



FS 0CPP 0002 - DSP Mico 5.0.6

Release note

Version 1.0

April 22, 2014

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Revisions & Approval

Version	Primary Author(s)	Description of Version	Date Completed
1.0	A. Lecours	First version	2014-04-22

Requirements Specification Approval History

Approving Party	Version Approved	Signature	Date

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1 Introduction

1.1 Purpose

This document is used as a release note on MICO's DSP Version 5.0.6

NOTE: The last release is 5.05.0034. The last release note is 5.05.

2 New Features

REHABILITATION

None (See general)

RESEARCH

None (See general)

GENERAL

None

3 Improvements / modifications

REHABILITATION

(See general)

RESEARCH

(See general)

GENERAL

3.1 Fingers gripping force

The fingers have more gripping force and more range.

3.2 Improved singularity management

Singularity management was improved, especially for the wrist.

3.3 Improved ready / home algorithm

The Cartesian ready / home algorithm was improved.

4 Bug Fix

REHABILITATION

(See general)

RESEARCH

4.1 Cartesian trajectory problem after a “Time Delay”

There was a problem with a “Time Delay” during a Cartesian trajectory. If the Cartesian point after the delay was not in a well-conditioned position, the arm was not moving and transferred in angular position.

4.2 Torque value not a number

The torque value sometimes appeared as “Not a number”. This was corrected.

(See general)

GENERAL

4.3 Basic retract position

The basic retract position alignment was improved to be more straight.

4.4 Model number

In Jacosoft, the model number is now set at “MICO” or “JACO”.

4.5 Force control activation

The force control is now activated while in ready (home) position and deactivated in the retract/ready sequence. It is also activated when moving from a normal position to the ready (home) position.

4.6 DSP Hex file for Mico was large

The DSP Hex file of Mico was large and it was long to reprogram the Mico. This has been corrected.

5 Known issues and workaround

REHABILITATION

5.1 Goto orientation with drinking mode

The Goto Orientation (automatic orientation) has some problem when the drinking mode is active. When the orientation can't be reached, the arm may drift in position.

5.2 If the advance ready boots at the ready position, it will go to the first point instead of the second point.

To be corrected.

RESEARCH

None (See General).

GENERAL

5.3 It is not possible to perform a retract if a motion is active

If a motion is active (XPlus on the stick for example), a ready can be performed but the stick must be released in order to perform the retract.

5.4 Mico Communication problems

The communication between the DSP and the joints should be improved. This results in communication errors.