

One System, Zero Complexity, Unlimited Opportunities

Save integration time and simplify deployment
with our complete solution.



2FG7



2FG14



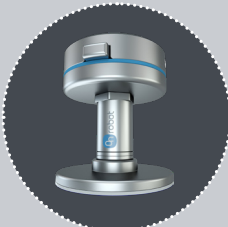
3FG15



3FG25



Soft Gripper



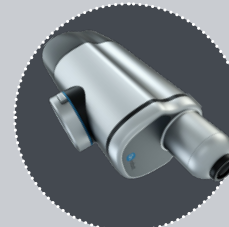
Gecko Gripper



VG10



OnRobot
Sander



OnRobot
Screwdriver



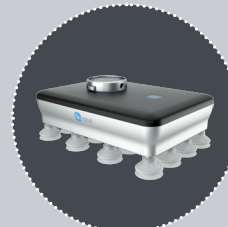
HEX



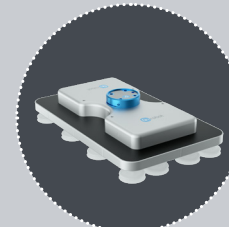
OnRobot Eyes



VGC10



VGP20



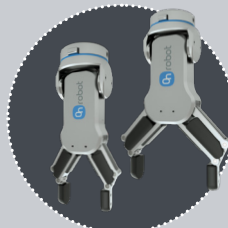
VGP30



2FGP20



Lift100



RG2/RG6



D:PLOY
CNC



D:PLOY
Palletizing



D:PLOY
Packaging



D:PLOY
Transferring

There are multiple ways to connect OnRobot products to FANUC robots - depending on the robot model and the specific tool being used. OnRobot's true value lies in offering a One-System, Zero-Complexity approach,

clearly setting us apart from other brands. Below are two illustrations and descriptions that show how our solutions work.

FANUC CR/LR

1. Mount the Gripper

Mount the adapter flange if applicable. Mount the OnRobot Quick Changer(QC). Attach the RG2/RG6 directly to the OnRobot QC.

2. Wiring

Connect the tool data cable between the QC and the Compute Box. Connect the ethernet communication cable between the robot controller and the Compute Box. Power supply the Compute Box.

3. Software installation

Setup the Compute Box. Set the robot IP address, as a Scanner or as an Adapter, map the signals. Upload the OnRobot functions to the robot.

4. Operation

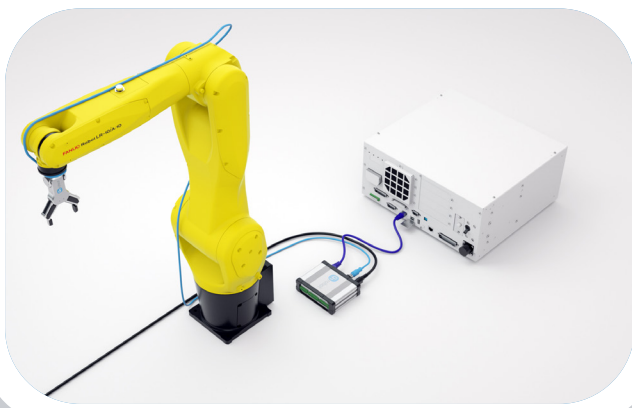
Use the functions installed.

RG2/6

Function	OR_RGX_MOVE(instance, width, force, wait)		
	Name	Type	Description
Input	instance	Integer	1: single or primary - in dual configuration 2: secondary in dual configuration
	width	Double	Define the desired opening in [mm].
	force	Double	Define the desired gripping force in [N].
	wait	Integer	0: return after command is executed (without waiting for execution to be complete) 1: return after fingers reached the position
Output	-	-	-
Behavior	Moves the fingers to the desired position.		
Example	:CALL OR_RGX_MOVE(1, 100, 40, 1);		

Function	OR_RGX_FTOFFSVAL(instance, fingertipOffset)		
	Name	Type	Description
Input	instance	Integer	1: single or primary - in dual configuration 2: secondary in dual configuration
	fingertipOffset	Double	Fingertip offset in [mm].
Output	-	-	-
Behavior	Sets the fingertip offset measured from the inside of the bare metal.		
Example	:CALL OR_RGX_FTOFFSVAL(1, 4.6);		

Function	OR_RGX_RESETPOWER(instance)		
	Name	Type	Description
Input	instance	Integer	1: single or primary - in dual configuration 2: secondary in dual configuration



FANUC CRX

1. Mount the Gripper

Mount the OnRobot QC, attach the RG2/RG6 directly to the OnRobot QC.

2. Wiring

Connect the QC to the robot M8 connector using the tool connector cable.

3. Software installation

Install Fanuc Plugin.

4. Operation

Use the functions installed with the Plugin.

