Random recommendations:

→ If the robot is not responding, don't turn it off already.
(can still press Fault button, though)
let it run for a while (some minutes)
maybe a loose ETH cable is causing very slow communications,
and errors would show up after a long time.

→ Old iCubs CPU in head: there was no hard disk. It was remotely mounted using NFS (from server)
this means the code was shared with the server computer
⇒ only the server computer needed to be updated

→ yarprobotinterface is a bunch of threads of equal priority.
But transmission tasks need to be run with high priority
The new version in iCub-main/master fixes this
and offers better debug information w/ respect to it.

→ icub-main/master now handles R-T mode with high priority threads
for smoother transmission

→ iCub Nancy has "version 1" arms. Joints can be calibrated through similar files
as with green/purple, in robot-configuration
Calibration is done through matrix e 23 (e.g.) ⇒ motor encoder → joint
by setting the first 4 cols. = 1 4 ... and then ask Julien/Valentina.
(or changing delta if lazy)

N ISSUE
OCUMENTATION
Ⓧ YARP → strain embObjInertials embObjMAIS... ON
inertial sensors: OFF

dow w/
RAIN
.1
.3
.6 / 7
.8 / 8
FOC Boards don't keep update.

Boards with skin
, 2, 4 → force ETH maintenance.
Select 4. Discover.
..2 left arm
-4 right arm
11 right leg
10 left leg
Select all skins (tactile board)
Upload application → skin.hex
Ⓧ if not all at same version! Turn off motors. turn on. Wait.
ETH → Discover. ! when doing software updates in //,
casini may happen.
Better to do it one by one: upload application → skin.hex
(try selecting boards with non neighboring IP
BLACK MAGIC e.g. : 12 and .8, not .1 and .2)
for doing in //
} Repeat with 2, 11, (10)
already
test version
date.