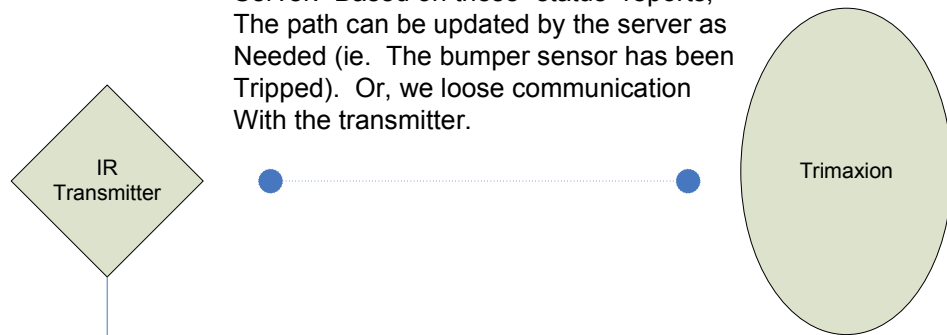
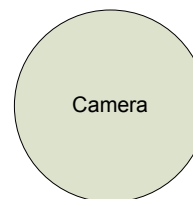


The IR Transmitter and Trimaxion will Communicate. The IR transmitter will Send movement directions to Trimaxion. Trimaxion will send reports back to the IR Transmitter, which in turn get sent to the Server. Based on these “status” reports, The path can be updated by the server as Needed (ie. The bumper sensor has been Tripped). Or, we loose communication With the transmitter.



Using the classes provided by Lejos, The server is going to start transmitting Opcodes to the IR transmitter. The Opcodes are generated by the server After the client sends an image to the Server (by clicking).



Camera will feed live video to the server
TODO: How do we do this?

Server and Client communication will be two way.

Server will stream a live video feed to Client. This will Mostl likely use the UDP protocol, but we will see.

Client will display the live video and wait for the user to Click on the live video feed. When the user clicks, The video is momentarily paused and that frame is Converted to a picture and sent to the server.

The Server will then take that image and decide on the Path for the Robot.

