YASKAWA

MotoROS2

Interface between ROS 2 and Yaskawa Robots

Unlock the potential of Yaskawa robots with the power and flexibility of ROS 2!

ROS 2 (Robot Operating System 2) is a powerful collection of open-source software libraries and instruments that provide a flexible framework for the development and operation of robotics applications.

With MotoROS2, Yaskawa offers an interface to ROS 2 that seamlessly integrates various tools such as path planners, cameras, sensors, AI, debugging tools and community support.

This Yaskawa platform is designed to be easy to deploy, customize and operate.
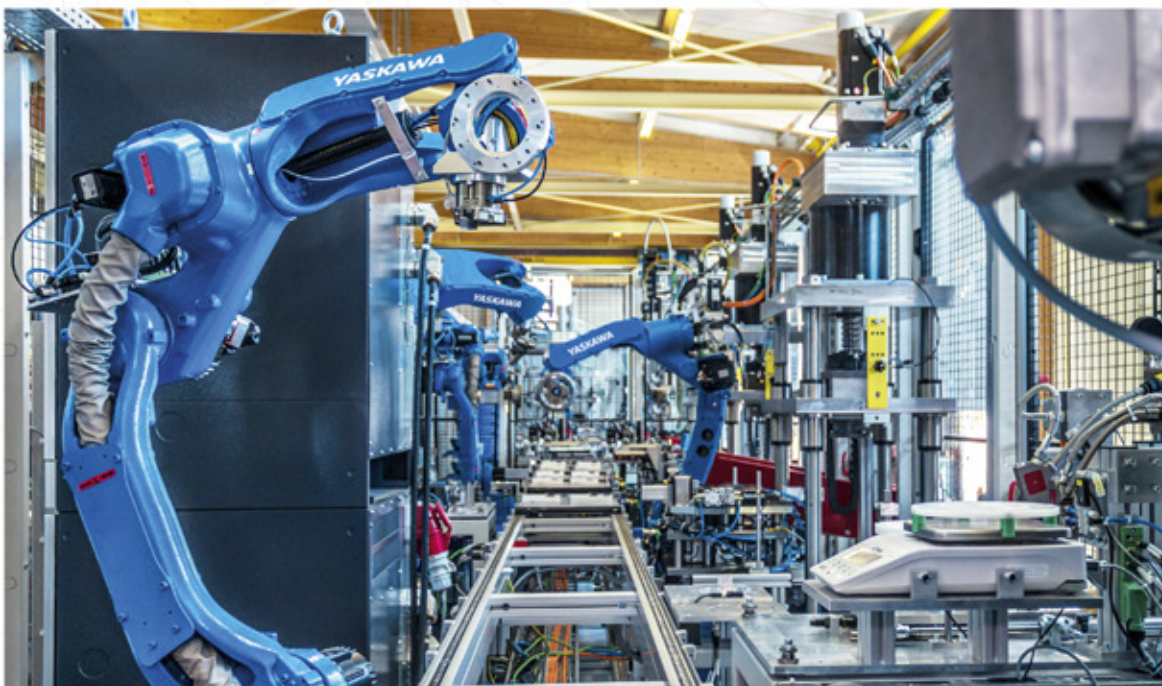
KEY BENEFITS

- Execution of pre-planned trajectories or building trajectories on the fly
- Support of up to 8 motion groups (motion groups are robots or positioner or external axis)
- Checking the robot status and its common states
- Reading and writing signals (input/output)
- Resetting / clearing error states
- Support through Yaskawa inhouse developer

Supported controller generations:

YRC1000

YRC1000 micro

DX200

HOW IT WORKS:

The Yaskawa Robot Controller is native ROS hardware on which MotoROS2 can be installed and operated.

Due to its hardware specifications, we use micro-ROS as the communication bridge between MotoROS2 and your ROS 2 application. Together with the motoros2_interfaces repository, MotoROS2 is all that's needed to allow a Yaskawa Robot Controller to be controlled by a ROS 2 application.
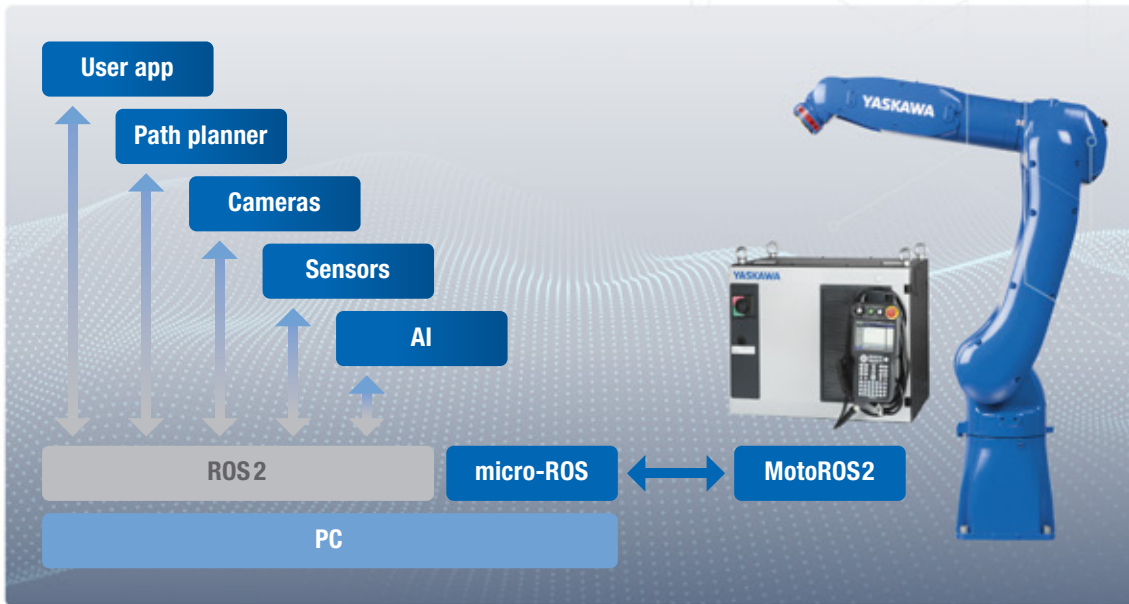
More information, repository and download at GitHub:
https://github.com/Yaskawa-Global/motoros2

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