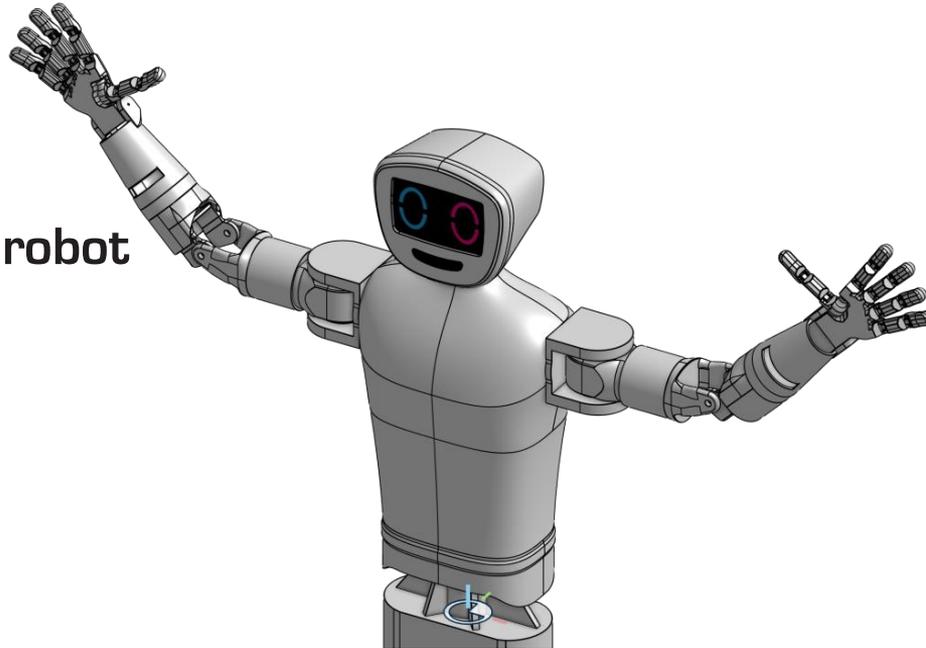# How to build your robot

www.pib.rocks/build

instructions for:
Recalibration
pib#4

PRINT
BUILD
DEVELOP
YOUR OWN ROBOT

Build it better: our suggestion for assembling pib

We recommend **tools** for each step. These are a suggestion, you can of course also use other tools.

1-5

We have categorized each step according to its **difficulty** - from **1-5** (1 being the easiest, 5 the hardest)
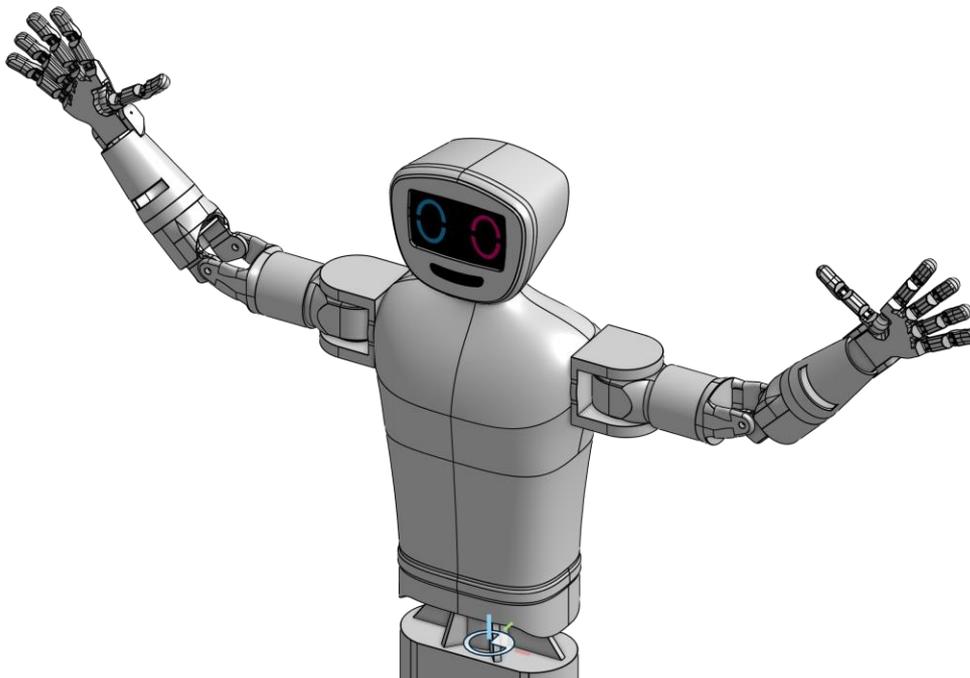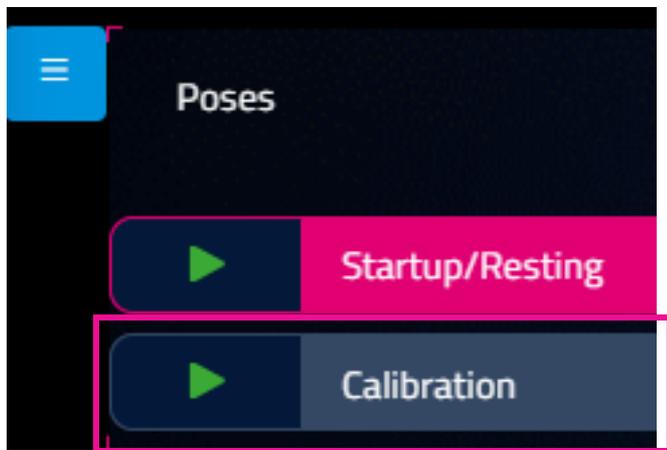
We also show you which **non-printable parts** you need for each step

Step 1

While assembling pib if you forgot a step or moved a motor by mistake, if you click on calibration pose and you see pib looking different than this, then we need to recalibrate joints that look different than their configuration here.

Step 2a

- Don't change pose, joint value or cutoff power
- Check which motors look uncalibrated in this picture for example, ist both elbow and shoulder horizontal left that look different from the calibration refrence picture
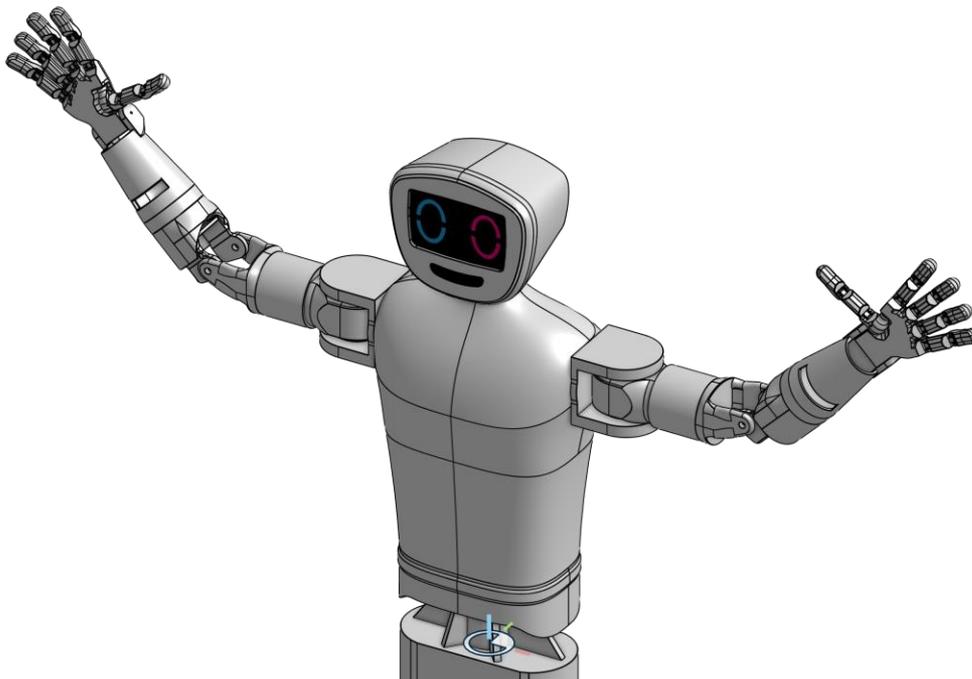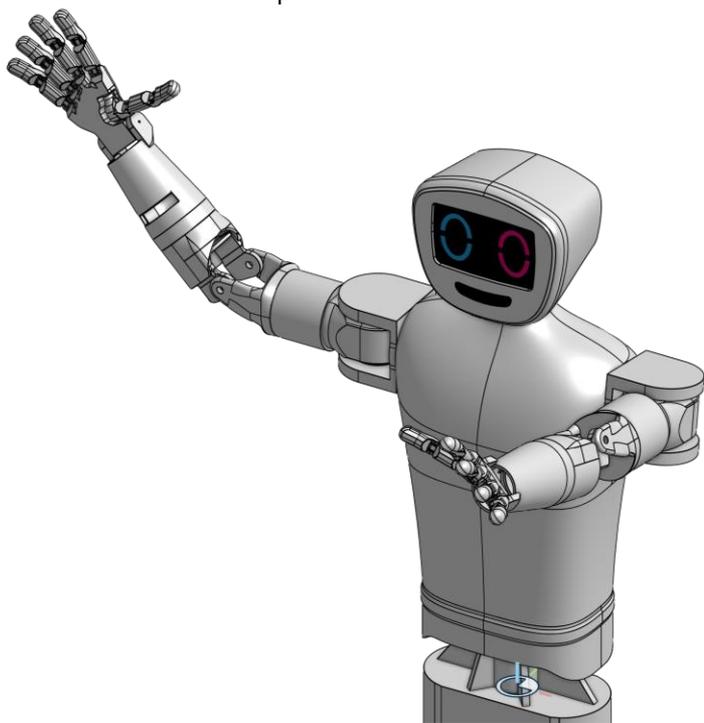
Step 2b

- Every joint has 2 40mm screws connecting it to the prior joint
- For elbow and shoulder horizontal, unscrew those 2 screws until you feel the joint is loose and can be moved by hand
- Move the joints by hand to match the calibration refrence
- Tighten the screws again
- You can repeat that for lal uncalibrated joint, the next slide shows the location of all 2 screws for each joint
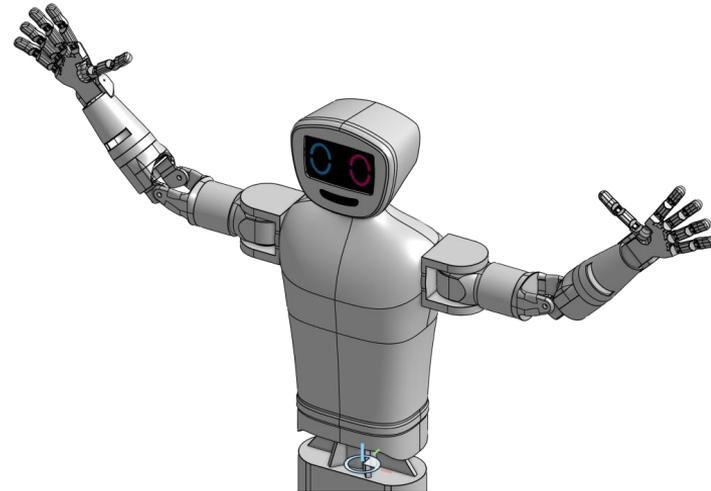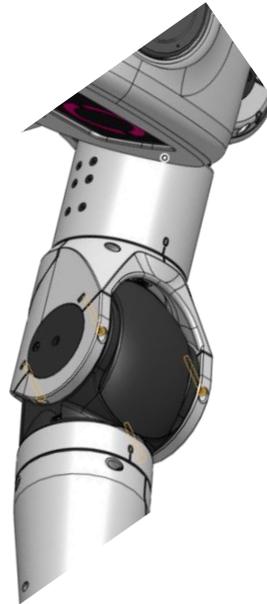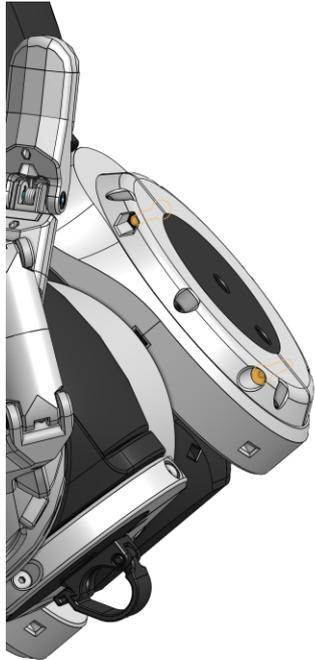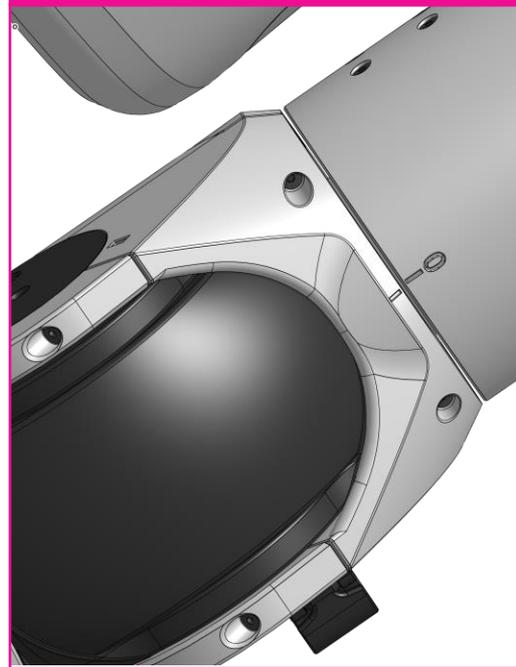
Note

Shoulder vertical screws
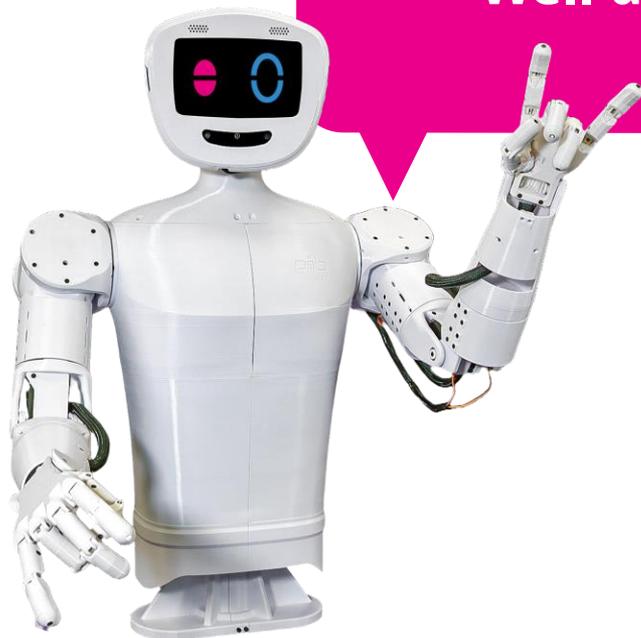
Lowerarm rotation screws

Lowerarm rotation screws

Congratulations

You did a great job, you have recalibrated pib !

Well done!

Do you need support?

Or do you need our pib.Box with all non-printable parts?

Or maybe you have some new ideas and improvements?

Please contact us.

team@pib.rocks
Send us an email.

discord.com/invite/GRdpyeDu7P
Join us on Discord.

shop.pib.rocks
Order non-printable parts for pib.