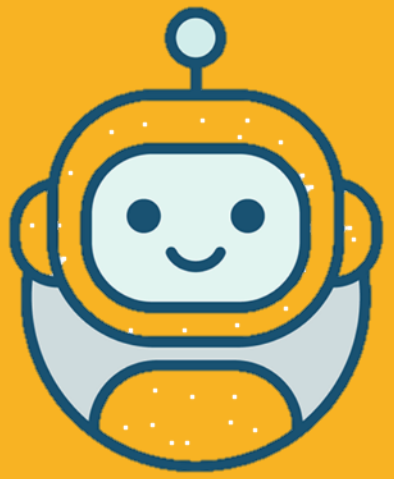
EASY ROBOTICS FORMATION FOR MAKERS

# MINICAT WORKSHOP & CURRICULUM



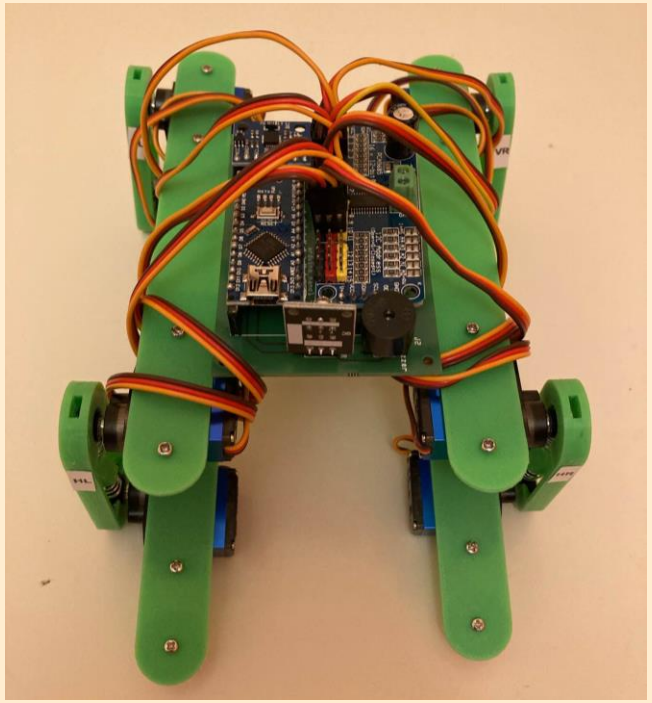
ALEXIS VEYNACHTER

16.11.2021

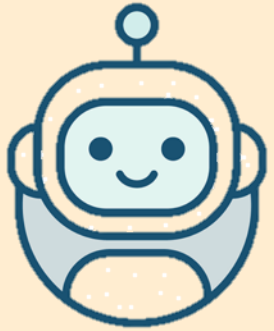
# MINICAT WORKSHOP

**Affordable robotics for makers**

- Build your full robot from scratch !
- Workshop at Schools / MakerFabs



# AGENDA



- Workshop Introduction
- 3D Parts models & Printing
- Hardware Modules & Test
- Final Software Integration

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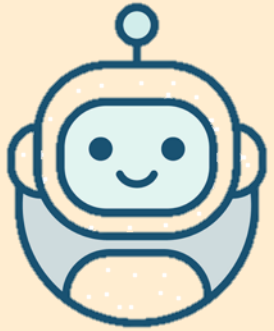

- **Workshop Introduction**
- 3D Parts models & Printing
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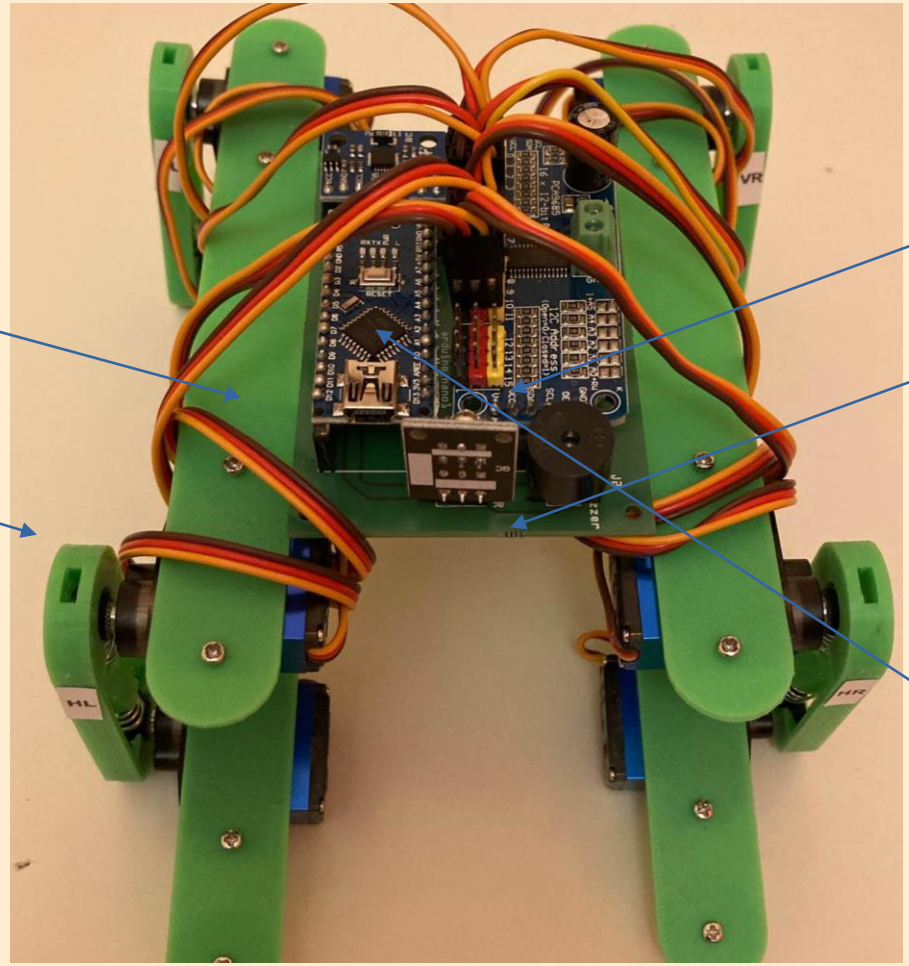
- Final Software Integration

# Workshop Overview
## MiniCat Robot modules



**1. 3D Printed parts**

Body structure

4 legs

**2. Electronics**

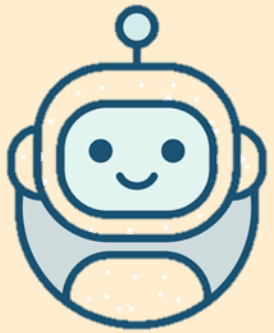
Electronics Modules on custom PCB (green)

**3. Software**

Running on Arduino Module

# Workshop Overview

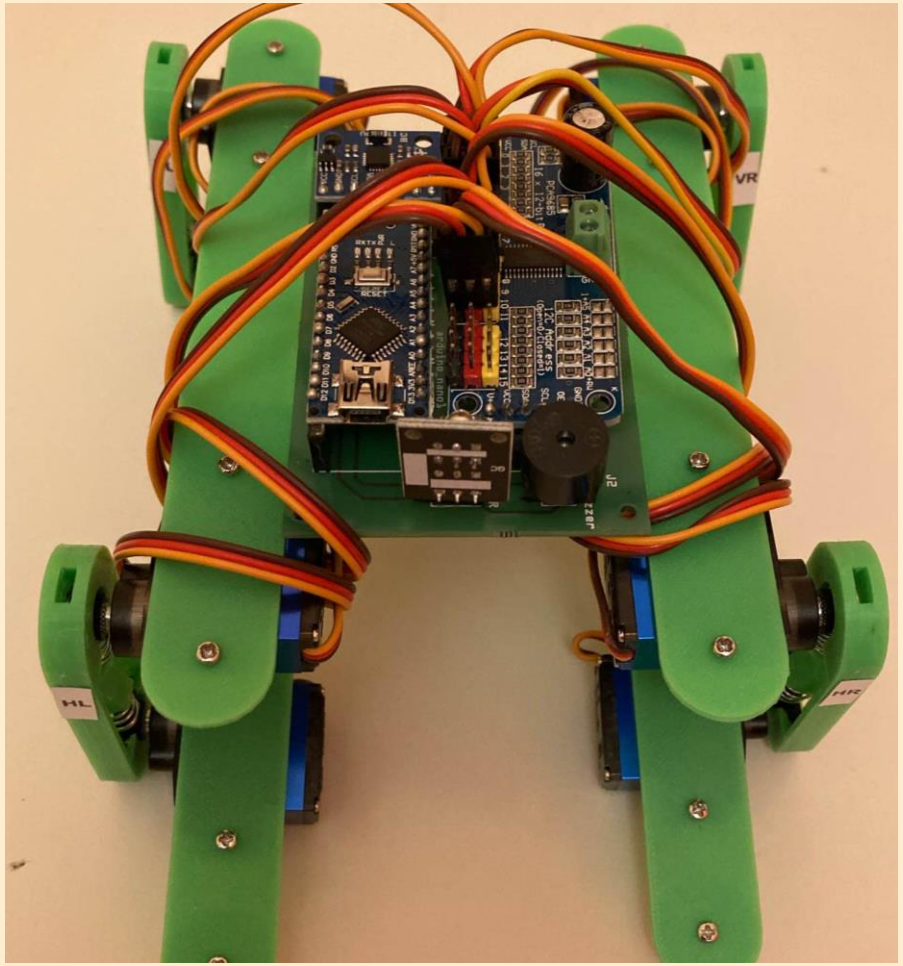
## Maker tools installation check w/ participants



**1. Tools for 3D Print**

**- Modelling**
- **Fusion360** tool
- .stp files

**- Slicing/Printing**
- **Cura** tool
- .STL files



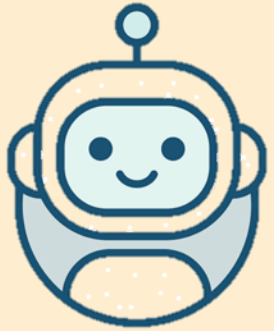
**2. Tools for Electronics**
- no in scope

**3. Software**

**- Development Environment**
- **Arduino IDE** tool

# Workshop Overview

## Toolset installation (to do before workshop)

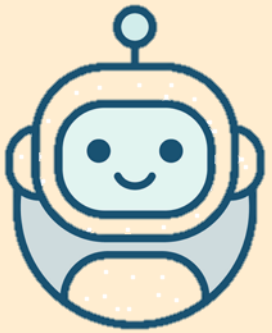


- **Open : https://roboticsformakers.com/index.php/maker-software-tools/**

- **Follow the instructions to install all the Maker tools**

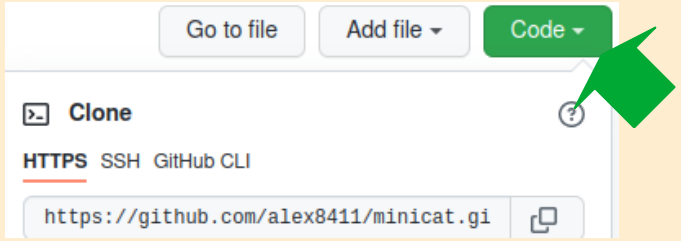
# Workshop Overview

## Software download



**- Open : https://github.com/alex8411/minicat**

**- Click on “Code” then “Download ZIP”:**



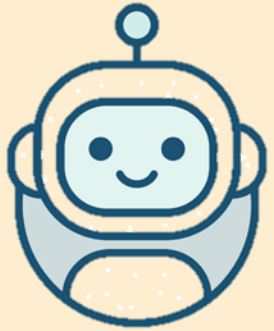

**- Store the ZIP in your preferred Folder & extract it to get “minicat-main”**

**ToDo :**

**- Explore the folder especially :**

- **“3D_printing”**
  - 3D parts for modelling & 3D print
- **“Software” for MiniCat Modules**
  - **GIT** .ino files
  - Remark: Libraries to install separately

# AGENDA



- Workshop Introduction
- **3D Parts models & Printing**
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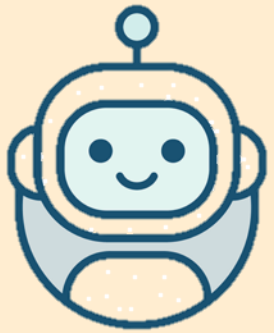
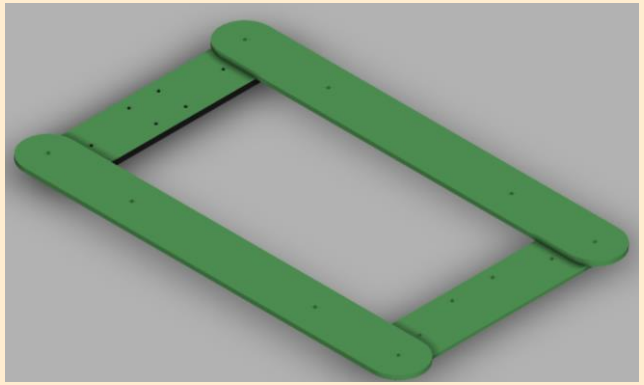
# 3D parts models & printing



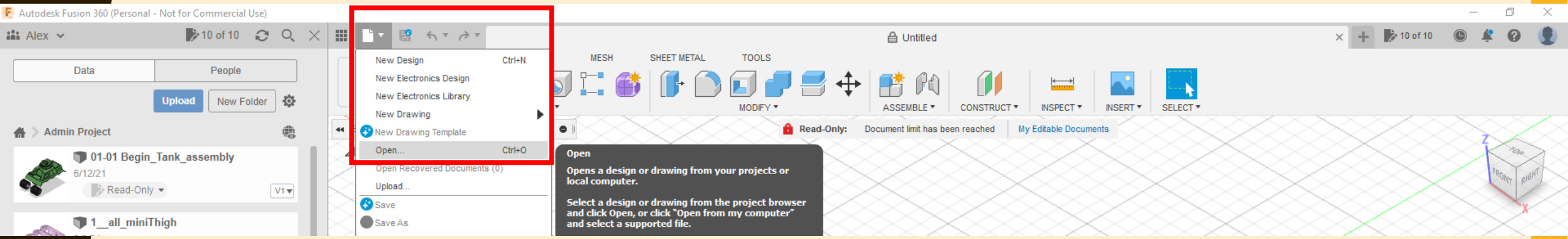
**ToDo** (.f3d assemby opening)



- Open **Fusion360**

- Click on “**File/Open/Open from my computer**”

- Navigate to “minicat-main/CAD/” & click “**MiniCat_full_assembly_v32.f3d**” (works only on Windows 10)



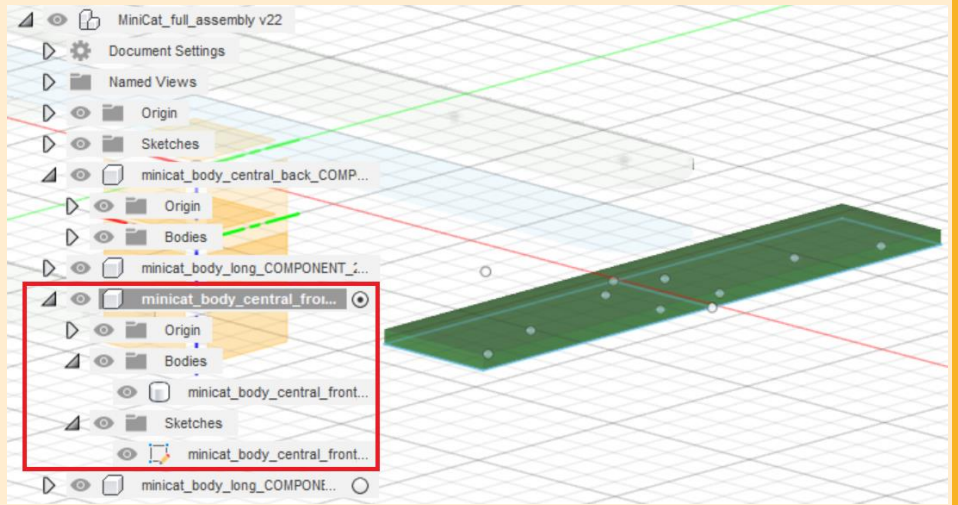
# 3D parts models & printing

**ToDo** (Sketch opening & modifying)

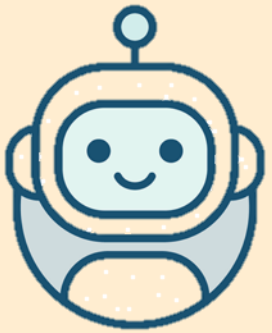
- Navigate to:
    - “minicat_body_central_front_COMPONENT”
        - “Sketches”
            - “minicat_body_central_front_SKETCH”

- Right click on: “minicat_body_central_front_SKETCH”
    - “Edit Sketch”

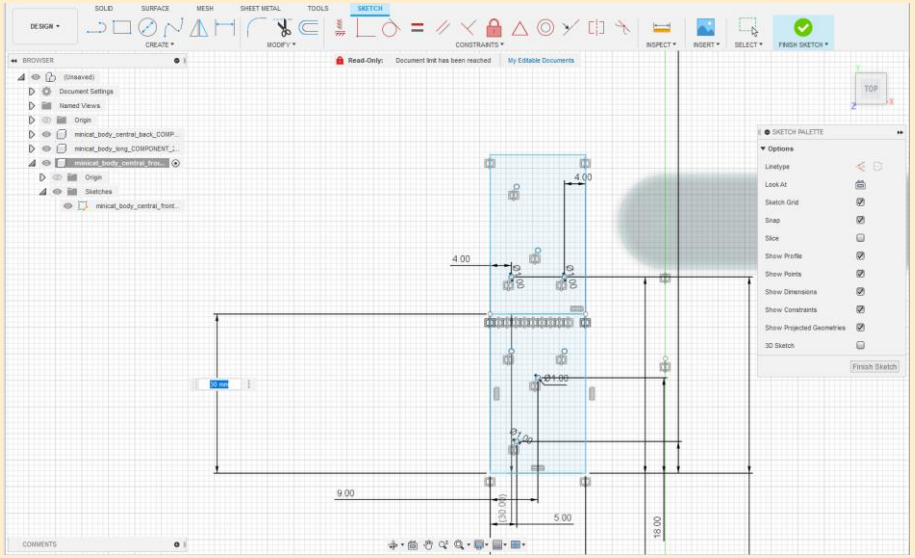
- Try to modify it

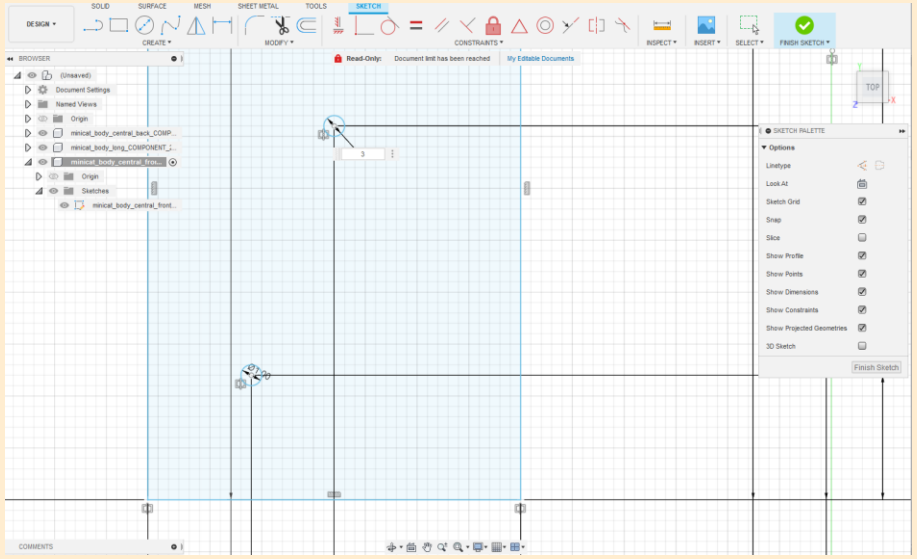


# 3D parts models & printing



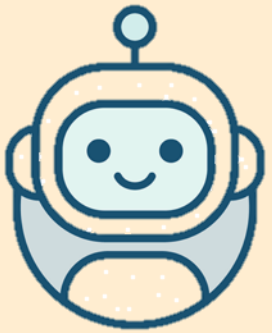
- **ToDo Editing the Sketch front part : rectangle and hole dimensions:**



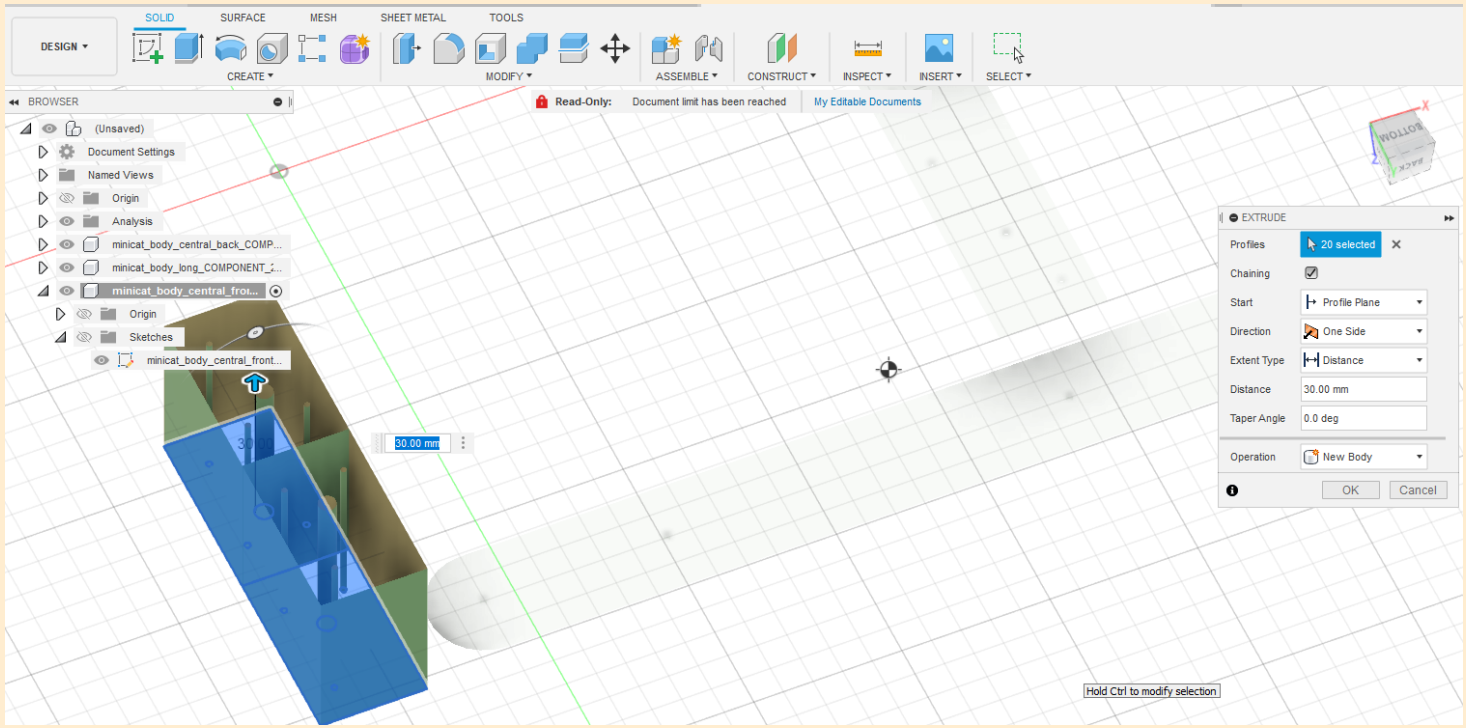


- click on “Finish Sketch” and observe the changes

# 3D parts models & printing

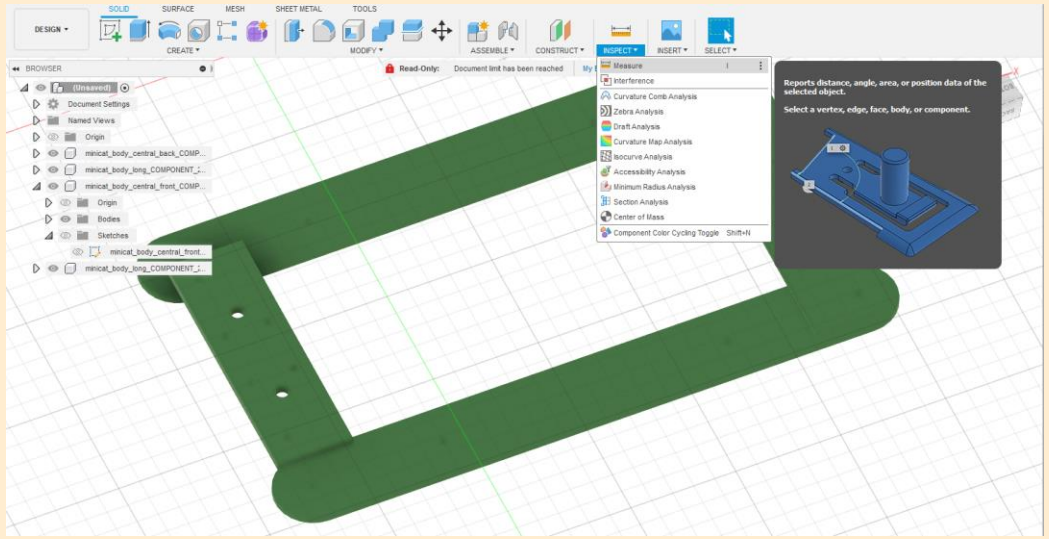


- **Changing the Extrusion dimension :**

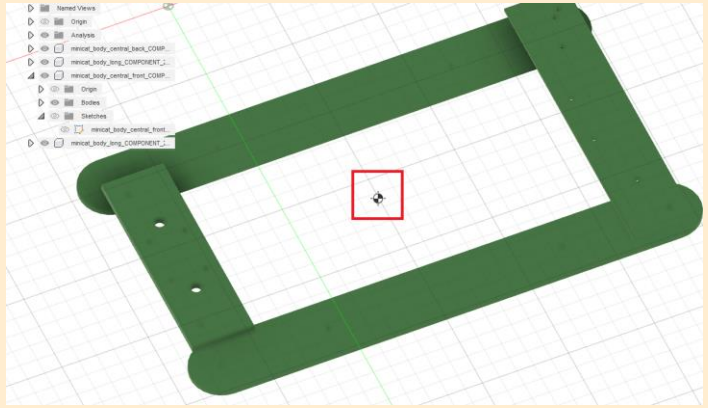


# 3D parts models & printing

- - measuring with “Inspect” a dimension :




- - and gravity center :

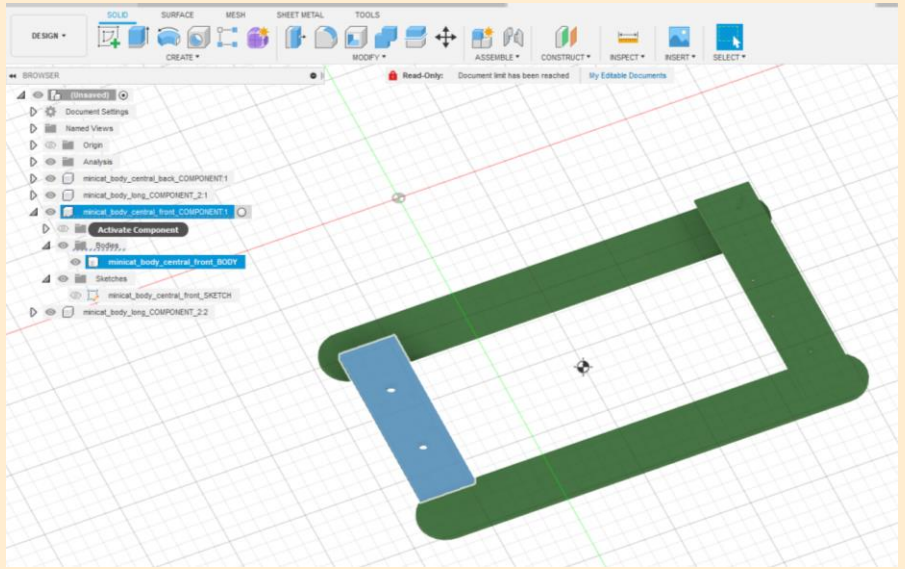


# 3D parts models & printing

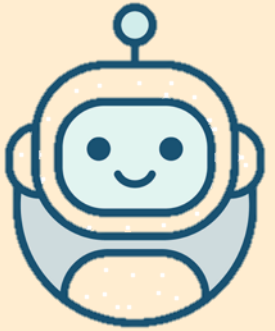
**ToDo** (.STL file generation)

- Navigate to: “**minicat_body_central_front_COMPONENT**”
  - “**Bodies**”
    - “**minicat_body_central_front_BODY**”

- “Activate” the “**minicat_body_central_front_COMPONENT**”



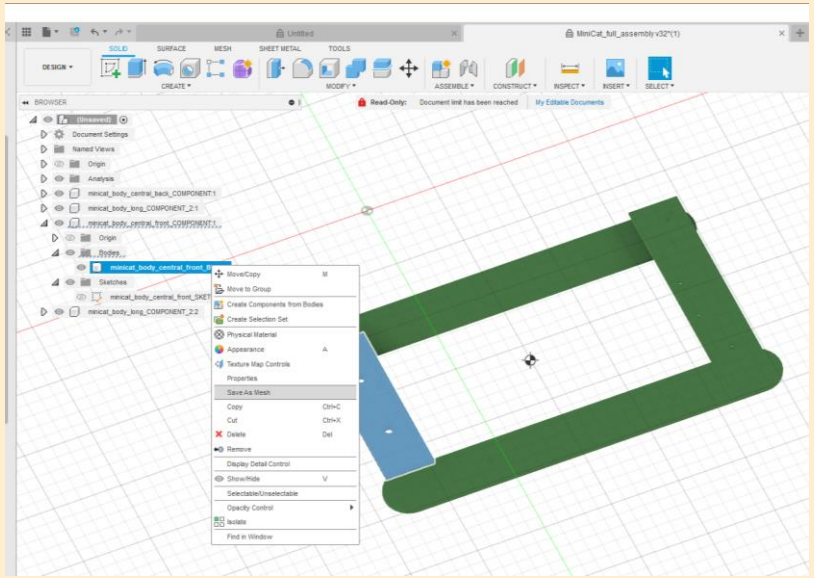
# 3D parts models & printing



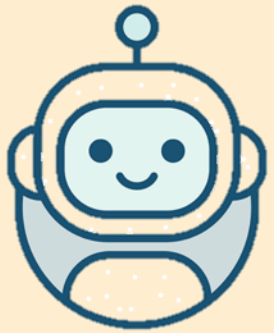
**ToDo** (.STL file generation)

- Right click on “minicat_body_central_front_BODY”

- “**Save as Mesh**” (=“als Netz speichern”)
/ and select Format “**STL (Binary)**” / “Save”



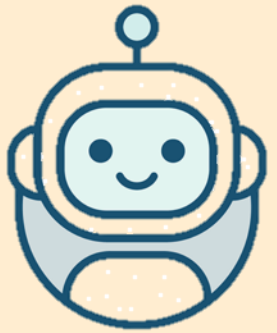
# 3D parts models & printing



**ToDo** (.STL file generation)

- Open CURA and Add a Non Networked Printer “**Creality Ender3 Pro**”
- “File/**Open file(s)” the .STL file you just generated** !
- “**Slice**” it !
- Check the “**Preview**” / click on “Play” button
- “**Save to Disk**” to save it as a 3D Printer Machine code **(.gcode**)

# 3D parts models & printing
## .STL file, generate your own



**ToDo** (Opening Toes .STL, Slicing & Simulation)

- For the Workshop we will not use the previously generated Body STL file but use an existing .STL : "**minicat-main/3D_printing/STL/3__all_miniToe_rubber.stl**"

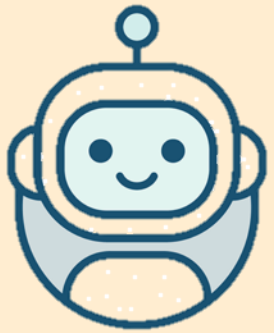
- Background :
  Printer is now optimized for TPU ("gummi") print, not PLA rigid plastic

- Open CURA

- Open "minicat-main/3D_printing/STL/3__all_miniToe_rubber.stl"

- **"Slice" and write the time**

# 3D parts models & printing
## .STL file, generate your own



**ToDo** (3D printer config for TPU)

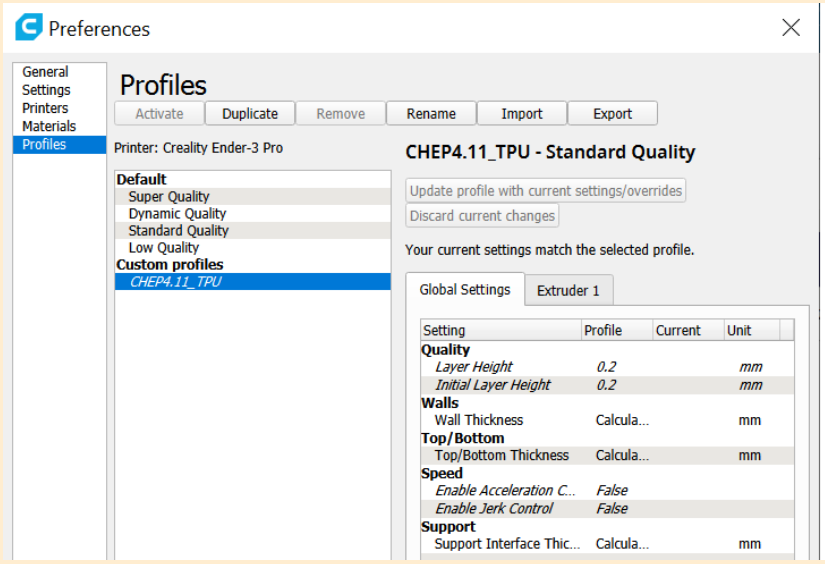
- Open Cura
- click on “Preferences/Configure Cura/Profiles

- ”Import” the content of “CHEP4.11_TPU” profile
  from “minicat-main/3D_printing/printing_profiles/ender3pro/tpu”

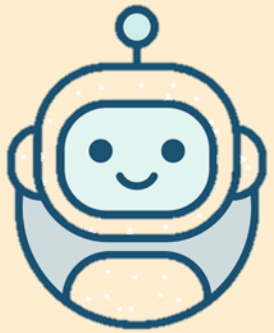
- ”Activate” the profile (work on on Mac, Windows10)

- Open your previously generated .STL file

- Slice it and check if the simulated printing time is different
  with the TPU profile vs “Default/Standard Quality” profile
- **“Save to Disk”** (**.gcode** machine code)



# 3D parts models & printing

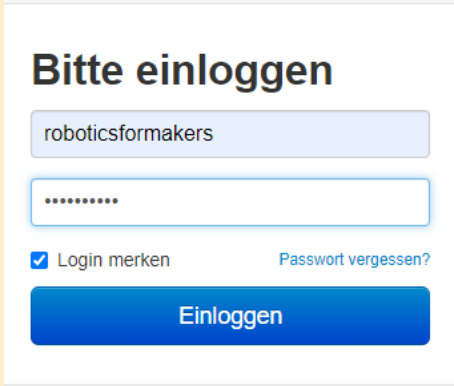


**ToDo** (Printing !)

**3 ways to print a .gcode file :**

**1- SD Card:**
- save generated .gcode and plugin in printer

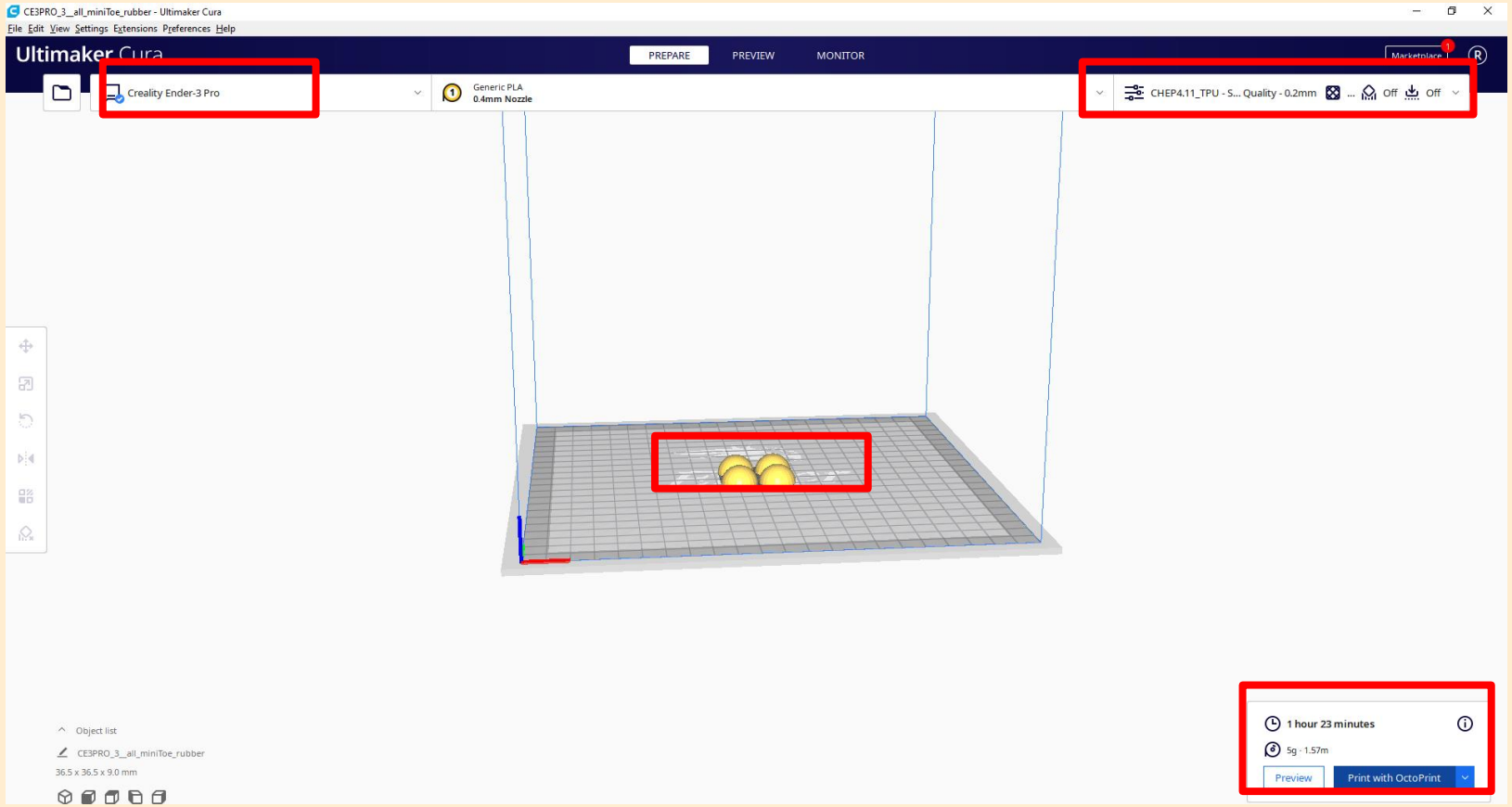
**2- Octoprint Server on Raspi:**
**<u>- WLAN :</u>**
connect to **HUAWEI** WLAN / Password: **2Groesser?**
**<u>- Server :</u>**
- open http://octopi.local/login in your browser
- login: **roboticsformakers** / Password: **2Groesser?**

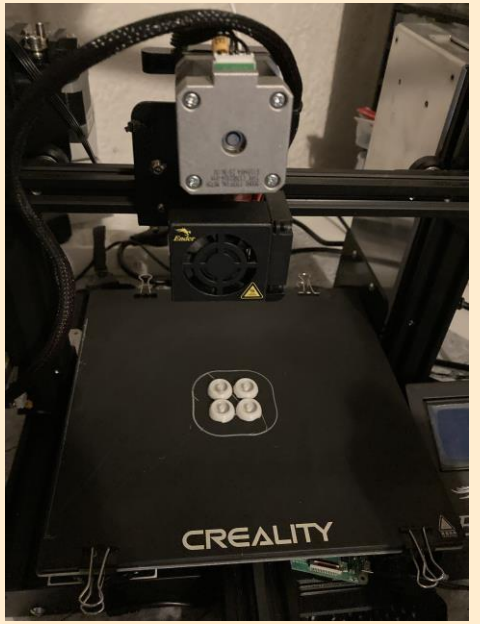



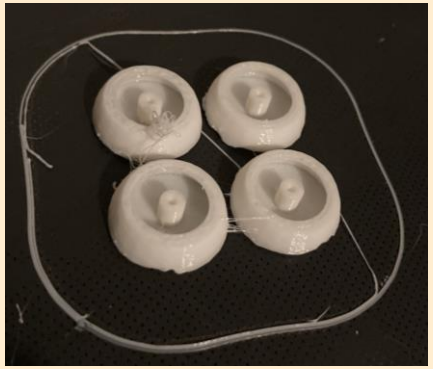

**3- Octoprint Plugin for CURA: -> Focus today**
- connect to HUAWEI WLAN / Password: 2Groesser?
- open CURA and install Octoprint Plugin
- start the “Preparation” and Print

# 3D printing

**I loaded the TPU (flexible filament profile) in CURA and generated the .gcode for you :**



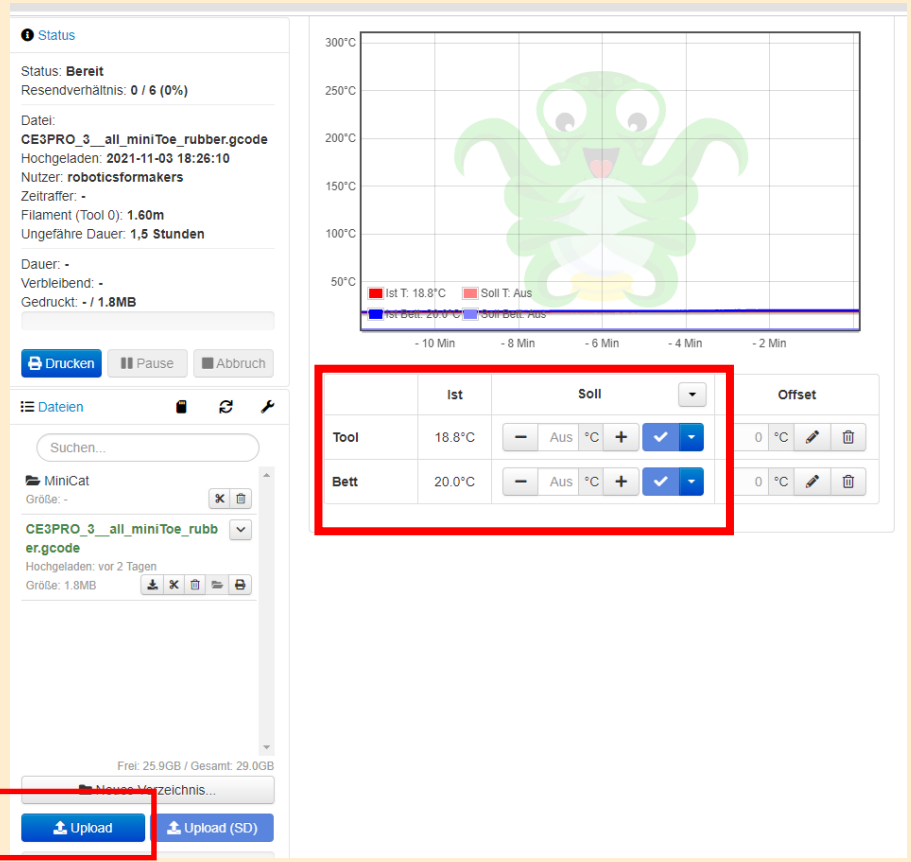



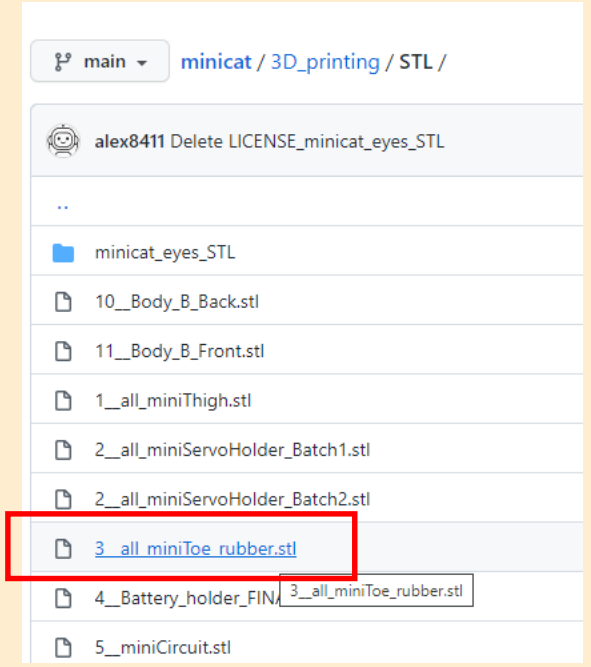



# 3D parts models & printing

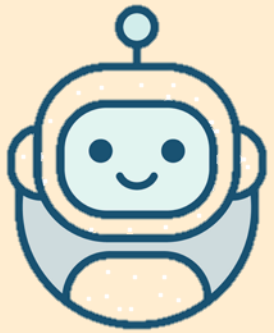
- Try to change some params : in “**Temperatur**” “Soll” for “**Tool**” and “**Bett**”
  - click on “**Upload**”

- - choose “minicat-main\3D_printing\gcode\creality_ender3pro\ CE3PRO_3__all_miniToe_rubber.gcode



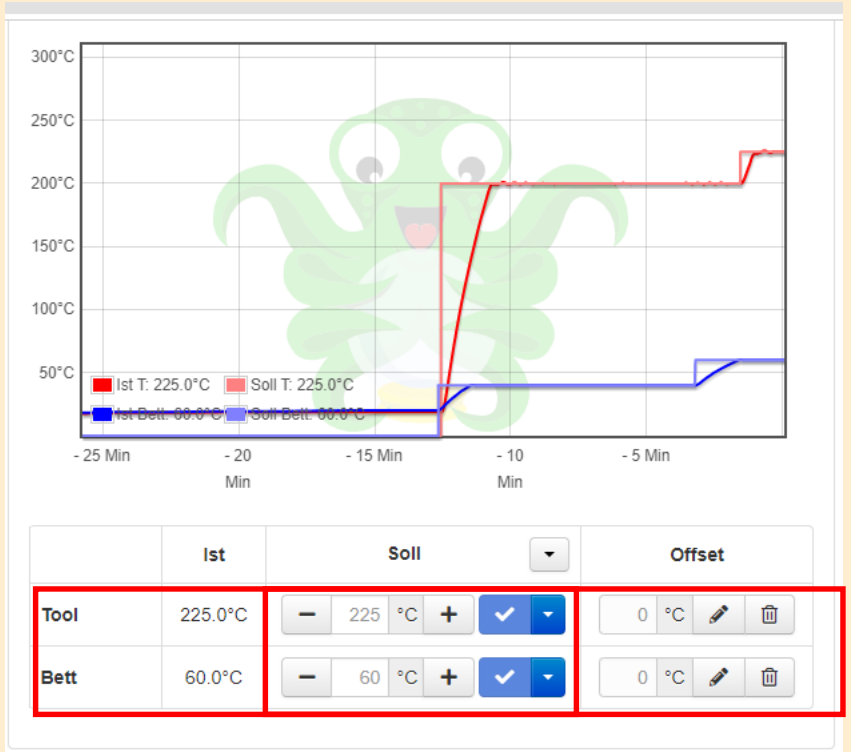



# 3D parts models & printing



**3D print w/ Octoprint :**

- Preheat the Tool (Extruder) at 225°C
- Preheat the Bed at 60°C



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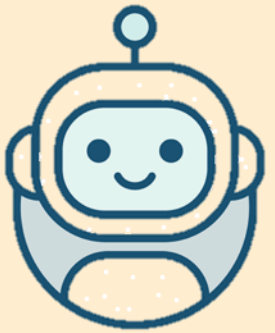
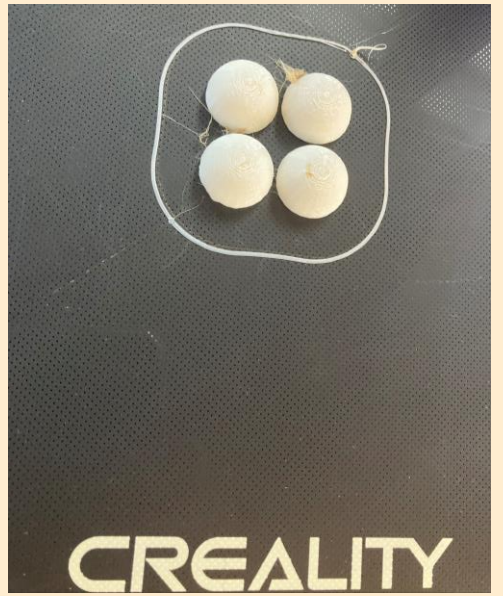


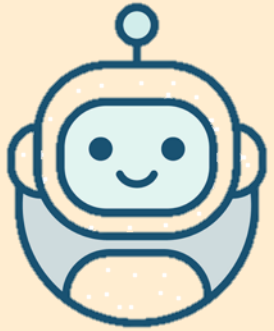
- **IMPORTANT**: Ask the teacher first !
- **only one participant can start the printing after another !**


End of the 2h

After the 2 hours break :



# AGENDA



- Workshop Introduction
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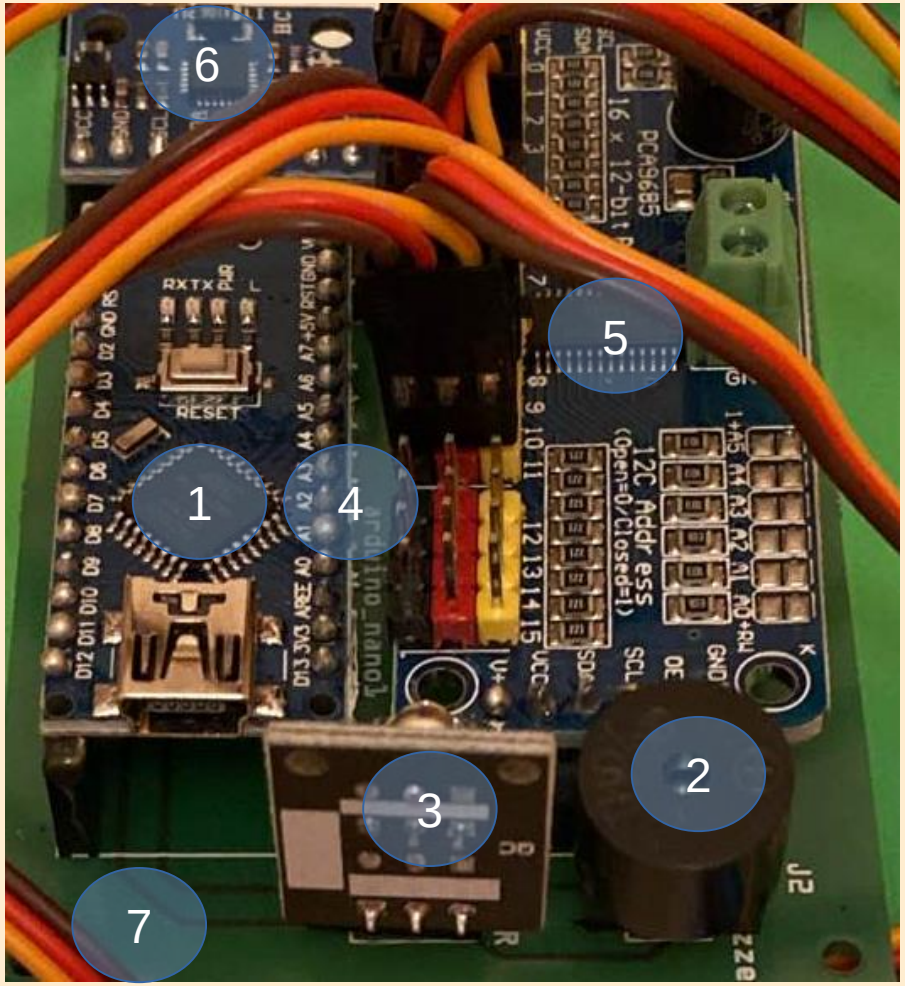
- **Hardware Modules & Test**
- Final Software Integration

# Hardware Modules & Test

## Overview




**Module 1: Arduino board**
- “Brain” of the robot, runs Software

**Module 2: Buzzer**
- “Alive” signal generation

**Module 3: Infrared Receiver & Remote**
- Remote control

**Module 4: I2C Bus**
- comm. Betw. Arduino, Servomotors & Gyro boards

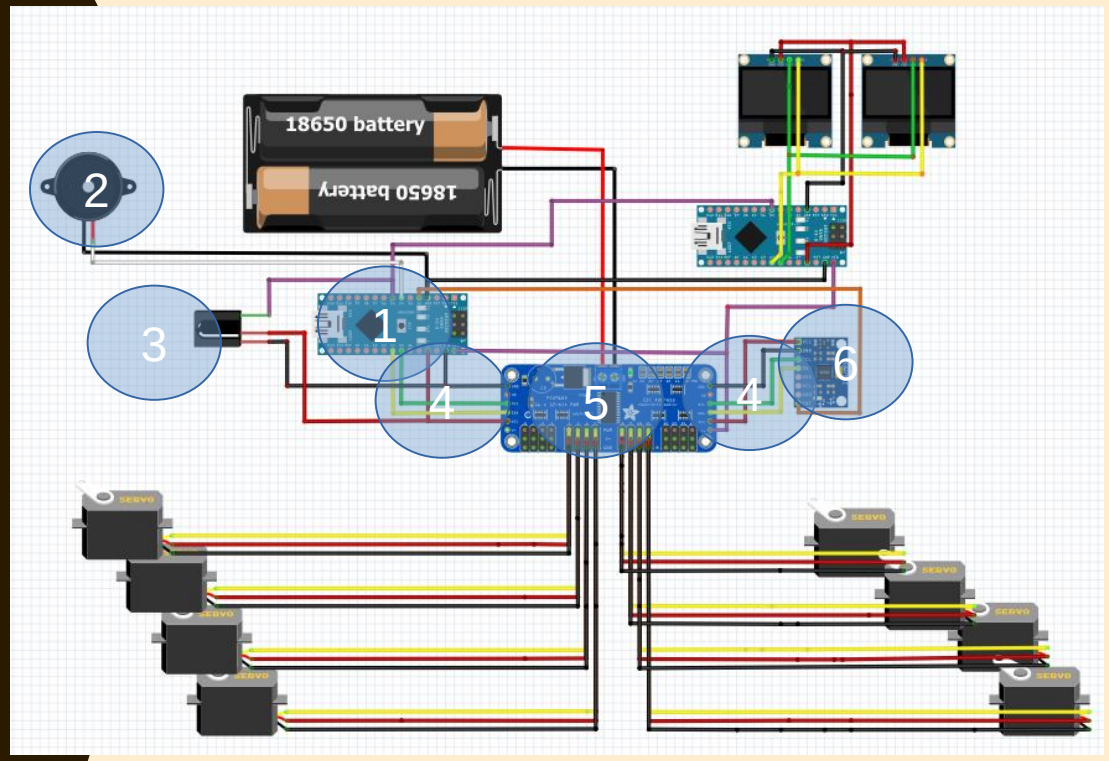
**Module 5: Servomotors driver board**
- drives the 8x Servomotors

**Module 6: Gyroscope board**
- roll/pitch/yaw meas. vs calibrated 0 for robot balance

**Module 7: PCB w/ all Modules & Final Software**

# Hardware Modules & Test

## Overview

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- comm. between Arduino, Servomotors & Gyro boards

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- roll/pitch/yaw meas. vs calibrated 0 for robot balance

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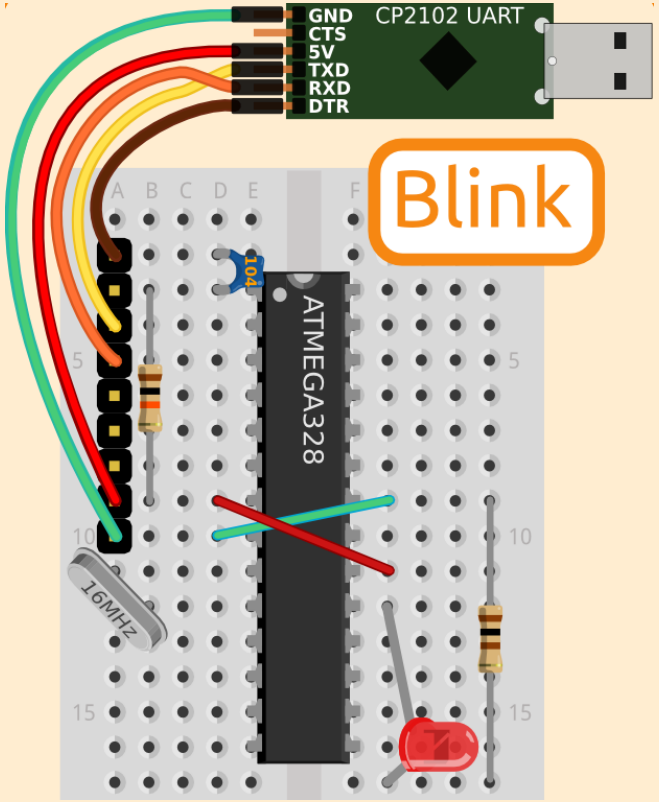
# Hardware Modules & Test

## Module 1: Arduino Board, blink Led

# Hardware Modules & Test

## Module 1: Arduino Board

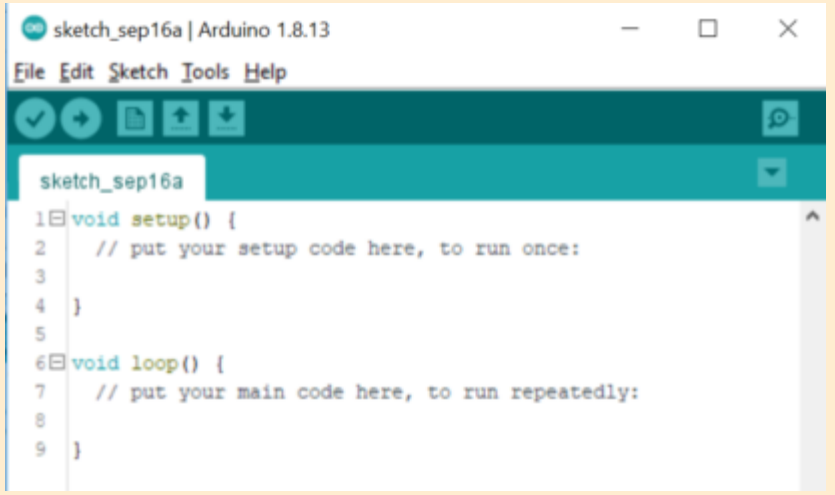

Your Laptop USB

**Module 1: Arduino board & blink Led**

- “Brain” of the robot, runs the Software

**ToDo**:

- Plugin the provided USB cable to your Laptop
- Start the Arduino IDE

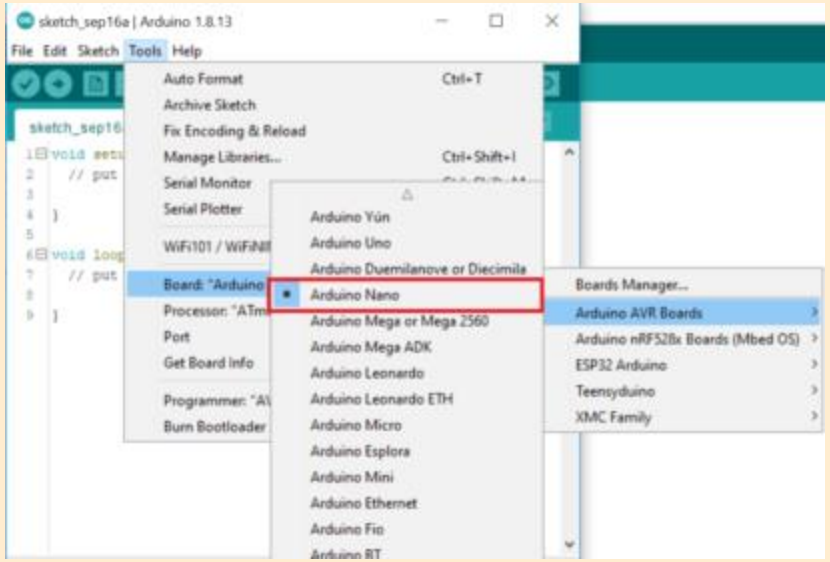


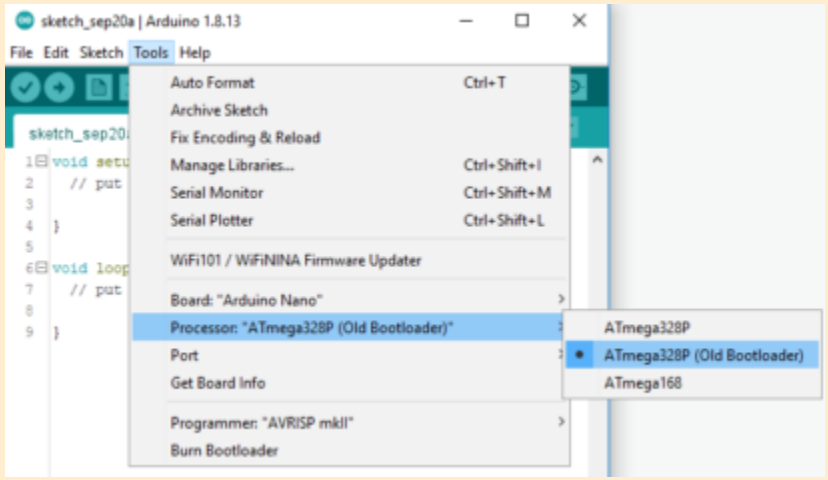
# Hardware Modules & Test

## Module 1: Arduino Board


Your Laptop USB

**ToDo**: - Connect Arduino Nano Board w/ PC over USB
- In the IDE, choose the Serial Port "**COM***"
- Choose the Board "**Arduino Nano**"
- Choose the Bootloader "**Old Bootloader**"



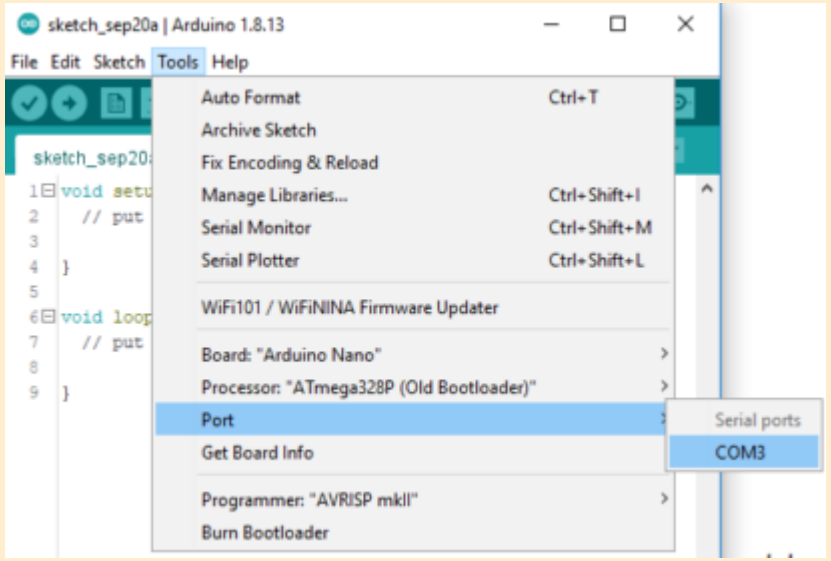
# Hardware Modules & Test

## Module 1: Arduino Board


Your Laptop USB

**ToDo**:

- In the IDE, choose the USB / Serial Port you are using :



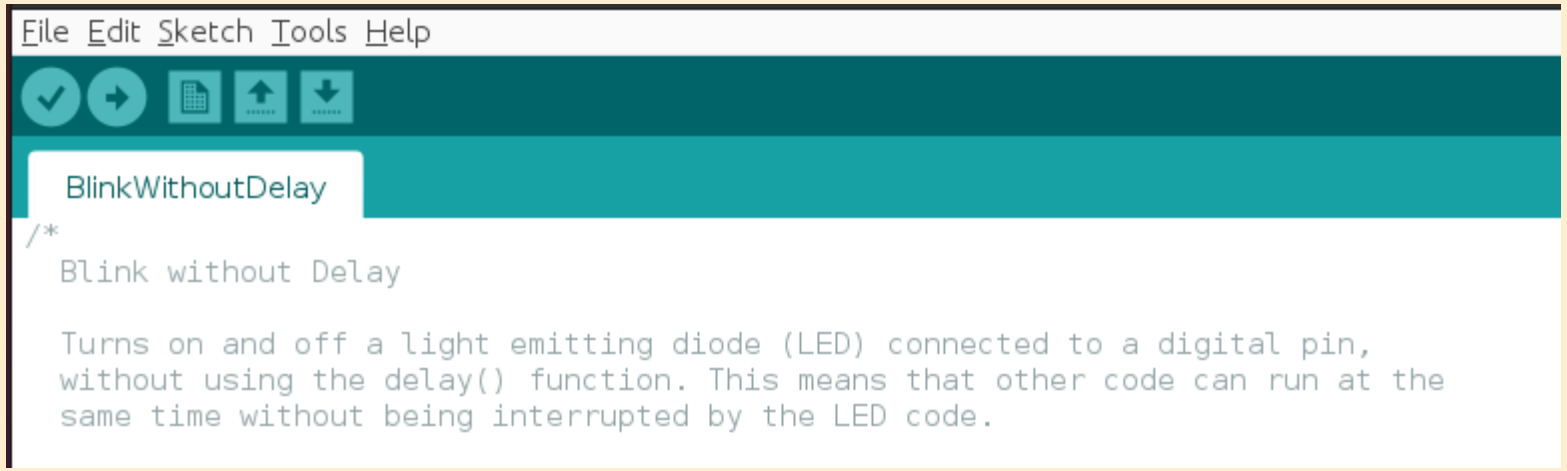
# Hardware Modules & Test

## Module 1: Arduino Board


Your Laptop
USB

**ToDo**:

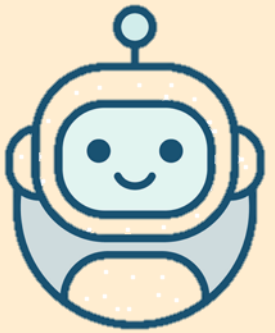
- Click on ”File/Examples/Digital/**Blink without delay**”




- For Windows 10, please install **USBtoSerial driver „CH340G**
this is part of MiniCat GIT, see Software folder (or „DirectLink“)
- MacOS and Ubuntu 20.04, no problems, no driver needed

# Hardware Modules & Test

## Module 1: Arduino Board & Led



*BlinkWithoutDelay.ino*

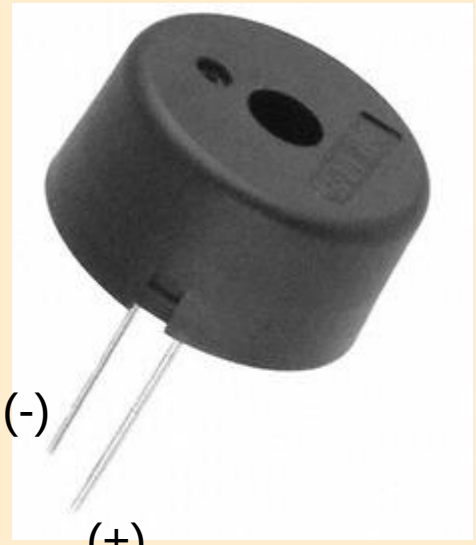
```
// constants won't change. Used here to set a pin number:
const int ledPin =  LED_BUILTIN;// the number of the LED pin

// Variables will change:
int ledState = LOW;             // ledState used to set the LED

// Generally, you should use "unsigned long" for variables that hold time
// The value will quickly become too large for an int to store
unsigned long previousMillis = 0;        // will store last time LED was updated

// constants won't change:
const long interval = 5000;           // interval at which to blink (milliseconds)
```

**ToDo (Software):**

- Change the **blinking interval** to 5000 (default 1000=1s)
- Click on **“Upload”** to start the Software
- **Observe the result on the Arduino board**

# Hardware Modules & Test

## Module 2: Buzzer




**Module 2: Buzzer**

- “Alive” signal generation

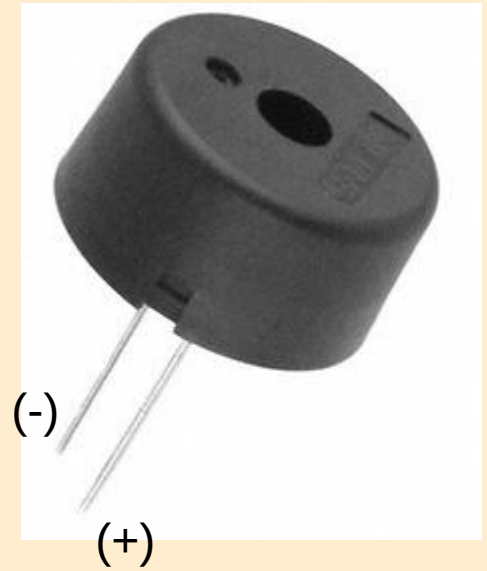
**ToDo**:

- Unplug the USB cable from your Laptop
- Plugin the **Arduino &** **Servodriver board** on the PCB
- Plugin the USB cable to your Laptop

**- open the buzzer test software :** double click on “minicat-main/Software/buzzer_test/minicat_buzzer_test.ino”

# Hardware Modules & Test

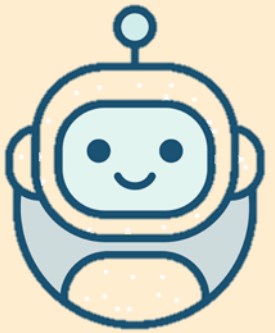
## Module 2: Buzzer, modify the code adding:




```
int counter = 0;

void loop() {

  while (counter < 5)

  {

   byte melody[] = {8, 13, 10, 13, 8, 0, 5, 8, 3, 5, 8,    // definition of the tones list as a "melody"
                    8, 8, 32, 32, 8, 32, 32, 32, 32, 32, 8
                    //8,8,16,16,8,16,16,16,16,8
                   };
  playMelody(melody, sizeof(melody) / 2); // we play the melody

  }

}
```

# Hardware Modules & Test

## Module 2: Buzzer



*minicat_buzzer_test.ino*

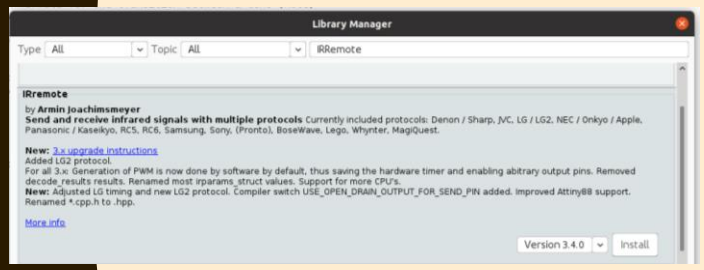
```
void loop() {


  byte melody[] = {8, 13, 10, 13, 8, 0, 5, 8, 3, 5, 8,   // definition of the tones list as a "melody"
                   8, 8, 32, 32, 8, 32, 32, 32, 32, 32, 8
                  };
```

**ToDo (Software):**

- Change the melody by changing the values / deleting some
- Click on **“Upload”** to start the Software
- **Observe the result on the Arduino board**

# Hardware Modules & Test

## Module 3: Infrared receiver & remote


**Module 3: Infrared receiver & remote**

- Remote Control

**ToDo**:

- Unplug the USB cable from your Laptop
- Plugin the Infrared receiver on the PCB
- Plugin the USB cable to your Laptop
- Check if the led is ON when you push the remote

- the **Software Library** "IRRemote" should be installed (Tools/Manage Libraries "IRremote")
- **open the IRRemote test software :** double click on "minicat-main/Software/ minicat_IRremote_test /minicat_IRremote_test.ino"

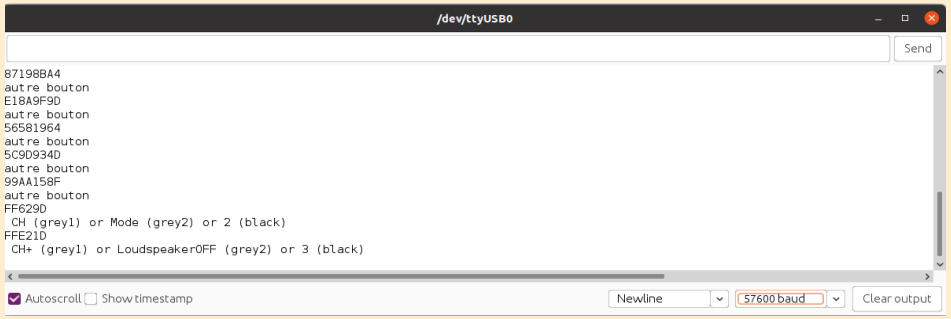
# Hardware Modules & Test

## Module 3: Infrared receiver & remote


**ToDo**:

- Open the Arduino **Serial Monitor** (Arduino IDE “Tools/Serial Monitor”)

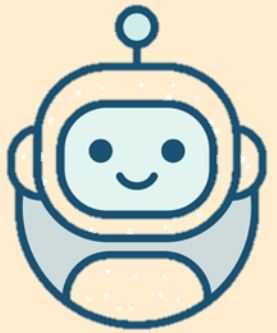
- in serial monitor, set the communication speed to **57600 baud**




- **Push on the buttons** on the Remote control and verify that they are correct in the Serial Monitor

# Hardware Modules & Test

## Module 3: Infrared receiver & remote



**ToDo (Software)**:

- change a button description :

- push this button on remote

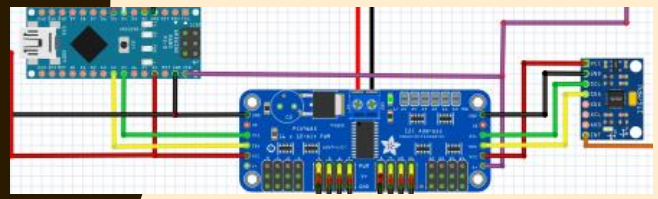
- verify that it is displayed in the serial monitor

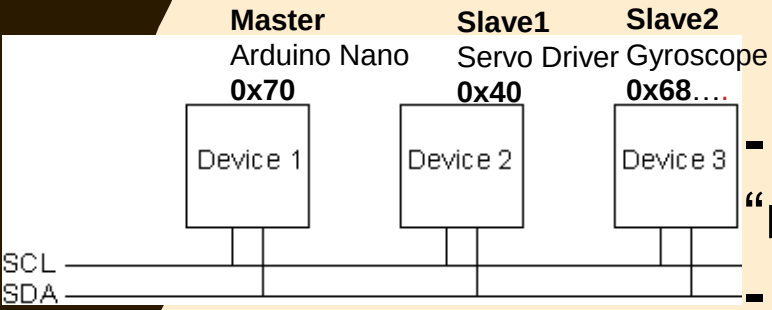
minicat_IRremote_test §

```
}

void translateIR() {//fonction pour associer une action à chaque bouton

  switch(result.value){ //switch permet de lister tous les cas possibles et
    //de leur associer une action

    //on va donc lister tous les codes et retourner leur nom sur la télécommande

    //AV: FOR MINICAT1, "Carmp3" RemoteControl
    //AV: almost all original MiniCat RemoteControl codes are working except for the "Carm

    //AV: original MiniCat SW :
    case 0xFF18E7: Serial.println(" 2 (grey1) or 2 (grey2) or UP (black)"); break;
    //case 0x3D9AE3F7: Serial.println(" HAUT"); break;

    case 0xFF10EF: Serial.println(" 4 (grey1) or 4 (grey2) or LEFT (black) or Mode (grey2)
    //case 0x8C22657B: Serial.println(" GAUCHE");    break;

    case 0xFF38C7: Serial.println(" 5 (grey1) or 5 (grey2) or OK (black)");    break;
    //case 0x488F3CBB: Serial.println(" -OK-");    break;

    case 0xFF5AA5: Serial.println(" 6 (grey1) or 6 (grey2) or RIGHT (black)");   break;
    //case 0x449E79F: Serial.println(" DROITE");   break;

    case 0xFF4AB5: Serial.println(" 8 (grey1) or 8 (grey2) or DOWN (black)"); break;
    //case 0x1BC0157B: Serial.println(" BAS"); break;

    case 0xFFA25D: Serial.println(" CH- (grey1) or ON (grey2) or 1 (black)");    break;
    //case 0xE318261B: Serial.println(" 1");    break;

    case 0xFF629D: Serial.println(" CH (grey1) or Mode (grey2) or 2 (black)");    break;
    //case 0x511DBB: Serial.println(" 2");    break;

    case 0xFFE21D: Serial.println(" CH+ (grey1) or LoudspeakerOFF (grey2) or 3 (black)");
    //case 0xEE886D7F: Serial.println(" 3");    break;
```

# Hardware Modules & Test

## Module 4: I2C Bus connections






**Module 4: I2C Bus connections / devices check**

- comm. between Arduino & Servomotors & Gyro boards

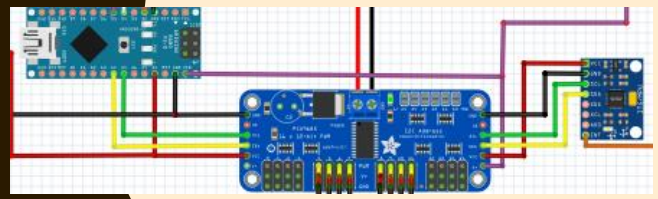
**ToDo**:

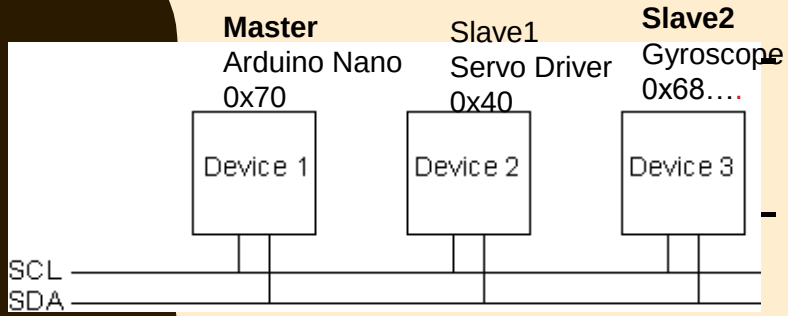
- Unplug the USB cable from your Laptop
- Plugin the Gyro and Servodrivers boards on PCB
- Plugin the USB cable to your Laptop
- Put the 2 batteries in place and turn ON on holder (MPU6050 need enough power from Servodrivers board)
- I2C library (“Wire”) is installed by default (Arduino IDE)

**- open the i2c communication test software:**
“minicat-main/Software/minicat_i2c_test/minicat_i2c_test.ino”
**- 3x I2C devices should appear (serial monitor)**

# Hardware Modules & Test

## Module 4: I2C Bus connections






**ToDo**:

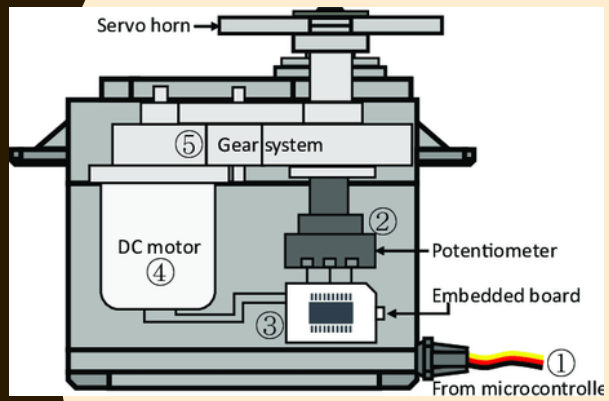
- Open the Arduino **Serial Monitor**
  (Arduino IDE “Tools/Serial Monitor”)

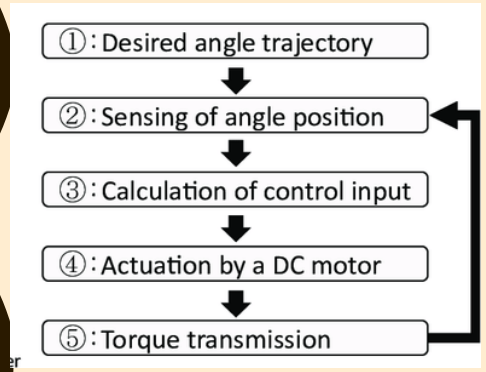
- Set the communication speed to **57600 baud**

- **Verify that the 3 I2C Devices are present:**
  - I2C device found at address 0x40 ! (Servos Driver)
  - I2C device found at address 0x68 ! (Gyro)
  - I2C device found at address 0x70 ! (Arduino Nano)

# Hardware Modules & Test

## Module 5: Servomotors driver board




**Module 5: Servomotors driver board**

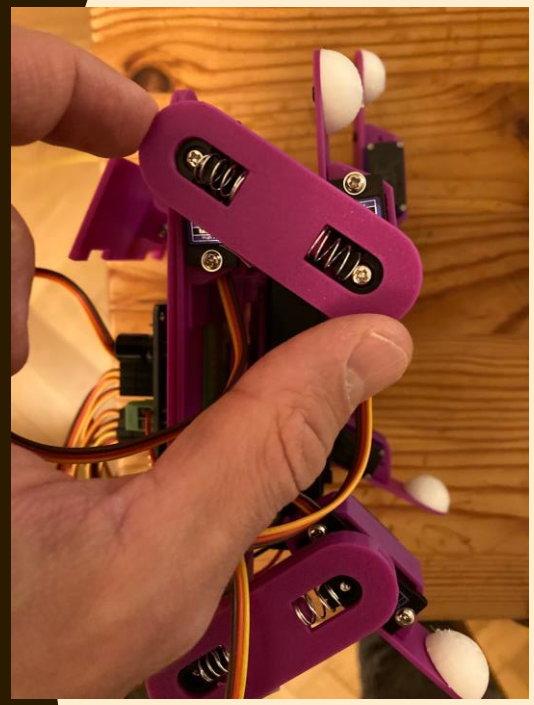
- drives the 8 servos, here we **test w/ 1 servomotor**
- based on Arduino inputs on I2C
- and Servodriver board 8 x PWM control signals outputs
- **we use first 5V supply from Arduino (no batteries)**

**ToDo**:

- Unplug the USB cable from your Laptop
- The 8x Servomotors cables are already plugged

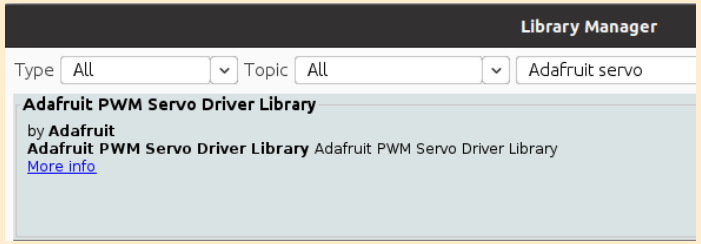
# Hardware Modules & Test

## Module 5: Servomotors driver board



**ToDo**:

- Plugin the USB cable to your Laptop
- Start the Arduino IDE

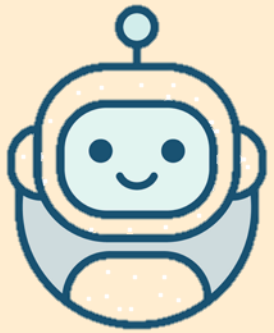



- the Software Library
"Adafruit PWM servo driver library"
should be installed
(Tools/Manage Libraries "Adafruit PWM Servo Driver Library")

**- open the minicat_one_servo_test software :** double click on
"minicat-main/Software/minicat_one_servo_test/minicat_one_servo_test.ino"

# Hardware Modules & Test

## Module 5: Servomotors driver board



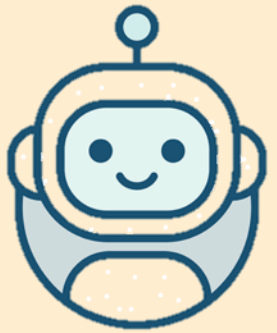
**ToDo (Software)**:

change servo n.
and delay :

```
minicat_one_servo_test §
  //pwm.setPWM(SERVO, 0, SERVOMIN+range/2);//l'impulsion est large de SERVOMIN + range
                                          //=>position milieu du servomoteur
  //delay(2000);

  //AV: Commenting out below lines and changing the rotation angle to avoid too much r

  //Contrôle du servomoteur par angle (voir fonction setToAngle)
  //Serial.println("position 45 degrés ");
  //setToAngle(45);

  //Serial.println("position 20 degrés");
  //setToAngle(20);


  //AV : ToDo : MODIFY here to test the Servo Angle position,

  /*************************************************************/

  //AV: ToDo : MODIFY THE 1st POSITION OF THE SERVO :

  Serial.println("position 10 degrés");
  setToAngle(10);



  //AV: ToDo : MODIFY THE DELAY (in Miliseconds) BETWEEN 2 POSITIONS AS YOU WANT :

  delay(1000);


  //AV: ToDo : MODIFY THE 2d POSITION OF THE SERVO :

  Serial.println("position 30 degrés");
  setToAngle(30);

 /*************************************************************/

}
```

# Hardware Modules & Test

## Module 5: Servomotors driver board



**ToDo (Software)**:

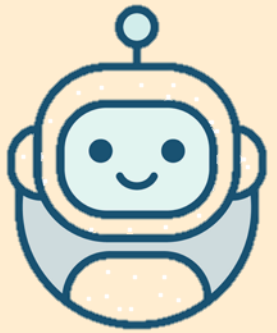
Change the servo number to test all servos one by one :

minicat_one_servo_test §

```
//on inclut les librairies nécéssaires


#include <Wire.h>
#include <Adafruit_PWMServoDriver.h> //librairie spécifique à notre servo driver

Adafruit_PWMServoDriver pwm = Adafruit_PWMServoDriver(); //déclaration du driver pwm

/*############################################################*/

//AV: ToDo : Modify the Servo number

#define SERVO 4 //pin où est branché le servomoteur // AV : ToDo: Modify here to test all the Servos (4 to 11)

/*############################################################*/
```

# Hardware Modules & Test

## Module 5**bis**: Servomotors driver board



**Module 5bis: Servomotors driver board**

**- we use now the 2x4,2V Lithium batteries supply**

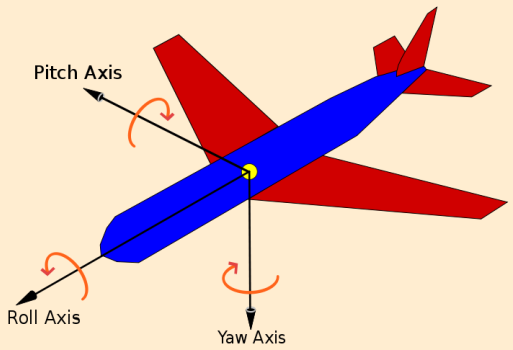
**(your teacher will install them, please ask him)**

**ToDo**:

- Unplug the USB cable from your Laptop
- Ask your teacher to install the 2 x Batteries in the robot
- Put the batteries holder button to “ON” under the robot
- Check if the Servomotor is moving (Front Right Top)

# Hardware Modules & Test

## Module 6: Gyroscope board




**Module 6: Gyroscope board**

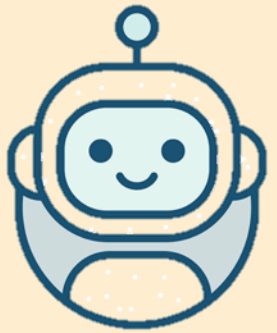
- measuring roll/pitch/yaw
- compared with calibrated “zero”
- compensate the legs height / balance

**ToDo**:

- Unplug the USB cable from your Laptop
- Plug the Gyro module in the PCB
- Plugin the USB cable to your Laptop
- Start the Arduino IDE’
- Get the Arduino Libraries “I2Cdev and MPU6050”
- Start the 1x Gyro test software “minicat_i2c_test.ino”

# Hardware Modules & Test

## Module 6: Gyroscope board



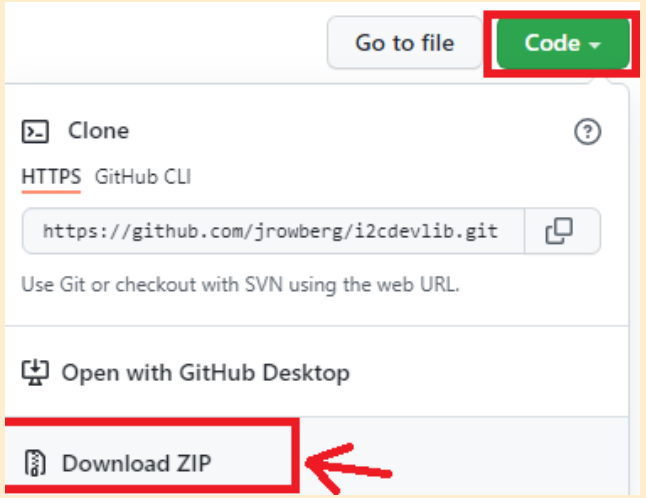
The Gyroscope module need the Libraries “**I2Cdev**” and “**MPU6050**” for I2C communication to Gyroscope MPU6050 sensor :

– Open : https://github.com/jrowberg/i2cdevlib

– Click on “Code” and then “**Download ZIP**”

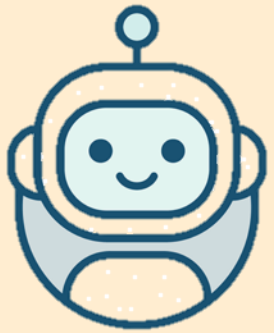
– the Downloaded .zip is normally stored into your “C:\Users*UserName*\Downloads” folder

– **Unzip** the “i2cdevlib-master.zip” in your “C:\Users*UserName*\Downloads” folder to get a “i2cdevlib-master” folder

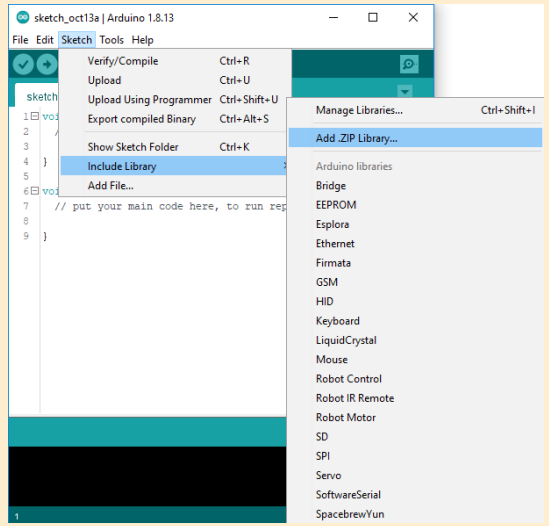


# Hardware Modules & Test

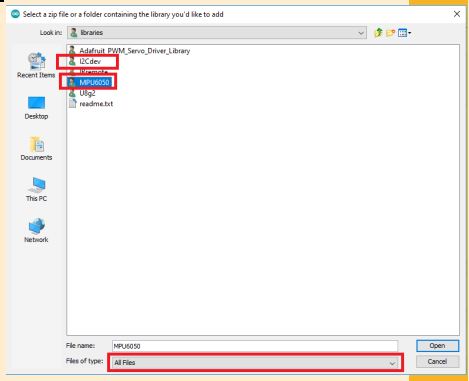
## Module 6: Gyroscope board



1- Now to add the 2 libs we need,
Click on “**Sketch/Include Library/Add .ZIP Library**”

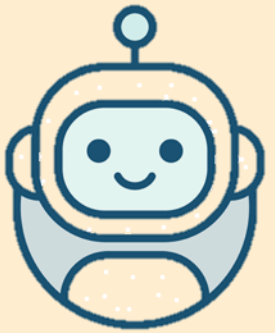



2- Change the “Files of type” to “**All Files**”
(as we already unzipped) :
3- Navigate to
“C:\Users*UserName*\Documents\Arduino\libraries\i2cdevlib-master\i2cdevlib-master**Arduino**\

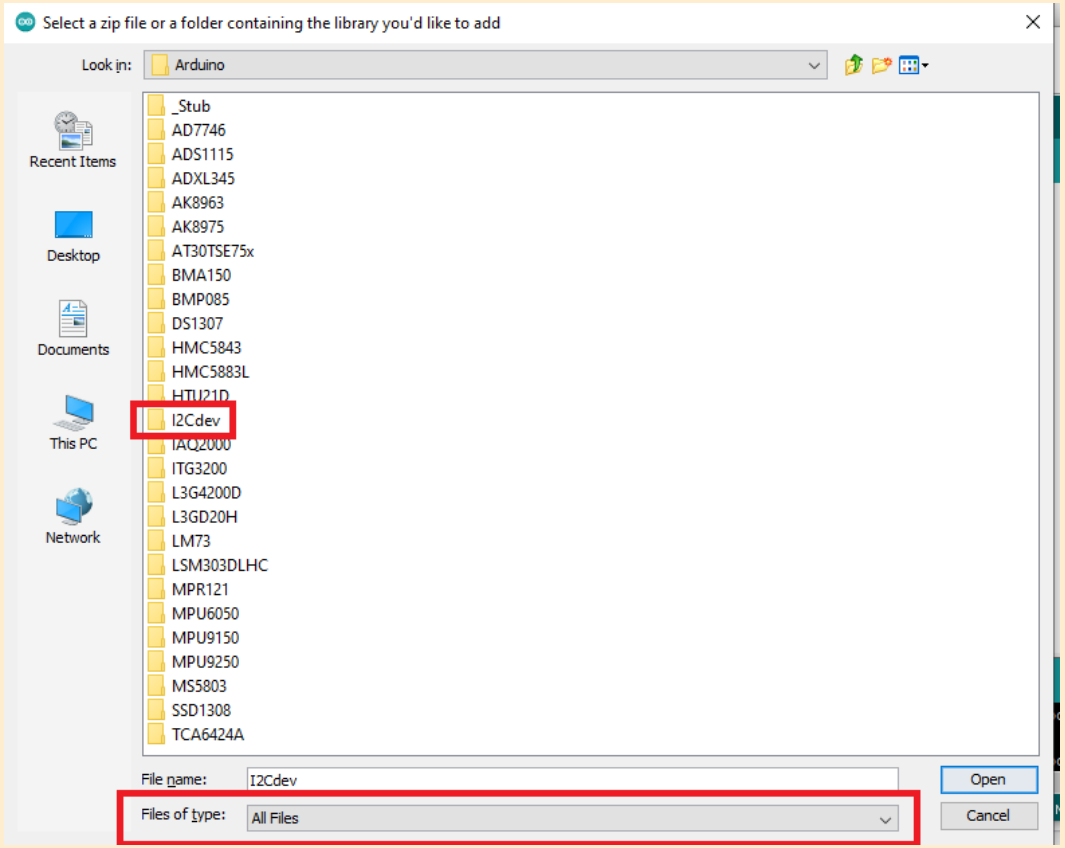


# Hardware Modules & Test

## Module 6: Gyroscope board

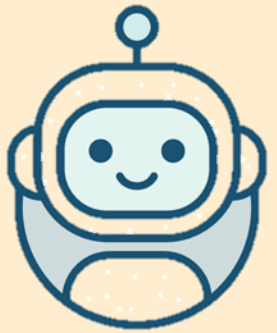


4- Then Single Click on the “**I2Cdev**” Folder and then “**Open**” :

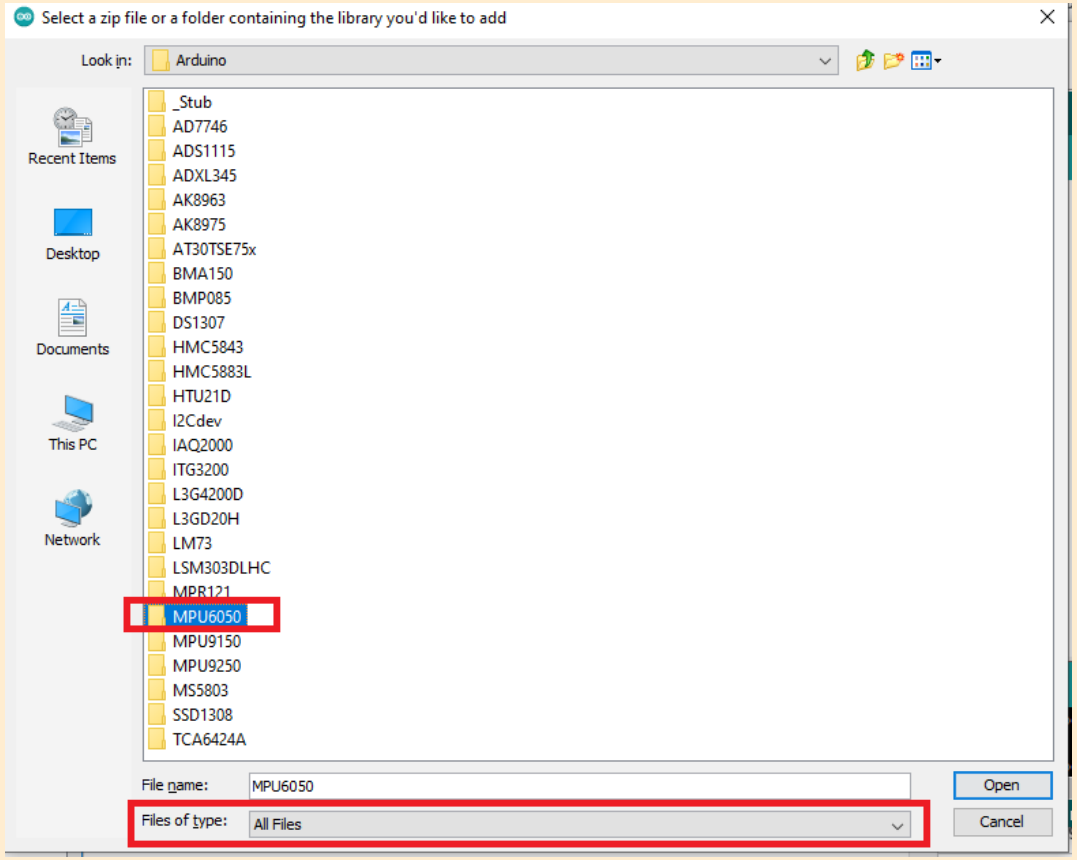


# Hardware Modules & Test

## Module 6: Gyroscope board

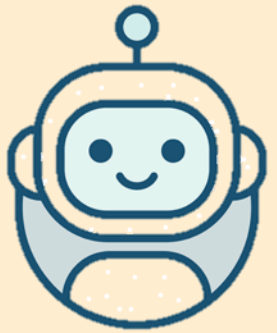


5- **Repeat** the steps above for adding the "**MPU6050**" lib :



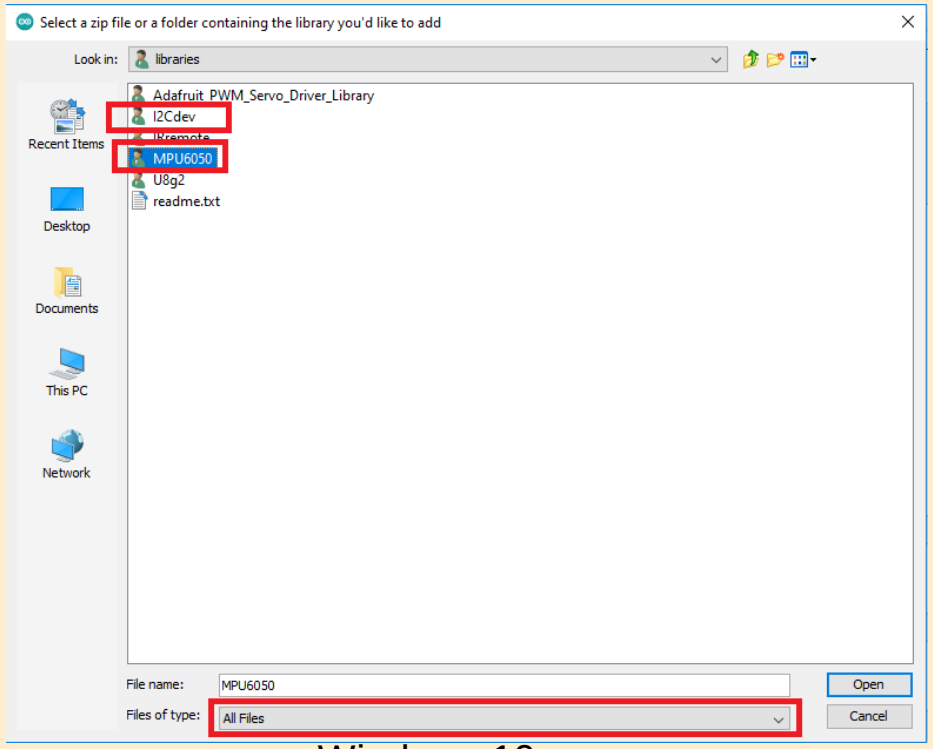
# Hardware Modules & Test

## Module 6: Gyroscope board

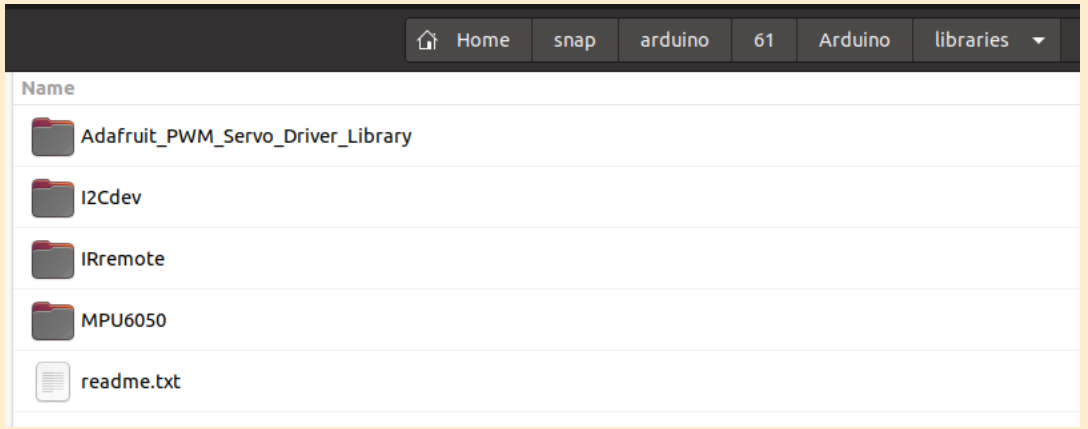


**6- RESULT:**

**The 2 Libs** should now appear in your “C:\Users*UserName*\Documents**Arduino\libraries** folder:




Windows 10




Ubuntu 20.04

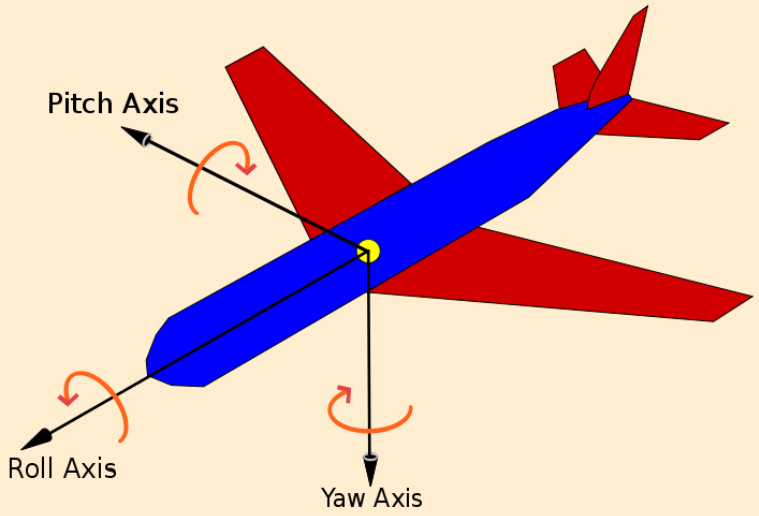
# Hardware Modules & Test

## Module 6: Gyroscope board

**ToDo:**

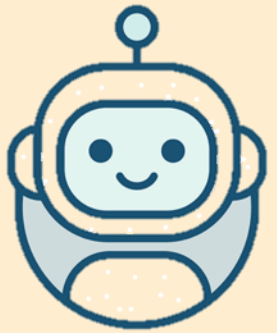
- Open the Serial Monitor

- Check the “**ypr**” = **y**aw **p**itch **r**oll values when moving MiniCat :
  (click on “Autoscroll” to stop)




# Hardware Modules & Test

## Module 7a: All modules + calib



**Module 7a: All Modules + calibration**

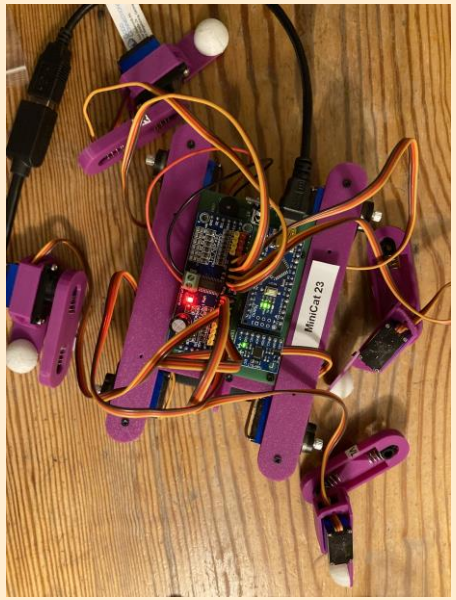
- **servos check + gyro calibration**
- **not in focus of this workshop (time consuming)**
- servo need to be placed at their zero (middle) angle
- gyro need to be calibrated to know its zero angles (rpy)

**Todo:**

- Make sure all modules plugged on the PCB
- **Put the battery holder button on “ON” first**
- **Plugin the USB cable to your Laptop**

# Hardware Modules & Test

## Module 7a: All modules + calib




**Todo (Software): calib done, not in focus of workshop**

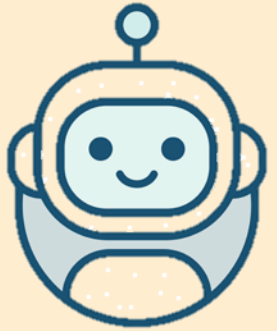
**- disconnect all legs of MiniCat, no servo blocked**

**- make sure MiniCat is on a flat surface**

- start the "**minicat_servos_and_gyro_calibration.ino**"
  - Open the **Serial Monitor**
  - "**Upload**" the Software
  - The Gyroscope will measure the MiniCat chassis roll/pitch/yaw angles offsets compared to the MPU6050 chip default zero angles, the **offsets will be shown ´' in the serial monitor**

# Hardware Modules & Test

## Module 7a: All modules + calib



**Background :**

**servos calib:**
- we need to put all servos at their central zero position before mounting the legs of MiniCat

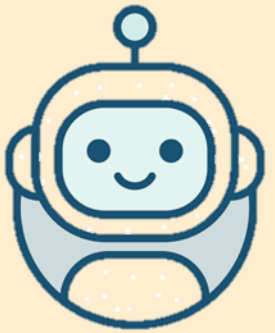
**gyroscope (MPU6050 chip) calib:**
- we need to measure the offset of the gyro yaw pitch roll angles compared to the default zero angles in the Gyro board firmware (MiniCat should be put on a flat surface)

Remark :

**the gyro angles offset values will be stored in EEPROM**
(non volatile memory of Arduino Nano)
so that this Calibration is needed only once on a particular Arduino

# Hardware Modules & Test

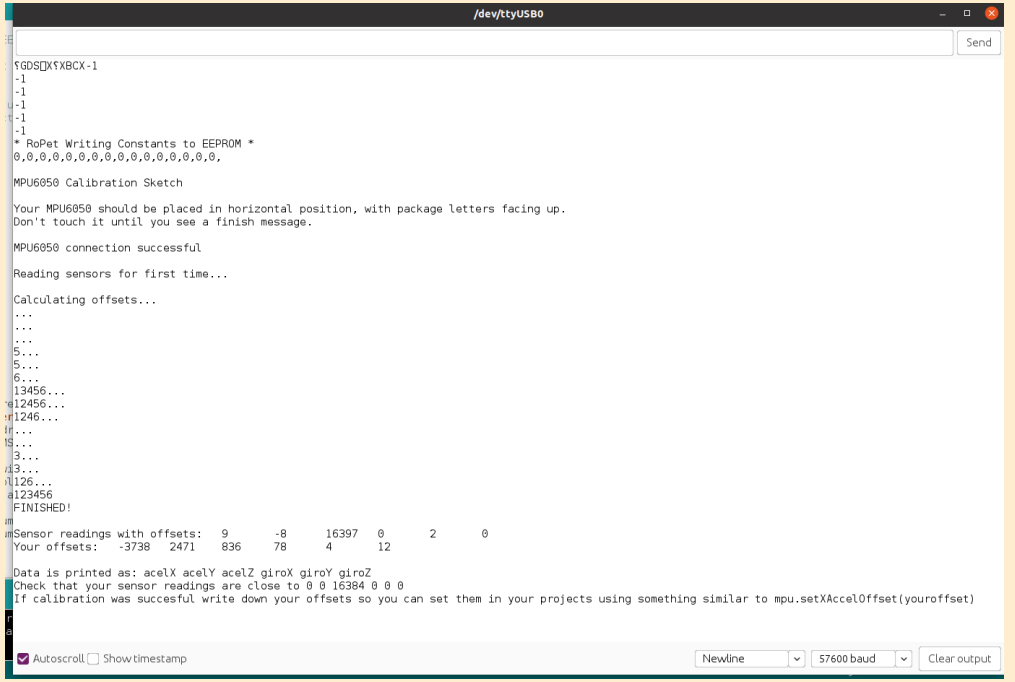
## Module 7a: All modules + calib



**Todo (Software):**

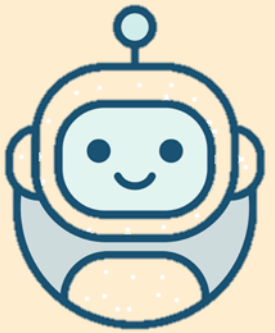
**- the gyro and servos calibration process will start**

- if everything is fine, you get this output in the serial monitor



# Hardware Modules & Test

## Module 7a: All modules + calib



**Todo (Software):**

- keep the serial monitor open and
**type "c"** in the command line then "**Enter**"
**This will place the servos at their central "zero" position**

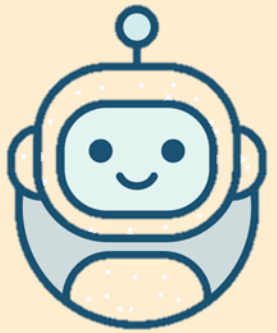
- The Servo angles will be shown w/ zeros in the serial monitor (only 8 to 15 are our 8 servos)

| **8,** | **9,** | **10,** | **11,** | **12,** | **13,** | **14,** | **15** |
|---|---|---|---|---|---|---|---|
| 0, | 0, | 0, | 0, | 0, | 0, | 0, | 0, |

**- Keep the battery holder button on "ON"**
**- Do not remove the USB cable from your Laptop yet !**
**- you will only insert the tighs & feet parts in the servos axis**
**see how on next slide, do not turn the servo axis manually !**
**(as you just set the servos to their zero angle pos.)**

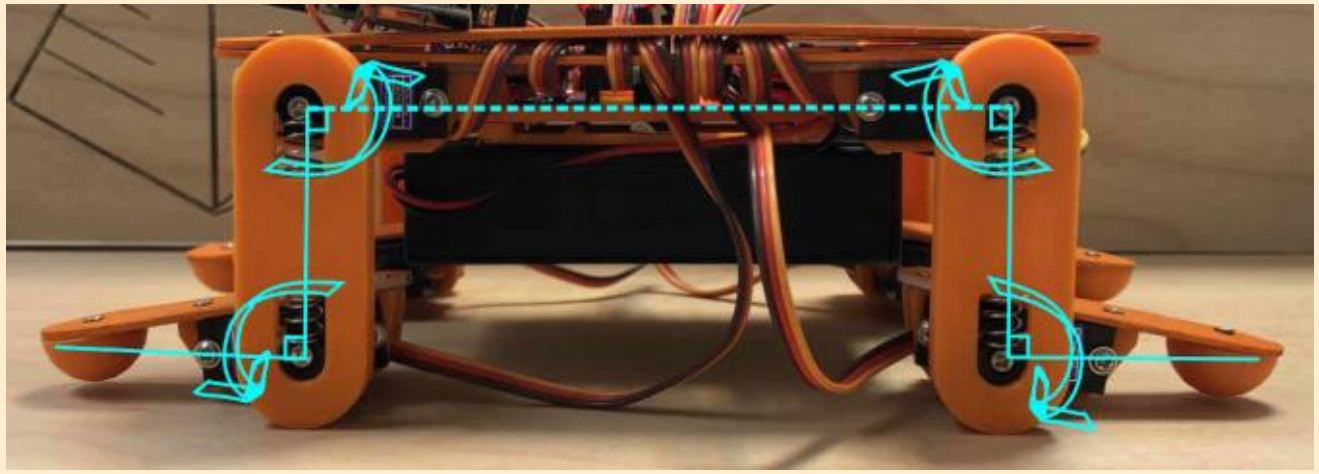
# Hardware Modules & Test

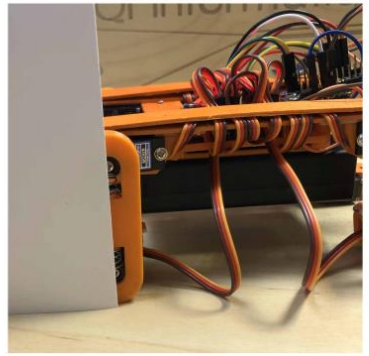
## Module 7a: All modules + calib

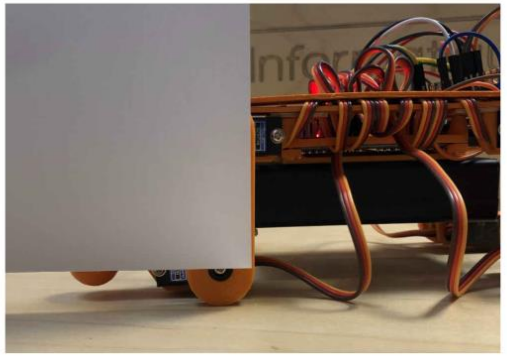


**Todo (Software):**

- Now that you have set the servos to their zero angle you can mount them as below
(Hint: **do not move the servo axis anymore!**
If so, start again
“minicat_servos_and_gyro_calibration.ino”) :

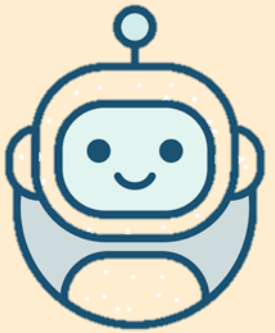






# Hardware Modules & Test

## Module 7a: All modules + calib



**Optional / Todo (Software): Servos angle Fine tuning :**

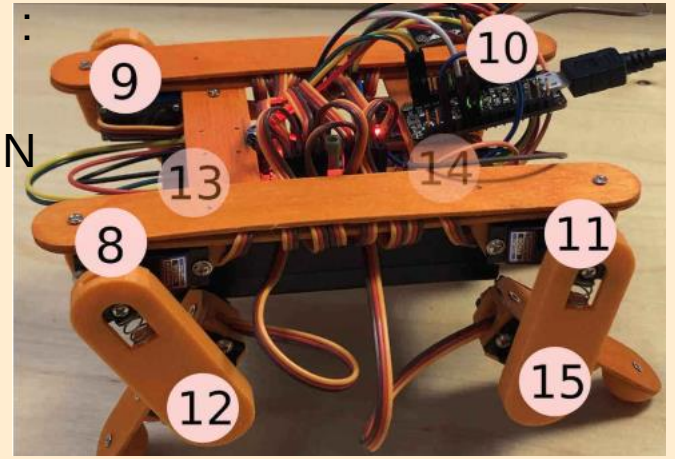
- If you can not achieve 100% the above, you can still **fine tune the servo angles by software by running the below in the Serial Monitor:**

***c "servo link index" "correction angle***

For example, if you want to change the angle of link 12 of +5 deg you can run : ***c12 5***

Servos indexes reminder :

FRONT



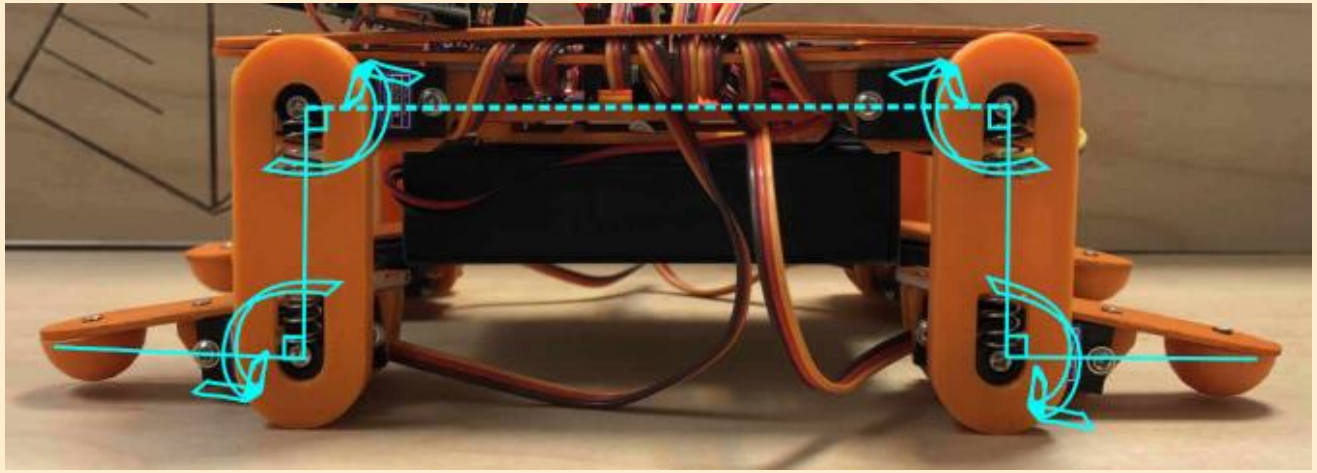

**Remark :** each tooth of the servo axis is 360deg/20teeth so 18deg so the fine tuning makes sense for +/- 9deg, if more needed just remove the servo arm from the servo axis and place it on a next tooth!

# Hardware Modules & Test

## Module 7a: All modules + calib

**Todo (Software):**

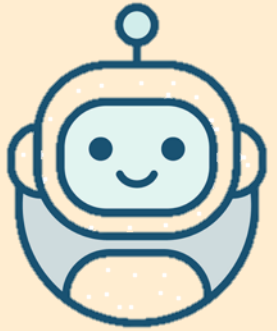
- put the servo screws in the servo axis to fix the positions :



- Once you have achieved the above, **type “s”** in the serial monitor (this will save your servos angles calibration in Arduino EEPROM (non volatile))

# Hardware Modules & Test

## Module 7a: All modules + calib



**Todo (Software):**

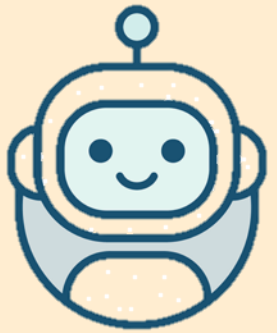
- to test your servos calibration, try different positions :

- type “**d**” in monitor to go in default position (“stop”), expected :

- type “**pbalance**” to go in “stand” position, expected :

# Hardware Modules & Test

## Module 7b: All modules on PCB



**Module 7b: All Modules on PCB and Play !**

**ToDo**:

- Unplug the USB cable from your Laptop
- Make sure all modules plugged on the PCB
- **Put the battery holder button on “ON” first**
- **Plugin the USB cable to your Laptop**

- **open the minicat_basic software :** double click on “minicat-main/Software/minicat_basic/minicat_basic.ino

**- Use the remote control to play !**