

2. Close the boot-up self-starting large program

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- 2.1 What is the boot-up program?
- 2.2. Temporarily close large programs
- 2.3. Permanently closing a large program
- 2.4 Setting up the boot-up startup applications
- 2.5. Temporarily starting a large program

2.1 What is the boot-up program?

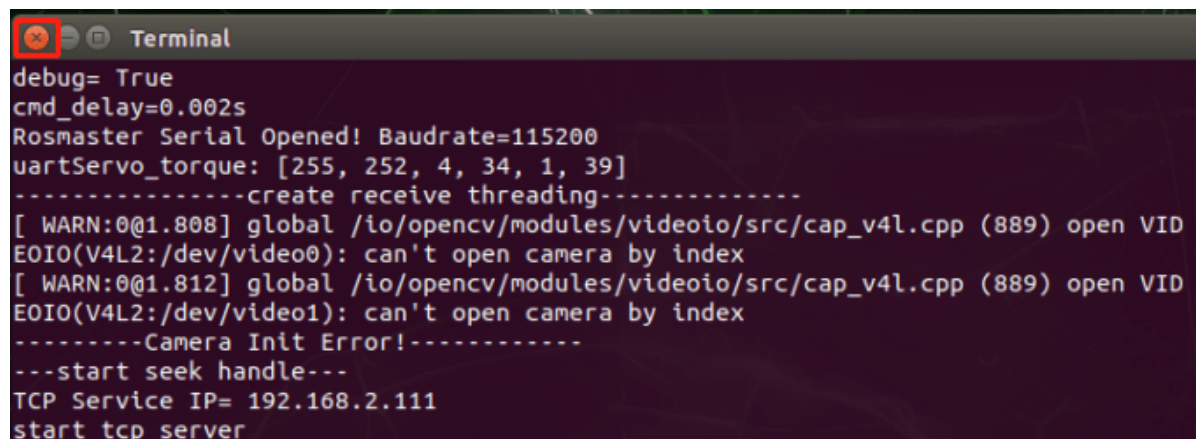
In order to experience the APP function of the trolley, a program is added to the system, which integrates the APP control function and gameplay, so it is called "Big Program", and this program will be started automatically when the system is booted up on the motherboard, so it is called "Booting Self-starting Big Program". The program will start automatically when the motherboard system is booting up, so it is called "boot-up big program".

The boot self-launching big program is only for the convenience of experiencing the function of the cell phone APP, in the actual development, it is necessary to close the big program, otherwise it will occupy the device, resulting in unpredictable errors. So before developing the program, please manually close the boot self-launching big program.

There are two ways to close the boot-up program, one is to close it only once and it will start automatically next time you turn on the device, which is called temporary closure, and the other way is to close it and it won't start automatically next time you turn on the device unless you manually turn it on again, which is called permanent closure.

The factory system default username and password are as follows:

- jetson series motherboard
Username: jetson Password: yahboom
- Raspberry Pi motherboard
Username: pi Password: yahboom

A terminal window titled "Terminal" with a red square icon in the top-left corner. The window displays the following text:

```
debug= True
cmd_delay=0.002s
Rosmaster Serial Opened! Baudrate=115200
uartServo_torque: [255, 252, 4, 34, 1, 39]
-----create receive threading-----
[ WARN:0@1.808] global /io/opencv/modules/videoio/src/cap_v4l.cpp (889) open VID
EOIO(V4L2:/dev/video0): can't open camera by index
[ WARN:0@1.812] global /io/opencv/modules/videoio/src/cap_v4l.cpp (889) open VID
EOIO(V4L2:/dev/video1): can't open camera by index
-----Camera Init Error!-----
---start seek handle---
TCP Service IP= 192.168.2.111
start_tcp_server
```

2.2. Temporarily close large programs

If there is a 7-inch touch screen or display and a mouse and keyboard, connect and log in to the desktop.

If there is no display and mouse, please use a computer in the same LAN to open VNC Viewer software to log in to the desktop remotely.

You can refer to the following webpage for the detailed operation of VNC remote login method, the configuration content has been configured, directly jump to step 6 to connect.

[VNC Remote Desktop Configuration \(yahboom.com\)](http://VNC Remote Desktop Configuration (yahboom.com))

Username: jetson

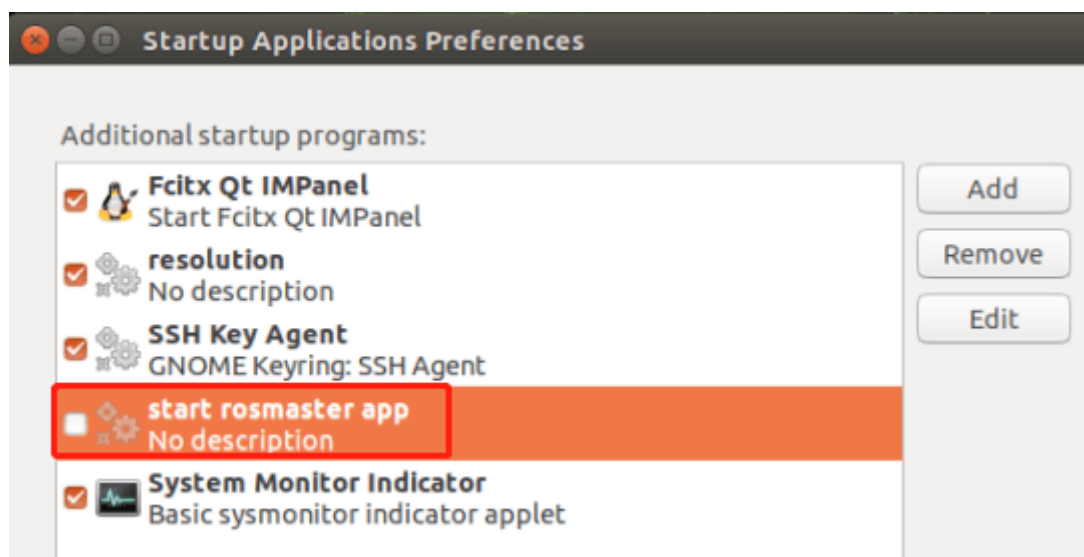
Password: yahboom

When you enter the desktop, you will see a terminal, you can close the terminal directly by clicking the X symbol in the upper left corner to close the big program. Sometimes you may be prompted to close the terminal will close the running program, choose to confirm the closure can be.

2.3. Permanently closing a large program

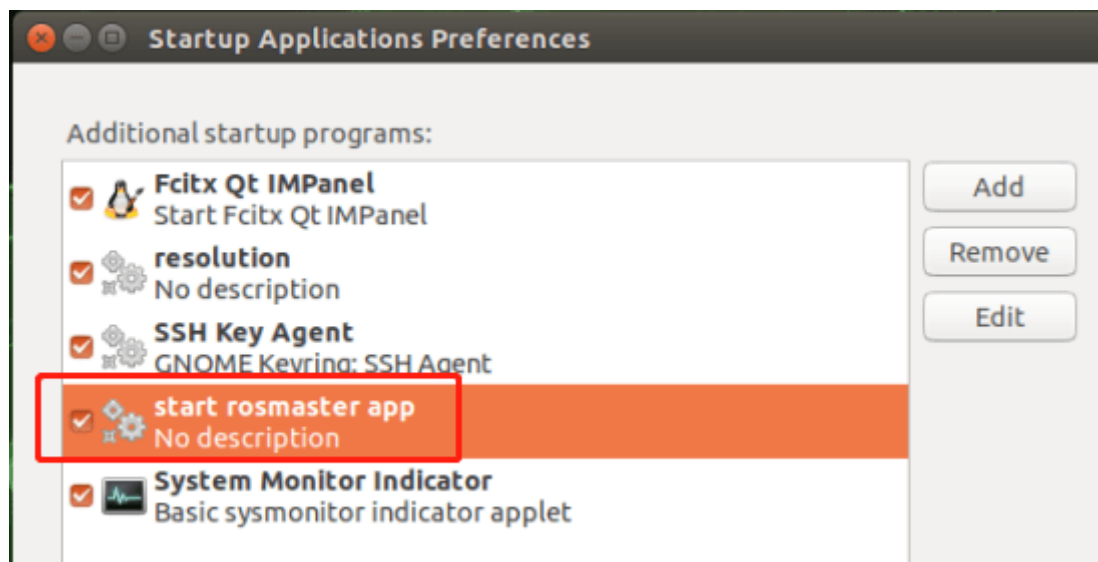
First, you can close the running application in the same way as you closed it temporarily.

Open Ubuntu system applications, search Startup Applications, remove the check mark in front of start_rosmaster_app as shown in the following figure to close the large program permanently.



2.4 Setting up the boot-up startup applications

When you open the application of Ubuntu system, search Startup Applications, put a check mark on the box in front of start_rosmaster_app as shown in the following picture, then the next time the system will boot up, it will automatically start the big program.



2.5. Temporarily starting a large program

If you need to manually exercise a large program, please open Ubuntu's terminal first, and then enter the following command:

```
python3 ~/Rosmaster-App/rosmaster/rosmaster_main.py
```