Realtime Controller Dedicated Linkage Function

Intelligent work such as assembly is controlled by a robot controller, and movement that autonomously avoids obstacles is a Realtime Controller. Robot operation is possible while switching between control and control.

Prepare a dedicated command as MELFA Library to easily set and control the Realtime Controller.

While controlling the Realtime Controller, the robot can be operated within the safe speed limit, making it easy to build a safety-friendly system.

Obstacle avoidance and advanced assembly system can be easily constructed by switching control rights.
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By controlling the Realtime Controller from the robot program (control right switching * 1), advanced positioning and assembly using vision and force sensors are performed by "MELFA control", and movement (interpolation) to the target position is performed by "MELFA control". Realable with "Realtime Controller Control"

Realtime Controller can be controlled by the same operation as MELFA. It is possible to stop / restart, change speed, etc. with the same operation feeling as a conventional robot. Easy programming and debugging can be realized because the program can be step-executed using the teaching box.

*1 "MELFA Library" will be provided for switching control rights between Realtime Controller and MELFA (robot controller). By using this MELFA library, programming and debugging time is greatly reduced.

The Realtime Controller dedicated linkage function is a function to easily realize "robot system construction" jointly developed with Realtime Robotics. Motion planning can significantly reduce design and start-up man-hours.
The safety speed monitoring function by the robot safety option is possible even during Realtime Controller control (always effective during MELFA control), realizing the construction of a safe robot system.

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