

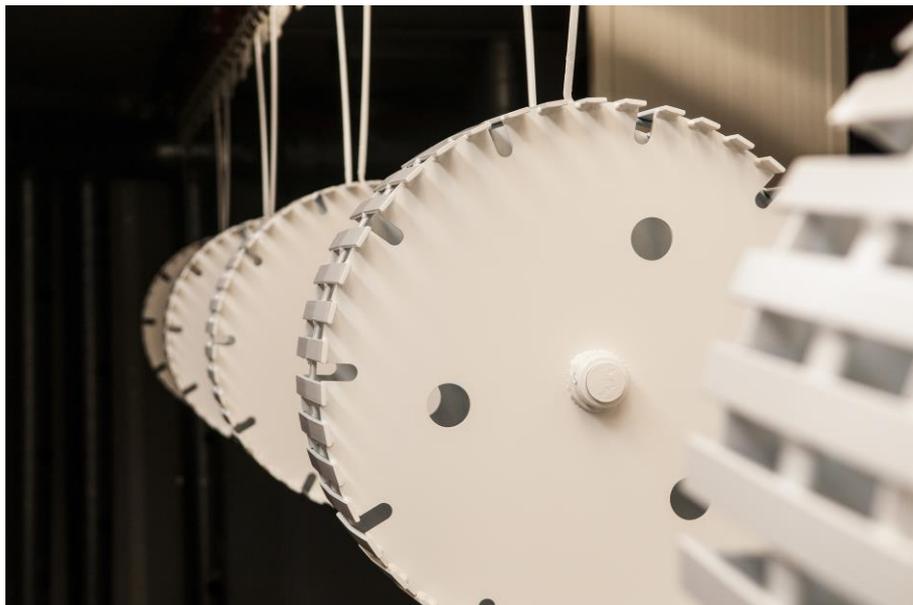
# Inropa™ OLP Automatic

## Automatic Scanning and Programming of Robots

*Inropa™ OLP Automatic is a technology that automatically programs robots by use of 3D-scanning of the parts.*

*Inropa™ OLP Automatic ensures a high flexibility and surface quality, reduces costs for personnel, material and increases production by ensuring a constant and smooth flow.*

*Inropa™ OLP Automatic is already used in several different industries such as metal, wind, wood and steel industry.*



### AUTOMATIC PROGRAMMING

With an Inropa™ OLP Automatic system, the operator mounts the parts on the conveyor and sends them through the paint line. Inropa™ OLP Automatic utilizes the Inropa™ LaserScanner to scan the parts. The parts are scanned in 3D.

The system then generates the robot programs automatically which means that no human robot programming is necessary.

The parts are scanned in 3D which means that along with the size and shape of each individual part, the position and orientation is also taken into account. As a result, the program is optimized for each individual part.

As each program is created on the fly the Inropa™ OLP Automatic is optimal for painting lot size one products whether it is metal parts for agriculture, windows and doors, cupboard doors, rotor blades for the windmill industry, truck engines, or steel rafters.



### BENEFITS OF OLP AUTOMATIC

The Inropa™ OLP Automatic system is optimized for painting and surface treatment. It ensures a high flexibility and surface quality, and will in most cases reduce cost for material and personnel. With the Inropa™ OLP Automatic system it is possible to adjust painting parameters such as angles, speed, and paint pressure for each surface type.

### WELL-PROVEN TECHNOLOGY

The technology for Inropa™ OLP Automatic is running in several different industrial paint or surface treatment lines worldwide and creates more than 7.000 robot programs every day.

**For further information, please visit our website [www.inropa.com](http://www.inropa.com)**

