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- (71) Applicant: **BRIGHT MACHINES, INC.** [US/US]; 2445
16th Street, San Francisco, California 94103 (US).
- (72) Inventors: **SHAFIEKHANI, Ali**; 2445 16th Street, San
Francisco, California 94103 (US). **KARMARKAR, Vish-
wajeet Padmanabh**; 2445 16th Street, San Francisco, Cal-
ifornia 94103 (US). **CLARK, Barrett Christopher**; 2445

- 16th Street, San Francisco, California 94103 (US). **GAL-
LO, Emmanuel**; 2445 16th Street, San Francisco, Califor-
nia 94103 (US). **PAPPOPPULA, Murali**; 2445 16th Street,
San Francisco, California 94103 (US).
- (74) Agent: **SZEPESI, Judith**; 99 Almaden Boulevard, Suite
575, San Jose, California 95113 (US).
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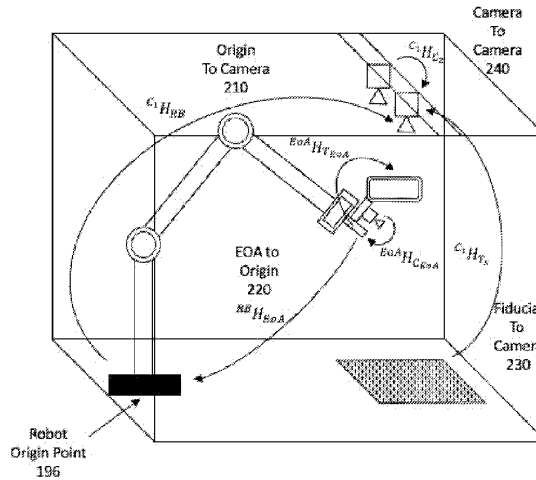


FIG. 2

(57) Abstract: A method of calibrating a robotic arm which includes perform iterative eye-in-hand and robot calibration, using a calibrated end of arm camera with known intrinsic parameters and a static target, to obtain eye-in-hand transformations and robotic parameters. The method further uses robotic parameters to estimate pose of end of arm, for eye-to-hand calibration, to obtain eye-to-hand transformations and calculates final error compensation based on the robotic parameters, eye-to-hand transformations, and eye-in-hand transformations. In one embodiment, the method calculates a robot positioning error map function, the robot positioning error map function used to adjust movement parameters for the robotic arm.

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