Object-Based Calibration

Ronald 2017.12.27 V1.0

ENG. Tory 2017.12.27 V1.0

Briefly

purpose :

1. If want to use Fixed Point alignment ,need to use dice board and make a Workspace ,before edit vision job.
2. However, sometime there don't have enough space to placing calibration plates or there is no calibration plate near.
3. Though this feature, users cloud directly uses the visual characteristics of the workpiece doing camera calibration

Method in the past

Camera clibration
(dice board)

↓

Vision job edit

↓

Create point
on vision base

Calibration with objects

Vision job edit
+
Object Based
Calibration

↓

Create point
on vision base

Step 1 : Do tilt calibration first

Step 2：Enter the visual task to select the object correction

Step 3：Edit vision job

Flow

TMCam_AF01
111.00 ms

ENHANCE
Contrast_1
9.00 ms

1
ND
ShapePattern_...
52.00 ms

2
CALIBRATION

All: 178.00 ms

Live Video

40%

1. Set object detection and ensure that positioning results are stable
2. Click CALIBRATION to enter the page

Step 4：Object-based Calibration

Object-based Calibration

Object-based Calibration

- Move to Initial Position

1 — Moving Range

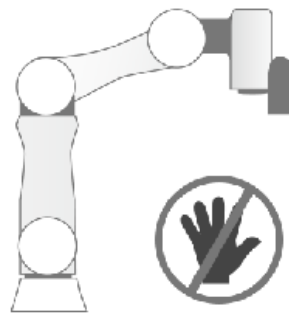Radius in X-Y Plane (mm)
200

Distance in ± Depth (mm)
100

2 — Start Calibration

Live Video

3 — **Move Robot**

Please press the "+" button on Robot Stick continuously to start the Visual Servo motion of the robot.
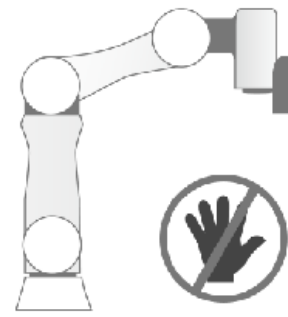
Cancel

4 — ⚠ **Success!**

Success! The calibration procedure is done.

OK

5 — **Move Robot**

Please press the "+" button on Robot Stick continuously to move the robot to the initial position.
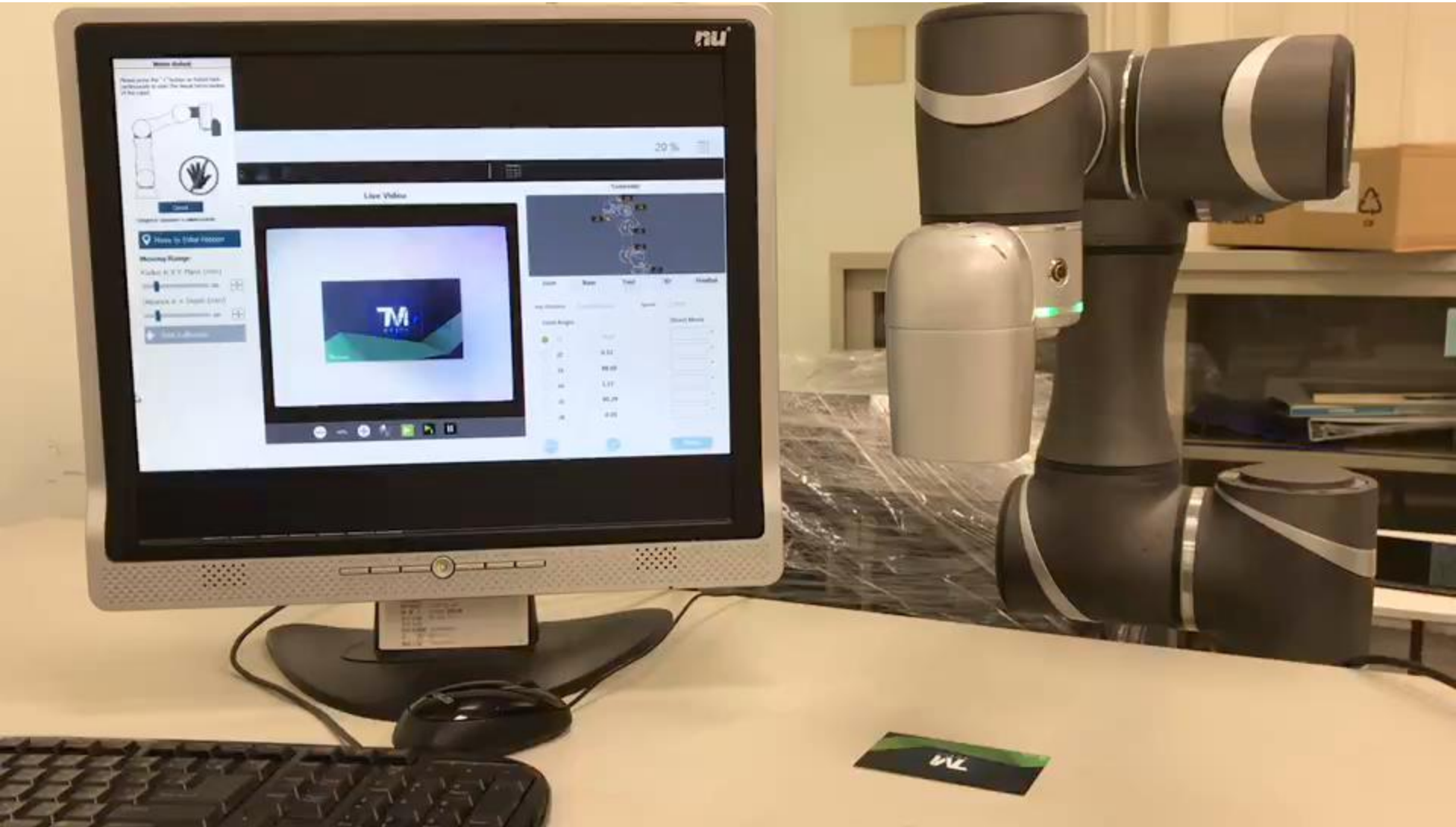
Cancel

6 — ⚠ **Success!**

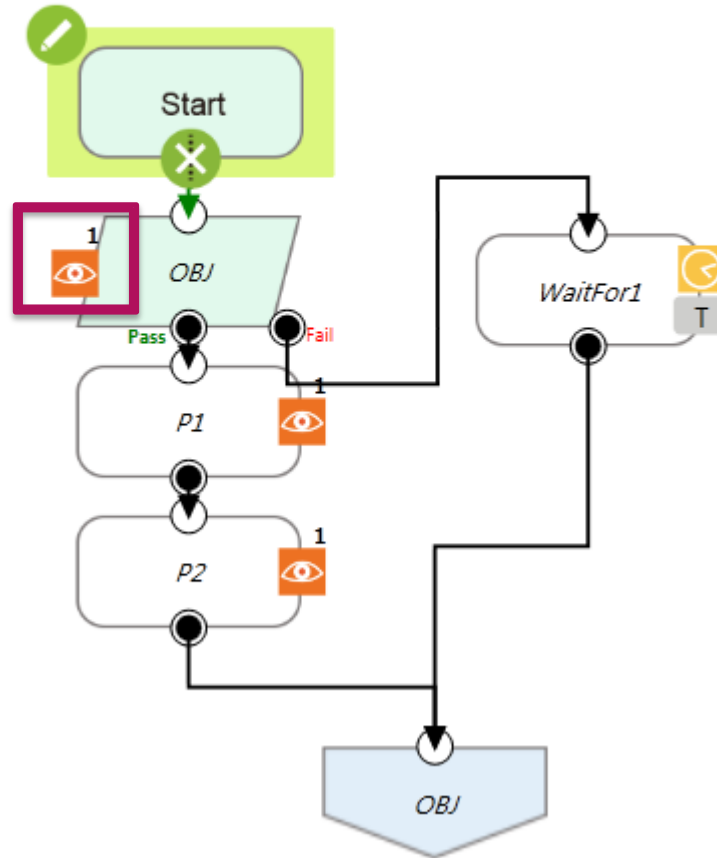The Robot is at the initial position.

OK

1. Set the movement range of the calibration process
2. Click Start Calibration
3. Long press the + button on the Robot Stick, the arm will move to 4 points for correction
4. Calibration success
5. Long press + again to return to the initial point
6. Homing success

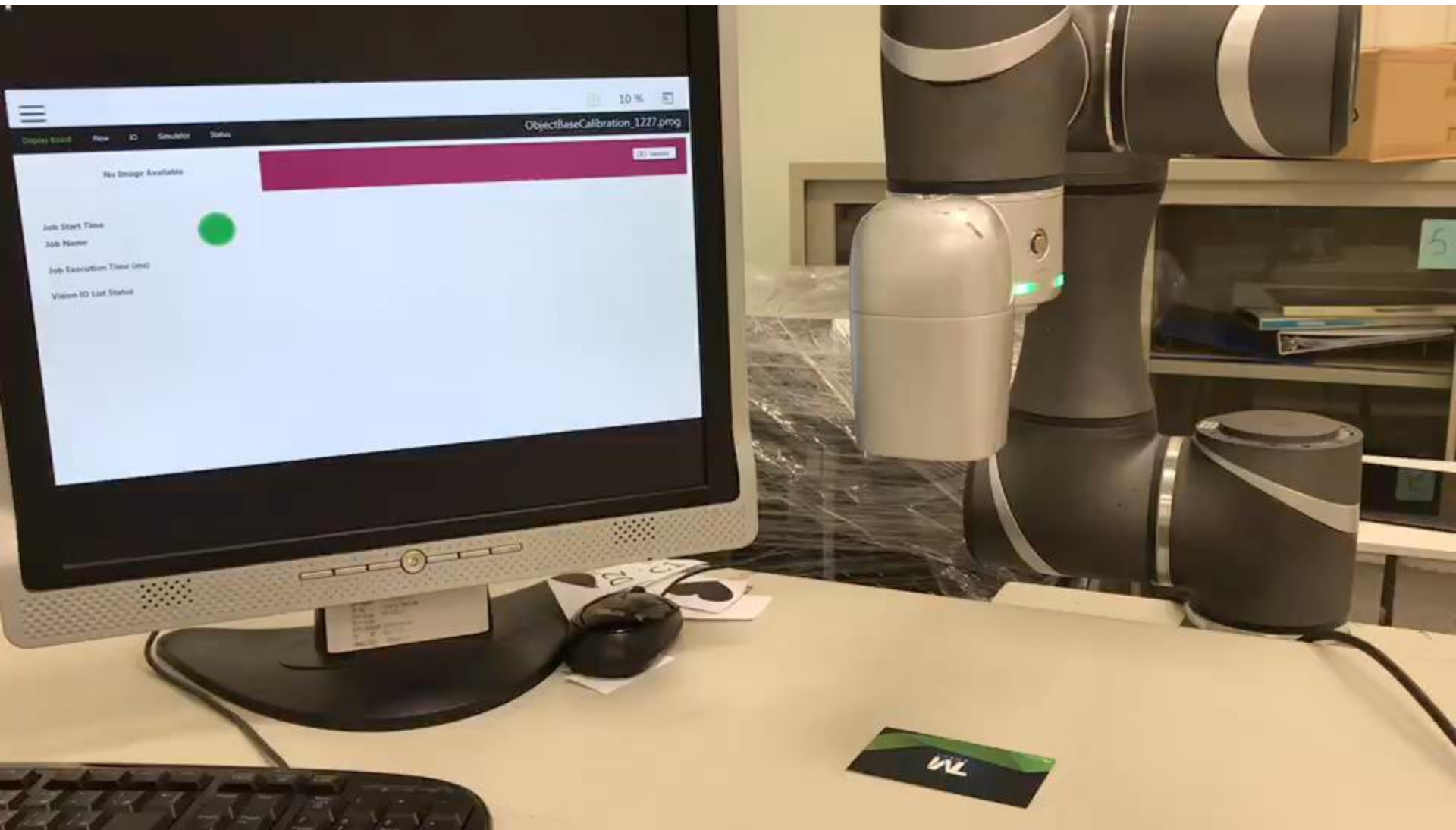# Step 4：Object-based Calibration

Step 5：Create points on vison base

Step 6：Project Execution

Thank You