getCPos

Get the calibrated position of the Herkulex motor

Contents

Syntax

```
CPos = getCPos(sObject,pID)
```

Description

CPos = getCPos(sObject,pID) gets the calibrated position of the Herkulex motor.

- Formula: Calibrated Position = Absolute Position - Calibrated Difference
- RAM register for calibrated position: 0x3A(58)

Input Arguments

- sObject - serial port object
- pID - integer

Output Arguments

- CPos - integer

Function Codes

```
function CPos = getCPos(sObject,pID)

    packet = pkGen(pID,04,'3A02'); % Calibrated position addr: 0x3A(58), read 2 bytes
data

    inHkx(sObject,packet);

    msg = outHkx(sObject);
```

```
    % Byte in reverse order by Little Endian Order

    % Position details are in 10 bits (refer to Herkulex Manual pg25)

    tempPos = hexToBinaryVector(strcat(msg(21:22),msg(19:20)),16);

    CPos = bi2de(tempPos(7:16),'left-msb');

end
```

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