## Robot Dynamic Calibration Toolbox Main Validation Scripts orientation, csv(t,q,v) wrench est csv(t,wrench) **Wrench Estimation Scripts** Force Torque Sensor Script t.a.v.tau.orientation Dynamic Identification Scripts Friction Identification Scripts EndEffector Model csv(t,q,v) csv(t,q,v,tau) \_\_\_\_\_t,q,v,tau,orientation out: rdcp(params) URDF,v csv(t,q,v,dv) URDF csv(t,q,v) csv(t,q,v) csv(t,q,v,tau) RegressionMLPRDCModel Robot Trajectory ExecutorFriction Model Trajectory Generator (get\_friction\_identification\_trajectories) RobotAPI SerialRobotTrajOptimizer MLPSolver JointTrajectory SciPy t,q,v,tau,orientation Z1\_SDK out: rdcp(params) q,v,tau,orientation ext tau est q,v,dv out: reduced regressor t,q,v,tau RegressionRDCModel Pinocchio PinocchioRegressionRDCModel FilteredPinocchioRegressionRDCModel LSESolver tau, regressor out: filtered tau, filtered regressor tau, regressor out: filtered tau, filtered regressor out: friction tau est get\_filtred (offline) Friction Model LiveFilter (get\_numerical\_coulomb\_viscouce\_friction\_regressor) SciPy SciPy LSESolver Легенда Модуль Модуль без подмодулей Подмодуль Внешние библиотеки Скрипты запуска согласно ПМИ