

STARTUP OF THE PIZZA ROBOT

Password: pizza1

To turn on the robot:

- put the main switch in upright position
- enable the switch box, the signal light will be turned on
- make sure the emergency stop is not pressed down

To start and configure Matlab:

- double click on the Matlab icon
- enter password
- change current directory to: /home/pizza/groupX (where X is your group number)
- open pizza_empty.mdl or your own saved model

To execute the model:

- in the model, type Ctrl+B to build the executable
- open a terminal
- to go to the right directory, type: cd /home/pizza/groupX
- to start the realtime target, type: sudo ./pizza_empty -w
- enter the password if prompted
- in your model, click Simulation -> Connect To Target
- wait a few seconds and then click Simulation -> Start Real-Time Code
- give the red Start/Stop box the value 1 (one)

To stop the model:

- give the red Start/Stop box the value 0 (zero)
- wait until the robot is in its downward position
- click Simulation -> Stop Real-Time Code

To start a file browser:

- double click on the Nautilus icon
- enter password

ABOUT THE MODEL

The sample frequency of the model is 500 Hz

The inputs of the robot can handle the following values:

axis 1 and 2: +- 6.25 (Volts? m/s?)

axis 3 and 4: +- 10 (Volts? m/s?)

Status Values:

STATUS	VALUE
WAITING_FOR_START	0
HOMING	1
MOVING	2
READY	3
P1_POS_VIOLATION	4
P2_POS_VIOLATION	5
P3_POS_VIOLATION	6
P4_POS_VIOLATION	7
P1_VEL_VIOLATION	8
P2_VEL_VIOLATION	9
P3_VEL_VIOLATION	10
P4_VEL_VIOLATION	11