PhantomX Hexapod Demos

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Wireless Handheld Control for the PhantomX Hexapod

Description:

The PhantomX Hexapod can be controlled wirelessly via the **ArbotiX Commander** In this demo, the ArbotiX Commander's joysticks will be used to control the movement of the cralwer while the pushbuttons allow for gait selection.

This demo code has an integrated Inverse Kinematics engine powered by **NUKE**. This software engine handles the calculations for each servo to make the cralwer walk. This demo code is a great place to start if you want to build modify the crawlers behavior and still use NUKE. You can learn more about NUKE here

Serial Control ArbotiX Commander Control

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DYNAPose - DYNAMIXEL/ArbotiX Pose Tool

Description:

All the InterbotiX robots turrets, arms, and crawlers use DYNAMIXEL servos. These servos all have positional feedback, allowing the ArbotiX-M Robocontroller to read the current position of each servo. This makes it possible to physically pose an InterbotiX robot, then capture the positions for each servo, allowing the user to save/capture the current pose. By capturing multiple poses, a user can create a sequence that can be repeated.

This firmware does not use any Inverse Kinematic calculations to position the servos - it simply moves the servos to a pre-set position. Please see the 'Demo' section for your Robot for more information on code examples that us IK engines.

PC Control

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Untethered Pose Playback with DYNAMIXEL/ArbotiX

Description:

The ArbotiX-M Robocontroller can be used to easily 'play' a sequence of poses on DYNAMIXEL servos. These poses can run automatically, triggered by an outside input (like a pushbutton) or integrated into more advanced code.

This tutorial can be used in conjunction with the DYNApose tutorial. The DYNApose tutorial will help you to capture a series of poses while this tutorial will help you integrate those poses into new code.

This firmware does not use any Inverse Kinematic calculations to position the servos - it simply moves the servos to a pre-set position. Please see the 'Demo' section for your robot for more information on code examples that use IK engines.

Standalone PC Control (Setup Only)

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Virtual Commander - Generic Software Robot Control

Description

The **Virtual Commander** software is a piece of software designed to mimic the ArbotiX Commander. This is a small demo application written in Processing/Java. This application allows you to control InterbotiX robots as if it were connected to a real ArbotiX Commander as if it were connected to a real ArbotiX Commander. This can be very handy for rapid development, as you can program and control the ArbotiX over the same USB-FTDI connection, switching back and forth between the Arduino IDE and the Virtual Commander

PC Control Serial Control

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LIDAR Lite Hexapod Demo

This demo will show off the capabilities of the LIDAR Lite by using it to control a PhantomX Hexapod.

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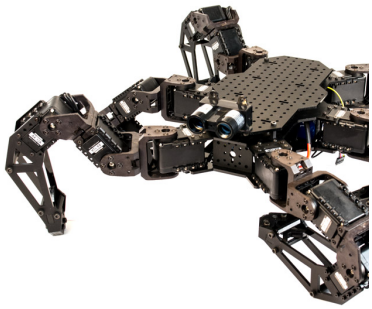

LIDAR Lite Product Page

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