Documentation (new): <https://docs.hiwonder.com/projects/MentorPi/en/latest/index.html>

Documentation (old): <https://drive.google.com/drive/folders/1Ox5xN5zpxXqDK-9ruDwwgcQgePXvMvHr>

**Assembly**

1. Follow getting ready to assemble
   1. 1.4 Step 1
   2. Skip to Ackerman Chassis and follow those steps
   3. Follow the top plate build instructions (as shown in the mecanum version)
   4. Refer to page 03 of the printed manual for the interface instructions to connect the components to the Rpi5
2. Turn on the robot and let it FULLY BOOT UP.
   1. If the power is switched off during first boot it will corrupt the EEPROM and will have to be reset using a special process
   2. You should hear a single beep when all the systems are ready

**Important MAYBE!**

It is possible that the robot will be defaulted into mecanum drive mode. If that is the case, this needs to be switched to Ackerman drive by connecting to VNC, following 2.2 in the new docs and switching machine to Acker

**First Run:**

1. Turn on the wireless remote. As long as the USB dongle is connected to the Pi, the remote should be recognized almost immediately.
   1. See 1.5 in old documentation

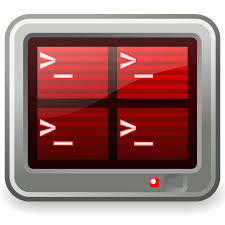
**A screenshot of a computer application

AI-generated content may be incorrect.App Control :**

1. The WonderPi app on iOS and Android allow experimenting with various features of the robot.   
   1. The device has to first be connected to the robots AP wifi which will start with ‘HW-‘
   2. The password is **hiwonder**

**Development and ROS2 access:**

**Connecting**

1. Connect to the RPi5’s Access Points from a computer (make sure to connect to the correct AP associated with your robot, should start with ‘HW-‘
2. Connect to realVNC viewer by following 2.1 of the new documentation
   1. Note the passwords for VNC connecton: **Username: pi Password: raspberrypi)**
3. The Terminator program SHOULD start in the robots Docker container. If it does not, 2.3.2 in the new docs describes how to enter the container

**IMPORTANT!**

Before running any commands App control needs to be disabled using ~/.stop\_ros.sh or thing will not work correct or at all.

Some of the custom scripts include commands that disable it when run.

To re-enable app control the robot can be restarted.