

## Axis 214 and 212 Network Cameras

ACTD041, ACT0099

Your robot is equipped with an Axis 214 network camera with pan/tilt/zoom control, or an Axis 212 wide-angle front-mounted camera.

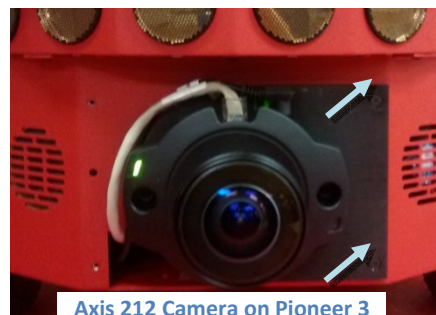
### Assembly and Installation:

The camera has been packed separately from the robot to protect it during shipping. To install the camera, use M4 screws provided to attach the camera via the black camera mounting bracket:

- Axis 214 on Pioneer 3, Powerbot, Patrolbot, and Peoplebot top deck: Attach the bracket to the two frontmost and one center-rear screw points on front portion of your robot's top plate
- Axis 214 on Pioneer 3, Powerbot, and Peoplebot on top of optional laser rangefinder: Attach via the two frontmost and two corner rear screw points to the top of the laser rangefinder bracket
- Axis 214 on Peoplebot inverted beneath top deck: Attach via two frontmost and one center-rear screw points under Peoplebot top deck
- Axis 212 on Pioneer 3 front-mounted: attach black adapter plate with two screws on its right side to front of robot. Ethernet and power cables (already installed in robot) pass through hole in front of robot, and connect to top of camera (see photo).



Axis 214 PTZ Camera



Axis 212 Camera on Pioneer 3 with screw locations indicated

Attach the ethernet (network) and power cables (already installed on robot) to the camera.

### Ethernet Connections and Configuration:

The Axis is a network camera. Images can be received from the camera and pan, tilt and zoom controlled via HTTP over the network, via the Vapix convention for HTTP interface. See "Software" below for details on MobileRobots software support.

**The default IP address of the camera is 192.168.0.90.** Access <http://192.168.0.90> from a web browser for camera configuration options and to view live images. The camera comes with the root user account configured with password set to "password".

When the camera is the only ethernet device on the robot, and the robot is equipped with an onboard computer, it is connected to the second ethernet port of the onboard computer (named eth1 in Linux), and this interface is configured for a 192.168.0.x network (in /etc/network/interfaces on Linux, and in the network adapter's IPv4 properties in Windows).

If there are multiple ethernet devices on the robot, or there are multiple onboard computers, then all computers and ethernet devices are connected to an ethernet switch. The primary ethernet port of the onboard computer is given a