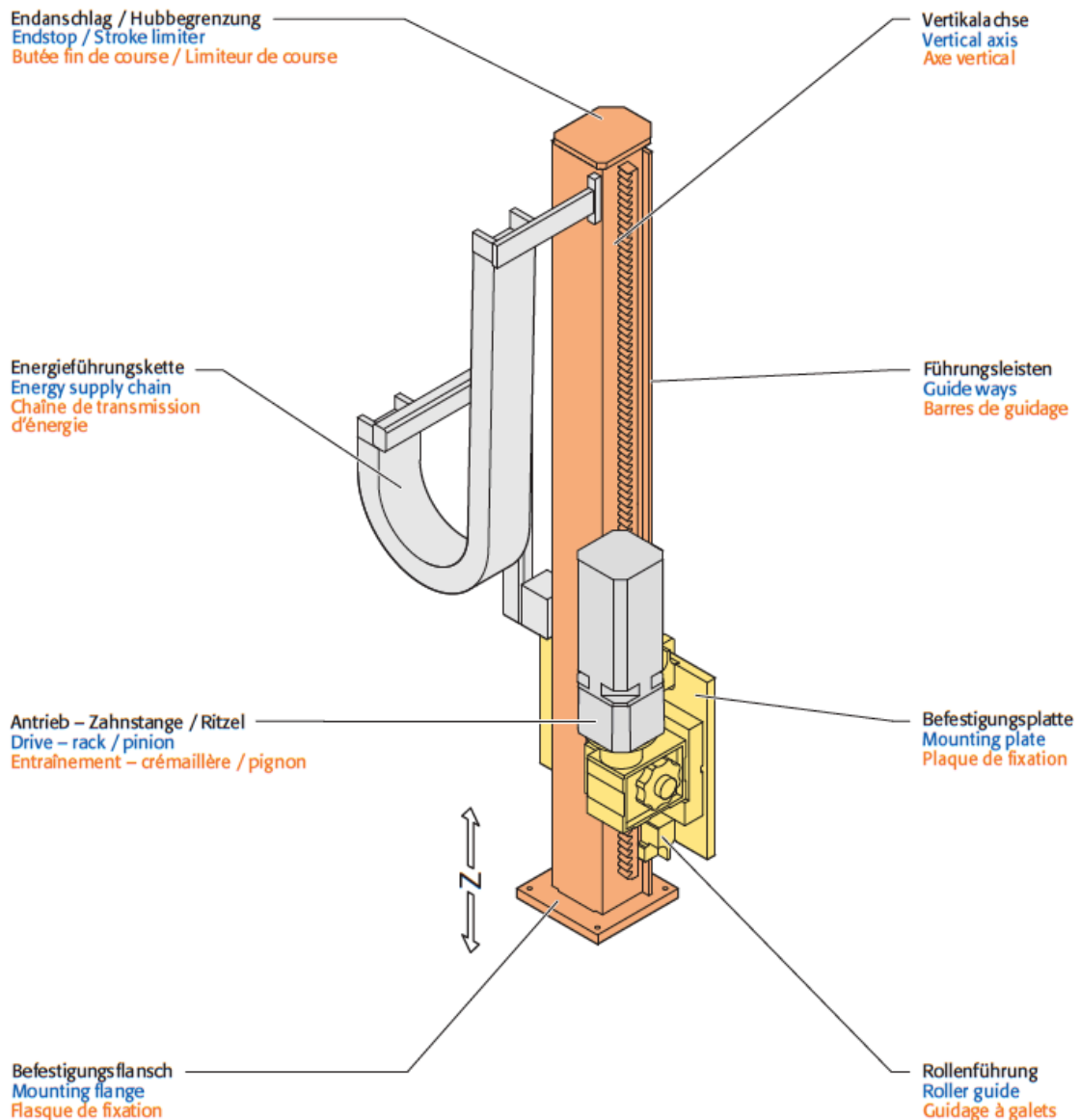


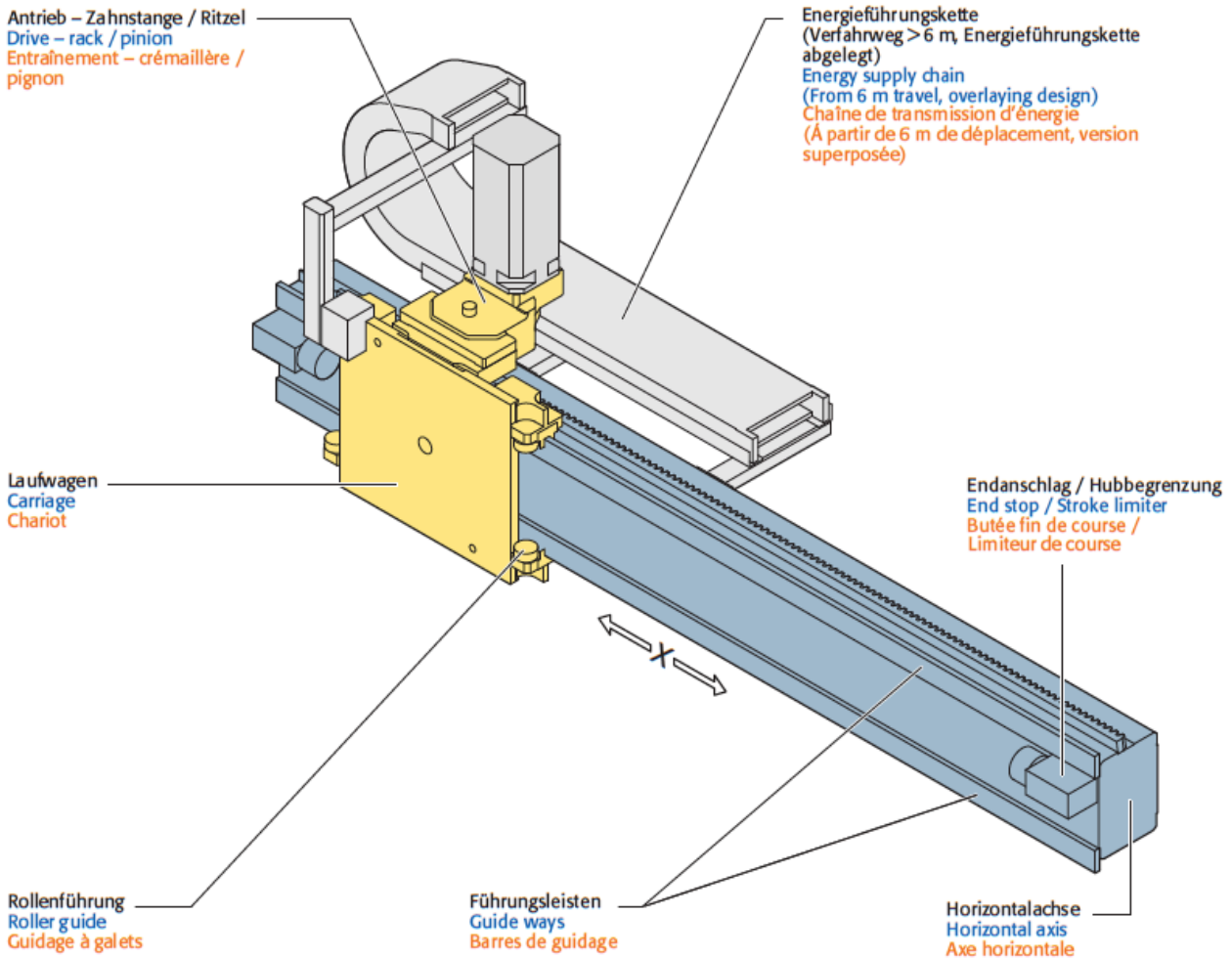


Allgemeine Beschreibung – Linearachse, vertikal, Typ
General description – Linear axis, vertical, Type
Description générale – Axes linéaires verticaux Type

LV



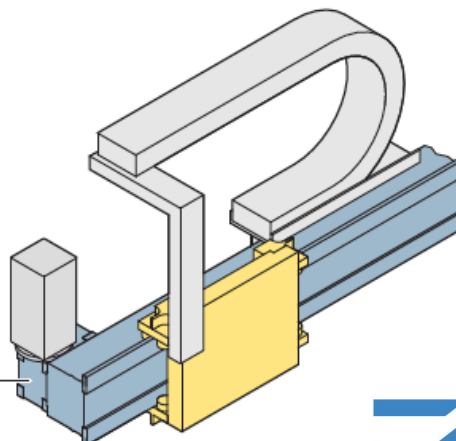
Allgemeine Beschreibung – Linearachse, horizontal, Typ
 General description – Linear axis, horizontal, Type
 Description générale – Axes linéaires horizontal Type



Antriebsvariante
 Drive variant
 Alternative entraînement

Baugröße LH 1/LH 2
 Size LH 1/LH 2
 Taille LH 1/LH 2

Zahnriementrieb
 Toothed belt drive
 Entraînement courroie dentée

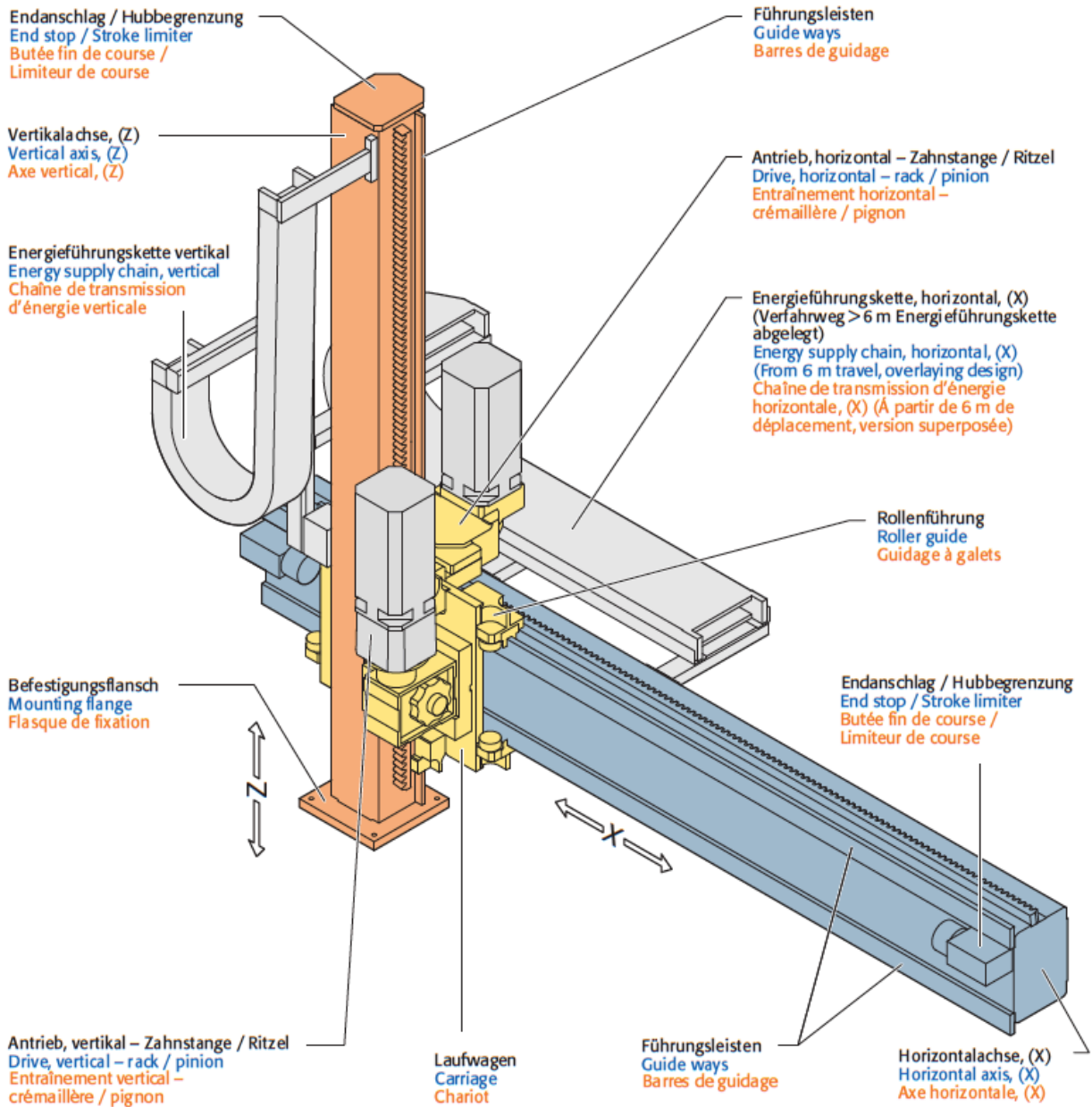


EK roboter®



Allgemeine Beschreibung – Kreuzlaufwagen, Typ
 General description – Cross carriage, Type
 Description générale – Chariot croisé Type

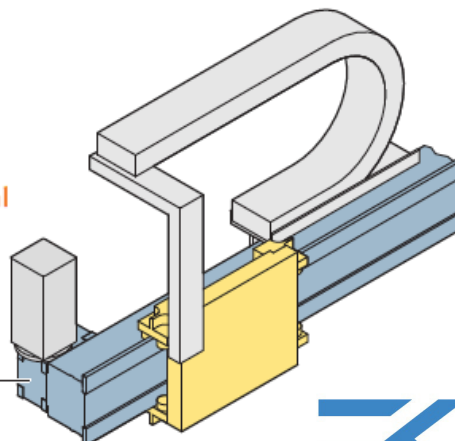
KL



Antriebsvariante, horizontal
 Drive variant, horizontal
 Alternative entraînement horizontal

Baugröße KL 1/ KL 2
 Size KL 1/ KL 2
 Taille KL 1/ KL 2

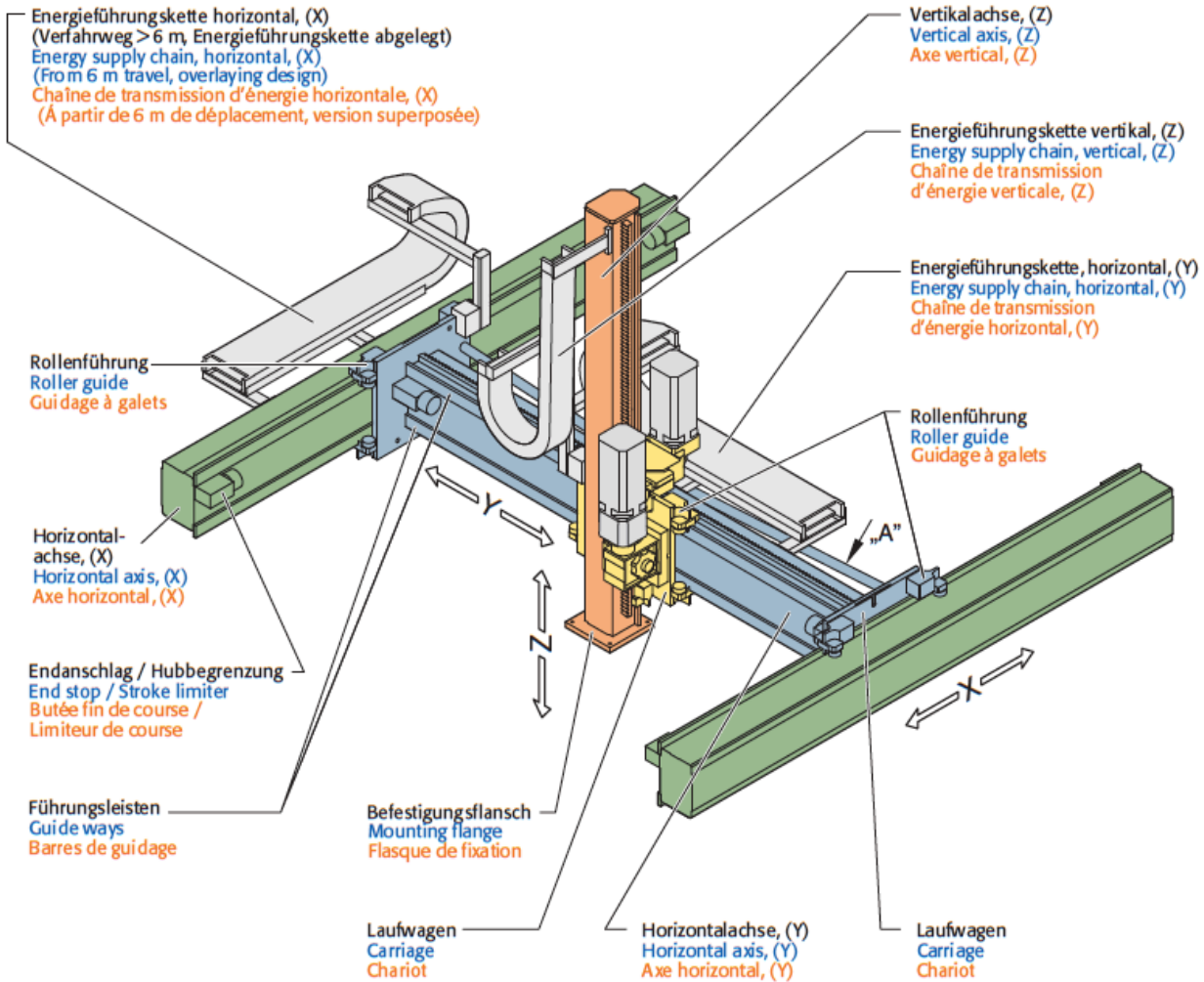
Zahnriementrieb
 Toothed belt drive
 Entraînement courroie dentée



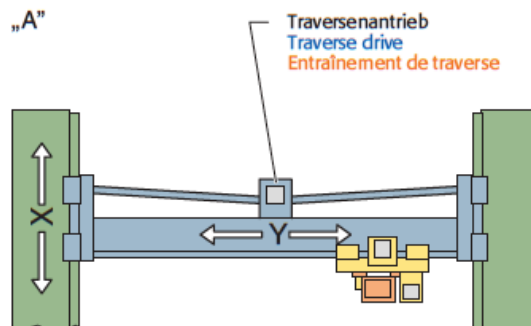
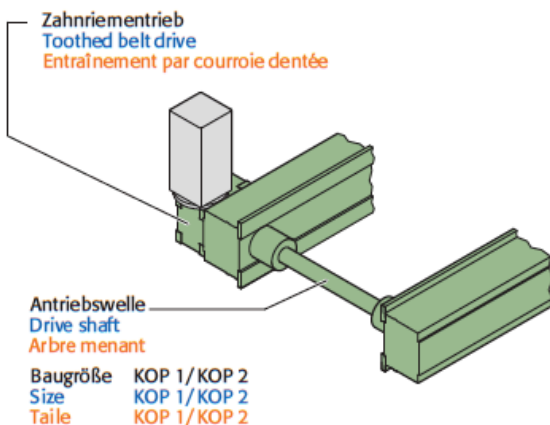
5.1.18.0104.2



Allgemeine Beschreibung – Portalroboter, Typ
 General description – Gantry robot, Type
 Description générale – Robot à portique Type



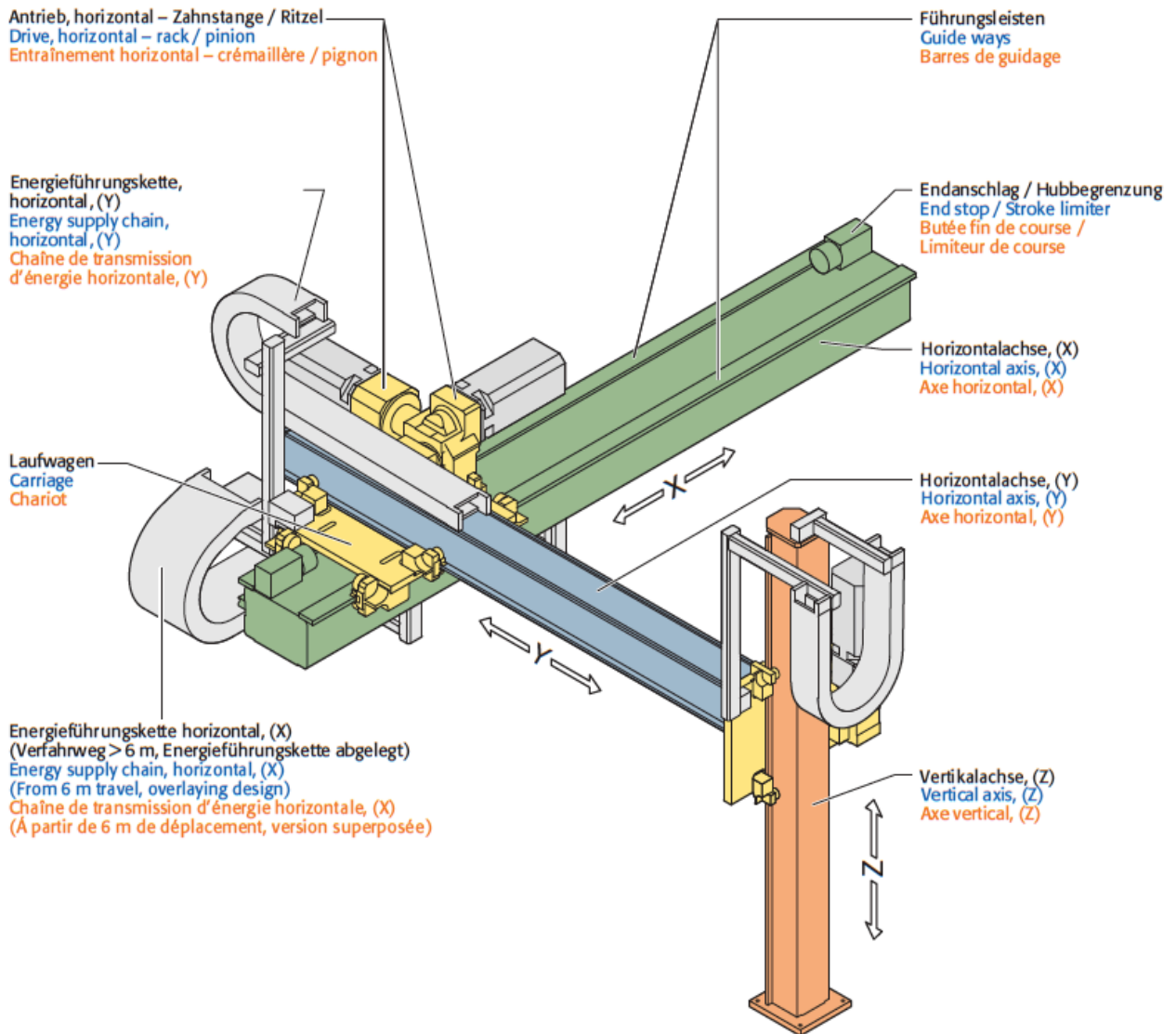
Antriebsvariante, X-Achse
 Drive variant, X-Axis
 Alternative entraînement, X-Axe





Allgemeine Beschreibung – Portalroboter mit Ausleger, Typ
General description – Gantry robot with cantilever, Type
Description générale – Robot à portique avec cantilever, Type

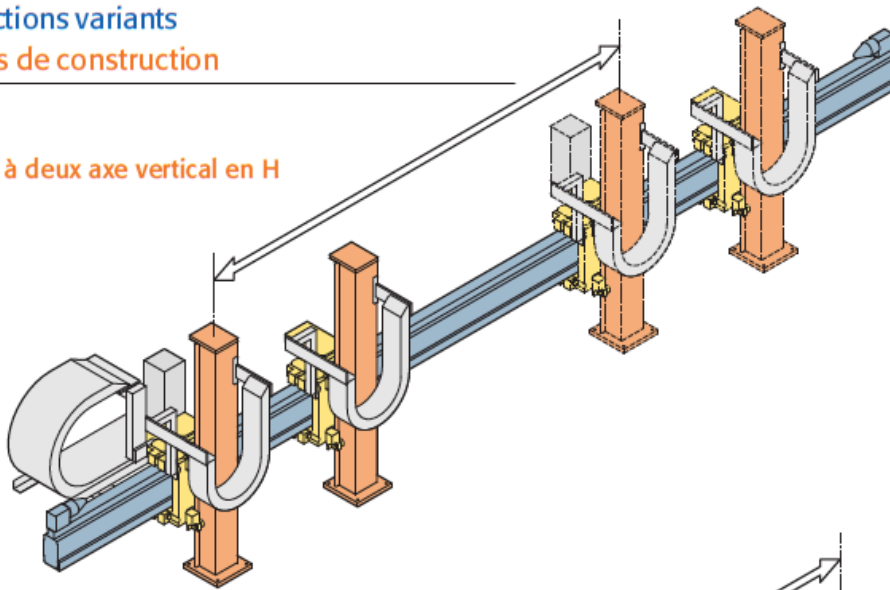
KOA



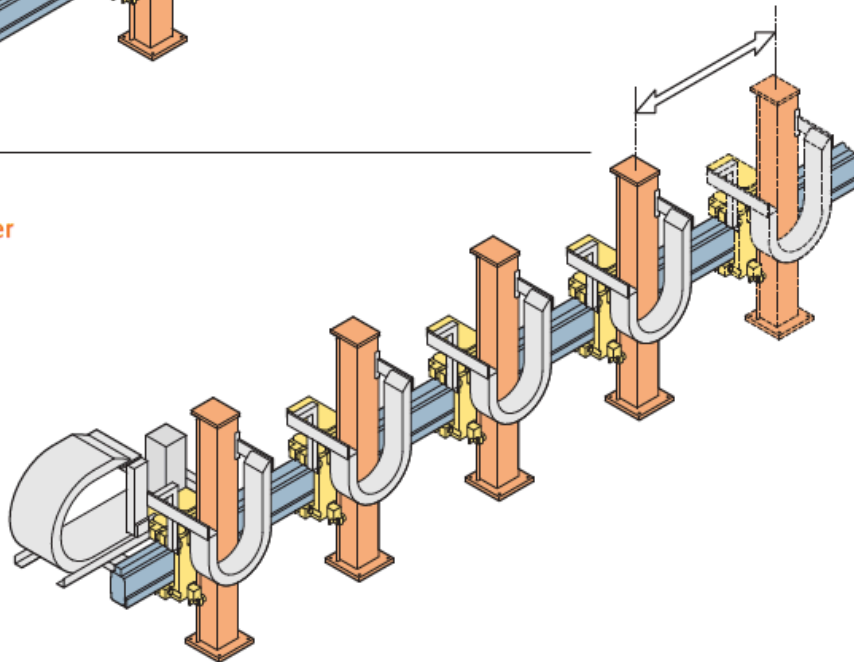
Ausführungsvarianten
Constructions variants
Variantes de construction



H-Lader
H-Loader
Portiques à deux axe vertical en H



Obertransfer
Transfer gantry
Portique transfer



Einzeln fahrende Laufwagen
Gantry system with independent moving carriages
Portique avec chariots à mouvement indépendant

