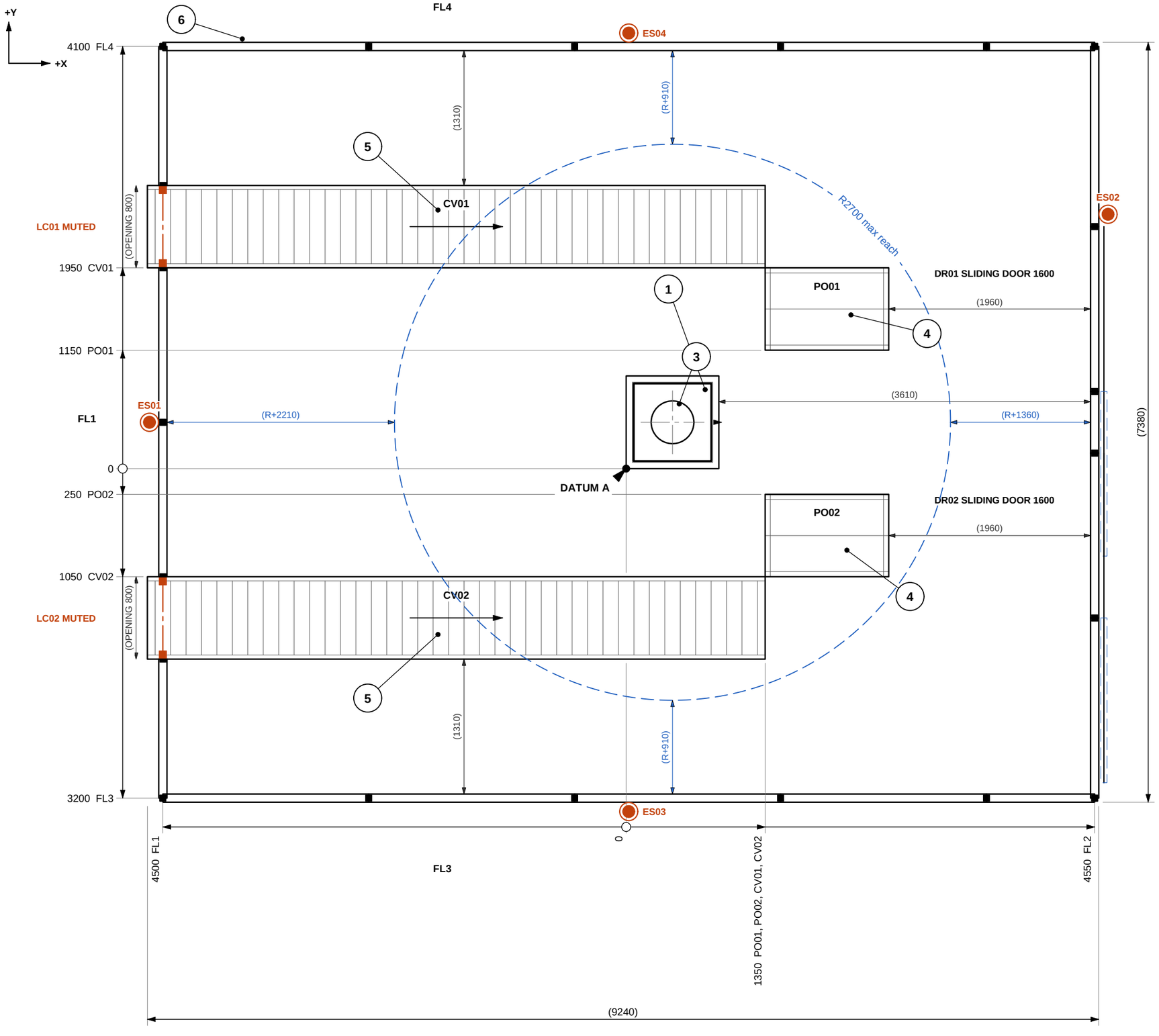

SETTING OUT (mm from DATUM A, to the corner dimensioned)

ITEM	TAG	X	Y	SIZE	ROT	REACH
1	RB01	0	0	900x900	0	-
4	PO01	1350	1150	1200x800	0	In reach
4	PO02	1350	-250	1200x800	0	In reach
5	CV01	1350	1950	6000x800	0	Partly
5	CV02	1350	-1050	6000x800	0	Partly
6	FN01	-2500	4060	2000x80	0	Outside
6	FN02	-500	4060	2000x80	0	Outside
6	FN03	-500	4060	2000x80	0	Outside
6	FN04	1500	4060	2000x80	0	Outside
6	FN05	3500	4060	1050x80	0	Outside
6	FN06	-2500	-3160	2000x80	0	Outside
6	FN07	-500	-3160	2000x80	0	Outside
6	FN08	-500	-3160	2000x80	0	Outside
6	FN09	1500	-3160	2000x80	0	Outside
6	FN10	3500	-3160	1050x80	0	Outside
6	FN11	-4460	2750	1350x80	270	Outside
6	FN12	-4460	450	1500x80	270	Outside
6	FN13	-4460	450	1500x80	270	Outside
6	FN14	-4460	-1850	1350x80	270	Outside
6	FN15	4510	2350	1750x80	270	Outside
6	FN16	4510	150	600x80	270	Outside
6	FN17	4510	-1450	1750x80	270	Outside
6	DR01	4510	750	1600x80	270	Outside
6	DR02	4510	150	1600x80	270	Outside

NOTES

1. All dimensions mm. DATUM A = -X/-Y corner of the robot base (pedestal if fitted). +X robot forward.
2. X and Y set out from DATUM A to a corner of each component: the nearest whose dimension lines run clear of other equipment (running dims, origin 0).
3. Reach circle = datasheet max reach to wrist centre. Tool, payload and A1 limits not included.
4. Balloons = item numbers in parts_list.xlsx. Tags (CV01, PO01...) = device tags in io_list.xlsx.
5. LC = light curtain, ES = e-stop (io_list.xlsx). Safety distances: safety_requirements.xlsx.

0 1000 2000 mm

SCALE 1:40 AT A3

PATH2 Robotics path2.io

CELL
Twin-line palletising cell

ROBOT
KUKA KR 210 R2700 extra

DATE	SCALE	SHEET
26 Nov 2026	**1:40 @ A3**	**1 of 1**

DRAWING
Concept layout, plan view. Palletising.

CONCEPT LAYOUT – NOT FOR CONSTRUCTION