*RASPBERRY PI DETAILS AND INSTALLATION INSTRUCTION*

* ***DETAILS***

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| Pi No. | Owner | Details | Xrdp | LAN | WAN | MAC | MOTION | Arduino IDE | pyFirmata | IMU | MOTION REPLACEMENT |
| 1 | URC | 32 GB | YES | 192.168.0.221 | 192.168.0.222 | B8:27:EB:50:7F:C9 | YES | YES | YES | YES | \* |
| 2 | Shourov | 16 GB | YES | 192.168.0.221 | 192.168.0.222 | B8:27:EB:50:7F:C9 | YES | YES | YES | NO | working |
| 3 | URC | 32 GB | YES | 192.168.0.221 | 192.168.0.222 | B8:27:EB:50:7F:C9 | YES | YES | YES | NO | \* |

* INSTALLATION GUIDE
* Xrdp
* sudo apt-get remove xrdp vnc4server tightvncserver -y
* sudo apt-get install tightvncserver -y
* sudo apt-get install xrdp -y
* Arduino IDE
* sudo apt-get install arduino -y
* pyFirmata
* sudo apt-get install python-pip python-serial -y
* sudo pip install pyfirmata
* MOTION
* sudo apt-get install motion
* lsusb
* sudo nano /etc/motion/motion.conf
* 'ctrl + w' to find & make Changes
  + Make sure 'daemon' is ON.
  + Set 'framerate' anywhere in between 1000 to 1500.
  + Keep 'Stream\_port' to 8081.
  + 'Stream\_quality' should be 100.
  + Change 'Stream\_localhost' to OFF.
  + Change 'webcontrol\_localhost' to OFF.
  + Set 'quality' to 100.
  + Set 'width' & 'height' to 640 & 480.
  + Set 'post\_capture' to 5.
* Press ctrl + x to exit. Type y to save and enter to conform.
* sudo nano /etc/default/motion
  + Set ' start\_motion\_daemon ' to yes. Save and exit.