

JACO²

6 DOF

Advanced specification guide

Version 1.0.2

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Revisions

Version	Primary Author(s)	Description of Version	Date Completed
1.0.1	A Lecours	First Draft	05-11-2014
1.0.2	A Lecours	New template	08-05-2015

Contents

REVISIONS	2
CONTENTS	3
SPECIFIC UTILIZATION LIMITATIONS	4
SPECIFIC ELECTRICAL LIMITATIONS	4
<i>Recommended maximum actuators utilization</i>	4
SOFTWARE POSITION LIMITATIONS OF ACTUATORS	4
<i>Software position limitations of actuators</i>	4
<i>Software position limitations of fingers</i>	4
ADVANCED CONFIGURATIONS	5
POSITION INDEXATION OF THE ARM	5
RESET TORQUE	5
KINEMATIC PARAMETERS	6
BASIC PARAMETERS OF JACO ²	6
<i>Classic DH Parameters</i>	8
DIRECTIONS OF EACH JOINTS IN ANGULAR SPACE	9
INERTIAL PARAMETERS	9
ADVANCED SENSORS INFORMATION	10
ACCELEROMETERS POSITIONS	10

Specific Utilization limitations

Specific electrical limitations

Recommended maximum actuators utilization

	Big actuators (75mm)	Small actuators (58mm)	Fingers actuators
Maximum RPM	6 RPM	8 RPM	600RPM
Maximum Command/sec	36 ° / sec	48 ° / sec	30 mm / sec 10800 ° / sec
Maximum repetitive Current	1.5A	1.6A	1,4A
Maximum temperature	80°C	80°C	80°C

Utilization over these maximum recommended parameters may affect lifetime of the arm and its modules.

Please refer to JACO² specification sheet for additional information

Software position limitations of actuators

The following limitations indicate the software limitations that are presents in JACO² controller to ensure safety of the robot. These limitations are there to protect the arm and its environment.

Software position limitations of actuators

When moving JACO² actuators, the following minimum and maximum positions should be followed. If the command sent to any of these actuators goes further than these values, the actuators will stop moving.

Actuator #	Minimum (degrees)	Maximum (degrees)
1	-10 000	10 000
2	50	310
3	19	341
4	-10 000	10 000
5	-10 000	10 000
6	-10 000	10 000

Software position limitations of fingers

When moving JACO² fingers, the following minimum and maximum positions should be respected. If the command sent to any of these fingers goes further than these values, the fingers will stop moving.

Finger #	Minimum	Maximum (degrees)
1	0 mm (0 °)	18.9 mm (6800°)
2	0 mm (0 °)	18.9 mm (6800°)
3	0 mm (0 °)	18.9 mm (6800°)

Position indexation of the arm



Figure 1 : Reset position

Angular position is : [180, 180, 180, 180, 180, 180]

Reset Torque

In order to reset the torque sensors zero, you must first place the arm in a position where gravity does not influence joint torques. The set zero position [180, 180, 180, 180, 180, 180] is good but it is suggested to use the position [*, 180, 180, 0, 0, 180] since this position also limits perpendicular torques on the actuators.

Kinematic Parameters

Basic parameters of JACO²

Theses following parameters are all necessary values for JACO² kinematics.

Robot length values (meters)		
D1	0.2755	Base to elbow
D2	0.4100	Arm length
D3	0.2073	Front arm length
D4	0.0741	First wrist length
D5	0.0741	Second wrist length
D6	0.1600	Wrist to center of the hand
e2	0.0098	Joint 3-4 lateral offset

Alternate parameters	
aa	$((30.0 \cdot \pi) / 180.0)$
ca	$(\cos(aa))$
sa	$(\sin(aa))$
c2a	$(\cos(2 \cdot aa))$
s2a	$(\sin(2 \cdot aa))$
d4b	$(D3 + sa/s2a \cdot D4)$
d5b	$(sa/s2a \cdot D4 + sa/s2a \cdot D5)$
d6b	$(sa/s2a \cdot D5 + D6)$

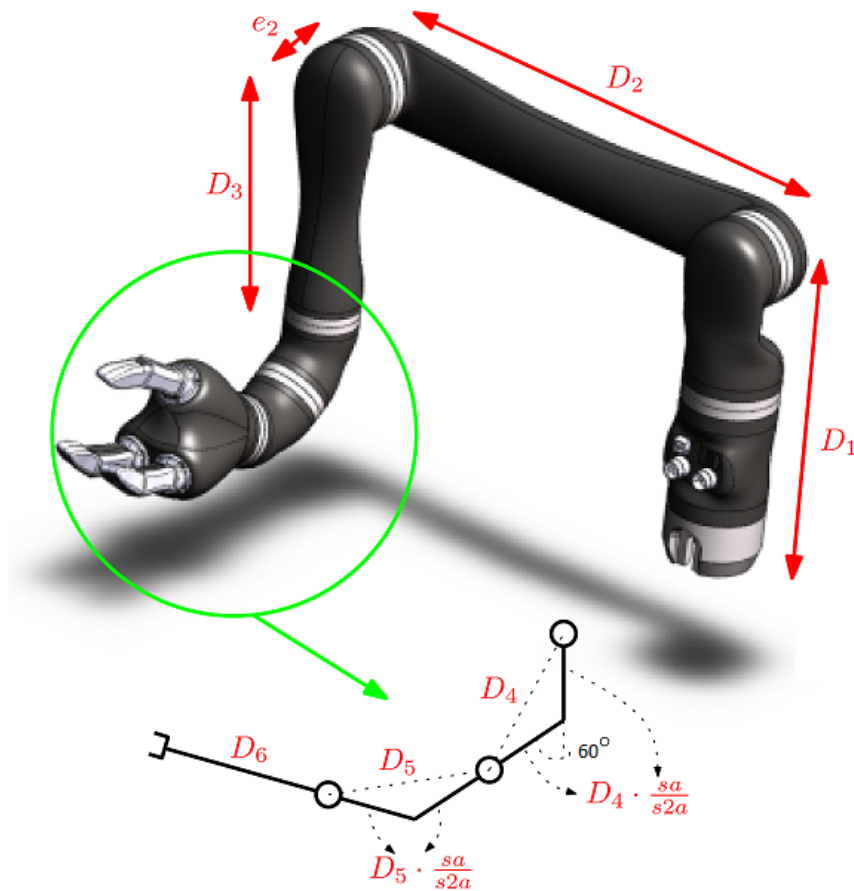


Figure 2: Robot length values

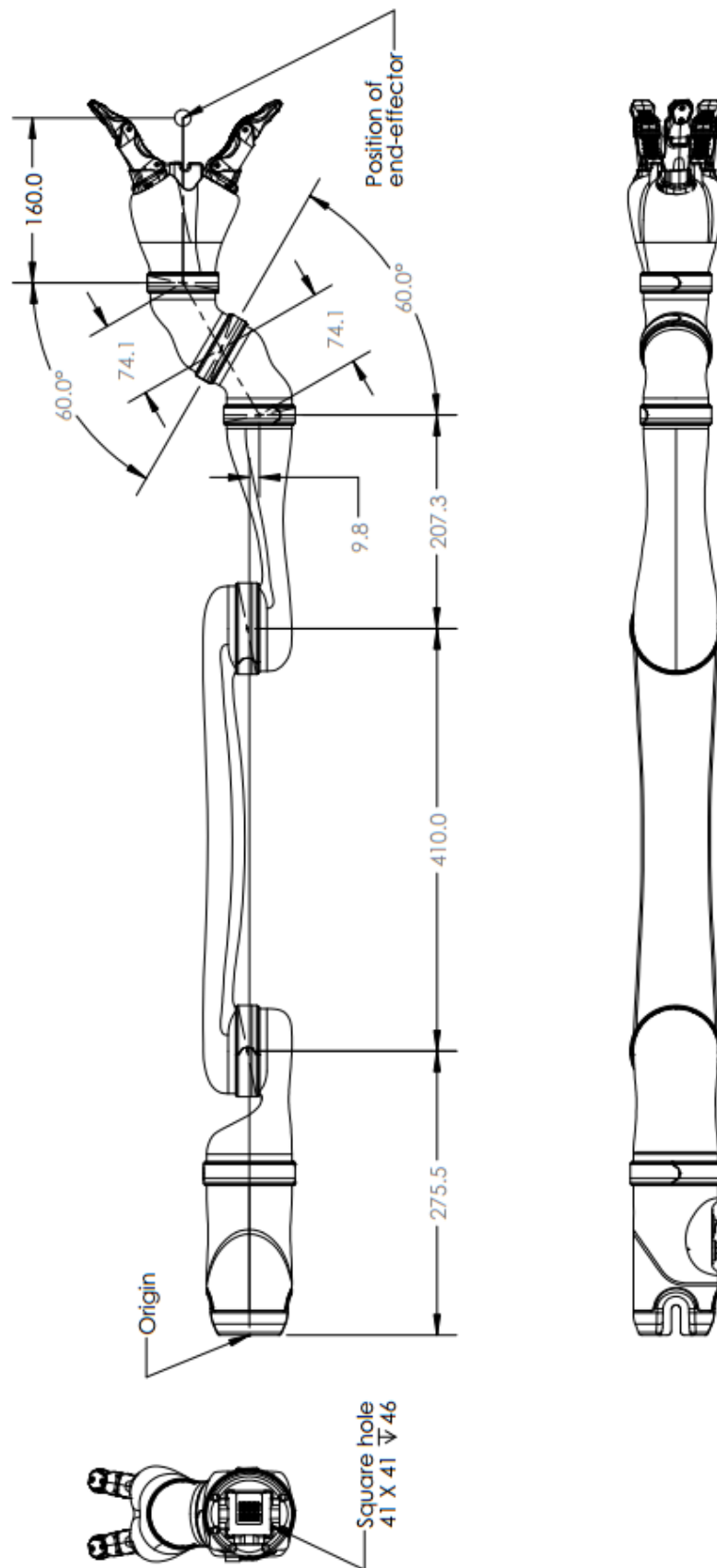


Figure 3: Detailed robot length values (units in mm)

Classic DH Parameters

The following charts represents the classic DH parameters of JACO² arm:

Classic DH parameters				
i	$\alpha(i-1)$	$a(i-1)$	d_i	θ_i
1	$\pi/2$	0	D1	q_1
2	π	D2	0	q_2
3	$\pi/2$	0	-e2	q_3
4	$2*aa$	0	-d4b	q_4
5	$2*aa$	0	-d5b	q_5
6	π	0	-d6b	q_6

Equations for transformation from DH algorithm to JACO ² physical angles
$Q1(\text{Jaco}^2) = -Q1(\text{DH Algo})$
$Q2(\text{Jaco}^2) = Q2(\text{DH Algo}) + 90$
$Q3(\text{Jaco}^2) = Q3(\text{DH Algo}) - 90$
$Q4(\text{Jaco}^2) = Q4(\text{DH Algo})$
$Q5(\text{Jaco}^2) = Q5(\text{DH Algo}) + 180$
$Q6(\text{Jaco}^2) = Q6(\text{DH Algo}) - 90$

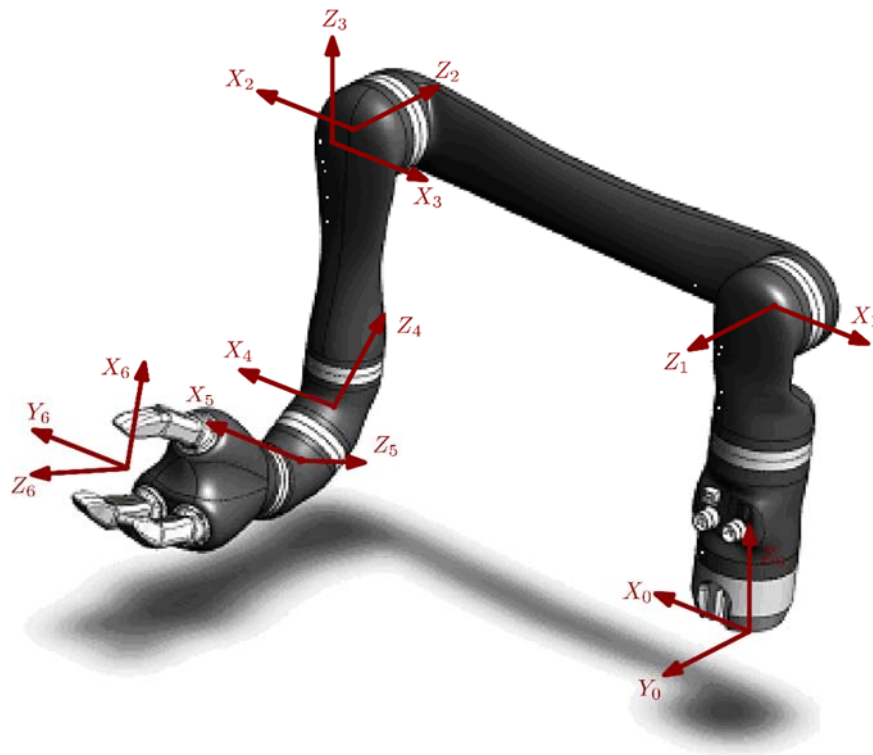


Figure 4: Classic DH parameters frame position
 Represented Jaco² angular position is : [180, 270, 90, 180, 180, 0]

Directions of each joints in angular space

The following image represents the positive direction of rotation of each actuator on the JACO² arm:

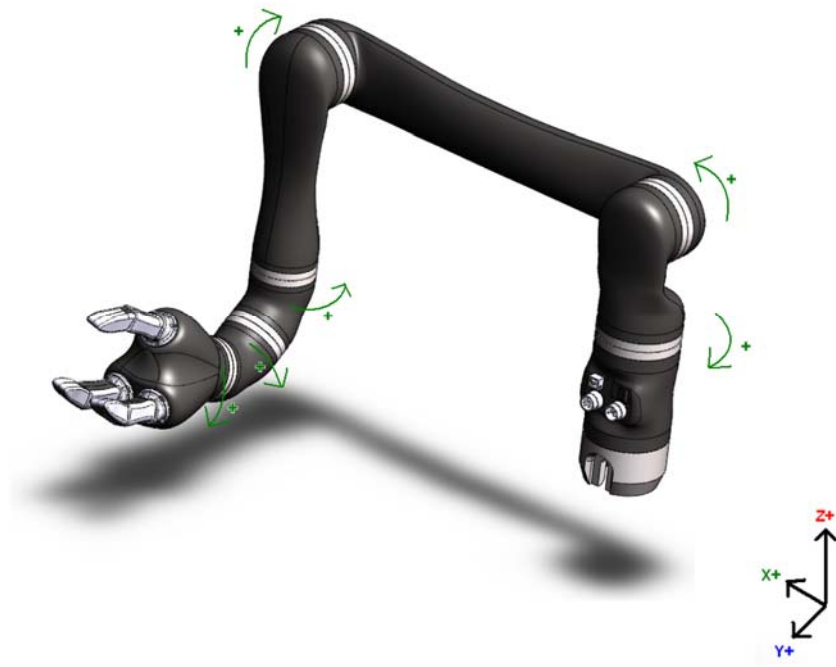


Figure 5: Directions of each joint in the angular space of the robot

Inertial parameters

The following image represents the inertial parameters of each JACO² module:

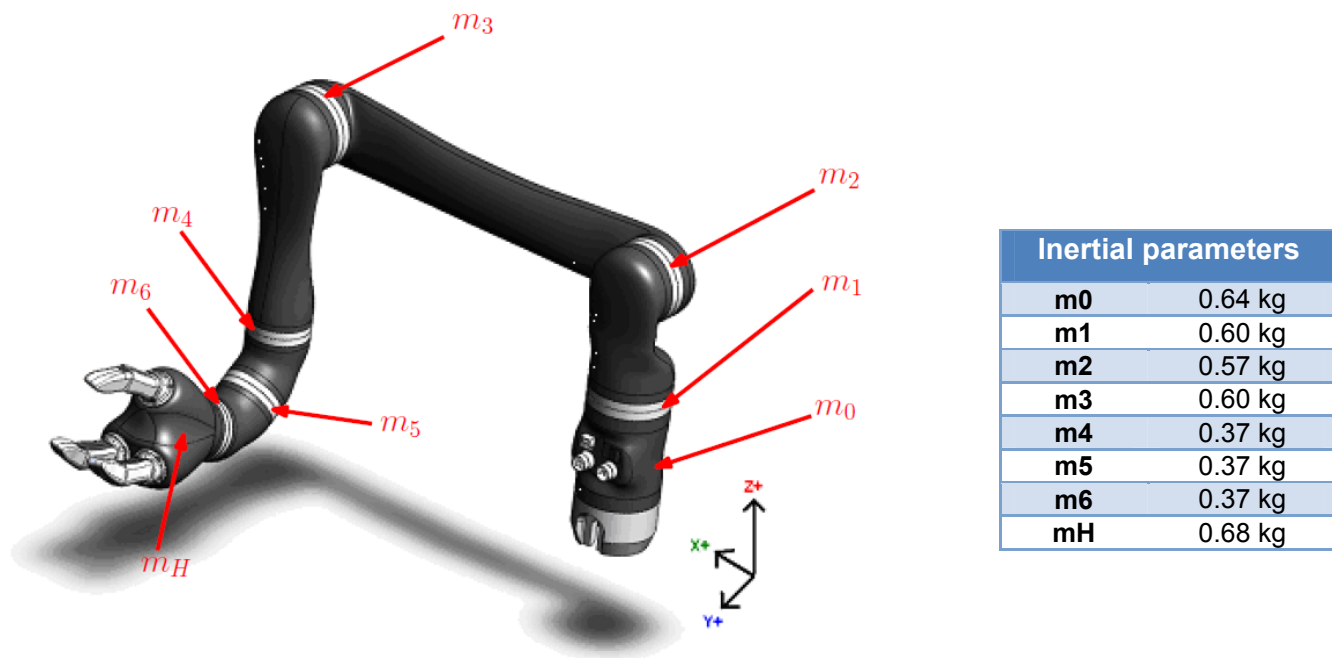
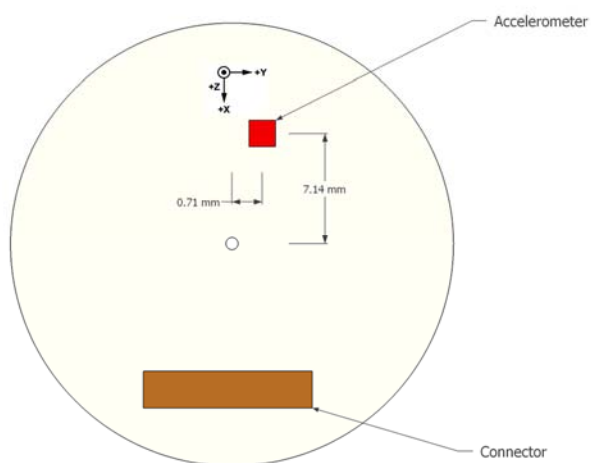
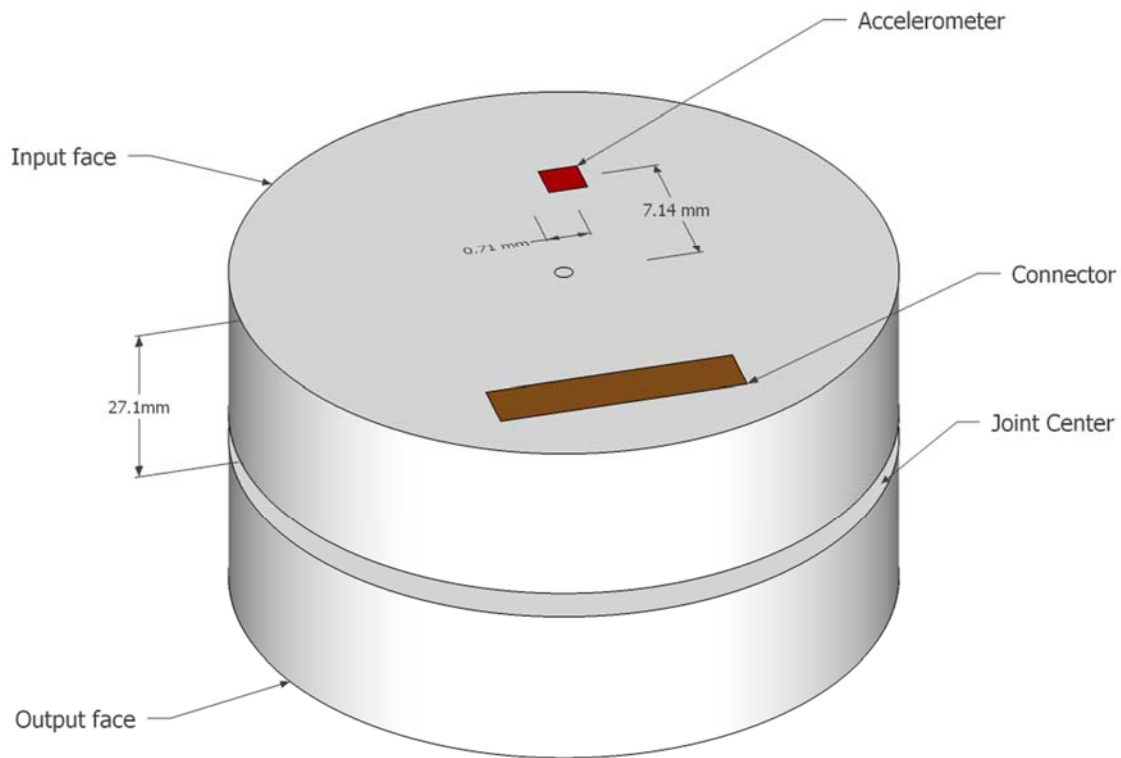


Figure 6: Inertial parameters

From Joint 6 to center of mass of the hand: ~8.5 cm

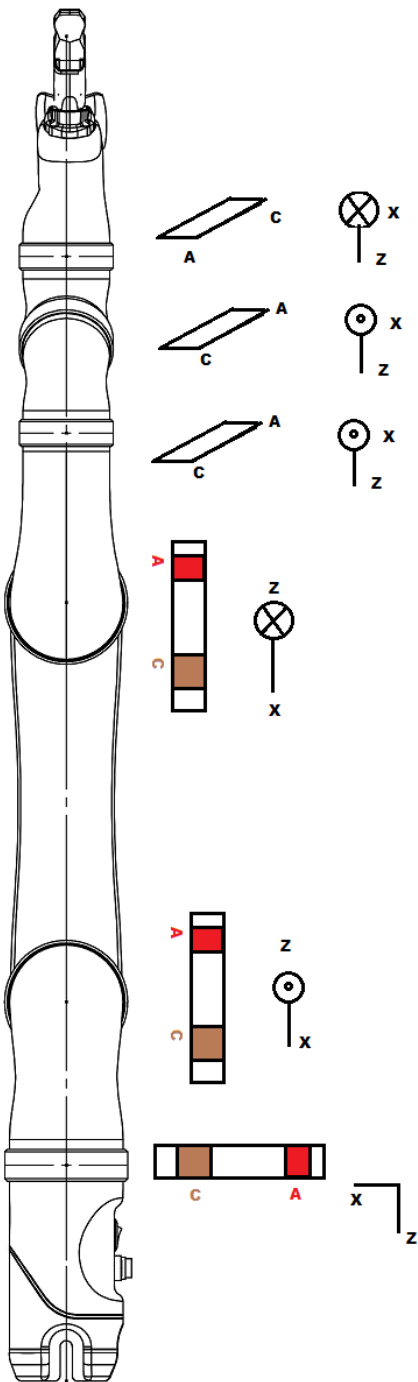
Accelerometers positions

Accelerometers in each joint.



Side view legend







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