DENSO Robotics Europe I DENSO EUROPE B.V.
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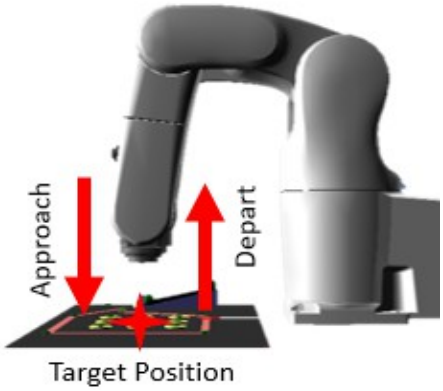
Simulation Request

Customer/Contact Details:	**Reference No.:**		**Date:**
Company		**Contact Person**	
Phone number		**Email**	
Simulation Details:		Simulation needs to be done until:	
Mounting	☐ Floor	☐ Wall	☐ Overhead
	Note: Not all robots can be mounted in each direction!		
Payload	**Tool:** g	**Part:** g	**Total:** g
Center of Gravity	**X:** mm	**Y:** mm	**Z:** mm
Product Handling	☐ Vacuum ☐ Gripper	**Grip:** ms	**Release:** ms
Pre-positioning	Pick Position	Accuracy: mm	
	Approach: mm	**Depart:** mm	
	Place Position	Accuracy: mm	
	Approach: mm	**Depart:** mm	
	Note: **Approach defines the distance the robot should move above the target position.**  **Depart defines the distance the robot should move above after target position has been reached.**		
Cycle Time	**Sec per Part:** s	**Parts per minute:** pcs/min	
CAD Data	☐ Application	☐ Gripper	

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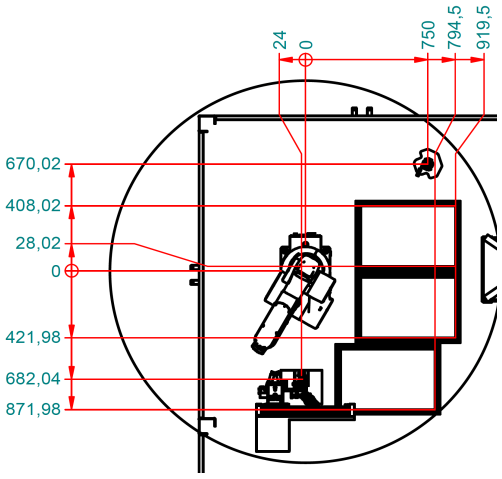
Workflow	No	Position (in mm)			Description
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	
		X:	Y:	Z:	
		Angle:		Degree	

Note:



Please specify the gripping and transition points based on the origin of the coordinate system being in the center of the robot base.