

MotoSim EG-VRC

ver. 2016SP2

OFFLINE PROGRAMMING | 3D SIMULATION | VIRTUAL ROBOT CONTROL

KEY BENEFITS

Offline programming of complex systems reduces robot downtime

Highly accurate simulation of advanced control capabilities between Motoman® robots and our industry-leading positioners

SYSTEM REQUIREMENTS

Recommended	Minimum
Windows® 10	Windows® 7
Intel Core i7 CPU	Intel Core i5 CPU
16 GB RAM	8 GB RAM
3D Pro graphics card	3D graphics card
5 GB of free hard drive space	

CONTROLLERS



YRC1000



DX200



DX100



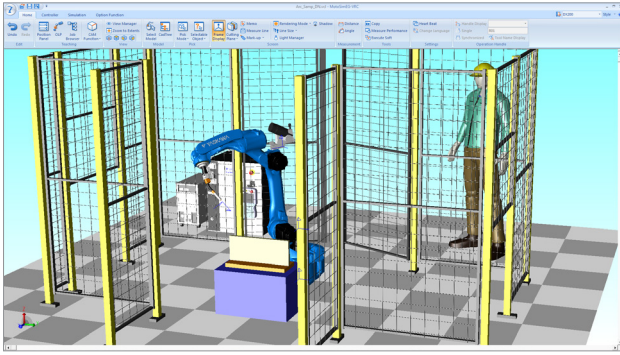
FS100



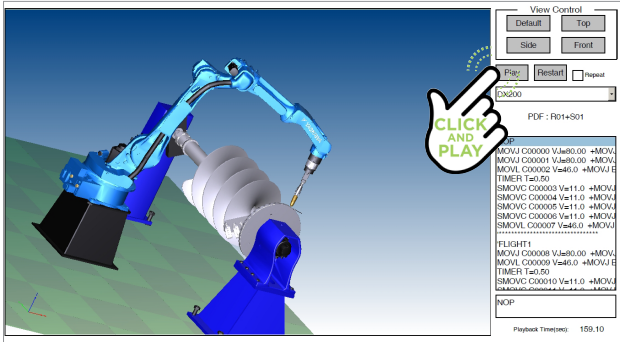
NX100

- Comprehensive software package that provides accurate 3D simulation of robot cells.
- Performs collision detection, reach analysis and cycle time calculations.
- Supports multiple process applications including arc and spot welding, cutting, handling, painting and sealing.
- This virtual robot controller displays the actual programming pendant interface; virtual programming steps are identical to those used in the real world.
- Supports standard INFORM programming language and completely simulates the controller software in the PC environment, including system configuration functions, condition file editing and FSU configuration.
- Easy-to-create 3D PDF and AVI files to view and share cell layouts or program operation. Viewing angle and start/stop playback of the robot program can be modified within the 3D PDF file.
- Offline programming and testing reduces programming time and increases production uptime:
 - Program new parts prior to production
 - Modify existing robot programs to increase efficiency and reduce cycle time
 - Detailed path calculation function plots robot's trajectory to simplify program verification
 - Programs created in MotoSim EG-VRC can be downloaded to the robot controller
- Offline cell design can minimize fixturing errors and reduce robot installation time:
 - Add markups and comments
 - Accurately measure distances
 - Create permanent measurement lines
 - Directly import 3D CAD files into MotoSim EG-VRC which eliminates need to convert files prior to import
- Utilize Yaskawa Motoman's model library or your own. Frequently used models can be dragged/dropped into a cell.

MotoSim EG-VRC

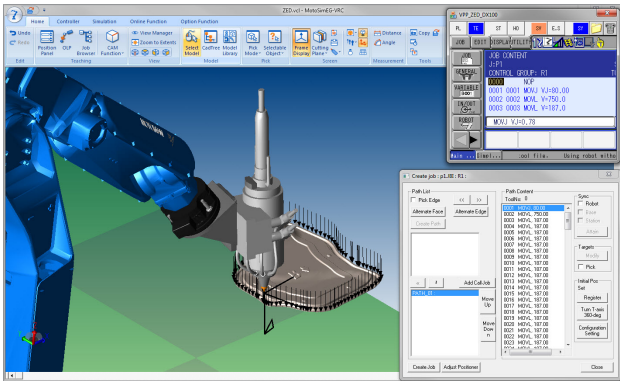


CELL LAYOUT AND DESIGN

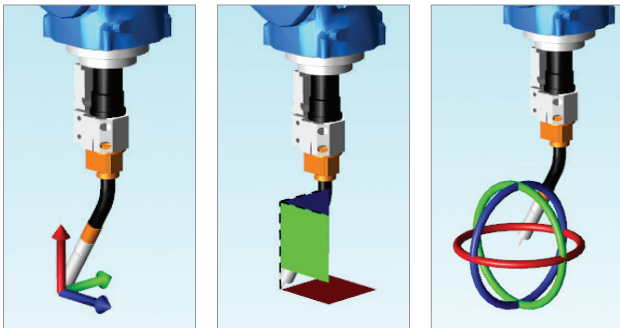


DOWNLOAD 3D PDF:

<http://www.motoman.com/motosim-3d/>



PATH GENERATION FROM 3D CAD MODEL (CAM)



TCP DRAG FUNCTION

CAPABILITIES

- Supports multi-robot and multi-controller simulation
- Robot(s) and external axes control, including independent/coordinated motion and twin synchronous motion functions
- 3D CAD file formats supported: IGES, STEP, Inventor, ProE/Creo, Solidworks, Catia V5, SAT, Parasolid, HSF, HMF, STL, 3DS, RWX, DXF and PLY
- Supports standard and optional controller functions such as Macro Command and Relative Job
- Component-level collision detection
- User-definable views
- Automatic robot path generation based on 3D CAD model information. Customizable to include application-specific instructions. Motion type, velocity, number of positions generated and work angle are adjustable. Generate numerous program positions in seconds!
- Modify robot position and manipulate each robot axis by dragging with the mouse. User can also position the robot in Cartesian mode.
- Accurately align models to one another:
 - Process tool or end effector to robot
 - Fixture to positioner
 - Part to fixture

YASKAWA

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