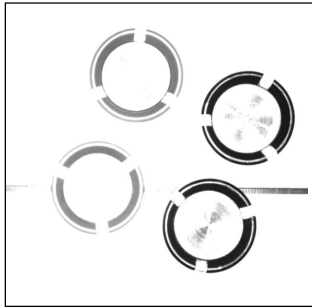




take picture →



apply vision function

detected shape positions [pixels]

derive product color and
product position

physical object positions [pixels]

convert object positions
from pixel to mm in
conveyor coordinate
system

physical object positions [mm]

create TrackingFrames
on the TrackingPath
(avoid duplication
caused by trigger
distance)

mapp Vision

application program

mapp Motion

latched conveyor axis position

physical object color