Callibration RobotArm

How to calibrate the robot with Ipos drives

1. Clear all
2. p = raspi('10.55.0.1','pi','sperte123')
3. Open Robot\_calibration\_Ipos.slx
4. Click initialize model en give the number of the robot which to calibrate.
5. Click Monitor & Tune in Simulink
6. After Homming Run m file ‘calibration\_camera\_robot’
7. Follow the steps in the file and if ready click ok.
8. calibration\_matrix.mat file is provided with the new value’s

**Check the Robot.**

1. Clear all
2. p = raspi('10.55.0.1','pi','sperte123')
3. Open Robot\_calibration\_check\_Ipos.slx
4. Click initialize model en give the number of the robot which to calibrate.
5. Click Monitor & Tune in Simulink
6. Robot moves to the calibrated position