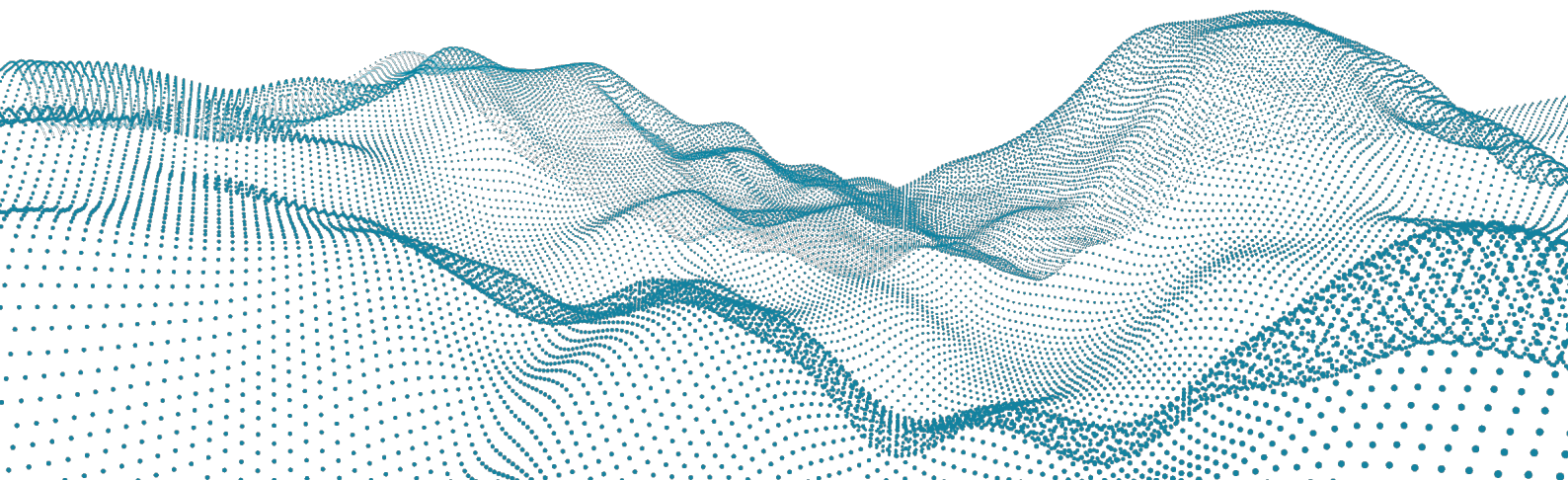




Roboception GmbH | July 2021

rc_visard 3D Stereo Sensor

FIRMWARE CHANGELOG



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1 21.07.0 (2021-07-21)

1.1 New Components

- OPC UA Server: New module that allows communicating with the rc_visard and the rc_visard via the [OPC UA](#) communication protocol.

The OPC UA Server is available as an Early Access preview feature. Please contact us if you would be interested in testing the OPC UA interface.

1.2 New Features

- add grasp sorting strategy selection to [ItemPick](#), [BoxPick](#) and [SilhouetteMatch](#)
- include grasps when downloading [SilhouetteMatch](#) templates
- LoadCarrier (rc_load_carrier):
 - add detection of gitter boxes/pallet cages by extending load carrier definition. This is available as an Early Access preview feature. Please contact us if you would be interested in testing this feature.
 - add pose_type to load carrier model to support [Exact Poses and Orientation Priors](#)
- WebGUI:
 - add 3D result visualization to [SilhouetteMatch](#)
 - add interactive Menus to all 3D visualizations with Controls and View Options

1.3 Improvements and Fixes

- persist parameters across [firmware updates](#)
- improve system ready notification at boot
- LoadCarrier (rc_load_carrier):
 - add snapshot dumps for last detection
- SilhouetteMatch (rc_silhouettematch):
 - fix bug that caused less object to be detected in some scenes
 - extend data included in snapshot dumps for last detection
- BoxPick (rc_boxpick):
 - improve detection with small dimension ranges
- ItemPick (rc_itempick):
 - fix segmentation for small clusters far away from camera
- WebGUI:
 - allow download of templates in [SilhouetteMatch](#)
 - new 3D orbiting control for unconstrained rotations
 - only show min distance warning if depth range is actually reduced
 - show hint if new rc_randomdot projector is connected
 - allow editing and deleting elements in Try-Out dropdowns
 - show if system requires a reboot when dongle is reconnected
- GEV server:
 - add ChunkLineStatus

1.4 Other Changes

- Grasps and load carriers are internally migrated to new storage format and not available any more if a rollback to a previous firmware version is performed. It is advised to create a [backup](#) before upgrading if a rollback might be desired.
- REST API:

- node status: rename `stale` to `idle` and add `initializing`
- IOControl [get_io_values service](#) changed to support varying number of IOs

1.5 Deprecations

- The `load_carrier` services and parameters in the `ItemPick`, `BoxPick` and `SilhouetteMatch` nodes are deprecated and will be removed in a future version. Please use the [services](#) and [parameters](#) provided by the `rc_load_carrier` module.

2 21.04.1 (2021-04-20)

2.1 Fixes

- network settings: fix check if IP is already in use when no route to given IP is available
- WebGUI:
 - fixed rotation of grid for `SilhouetteMatch` template visualization
 - only show full screen icons for depth images in continuous acquisition mode

3 21.04.0 (2021-04-15)

3.1 New Components

- [LoadCarrier](#) (`rc_load_carrier`): New module that allows setting and retrieving load carriers, as well as detecting load carriers and their filling levels.

The `LoadCarrier` module is an optional on-board module of the `rc_visard` and is licensed with any of the modules `ItemPick`, `BoxPick`, or `SilhouetteMatch`. Otherwise it requires a separate `LoadCarrier` license to be purchased.

3.2 New Features

- `SilhouetteMatch` (`rc_silhouettematch`):
 - add [check_collisions_with_matches](#) and [check_collisions_with_base_plane](#) parameters
- REST API:
 - add [backup/restore functionality](#) to download and upload the complete configuration of an `rc_visard`
- WebGUI:
 - organize modules into detection modules and configuration modules
 - add import/export of grasps for `SilhouetteMatch` templates
 - new `LoadCarrier` detection module
 - new `Regions of Interest` page for configuring regions of interest for all detection modules
 - add optional item maximum dimensions to `ItemPick` Try-Out section
 - add fullscreen control to images in stream view

3.3 Improvements and Fixes

- `LoadCarrier` (`rc_load_carrier`)
 - return estimated dimensions of detected load carriers
 - improve load carrier detection in low contrast scenes

- SilhouetteMatch (rc_silhouettematch):
 - grasp sorting combines orientation and distance to preferred orientation
 - allow collision check with all detectable objects
 - disambiguate equally good grasps for symmetric templates
 - enforce detection timeout of 5 seconds
- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - improve detection of small rectangles at large camera distances
 - added compartment to load carrier visualization
- REST API:
 - return object_uuid for SilhouetteMatch templates
- WebGUI:
 - allow up to 8 poses during Hand-Eye Calibration
 - moved Try-Out sections below image streams in all detection modules
 - add shortcuts to create Load Carriers, Regions of Interest and Grippers from the Try-Out section of all detection modules
 - show positions with four digit precision in detection result tables
 - show SilhouetteMatch 3D collision model when configuring grasps
 - show default values for all parameters in info boxes
 - ask if firmware update should be applied if filename indicates wrong image
 - show message if websocket connection is not available
 - also use port 80 for websocket
 - enforce max length of 60 characters for all IDs
 - show logs for EKI bridge
 - show why network setting could not be applied

4 21.01.0 (2021-01-29)

4.1 New Features

- BoxPick (rc_boxpick):
 - add prefer_splits parameter
- SilhouetteMatch (rc_silhouettematch):
 - collision check with other detected objects
- REST API:
 - UBJSON support, via application/ubjson mime type in Content-Type and/or Accept headers
- WebGUI:
 - Download last detection of ItemPick, BoxPick, SilhouetteMatch as tarball with visualization images

4.2 Improvements and Fixes

- ItemPick (rc_itempick):
 - improve segmentation of objects with dimensions and few 3D edges
- BoxPick (rc_boxpick):
 - improve box detection using confidence image for 2D edges as well
- Hand-Eye calibration (rc_hand_eye_calibration):
 - minimize geometric loop closure error instead of reprojection error and return more error values
- WebGUI:
 - downloadable JSON response of try-outs now matches full REST-API response
 - visualization image selection via dropdown

4.3 Other Changes

- REST-API:
 - return image version without device and 'v' prefix

5 20.11.0 (2020-11-23)

5.1 New Features

- SilhouetteMatch (rc_silhouettematch):
 - Add collision detection with base plane
- StereoMatching (rc_stereomatching):
 - New double_shot mode: Combine images from two subsequent stereo image pairs. This is meant for the use with a random-dot projector in ExposureAlternateActive or SingleFrameOut1 acquisition mode.
- Camera (rc_stereocamera):
 - New Out1High auto exposure mode: Adapt exposure time using only images with GPIO Out1 high. This is meant for the use with a random-dot projector in SingleFrameOut1 acquisition mode.
- WebGUI:
 - Japanese translation
 - Add snapshot download on depth image page (with disparity and pointcloud as ply)
 - Optionally show image that is actually used by stereo matching on depth image page
 - Download try-out requests as JSON

5.2 Improvements and Fixes

- BoxPick (rc_boxpick):
 - Fix missing detections in packed scenes
 - Also draw detected box in grasp visualization
- SilhouetteMatch (rc_silhouettematch):
 - Improve refinement
- Hand-Eye calibration (rc_hand_eye_calibration):
 - Service get_calibration strictly returns only saved result. Before it returned values of calibrate call, even if save_calibration was not called
 - Service set_calibration implicitly calls save_calibration
 - Extended collinearity check to ensure that positions are at least 3 mm apart from each other

5.3 Other Changes

- GigE Vision/GenICam:
 - add DepthDoubleShot feature
 - add Out1High to ExposureAuto enum
 - rename RcAdaptiveOut1Reduction to RcOut1Reduction

6 20.10.0 (2020-10-13)

6.1 New Features

- WebGUI:
 - 3D ROI visualization
 - simplified specification of grid size for calibration
- SilhouetteMatch (rc_silhouettematch):
 - added load carrier detection
 - added grasp point specification
 - integrated CollisionCheck module
- StereoMatching (rc_stereomatching):
 - smooth disparity interpolation
 - disparity border smoothing
- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - common loadcarrier and ROI dbs
- GigE Vision/GenICam:
 - add support for GevSCSP (stream channel source port) with fixed port 50010

6.2 Fixes

- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - updated grasp quality computation by taking distance into account

6.3 Other Changes

- Camera (rc_stereocamera):
 - set default for maximum exposure time to 18 ms
 - add parameters exp_auto_average_min and exp_auto_average_max for fine tuning of auto exposure
- StereoMatching (rc_stereomatching):
 - remove parameter disprange
 - remove parameter median
- IOControl (rc_iocontrol):
 - Set default of out1_mode to low
- GigE Vision/GenICam:
 - removed DepthMedian, DepthDispRange
 - add RcExposureAutoAverageMax and RcExposureAutoAverageMin
 - add DeviceLinkSpeed
 - minor updates and generic SFNC features

7 20.04.1 (2020-05-07)

7.1 Fixes

- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - fix ROI pose if external frame is used
 - fix rejection un-normalized input quaterions
 - set timestamp in response even if request is invalid
- TagDetect (rc_april_tag_detect and rc_qr_code_detect):
 - set timestamp in response even if request is invalid
 - always use full name for quality parameter (High, Medium, Low)
- SilhouetteMatch (rc_silhouettematch):
 - always use full name for quality parameter (High, Medium, Low)

- detect service: return -1 (invalid argument) if ROI offset is larger than image
- Hand-Eye calibration (rc_hand_eye_calibration):
 - re-compute calibration on calibrate service call if robot_mounted parameter changed
- REST API and Web GUI:
 - correctly report MAC and link speed even if no default gateway is set
 - show 'AdaptiveOut1 Reduction' value on camera page if this exposure mode is chosen
 - fix issues with floating image streams on Chrome

8 20.04.0 (2020-04-17)

8.1 New Features

- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - integrate new CollisionCheck module
 - add [load carrier filling level detection](#)
 - add load carrier overfilled flag
- SilhouetteMatch (rc_silhouette):
 - support [calibration to closest base plane](#) via new plane_preference parameter
- TagDetect (rc_april_tag_detect and rc_qr_code_detect):
 - add support for [external pose frame](#)
- Hand-Eye calibration (rc_hand_eye_calibration):
 - support calibration for robots with constrained motion, e.g. 4 DOF
 - add [set_calibration service](#) to re-upload calibration previously retrieved via get_calibration
- Camera:
 - add new [auto exposure mode AdaptiveOut1](#) that optimizes exposure for use with a projector
- Web GUI:
 - add [network configuration](#)
 - add download snapshot button on camera page
 - Try-out results can be downloaded as JSON file
 - show if device is not yet ready
- REST API:
 - add endpoints to change [network configuration](#)

8.2 Improvements and Fixes

- Stereo Matching (rc_stereomatching):
 - improvement of sub-pixel interpolation which reduces disparity steps
- Camera:
 - fixed auto-exposure flicker in full sunlight
- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - improve segmentation and box detection
 - increase maximum number of ROIs and load carriers to 50
 - increase maximum allowed load carrier dimensions to 2m

8.3 Other Changes

- rc_dynamics:
 - add return_code to get_cam2imu_transform service
- REST API:
 - improve error messages for invalid requests
 - new return_code values for adding elements, e.g. ROIs or load carriers:
 - * 10: element was added but max capacity is now reached

- * -10: new element could not be added because the capacity was exceeded

8.4 New Components

- CollisionCheck (rc_collision_check): This module provides an easy way to check if a gripper is in collision with a load carrier. It is integrated with the ItemPick and BoxPick modules, but can be used as standalone product. This feature is currently only available as part of the 3D-R Vision & Handling Set from our partner J. Schmalz GmbH.
 - documentation: <https://doc.rc-visard.com/latest/en/collisioncheck.html>
 - access via REST-API and EKI interface
 - configurable via Web GUI

9 1.8.4 (2020-01-24)

9.1 Fixes

- EKI bridge: on error return more useful return_code from corresponding module
- rc_stereomatching:
 - Reset image buffer for static mode on trigger or switching to single shot
- rc_stereocamera:
 - Fixed reporting of baseline in diagnostic messages

10 1.8.3 (2019-12-02)

10.1 Fixes

- SilhouetteMatch (rc_silhouettematch): increase data acquisition timeout to 5s
- rc_stereomatching: make acquisition_trigger service available again
- REST-API:
 - improve serialization error messages
 - return http code 400 if service call failed with invalid argument

11 1.8.2 (2019-11-19)

11.1 Fixes

- fix model name for color sensors

12 1.8.1 (2019-11-18)

12.1 Fixes

- EKI bridge: fix handling of empty lists
- SilhouetteMatch (rc_silhouettematch): performance improvements
- rc_stereocamera:

- Fixed error when choosing very small exposure region
- Only apply new signal masks for GPIO outputs if they differ from the previous ones, so that the alternate pattern is not interrupted
- Web GUI: fix flipped grid visualization thumbnails on hand-eye-calibration page

13 1.8.0 (2019-10-07)

13.1 New Components

- SilhouetteMatch (`rc_silhouettematch`): This module detects position and orientation of comparatively flat objects that are positioned on a plane, by matching the scene at hand to a previously taught template.
 - documentation: <https://doc.rc-visard.com/latest/en/silhouettematch.html>
 - shop: <https://roboception.com/product/silhouettematch/>
 - access via REST-API
 - configurable via Web GUI
- EKI bridge: The Ethernet KRL Interface (EKI Bridge) allows communicating with the `rc_visard` from KUKA KRL via `KUKA.EthernetKRL.XML`.
 - Use `rc_reason` onboard software with KUKA robots without any external PC
 - documentation: <https://doc.rc-visard.com/latest/en/eki.html>
 - shop: <https://roboception.com/product/ekibridge/>

13.2 New Features

- Web GUI:
 - Hand-eye calibration: allow redoing poses
- `rc_stereomatching`:
 - Add new acquisition mode `SingleFrameOut1`. This mode can be used to control an external projector. It sets the line source of `Out1` to `ExposureAlternateActive` upon each trigger and resets it to `Low` as soon as the images for stereo matching are grabbed. (Requires IOControl license)

13.3 Fixes

- ItemPick (`rc_itempick`):
 - bugfix for grasp computation on surfaces with holes
- GigE Vision/GenICam:
 - fix max `PayloadSize`

13.4 Other Changes

- REST-API:
 - `save_parameters` and `reset_defaults` return `return_code` instead of just message string

14 1.7.0 (2019-07-22)

14.1 New Features

- GigE Vision/GenICam:
 - add ChunkComponentIDValue according to SFNC 2.5
 - add ChunkDecimationHorizontal ChunkDecimationVertical
 - add ChunkLineSource and ChunkLineSelector
- ItemPick (rc_itempick):
 - sorting of grasps using gravity and size
 - accept lc and roi in camera pose_f frame even if request is for external
 - compute grasp quality from surface rmse
 - performance improvements

14.2 Fixes

- fix log rotation for nginx to prevent disk running full
- GigE Vision/GenICam:
 - fix Decimation and Width for depth images in Low res
 - also apply AcquisitionAlternateFilter for SynchronizedComponents except if it would result in no images being sent
- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - various small fixes/improvements

14.3 Other Changes

- rc_dynamics:
 - added state-machine state "STOPPING"
- REST-API:
 - possibility to add/delete multiple datastream destinations at once
- ItemPick (rc_itempick) and BoxPick (rc_boxpick):
 - made pose_f frame argument always required

15 1.6.1 (2019-04-01)

15.1 Fixes

- Web GUI:
 - fix for new BoxPick page

16 1.6.0 (2019-03-28)

16.1 New Components

- BoxPick (rc_boxpick): The optional on-board component of the rc_visard, which provides a perception solution for robotic pick-and-place applications such as de-/palletizing and sorting of packets. It allows the detection of stationary items with rectangular surfaces and the determination of their position, orientation and size for picking.
 - documentation: <https://doc.rc-visard.com/latest/en/boxpick.html>
 - shop: <https://roboception.com/product/boxpick/>
 - access via REST-API

- configurable via Web GUI

16.2 New Features

- Web GUI:
 - depth image: add single frame acquisition mode
 - page for new BoxPick component
- GigE Vision/GenICam:
 - add DecimationHorizontal and DecimationVertical as readonly features
 - report if system is ready (fully booted) via custom RcSystemReady feature

16.3 Fixes

- Web GUI:
 - Improve translation of labels and info boxes
 - Various fixes in region of interest modal
 - Fix race condition in hand-eye-calibration
- ItemPick (rc_itempick):
 - scale all pixel parameters with resolution
 - various fixes/improvements for corner cases

16.4 Other Changes

- Web GUI:
 - Add acquisition mode parameter to depth image page
 - ItemPick, BoxPick, TagDetect, QRDetect: Request new detection only, if last response has arrived.
 - Hand-Eye-Calibration replace error modal popup with error message under each pose
- REST-API:
 - warn if service request contains unused args
 - itempick RegionOfInterest: only return actually used type (box or sphere)
 - also lock service calls of rc_stereocamera, rc_stereomatching and rc_iocontrol if a GEV application is connected
- StereoPlus (rc_stereomatching):
 - enable smoothing by default
- ItemPick (rc_itempick):
 - deprecate item_model_tolerance parameter (now read-only)
- TagDetect (rc_april_tag_detect):
 - performance improvements
- SLAM (rc_slam):
 - improve map loading and resets/restarts

17 1.5.0 (2019-01-31)

17.1 New Features

- New Module: StereoPlus (rc_stereomatching):
 - disparity image smoothing (enabled via smooth parameter)
 - full resolution disparity image
- Web GUI:
 - add exposure region selection via mouse

- floating video streams
- new parameters for StereoPlus (full resolution and smoothing)
- allow deletion of hand-eye-calibration
- hand-eye-calibration page shows current sensor mounting

17.2 Fixes

- Web GUI:
 - several layout/UI improvements and fixes
 - Hide white balance settings on calibration page
 - ItemPick update streams shown only after detection
 - fix kuka pose format calculations
- rc_hand_eye_calibration:
 - If calibration error is NaN or Inf, return failure with status code 2 and a message
 - fix concurrency bug
- ItemPick (rc_itempick):
 - surface segmentation: fix return code when roi is empty
- GigE Vision/GenICam:
 - return correct baseline and focal_length_factor even before fully booted up
- IOControl
 - fix GPIO output when switching from active to low

17.3 Other Changes

- add baseline and color/monochrome version to model name, e.g. "rc_visard 160m"
- GigE Vision/GenICam:
 - add GenICam parameters for StereoPlus:
 - * add DepthSmooth (requires stereo_plus license)
 - * add Full quality (requires stereo_plus license)
 - * remove StaticHigh quality
 - * add DepthStaticScene parameter (replacing StaticHigh, but also works in Full)
 - remove GevTimestampControlReset
 - add and fix TimestampLatch and TimestampLatchValue (GEV counterparts are deprecated)
 - add DeviceFirmwareVersion (same as DeviceVersion for now)
 - add sent_frames, dropped_frames and packet_resends in REST-API status values
- SLAM (rc_slam):
 - add return_code in get_trajectory response
 - add number of map_frames in status values

18 1.4.0 (2018-10-19)

18.1 New Components

- ItemPick (rc_itempick): The optionally available software component provides an out-of-the-box and model-free perception solution for robotic pick-and-place applications with suction grippers.
 - documentation: <https://doc.rc-visard.com/latest/en/itempick.html>
 - access via REST-API
 - configurable via Web GUI

18.2 New Features

- Web GUI redesign:
 - additional modules pages:
 - * ItemPick
 - * AprilTag and QRCode Detect
 - * IOControl
 - camera page:
 - * set gain manually
 - * set white balance manually for color cameras
- GigE Vision/GenICam:
 - support for GigE Vision 2.1 MultiPart
 - add DepthAcquisitionMode and DepthAcquisitionTrigger
 - add SFNC 2.4 category PtpControl with
 - * PtpEnable
 - * PtpDataSetLatch
 - * PtpStatus
 - * PtpOffsetFromMaster
 - add AcquisitionMultiPartMode enum with
 - * SingleComponent: Immediately send one single component per frame/buffer when it becomes available.
 - * SynchronizedComponents: Only send a multipart frame/buffer iff all enabled components are available for that time.
- Improved auto exposure for reducing overexposure

18.3 Fixes

- REST-API:
 - return 400 error if parameter is out of min/max range
 - update Swagger UI to get correct cURL examples for Windows

18.4 Other Changes

- Web GUI:
 - removed French and Chinese translations

19 1.3.1 (2018-08-28)

19.1 Fixes

- REST-API:
 - fix error messages on service call failures (when some messages fields are of wrong type)
- GigE Vision/GenICam:
 - only reset block id when a new stream channel is opened
 - reduce latency on changing enabled components
- Web-GUI:
 - make doc links work in proxied environment

20 1.3.0 (2018-07-25)

20.1 New Components

- IO and projector control (`rc_iocontrol`): The optionally available software component allows read and write access to the `rc_visard`'s GPIOs, e.g. to synchronize with external pattern projectors.
 - documentation: <https://doc.rc-visard.com/latest/en/iocontrol.html>
 - access via REST-API
 - access via GigE Vision/GenICam interface:
 - * category: `DigitalIOControl`, features: `LineStatus`, `LineSource`, etc.
 - * custom `AcquisitionAlternateFilter` which makes it possible to receive only images with/without projector(`gpio`) on

20.2 New Features

- TagDetect (`rc_april_tag_detect` and `rc_qr_code_detect`):
 - add `detect_inverted_tags` parameter that allows detection of negative, i.e. black/white inverted QRcodes and AprilTags in front of black background.
 - possibility to specify approximate tag size to resolve ambiguous stereo tag matching
- GigE Vision/GenICam:
 - add support for setting exposure region:
 - * `ExposureRegionWidth`, `ExposureRegionHeight`, `ExposureRegionOffsetX`, `ExposureRegionOffsetY`
 - support extended chunk mode
 - new SFNC 2.4 features:
 - * `Scan3dFocalLegth`, `Scan3dBaseline`, `Scan3dPrincipalPointU`, `Scan3dPrincipalPointV`
- SLAM (`rc_slam`):
 - add services to persist and load onboard created maps (`save_map`, `load_map`, `remove_map`)

20.3 Other Changes

- `rc_stereomatching`:
 - remove `force_on` parameter from public interface
- `rc_itempick`:
 - add `clustering_max_surface_rmse` parameter
 - performance improvements

20.4 Fixes

- `rc_stereo_ins`:
 - fixed correction offsets in case of long vision outages
- `rc_april_tag_detect` and `rc_qr_code_detect`:
 - fix memory leak
 - improved matching between left and right image
- REST-API:
 - fix locking of service calls if module is not licensed
 - make log download work in tunneled/proxied environment
 - fix persistent storage of boolean parameters
- GigE Vision/GenICam:
 - fixes for better compatibility with some clients
 - some nodes like `PixelFormat`, `Width`, `Height` now correctly depend on `ComponentSelector`
 - `DeviceVersion`: report image version instead of `rc_gev_server` version

21 1.2.1 (2018-05-04)

21.1 Changes

- rc_gev_server:
 - add packet_size to status values in REST-API

21.2 Fixes

- rc_slam:
 - fixed map localization
 - fixed various internal issues
 - do "restart" when "start"ed in HALTED, so the internal state is cleared.
- rc_stereo_ins and rc_dynamics
 - fixes for communication timeouts
 - Use start on SLAM, not always restart (which drops the map)
- GigE Vision/GenICam:
 - fix race on (un)subscribing to images on heartbeat timeout
- REST-API:
 - fix loading of saved boolean parameters at startup

22 1.2.0.1 (2018-04-05)

22.1 Fixes

- rc_itempick:
 - Make sure that the grasp z-axis points into item (according to the camera z-axis)

23 1.2.0 (2018-03-29)

23.1 New components

- rc_itempick
- rc_april_tag_detection
- rc_qr_code_detection

23.2 Changes

- rc_hand_eye_calibration
 - add remove_calibration service

23.3 Fixes

- request NTP servers from DHCP
- rc_stereocalib
 - Force syncing of calibration files and images to disc
- Web GUI:

- show hand-eye calibration images again
- update chinese translation

24 1.1.1 (2018-02-22)

24.1 New Features

- rc_stereocamera:
 - added parameters to select a rectangular region used for calculating auto exposure:
 - * exp_offset_x, exp_offset_y, exp_width and exp_height

24.2 Changes

- rc_hand_eye_calibration:
 - provide robot_mounted bool with get_calibration service
- REST API:
 - include detailed info for all nodes (status, parameters, services) in log tarball
 - limit to 10 destinations per datastream

24.3 Fixes

- GigE Vision/GenICam:
 - immediately sync network settings to disk after changes
- Web GUI:
 - minor update to chinese translations
- fix switching of partitions via magic packet (via rcdiscover)
- improve system robustness under high load
- REST API:
 - fixes for ros service call response to API mappings
 - fix: correctly boot into new image if sensor is power-cycled immediately after update
- rc_stereo_ins:
 - fix initialization when camera doesn't see anything
 - improve robustness
- rc_slam:
 - autorecovery now also recovers the map
- rc_dynamics:
 - improve performance and robustness

25 1.1.0 (2018-01-19)

- Web GUI now also in French and Chinese
- new "producer" field in rc_dynamics_msgs Frame and Dynamics
- REST API:
 - fix bool parameters, actually return true/false and validate input correctly
- first release of SLAM
- rc_dynamics:
 - add start_slam, stop_slam, restart_slam services



rc_visard 3D Stereo Sensor

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