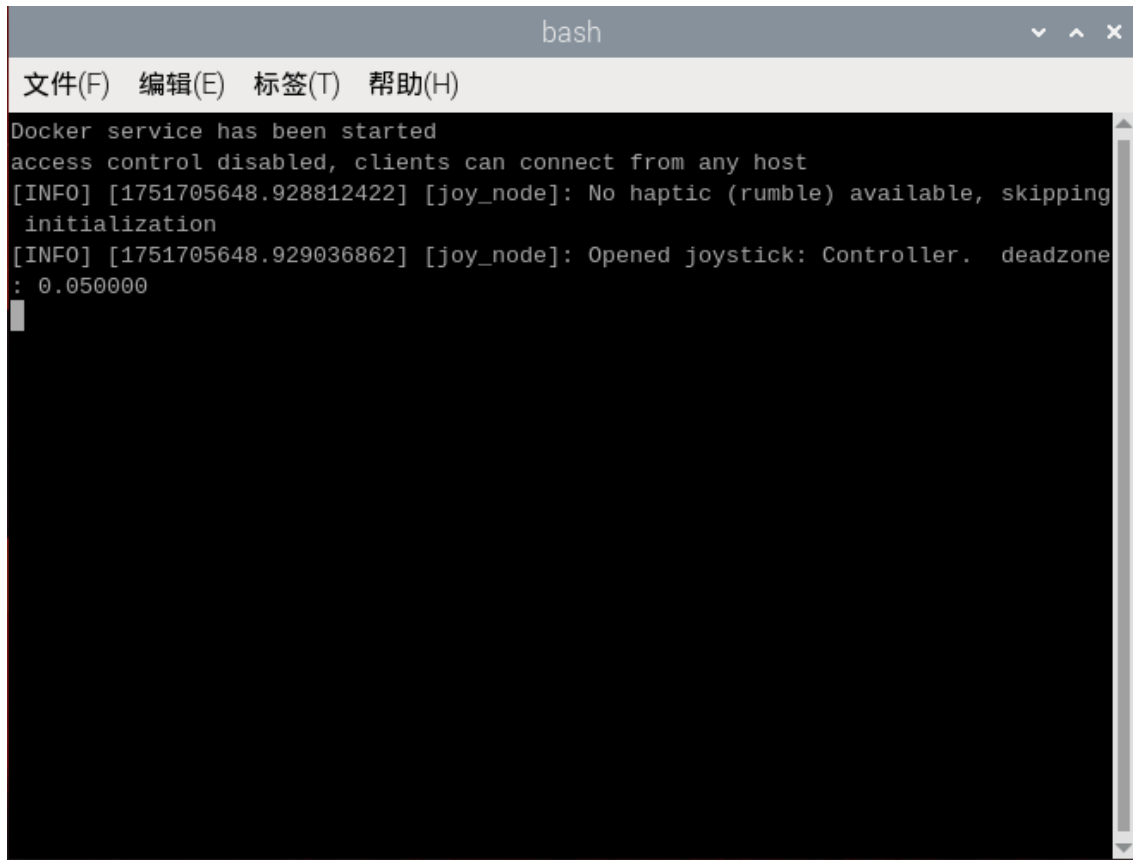# Quick start handle to control the car

Plug the controller receiver into the mainboard or HUB expansion board. After the robot is powered on, the system will automatically connect to the proxy and start the controller control program. Press the [START] button on the controller to activate the controller, then press R2 to unlock the buttons. You can then use the remote control to control the robot according to the table below.

Buttons	Functions
Left joystick up/down	Car moves forward/backward
Left joystick left/right	Car moves straight left/right
Right joystick left/right	Car rotates left/right
START button	End sleep
Left joystick pressed	Adjust linear velocity of X/Y axis
Right joystick pressed	Adjust angular velocity
Button up	Robotic arm No.4 servo up
Button down	Robotic arm No.4 servo down
Button left	Robotic arm No.3 servo down
Button right	Robotic arm No.3 servo up
Button X	Robotic arm No.1 servo left
Button B	Robotic arm No.1 servo right
Button Y	Robotic arm No.2 servo up
Button A	Robotic arm No.2 servo down
Left "1" button	Robotic arm No.6 servo gripper(Tight)/No. 5 servo turn right
Left "2" button	Robotic arm No.6 servo gripper(Loose)/No. 5 servo turn left
SELECT button	Switch control robotic arm No.6/No. 5 servo
Right "1" button	Switch light effect
Right "2" button	Unlock button

1. Turn off controller control
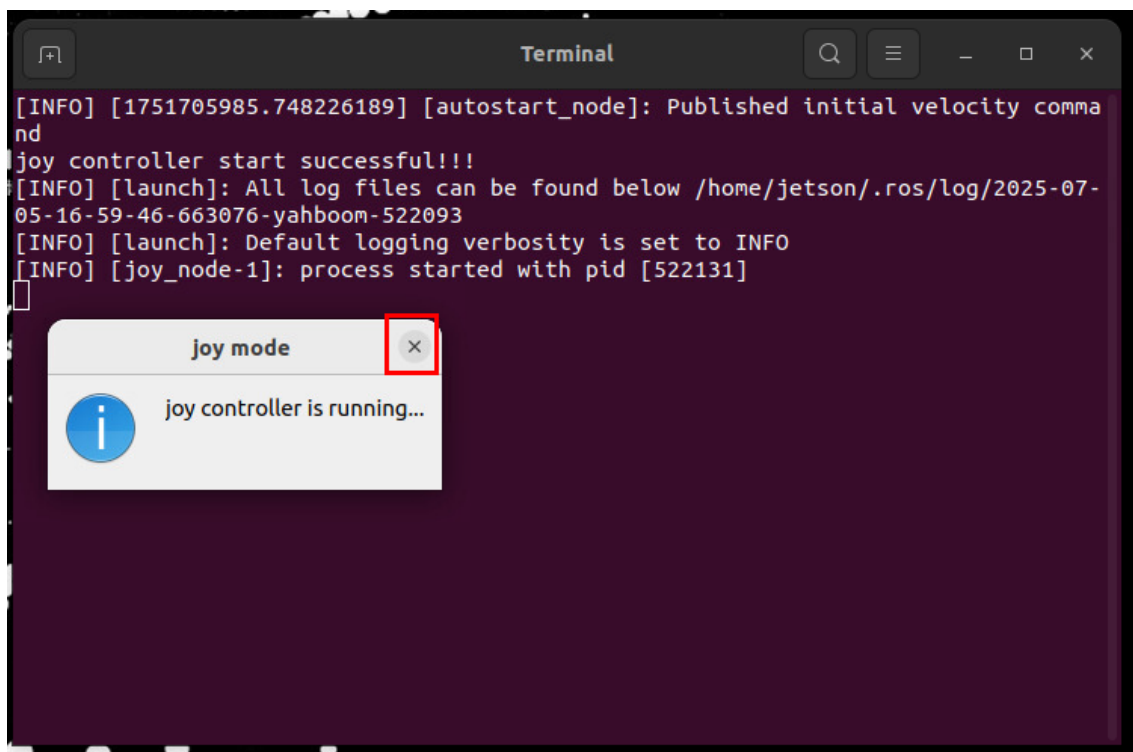
- Raspberry Pi and Jetson-nano motherboard

Close the window running the handle control program, as shown in the figure below, and press ctrl c to close the terminal.

- Orin Motherboard

Click the [x] in the pop-up window below to close the handle control program.

2. Temporarily start the handle control

If we shut down the handle control node that was started at startup, and want to restart the handle control program without shutting down and restarting, the method is as follows:

- Raspberry Pi and Jetson-nano motherboard

  Terminal input,

  ```
  sh Docker_M3Pro.sh
  ```

- Orin Motherboard

  Terminal input,

  ```
  sh ~/joy_control/joy.sh
  ```

3. Permanently turn off the handle to control the startup

If you want to permanently turn off the handle control self-start function, the method is as follows:

- Raspberry Pi and Jetson-nano motherboard

  Terminal input,

  ```
  mv ~/.config/autostart/uros.desktop ~
  ```

  Cut uros.desktop to the ~ directory. It is recommended to save this file. Next time you want to restore handle control at startup, just copy it to the ~/.config/autostart directory.

- Orin Motherboard

  Terminal input,

  ```
  mv ~/.config/autostart/joy_control.desktop ~
  ```

  Cut joy_control.desktop to the ~ directory. It is recommended to save this file. Next time you want to restore handle control at startup, just copy it to the ~/.config/autostart directory.