At this position the joint angles are [180;270;90;180;180;0] and with the next figure representing joints direction, we can infer the angular position to have the real all 180deg position.

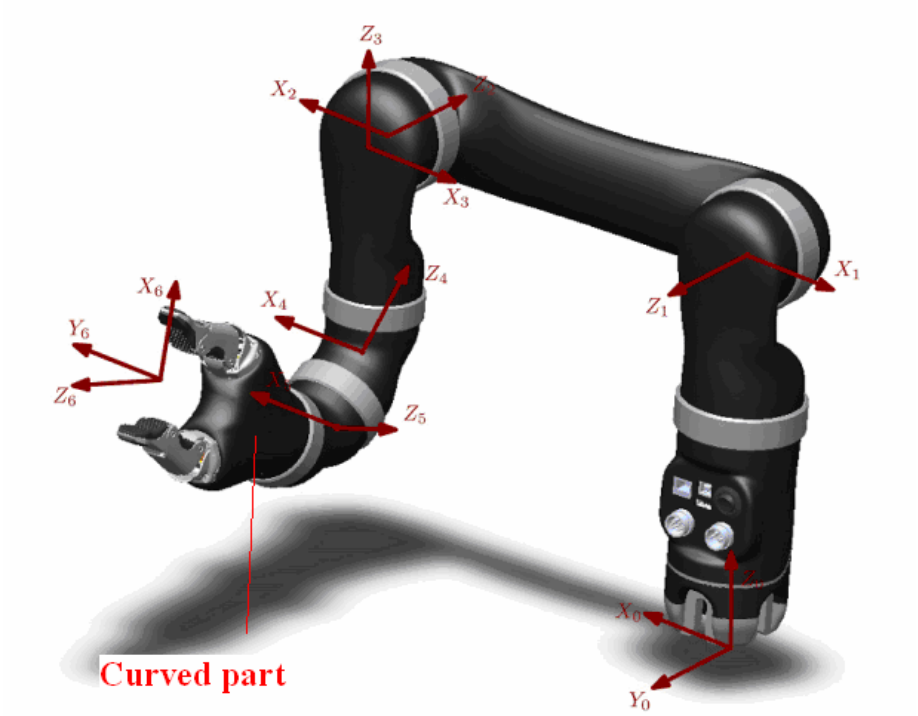


Figure 3 : Classic DH parameters frame position

Angular position is : [180, 270, 90, 180, 180, 0]

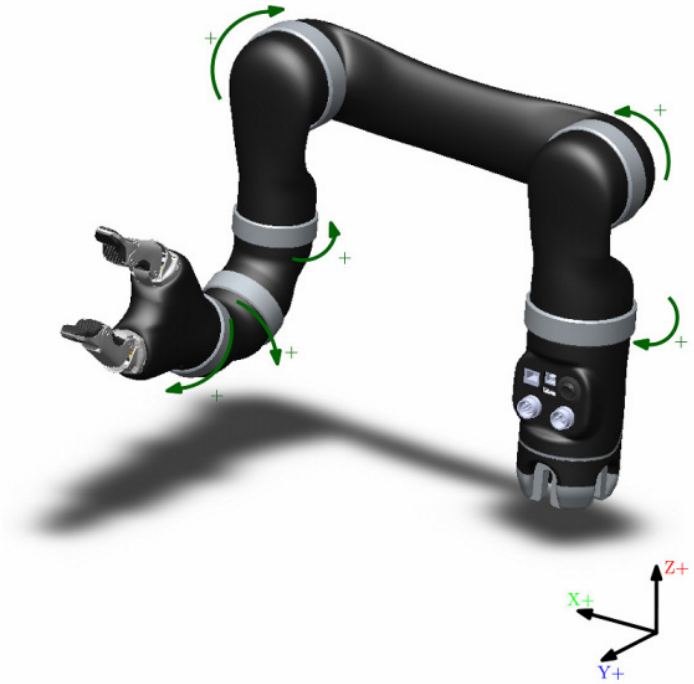
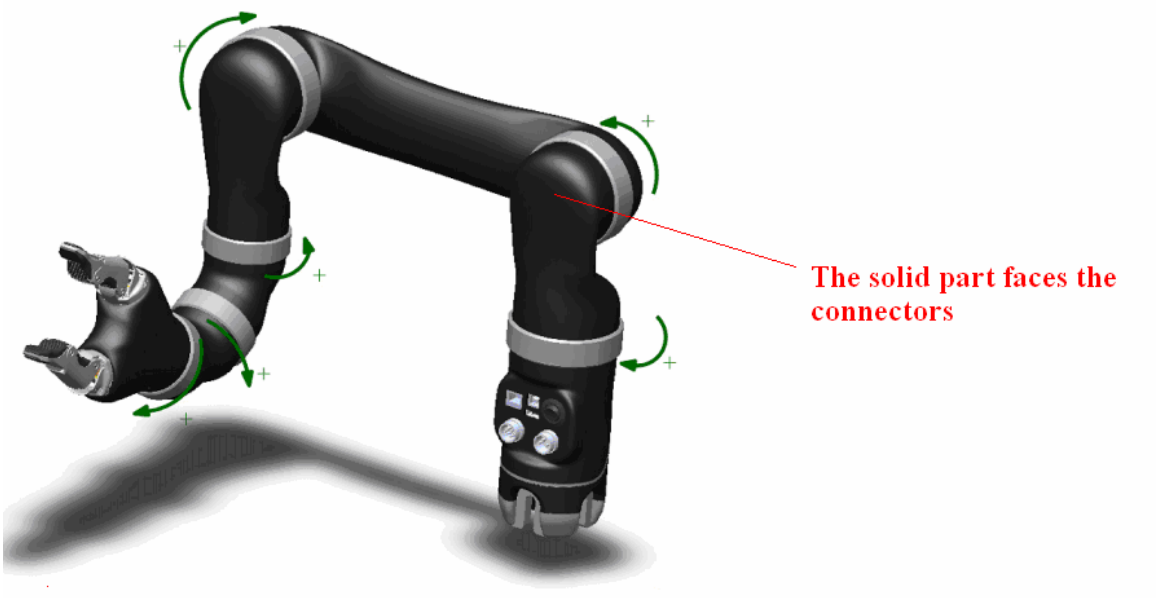


Figure 4 : Directions of each joint in the angular space of the robot

Joint 1



Joint 2

Must be vertical

Joint 3
Must be vertical

Joint 4 and Joint 5
If you face the connectors, going straight towards you.

Joint 6
If you face the connectors, the curved parts of the hand facing right.

Jacosoft
In Jacosoft, make sure the connection is established and then go on the Robotiscist tab. Place Mico at the good index position. You can move in angular mode (Jacosoft / Trajectory / Angular) to place the joints at the desired position. In the drop down list select the option “Reset zero position” or something similar. Click on Send To All. Reboot Mico. When restarted, make a ready (be cautious) and try the Cartesian. The Joystick will then make the robot move joint by joint.