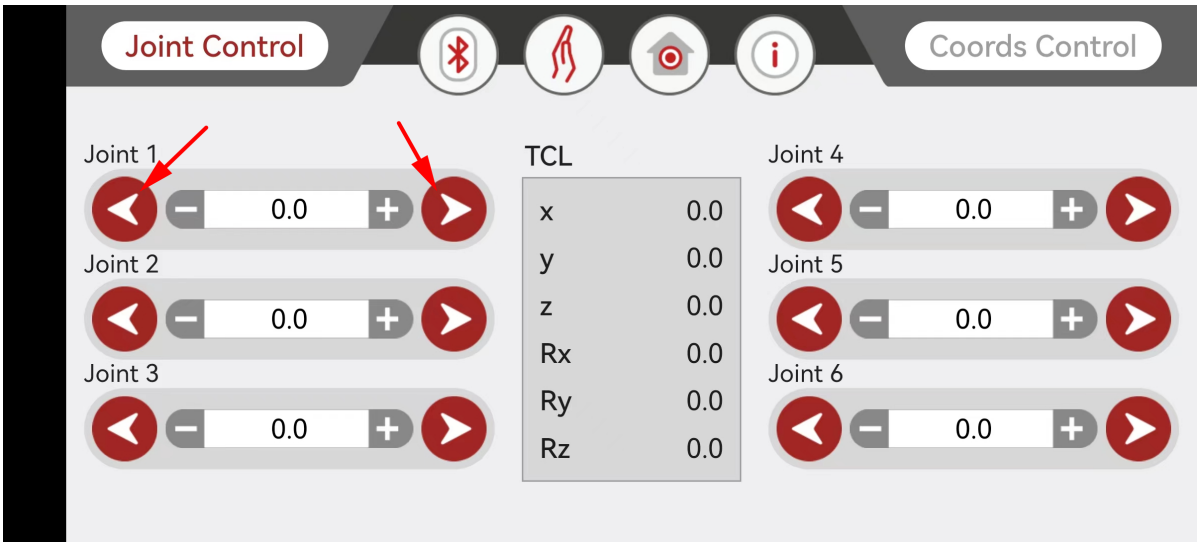
3. Enable the robot control function

Click [Joint Control] in the upper left corner to switch to the servo control mode, and then click the second icon in the middle to enable the robot control function.



4. Control the robot arm

Joint1~6 represents the six degrees of freedom joints of the robot arm from bottom to top, which can control a joint to reach the corresponding angle. Short press to control once, long press for continuous control.



Handle remote control

1. Make sure the USB wireless handle receiver has been inserted into the USB port of the motherboard before turning on the computer.
2. Install the battery of the wireless handle and turn the power switch of the wireless handle to [ON].

3. Press the [START] button to activate the handle.
4. You can now start controlling the robot arm. The button functions are as 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, R2 controls the gripper to release immediately.

⑦: [SELECT] button controls the robot 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 robot arm.

Turn off APP service

The APP and controller trial service are automatically started at boot time in the factory image by default, which may cause interference in actual development. Therefore, if you do not need to automatically start the APP and controller control service at boot time, please enter the following command.

Temporarily turn off the APP service

```
sudo systemctl stop yahboom_app.service
```

Permanently turn off the APP service

```
sudo systemctl disable yahboom_app.service
```

Query the APP service status

```
sudo systemctl status yahboom_app.service
```

Restart the service

If you permanently turned off the APP service in the previous step and want to turn it on or restore the APP service to start automatically at boot time, please enter the following command.

Temporarily start the APP service

```
sudo systemctl start yahboom_app.service
```

Set the APP service to start automatically at boot

```
sudo systemctl enable yahboom_app.service
```