

login /iCub	iCub-head
/iCubAdmin	iCub

Calibration if fine calibration is quite fine

(e.g. ankles turned, feet not flat)
put leg joints idle 0.25s. and back.

⇒ twoFeetStandingIdleAndCalib.sh (hold the robot. It will adjust position)

⑭ red light blinking

long press button — until green. wait motors^{Lights} stop blinking
shut down yauprobotinterface.

yaup clean.

start again.

see forces measured by robot with iCubGui.

move base in iCubGui

yaup rpe /iCubGui/base:i

>> 0.0 0.0 0.0 0.0 0.0 1000.0

} This is to visualize
vertical forces at the
feet (when on ground)

Sometimes if robot falls / goes into hardware fault, some joints will reach their limits. When restarting yauprobotinterface, these joints will not fail being started / put into home position / controlled

+ yaup motorgui : put joints in idle (the faulty joints)
move them back into their range
run joints
home the robot.