

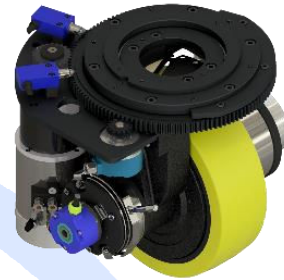
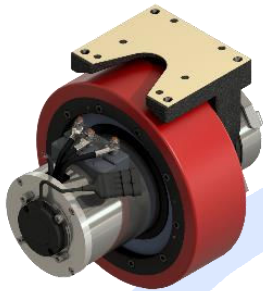
Company Name: _____ Country: _____
 E-mail: _____ Telephone: _____
 Main contact: _____

DRIVE WHEEL APPLICATION FORM

Horizontal

Without steering system

With electrical steering system

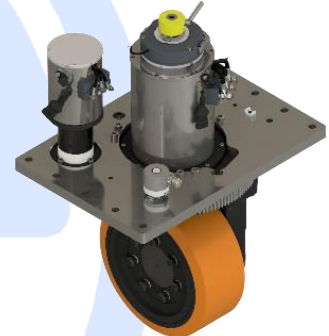


Vertical

Steering by tiller hand

With steering no plate

With electrical steering system



Vehicle type: _____ Nr of wheel drives: _____ Nr of swivel carters: _____
 Floor surface: _____
 Wheel diameter [mm]: _____ Wheel material: _____
 Traction motor: AC DC PMAC Voltage: _____
 Steering motor: AC DC PMAC Voltage: _____
 Integrated sensor if PMAC: Sin/Cos Incremental encoder + Hall cells Resolver
 Ambient temperature: Min _____ °C Max _____ °C Humidity level [%]: _____

	Vehicle only	Vehicle and Load
Vehicle weight [kg]:		
Max radial wheel load [kg]:		
Max climbing slope [%]:		
Max speed on flat [km/h]:		
Max speed on slope [km/h]:		
Acceleration [m/s ²]:		
Duty cycle:	Number of shifts [1, 2, 3]: _____	Service [%]: _____
	Service time [min]: _____	Resting time [min]: _____

E/m brake voltage: _____ E/m brake release lever: Yes No
 Thermal sensor: Yes No Steering limit switches: Yes No
 Steering with stopped vehicle: Yes No Mechanical stop: Yes No

Plan:

Prototype Q.ty: _____ Series Q.ty: _____ / year

Only predisposition for encoder mounting

Shaft diameter: _____ mm Shaft lenght: _____ mm

Traction motor encoder

Absolute

Monoturn Multiturn

Fieldbus interfaces

Profibus Profinet CANopen DeviceNet

Connection

Connector Cable glands

Serial interfaces

SSI EnDat2.2

Connection

Connector Cable glands

Incremental

Number of pulse per revolution: _____ ppr

Power supply

5 Vdc 9-30 Vdc

Output signal

TTL HTL

Connection

Connector Cable

Steering motor encoder

Absolute

Monoturn Multiturn

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Any other information about the project:

Lined area for providing additional information about the project. A large, faint watermark of the Metalrota logo is visible in the center of the page.