

INTROBOT[®]

THE ROBOT MAIN CHARACTERISTICS

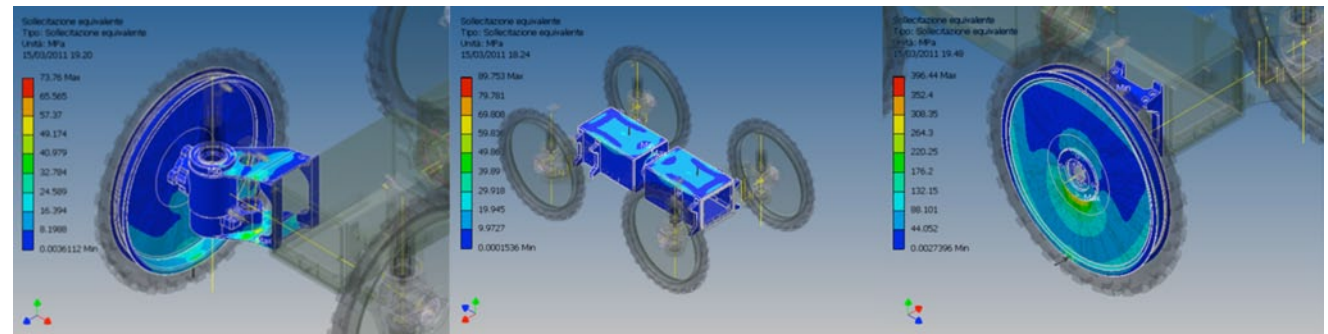


FLEXIBILITY AND ROBUSTNESS

The robot allows to easily extend its functionality, allowing easy integration of new components and new software packages in scalar and/or reconfigurable form. This ability to customise, results from its flexibility.

The robustness is due to the fact that the robot is so resistant to external forces (the forces induced in the

platform due to the physical rigours of the operation/ground), as well as to wear and tear from prolonged operations (by controlling the operating state of the components, such as overheating or quality of communications, preventing the robot from entering a condition of failure).



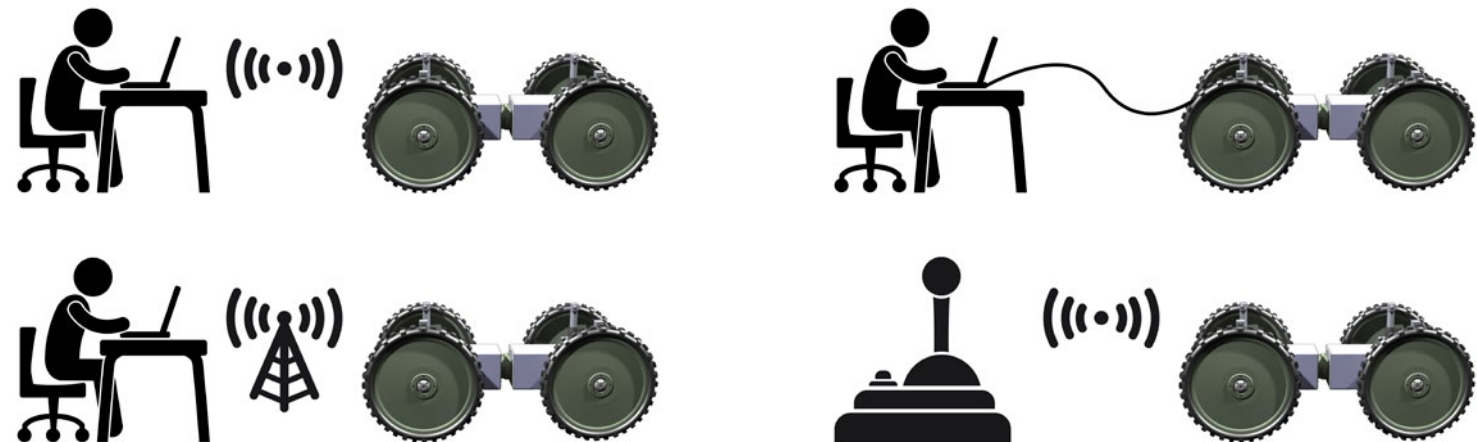
Simulation of Stress for vertical loads (a and b) and lateral loads (c)

VERSATILITY AND MANOEUVRABILITY

The versatility results from the different control methods, with control centre or short-range command, easily interchangeable between themselves.

The manoeuvrability of its locomotor system results

from a rotating shaft and directional four-wheel drive. The wheels allow for omnidirectional, lateral, ackerman and double ackerman movements.



Methods of Control. a. through the control centre; b. with short-range command

