

# NVIDIA Jetson Nano Setup

## Setup Headless Jetson with GUI Client

### Harley's Tutorial for different client side DMs

We use **X2Go**.

[https://teawiki.net/doku.php?id=workshops:nvidia\\_jetson:xavier\\_nx:start](https://teawiki.net/doku.php?id=workshops:nvidia_jetson:xavier_nx:start)

### Changing Runlevel

Change the Jetson runlevel to non-GUI to switch off the gnome display manager (or other DM) to free memory.

Instead enable graphical login with [X2Go](#).

```
# Temporary
sudo systemctl isolate multi-user.target

# Permanent
sudo systemctl set-default multi-user.target
```

## ROS Setup

### Use Docker Containers

- NVIDIA Forum on [ROS2 on Jetson Nano](#)

[https://nvidia-ai-iot.github.io/ros2\\_jetson/ros2-jetson-dockers/](https://nvidia-ai-iot.github.io/ros2_jetson/ros2-jetson-dockers/)

<https://github.com/dusty-nv/jetson-containers#ros-containers>

```
git clone https://github.com/dusty-nv/jetson-containers
cd jetson-containers
```

```
./scripts/l4t_version.sh
```

```
# Result:
# ARCH:  aarch64
# reading L4T version from /etc/nv_tegra_release
# L4T BSP Version:  L4T R32.7.3
```

### Can't find docker image for L4T 32.7.2

<https://github.com/dusty-nv/jetson-containers/issues/177>

## Misc

Harley's tutorial for [setting up ROS](#) on NVIDIA Jetson **Xavier NX**. It is not applicable to Jetson Nano because binaries are not provided in the repos.

## UPDATE: Let us build the software from scratch!

Harley suggests to use <https://docs.ros.org/en/eloquent/Installation/Linux-Development-Setup.html>

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