



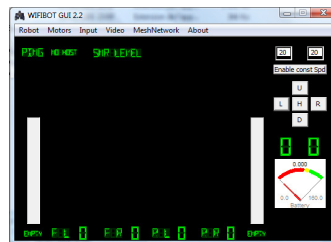
- High range WIFI for High mobility 4x4 platform
- Modular and open architecture
- Fully controllable using TCP/IP up to 16 servos
- Fully customizable by adding Camera etc...

Wifibot RC KIT



Multi-purpose WIFI KIT

Our WIFI Kit gives you the capability to control any servo or motor controller that use PWM signal. We have merged the PC/WIFI world to the RC world by having a networkable servo controller. We can drive all kind of RC car using a pc , a PSP or a Nintendo DS device for example. But any devices that have wifi and c++ sdk can do the same (iphone pda etc...).

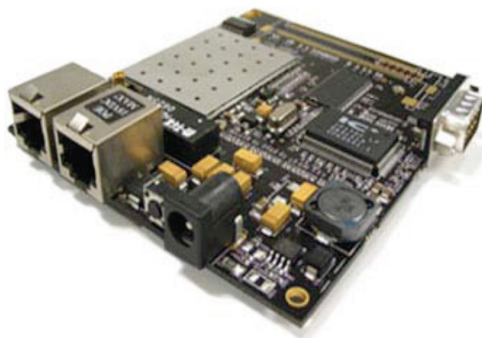


www.wifibot.com

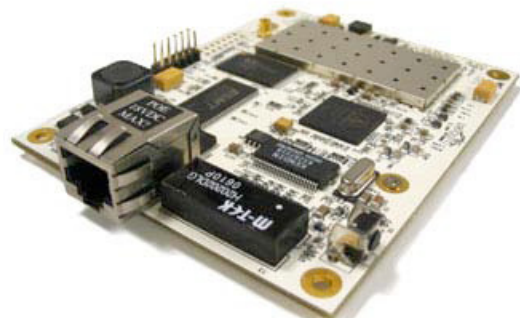
WifibOT RC KIT



Inside the Kit:



LiteStation2



LiteStation5

The LiteStation platform was designed for high-performance outdoor and industrial OEM applications. It features an industry best radio design offering hi-power, great receive sensitivity, and capable of multi-km wireless links. The system was designed for high temperature operation and features industrial grade components as well as a integrated heatsink beneath the board. The LiteStation ships with basic bridging and routing software, as well as publicly available software development materials needed for custom OEM use. (2.4Ghz or 5Ghz)

APPLICATIONS

MultiPoint CPE



Mesh/Mobility CPE



Bridging

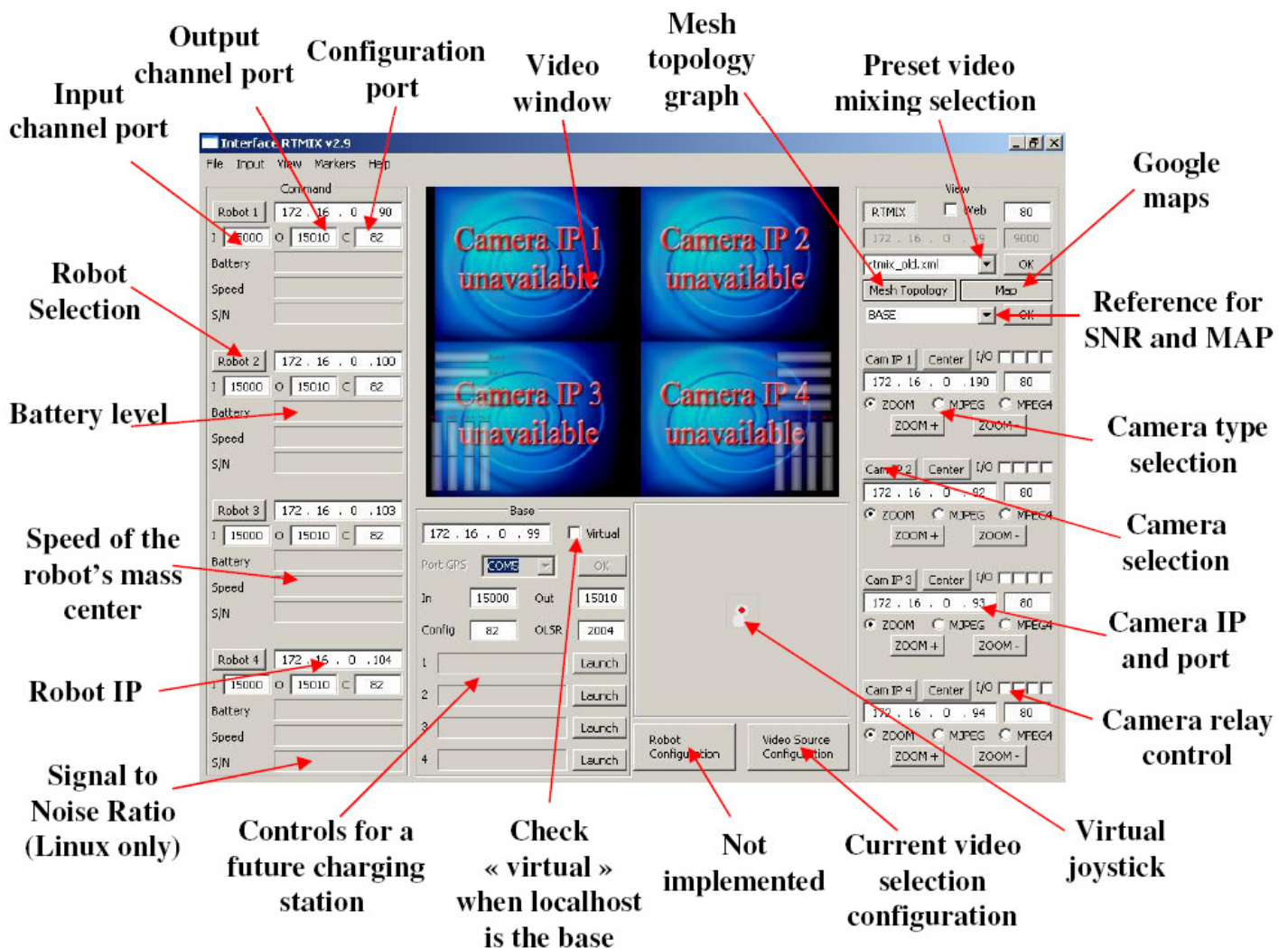




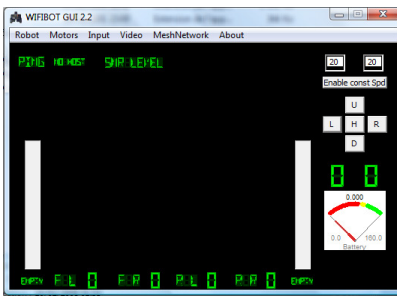
RTMIX multi-robot interface (UDP)

Features:

- The RTMIX multi-robot interface allows the user to control a team of up to four robots.
- The interface is best viewed with a 1024x768 resolution.
- Platform related controls are located on the left while visual related ones are located on the right.
- Before operation the user has to make sure all IP addresses and ports are correctly set.
- Selected robots can be controlled using the virtual joystick, a joystick or a wiimote, selecting more than one robot at a time will have as a result having all of them receiving the same command.
- Cameras can be selected individually or blended in one image with RTMIX. Preset mixing layouts can be selected and new ones added thanks to the "video source configuration" webpage.
- Certain functionalities need a reference which can be selected with a menu located just under the Mesh and Map buttons.
- Certain types of supported cameras have incorporated relays which are set with the I/O checkbox.
- The "base" can be either an external gateway or the control computer itself (check "virtual" for this).
- The Map button needs to have an active internet connection and will show the robot's and the base position on a Google Maps webpage provided those are equipped with a GPS.



The simple control software (TCP) :

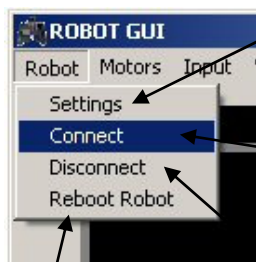


The control software:

The control software can be found in the CDROM in
 ..\Software\control software\

- Install if necessary the **Video Decoder** present in the same folder.
- Launch the **WifibotGUI** program.
- Click on **Robot** then **Settings**. The **Robot Settings** window appears.
- Set the **Control Server IP** and the **Control Server Port** which by default is **15000**.
- Set the **Camera IP** and the **Camera Port** which for the image is by default **80**.
- Select the proper **Camera Type**.
- Click on **Video**, then select **VideoOn**. The image from the camera will appear.
- Click on **Robot** then **Connect**.
- Click on **Input** then select **Joystick** or **Virtual_joy**. The robot can now be operated.

The menu options:

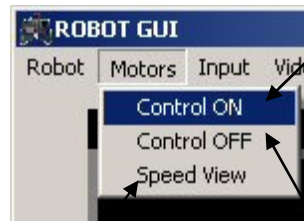


Reboot: Reboots the robot's CPU.

Settings: IP settings of the Control Server and the Camera.

Connect: Starts the communication with the Control Server.

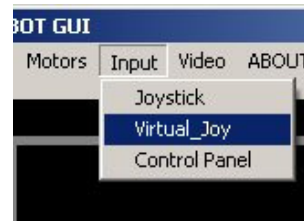
Disconnect: Stops the communication with the Control Server.



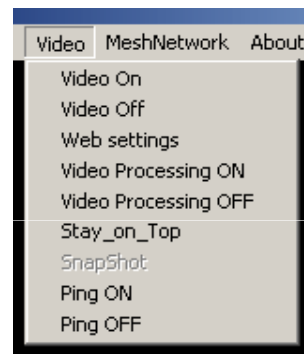
Motor Control ON: Activates the speed control, Input_Left and Input_Right set on the dialog will be applied.

Speed View: Plots in real time the speed signal from the code wheels.

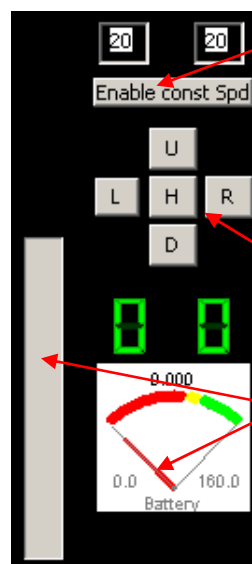
Motor Control OFF: Deactivates the speed control.



Input Selections (control panel for calibrating the joystick)



Video selections: Allows to configure and control some options of the camera.



Current input: shows the current input or allows to set it manually with keyboard.

Pan-Tilt camera control: The red button takes the camera to the default position. You can click on the image too for moving the camera.

Sensor feedback: shows the data retrieved from the range sensors, the battery level and the speed of the robot.