

BAXTER_CALIBRATION

http://sdk.rethinkrobotics.com/wiki/Arm_Calibration

We have two arm calibration routines that we recommend you run regularly (roughly once a month) to keep your robot's arms responding reliably.

These are `calibrate_arm.py` and `tare.py`, and both are located in the `baxter_tools` repo.

Before running either, you must remove any grippers from the arms, level the robot using the feet on its base, and make sure that there are no obstructions within reach of its arms, as they will move through the most of their accessible range throughout the procedure, and collisions will result in a failed calibration.

Note: The recommended order of operations in calibration is:

1. Run the `calibrate_arm` routine on both arms
2. Reboot
3. Run the `tare.py` routine on both arms
4. Reboot

On the final boot, the robot's arms will be fully calibrated.

Note: The Demo Mode UI will run through this entire routine for you by selecting Tare/Calibrate from the Tools menu.

Baxter Research Robot Calibration (Part 1) 2:50

<https://www.youtube.com/watch?v=Vd04gb6SB-w>

Baxter Research Robot Calibration (Part 2) 5:12

<https://www.youtube.com/watch?v=sO4urgKwxEA>