



Wireless (WiFi 802.11g), Dual 5DOF Arm and 1DOF Grippers,
Internet Remote Monitoring Robot

Scout²

Quick Start Guide



WARNINGS

Do **NOT** power on the robot before reading and fully understanding the operation procedures explained in this manual.

Neither the robot, nor the program is bug free, accidents could happen; you have to make sure that the robot always maintains a safe distance from people during operation.

The robot should be turned off (i.e. the power switch should be on OFF position) when not in use. Battery should be fully charged before storage. Battery pack should be recharged every two weeks while in storage.

Failure to follow these warnings could cause serious injury or death and/or damage to the robot.

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Introduction

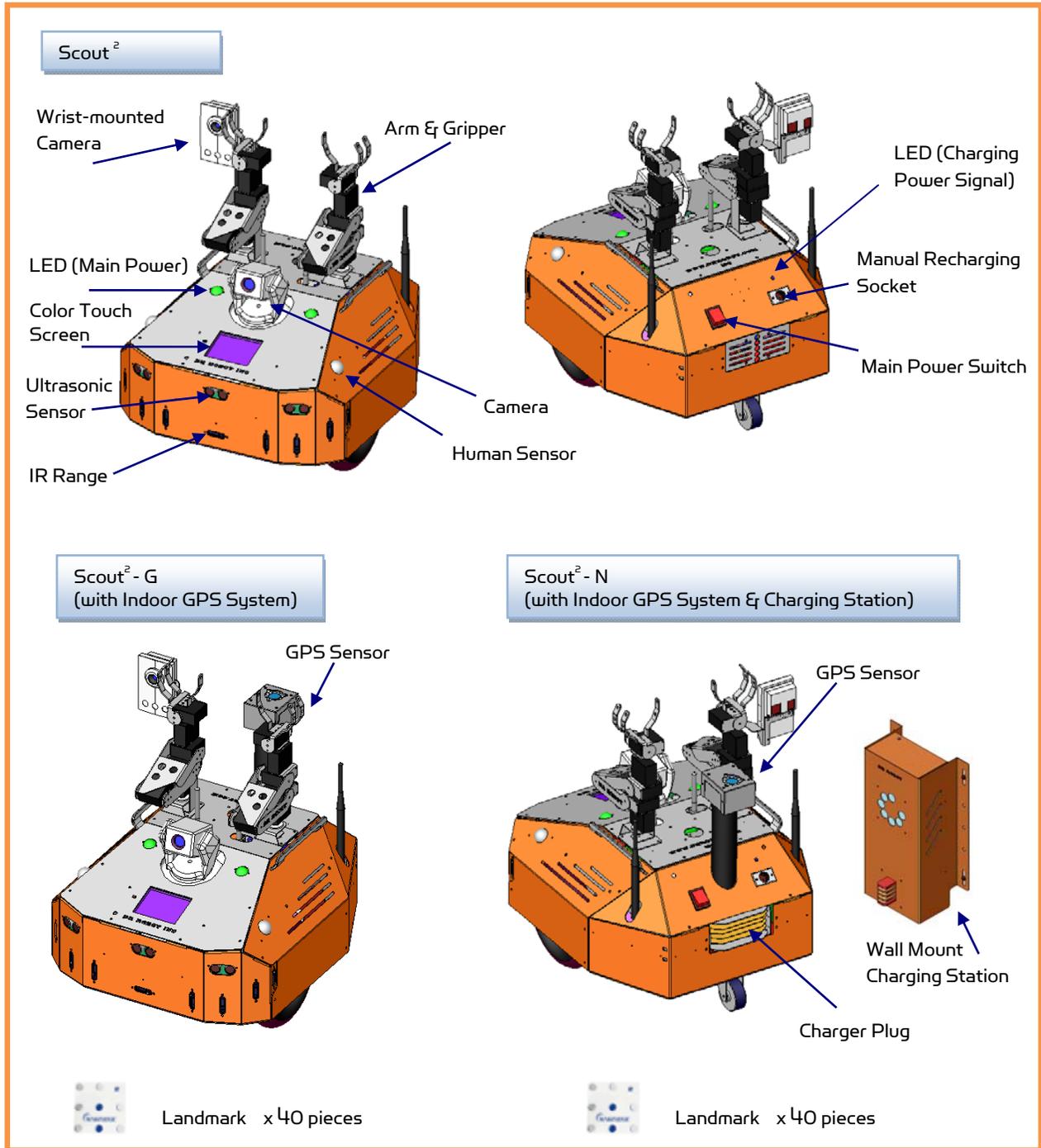
Scout² is a ready to use mobile robot platform designed for remote monitoring / patrolling applications requiring object manipulation or other direct physical interaction with the robot's surroundings.

Key Features

- *Max 704x480 pixels, max 30fps, Pan-Tilt-Zoom High Resolution Camera with 2-way audio on chassis*
- *2 Arms and grippers (5-DOF Arm x2 + 1-DOF Gripper x2)*
- *640x480 Wrist-mounted Camera*
- *550 oz.-inch(40 kg.cm) 12V DC motor with integrated optical encoder*
- *Fully wireless networked 802.11g*
- *OS independent application development tools*
- *Max speed of 0.75 m/sec*
- *320x240 Color Programmable Touch LCD, Display image, message or sensor data*
- *Collision detection sensors include 3 Ultrasonic range sensors and 9 IR range sensors*
- *Comprehensive circuit protection*
- *Max payload 15 kg (optional 40 kg) with robot weight of 7 kg*
- *Dimension: 43cm (L) x 38cm (W) x 54cm (H)*
- *Extended operating time. 3 hours nominal operation time for each recharging*
- *Gamepad Control included*
- *Upgrade options:*
 - *Vision-landmark base indoor localization (indoor GPS, position/orientation) sensor and the landmarks together provide precise position and direction information covering every inch of the floor*
 - *Auto-docking and recharging station*
 - *Laser scanner*
 - *Power and battery systems for 6 hours operation time are available*

Sensors and External Components

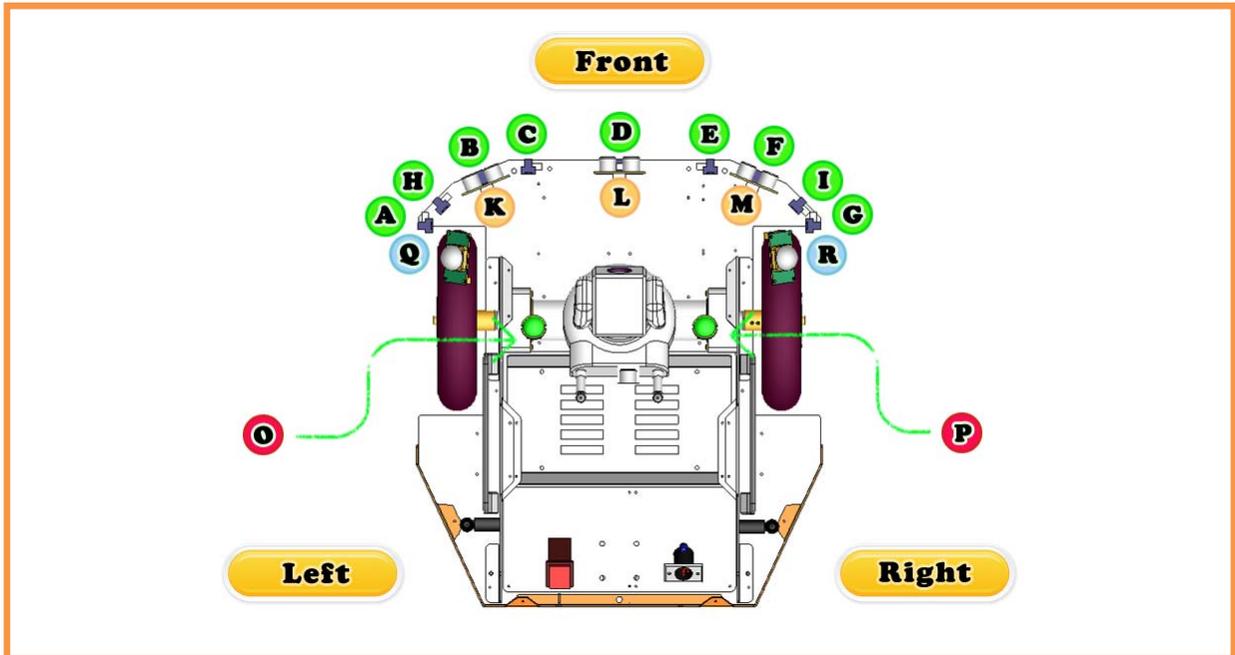
The figure below illustrates the key functional components you will identify on the outside of Scout² robot.



Scout² Overview

When the main power switch is on, the main power LED will be lit. When the robot detects input power from the recharging socket, the charging power signal LED will be lit.

The robot comes with 3 Ultrasonic and 9 IR range sensors. These range sensors are for environment detection and collision avoidance.



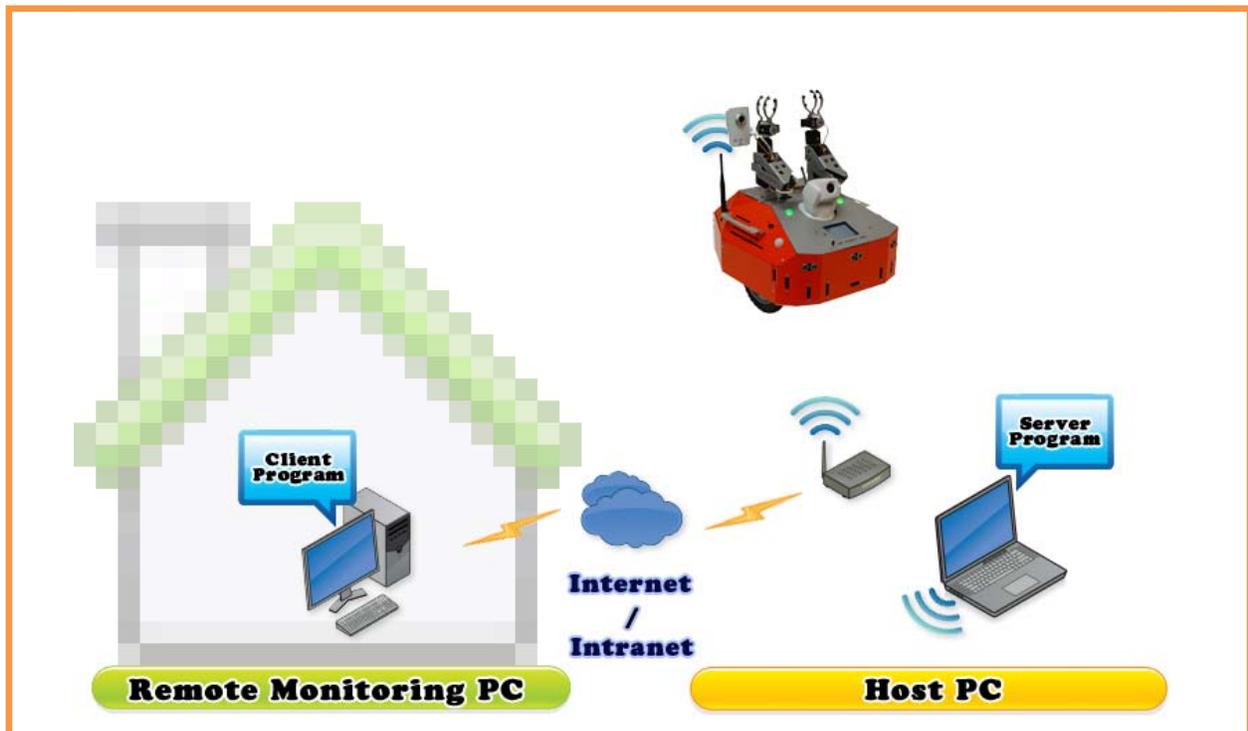
Scout² Sensor Module Location (Top View)

Sensor Module	Location
Ultrasonic #1	K - Left front
Ultrasonic #2	L - Middle front
Ultrasonic #3	M - Right front
Human Sensor #1	Q - Left front
Human Sensor #2	R - Right front
Infrared Range Sensor #1	A - Front left
Infrared Range Sensor #2	B - Front left
Infrared Range Sensor #3	C - Front middle
Infrared Range Sensor #4	D - Front middle
Infrared Range Sensor #5	E - Front middle
Infrared Range Sensor #6	F - Front right
Infrared Range Sensor #7	G - Front right
Infrared Range Sensor #9	H - Front left
Infrared Range Sensor #10	I - Front right
DC Motor #1 with quadrature encoder	O - Left , use channel 1
DC Motor #2 with quadrature encoder	P - Right, use channel 2

Operation Scenario

Diagram below shows the typical operation scenario. The Scout² is a wireless networked robot. It connects to the wireless AP or router via IEEE 802.11b/g network. The host PC (or called server PC) running the Scout² Control program could connect to this network via either:

- Network cable – Connect the host PC to one of the LAN ports on the back of the router (DO NOT connect to the WAN port), or
- Wireless – To connect the host PC to the wireless router, configure the host PC's wireless settings using the default wireless configuration settings found in the Network Connection session of this manual.



Typical Operation Scenario

Note: The host PC (or called server PC) could also be mounted on the robot if your application requires so.

User could be able to control the robot, see, talk and listen through the robot via the Dr Robot Remote Client program from anywhere around the world with Internet connection (refer to "Remote Monitoring and tele-operation" section for detail).

User could also play video, audio and displaying images on the Scout² color display.

Software Installation

Server PC

On the Server Computer, you should install the "Scout-II Control" program from the installation CD.

After program installation, you will find the following programs under the "Start-All Programs" list, and they are installed under the "Program Files" folder.

Dr Robot Inc – Scout-II Control

Application data folder is set to "C:\DrRobotAppFile\"

You will find the following files in this folder:

<i>DrRobotServiceConfig.xml</i>	It contains the IP and port information about the service programs.
<i>RobotConfig.xml</i>	It contains the robot information, such as WiFi modules' IP, Cameras' IP, robot ID, camera user ID and password.
<i>gatewayConfig.xml</i>	Control Center program will save communication settings in this file. Gateway program will use it to setup communication with the robot.
<i>WiRobotGateway.exe</i>	This communication program will setup communication with robot.
<i>RobotHardWareConfig.xml</i>	

Following sub-directories could be found under "C:\DrRobotAppFile\"

.\PathFile\	contains path script files.
.\SensorConfig\	contains the IR Range sensor location information file "IrSensorConfig.xml" and the ultrasonic sensor location information file "UsSensorConfig.xml".
.\Record\	contains all camera video recording files.

PDA (Color Touch Screen) on the Robot

Programs have been pre-installed on the PDA (color touch screen) on Scout².

DrRobotPDASensorClient This program displays Scout² sensor information.

Remote Client Program on Client PC

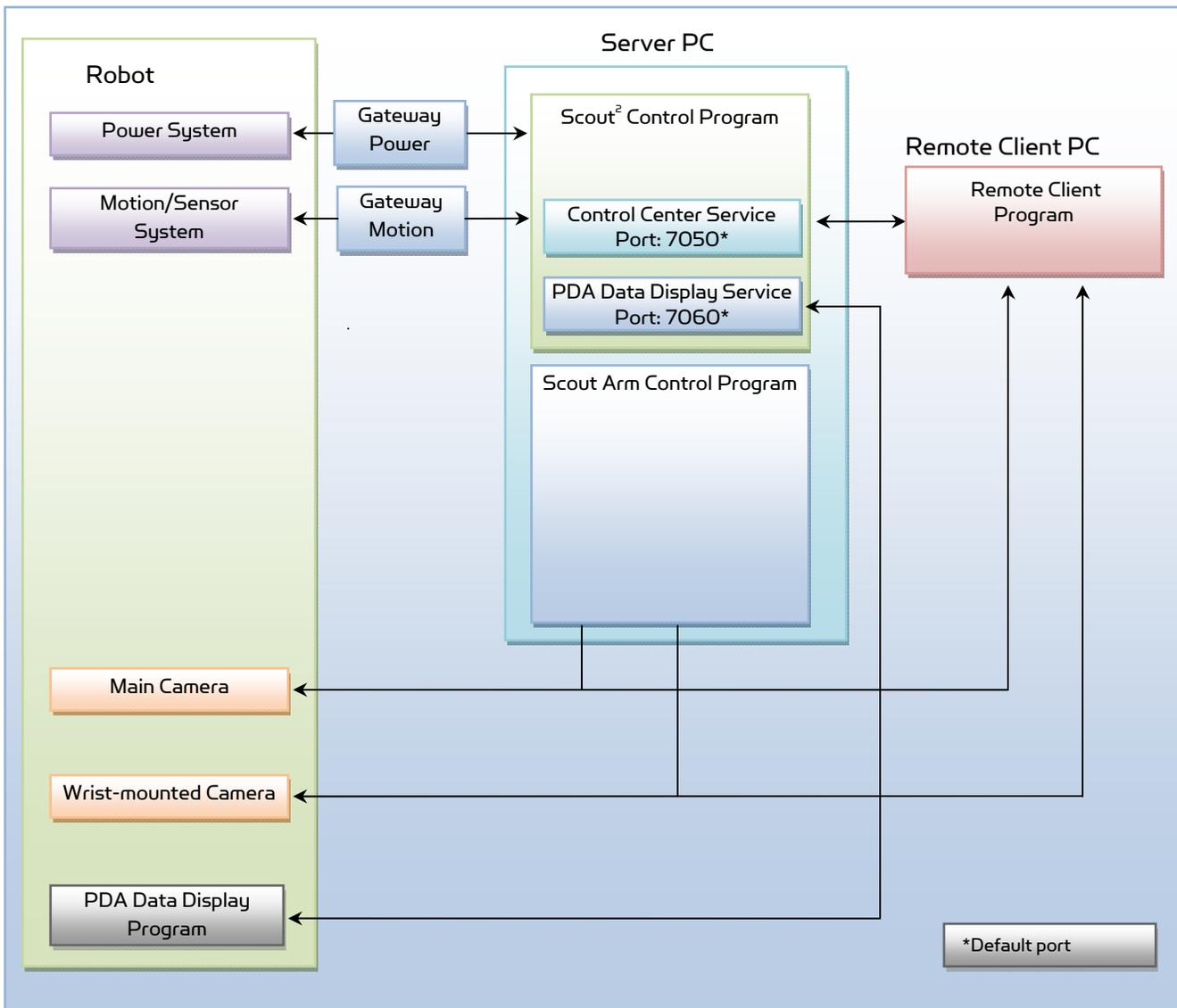
On the client computer, you should install the "Scout-II Remote Client" program from the installation CD.

After program installation, you will find the following programs under the "Start -> All Programs" list, and they are installed under the "Program Files" folder.

Dr Robot Inc – Scout-II Client

Application data folder is set to "C:\DrRobotAppFile\", following sub-directories could be found under "C:\DrRobotAppFile\"

- .\Record\ contains all camera video recording files.
- .\Scout-IIClient\ "DrRobotServerConfig.xml" contains the IP and port information about the server programs.



Robot Operations

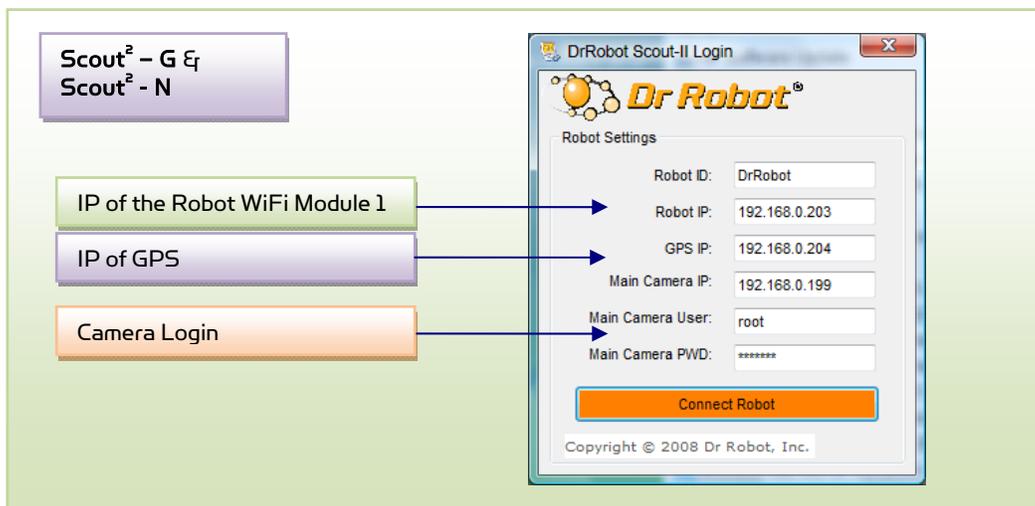
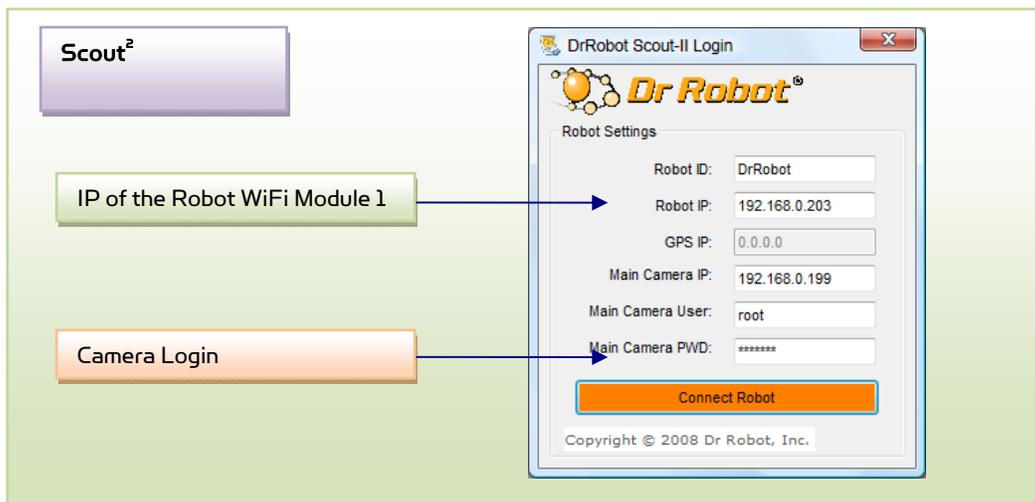
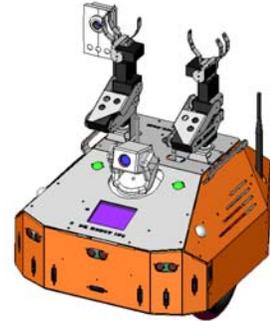
Scout-II Control Program

Step 1: If you have not installed the programs, insert the installation CD to CDROM and run the "Setup.exe" program which under "Scout-II Control Installation" folder to a PC (called server PC), set your PC IP to 192.168.0.104, Gateway: 192.168.0.200 and Subnet Mask 255.255.255.0.

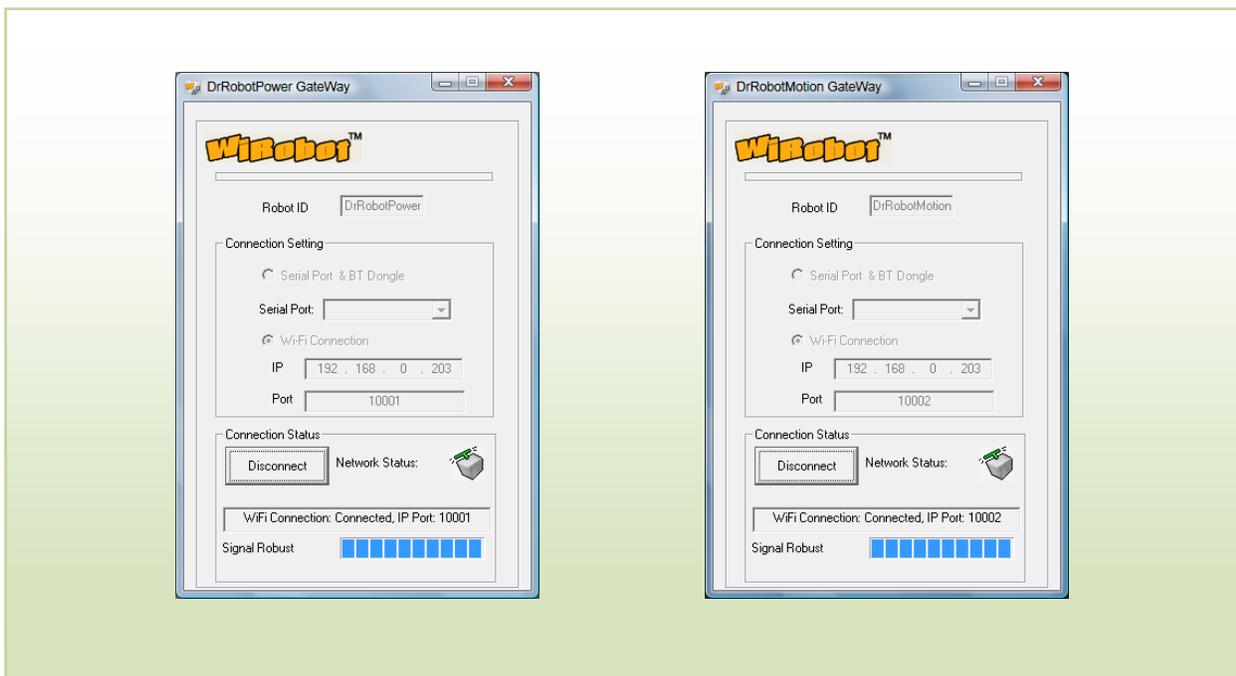
Step 2: Connect the server PC to the wireless router (one of the LAN ports) included in the package (the router has IP 192.168.0.200).

Step 3: Turn on the robot main power switch on the back. NOTE: Always keep a safe distance from the robot.

Step 4: Run the "DrRobot Scout-II Control" from Start -> All Programs -> Dr Robot Inc -> Scout-II Control. The "Scout-II Control" connects to robot via the DrRobotMotion gateway & DrRobotPower gateway programs. It requires robot information which can be found in "Networking Connection and Login Information" section in this manual. After entering or confirming the information, then click "Connect Robot".



Two gateway programs will be called up to establish communication connections with the electronic system on the robot.



The screenshot shows the DrRobot Scout -II Control software interface. It features several tabs: 'Main Sensor Info & Control', 'Path Control', and 'Localization/GPS & SensorMap & Remote Control'. The main window is divided into several sections:

- Camera Section:** Includes a live video feed of a room with a plant and a chair. Below the feed are icons for microphone, speaker, and network. To the right, there are fields for Camera IP (192.168.0.199), Camera Port (8081), Camera ID (root), and Password (*****). A 'Connected' status is shown with a 'Disconnect' button. Below that are 'Camera Control' buttons: Snapshot, Pan, AVI Rec, Stop, and Reset.
- Power Status Section:** Shows Voltage (12.84V), Temperature (18.28°C), and Status (Using) for Battery-I. Battery-II shows 12.92V and 18.48°C, also 'Using'. DCIN is 0.00V.
- Power Path Control:** Includes checkboxes for PowerByBattery-I, PowerByBattery-II, and PowerByDCIN.
- Charge Path Control:** Includes checkboxes for Charge Battery-I and Charge Battery-II, and a 'Stop' button.
- Charge Current Control:** Includes radio buttons for Full Current, Half Current, 1A Current, and Trickle Current.
- Power Switch Control:** Includes radio buttons for ON/OFF for Channel-I, Channel-II, and Channel-III.
- Motion Control Section:**
 - Set Drive Power:** Left: 26384, Right: 6384. Includes 'Go' and 'Stop' buttons.
 - Set Drive Speed:** Left: 200, Right: -200. Includes 'Go' button.
 - Set Drive Distance:** Distance: 0.5, Unit: m, Time: 2000, Unit: ms. Includes 'Go' button.
 - Set Rotation:** Turn: 45, Unit: degree, Time: 2000, Unit: ms. Includes 'Go' button.
 - Chassis Control:** Includes directional arrow buttons and a 'Speed' slider.
- Joystick Section:** Shows X: 4960, Y: 4960. Includes a joystick icon, 'MaxPower: 75%', and 'Joystick Sent Power' (Left: 0, Right: 0). Includes checkboxes for 'Enable Joystick' and 'Joystick Collision Avoidance Drive'.
- Sensors Section:**
 - Ultrasonic Sensor:** #1-#6 all at 2.55m.
 - IR Sensor:** #1-#10 at various distances (0.81m, 0.10m).
 - Human Sensor:** Motion (Left: 2034, Right: 2016), Alarm (Left: 2031, Right: 2031).
 - Extended IO:** Input: 255, Output: 0, with a 'Set' button.
 - Motor Sensor:** Table with columns: Encoder Position, Encoder Speed, Current Feedback, HeatProtect, StuckState.

	Encoder Position	Encoder Speed	Current Feedback	HeatProtect	StuckState
Left Motor	32713	0	0.00A	False	False
Right Motor	32358	0	0.00A	False	False
 - Position Information:** Dead Reckoning: (0.39, 0.21, -3.58), GPS: (0.39, 0.21, -3.58). Includes 'Enable GPS Sensor' checkbox.
- Footer:** Dr Robot logo with 'Extend your imagination™', Copyright © 2008 Dr Robot, Inc. All rights reserved., and www.DrRobot.com.

Three callout boxes on the left side of the image point to specific features:

- Camera Login:** Points to the live video feed window.
- Robot sensor data:** Points to the Ultrasonic and IR sensor data tables.
- Robot position and direction estimated by dead reckoning:** Points to the 'Position Information' section.

Showing status of all power sources:
Battery I, II and external DC input

From where the system will take power from: Battery I, II or external DC input

To control which battery or both to be charged and the max charging time

Charging speed/mode control

Power on/off the sub-systems (detail in Appendix I)

Motor PWM control

Motor speed control

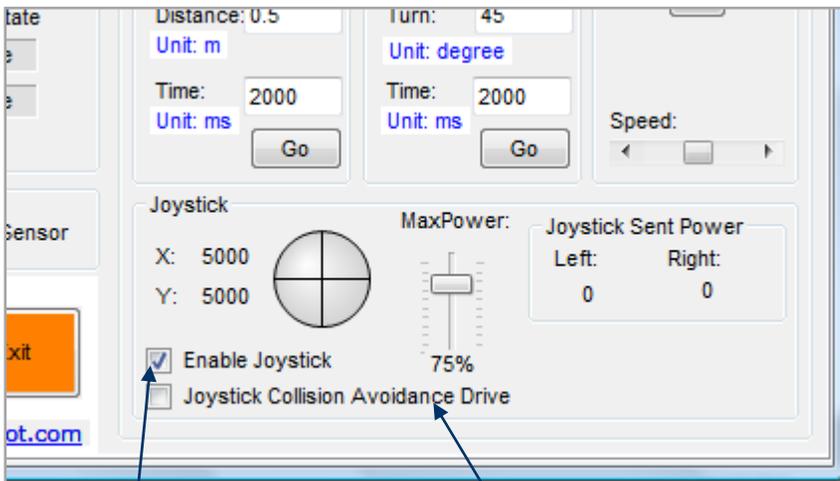
Simple motion control: drive forward, backward, left, right and stop

To turn within set time

Drive forward (set distance) within set time

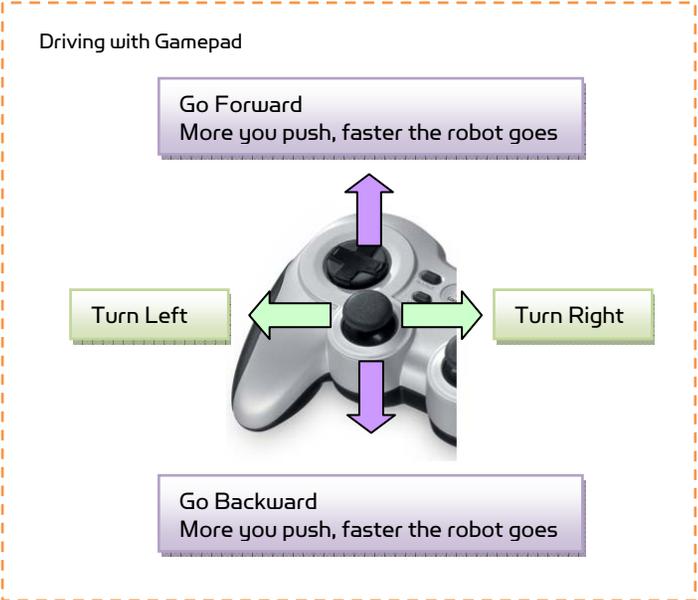
When checked, autonomous collision avoidance feature will be activated during the Gamepad control

Max power output when Gamepad is fully pushed

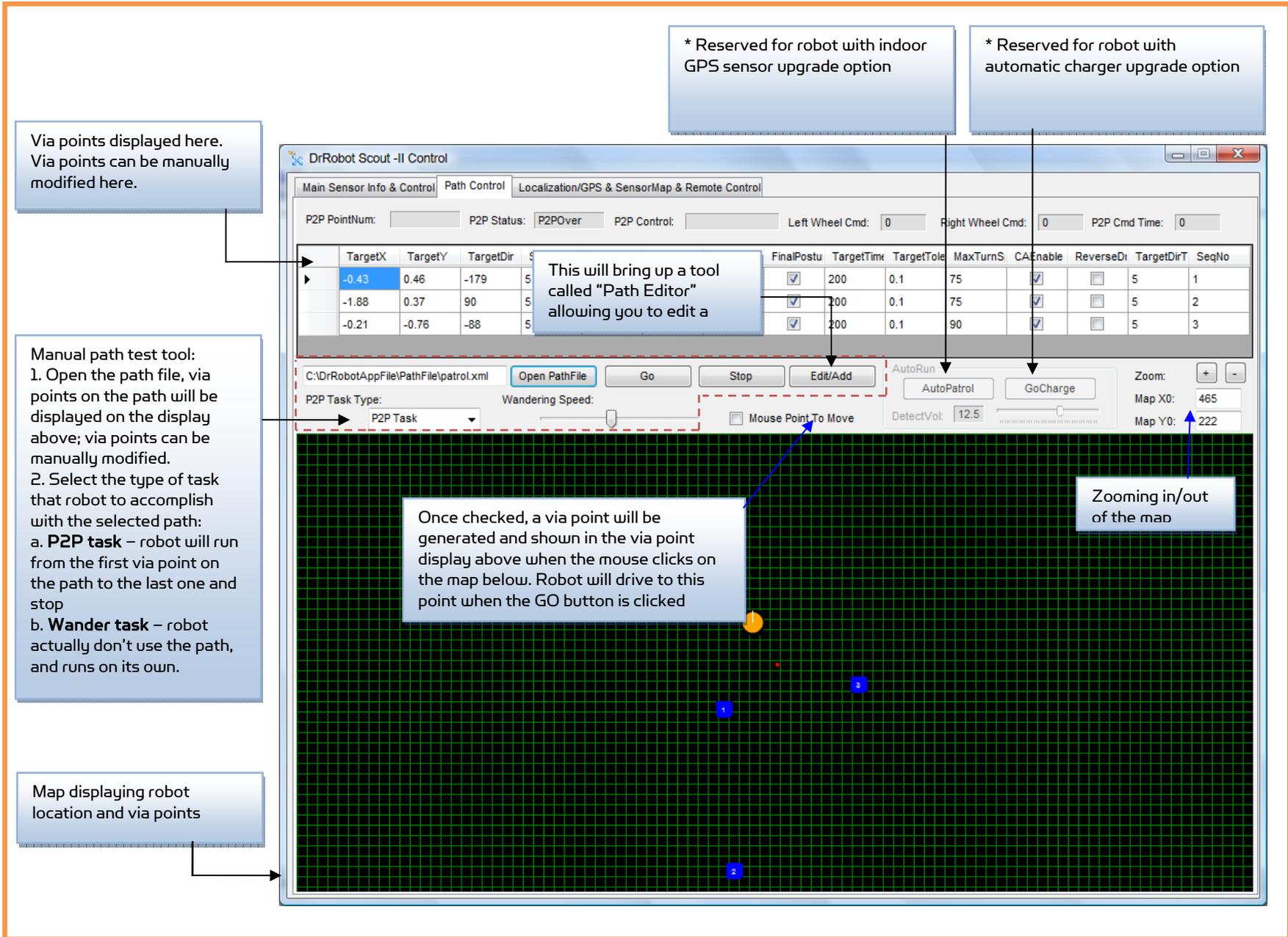


To Enable Gamepad

Robot base collision avoidance feature is enabled by default. During Gamepad operation, you could temporarily disable this feature by holding the red button (#B) on the Gamepad handle (as shown above)



Red Button (#B)
Suspend collision avoidance feature



DrRobot Scout -II Control

Main Sensor Info & Control Path Control Localization/GPS & SensorMap & Remote Control

P2P PointNum: P2P Status: P2POver P2P Control: Left Wheel Cmd: 0 Right Wheel Cmd: 0 P2P Cmd Time: 0

TargetX	TargetY	TargetDir	FinalPostu	TargetTime	TargetTol	MaxTurnS	CAEnable	ReverseDi	TargetDirT	SeqNo
-0.43	0.46	-179	<input checked="" type="checkbox"/>	200	0.1	75	<input checked="" type="checkbox"/>	<input type="checkbox"/>	5	1
-1.88	0.37	90	<input checked="" type="checkbox"/>	200	0.1	75	<input checked="" type="checkbox"/>	<input type="checkbox"/>	5	2
-0.21	-0.76	-88	<input checked="" type="checkbox"/>	200	0.1	90	<input checked="" type="checkbox"/>	<input type="checkbox"/>	5	3

C:\DrRobotAppFile\PathFile\patrol.xml Open PathFile Go Stop Edit/Add

P2P Task Type: P2P Task Wandering Speed: Mouse Point To Move

AutoRun AutoPatrol GoCharge Zoom: + - Map X0: 465 Map Y0: 222 DetectVol: 12.5

The Path Editor opened from the "Path Control" allows you to edit a path file such as the charging and patrol path

The screenshot shows the Path Editor window with several callouts explaining its features:

- Top Callout:** "All path files are listed here, when double clicking on the file, the via points will be loaded onto the via point list for editing." (Points to the Path Motion table)
- Left Callout 1:** "You could create a new path file or save the edited path file from here." (Points to the Record File Name field and New/Save buttons)
- Left Callout 2:** "This path via point list allows you to modify the motion specification of each via point." (Points to the main table of motion specifications)
- Bottom Callout 1:** "You could position the robot to the location you like the robot to go. The robot location will be displayed here. You could add this location into the path by using the 'Add Point'" (Points to the Robot Position fields and Add Point button)
- Bottom Callout 2:** "This path via point display windows shows the via point location. You could drag the point to the location you want the robot to go." (Points to the grid map area)

Path Motion Table:

FileName	PointNum
Charge.xml	4
patrol.xml	2

	TargetX	TargetY	TargetDir	StopTime	ForwardSp	Forgetable	NonStop	FinalPostur	TargetTime	TargetTole	MaxTurnSp	CAEnable	ReverseDr	TargetDirT	SeqNo
▶	-0.41	0.18	0	2	0.5	<input type="checkbox"/>	<input type="checkbox"/>	<input checked="" type="checkbox"/>	200	0.2	75	<input checked="" type="checkbox"/>	<input type="checkbox"/>	5	1
	-0.78	0.17	0	2	0.3	<input type="checkbox"/>	<input type="checkbox"/>	<input checked="" type="checkbox"/>	200	0.2	90	<input type="checkbox"/>	<input checked="" type="checkbox"/>	5	2
	-1	0.175	0	2	0.3	<input type="checkbox"/>	<input type="checkbox"/>	<input checked="" type="checkbox"/>	200	0.2	90	<input type="checkbox"/>	<input checked="" type="checkbox"/>	5	3
	-1.3	0.175	0	2	0.2	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input type="checkbox"/>	200	0.2	45	<input type="checkbox"/>	<input checked="" type="checkbox"/>	5	4

Robot Position Fields: Robot Position X: -3.98, Robot Position Y: -3.93, Robot Orientation: -0.6

Map Coordinates: Map X0: 471, Map Y0: 170

* Reserved for Scout²-N and Scout²-G which with indoor GPS sensor upgrade

Scout²-N & Scout²-G

IP Address:

Port Number:

Mark ID:

Position Data: Position X: m

Position Y: m

Position Dir: degree

GPS Sensor Info:
Connected with Dr Robot GPS

DrRobot Scout -II Control

Main Sensor Info & Control | Path Control | Localization/GPS & SensorMap & Remote Control

Localization/GPS

IP Address:

Port Number:

Mark ID:

Position Data: Position X: m

Position Y: m

Position Dir: degree

Remote Client Control

Server Log:

Remote Client IP:

Received Command

Received Command:

Joystick X:

Joystick Y:

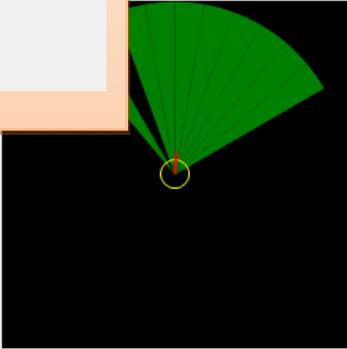
PDA Connection

Server Log:

PDA Client IP:

Set PID Parameter

S_Kp	S_Kd	S_Ki	<input type="button" value="Set"/>
<input type="text" value="15"/>	<input type="text" value="3"/>	<input type="text" value="0"/>	
P_Kp	P_Kd	P_Ki	<input type="button" value="Set"/>
<input type="text" value="1500"/>	<input type="text" value="20"/>	<input type="text" value="0000"/>	



Range (Ultrasonic and IR) sensor object distance measurement

Information about the tele-operation and remote monitoring client
You could disable the remote client

Remote Monitoring and Tele-operation

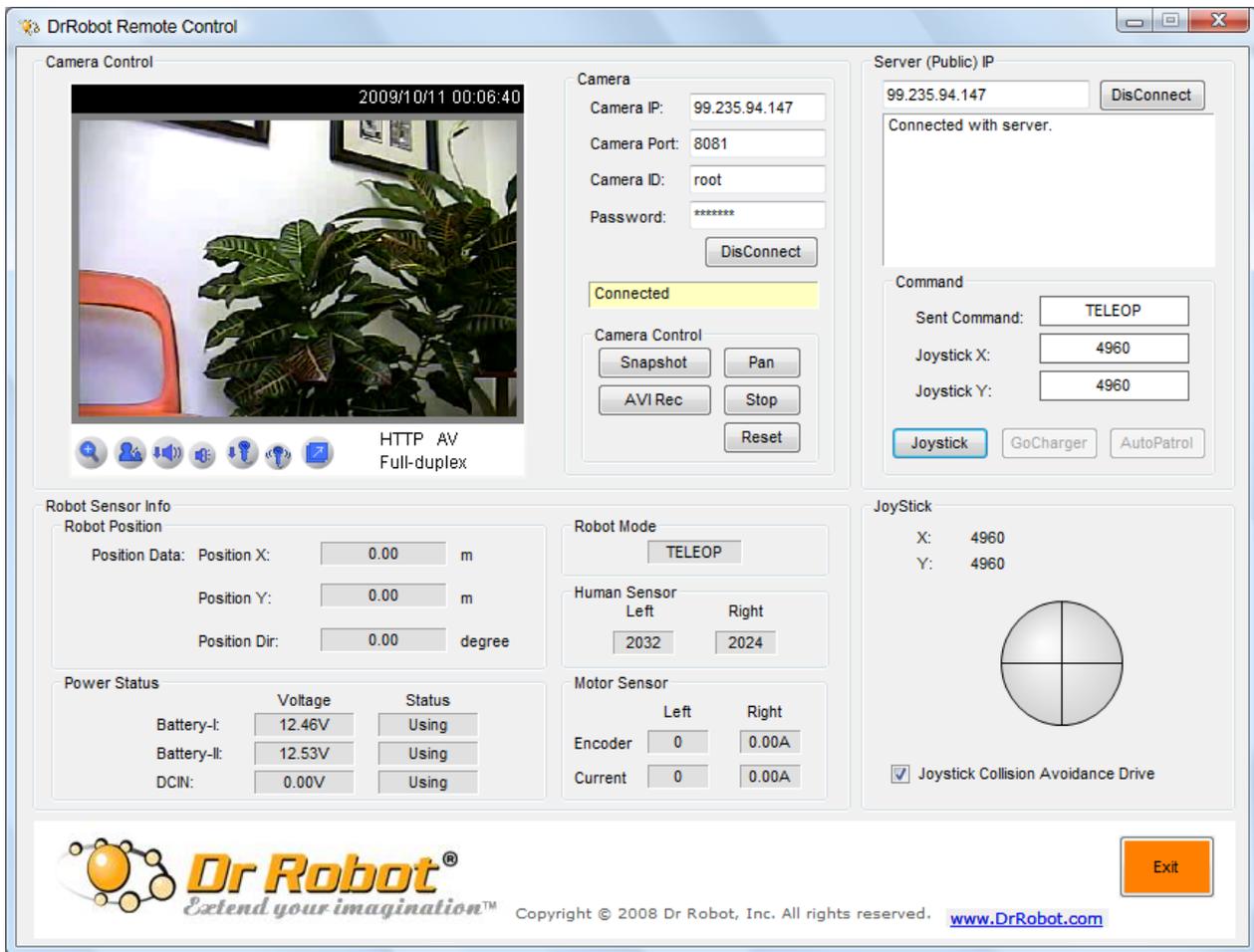
Step 1: If Internet remote monitoring/control is required, you need to connect the wireless router WAN port to your broadband Internet modem. You need to find out the public IP assigned by your ISP. (You should be able to find this information from the router status page) This IP will be used by the remote client to connect to the host PC and the devices on the robot.

If firewall is in-place in your network, you also need to make sure all the network ports used by the wireless devices (8081, 8082 for cameras, 7050 for server program) on the server and remote client sides are not blocked for the Internet remote monitoring/control tasks to operate properly. Proper "Virtual Application" settings should be in place on the router (the robot side). The included router already has these settings pre-configured to direct the outside traffic to appropriate devices (cameras and server PC) behind router. Please refer to "Network Connection and Login Information" section for detail.

Step 2: Installing the Scout² Remote Client program from the installation CD. "Scout-II Client" program allows you to remotely control the robot, obtain main robot sensor information, view, listen and talk through robot.

Step 3: Run the Scout² Client program.

Step 4: Enter or confirm the remote server and other devices' IP. When you are connecting from public network, your server IP must be a public IP, and with the pre-configured router settings, all the devices on the robot will share the same public IP with the server IP. Then click the "Connect".



Arm Control Program

Run the "scout_arm.exe" from Start -> All Programs -> Dr Robot Inc -> ScoutArm Control

The screenshot shows the Scout Arm Control software interface. It features a top section for communication and script motion, and two main sections for arm control (Left and Right). The communication section includes fields for Arm IP (192.168.0.204) and Port Num (10001), with a 'Connect' button. The script motion section includes fields for Left and Right Arm Script Motion Files, with 'Go' and 'Stop' buttons. The arm control sections each have a diagram of the robot arm with numbered joints (1-6) and a list of sliders with numerical values and 'Disable' buttons. The Right Arm Control section has a callout pointing to it labeled 'Arm control section'. Below the arm control sections is a camera control section with a video feed and fields for Camera IP (192.168.0.99), Camera Port (8082), Username (root), and Password (*****). A callout points to the password field labeled 'Wrist-Mounted Camera (* option for Scout)'. The bottom of the interface features the Dr Robot logo and website information.

Type in the IP and Port number, click "Connect"

Select demo "Motion" script; click "Go" to run.

Arm control section

Wrist-Mounted Camera (* option for Scout)

Recharging

To keep the battery at ideal condition, we recommend recharging the robot at least once every two weeks during storage (e.g. robot is not in use).

Plug the charging plug from the portable charger onto the secondary recharging socket on the back of the robot, **and then turn on the robot**. The charging process will normally take about 2 hours if the battery power is totally exhausted. The charging process will automatically stop when completed.

Further Development & Programming

The Scout² Control program is written with C# program with Visual Studio 2008 express under .Net 3.5 framework. You could download the development tools (Visual Studio 2008 express under .Net 3.5 framework) free from Microsoft. Please refer to the "Dr Robot Application Development Notes on C# Programming for Robot Control" for further information.

The control program uses the supporting components and libraries that should have been installed when you install the control program from the installation CD:

1. **DRROBOTSentinelCONTROL.OCX**: Please refer to "WiRobot SDK API Reference Manual.pdf" for detail.
2. **WiRobotGateway.exe**
3. **DrRobotSensorMapBuilder.dll**: This dll file provides functions to build the environmental map for collision avoidance feature.
4. **DrRobotP2PSpeedDrive.dll**: This dll file provides functions to drive a robot from one specific point to another.
5. **DrRobotConstellation.dll**: Scout² robot uses the ultrasonic based Constellation indoor GPS localization system (option). This dll file provides the functions to locate the robot position with the Constellation system.
6. **DrRobotGPS.dll** Scout² use the vision-landmark based indoor GPS localization system (option). This dll file provides the functions to locate the robot position with vision based GPS system.
7. **VitaminControl.dll** This is the camera control component for the Pan-Tilt-Zoom camera (P/N: AV-PTZ-VH) used for i90 series robots such as Sentinel², Sentinel³, Scout², Sputnik² and Sputnik³. Please refer to "PTZ Camera ActiveX Control Reference Manual.pdf" for detail.
8. **AXIS Media Control Library Set** These are the camera control component for the AXIS Mini Camera used for the Dual-camera Head and Scout arm. Please refer to "AXIS Media Control SDK Help" for detail.

For support on development using Microsoft Robotics Studio, operation system other than MS Windows, or raw communication protocol, please contact support@DrRobot.com.

Network Connection and Login Information

Network Settings

As default, your PC running the Scout² Control program should have IP settings as below:

Name	Server PC	IP (Port)	192.168.0.104
Gateway	192.168.0.200(Router IP)	Subnet Mask	255.255.255.0

The included pre-configured wireless 802.11 b/g router has the following pre-set settings:

SSID	dri	Router LAN	192.168.0.200
WEP	128bits	Login ID	admin
KEY	112233445566778899AABBCCDD	Password	drrobot
Key Type	Open Key		

with virtual server settings as followings:

Virtual Server	Port	Protocol	Server IP
Scout ² Client program	7050	TCP/IP	192.168.0.104
Main Camera	8081	TCP/IP	192.168.0.199
Hand Camera	8082	TCP/IP	192.168.0.99

WiFi module connects to two serial devices through channel I and II (TCP/IP port 10001 and 10002 respectively). They are pre-configured as below:

Name	Robot WiFi Module 1	IP	192.168.0.203 (or labeled on robot)
Channel-I (10001)	115200,,8,N,1, no flow control, UDP, Datagram 01, remote IP:0.0.0.0	Channel-II (10002)	115200, 8,N,1, flow control, UDP, Datagram 01, remote IP:0.0.0.0

Name	Robot WiFi Module 2	IP	192.168.0.204(or labeled on robot)
Channel-I (10001)	115200,,8,N,1, no flow control, TCP, remote IP:0.0.0.0	Channel-II (10002)	115200, 8,N,1, no flow control, TCP, remote IP:0.0.0.0

Other wireless devices settings are listed below:

Name	IP (Port)	Login	Password
Main Camera	192.168.0.199 (8081)	root	drrobot
Hand Camera	192.168.0.99 (8082)	root	drrobot

Advanced Network Settings

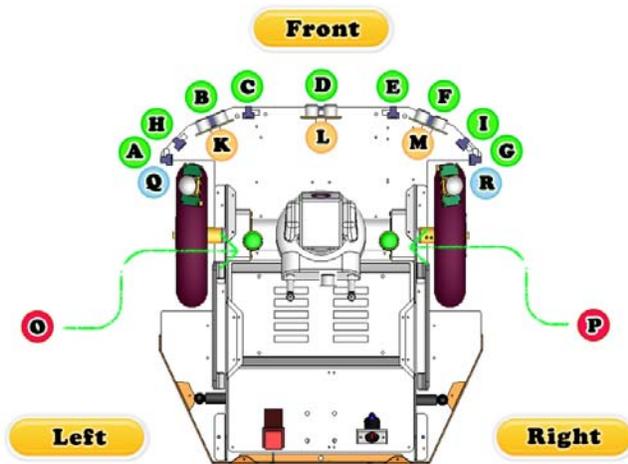
It's possible to use different network settings (e.g. IP) for the server PC, in this case, the "Virtual Server" settings on the router must also be changed accordingly in order for the Internet remote monitoring feature to work properly. You could also change the router settings such as IP and SSID etc. If you need to do so, you are required to change the network settings on the WiFi modules on the robot by following the guidelines as illustrated on the WiFi Module manual.

Appendix I Power Switching Control

Three power sub-systems as defined below could be turn on or off individually through the "Scout-II Control" or "Scout-II Client" Program.

Channel-I	DC-DC board -I	Main Camera (12V)
Channel-II	DC-DC board -I	1. PMS5005 Main power (5V), GPS (5V) power, Arm Servo Control Board (5V)
		2. PDA, LED 5V, Hand Camera 5V
	DC-DC board-II	3.3V for WiFi module 2
Channel-III	DC_DC board -I	6V left arm servo power
		6V right arm servo power

Appendix II IR Sensor Control Reference



- Using AD Extended Port
- A--- IR Range sensor
 - B--- AD extended port 3
 - C--- AD extended port 4
 - D--- AD extended port 5
 - E--- AD extended port 6
 - F--- AD extended port 7
 - G--- AD extended port 8
 - H--- Tilting sensor X
 - I--- Tilting Sensor Y

Appendix III SSC-32 Board Connection

Right Arm using channel 0 – channel 5

Left Arm using channel 16 – channel 21



Support Team Contact Information:

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