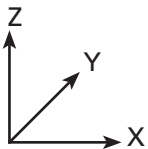


Enquiry systems + controllers

Company: Customer code:
Address: Location:
Telephone: Telefax:
Contact person: E-Mail:
Notes:
.....
Sketch:



Max. admissible load on the guide table N

Axes travel speed: x-axis: $v_x = \dots\dots\dots$ m/min.
 y-axis: $v_y = \dots\dots\dots$ m/min.
 z-axis: $v_z = \dots\dots\dots$ m/min.

Min. axes acceleration: x-axis: $t_x = \dots\dots\dots$ sec.
 y-axis: $t_y = \dots\dots\dots$ sec.
 z-axis: $t_z = \dots\dots\dots$ sec.

Axes travel: x-axis: $h_x = \dots\dots\dots$ mm
 y-axis: $h_y = \dots\dots\dots$ mm
 z-axis: $h_z = \dots\dots\dots$ mm

Controller/motor: yes no

Drag change: yes no

Underframe: yes (Skizze) no

Position accuracy: mm

Ambient conditions:

Type of driven is known: yes no
 3 phase motor with frequency converter
 step motor + controller servo motor + controller

Position control: yes no

Independent program flow in the motor powerstack yes no

Control with PLC by means of: in/output
 fieldbus: type.....
 puls/direction

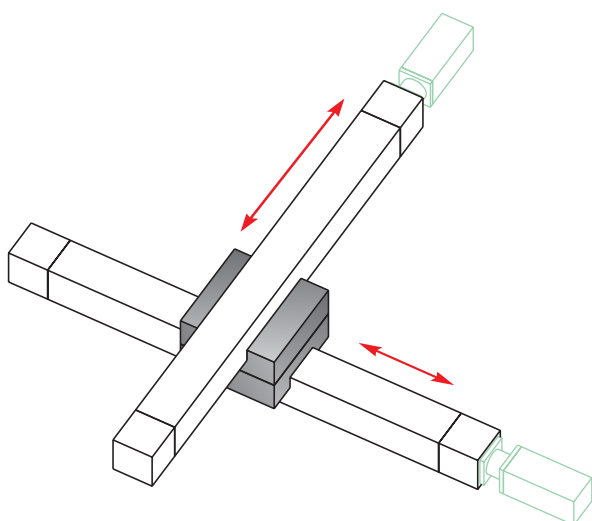
Requested number of travels max.cycle time: sec.
Length of the cable between motor and controller: m.

Application examples

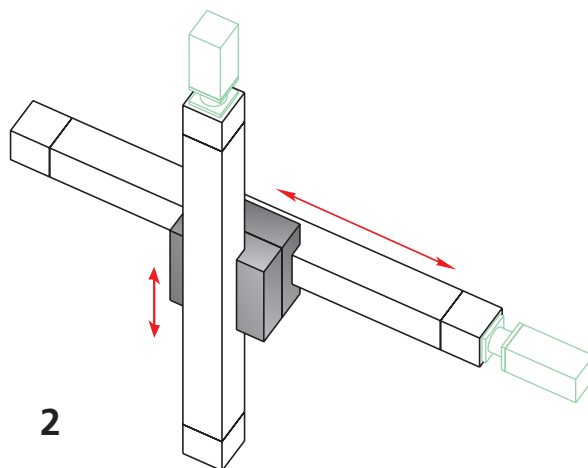
You can use the numbers instead of the scetch.

↔ Profile moving direction

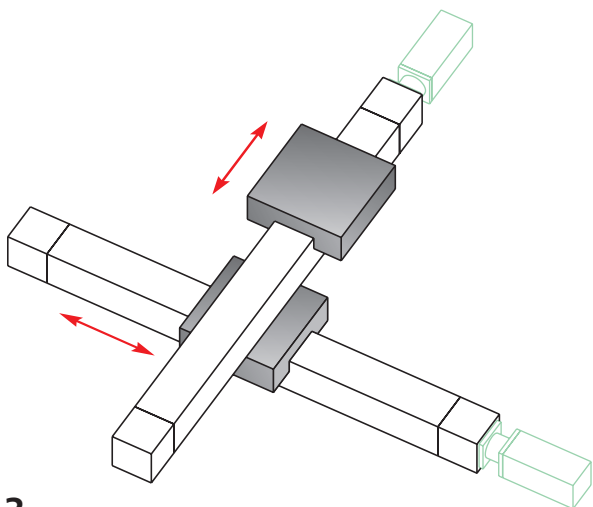
↔ Table moving direction



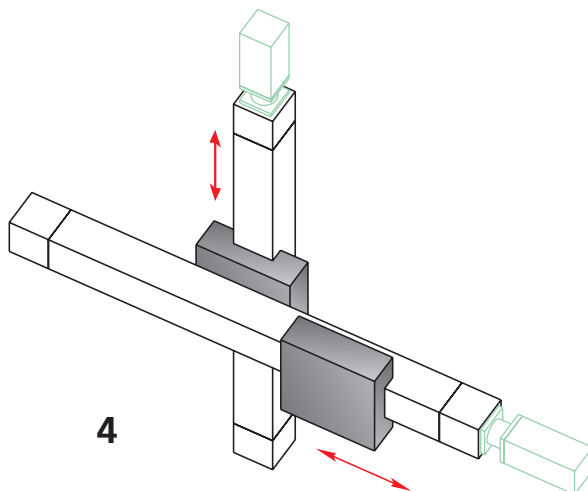
1



2



3



4

