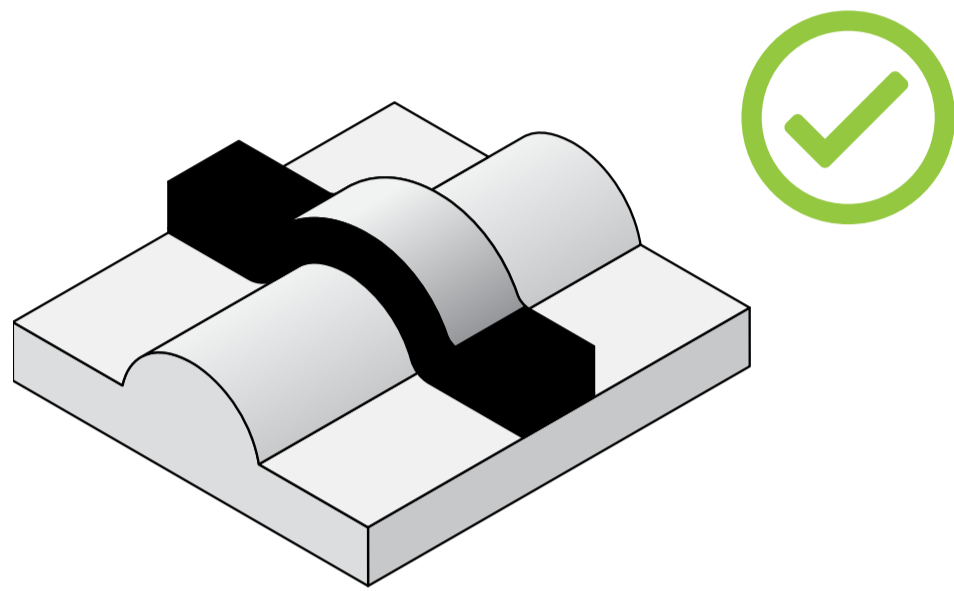
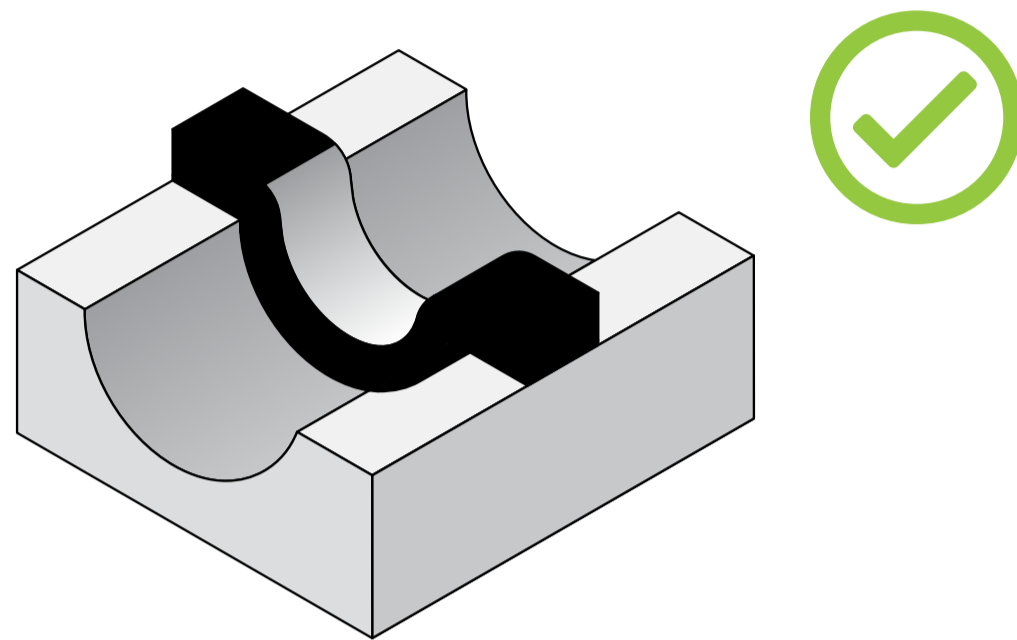


# ROBOTAPE APPLICATION CAPABILITIES

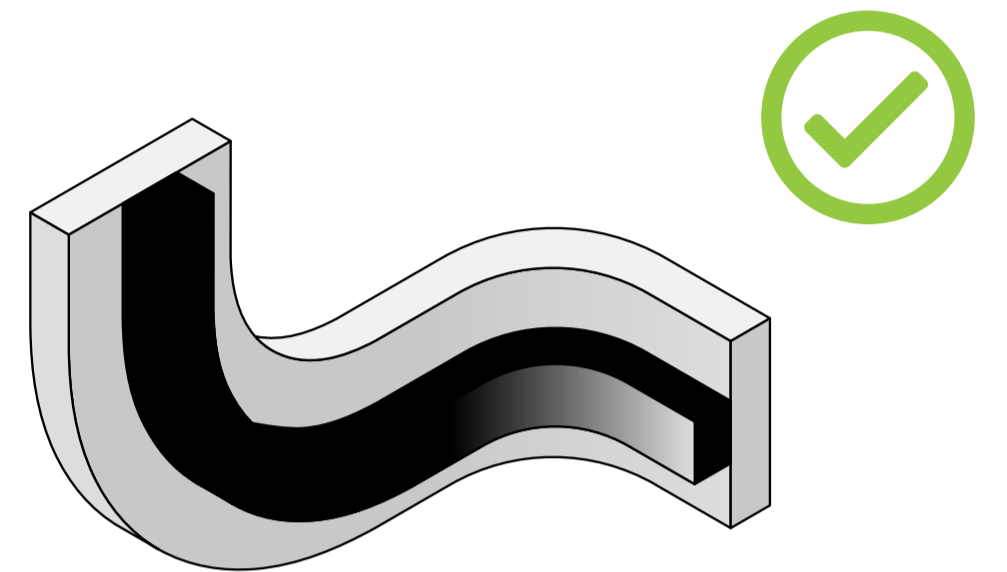


**Convex surfaces**

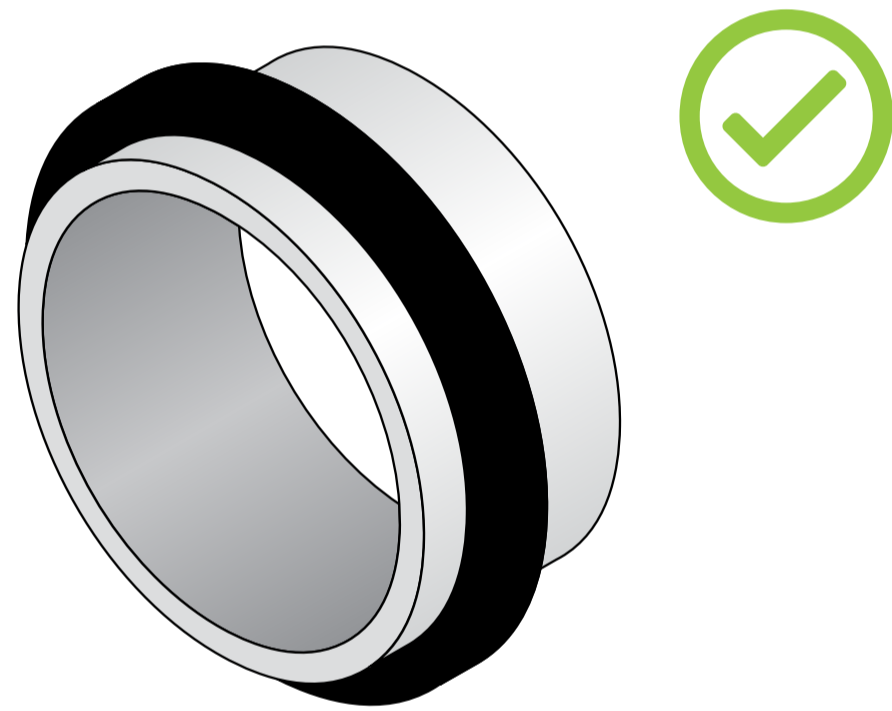


**Concave surfaces**

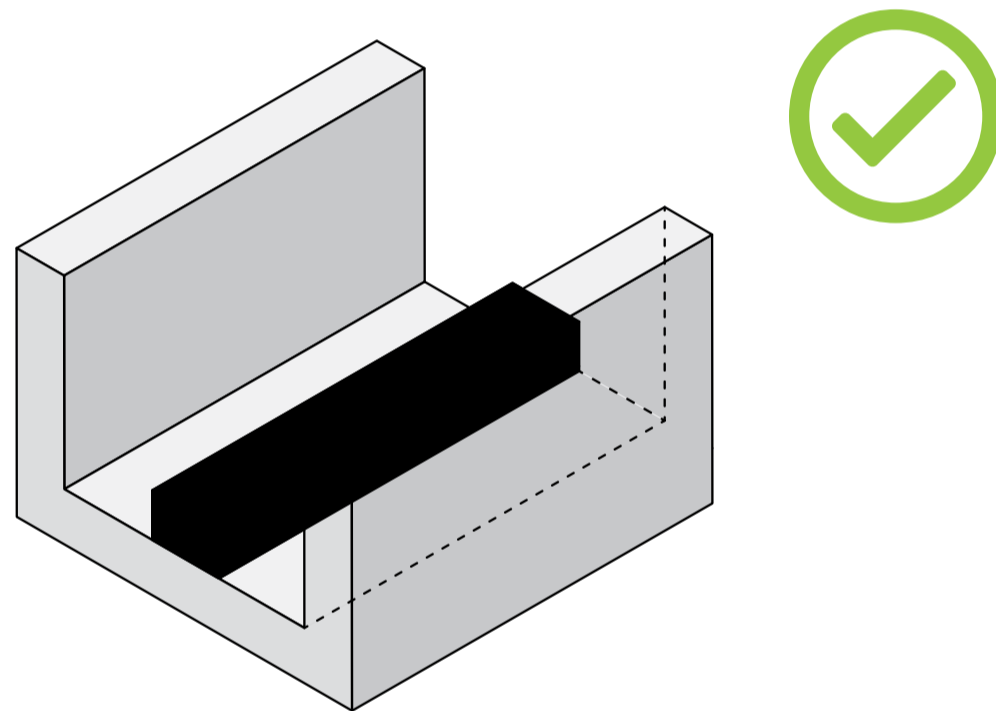
\* Depth and width impact feasibility



**Curved and 3D surfaces**

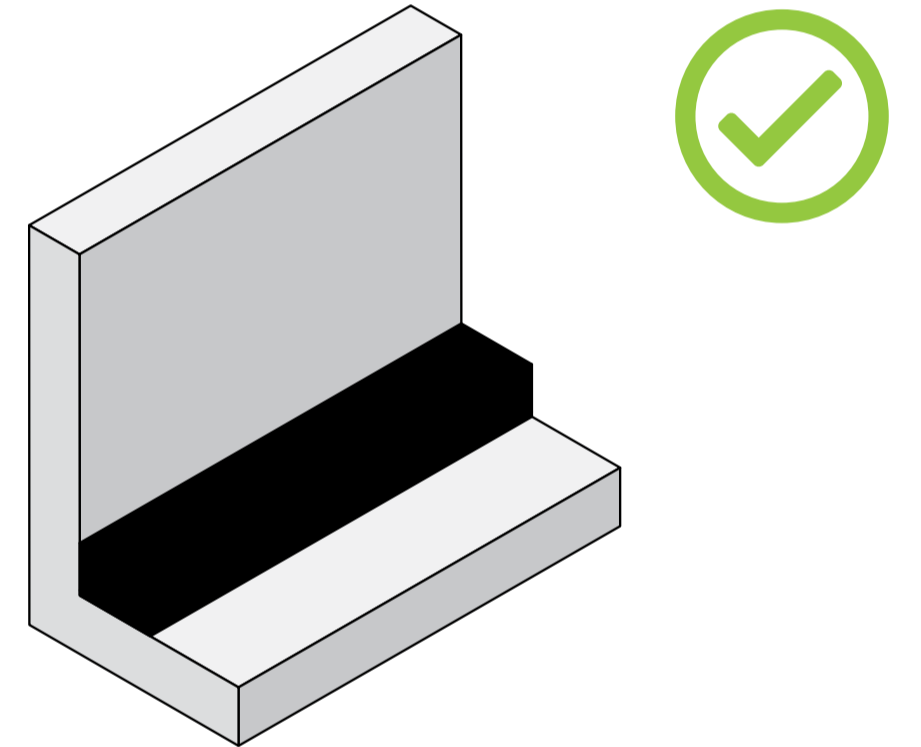


**Outside diameters**



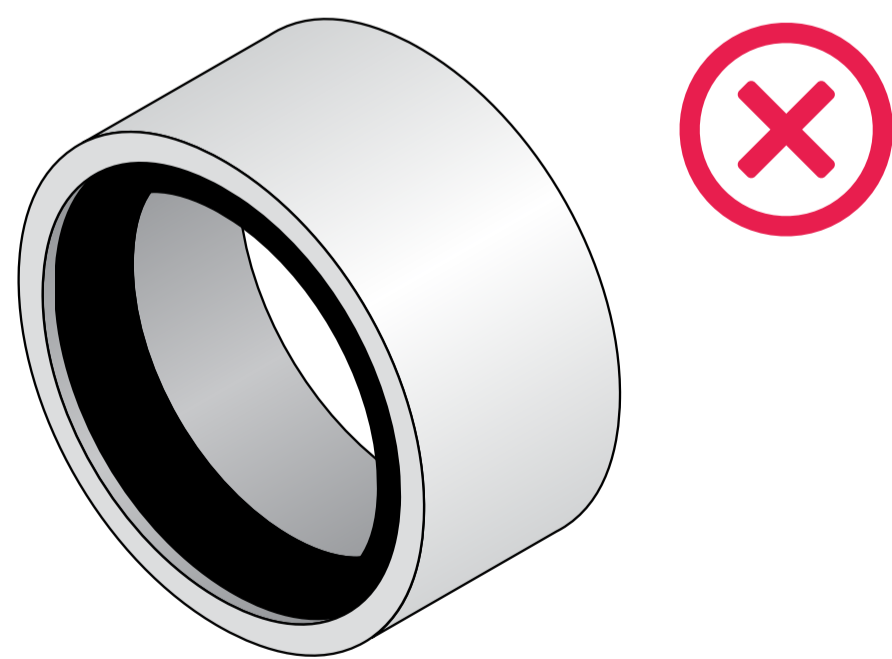
**Grooves & channels**

\* Depth and width impact feasibility

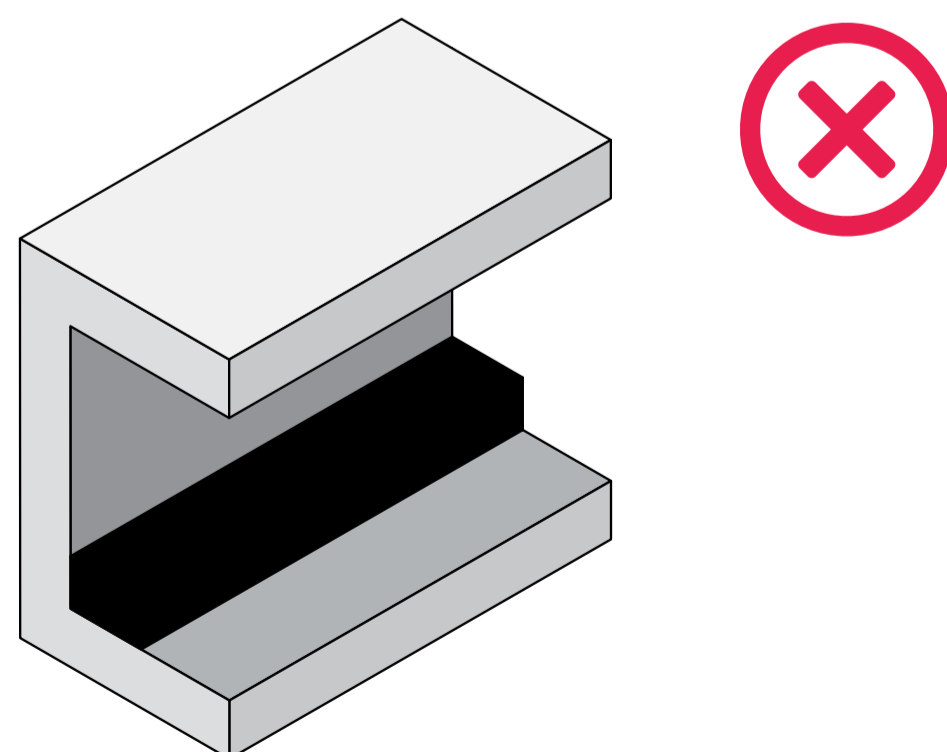


**Close clearance to walls**

\* Wall height impacts feasibility

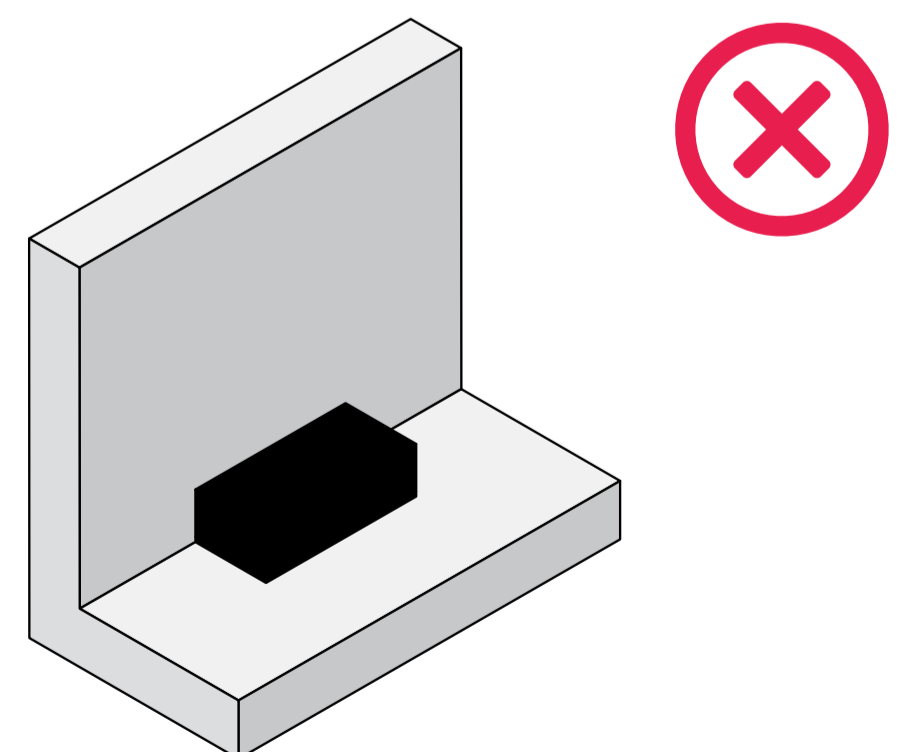


**Inside diameters**



**Beneath undercuts**

\* Minor undercuts can be possible without using integrated wetout



**Short segments against tall walls**

\* Can be possible when spaced out from the wall