

# 外参标定流程

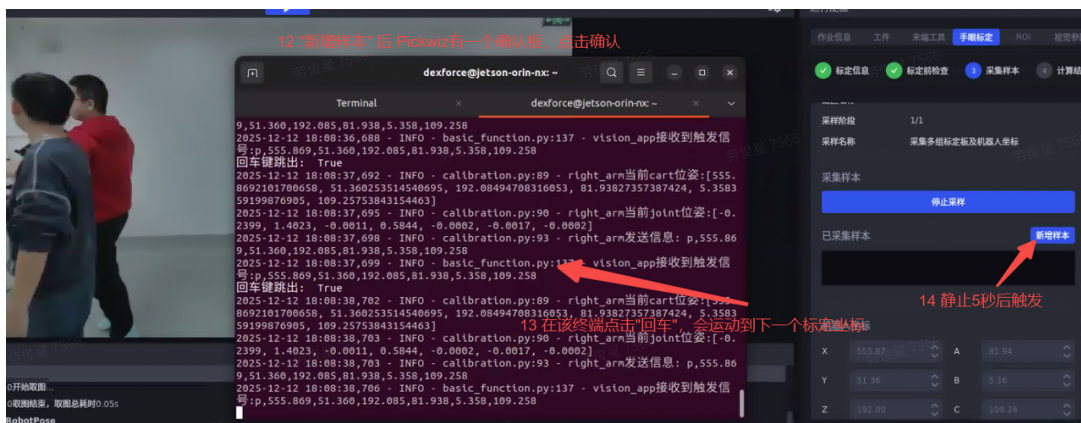
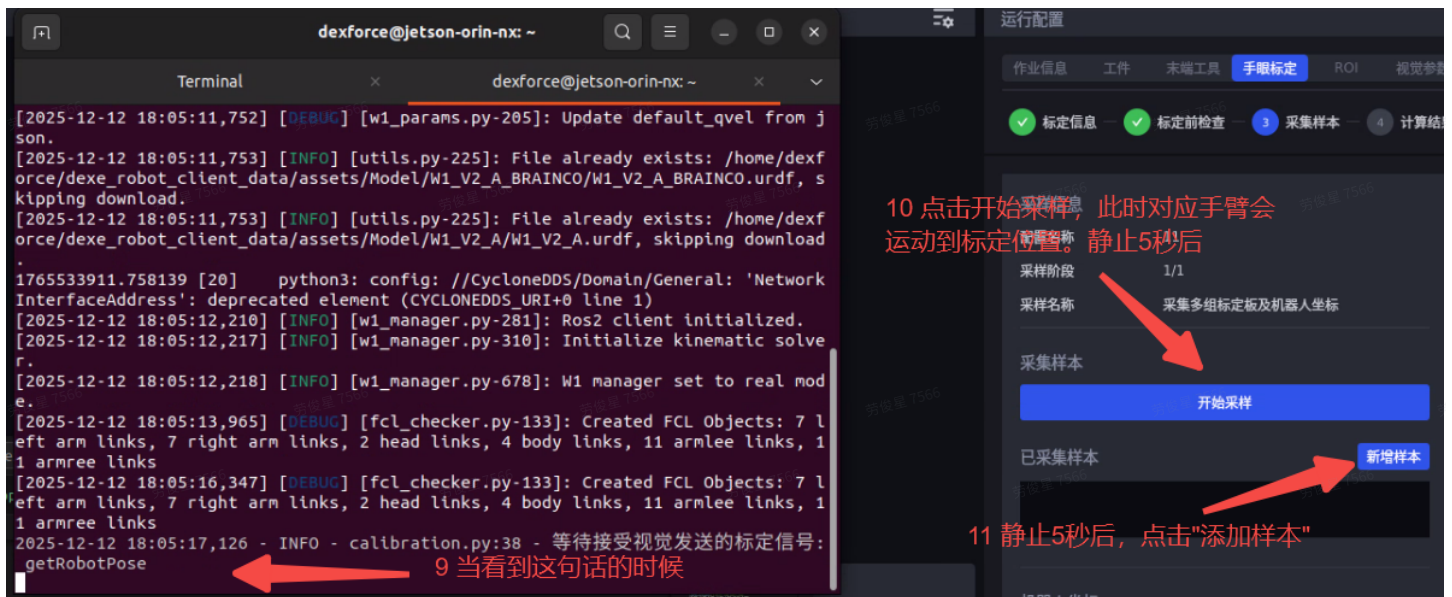
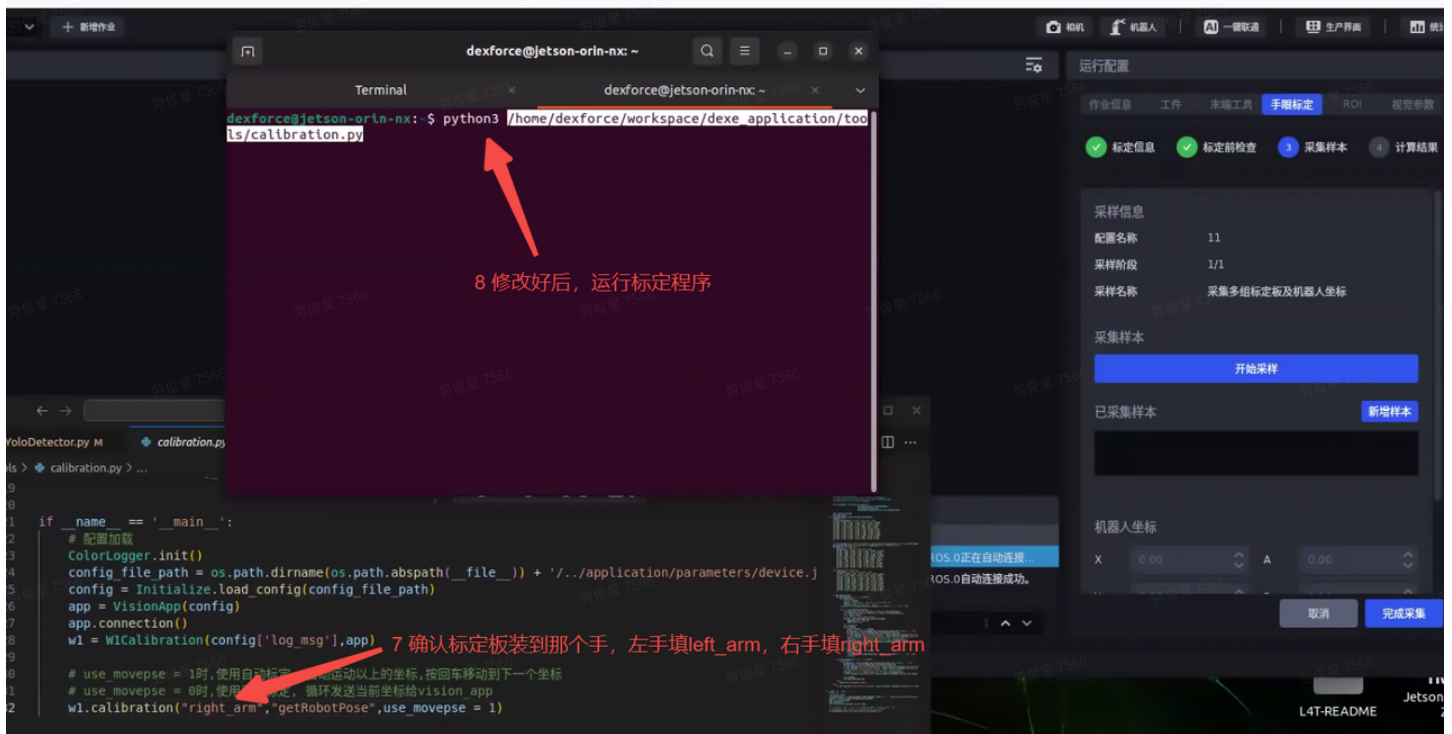
手动点击W1-UI中的"启动Pickwiz"，打开Pickwiz。随后按着1-25的步骤即可完成左右手标定





#### 代码块

```
1 python3 /home/dexforce/workspace/dexe_application/tools/calibration.py
```



12 "新增样本" 后，会有个添加样本成功的小框，点击确认

Terminal

```
dexforce@jetson-orin-nx: ~  
9,51.360,192.085,81.938,5.358,109.258  
2025-12-12 18:10:05,360 - INFO - basic_function.py:137 - vision_app接收到触发信号:p,555.869,51.360,192.085,81.938,5.358,109.258  
回车键跳出: True  
2025-12-12 18:10:06,362 - INFO - calibration.py:89 - right_arm当前cart位姿:[555.8692101700658, 51.360253514540695, 192.08494708316053, 81.93827357387424, 5.358359199876905, 109.25753843154463]  
2025-12-12 18:10:06,365 - INFO - calibration.py:90 - right_arm当前joint位姿:[-0.2399, 1.4023, -0.0011, 0.5844, -0.0002, -0.0017, -0.0002]  
2025-12-12 18:10:06,365 - INFO - calibration.py:93 - right_arm发送信息: p,555.869,51.360,192.085,81.938,5.358,109.258  
2025-12-12 18:10:06,365 - INFO - basic_function.py:137 - vision_app接收到触发信号:p,555.869,51.360,192.085,81.938,5.358,109.258  
回车键跳出: True  
2025-12-12 18:10:07,368 - INFO - calibration.py:89 - right_arm当前cart位姿:[555.8692101700658, 51.360253514540695, 192.08494708316053, 81.93827357387424, 5.358359199876905, 109.25753843154463]  
2025-12-12 18:10:07,374 - INFO - calibration.py:90 - right_arm当前joint位姿:[-0.2399, 1.4023, -0.0011, 0.5844, -0.0002, -0.0017, -0.0002]  
2025-12-12 18:10:07,379 - INFO - calibration.py:93 - right_arm发送信息: p,555.869,51.360,192.085,81.938,5.358,109.258  
2025-12-12 18:10:07,380 - INFO - basic_function.py:137 - vision_app接收到触发信号:p,555.869,51.360,192.085,81.938,5.358,109.258
```

13 点击一下该终端，触发回车键，对应臂会运动到下一个标定坐标

14 静止5秒后触发

15 循环12- 14步骤10次，第11次触发13会退出程序，代表10个样本添加完成

作业信息 工件 末端工具 手眼标定 ROI 视觉参数

✓ 标定信息 ✓ 标定前检查 3 采集样本 4 计算结果

采样阶段 1/1  
采样名称 采集多组标定板及机器人坐标

采集样本

停止采样

已采集样本

新增样本

机器人坐标

X	555.87	A	81.94
Y	51.36	B	5.36
Z	192.09	C	

取消 完成采集

Home / workspace / w1\_demo / config / calibration

calibration\_17 calibration\_39 calibration\_40

19 进入到该文件夹

20 进入最新的标定，数字越大越新



