

	STANDARD	PRO
<b>Features and Inclusions</b>	<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 <b>Pro Features and Inclusions</b></p> <p>Inclusions: Interlocking Quad Jaws <b>Mission Tool Kit including:</b> - <b>Bravo External End-Effector Interface<sup>i</sup></b> - <b>Wide Quad Jaws</b> - <b>Parallel Jaws</b> - <b>Softline Cutter</b> <b>Wrist 1080p IP Camera<sup>ii</sup></b> <b>Integrated Accessory Port Upgrade and Accessory Port Connector<sup>iii</sup></b> <b>Cartesian Control Engine<sup>iv</sup></b> <b>Reach Control Pro<sup>v</sup></b> <b>Custom Control Interface (CCI) Enabled<sup>vi</sup></b> <b>CCI API including Communication Protocol and Software Developers Kit (SDK)<sup>vii</sup></b> <b>Research Datapack (including Hydro-Dynamic Model, Torque-Current Model, Denavit-Hartenberg Parameters)<sup>viii</sup></b></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**

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

<sup>ii</sup> 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.

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

<sup>iv</sup> A firmware engine enabling the ability to control the manipulator in Cartesian space in Global and End X,Y,Z co-ordinates.

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

<sup>vi</sup> A firmware interface that enables the user to communicate directly with the manipulator control system, reading and sending data packets and implementing custom algorithms.

<sup>vii</sup> A set of documentation required to interface with a Blueprint Lab manipulator, including example implementations.

<sup>viii</sup> A set of research-grade data relating to the manipulator physical and control characteristics, allowing for the development of accurate models for simulation.