Frequently Asked Questions and Precautions

1. Docker on Raspberry Pi and Jetson Nano versions automatically shuts down.
   This may be caused by a device failure, causing Docker to crash on startup. Use `ll /dev/` to check for missing devices.
2. The robotic arm is in a torque-free state upon power-up.
   This is normal. Use the ros2 topic `pub /arm6_joints arm_msgs/msg/ArmJoints {"joint1: 90, joint2: 90, joint3: 90, joint4: 90, joint5: 90, joint6: 90, time: 1500"} --once` to send the angles to the robotic arm, and the arm will return to torque mode.
3. The AI large model voice example fails to play sound.
   For the Jetson Orin version, check the settings to see if the input/output devices have been changed and whether the output device's audio channel is set to middle. For the Raspberry Pi and Jetson Nano, check `ll /dev/mic` within Docker to see if a device is present. 4. Starting the communication agent is stuck and failing.
   Use the docker ps command to check if there are duplicate agent programs running. If the name contains ros-agent, the agent is running and there is no need to repeatedly restart multiple agents.
4. Why does changing the Wi-Fi OLED screen IP not change when the motherboard is connected to the network cable?
   By default, the OLED display IP priority is that the network port IP takes precedence over the Wi-Fi IP.