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(54) **A CALIBRATION CONFIGURATION AND A METHOD OF CALIBRATION**

(57) The present invention regards a calibration configuration and a method of calibration of a weighing arrangement (3) configured for dynamic weighing. A proximity sensor (61) is adapted to detect a distance measure (62); wherein an electrical control circuitry (9) is configured to convert the distance measure (62) to a weighing arrangement measured weight value of the load. The electrical control circuitry (9) is adapted to register the weighing arrangement measured weight value.

The programmable robot apparatus (11) comprises a motion control circuitry (25); an end effector device (13); a calibration circuitry (21) adapted for electrical communication with the electrical control circuitry (9) adapted to register an actual weight value of a first calibration weight member (17').

-processing the weighing arrangement measured weight value of the first calibration weight member (17') and the actual weight value of the first calibration weight member (17'),

-registering the adjusted weighing arrangement measured weight value of the first calibration weight member (17') in a memory circuitry of the electrical control circuitry 9 of the weighing arrangement 3; and

-releasing the first calibration weight member (17') from the weighing arrangement (3).

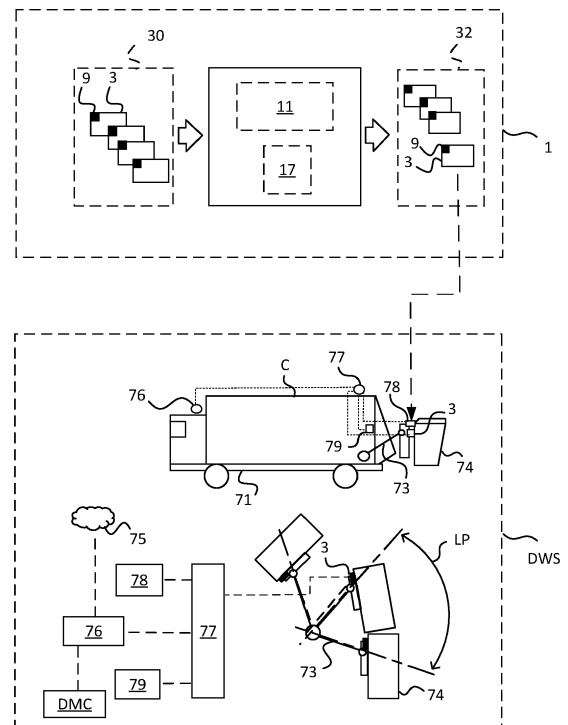


FIG. 7