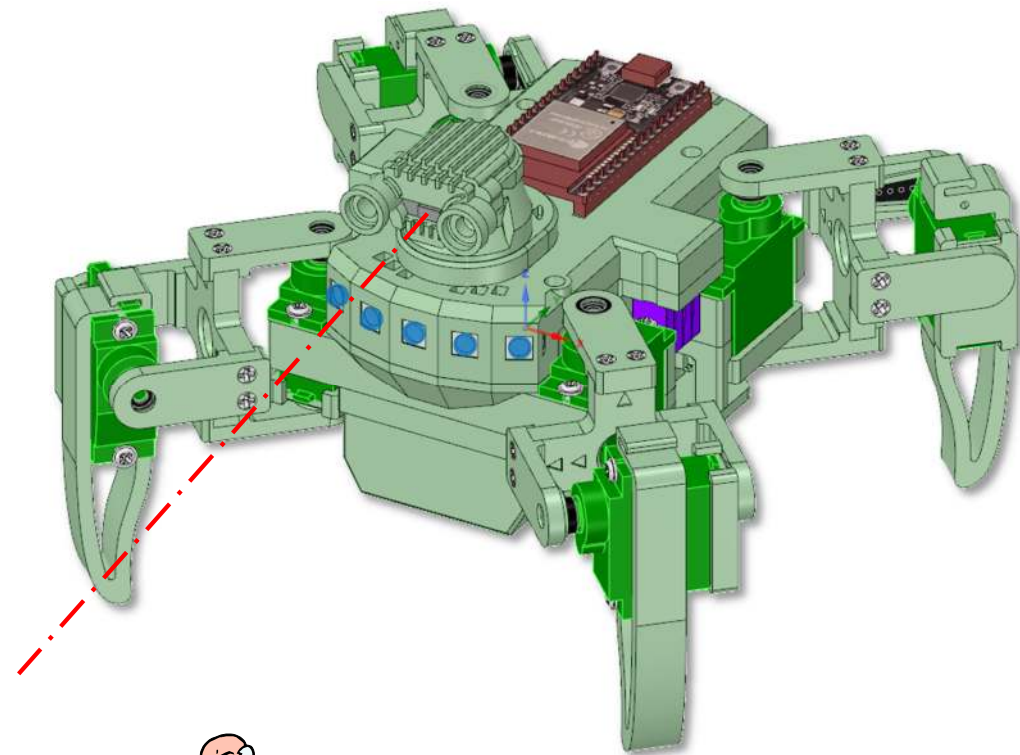
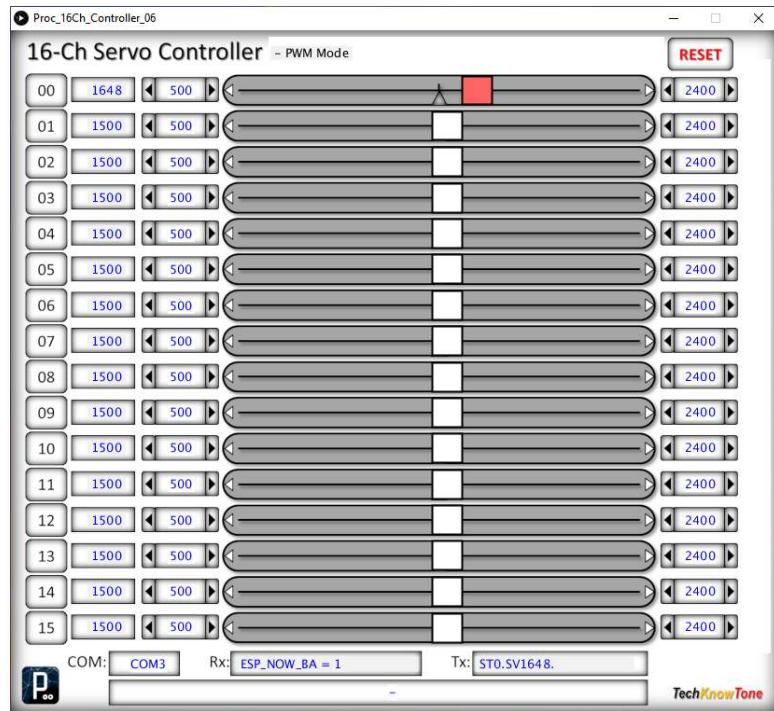


Autonomous Quadruped Robot ESP32 Calibration



Overview

Servo calibration is a two step process; Course settings are used in the assembly process, when attaching servo lever arms, and fine tuning is covered in this document. A Servo Consistency Tester is used for course settings, and fine tuning uses a custom Windows app, written specifically for this project by me.

Course: The servo tester is used to set the centre position, when fitting the cross shaped lever in the robots head. This is to ensure that the servo will have sufficient movement range in both directions when mounted in your robot.

The PWM centre position of a servo is 1,500 μ s.

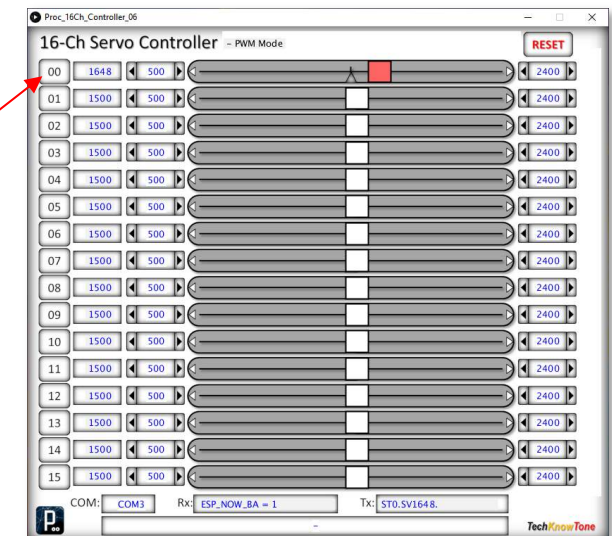
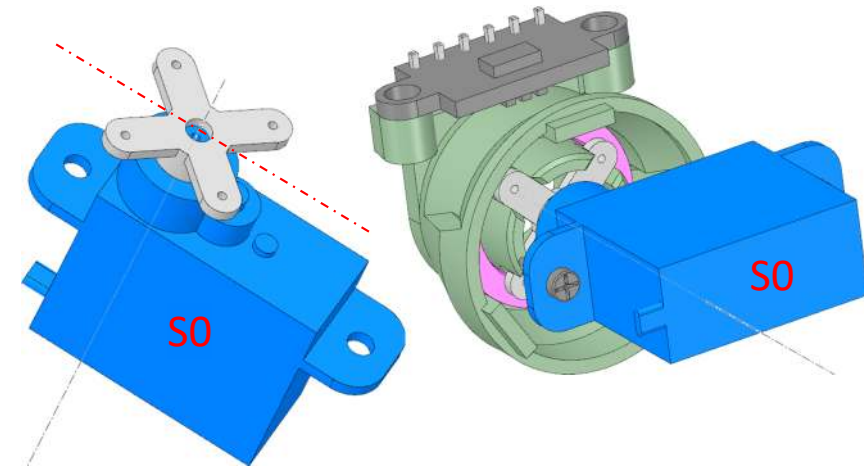
It is simply a matter of powering up the servo tester, plugging in the servo and setting the testers output to 1500. Then fitting the servos cross shaped lever onto the servos splined drive shaft in the correct position shown here. The splined drive shaft teeth positions may prevent you from getting it exactly right, but the nearest position possible will do. This cross shaped lever mates with recesses in the neck, to drive the head in a pan motion, for the laser range finder.

Fine: Once the head servo is installed in the robot, and the wiring of the chassis is complete, we can then use the 16-channel app to adjust the servo angles, to determine limits to be set in code, and to set the leg servos.

The channels on this controller app correspond to:

- 00 - head servo angle in microseconds
- 01 – 08 - leg servos angles in microseconds (see numbered diagrams)

The robot should be placed on its stand, code set to TESTmode `true`, powered up and connected to your PC using a USB lead. You need to turn ON a channel, by clicking on the channel button, before it will receive PWM signals and respond to the slider values. Turning the channel OFF will remove the PWM signal,



Head servo limits

Setting the head servo will get you familiar with using the Windows app. The numbers shown are from my robot. Yours will be different.



Code references are shown here in blue.

Head_0

1552

These PWM limit values enable the robot code to calculate angles, and prevent the head drive mechanism colliding with mechanical stops.

Notice the small notches around the head scalp model, and the reference mark on the shroud to aid calibration.

Head_60N

890

0°

-60°

0°

Head_60P

2203

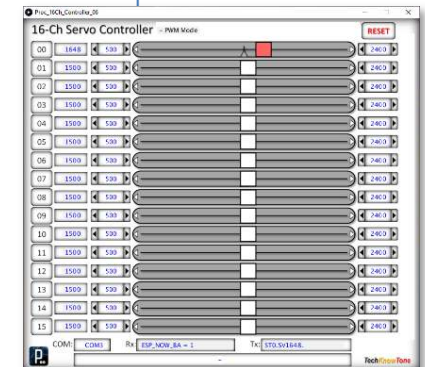
0°

+60°

50



Use the features of the model to align the head with the shroud when taking readings.



Leg servo limits

Just like the head servo, we use a servo tester when attaching the leavers to servos, before attaching the servos to your robot initially, to set the angles of the attached levers in their approximate positions. Leg servos can collide with each other and with the robot body, so fine settings stored in code prevent this.

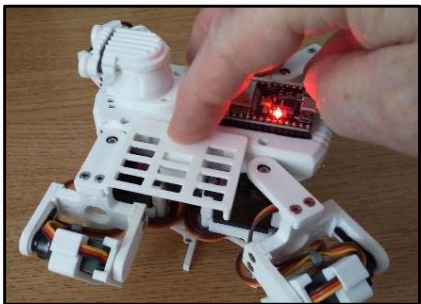
Course: Leg hip servo lever arms are set with the servo mounted in the robots body, at approximately 45° which corresponds to a PWM value of $1500\mu\text{s}$. The centre of the hip servos mounting screw gives you an indication of this angle.

The leg pivot servos have their arms fitted at a point where they touch the lower part of the cross mounting, with a servo value of either 800 or $2200\mu\text{s}$, whichever is the appropriate value for that servo.

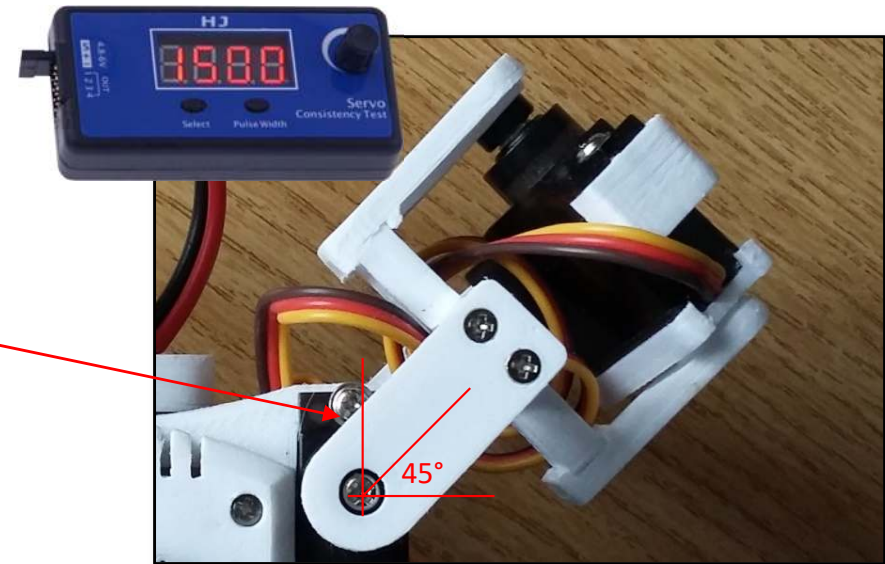
Fine: Once you have assembled and wired up your robot you can use the 16-channel application I have provided. You can select each servo in turn and move their sliders to determine values needed to achieve the calibration angles shown in the subsequent pages of this guide. Take care to avoid collisions, as this causes your servo motors to over-heat, and could permanently damage them.

Note that as no two servos are alike, the values I have given in this guide, and included in the sample code, will be similar but different from the ones you derive from your robot. That's the nature of servos!

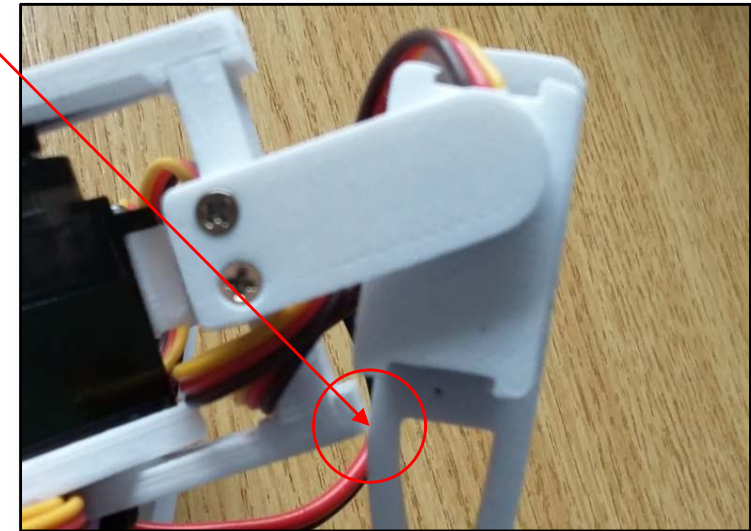
Performing these tasks with patience and accuracy will lead to good robot performance and longer battery life.



There is an angle gauge included in the model files which will help you determine the hip 135 angles. Simply hold it against the robot, whilst adjusting the appropriate slider in the app.

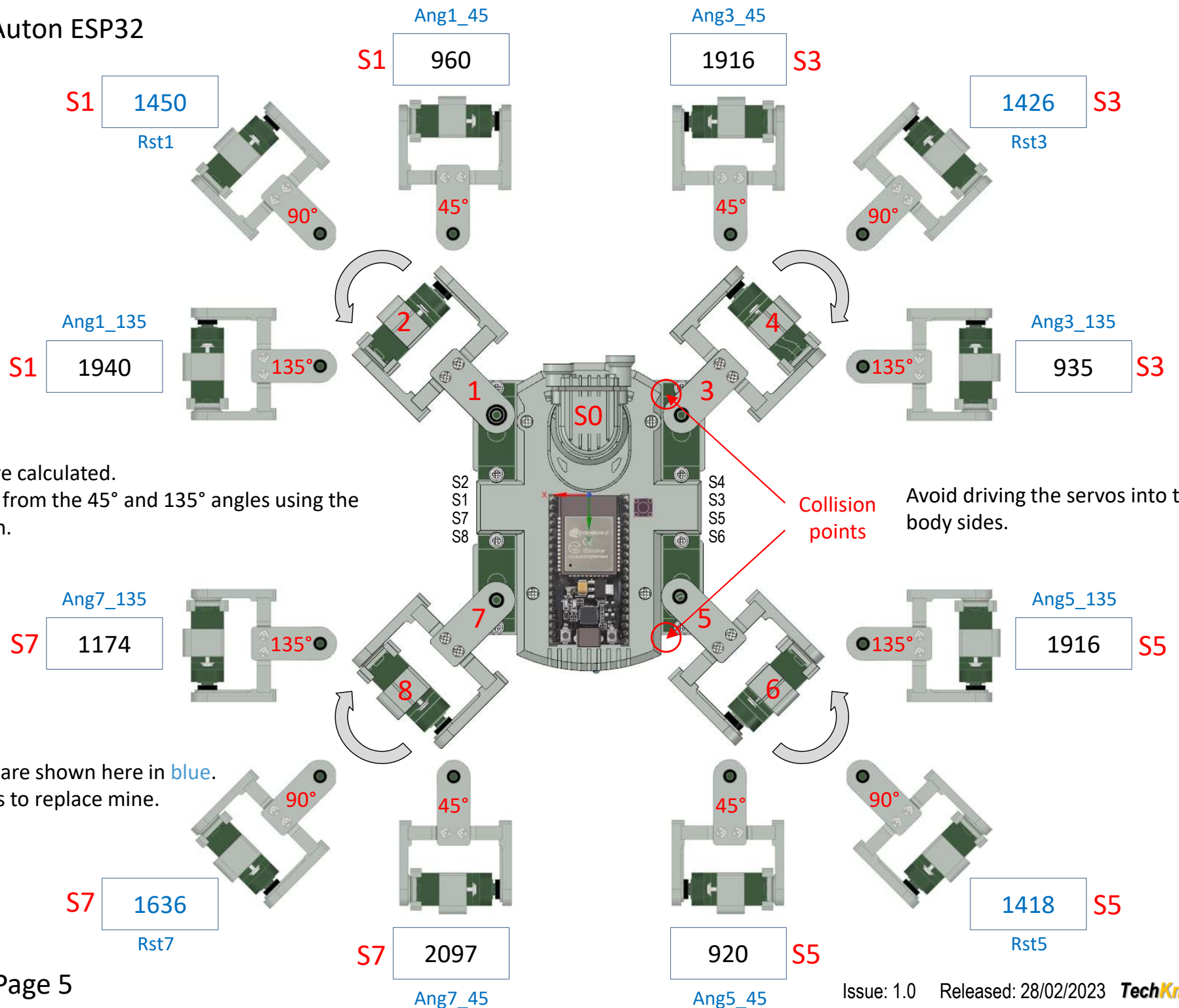


Fit the hip joints at $1500\mu\text{s} == 45^\circ$



Fit legs just touching their collision points.

Quadruped Auton ESP32 Hips Cal.

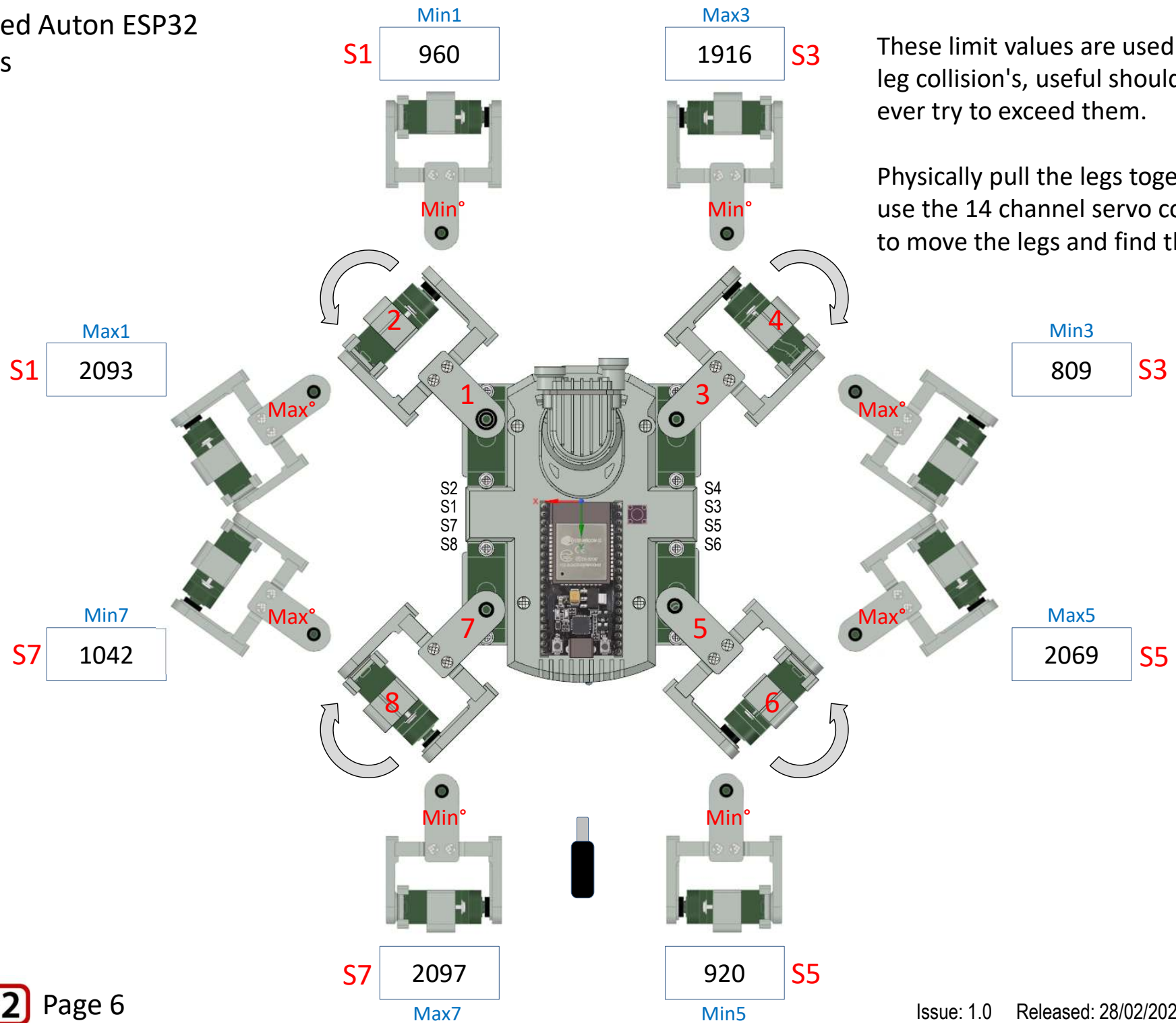


The 90° values are calculated.
They are derived from the 45° and 135° angles using the mapping function.

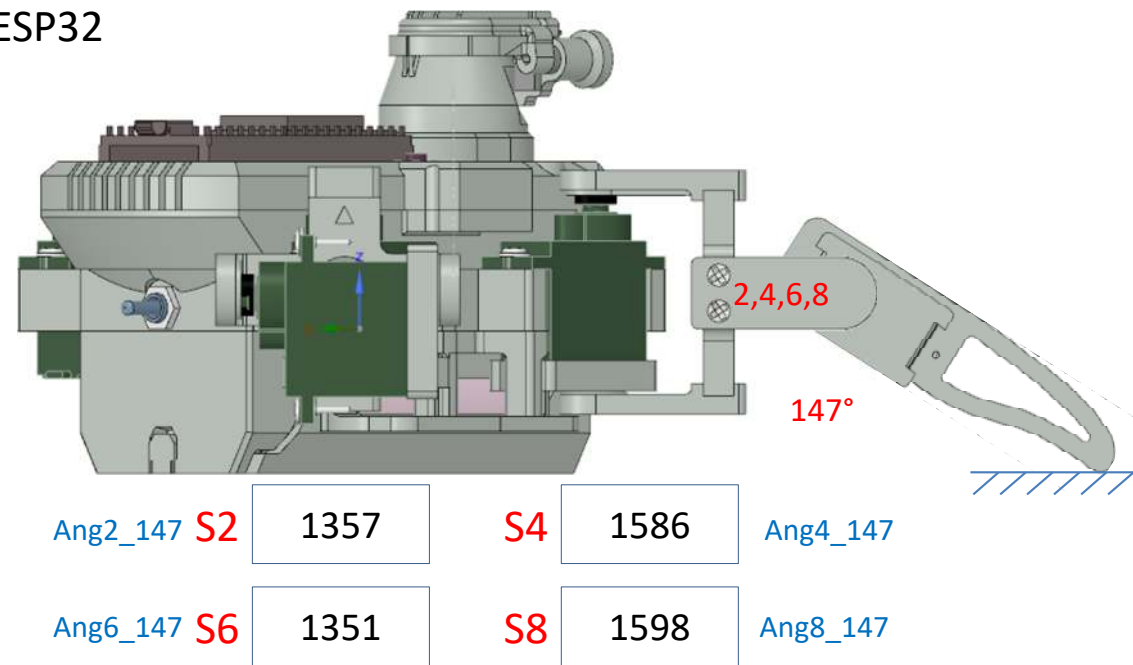
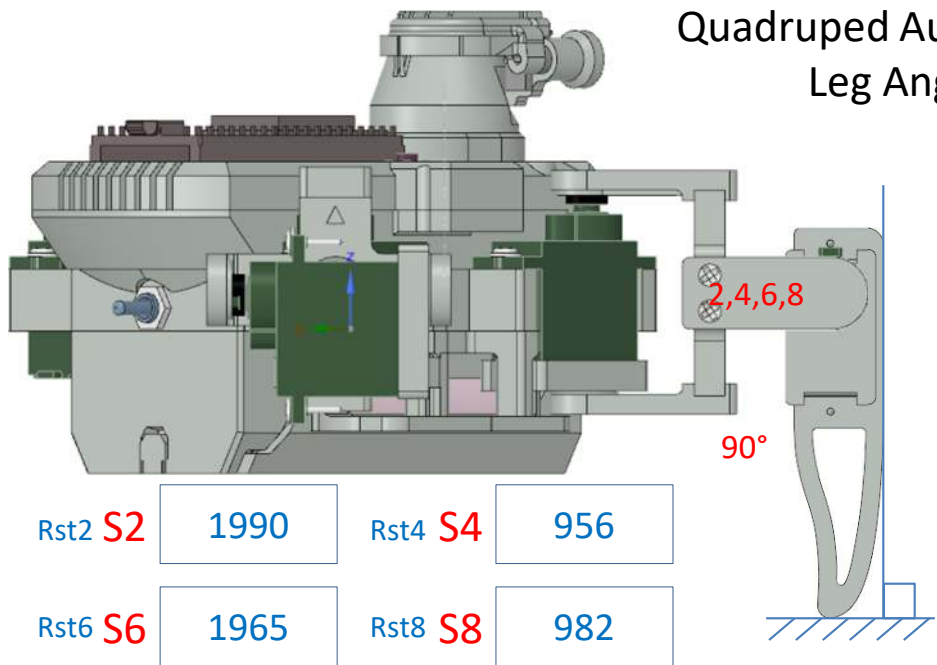


Code references are shown here in blue.
Enter your values to replace mine.

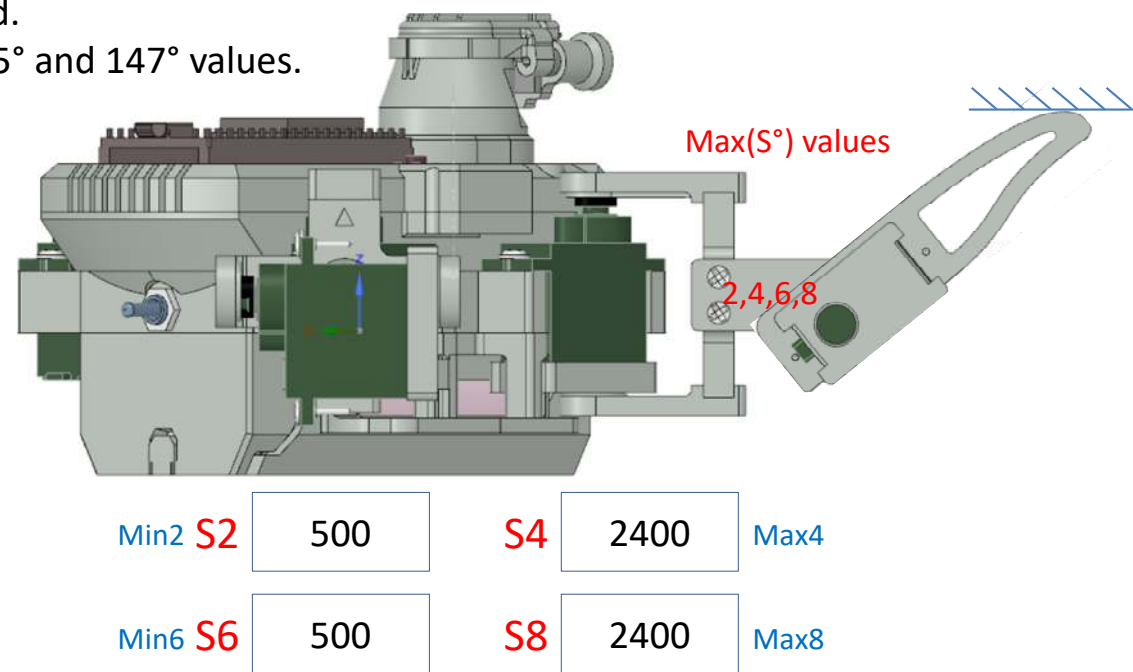
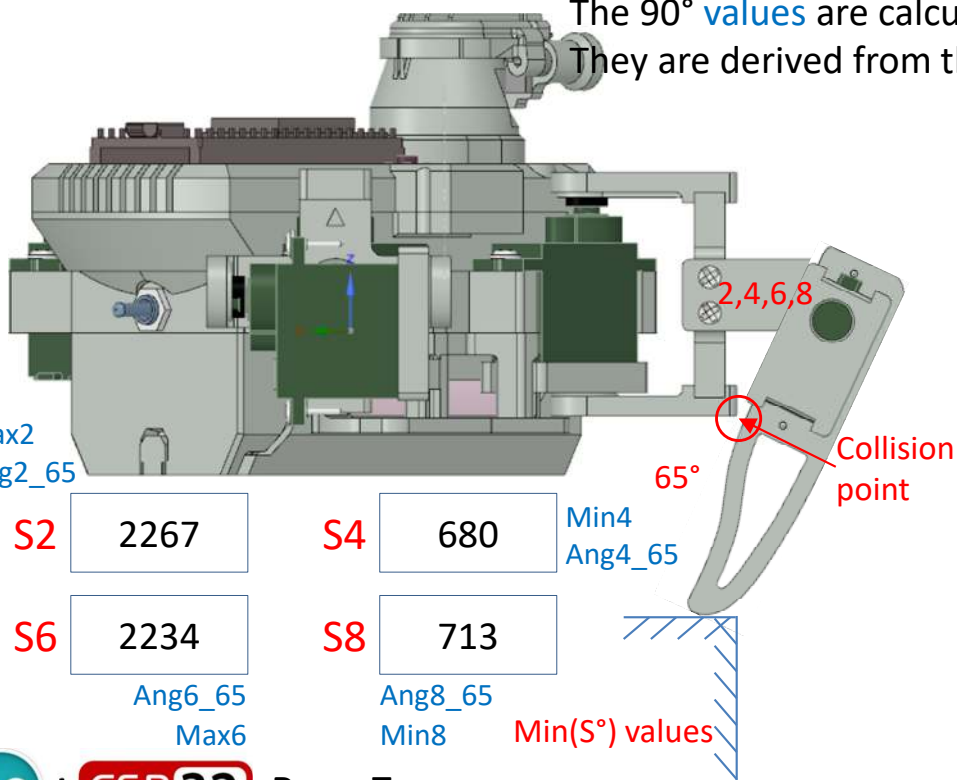
Quadruped Auton ESP32 Hip Limits



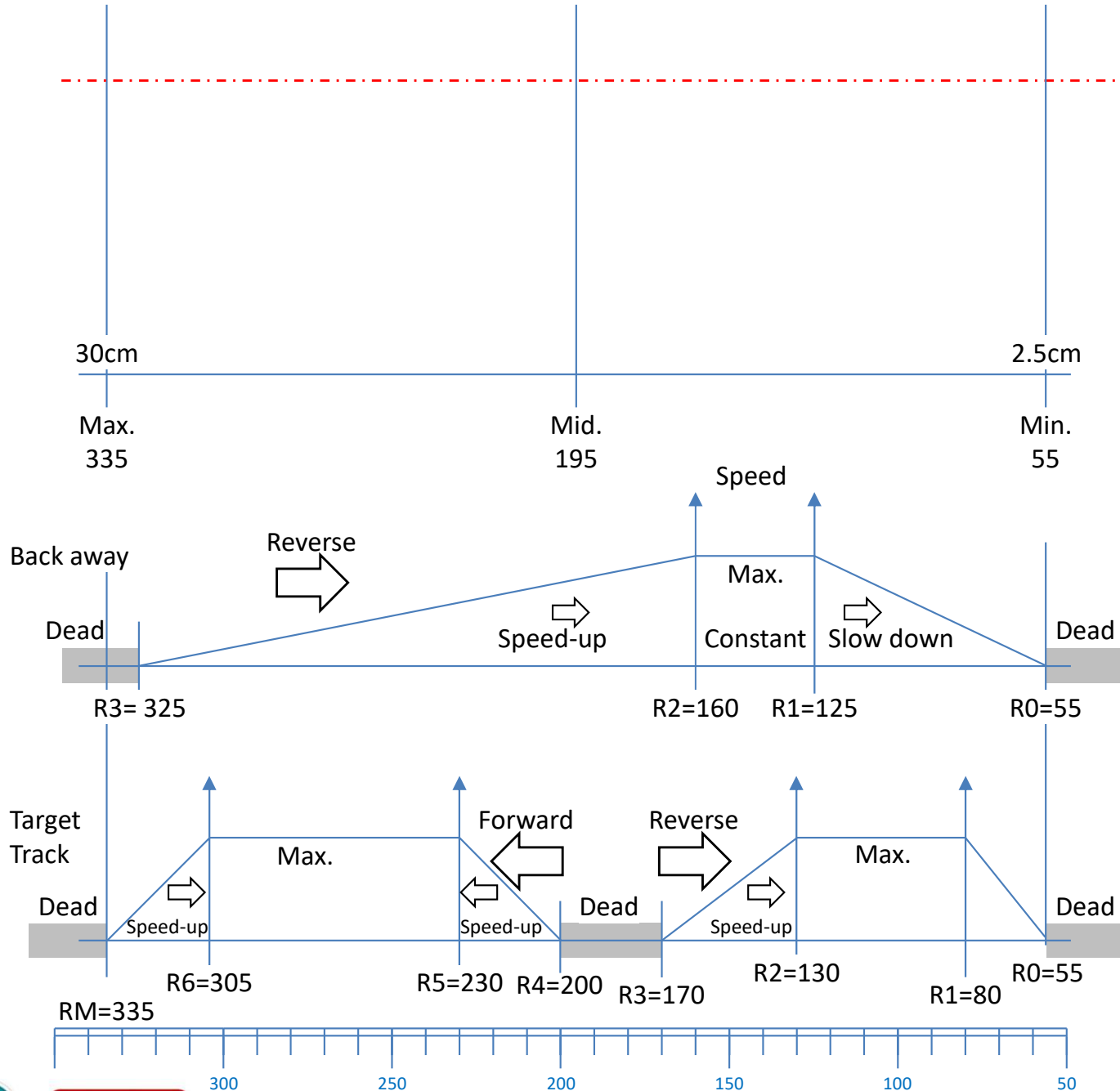
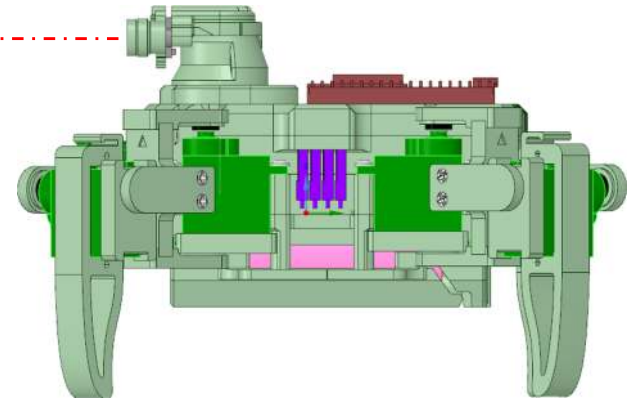
Quadruped Auton ESP32 Leg Angles



The 90° values are calculated.
They are derived from the 65° and 147° values.



VL53L0X LTOF Sensor Ranges

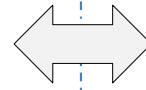


These are the values I determined from my LTOF sensor, and the speed maps I developed for the back away and target tracking functions.

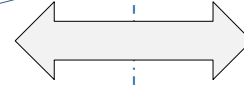
You should be able to find these values in the code and if necessary substitute the values you have determined from your sensor. Use the serial monitor in the IDE along with Serial.print() functions to display your values.

Quadruped Autonomous Scanning

Out of range – full sweep scan



Limited sweep - increasing



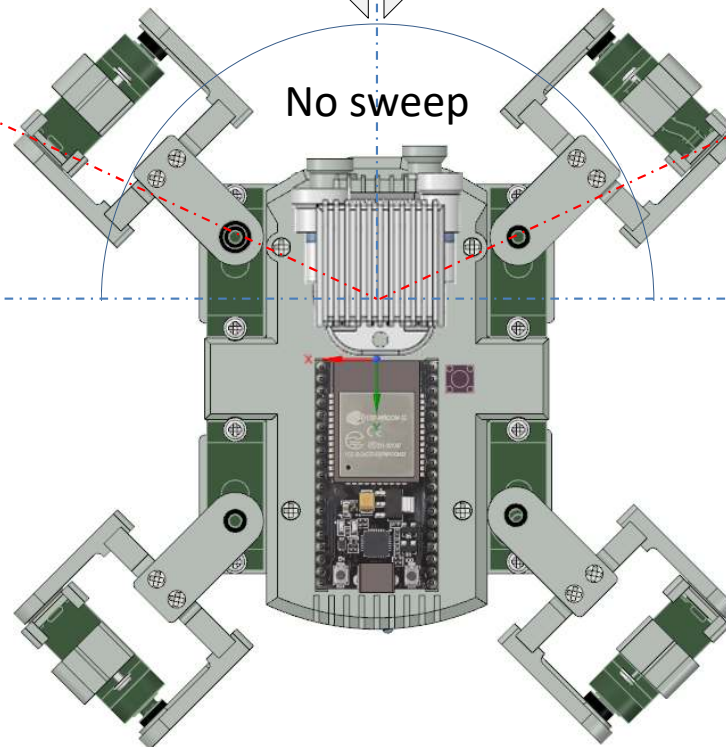
Limited sweep - decreasing



No sweep

Head_60N

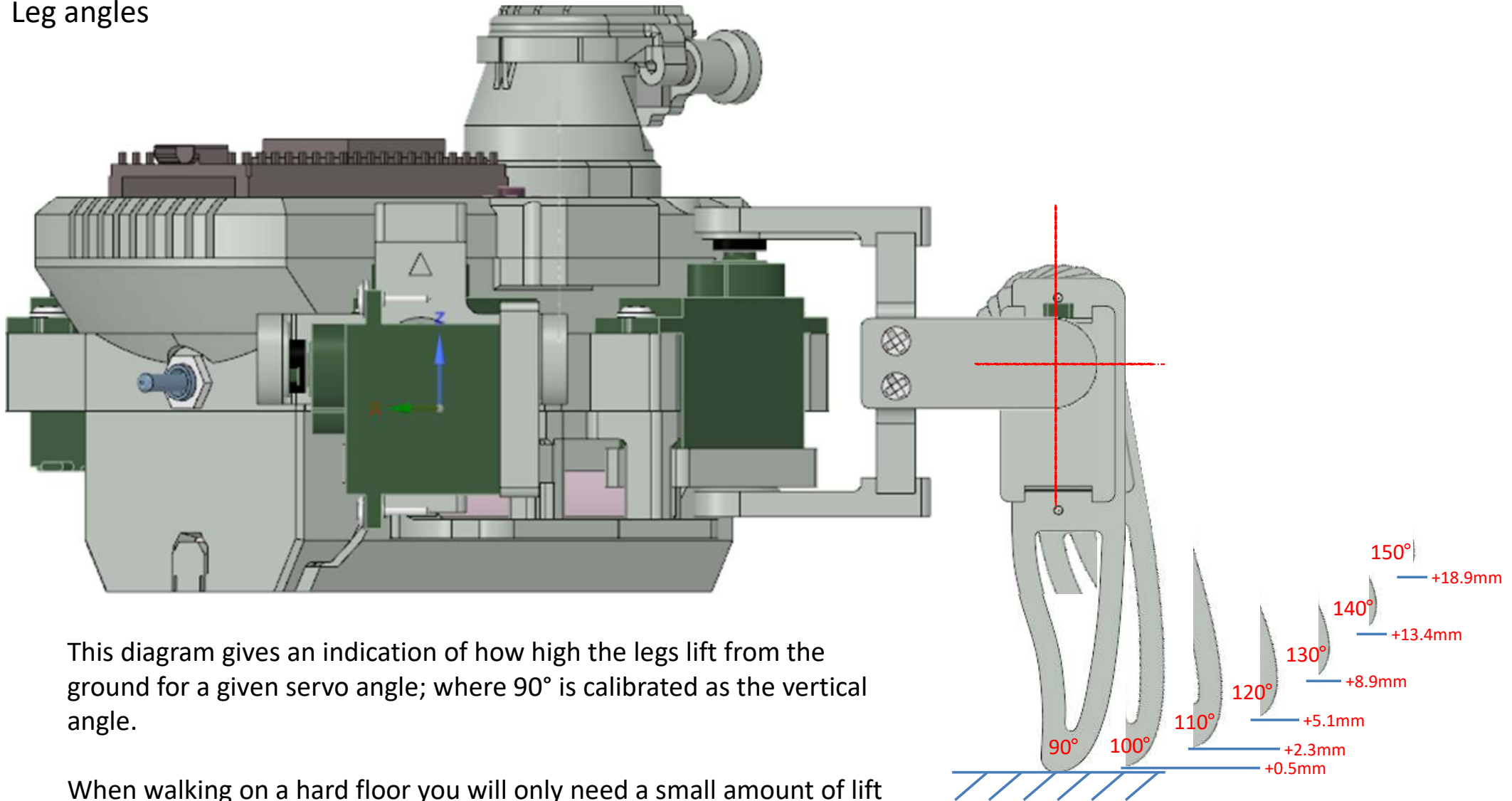
Head_60P



Variables:

- Range
- Target angle
- Sweep delta
- Sweep direction +/-
- Sweep rate/period
- Range min
- Min angle

Leg angles



This diagram gives an indication of how high the legs lift from the ground for a given servo angle; where 90° is calibrated as the vertical angle.

When walking on a hard floor you will only need a small amount of lift on the freely moving legs for it to walk; where as in thick piled carpet the robot will sink in and a higher leg lift will be needed to avoid unnecessary drag. You could change the code to use options to set different heights from the infrared controller.