

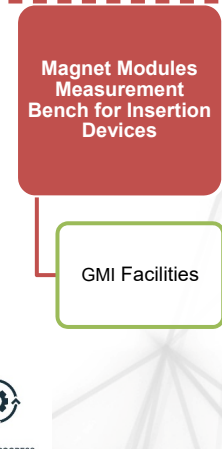
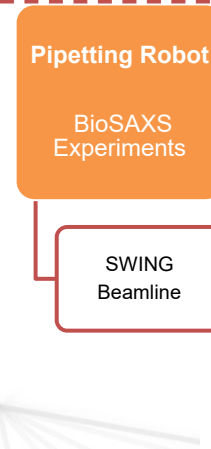
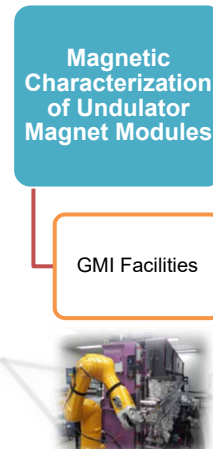
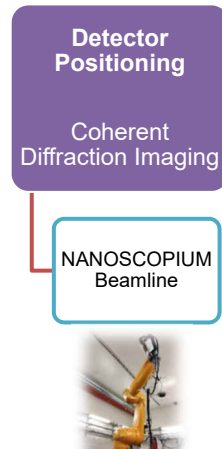
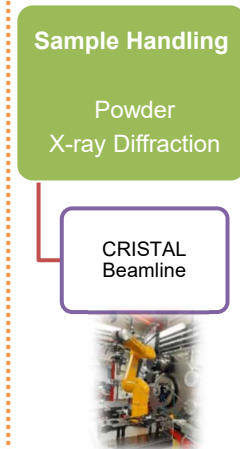
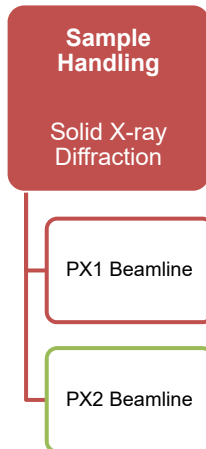
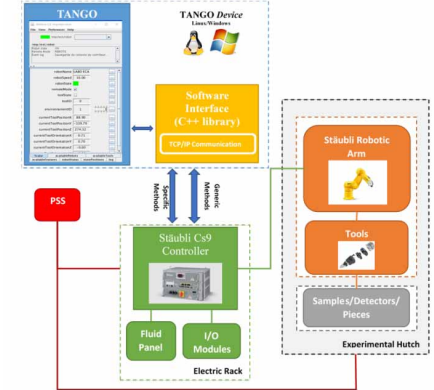
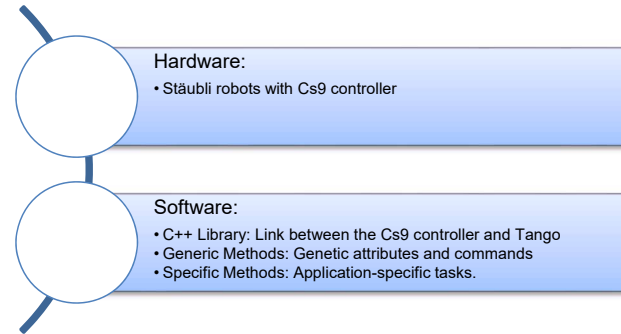
Robotic Process Automation: on the Continuity of Applications Development at SOLEIL

Laura Munoz*, Yves-Marie Abiven, Marie-Emmanuelle Couprie, Arafat Noureddine, Javier Perez, Aurélien Thureau, Mathieu Valléau

Main uses of 6-axis robot arms in a synchrotron:

- ❖ Sample Changer
- ❖ Detector Holder
- ❖ Sample Holder

Standardized approach:

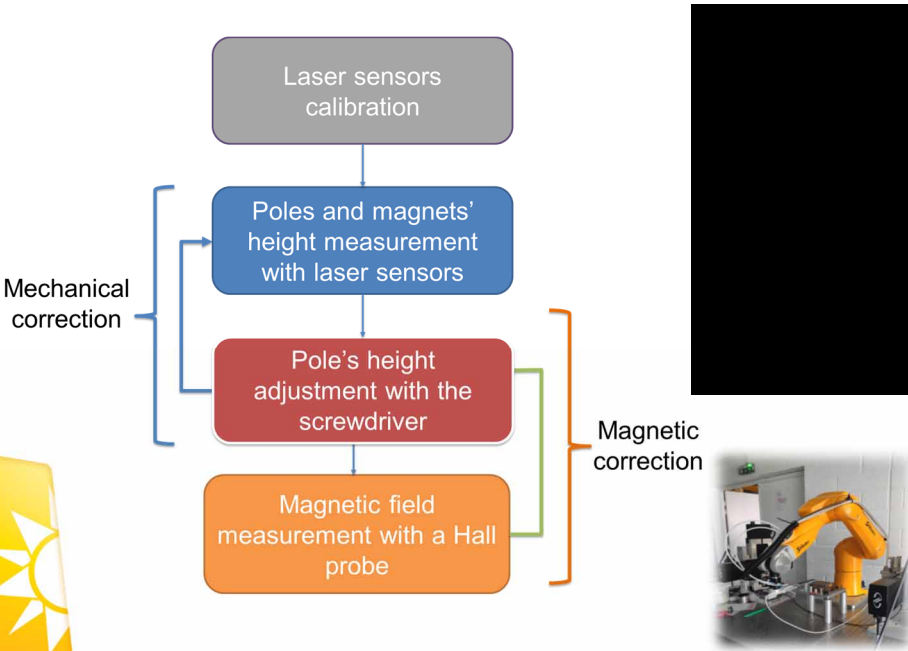


Standardization



ROBOTIC MAGNETIC MEASURING BENCH FOR INSERTION DEVICES

GOAL: to perform magnetic and mechanical corrections of the supermodules of the CPMU12 prototype (undulator) regarding SOLEIL II.



PIPETTING APPLICATION FOR BioSAXS EXPERIMENTS

GOAL: to be able to inject liquid samples as close as possible to the measurement cell to avoid wasting sample and eliminate potential cross-contamination with disposable tips.

