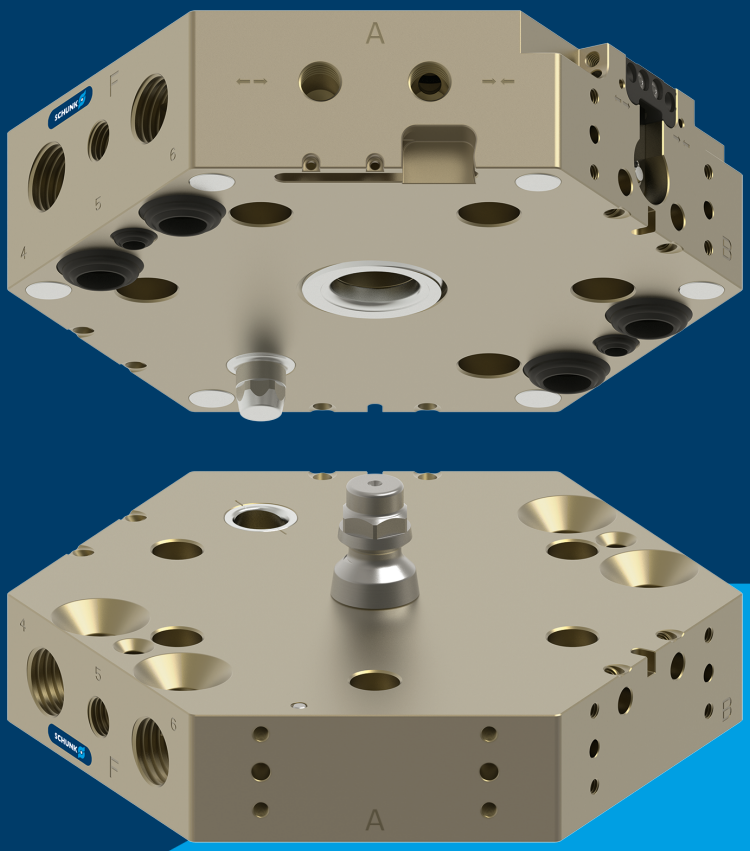


Assembly and Operating Manual CPB

Tool changer

Translation of the original manual

Hand in hand for tomorrow

Imprint

Technical changes:
We reserve the right to make alterations for the purpose of technical improvement.

Document number: 1631313

Version: 01.00 | 04/08/2025 | en

Dear Customer,

Thank you for trusting our products and our family-owned company, the leading technology supplier of robots and production machines.

Our team is always available to answer any questions on this product and other solutions. Ask us questions and challenge us. We will find a solution!

Best regards,

Your SCHUNK team

Customer Management
Tel. +49-7133-103-2503
Fax +49-7133-103-2189
cmg@de.schunk.com

Please read the operating manual in full and keep it close to the product.

Table of Contents

1 General

1.1 About this manual

This manual contains important information for a safe and appropriate use of the product.

This manual is an integral part of the product and must be kept accessible for the personnel at all times.

Before starting work, the personnel must have read and understood this operating manual. Prerequisite for safe working is the observance of all safety instructions in this manual.

In addition to these instructions, the documents listed under ▸ 1.1.4 [🗋 7] are applicable.

NOTE: The illustrations in this manual are intended to provide a basic understanding and may deviate from the actual version.

1.1.1 Presentation of Warning Labels

To make risks clear, the following signal words and symbols are used for safety notes.

⚠ DANGER

Dangers for persons!

Non-observance will inevitably cause irreversible injury or death.

⚠ WARNING

Dangers for persons!

Non-observance can lead to irreversible injury and even death.

⚠ CAUTION

Dangers for persons!

Non-observance can cause minor injuries.

NOTICE

Material damage!

Information about avoiding material damage.

1.1.2 Definition of Terms

The term "product" replaces the product name on the title page in this manual.

1.1.3 Symbol definition

The following symbols are used in this manual:

■ Prerequisite for an action

1. Action 1
2. Action 2
   ⇨ Intermediate results

⇨ Final results

▸ 1.1.3 [🗋 7]: chapter number and [page number] in hyperlinks

1.1.4 Applicable documents

- General terms of business *
- Catalog data sheet of the purchased product *
- Assembly and Operating Manual for optional modules COB *
- Assembly and Operating Manual for the storage rack CTS *
- Catalog data sheets for optional modules COB *
- Catalog data sheet for storage racks CTS *

The documents labeled with an asterisk (*) can be downloaded from **schunk.com/downloads**.

1.1.5 Sizes

This operating manual applies to the following sizes:

- CPB 040
- CPB 050
- CPB 063
- CPB 080
- CPB 100
- CPB 125
- CPB 160

1.2 Warranty

If the product is used as intended, the warranty is valid for 24 months from the ex-works delivery date under the following conditions:

- Observe the specified maintenance and lubrication intervals
- Observe the ambient conditions and operating conditions

Parts touching the workpiece and wear parts are not included in the warranty.

1.3 Scope of delivery

The scope of delivery includes

- Master CPB-K and/or tool CPB-A in the version ordered
- Safety information (product-specific instructions available online)
- Accessory pack

Accessory pack CPB-K

CPB-K Contents of the accessory kit:

- Mounting screws
- Fitting screw
- 1x cylindrical pin for position orientation

Size	ID.-No. of the accessory pack
040	1608569
050	1608580
063	1608581
080	1608583
100	1608584
125	1608585
160	1608586

Tab.: ID.-No. of the accessory pack CPB-K

Accessory pack CPB-A

CPB-A Contents of the accessory kit:

- O-rings for axial pneumatic feed-throughs

Size	ID.-No. of the accessory pack
040	1630420
050	1630424
063	1630425
080	1630426
100	1630427
125	1630429
160	1630430

Tab.: ID.-No. of the accessory pack CPB-A

1.4 Accessories

The following accessories are available for the product, which must be ordered separately:

- Optional module COB
- Modular storage rack CTS
- Sensors for lock/unlock monitoring and for tool presence monitoring
- Seal kit
- Cable connectors and cable extensions
- Adapter plates for fastening to the robot

For information regarding which accessory articles can be used with the corresponding product variants, see catalog data sheet.

Seal kit

Contents of the seal kit:

- Seals Items 75, 76, 77, (78)
- See assembly drawing for position of seals, ▶ 7.7 [🗋 57]

Size	ID.-No. of the seal kit
040	1608082
050	1608083
063	1608087
080	1608088
100	1608091
125	1608092
160	1608093

Tab.: ID.-No. of the seal kit

Seal kit "rubber bushing"

Contents of the "rubber bushing" seal kit:

- 5x item 01, (5x item 02)
- See assembly drawing for position of seals, ▶ 7.7 [🗋 57]

Size	ID.-No. of the seal kit
M5	1602942
G1/8"	1602944
G3/8"	1602945

Tab.: ID.-No. of the seal kit "rubber bushing"

2 Basic safety notes

2.1 Intended use

- Tool changer for automatic changing of a tool or a suitable end effector on a robot, taking into account defined technical data and using suitable and effective technical equipment around the danger zone, e.g. of the robot.
- When implementing and operating components in safety-related parts of the control systems, the basic safety principles in accordance with DIN EN ISO 13849-2 apply. The proven safety principles in accordance with DIN EN ISO 13849-2 also apply to categories 1, 2, 3 and 4.
- The product is intended for installation in a machine/automated system. The applicable guidelines for the machine/automated system must be observed and complied with.
- The product may only be used within the scope of its technical data, ▸ 3 [🗋 17].

Operating conditions

- Use only in covered or closed areas.
- Use in non-explosive areas.
- Only the substances permitted for the respective product should be fed through (fluids, electricity). All substances are only to be fed through the modules provided for this purpose. Never feed through corrosive or flammable gases.
- Only use the accessories permitted for the respective product.
- The product is intended for industrial and industry-oriented use.
- Appropriate use of the product includes compliance with all instructions in this manual.

2.2 Not intended use

Any use that exceeds or differs from the appropriate use is regarded as misuse. This includes in particular:

- Assembly on products that are not robots
- Use of the product as lifting equipment
- Outdoor use
- Use in potentially explosive areas

2.3 Constructional changes

Implementation of structural changes

Modifications, changes or reworking, e.g. additional threads, holes, or safety devices, can damage the product or impair its functionality or safety.

- Structural changes should only be made with the written approval of SCHUNK.

2.4 Spare parts

Use of unauthorized spare parts

Using unauthorized spare parts can endanger personnel and damage the product or cause it to malfunction.

- Use only original spare parts or spares authorized by SCHUNK.

2.5 Ambient conditions and operating conditions

Required ambient conditions and operating conditions

Incorrect ambient and operating conditions can make the product unsafe, leading to the risk of serious injuries, considerable material damage and/or a significant reduction to the product's life span.

- Make sure that the product is used only in the context of its defined application parameters, ▶ 3 [🗋 17].

2.6 Personnel qualification

Inadequate qualifications of the personnel

If the personnel working with the product is not sufficiently qualified, the result may be serious injuries and significant property damage.

- All work may only be performed by qualified personnel.
- Before working with the product, the personnel must have read and understood the complete assembly and operating manual.
- Observe the national safety regulations and rules and general safety instructions.

The following personal qualifications are necessary for the various activities related to the product:

Trained electrician

Due to their technical training, knowledge and experience, trained electricians are able to work on electrical systems, recognize and avoid possible dangers and know the relevant standards and regulations.

Qualified personnel

Due to its technical training, knowledge and experience, qualified personnel is able to perform the delegated tasks, recognize and avoid possible dangers and knows the relevant standards and regulations.

Instructed person

Instructed persons were instructed by the operator about the delegated tasks and possible dangers due to improper behaviour.

Service personnel of the manufacturer

Due to its technical training, knowledge and experience, service personnel of the manufacturer is able to perform the delegated tasks and to recognize and avoid possible dangers.

2.7 Personal protective equipment

Use of personal protective equipment

Personal protective equipment serves to protect staff against danger which may interfere with their health or safety at work.

- When working on and with the product, observe the occupational health and safety regulations and wear the required personal protective equipment.
- Observe the valid safety and accident prevention regulations.
- Wear protective gloves to guard against sharp edges and corners or rough surfaces.
- Wear heat-resistant protective gloves when handling hot surfaces.
- Wear protective gloves and safety goggles when handling hazardous substances.
- Wear close-fitting protective clothing and also wear long hair in a hairnet when dealing with moving components.

2.8 Notes on safe operation

Incorrect handling of the personnel

Incorrect handling and assembly may impair the product's safety and cause serious injuries and considerable material damage.

- Avoid any manner of working that may interfere with the function and operational safety of the product.
- Use the product as intended.
- Observe the safety notes and assembly instructions.
- Do not expose the product to any corrosive media. This does not apply to products that are designed for special environments.
- Eliminate any malfunction immediately.
- Observe the care and maintenance instructions.
- Observe the current safety, accident prevention and environmental protection regulations regarding the product's application field.

2.9 Transport

Handling during transport

Incorrect handling during transport may impair the product's safety and cause serious injuries and considerable material damage.

- When handling heavy weights, use lifting equipment to lift the product and transport it by appropriate means.
- Secure the product against falling during transportation and handling.
- Stand clear of suspended loads.

2.10 Disposal

Handling of disposal

The incorrect handling of disposal may impair the product's safety and cause serious injuries as well as considerable material and environmental harm.

- Follow local regulations on dispatching product components for recycling or proper disposal.

2.11 Fundamental dangers

General

- Observe safety distances.
- Never deactivate safety devices.
- Before commissioning the product, take appropriate protective measures to secure the danger zone.
- Disconnect power sources before installation, modification, maintenance, or calibration. Ensure that no residual energy remains in the system.
- If the energy supply is connected, do not move any parts by hand.
- Do not reach into the open mechanism or movement area of the product during operation.

2.11.1 Protection during handling and assembly

Incorrect handling and assembly

Incorrect handling and assembly may impair the product's safety and cause serious injuries and considerable material damage.

- Have all work carried out by appropriately qualified personnel.
- For all work, secure the product against accidental operation.
- Observe the relevant accident prevention rules.
- Use suitable assembly and transport equipment and take precautions to prevent jamming and crushing.

Incorrect lifting of loads

Falling loads may cause serious injuries and even death.

- Stand clear of suspended loads and do not step into their swiveling range.
- Never move loads without supervision.
- Do not leave suspended loads unattended.

2.11.2 Protection during commissioning and operation

Falling or violently ejected components

Falling and violently ejected components can cause serious injuries and even death.

- Take appropriate protective measures to secure the danger zone.
- Never step into the danger zone during operation.

2.11.3 Protection against dangerous movements

Unexpected movements

Residual energy in the system may cause serious injuries while working with the product.

- Switch off the energy supply, ensure that no residual energy remains and secure against inadvertent reactivation.
- Never rely solely on the response of the monitoring function to avert danger. Until the installed monitors become effective, it must be assumed that the drive movement is faulty, with its action being dependent on the control unit and the current operating condition of the drive. Perform maintenance work, modifications, and attachments outside the danger zone defined by the movement range.
- To avoid accidents and/or material damage, human access to the movement range of the machine must be restricted. Limit/prevent accidental access for people in this area due through technical safety measures. The protective cover and protective fence must be rigid enough to withstand the maximum possible movement energy. EMERGENCY STOP switches must be easily and quickly accessible. Before starting up the machine or automated system, check that the EMERGENCY STOP system is working. Prevent operation of the machine if this protective equipment does not function correctly.

2.12 Notes on particular risks

⚠ WARNING

Risk of injury due to unexpected movements!

If the power supply is switched on or residual energy remains in the system, components can move unexpectedly and cause serious injuries.

- Before starting any work on the product: Switch off the power supply and secure against restarting.
- Make sure, that no residual energy remains in the system.

⚠ WARNING

Risk of crushing from objects falling and being ejected!

During operation, the load can no longer be held if the maximum permissible load is exceeded, if a component breaks or if the pressure drops.

- Check product for damage before operation. Arrange for repairs if necessary.
- Observe maintenance intervals.
- Take suitable protective measures to secure the danger zone.

⚠ CAUTION

Risk of injury due to contact with lubricants!

Lubricant may cause irritation and allergic reactions if it contacts the skin or eyes.

- Avoid contact between lubricant and skin or eyes.
- Wear safety goggles and protective gloves.
- Observe information on the safety data sheet of the lubricant.

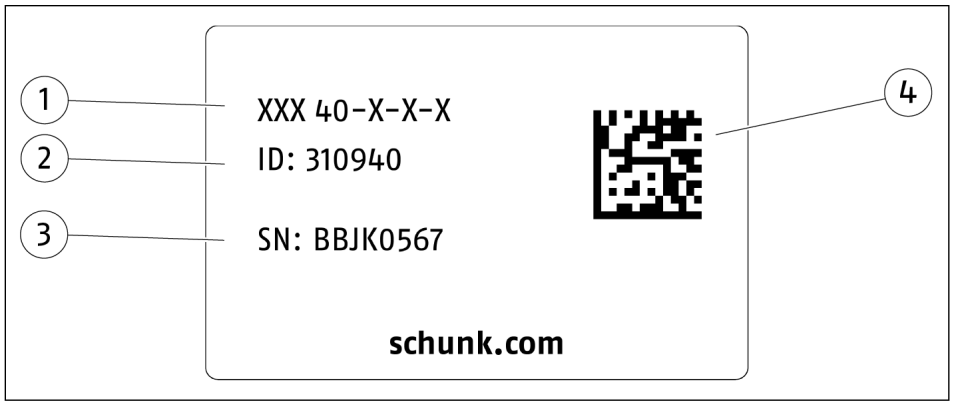
⚠ CAUTION

Risk of injury due to contamination in the tool changer's media feed-throughs!

- Wear safety goggles and protective gloves when pressurizing in an uncoupled state.

3 Technical data

3.1 Name plate



1	Product designation
2	ID
3	Serial number
4	Data matrix code

Scan code or enter serial number on the web and get all the product information: operating manuals, spare parts packages, software updates and much more.

For further information, visit **schunk.com/serialisierung**

A separate app may be required for scanning with a mobile phone.

3.2 Basic data

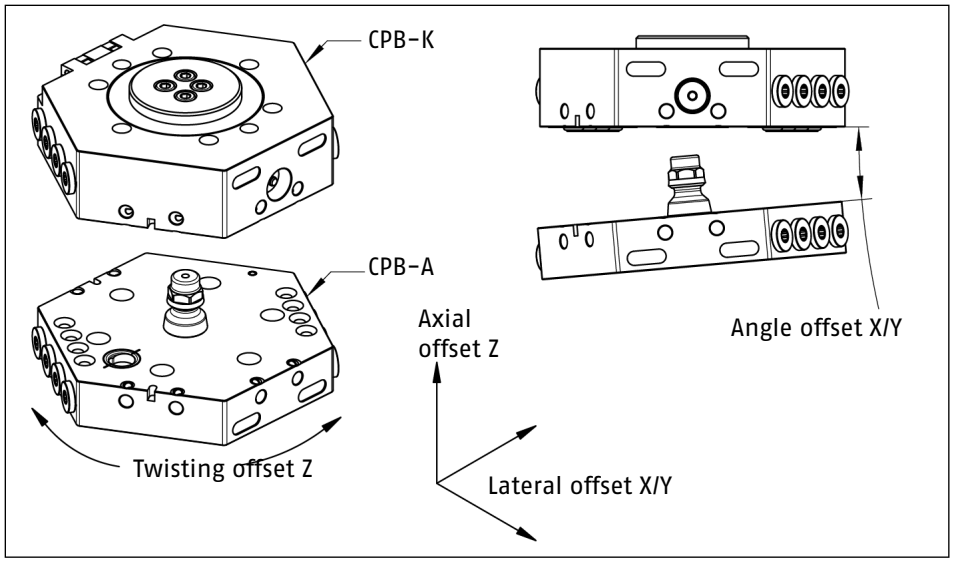
Size	Weight [kg]		Max. moment, static [Nm]	
	CPB-K	CPB-A	M_x, M_y	M_z
040	0.22	0.19	200	200
050	0.33	0.24	250	250
063	0.72	0.51	700	700
080	1.15	0.78	1000	1000
100	1.70	1.33	1600	1200
125	4.01	3.21	4000	2000
160	5.99	4.57	6000	3000

More technical data is included in the catalog data sheet. Whichever is the latest version.

3.3 Ambient conditions and operating conditions

Designation	Value
Ambient temperature [°C] min. max.	 +5 +60
Pressure medium	Compressed air, compressed air quality according to ISO 8573-1:2010 [7:4:4]
Nominal operating pressure [bar]	6
Minimum pressure [bar]	4.5
Maximum pressure [bar]	7
Protection class IP, DIN EN 60529	54

3.4 Max. permissible offset between master and tool



Offset definition

Size	Max. torsional offset Z [°]	Max. axial offset Z [mm] *	Max. lateral offset XY [mm] **	Max. angular offset XY [°]
040	±2	0.5	±1	±0.8
050	±2	0.5	±1	±0.8
063	±2	1	±2	±1
080	±2	1	±2	±1
100	±2	1	±2	±1
125	±2	1.5	±2	±1
160	±2	1.5	±2	±1

* Maximum values specified. By reducing the actual values, wear when locking / unlocking is minimized.

** The actual values may be higher in some cases. However, higher offset values increase wear when locking / unlocking.

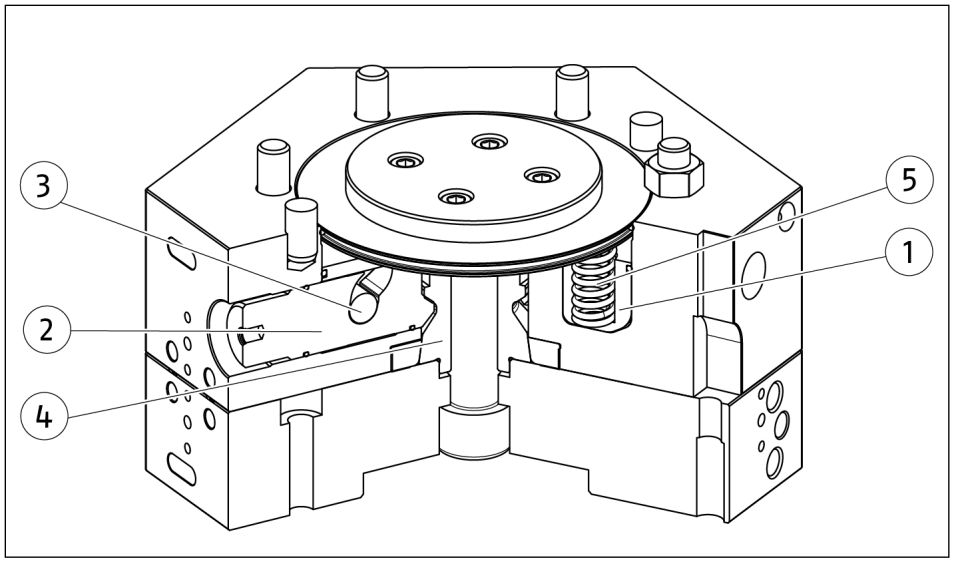
4 Design and description

4.1 Description

The product (CPB) enables automated tool changing and consists of a master CPB-K and a tool CPB-A.

- The master CPB-K is connected with the robot and together with the CPB-A forms the interface between the robot and the end effector.
- The tool CPB-A is connected to the end effector. If different tools are used with a CPB-K, each end effector is equipped with a CPB-A. Unused tools are stored by the robot in a storage rack when not in use.
- Optional modules COB for transferring media and storage racks CTS are optionally available as accessories from SCHUNK.

4.1.1 Functional principle



Schematic diagram of locking mechanism

1	Piston
2	Clamping slide
3	Cylindrical pin
4	Storage pins
5	Pressure spring

Locking

The dowel pins (3) are mounted in the piston (1). When the module is actuated, the cylinder pin (3) transmits the force from the piston (1) to the clamping slides (2). The storage pin (4) is mounted on the tool. The diagonal pull on the clamping slide (2) and storage pin (4) pulls the master and tool together when locking. The module is also locked without pressure by the pressure springs (5).

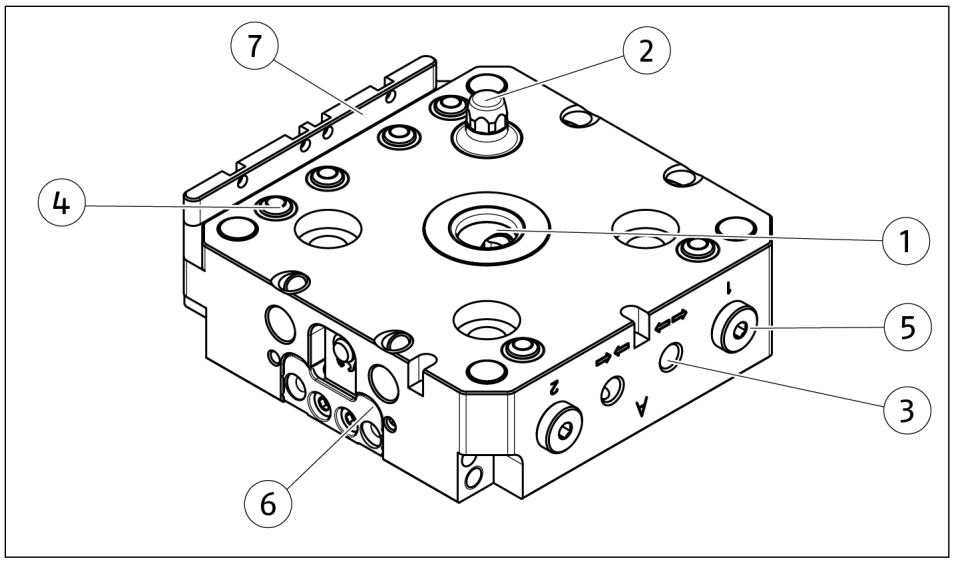
Unlocking

If the piston (1) is actuated via the "unlock" connection, it moves in the opposite direction. The dowel pins (3) push back the clamping slides (2) and the storage pin (4) is released. The master is in unlocked state and can be separated from the tool.

4.2 Design

4.2.1 Size 040/050/063

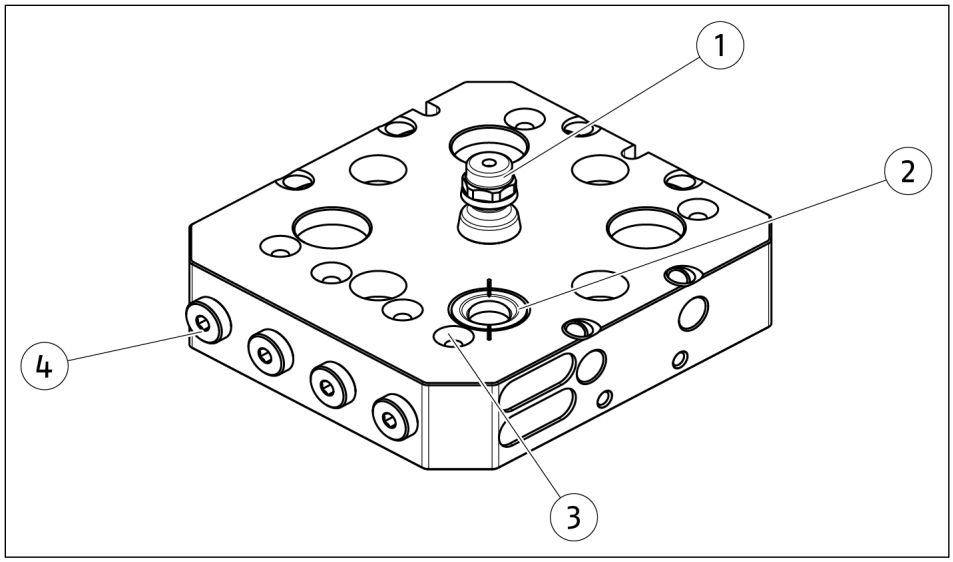
CPB-K



Design shown by way of example on CPB 050-K

1	Locking mechanism
2	Fitting screw
3	Main air connections: Locking and unlocking
4	Pneumatic feed-through with rubber bushing
5	Port for pneumatic feed-through
6	Monitoring "locked/unlocked"
7	"Ready to lock" query screen

CPB-A

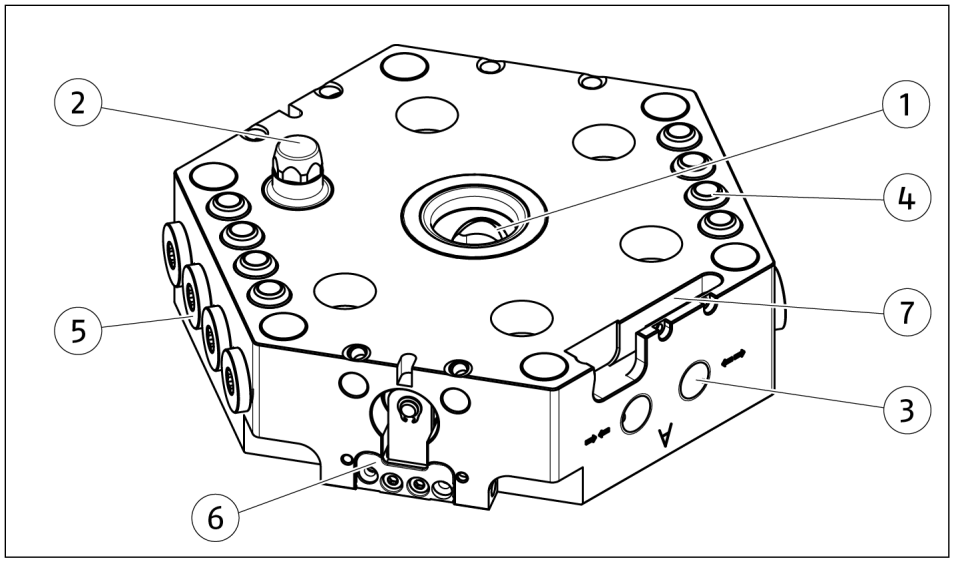


Design shown by way of example on CPB 050-A

1	Storage pins
2	Fitted bushing
3	Pneumatic feed-through
4	Port for pneumatic feed-through

4.2.2 Size 080/100

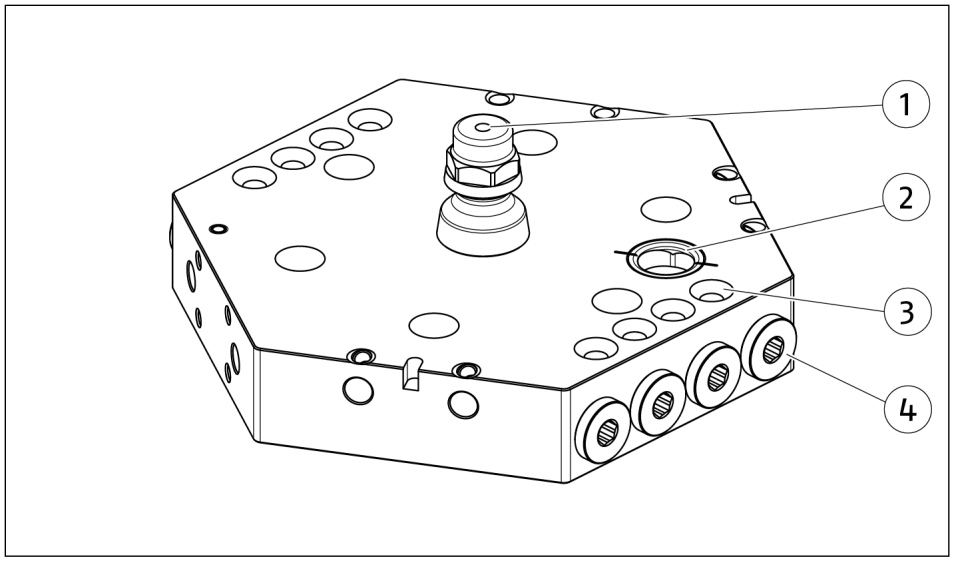
CPB-K



Design shown by way of example on CPB 080-K

1	Locking mechanism
2	Fitting screw
3	Main air connections: Locking and unlocking
4	Pneumatic feed-through with rubber bushing
5	Port for pneumatic feed-through
6	Monitoring "locked/unlocked"
7	"Ready to lock" query screen

CPB-A

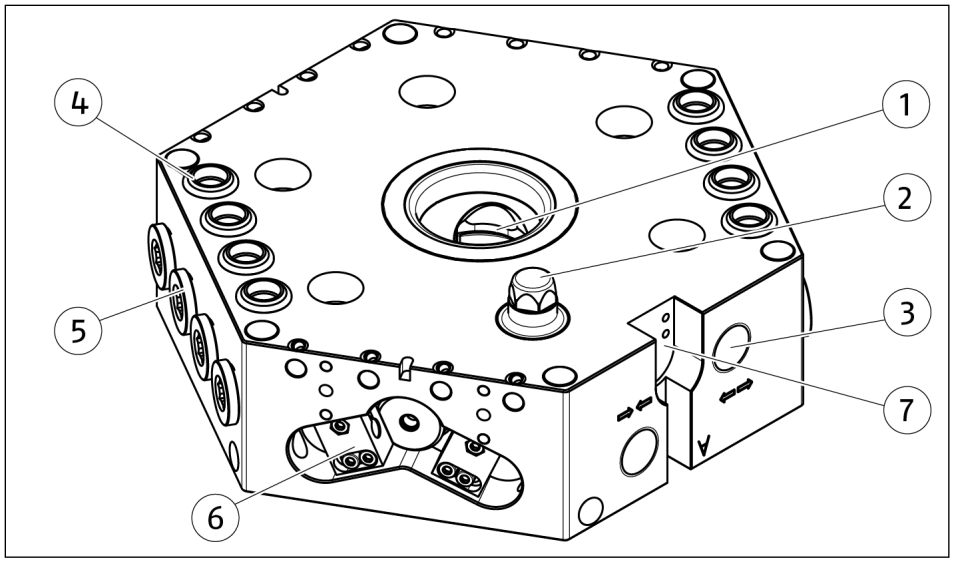


Design shown by way of example on CPB 80-A

1	Storage pins
2	Fitted bushing
3	Pneumatic feed-through
4	Port for pneumatic feed-through

4.2.3 Size 125/160

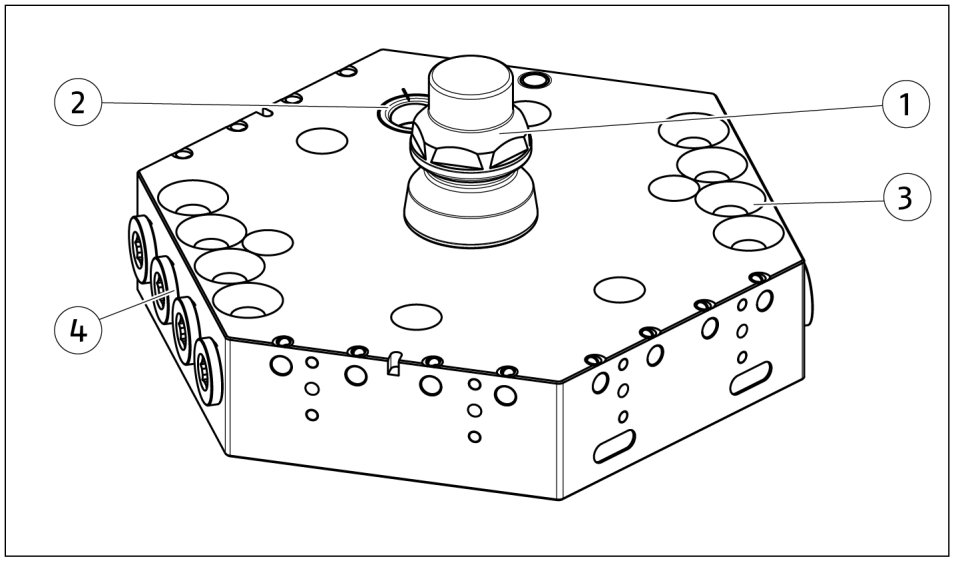
CPB-K



Design shown by way of example CPB 125-K

1	Locking mechanism
2	Fitting screw
3	Main air connections: Locking and unlocking
4	Pneumatic feed-through with rubber bushing
5	Port for pneumatic feed-through
6	Monitoring "locked/unlocked"
7	"Ready to lock" query screen

CPB-A



Design shown by way of example CPB 125-A

1	Storage pins
2	Fitted bushing
3	Pneumatic feed-through
4	Port for pneumatic feed-through

5 Assembly

5.1 Installing and connecting

⚠ WARNING

Risk of injury due to unexpected movements!

If the power supply is switched on or residual energy remains in the system, components can move unexpectedly and cause serious injuries.

- Before starting any work on the product: Switch off the power supply and secure against restarting.
- Make sure, that no residual energy remains in the system.

⚠ WARNING

Risk of injury due to improperly carried out assembly!

Improperly carried out assembly work can lead to severe injuries and property damage.

- Before beginning work, ensure sufficient assembly clearance.
- Secure components from falling down or over.
- Ensure that all work has been carried out in accordance with the specifications in these instructions.
- Observe tightening torques.

⚠ CAUTION

Risk of injury due to moving parts coming into proximity with stationary parts!

Moving components may cause severe injuries. Body parts may get crushed and bruised.

- Do not reach between the product and robot during assembly.
- During the coupling procedure, do not grip between the master and the tool.

1. Check the evenness of the mounting surface, ▸ 5.2 [🗋 26].
2. Attach the product to the robot, ▸ 5.2 [🗋 26].
   ⇨ Use the fastening elements from the accessory kit, ▸ 1.3 [🗋 8].
   ⇨ Observe the maximal tightening torque, admissible screw-in depth and, if necessary, strength class.
3. Connect pneumatic connections to compressed air supply via a suitable 4 or 5-way valve, ▸ 5.3 [🗋 33]
4. Mount sensors if necessary, ▸ 5.4 [🗋 37].
5. If necessary, install optional modules, see separate assembly and operating manual for the optional module.
6. Make sure that the connections are not stressed due to tensile and pressure forces. Apply appropriate strain relief devices if required.

5.2 Mechanical connection

NOTE

- Secure all screws with medium-strength threadlocker. To do this, apply adhesive to the exposed screw threads.
  ⇨ Use adhesive only once. Always apply new adhesive if reusing fastening elements.
- *CPB 040-K/CPB 050-K*: The screws included in the accessory kit should protrude above the surface. Corresponding recesses are provided in CPB-A.
- *CPB 063-K/CPB 080-K/CPB 100-K/CPB 125-K/CPB 160-K:* Mounted screws must not protrude above the surface! Select screws so that they are flush with the surfaces and screw them together without washers.

Evenness of the mounting surface

The values apply to the whole mounting surface to which the product is mounted.

Edge length	Permissible unevenness
< 100	< 0.02
> 100	< 0.05

Tab.: Requirements for evenness of the mounting surface (Dimensions in mm)

Adapter plate requirements

An adapter plate can be used for mounting the CPB-K on the robot and the end effector on the CPB-A. An adapter plate is necessary if the screw connection pattern of the CPB has to be adapted to the customer's equipment (robot flange, end effector). **NOTICE! Only use adapter plates if they have bore**

holes and recesses that match the product exactly. Precise assembly is a prerequisite for proper functioning.

The adapter plate must meet the following requirements:

- The adapter plate requires bores for the mounting screws with sufficient thread depth for mounting on the robot.
- The adapter plate requires centering recesses for dowel pins with sufficient depth so that no gap is created during assembly.
- Depending on the robot flange, the adapter plate requires a centering plate on the robot side and a fitting bore at the interface to the CPB-K robot side.
- Depending on the end effector, the adapter plate requires a centering plate on the CPB-A tool side and a fitting bore at the interface to the end effector.

The catalog data sheet contains detailed information and precise manufacturing instructions for possible adapter plate design.

5.2.1 Tightening torques for screws

The following overview shows the tightening torques for the fastening screws for CPB-K and CPB-A.

Size	Screw	Strength class	Standard	Tightening torque [Nm]
040-K *	M6x25	10.9	ISO 4762	13
040-A **	M6	12.9	ISO 4762	15
040-A	M4	12.9	ISO 4762	5
050-K *	M6x25	10.9	ISO 4762	13
050-A **	M6	12.9	ISO 4762	15
050-A	M5	12.9	ISO 4762	9
063-K *	M6x35	12.9	ISO 4762	15
063-A **	M6	12.9	ISO 4762	15
063	M5	12.9	ISO 4762	9
080-K *	M8x35	12.9	ISO 4762	32
080-A **	M8	12.9	ISO 4762	32
080-A	M6	12.9	ISO 4762	15
100-K *	M8x40	12.9	ISO 4762	32
100-A **	M8	12.9	ISO 4762	32
100-A	M6	12.9	ISO 4762	15
125-K *	M10x60	12.9	ISO 4762	62
125-A **	M10	12.9	ISO 4762	62
125-A	M8	12.9	ISO 4762	32
160-K *	M10x60	12.9	ISO 4762	62
160-A **	M10	12.9	ISO 4762	62
160-A	M8	12.9	ISO 4762	32

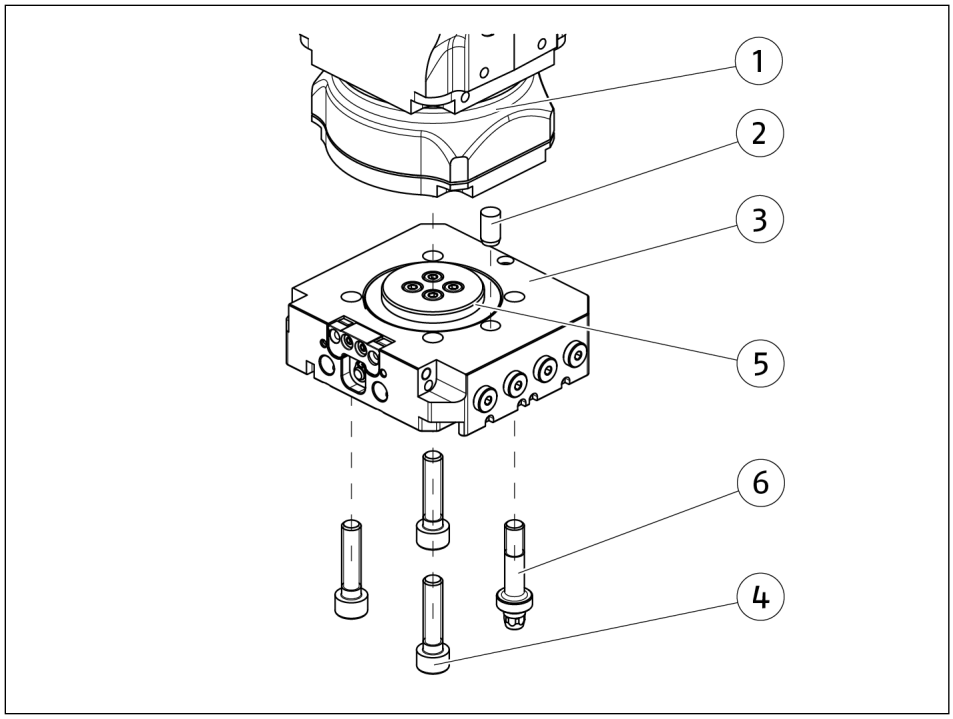
* Material of the screw-on flange Tensile strength ≥ 400 MPa

** Provide screw-in depth min. 1.1 x D

5.2.2 Size 040/050/063

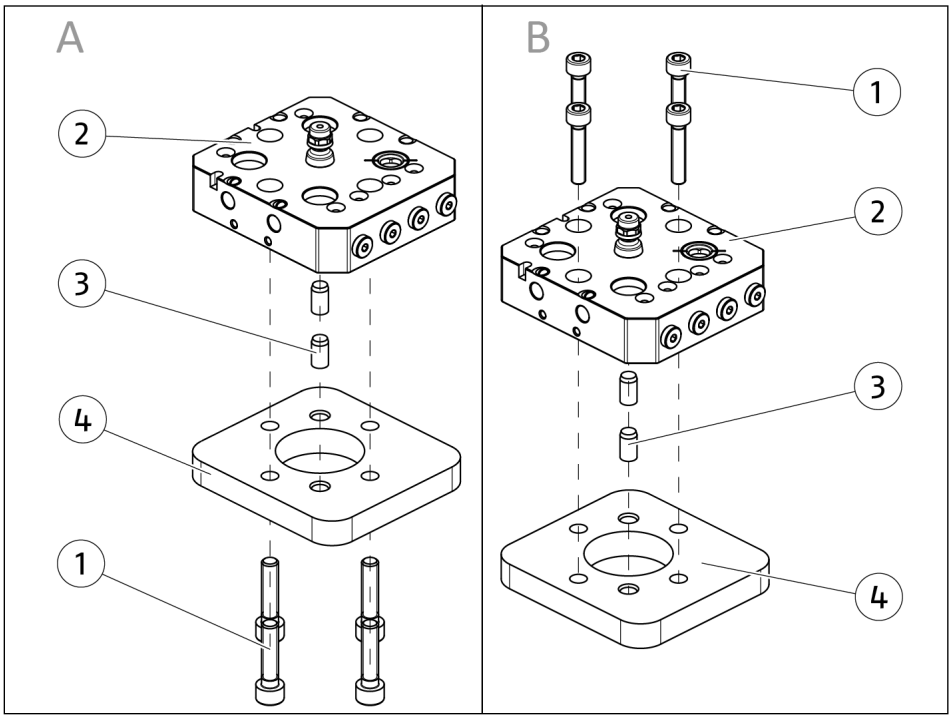
NOTE

The product has an ISO flange as standard. When using a robot without an ISO flange interface, the product can be mounted to the robot using an adapter plate.



Mounting on the robot for CPB 040-K/050-K/063-K, shown as an example on CPB 050-K

1. Clean the mounting surfaces on the robot (1) and CPB-K (3).
2. *For mounting on a robot without an ISO flange interface:* Mount adapter plate between robot (1) and CPB-K (3).
3. Insert alignment pin (2) in CPB-K (3).
4. Apply threadlocker to screws (4) and fitting screw (6).
5. Align CPB-K with centering pin (2) on robot and insert CPB-K (3) with centering collar (5) into the fitting bore on the robot (1).
6. Fasten CPB-K (3) to the robot (1) with screws (4) and fitting screw (6).
   ⇨ Observe the tightening torque of the mounting screws, ▸ 5.2.1 [🗋 28].



Mounting adapter plate (4) (shown as an example) to CPB 050-A, (A= mounting from below; B = mounting from above)

NOTE

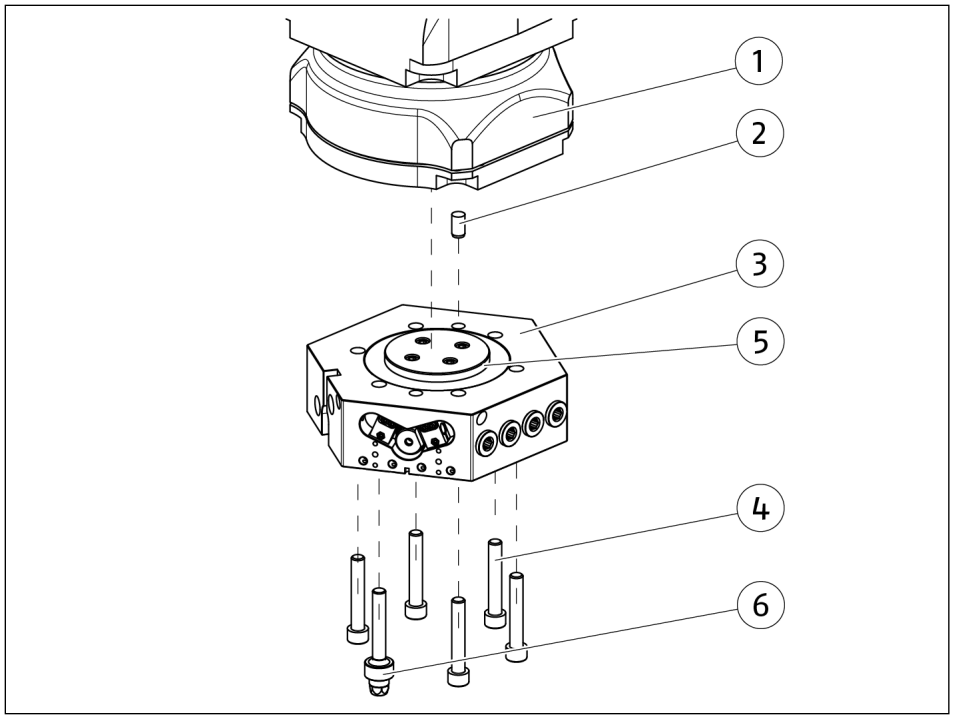
If the axial pneumatic feed-throughs are to be used on CPB-A, it is very important to observe the notes in the "Axial pneumatic feed-throughs" chapter, ▸ 5.3.3 [🗋 35].

1. Clean mounting surfaces on CPB-A (2) and adapter plate (4).
2. Insert the adapter plate (4) with two dowel pins (3) or one dowel pin and a centering plate into the bores provided for this purpose.
3. Secure the adapter plate (4) to the CPB-A (2) from above or below with screws (1).
   ⇨ Observe the tightening torque of the mounting screws, ▸ 5.2.1 [🗋 28].
4. Mount the end effector.

5.2.3 Sizes 080/100/125/160

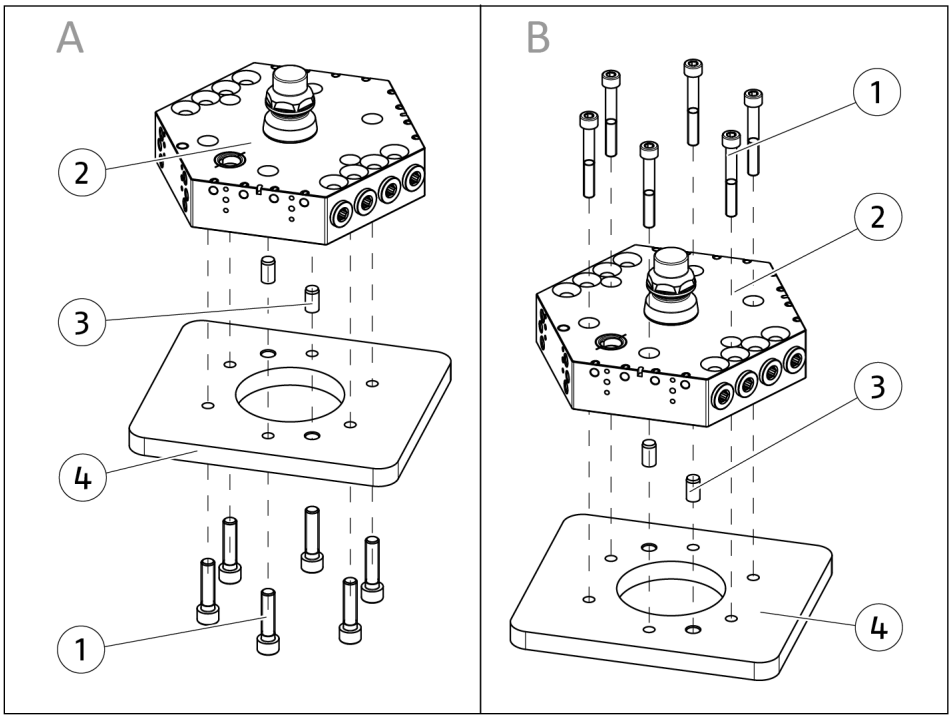
NOTE

The product has an ISO flange as standard. When using a robot without an ISO flange interface, the product can be mounted to the robot using an adapter plate.



Mounting on the robot for CPB 080-K/100-K/125-K/160-K, shown as an example on CPB 125-K

1. Clean the mounting surfaces on the robot (1) and CPB-K (3).
2. *For mounting on a robot without an ISO flange interface:* Mount adapter plate between robot (1) and CPB-K (3).
3. Insert alignment pin (2) in CPB-K (3).
4. Apply threadlocker to screws (4) and fitting screw (6).
5. Align CPB-K with centering pin (2) on robot and insert CPB-K (3) with centering collar (5) into the fitting bore on the robot (1).
6. Fasten CPB-K (3) to the robot (1) with screws (4) and fitting screw (6).
   ⇨ Observe the tightening torque of the mounting screws, ▸ 5.2.1 [🗋 28].



Mounting adapter plate (4) (shown as an example) to CPB 125-A,
(A= mounting from below; B = mounting from above)

NOTE

If the axial pneumatic feed-throughs are to be used on CPB-A, it is very important to observe the notes in the "Axial pneumatic feed-throughs" chapter, ▸ 5.3.3 [🗋 35].

1. Clean mounting surfaces on CPB-A (2) and adapter plate (4).
2. Insert the adapter plate (4) with two dowel pins (3) or one dowel pin and a centering plate into the bores provided for this purpose.
3. Secure the adapter plate (4) to the CPB-A (2) from above or below with screws (1).
   ⇨ Observe the tightening torque of the mounting screws, ▸ 5.2.1 [🗋 28].
4. Mount the end effector.

5.3 Pneumatic connection

NOTICE

Material damage due to loss of compressed air!

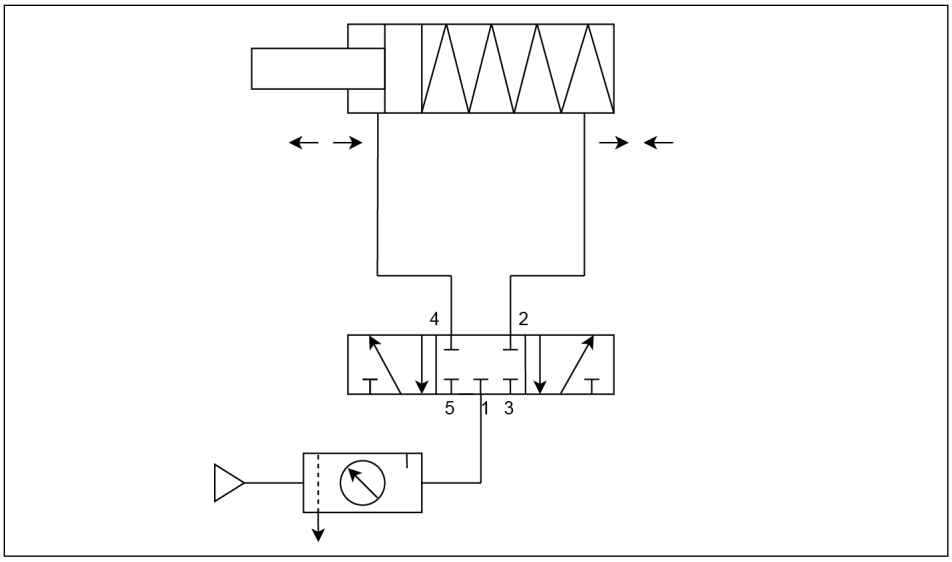
The CPB-A can become loose in the event of a loss of compressed air, however, the connection between CPB-K and CPB-A is ensured. The CPB-K can then no longer decouple a coupled CPB-A or accept a new CPB-A. A loss of compressed air leads to increased wear.

- End the fail-safe operation as soon as possible. To do this, restore the compressed air supply or stop operation of the machine/automated system to eliminate the cause of the failure.
- After a fail-safe operation, check the system for damage and monitor the resumption of normal operation for proper functioning.

NOTE

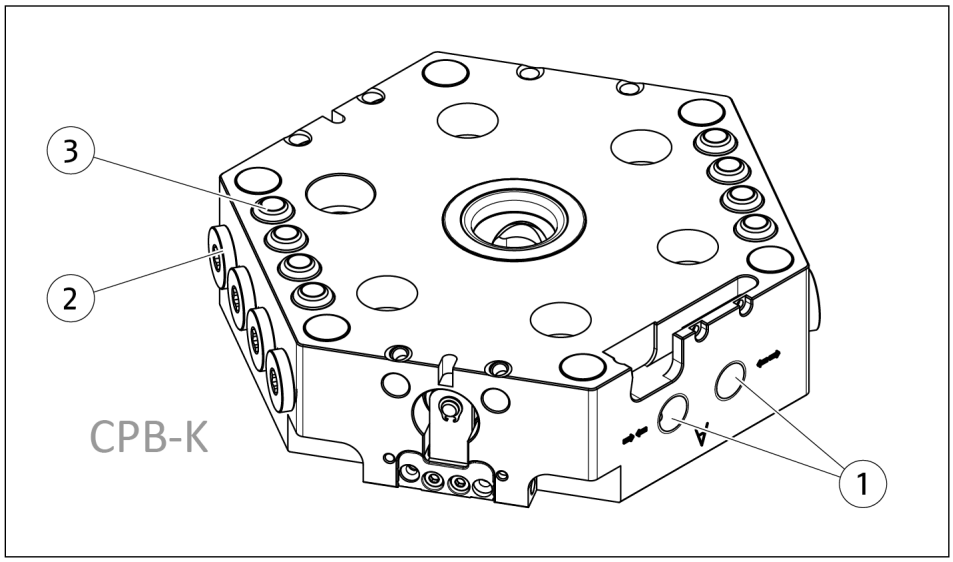
Observe the requirements for the compressed air supply, ▶ 3 [🗋 17].

5.3.1 Example for pneumatic control



Main air connections CPB-K: Locking ->><-, Unlocking <<-->>

5.3.2 Dimensions of the main air connections and pneumatic feed-throughs on CPB-K



Pneumatic connection, shown as an example on CPB 080-K

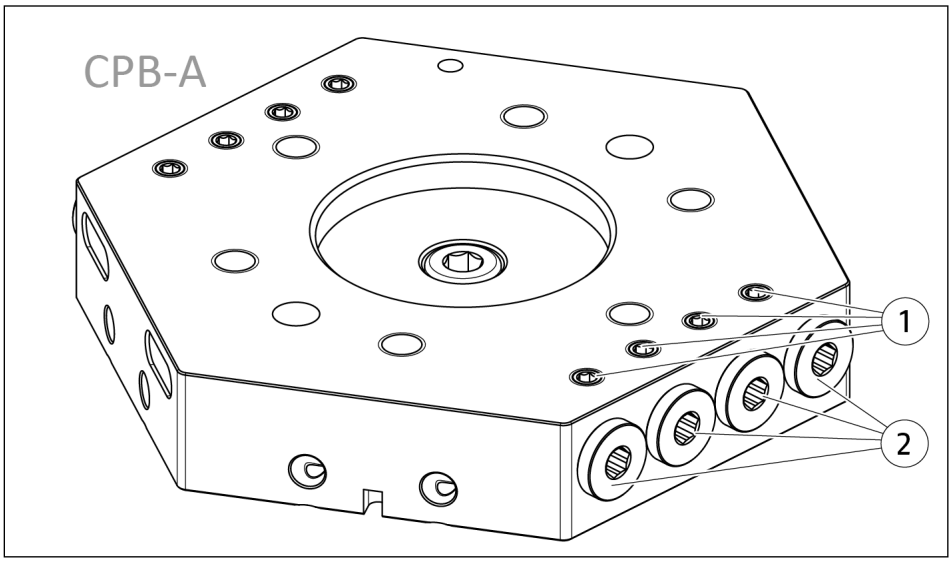
1	Main air connections: Locking ->><-, Unlocking <-->
2	Port for pneumatic feed-through
3	Pneumatic feed-through with rubber bushing

Size	① Main air connections * Locking ->><- Unlocking <-->	② Pneumatic feed-throughs *
040	M5 / 6	6x M5 / 6
050	M5 / 7	6x M5 / 7
063	G1/8 / 6	6x G1/8 / 6
080	G1/8 / 7	8x G1/8 / 7
100	G1/8 / 7	2x G1/8 / 7 4x G3/8 / 12
125	G3/8 / 15	8x G3/8 / 15
160	G3/8 / 15	8x G3/8 / 15

Tab.: Dimensions of compressed air connections
** Thread / Max. depth of engagement from locating surface [mm]*

5.3.3 Axial pneumatic feed-throughs on CPB-A

For pneumatic feed-throughs, the CPB-A has axial ports, which can optionally be used instead of the radial connections.



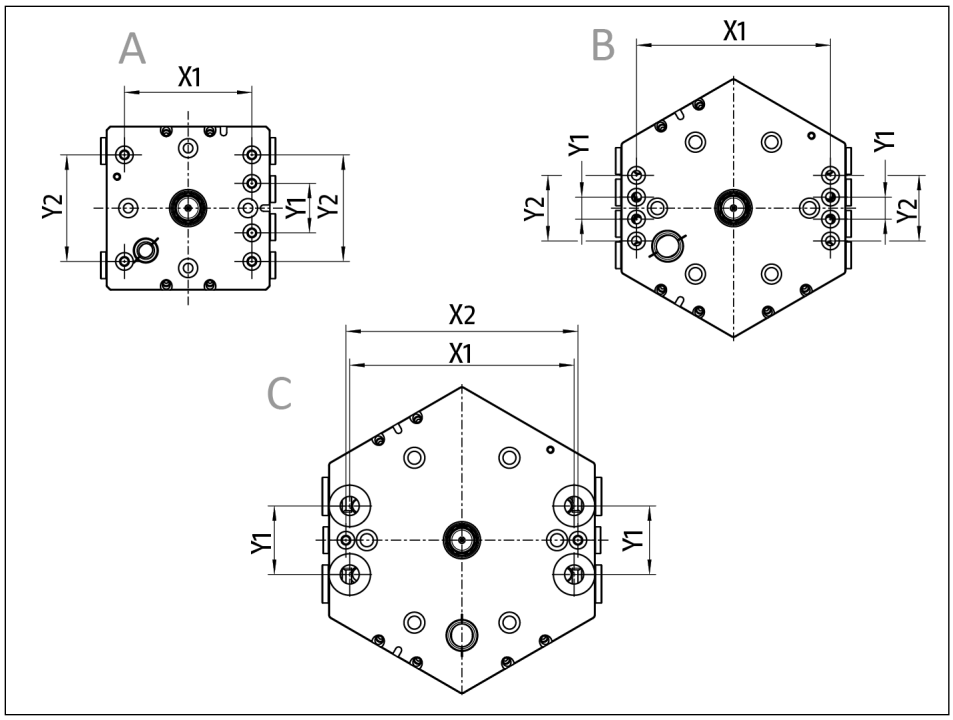
Pneumatic connection, shown as an example on CPB 080-K

1	Axial port for pneumatic feed-through
2	Radial port for pneumatic feed-through

Using the axial connections

1. Remove the grub screws from the axial connections (1) on the underside of the CPB-A.
2. Seal the radial connections (2) with locking screws.
3. Fit adapter plate with O-rings, see following section for position and dimensions.

Position and dimensions of the axial connections



Principle sketch layout variants axial pneumatic feed-throughs

Size	Layout	X1 [mm]	X2 [mm]	Y1 [mm]	Y2 [mm]
040	A	45	-	12.5	37.5
050	A	55	-	16	39
063	A	67	-	26	56
080	B	100	-	13.5	40.5
100	C	108	122	36	-
125	B	154	-	21	63
160	B	190	-	23	69

Tab.: Position of the axial connections

Size	O-ring	Sealing groove [mm]	Sealing groove Ø [mm]	Quantity
040	Ø5x1.5	1.2 +0.1	8 -0.1	6
050	Ø5x1.5	1.2 +0.1	8 -0.1	6
063	Ø7x1.5	1.2 +0.1	10 -0.1	6
080	Ø7x1.5	1.2 +0.1	10 -0.1	8
100	Ø7x1.5	1.2 +0.1	10 -0.1	2
	Ø13x1.5	1.2 +0.1	16 -0.1	4
125	Ø13x1.5	1.2 +0.1	16 -0.1	8
160	Ø13x1.5	1.2 +0.1	16 -0.1	8

Tab.: Dimensions of the axial connections

5.4 Mounting the sensor

The product is equipped for the use of sensors.

- For the exact type designations of suitable sensors, please see catalog datasheet and ▶ 5.4.1 [🗋 37].
- For technical data for the suitable sensors, see Assembly and Operating Manual and catalog datasheet – which can be found at schunk.com.
- Information on handling sensors is available at schunk.com or from SCHUNK contact persons.

5.4.1 Overview of sensors

The **lock/unlock monitoring** checks whether the locking mechanism is locked or unlocked.

The **presence monitoring** for CPB-A checks whether the master and tool have the correct minimum distance and position for locking. A sensor is attached to the CPB-K for this purpose. A presence signal is transmitted on contact with the sensor target integrated in the CPB-A.

NOTE

The change system does not contain any sensors as standard; these are available from SCHUNK as accessories. The catalog data sheet contains more information.

5.4.2 Mounting and checking sensor for lock monitoring

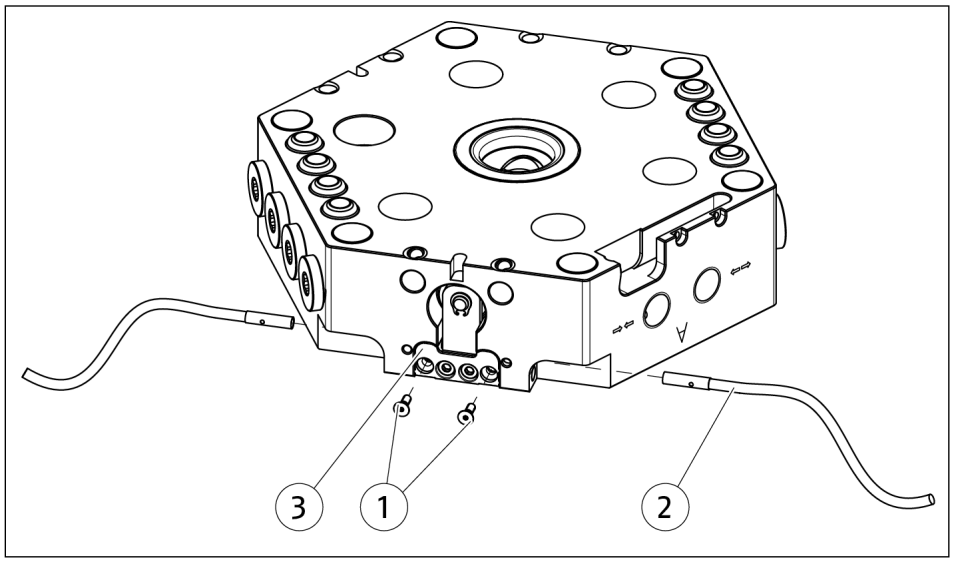
5.4.2.1 Size 040/050/063/080/100

Disassembling CPB-A

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Remove the compressed air pipes on the CPB-K.
4. Disassemble the CPB-K from the robot and safely set the CPB-K aside, ▸ 7.3 [🗋 46].

Installing the sensor

1. Apply medium-strength threadlocker to screws (1).
2. Secure sensors (2) to bracket (3) with screws (1).
   ⇨ Tightening torque [Nm]: 0.3 (TX6)
3. Check sensor for secure hold.



Sensor testing

1. Connect the sensor cable to the robot control system.
2. Connect all compressed air lines.
3. Switch on energy supply.
4. Lock and unlock the product and check the signals of the sensors.

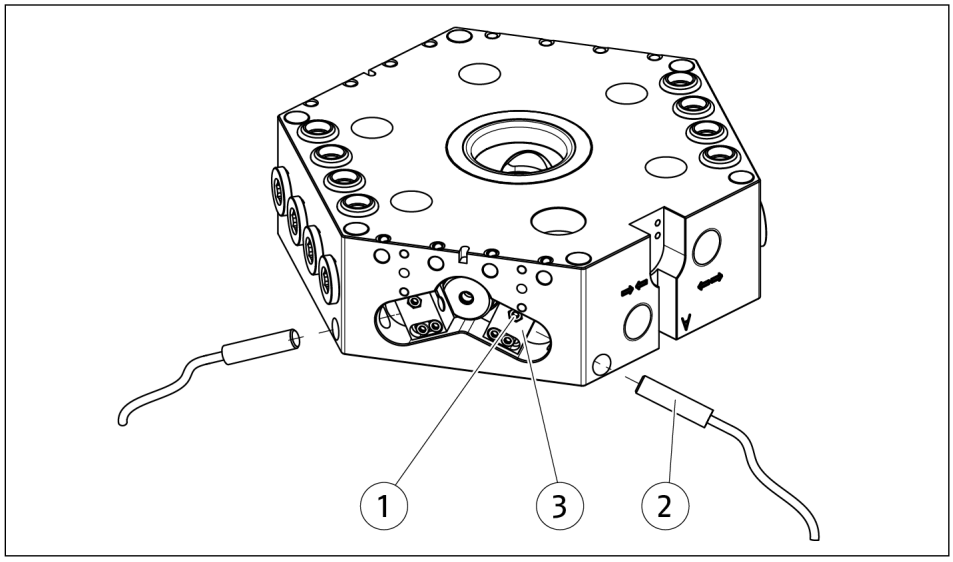
5.4.2.2 Size 125/160

Disassembling CPB-A

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Remove the compressed air pipes on the CPB-K.
4. Disassemble the CPB-K from the robot and safely set the CPB-K aside, ▶ 7.3 [🗋 46].

Installing the sensor

1. Apply medium-strength threadlocker to the screw (1).
2. Secure sensor (2) to bracket (3) with screw (1).
   ⇨ Tightening torque [Nm]: 0.5 (SW 2.5)
3. Check sensor for secure hold.
4. Install second sensor in the same way.



Sensor testing

1. Connect the sensor cable to the robot control system.
2. Connect all compressed air lines.
3. Switch on energy supply.
4. Lock and unlock the product and check the signals of the sensors.

5.4.3 Installing the sensor for the tool presence monitoring.

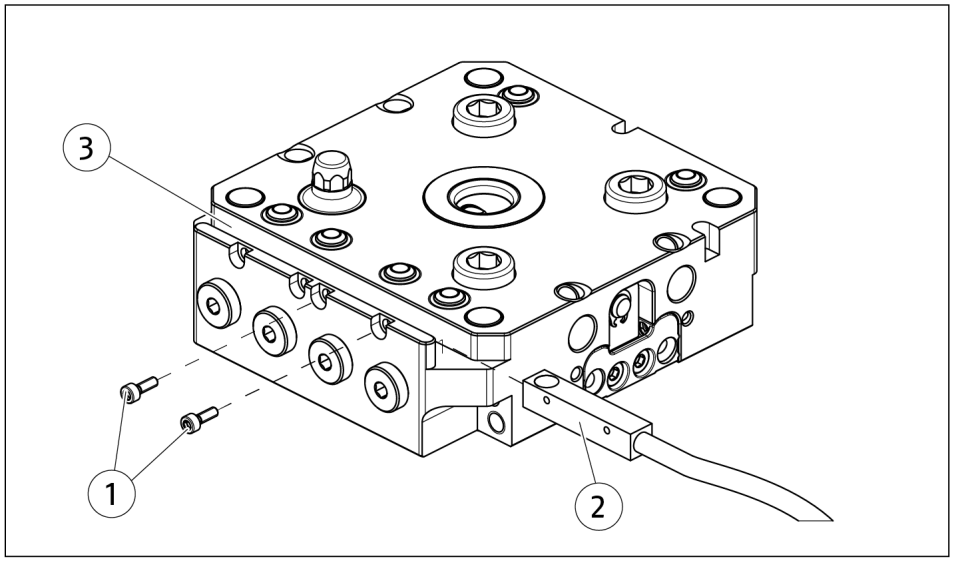
5.4.3.1 Size 040/050

Disassembling CPB-A

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Remove the compressed air pipes on the CPB-K.
4. Disassemble the CPB-K from the robot and safely set the CPB-K aside, ▸ 7.3 [🗋 46].

Installing the sensor

1. Apply medium-strength threadlocker to screws (1).
2. Fasten sensor (2) with screws (1) in recess (3).
   ⇨ Tightening torque [Nm]: 0.3 (SW 1.5)
3. Ensure that the sensor is positioned at the bottom of the recess.



Sensor testing

1. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.
2. Mount CPB-K to the robot, ▸ 5.2 [🗋 26].

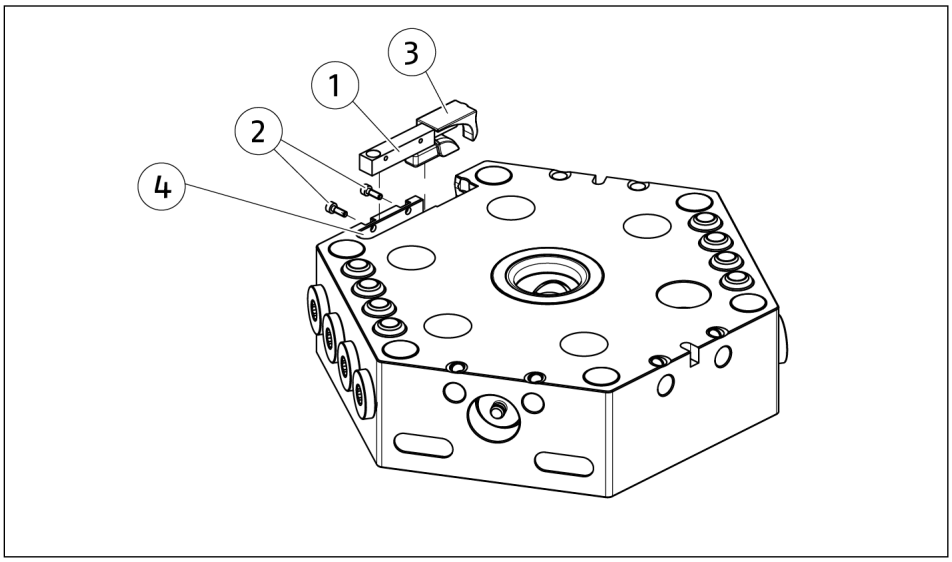
5.4.3.2 Size 063/080/100

Disassembling CPB-A

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Remove the compressed air pipes on the CPB-K.
4. Disassemble the CPB-K from the robot and safely set the CPB-K aside, ▸ 7.3 [🗋 46].

Installing the sensor

1. Apply medium-strength threadlocker to screws (2).
2. Insert the sensor (1) together with the cable guide (3) into the recess (4) and fasten with screws (2).
   ⇨ Tightening torque [Nm]: 0.3 (SW 1.5)
3. Ensure that the sensor is positioned at the bottom of the recess.



Sensor testing

1. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.
2. Mount CPB-K to the robot, ▸ 5.2 [🗋 26].

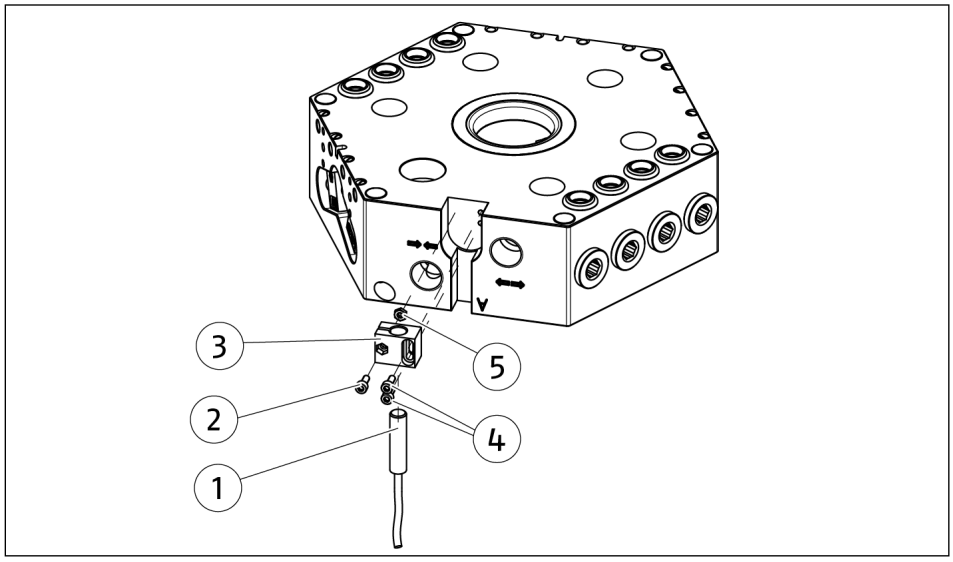
5.4.3.3 Size 125/160

Disassembling CPB-A

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Remove the compressed air pipes on the CPB-K.
4. Disassemble the CPB-K from the robot and safely set the CPB-K aside, ▸ 7.3 [🗋 46].

Installing the sensor

1. Apply medium-strength threadlocker to screws (4).
2. Insert the hexagon nut (5) into the bracket (3).
3. Fasten bracket (3) to the CPB-K using screws (4).
4. Apply medium-strength threadlocker to screw (2).
5. Secure sensor (1) to bracket (3) with screw (2).
   ⇨ Tightening torque [Nm]: 0.5 (SW 2.5)
6. Check sensor for secure hold.



Sensor testing

1. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.
2. Mount CPB-K to the robot, ▸ 5.2 [🗋 26].

6 Troubleshooting

6.1 Product does not lock or unlock

Possible cause	Possible cause
Dirt between CPB-K and CPB-A.	Separate and clean CPB-K and CPB-A. ▶ 7.4 [🗋 48]
The clamping surfaces on the clamping slides and clamping pin are dirty.	Remove the CPB-A clamping pin and clean the clamping surfaces on the clamping slides and clamping pin
Pressure drops below minimum.	Check compressed air lines. ▶ 5.3 [🗋 33]
	Checking operating pressure (min. 5 bar)
	Check seals, disassemble product if necessary and replace seals. ▶ 7.5 [🗋 49]
Compressed air in the locking or unlocking connection cannot escape.	Vent connection. ▶ 5.3 [🗋 33]
Defective air connections Min. hose diameter below minimum	Check air supply, ▶ 5.3 [🗋 33]
CPB-K and CPB-A have a greater offset to each other than permitted.	Check whether the CPB-A is properly placed in the storage rack. Teach the robot again to bring CPB-A and CPB-K closer together before attempting to lock. For the permissible offset, see ▶ 3.4 [🗋 19].
A component is broken (e.g. due to overloading)	Replace component or send it to SCHUNK for repair.
Excess tensile load on clamping pins.	Reduce support weight.

6.2 Locking or unlocking signal faulty

Possible cause	Corrective action
Sensor defective or incorrectly adjusted.	Adjust or replace sensor. ▶ 7.6 [🗋 52]
Sensor cable damaged or connection loose.	Check cables and connections for damage and replace, if necessary.

6.3 Tool presence monitoring faulty

Possible cause	Corrective action
Sensor defective or incorrectly adjusted.	Adjust or replace sensor. ▶ 7.6 [🗋 52]
Sensor cable damaged or connection loose.	Check cables and connections for damage and replace, if necessary.
End effector not placed correctly.	Check end effector in the storage rack. Re-teach the robot if necessary.

6.4 Electrical signals are not transmitted

NOTE

Troubleshooting notes can be found in the separate assembly and operating manual for the *electrical* optional module, ▸ 1.1.4 [🗋 7].

7 Maintenance

7.1 Maintenance intervals

NOTICE

Material damage due to hardening lubricants!

Lubricants harden more quickly at temperatures above 60°C, leading to possible product damage.

- Reduce the lubricant intervals accordingly.

Original spare parts

Use only original spare parts of SCHUNK when replacing spare and wear parts.

Ambient conditions and operating conditions	Maintenance interval	Maintenance work
in dirty environments or with a tool change > 1 time per minute	weekly	Clean all parts thoroughly, check for damage and wear and grease with a lint-free cloth or brush, ▸ 7.4 [🗋 48].
tool change < 1 time per week	monthly	Check product for tightness, replace seals if necessary, ▸ 7.5 [🗋 49].
		Check fitting screw for damage and wear, replace if necessary.
		Check sensors for damage and wear, replace if necessary, ▸ 7.6 [🗋 52].
		Check optional modules for damage and wear, clean if necessary and change seals, see separate assembly and operating manuals for the optional modules COB.
all	as required	Send damaged products to SCHUNK for repair.

7.2 Lubricants/greasing areas

During maintenance, treat all greased areas with lubricant. Thinly apply lubricant with a lint-free cloth.

SCHUNK recommends the listed lubricant.

Lubricant point	Lubricant
Fitting screw	SCHUNK grease 1
Fitted bushing	
Seals and sealing surfaces	

Details regarding SCHUNK lubricant designations are available at **schunk.com/lubricants**.

The product contains food-compliant lubricants as standard. **The requirements of standard EN 1672-2:2020 are not fully met.**

NOTE

- Change contaminated food-compliant lubricant.
- Observe information in the safety data sheet from the lubricant manufacturer.

7.3 Removing the product from the robot arm

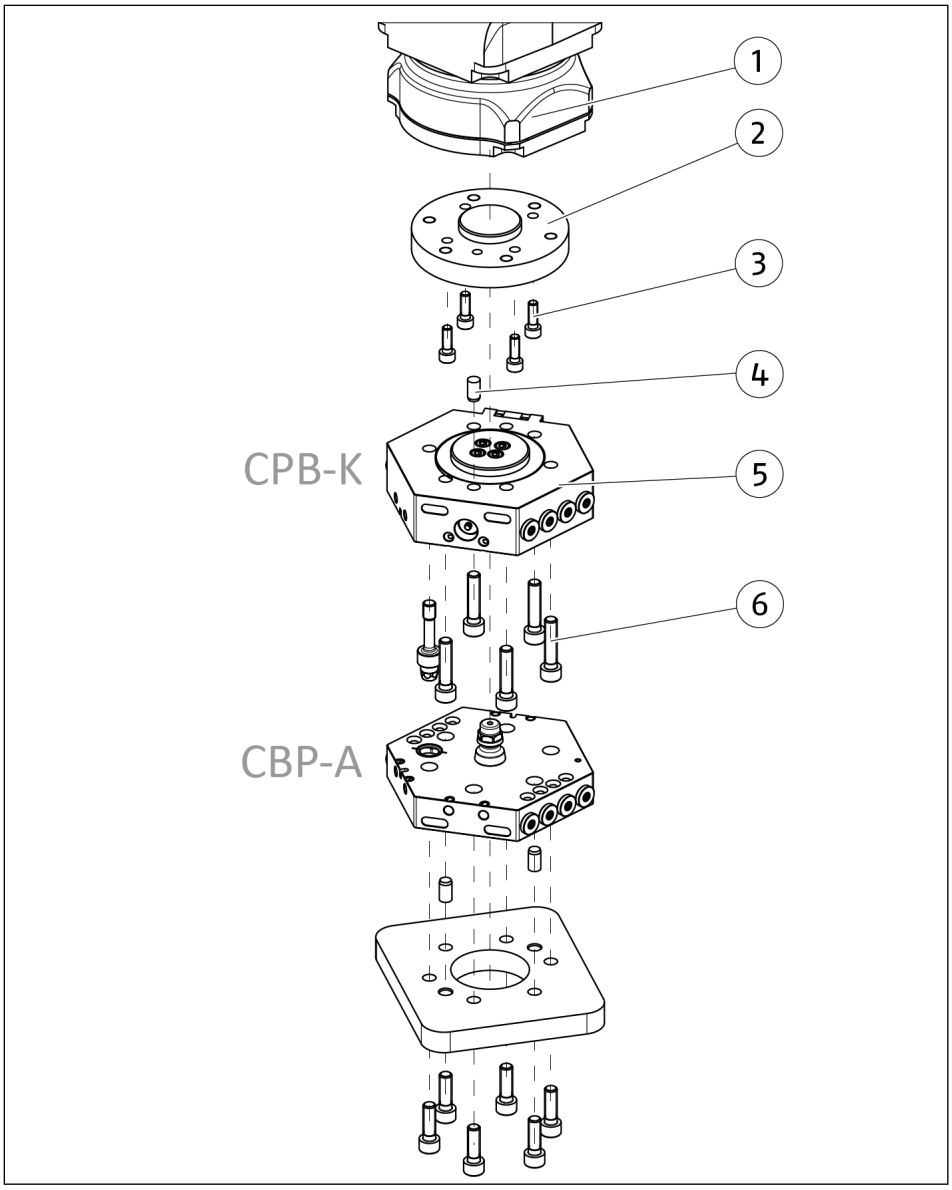
⚠ WARNING

Risk of injury due to unexpected movements and falling tools!

If the energy supply is switched on or if residual energy is still present in the system, this can cause components to move unexpectedly or fall, which may result in serious injuries.

- Before starting any work on the product: Switch off the energy supply and secure against re-connection.
- Ensure that no residual energy remains in the system.
- Only carry out maintenance work when the tool is placed in the storage rack or secured against falling.

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off and deactivate all activated supply circuits (e.g. electrical, air, water, etc.).
3. Ensure that there is no residual energy in the system.
4. Remove the compressed air pipes on the CPB-K.
5. Loosen screws (6) and remove CPB-K (5) from the robot (1). Make sure that the dowel pin (4) does not fall off.
6. Place down the CPB-K (5).
7. **When using an adapter plate:** If necessary, loosen the screws (3) and remove the adapter plate (2) from the robot (1).



Disassembling the product from the robot, shown as an example on CPB 080-K

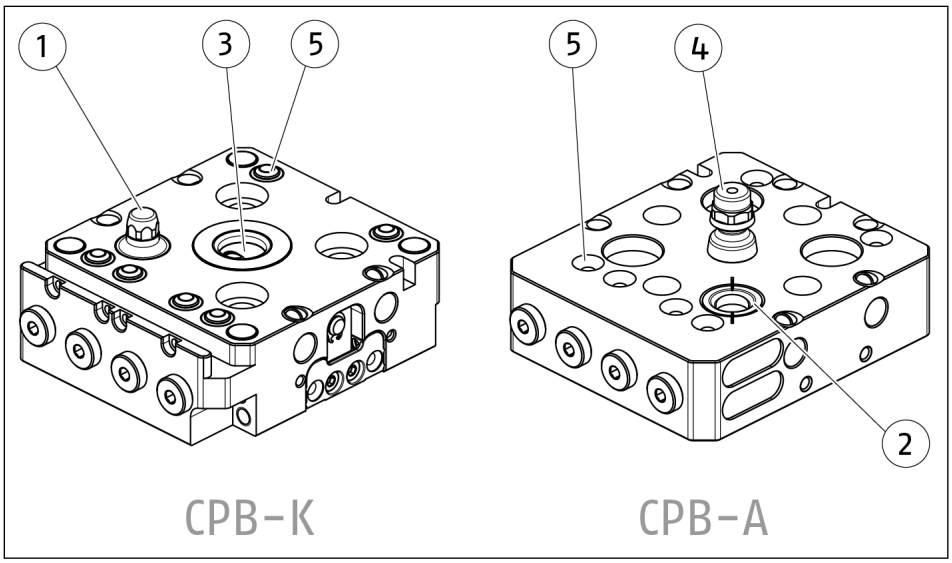
7.4 Clean and lubricate product

- CPB-A is in the storage rack, CPB-K has been removed from the robot, ▸ 7.3 [🗋 46]

1. Remove lubricant residue and dirt from the fitting screw (1), fitting bush (2), clamping slide (3), storage pin (4) and sealing surfaces (5).
2. Generously lubricate the fitting screw (1), fitting bush (2) and sealing surfaces (5), ▸ 7.2 [🗋 46].

NOTE

The modules are sufficiently lubricated at the factory on delivery.



CPB Clean with a non-fibrous cloth, shown as an example at CPB 040

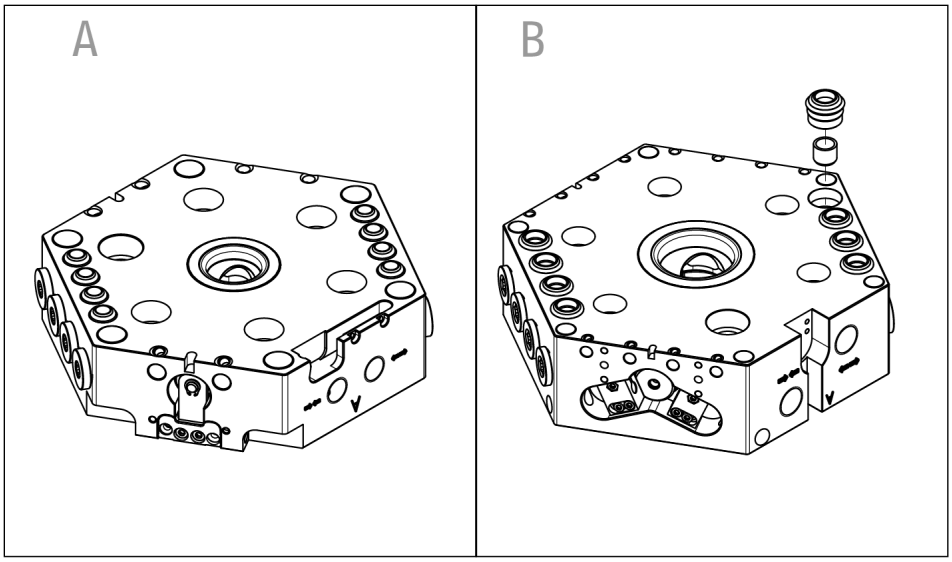
7.5 Replacing seals

7.5.1 Overview of the seals

NOTE
For information on the available seal kits, see chapter ▶ 1.4 [🗋 9].

The seals on the pneumatic feed-throughs in the CPB-K may look as follows:

- Gaskets (A)
- Gaskets with press sleeve (B)



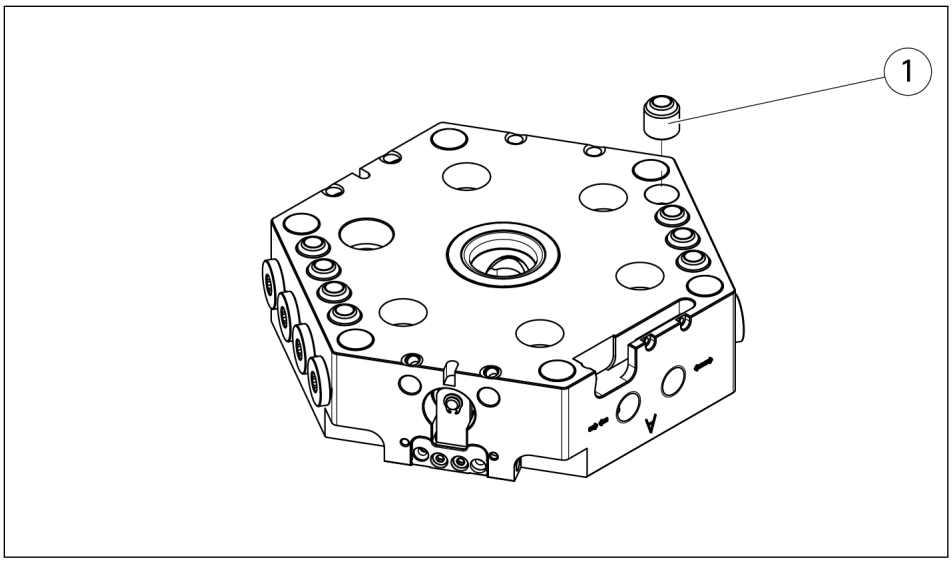
Seals on the pneumatic feed-throughs

Size	A	B
040	✓	
050	✓	
063	✓	
080	✓	
100	✓	✓
125		✓
160		✓

7.5.2 Change rubber bushing

- CPB-A is in the storage rack, CPB-K has been removed from the robot, ▶ 7.3 [🗋 46]

1. Remove damaged rubber bushing (1).
2. Lightly lubricate the new rubber bushing (1), ▶ 7.2 [🗋 46].
3. Carefully insert the rubber bushing (1) into the bore with the flat end up to the stop. The conical end points upwards.

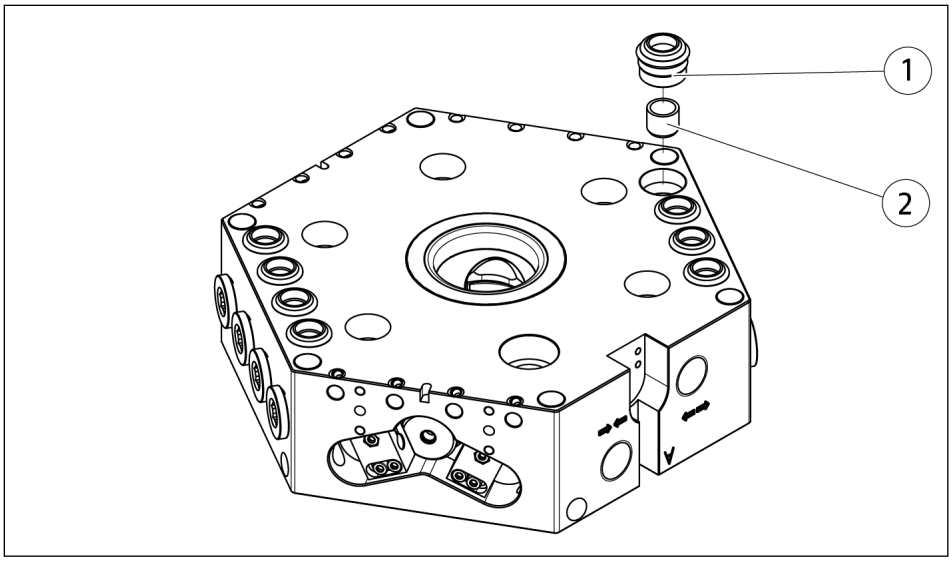


Change rubber bushing

7.5.3 Replace rubber bushing with sleeve

- CPB-A is in the storage rack, CPB-K has been removed from the robot, ▶ 7.3 [🗋 46]

1. Remove damaged rubber bushing (1) and sleeve (2).
2. Lightly lubricate the new rubber bushing (1), ▶ 7.2 [🗋 46].
3. Carefully insert the rubber bushing (1) into the bore with the flat end up to the stop. The conical end points upwards.
4. Press sleeve (2) into the rubber bushing (1) up to the stop.



Replace rubber bushing with sleeve

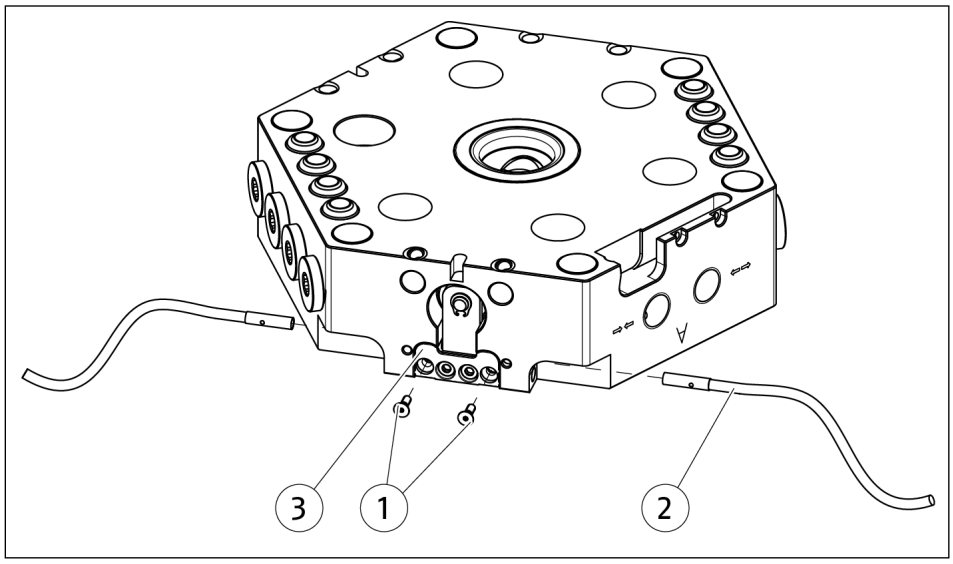
7.6 Change sensors

7.6.1 Changing the sensor for lock monitoring

7.6.1.1 Size 040/050/063/080/100

Removing a defective sensor

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Check sensor cable for damage, replace if necessary.
3. Lock and unlock the product and check the signals of the sensors.
4. Switch off the power supply and ensure that there is no residual energy in the system.
5. Loosen the screw (1) on the side of the damaged sensor and remove the damaged sensor (2) from the bracket (3).



Changing sensor for lock monitoring

Mounting new sensor

1. Slide new sensor (2) into the bracket as far as the end stop (3).
2. Apply medium-strength threadlocker to screws (1).
3. Secure sensor (2) into bracket (3) with screws (1).
   ⇨ Tightening torque [Nm]: 0.3 (TX6)
4. Check sensor for secure hold.

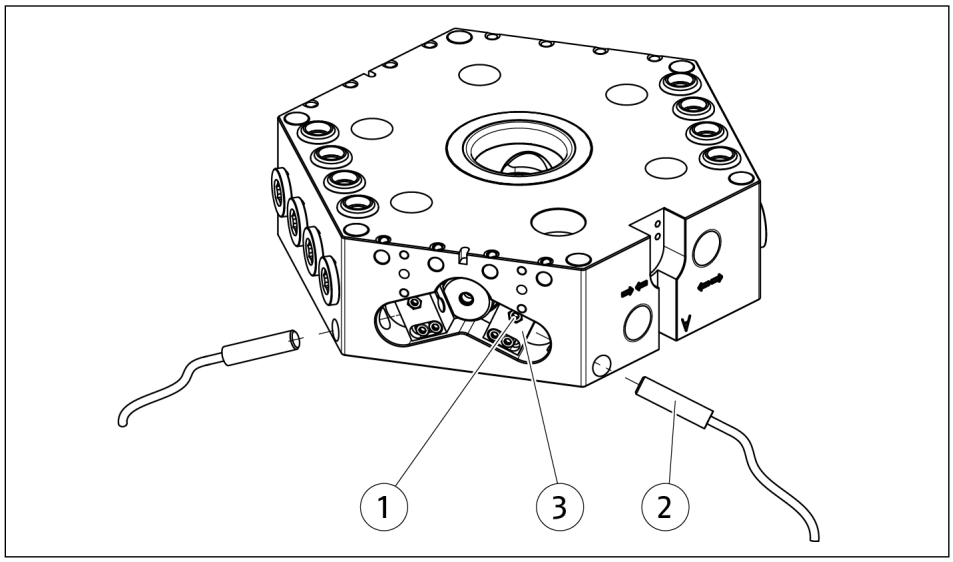
Check the new sensor

1. Switch on energy supply.
   ⇨ The sensor LED will illuminate.
   ⇨ Sensor signal is ON.
2. Lock and unlock the product and check the signals of the sensors.

7.6.1.2 Size 125/160

Removing a defective sensor

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Check sensor cable for damage, replace if necessary.
3. Lock and unlock the product and check the signals of the sensors.
4. Switch off the power supply and ensure that there is no residual energy in the system.
5. Remove screw (1) and damaged sensor (2) from bracket (3).



Changing sensor for lock monitoring

Mounting a new sensor

1. Slide new sensor (2) into the bracket as far as the end stop (3).
2. Apply medium-strength threadlocker to the screw (1).
3. Secure sensor (2) to bracket (3) with screw (1).
   ⇨ Tightening torque [Nm]: 0.5 (SW 2.5)

Check the new sensor

1. Switch on energy supply.
   ⇨ The sensor LED will illuminate.
   ⇨ Sensor signal is ON.
2. Lock and unlock the product and check the signals of the sensors.

7.6.2 Replacing the sensor for tool presence monitoring

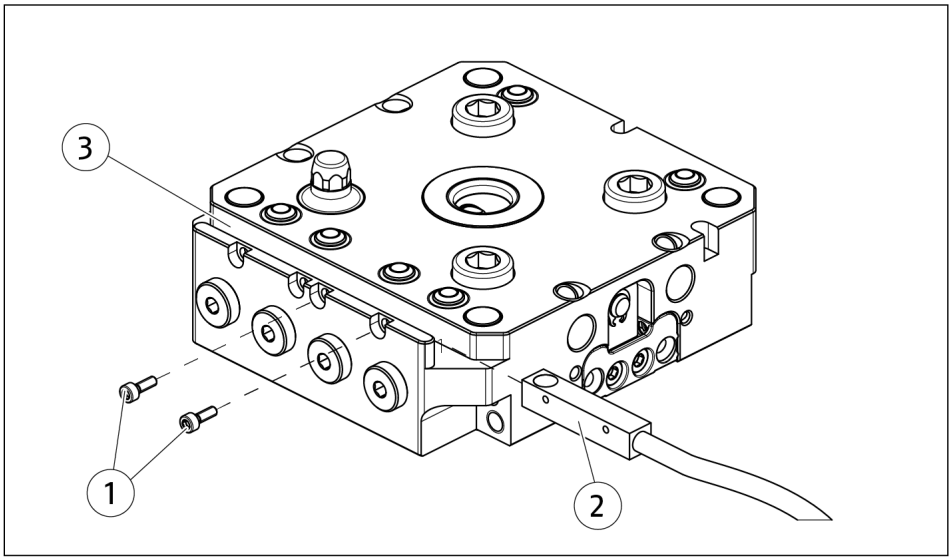
7.6.2.1 Size 040/050

Removing a defective sensor

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Loosen the screws (1).
4. Remove sensor (2).

Mounting and checking new sensor

1. Apply medium-strength threadlocker to screws (1).
2. Secure new sensor in recess (3) with screws (1).
   ⇨ Tightening torque [Nm]: 0.3 (SW 1.5)
3. Ensure that the sensor is positioned at the bottom of the recess.
4. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.



Replacing the sensor for presence monitoring

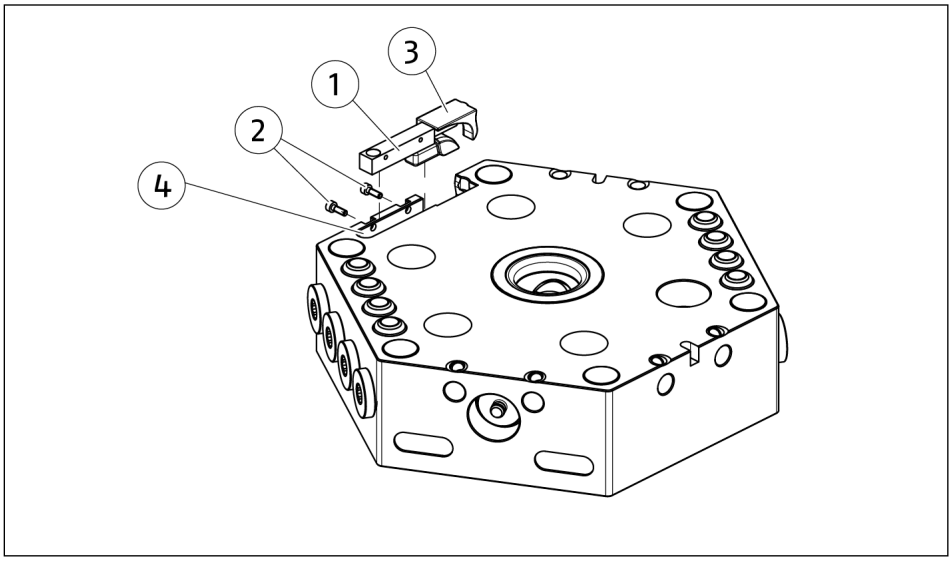
7.6.2.2 Size 063/080/100

Removing a defective sensor

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Undo the screws (2).
4. Remove the sensor (1) together with the cable guide (3).

Mounting and checking the new sensor

1. Apply medium-strength threadlocker to screws (2).
2. Insert the sensor (1) together with the cable guide (3) into the recess (4) and fasten with screws (2).
   ⇨ Tightening torque [Nm]: 0.3 (SW 1.5)
3. Ensure that the sensor is positioned at the bottom of the recess.
4. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.



Replacing the sensor for presence monitoring

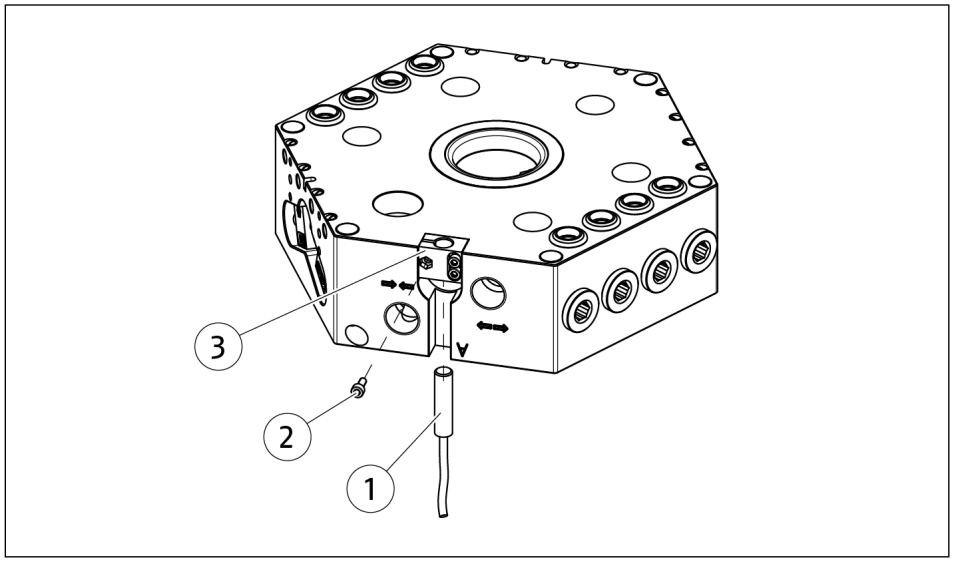
7.6.2.3 Size 125/160

Removing a defective sensor

1. Place the CPB-A in the storage rack, secure and uncouple it.
2. Switch off the power supply and ensure that there is no residual energy in the system.
3. Undo screw (2).
4. Remove sensor (1).

Mounting and checking new sensor

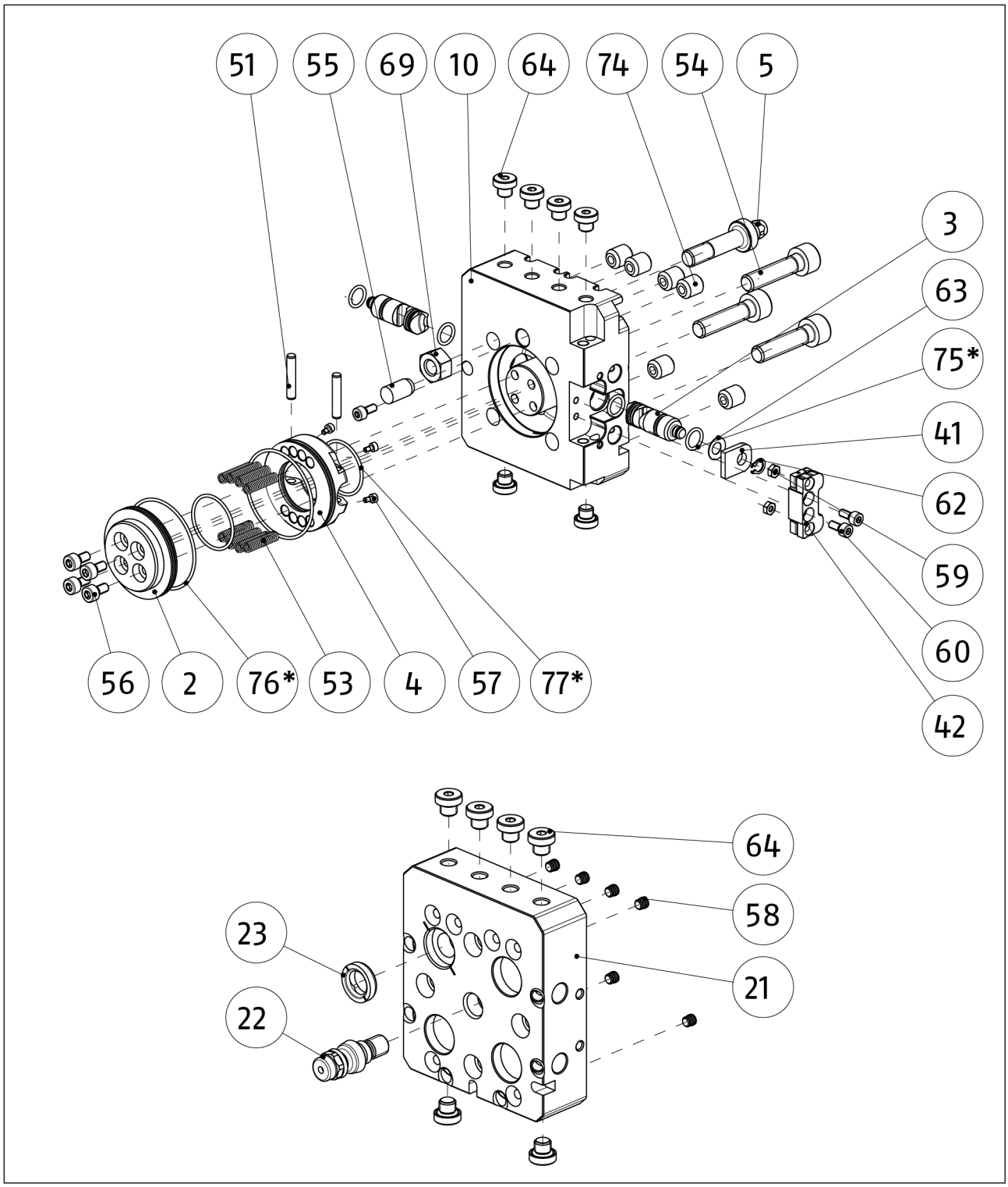
1. Slide new sensor (1) into the bracket as far as the end stop (3).
2. Apply medium-strength threadlocker to screw (2).
3. Secure sensor (1) to bracket (3) with screw (2).
   ⇨ Tightening torque [Nm]: 0.5 (SW 2.5)
4. Check sensor for secure hold.
5. Hold a ferromagnetic object on the sensor surface and test the presence monitoring LED.
   ⇨ The sensor LED will illuminate.



Replacing the sensor for presence monitoring

7.7 Assembly drawings

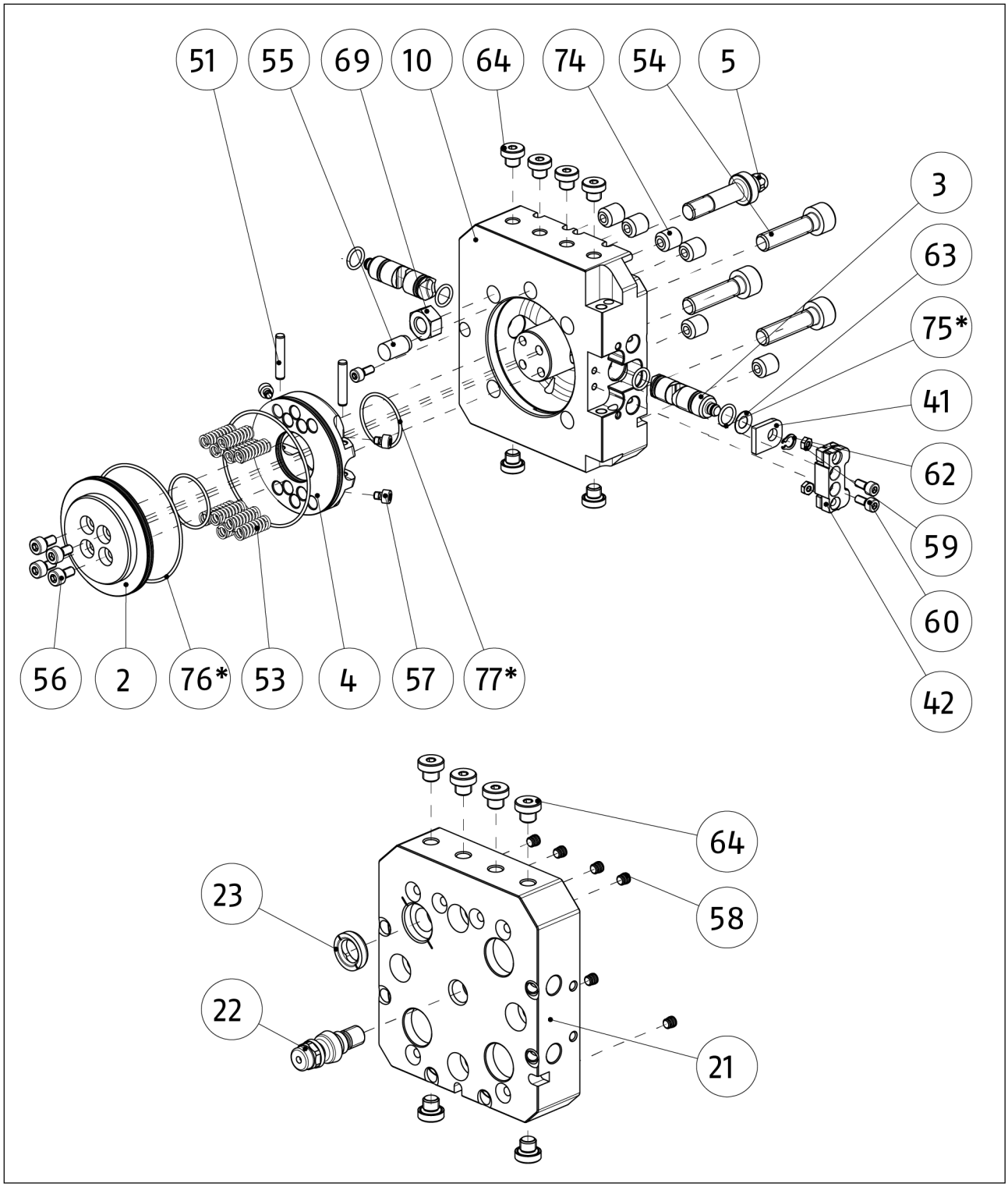
7.7.1 Size 040



Assembly of CPB 040-K (top) and CPB 040-A (bottom)

* Spare- and Wearing parts

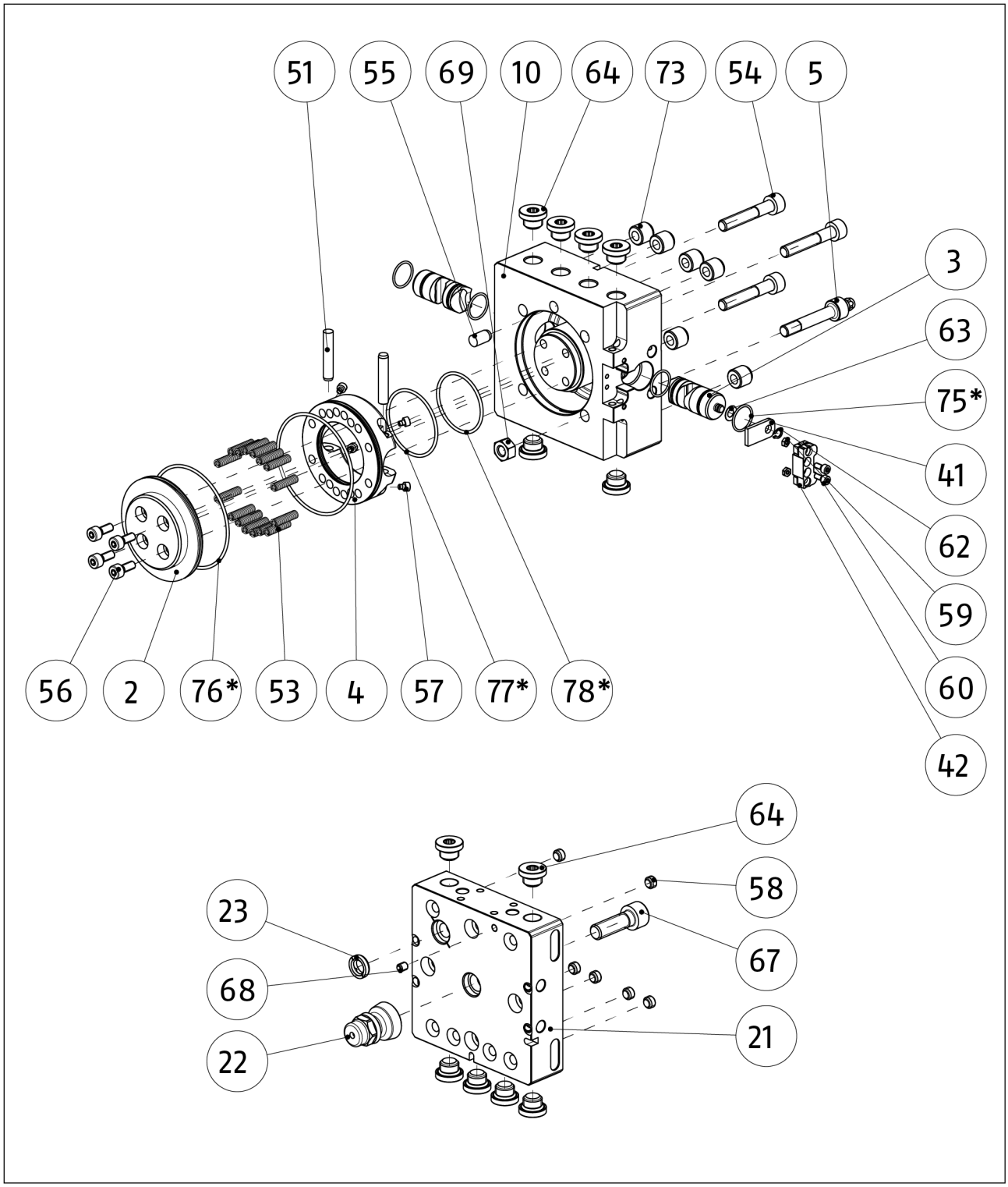
7.7.2 Size 050



Assembly of CPBCPB 050-K and CPB 050-A (bottom)

* Spare- and Wearing parts

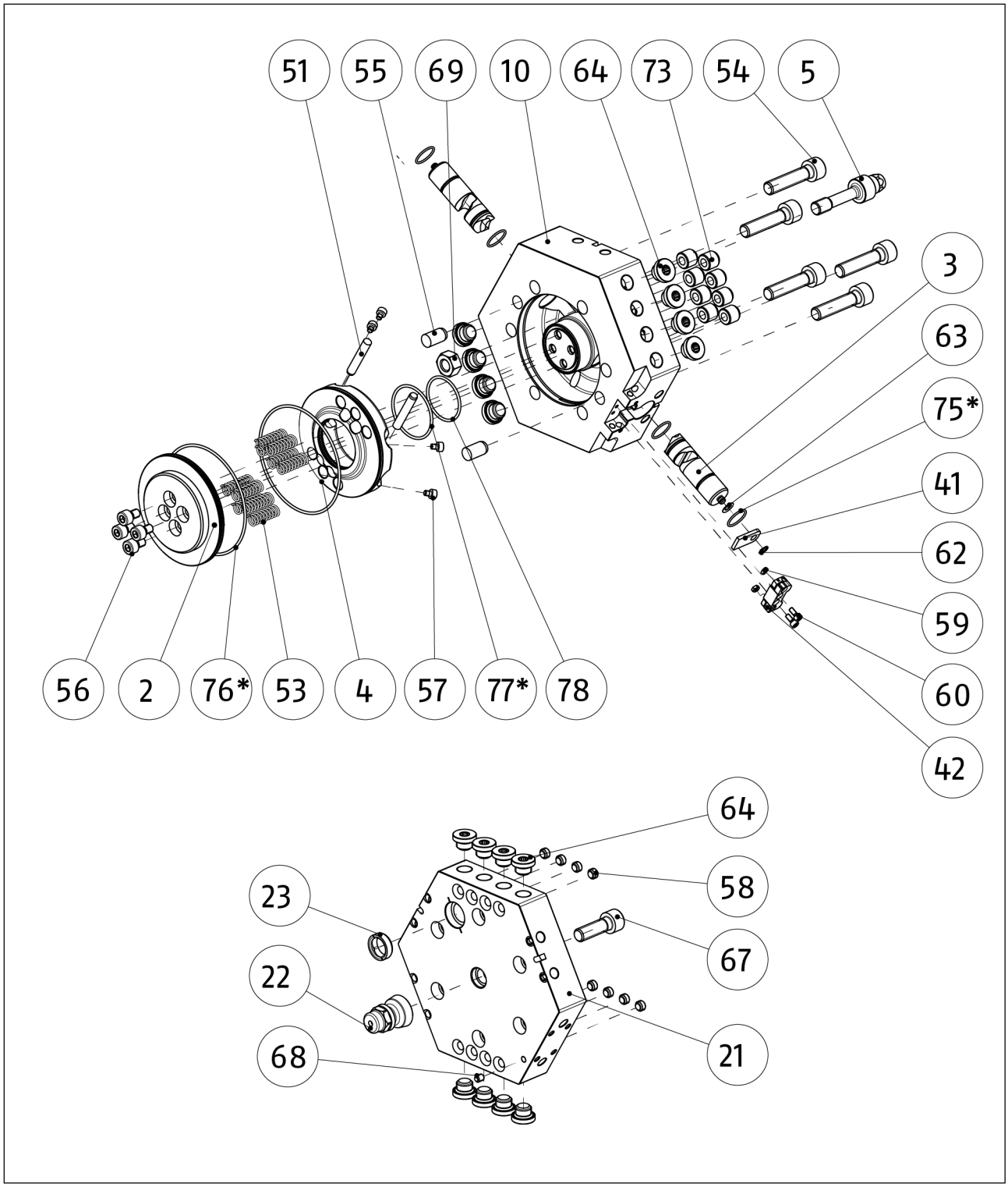
7.7.3 Size 063



Assembly of CPB 063-K (top) and CPB 063-A (bottom)

* Spare- and Wearing parts

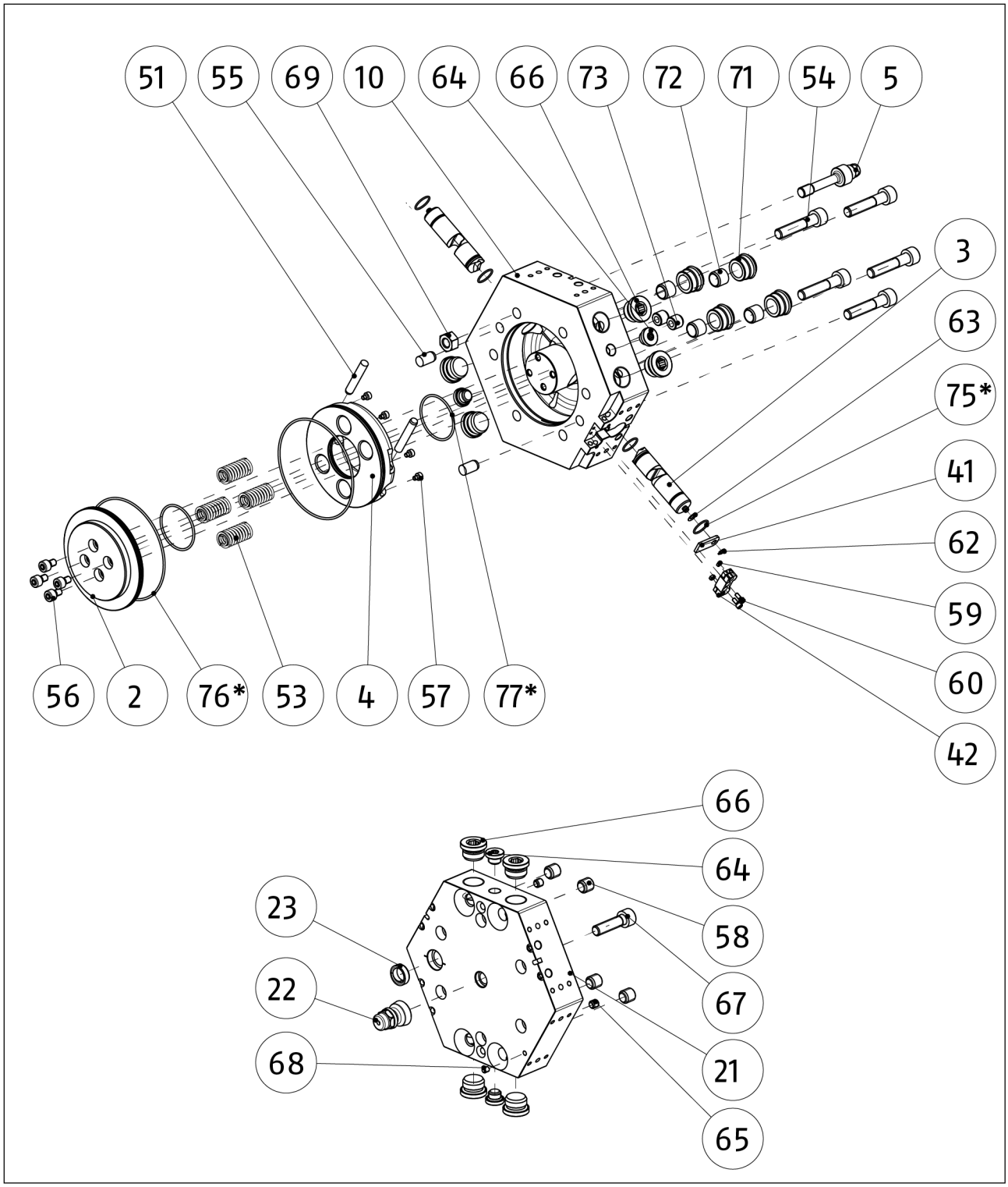
7.7.4 Size 080



Assembly of CPB 080-K and CPB 080-A (bottom)

* Spare- and Wearing parts

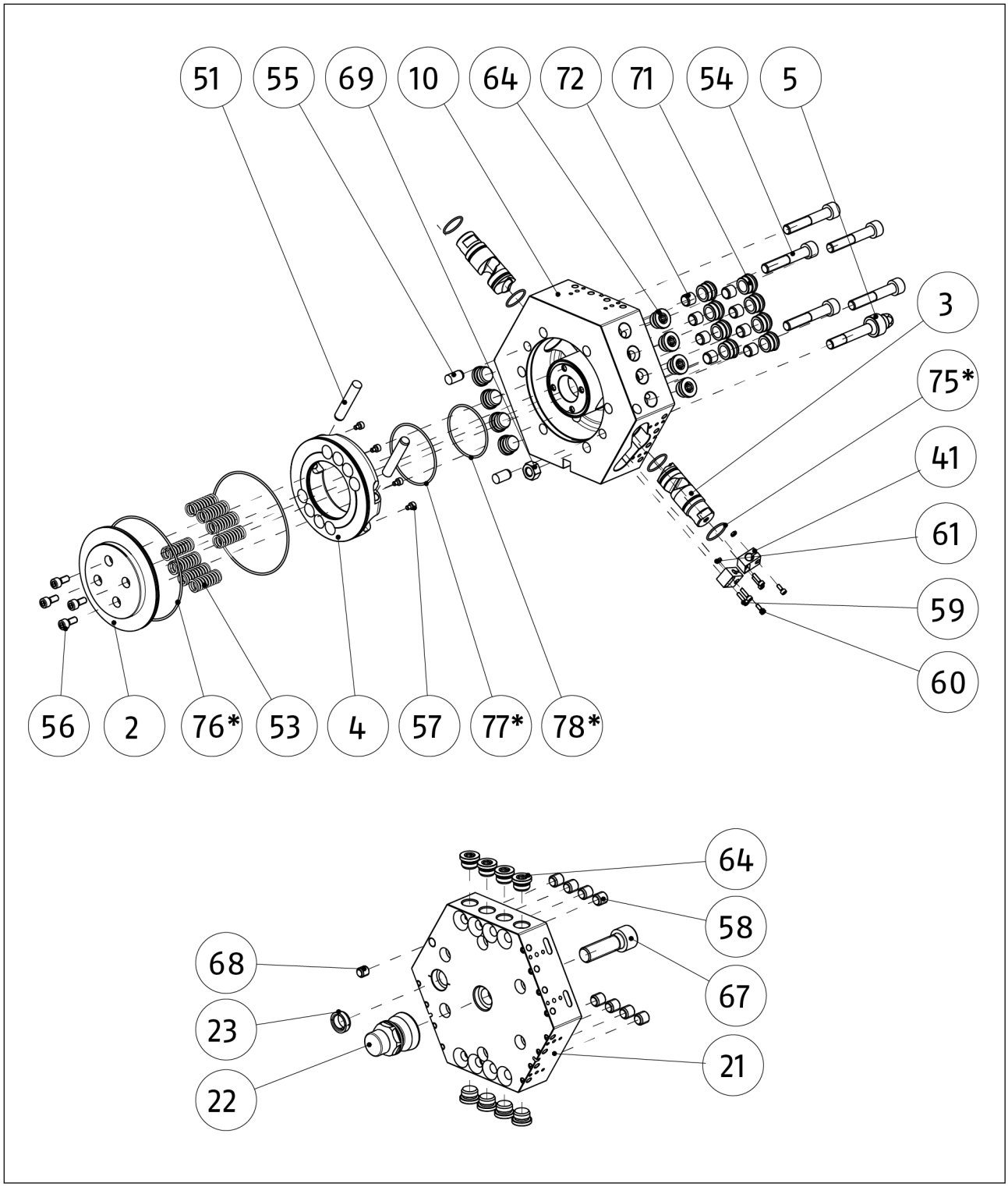
7.7.5 Size 100



Assembly of CPB 100-K (top) and CPB 100-A (bottom)

* Spare- and Wearing parts

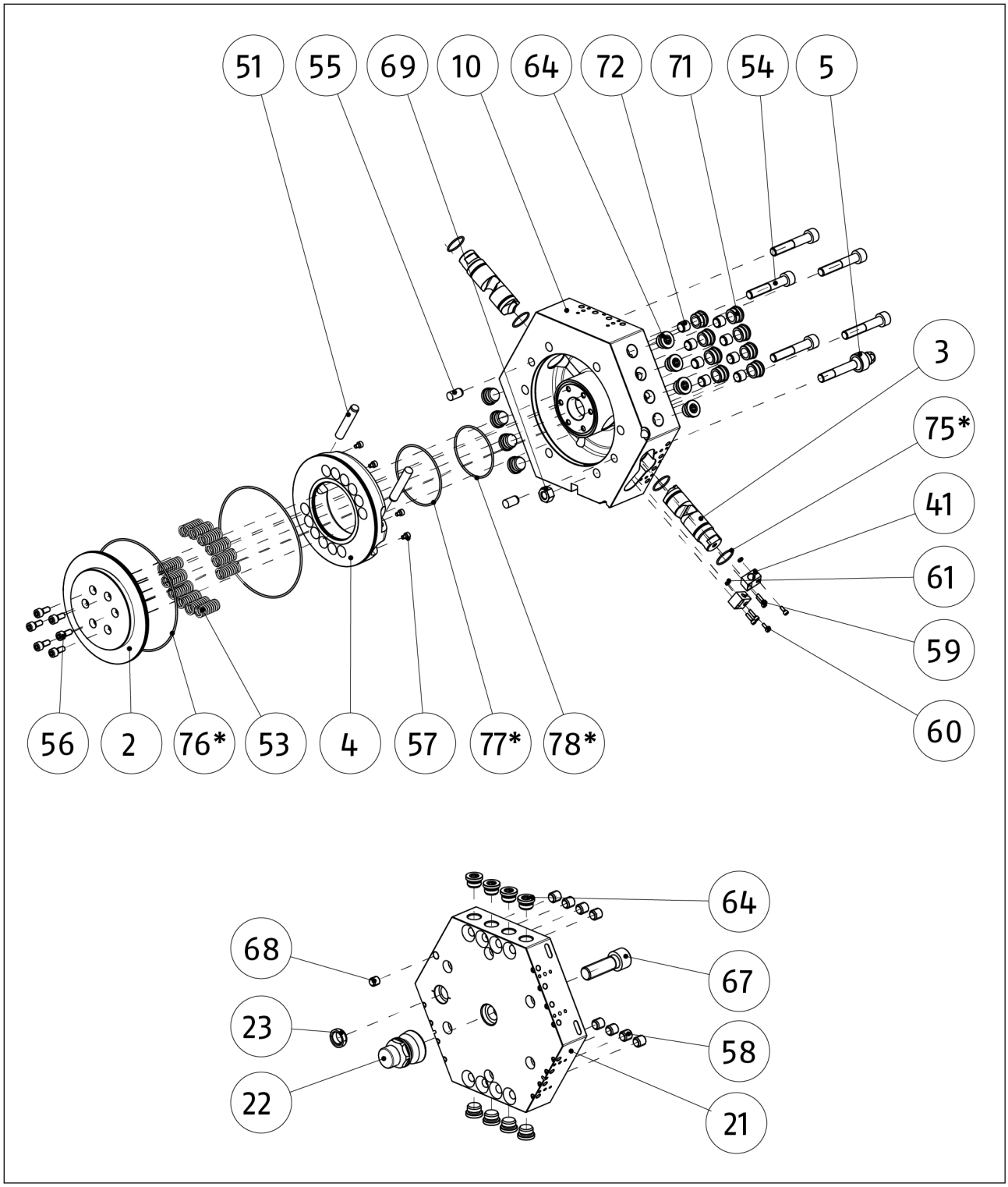
7.7.6 Size 125



Assembly of CPB 125-K (top) and CPB 125-A (bottom)

* Spare- and Wearing parts

7.7.7 Size 160



Assembly of CPS 160-K (top) and CPS 160-A (bottom)

* Spare- and Wearing parts

8 Disassembly and disposal

⚠ WARNING

Risk of injury due to unexpected movements!

If the power supply is switched on or residual energy remains in the system, components can move unexpectedly and cause serious injuries.

- Before starting any work on the product: Switch off the power supply and secure against restarting.
- Make sure, that no residual energy remains in the system.

- Disconnect the entire energy supply from the product, discharge any accumulated residual energy.
- Remove any lubricant and dispose of in an environmentally friendly manner.
- Follow local regulations on dispatching product components for recycling or proper disposal.

9 Translation of the original declaration of incorporation

in terms of the Directive 2006/42/EG, Annex II, Part 1 Section B.

Manufacturer/ Distributor	SCHUNK SE & Co. KG Spanntechnik | Greiftechnik | Automatisierungstechnik Bahnhofstr. 106 – 134 D–74348 Lauffen/Neckar

We hereby declare that the partly completed machine described below

Product designation:	Tool changer / CPB /pneumatic
ID number	1595203, 1595207, 1595210, 1595211, 1595213, 1595214, 1595216, 1595217, 1595219, 1595220, 1595221, 1595223, 1595224, 1595225

meets the following basic occupational health and safety of the Machinery Directive 2006/42/EC:

No. 1.1.1, No. 1.1.2, No. 1.1.3, No. 1.1.5, No. 1.3.2, No. 1.5.3, No. 1.5.4, No. 1.5.6, No. 1.5.8, No. 1.5.10, No. 1.5.11, No. 1.5.13

The partly completed machinery may not be put into operation until it has been confirmed that the machine into which the partly completed machinery is to be installed complies with the provisions of the Machinery Directive (2006/42/EC). The declaration shall be rendered invalid if modifications are made to the product.

Applied harmonized standards, especially:

EN ISO 12100:2010	Safety of machinery – General principles for design – Risk assessment and risk reduction

The special technical documentation according to Annex VII, Part B, belonging to the partly completed machine, has been created.

Person authorized to compile the technical documentation:
Stefanie Walter, Address: see manufacturer's address

Signature: see original declaration

Dr.-Ing. Manuel Baumeister,
Head of Systems Engineering,
Technology & Innovation

Lauffen/Neckar, June 2025

10 UKCA declaration of incorporation

in accordance with the Supply of Machinery (Safety) Regulations 2008.

Manufacturer/ Distributor	SCHUNK Intec Limited Clamping and gripping technology 3 Drakes Mews, Crownhill MK8 0ER Milton Keynes

We hereby declare that on the date of the declaration the following partly completed machine complied with all basic safety and health regulations found in the
"Supply of Machinery (Safety) Regulations 2008".
The declaration shall be rendered invalid if modifications are made to the product.

Product designation:	Tool changer / CPB / pneumatic
ID number	1595203, 1595207, 1595210, 1595211, 1595213, 1595214, 1595216, 1595217, 1595219, 1595220, 1595221, 1595223, 1595224, 1595225

The partly completed machine may not be put into operation until it has been confirmed that the machine into which the partly completed machine is to be installed complies with the provisions of the "Supply of Machinery (Safety) Regulations 2008".

Applied harmonized standards, especially:

EN ISO 12100:2010	Safety of machinery – General principles for design – Risk assessment and risk reduction

The special technical documentation according to Annex VII, Part B, belonging to the partly completed machine, has been created.

Person authorized to compile the technical documentation:
Marcel Machado, address: refer to manufacturer's address

Dr.-Ing. Manuel Baumeister,
Head of Systems Engineering,
Technology & Innovation

Lauffen/Neckar, June 2025

11 Information on the RoHS Directive, REACH Regulation and Substances of Very High Concern (SVHC)

RoHS Directive

SCHUNK products are classified as "large-scale stationary installations" or as "large-scale stationary industrial tools" within the meaning of Directive 2011/65/EU and its extension 2015/863/EU "on the restriction of the use of certain hazardous substances in electrical and electronic equipment (RoHS)", or fulfill their intended function only as part of one. Therefore products from SCHUNK do not fall within the scope of the directive at this time.

REACH Regulation

Products from SCHUNK fully comply with the regulations of Regulation (EC) No. 1907/2006 "concerning the Registration, Evaluation, Authorization and Restriction of Chemicals (REACH)" and its amendment 2022/477. SCHUNK attaches great importance to completely avoiding chemicals of concern to humans and the environment wherever possible.

Only in rare exceptional cases do SCHUNK products contain SVHC substances on the candidate list with a mass content above 0.1%. In accordance with Article. 33 (1) of Regulation (EC) No. 1907/2006, SCHUNK complies with its duty to "communicate information on substances in articles" and lists the components concerned and the substances used in an overview that can be viewed at **schunk.com\SVHC**.

Signature: see original declaration

Dr.-Ing. Manuel Baumeister,
Head of Systems Engineering,
Technology & Innovation

Lauffen/Neckar, June 2025

SCHUNK SE & Co. KG
Spanntechnik | Greiftechnik | Automatisierungstechnik

Bahnhofstr. 106 – 134
D-74348 Lauffen/Neckar
Tel. +49-7133-103-0
info@de.schunk.com
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