MANIPULATOR DATA FORM

Date:
Company:
Industry branch:
Address:
First name:
Last name:
Phone:
E-mail:

Description of carried load:

1. Type of load:
2. Shape:
3. Type of load surface: smooth rugged dry wet
   irregular dusty rusty oily
   temperature: °C
   other remarks:
4. Is the load air permeable? ○ YES ○ NO
5. Is the load solid (non-deformable)? ○ YES ○ NO
6. Approximate size of carried load:

a) length:	max:	mm	min:	mm
b) width:	max:	mm	min:	mm
c) height:	max:	mm	min:	mm
d) diameter:	max:	mm	min:	mm
e) weight:	max:	kg	min:	kg
f) lifting height:	max:	mm	min:	mm

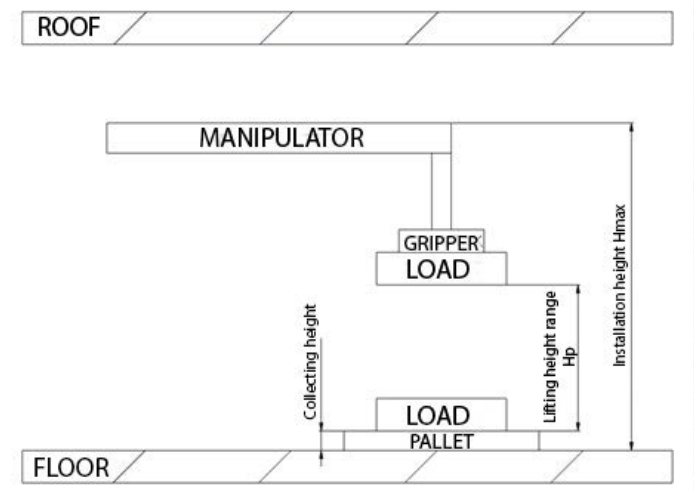
7. Proposed method of gripping:
   vacuum system mechanical manual mechanical with drive

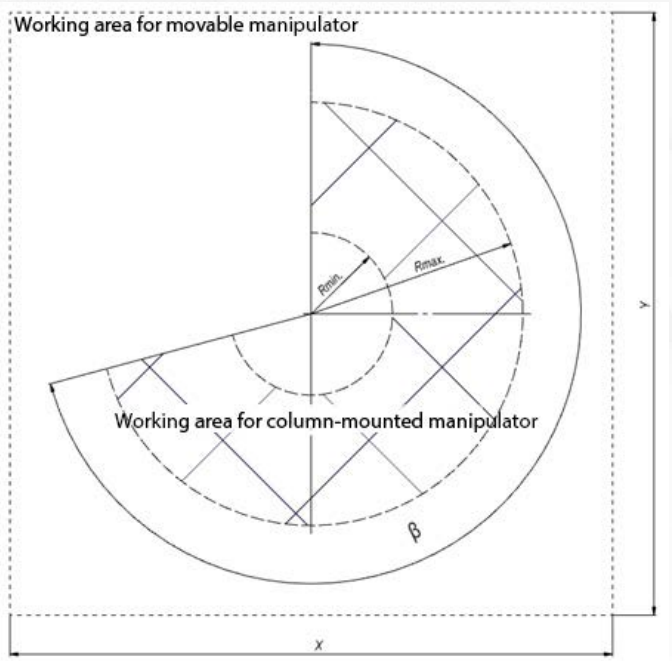
Description of working cycle:

8. Current way of carrying out the process cycle:

9. Description of individual concept of manipulator operation:

10. Working area parameters:





roof height: mm

installation height H_{max}: mm

collecting height: mm

lifting height range H_p: mm

dimension X (ref. movable type): mm

dimension Y (ref. movable type): mm

minimal radius range R_{min}: mm

maximal radius range R_{max}: mm

angle of rotation in column's axis β: °

11. Load makes following movement:

horizontally — rotation in horizontal surface 90°

vertically — rotation in vertical surface 180°

other:

12. How precisely the load shall be put down:

13. Expected performance (time of cycle):

Conditions of manipulator's installation:

14. Place of installation: outside | outside under roof | inside the building

15. Type of manipulator's mounting:

column-mounted stationary | suspended stationary

wall-mounted stationary | suspended movable

other:

16. Layout of working area (spatial conditions, collision areas/elements, description of load collection and putting down area):

17. Available utilities:

18. Device operating conditions referring to anticorrosive protection:

temperature:: min: °C max °C

dust: ◯ YES ◯ NO

corrosive environment: ◯ YES ◯ NO

19. Other special conditions:

Additional requirements:

20. Required delivery time of manipulator:

21. Remaining information: