

# A Software to Accelerate Your Robotic Control Implementation

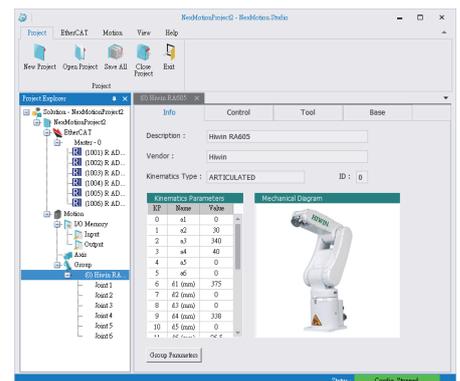
- ✓ Support eight common types of robots
- ✓ Provide a powerful configuration tool NexMotion Studio
- ✓ Provide a ready-to-use teach-pendant software NexTPUI



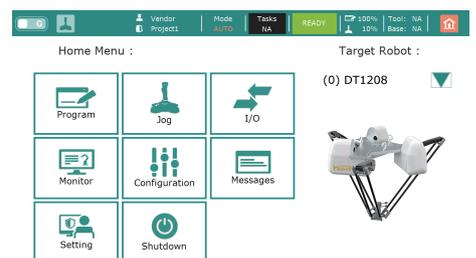
## Robot types NexGRC supported

Cartesian robot(2-6 axes)	Delta(3-axis/4-axis robot)	3RRR(3-axis robot)
6-axis collaborative robot	SCARA(4-axis robot)	6-axis robot(standard)
6-axis robot(deviation)	7-axis articulated robot	

## Debugging software

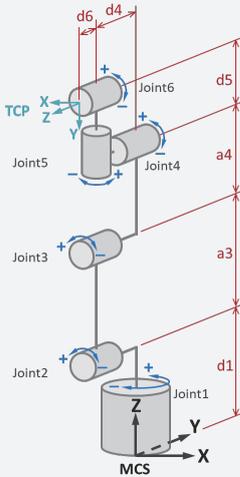


▲ NexMotion Studio  
Significantly shorten the setting time,  
it only takes 10 minutes from setting to controlling



▲ NexTPUI  
Designed for field applications,  
for robot calibration and programming

**New types of robots: ARU6 type, AR7 type, ARS6 type**

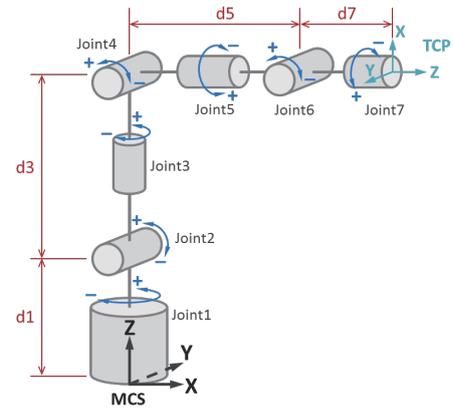


**▶ ARU6 type (6-axis collaborative robot)**

The motor mechanism configuration of ARU6 type is shown in the figure. This type of robot provides six degrees of freedom in three dimensions. Robots with this configuration are mostly collaborative such as Universal Robot or Techman robot.

**▶ AR7 type (7-axis articulated robot)**

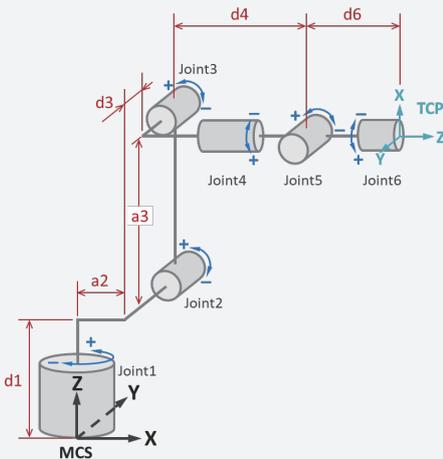
The motor mechanism configuration of AR7 type is shown in the figure. This type of robot provides six degrees and one redundant degree of freedom in three dimensions, which is suitable for working environments with narrow spaces and obstacles.



**▶ ARS6 type (6-axis articulated robot)**

The motor mechanism configuration and kinematic parameters of ARS6 type are shown in the figure. This type of robot provides six degrees of freedom in three dimensions. Differences between ARS6 and AR6 are:

1. Add side deviation ( $d_3$ ) that can be set between Joint1 and Joint2
  2. Remove the upward offset ( $a_3$ ) between Joint3 and Joint4
- Robot type for reference: Stäubli robot



**Ordering information**

- NexGRC (P/N:98ROBO000007)
- EtherCAT Robotic Control Software

**TPUI Online Manual**



**NRPL Online Manual**

