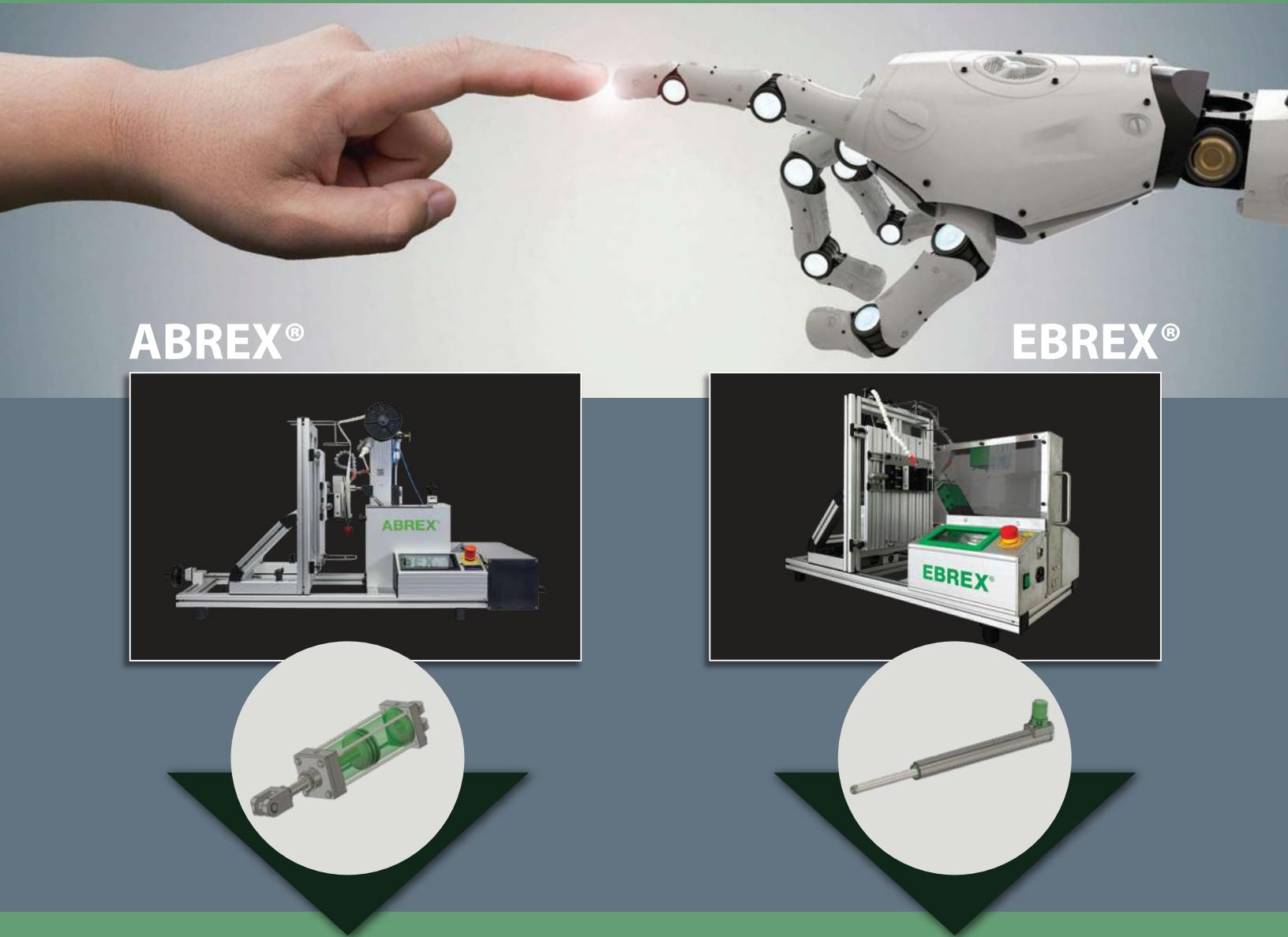


HUMAN TOUCH VS. ROBOT TOUCH



Human Fingertip Touch Simulation
with Pneumatic Drive System

Provide dynamic, non-linear movement

99% simulation providing the same
wear pattern as the one from the field

Feasible air-blow function to avoid
unnecessary abrasive

Robot Finger Touch Simulation with
non-Pneumatic Drive System

Provide linear and constant speed

Perform tribological material testing

Provide high speed performance

No air supply required



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quality + durability + haptic

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