# Anklebot Getting Started Guide:

1. To start the actuators press start button, after you have turned on the computer button.
2. press ready button
3. Press the “roborec” with the foot icon.
4. You press calibrate and then you press move home, the robot should go to it’s homing position.
5. You can press record from robot, and then you can move the actuators. Then you press playback to robot and it’ll run the same movement you did in a cycle.
6. You should keep this program running

It runs on Ubuntu, linux operating system

Username is: emfichna

Password is : inmotion2

## Anscales

Anscales, for making stochastic motions on the robot. You can set the stiffness of the actuator, damping and offset.

You can press vibrate on and vibrate off to test the vibration for testing without logging.

You can press log file to log the motion too. There is a back ground file that you can change to add different logging times.

Instructions on the desktop tells you how to convert files and you can change random IE, DP motions.

You can press calibrate to set the current position as the homing position.

## You can do quasi static motion with

There is a static protocol on the desktop that you can run after closing everything. You can double click and select run in terminal, all of the files to change are in crob, static, imt\_logs.

## How to convert data to use in matlab

Go to home folder to find the logged files. They are named based on the date.

Go to terminal, type what is written in the instructions.

It writes files into home/mirror/ …