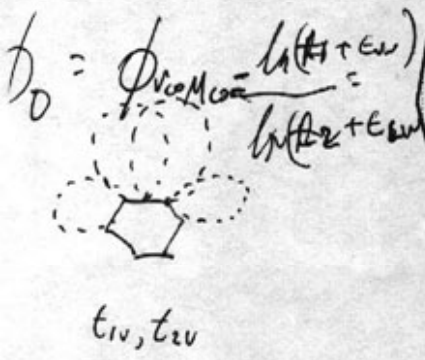
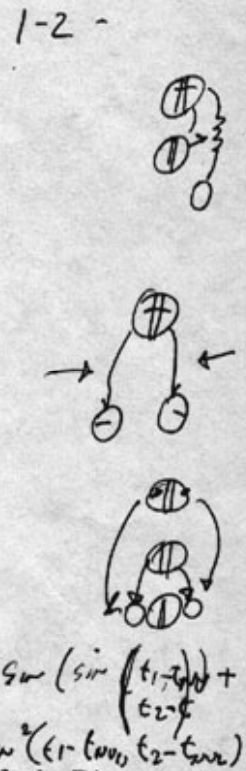
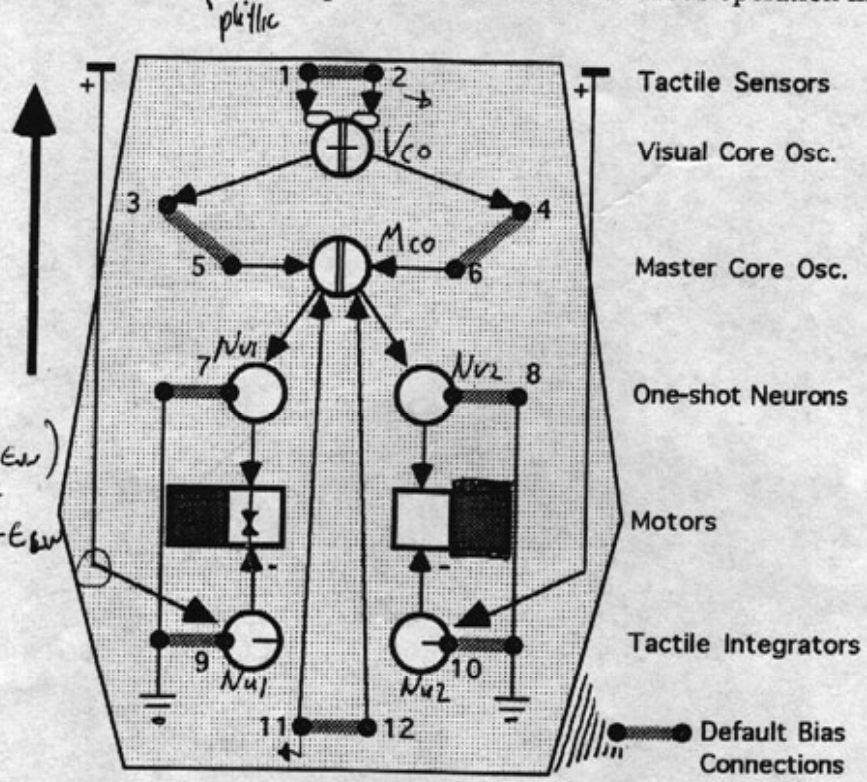


Burn 24/87
Tolluville, CO.

BEAMant 6.0 Series Mobile Robot: Configuration Details

The BEAMant 6 series of biomech robots is a high-efficiency solar powered roving breadboard with many reconfigurability parameters, two forward tactile and visual sensors (default - Visually phototropic behavior, but tactile-phobic operation), and a high quality solar-engine that allows the device up to 4000 hours of continuous operation in sunlight.

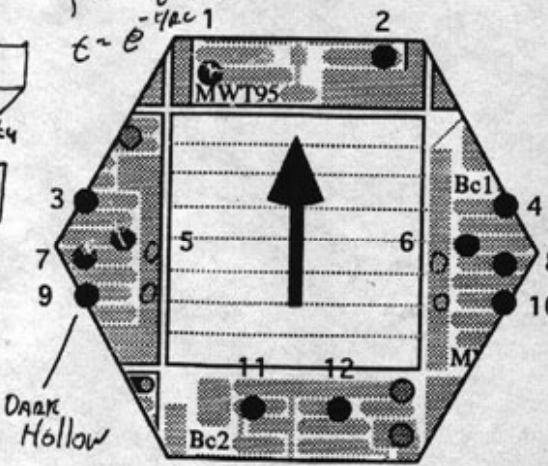
Groups @
7:30-8:



Showing the topologically correct BEAMant Nervous-Net Schematic, the Default Bias Connections are the suggested resistor positions for a minimal phototropic, tactile-phobic device. The acuity of the photosensors is linear and extends from the front left and right of the robot in a 20 cm teardrop sensitivity pattern resistant to overhead lighting influences.

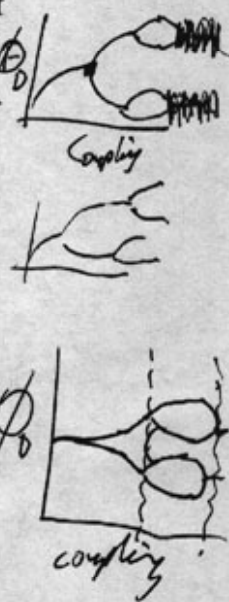


$f = \frac{1}{RC}$
 $\epsilon = e^{-\frac{t}{RC}}$



Physical Layout and Resistor bias input locations

The BEAMant is configured so that ~~layers~~ other controllers can be placed on top of the rover, but also so that high-impedance connections between its internal non-linear oscillators can be rewired quickly and in various different ways. Because of the efficiency of the robot, resulting behaviors can be tested out immediately as to their effectiveness in a level work environment. Examples of possible behaviors include phototropism, photophobia, bulldozer, flocker, fighter, sorter and many others. Use this page to sketch out your connection and bias-resistor connection ideas.



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3 S2/F1/ES?

