Common Problems and Solutions

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 wrong insertion, please carefully check the power supply voltage of the power adapter before inserting it.

2. How does Jetcobot access data through JupyterLab?

   Answer: Connect the computer and Jetcobot to the same LAN, open the computer browser, then enter the IP address of Jetcobot: 8888, then press Enter, and enter the password yahboom 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 failure of the routine to call resources or cause 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. 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-Send Data]**.