

# OnRobot Eyes

## Adding vision to robotic applications has never been easier



Robot wrist mount



External mount

### TECHNICAL SPECIFICATIONS

Camera Characteristics				Unit	
Interface	USB-C 3.x				
Output Resolution	1280 x 720			[px]	
Working distance	400-1000 [15.75 – 39.37]			mm [inch]	
Operating Temperature	0 – 35 [32 – 95]			°C [°F]	
IP rating	IP 54				
Weight	0.260 [0.57]			kg [lb]	
Eyes Features				Unit	
Type of vision system	2.5 D				
Minimum part size	10x10 or 15 diameter [0.39x0.39 or 0.59 diameter]			mm [inch]	
Applications Supported	Detection, Sorting, Inspection, Landmark				
Mounting options supported	Robot and External				
Reconfigurability when Robot mounted	12 configurations (4 x 3)				
	Around robot's flange	Tilt orientations			
	0 - 90 - 180 - 270	0 - 45 - 90		[degrees]	
Detection Repeatability	< 2 [< 0.078]			mm [inch]	
Detection Accuracy (typical) measured at 500 mm	External Mount		Robot Mount		
	2 [0.078]		2 [0.078]	mm [inch]	
Minimum Inspection Defect Size	5 [0.197]			mm [inch]	
Landmark accuracy **	Waypoint distance from Landmark	Minimum error	Typical error	Maximum error	
	200 [7.874]	0.2635 [0.0104]	0.6596 [0.0260]	0.9500 [0.0374]	mm [inch]
	500 [19.68]	0.6586 [0.0259]	1.6490 [0.0649]	2.3750 [0.0935]	mm [inch]
	1000 [39.37]	1.3173 [0.0519]	3.2981 [0.1298]	4.7500 [0.1870]	mm [inch]

## POWER UP PRODUCTION

- Adding vision to robotic applications has never been easier, with one-picture calibration, fast programming and seamless gripper integration
- Flexible, adaptable vision system with on-robot or external mounting is ideal for almost any collaborative application
- Affordable, efficient 2.5D vision offers depth perception for varying heights or stacked objects
- Easily sort, pick and place unstructured applications with high reliability using any robot arm
- One-shot detection for multiple objects minimizes cycle time
- Inspect objects using color and contour detection — with or without a robot, and ensure consistent quality
- Automatic landmark enables dynamic working environments and mobile robot setups