

	STANDARD	PRO
Features and Inclusions	<p>Reach Bravo 7-Function 300m Depth Rated Dexterous Manipulator with internal NVIDIA TX2</p> <p>Inclusions: Interlocking Quad Jaws</p> <p>Power Cable (1m, MCIL4F Female Connector to unterminated 4-core) Communication Cable (1m,MCIL8FE10 Female Connector to unterminated 8-core) RS485, RS232 and Ethernet Bench Test Interface Board 24V Power Adaptor (for your region) Reach Control Lite Software Integration and Operators Manuals Mounting Fasteners Hard Carry Case</p>	<p>Reach Bravo 7-Function 300m Depth Rated Dexterous Manipulator with internal NVIDIA TX2 and Pro Features and Inclusions</p> <p>Inclusions: Interlocking Quad Jaws Mission Tool Kit including: - Bravo External End-Effector Interfaceⁱ - Wide Quad Jaws - Parallel Jaws - Softline Cutter Wrist 1080p IP Cameraⁱⁱ Integrated Accessory Port Upgrade and Accessory Port Connectorⁱⁱⁱ Cartesian Control Engine^{iv} Collaborative Collision Avoidance Reach Control Pro^v Custom Control Interface (CCI) Enabled^{vi} CCI API including Communication Protocol and Software Developers Kit (SDK)^{vii} Research Datapack (including Hydro-Dynamic Model, Torque-Current Model, Denavit-Hartenberg Parameters)^{viii}</p> <p>Power Cable (1m, MCIL4F Female Connector to unterminated 4-core) Communication Cable (1m,MCIL8FE10 Female Connector to unterminated 8-core) RS485, RS232 and Ethernet Bench Test Interface Board 24V Power Adaptor (for your region) Reach Control Lite Software Integration and Operators Manuals Mounting Fasteners Hard Carry Case</p>

Feature Descriptions

ⁱ A mechanical interface to allow for attachment of external payloads instead of standard jaws. See more here: <https://blueprintlab.com/products/reach-bravo/>

ⁱⁱ A pencil-style Low-Light Operable 1080p IP camera attached to the wrist of the manipulator. Provided with an unterminated Impulse connector for vehicle integration.

ⁱⁱⁱ An attachment that provides access to power and communication at the end stage of the manipulator. Ideal for attachment of external sensors.

^{iv} A firmware engine enabling the ability to control the manipulator in Cartesian space in Global and End X,Y,Z co-ordinates.

^v See Reach Control Pro features and inclusions here: <https://blueprintlab.com/products/reach-control/>

^{vi} A firmware interface that enables the user to communicate directly with the manipulator control system, reading and sending data packets and implementing custom algorithms.

^{vii} A set of documentation required to interface with a Blueprint Lab manipulator, including example implementations.

^{viii} A set of research-grade data relating to the manipulator physical and control characteristics, allowing for the development of accurate models for simulation.