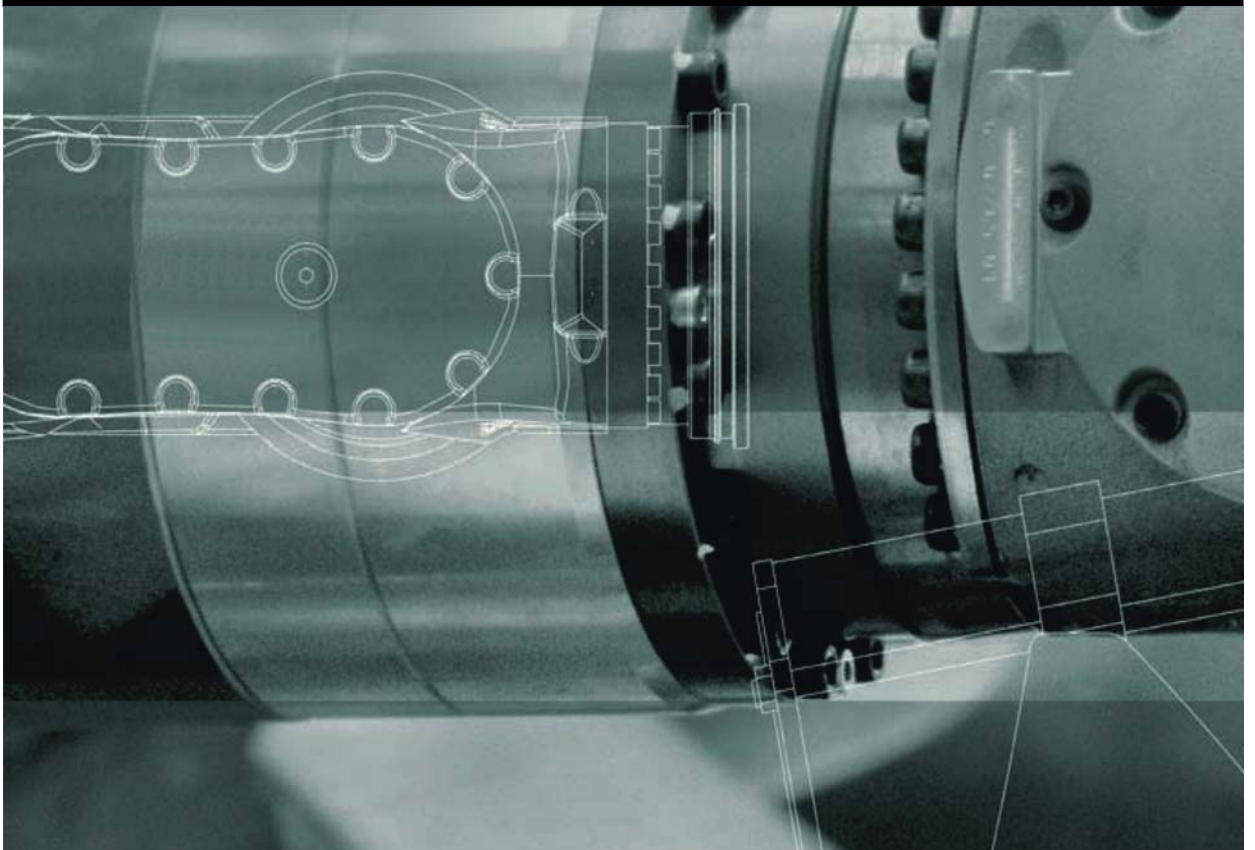


KR AGILUS sixx

With W and C Variants
Assembly Instructions



Issued: 28.03.2013

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Other functions not described in this documentation may be operable in the controller. The user has no claims to these functions, however, in the case of a replacement or service work.

We have checked the content of this documentation for conformity with the hardware and software described. Nevertheless, discrepancies cannot be precluded, for which reason we are not able to guarantee total conformity. The information in this documentation is checked on a regular basis, however, and necessary corrections will be incorporated in the subsequent edition.

Subject to technical alterations without an effect on the function.

Translation of the original documentation

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1 Introduction

1.1 Industrial robot documentation

The industrial robot documentation consists of the following parts:


- Documentation for the manipulator
- Documentation for the robot controller
- Operating and programming instructions for the KUKA System Software
- Documentation relating to options and accessories
- Parts catalog on storage medium


Each of these sets of instructions is a separate document.


1.2 Representation of warnings and notes

Safety


These warnings are relevant to safety and **must** be observed.

 DANGER	These warnings mean that it is certain or highly probable that death or severe injuries will occur, if no precautions are taken.
---	---

 WARNING	These warnings mean that death or severe injuries may occur, if no precautions are taken.
--	--

 CAUTION	These warnings mean that minor injuries may occur, if no precautions are taken.
--	--

NOTICE	These warnings mean that damage to property may occur, if no precautions are taken.
---------------	--


	These warnings contain references to safety-relevant information or general safety measures. These warnings do not refer to individual hazards or individual precautionary measures.
---	---

This warning draws attention to procedures which serve to prevent or remedy emergencies or malfunctions:

SAFETY INSTRUCTIONS	Procedures marked with this warning must be followed exactly.
----------------------------	--

Notes

These hints serve to make your work easier or contain references to further information.

	Tip to make your work easier or reference to further information.
---	---

1.3 Terms used

Term	Description
MEMD	Micro Electronic Mastering Device
KL	KUKA linear unit

Term	Description
RDC	Resolver Digital Converter
smartPAD	The smartPAD teach pendant has all the operator control and display functions required for operating and programming the industrial robot.

2 Purpose

2.1 Target group

This documentation is aimed at users with the following knowledge and skills:

- Advanced knowledge of mechanical engineering
- Advanced knowledge of electrical and electronic systems
- Knowledge of the robot controller system



For optimal use of our products, we recommend that our customers take part in a course of training at KUKA College. Information about the training program can be found at www.kuka.com or can be obtained directly from our subsidiaries.

2.2 Intended use

Use The industrial robot is intended for handling tools and fixtures, or for processing or transferring components or products. Use is only permitted under the specified environmental conditions.

Misuse Any use or application deviating from the intended use is deemed to be impermissible misuse. This includes e.g.:

- Transportation of persons and animals
- Use as a climbing aid
- Operation outside the permissible operating parameters
- Use in potentially explosive environments
- Use in underground mining

NOTICE

Changing the structure of the manipulator, e.g. by drilling holes, etc., can result in damage to the components. This is considered improper use and leads to loss of guarantee and liability entitlements.



The robot system is an integral part of a complete system and may only be operated in a CE-compliant system.

3 Product description

3.1 Overview of the robot system

A robot system (>>> Fig. 3-1) comprises all the assemblies of an industrial robot, including the manipulator (mechanical system and electrical installations), control cabinet, connecting cables, end effector (tool) and other equipment. The KR AGILUS product family consists of the following type:

- KR 6 R900 sixx
- KR 10 R900 sixx
- KR 10 R1100 sixx

The robots are also available as W and C variants (wall-mounted and ceiling-mounted versions).

An industrial robot of this type comprises the following components:

- Manipulator
- Robot controller
- smartPAD teach pendant
- Connecting cables
- Software
- Options, accessories

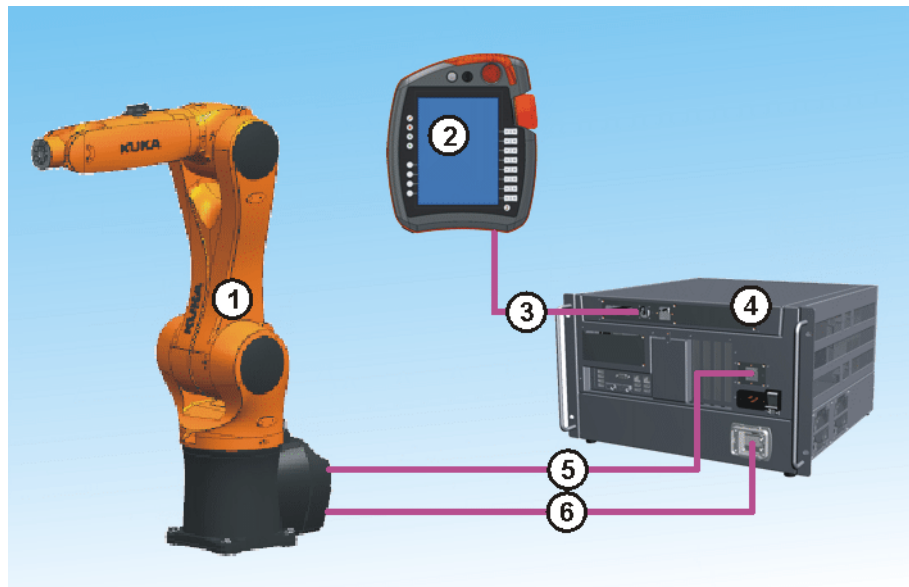


Fig. 3-1: Example of an industrial robot

- 1 Manipulator
- 2 smartPAD teach pendant
- 3 Connecting cable, smartPAD
- 4 Robot controller
- 5 Connecting cable, data cable
- 6 Connecting cable, motor cable

3.2 Description of the manipulator

Overview

The manipulators are 6-axis jointed-arm manipulators made of cast light alloy. Each axis is fitted with a brake. All motor units and current-carrying cables are protected against dirt and moisture beneath screwed-on cover plates.

The robot consists of the following principal components:

- In-line wrist
- Arm
- Link arm
- Rotating column
- Base frame
- Electrical installations

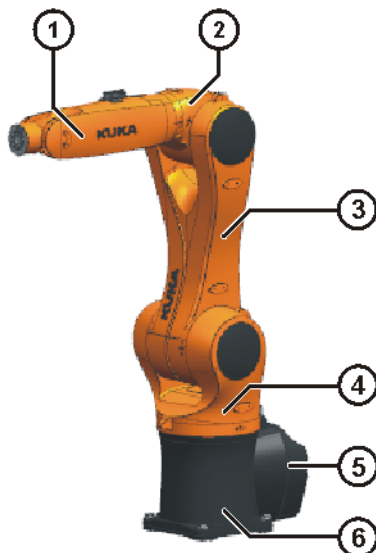


Fig. 3-2: Principal components

- | | | | |
|---|---------------|---|--------------------------|
| 1 | In-line wrist | 4 | Rotating column |
| 2 | Arm | 5 | Electrical installations |
| 3 | Link arm | 6 | Base frame |

In-line wrist
A4, A5, A6

The robot is fitted with a 3-axis in-line wrist. The in-line wrist consists of axes 4, 5 and 6.

There are three 4/2-way solenoid valves and a CAT5 data cable in the in-line wrist that can be used for controlling tools.

The in-line wrist also accommodates the 10-contact circular connector of the wrist I/O cable and interface A4 for the energy supply system.

Arm
A3

The arm is the link between the in-line wrist and the link arm. The arm is driven by the motor of axis 3.

Link arm
A2

The link arm is the assembly located between the arm and the rotating column. It houses the motor and gear unit of axis 2. The supply lines of the energy supply system and the cable set for axes 2 to 6 are routed through the link arm.

Rotating column
A1

The rotating column houses the motors of axes 1 and 2. The rotational motion of axis 1 is performed by the rotating column. This is screwed to the base frame via the gear unit of axis 1 and is driven by a motor in the rotating column. The link arm is also mounted in the rotating column.

Base frame

The base frame is the base of the robot. Interface A1 is located at the rear of the base frame. It constitutes the interface for the connecting cables between the robot, the controller and the energy supply system.

Electrical installations

The electrical installations include all the motor and control cables for the motors of axes 1 to 6. All connections are pluggable. The electrical installations also include the RDC box, which is integrated into the robot. The connectors

for the motor and data cables are mounted on the robot base frame. The connecting cables from the robot controller are connected here by means of connectors. The electrical installations also include a protective circuit.

Options

The robot can be fitted and operated with various options, e.g. working range limitation A1 or brake release device. The option is described in separate documentation.

4 Technical data

The technical data for the individual robot types can be found in the following sections:

Robot	Technical data
KR 6 sixx	
KR 6 R900 sixx <ul style="list-style-type: none"> ■ KR 6 R900 sixx ■ KR 6 R900 sixx W ■ KR 6 R900 sixx C 	Basic data (>>> 4.1 "Basic data, KR 6 sixx" Page 16)
	Axis data (>>> 4.2 "Axis data, KR 6 sixx" Page 17)
	Payloads (>>> 4.3 "Payloads, KR 6 sixx" Page 22)
	Foundation data (>>> 4.4 "Mounting base data, KR 6 sixx" Page 26)
	Plates and labels (>>> 4.9 "Plates and labels" Page 44)
	Stopping distances (>>> 4.10.3 "Stopping distances and times, KR 6 R900 sixx " Page 47) (>>> 4.10.4 "Stopping distances and times, KR 6 R900 sixx W" Page 52)
KR 10 sixx	
KR 10 R900 sixx <ul style="list-style-type: none"> ■ KR 10 R900 sixx ■ KR 10 R900 sixx W ■ KR 10 R900 sixx C KR 10 R1100 sixx <ul style="list-style-type: none"> ■ KR 10 R1100 sixx ■ KR 10 R1100 sixx W ■ KR 10 R1100 sixx C 	Basic data (>>> 4.5 "Basic data, KR 10 sixx" Page 27)
	Axis data (>>> 4.6 "Axis data, KR 10 sixx" Page 28)
	Payloads (>>> 4.7 "Payloads, KR 10 sixx" Page 37)
	Foundation data (>>> 4.8 "Mounting base data, KR 10 sixx" Page 43)
	Plates and labels (>>> 4.9 "Plates and labels" Page 44)
	Stopping distances (>>> 4.10.5 "Stopping distances and times, KR 10 R900 sixx and KR 10 R1100 sixx" Page 58) (>>> 4.10.6 "Stopping distances and times, KR 10 R900 sixx W and KR 10 R1100 sixx W" Page 64)

4.1 Basic data, KR 6 sixx

Basic data

Type	KR 6 R900 sixx KR 6 R900 sixx W KR 6 R900 sixx C
Number of axes	6
Volume of working envelope	KR 6 R900 sixx: 2.85 m ³ KR 6 R900 sixx W: 2.85 m ³ KR 6 R900 sixx C: 2.85 m ³
Pose repeatability (ISO 9283)	±0.03 mm KR 6 R900 sixx: ±0.03 mm KR 6 R900 sixx W: ±0.03 mm KR 6 R900 sixx C: ±0.03 mm
Working envelope reference point	Intersection of axes 4 and 5
Weight	approx. 52 kg KR 6 R900 sixx: approx. 52 kg KR 6 R900 sixx W: approx. 52 kg KR 6 R900 sixx C: approx. 52 kg
Principal dynamic loads	See Loads acting on the foundation
Protection classification of the robot	IP 54 ready for operation, with connecting cables plugged in (according to EN 60529)
Protection classification of the in-line wrist	IP 54
Sound level	< 70 dB (A) outside the working envelope
Mounting position	Floor, wall, ceiling
Surface finish, paint-work	Base (stationary) and covers on link arm: black (RAL 9011); moving parts: KUKA orange 2567

Ambient conditions

Operation	278 K to 318 K (+5 °C to +45 °C) No condensation permissible.
Storage and transportation	-40 °C to +60 °C (233 K to 333 K)
Ambient conditions	Relative air humidity ≤ 90% DIN EN 60721-3-3, Class 3K3
Altitude	<ul style="list-style-type: none"> ■ up to 1000 m above mean sea level with no reduction in power ■ 1000 m ... 4000 m above mean sea level with a reduction in power of 5%/1000 m

The maintenance intervals and the specified service life are based on typical gear unit temperatures and axis motions. If special functions or applications result in atypical gear unit temperatures or axis motions, this can lead to increased wear. In this case, the maintenance intervals or service life may be shortened. If you have any questions, please contact KUKA Customer Support.

Connecting cables

Cable designation	Connector designation robot controller - robot	Interface with robot
Motor cable	X20 - X30	Han Yellock 30
Data cable	X21 - X31	Han Q12
CAT5 data cable (can be ordered as an option)	X65/X66 - XPN1	M12 connector
Connecting cable, external axes A7 and A8 (can be ordered as an option)	XP7 - XP7.1 XP8 - XP8.1	Connector M17 in each case
Ground conductor, equipotential bonding (can be ordered as an option)		Ring cable lug M4

Only resolvers can be connected to the connections XP7.1 and XP8.1.

	Cable lengths
Standard	4 m
Option	1 m, 7 m, 15 m, 25 m

For detailed specifications of the connecting cables, see (>>> 8.6 "Description of the connecting cables" Page 112).

4.2 Axis data, KR 6 sixx**Axis data**

The following axis data are valid for the robots:

- KR 6 R900 sixx
- KR 6 R900 sixx W
- KR 6 R900 sixx C

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-170°	360 °/s
2	+45° to -190°	300 °/s
3	+156° to -120°	360 °/s
4	+/-185°	381 °/s
5	+/-120°	388 °/s
6	+/-350°	615 °/s

The direction of motion and the arrangement of the individual axes may be noted from the diagram (>>> Fig. 4-1).

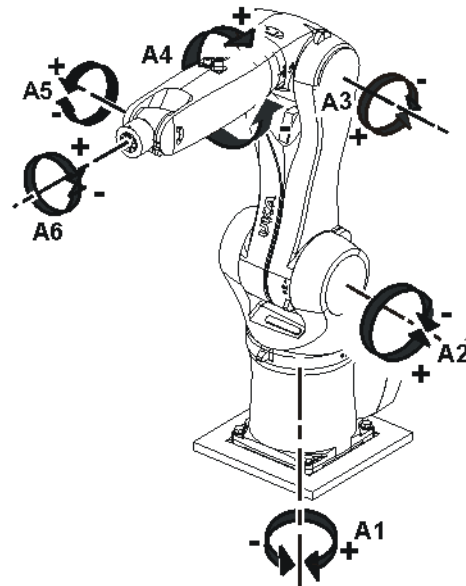


Fig. 4-1: Direction of rotation of robot axes

Working envelope

The following diagram (>>> Fig. 4-2) shows the shape and size of the working envelope for the robot:

- KR 6 R900 sixx

Maße / Dimensions: mm

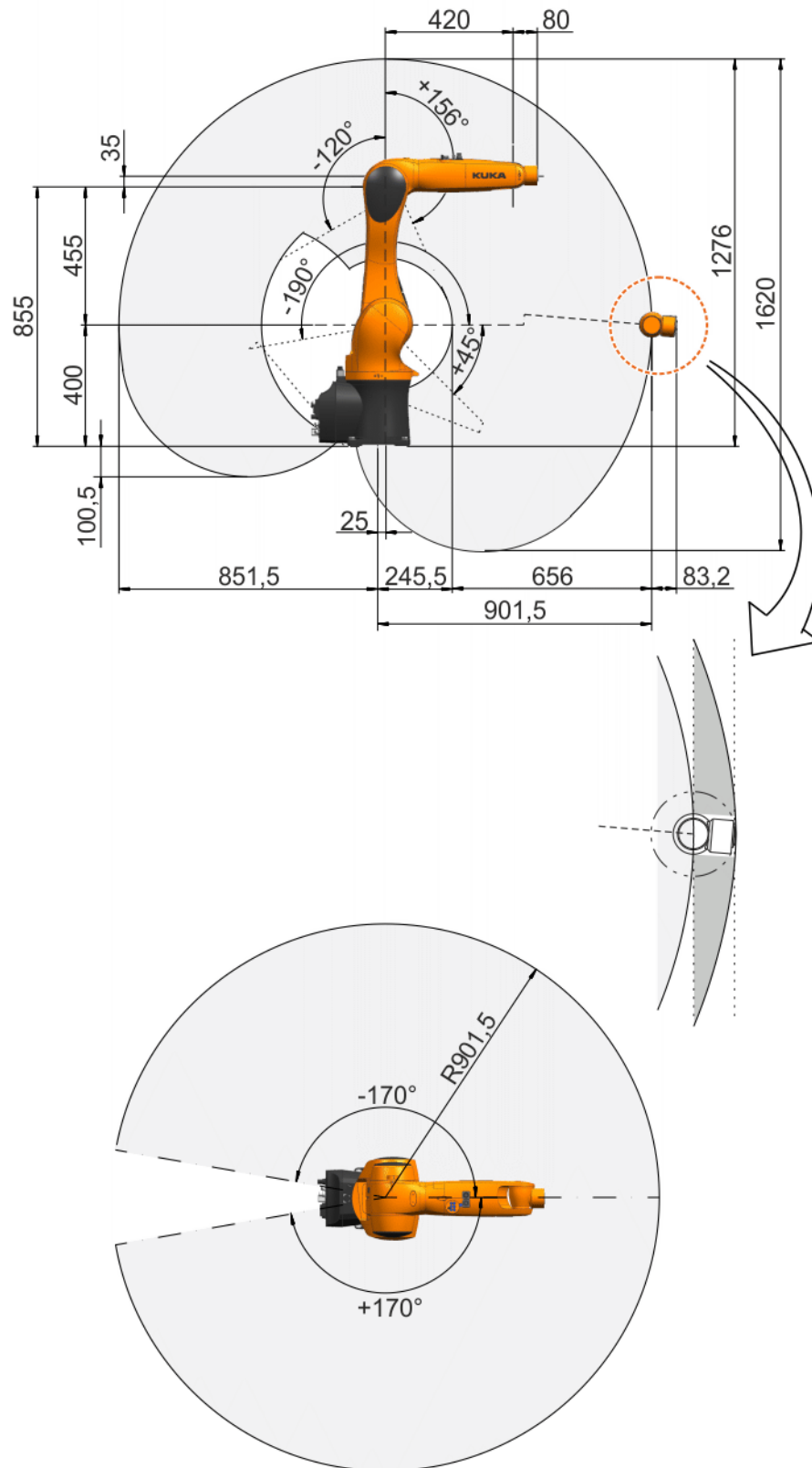


Fig. 4-2: Working envelope, KR 6 R900 sixx

The following diagram (>>> Fig. 4-3) shows the shape and size of the working envelope for the robot:

- KR 6 R900 sixx W

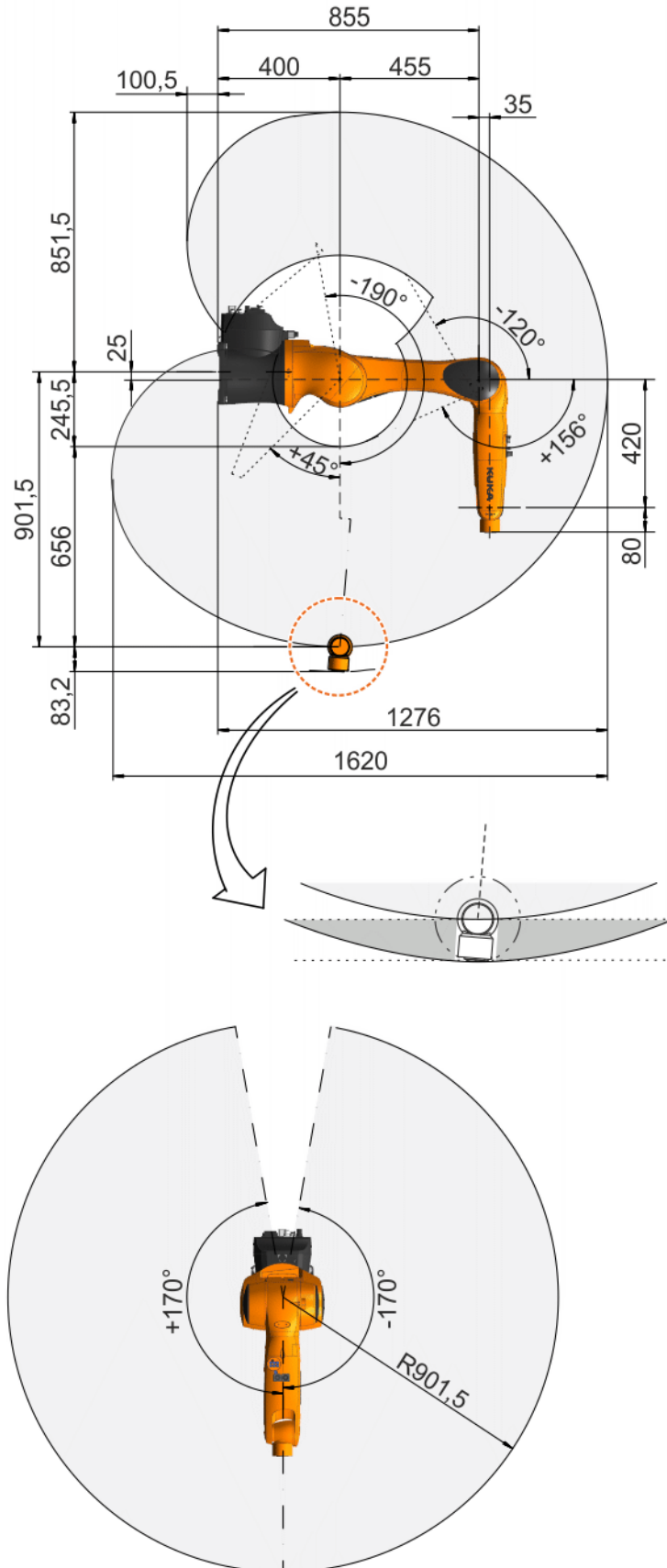


Fig. 4-3: Working envelope, KR 6 R900 sixx W

The following diagram (>>> Fig. 4-4) shows the shape and size of the work-
ing envelope for the robot:

- KR 6 R900 sixx C

Maße / Dimensions: mm

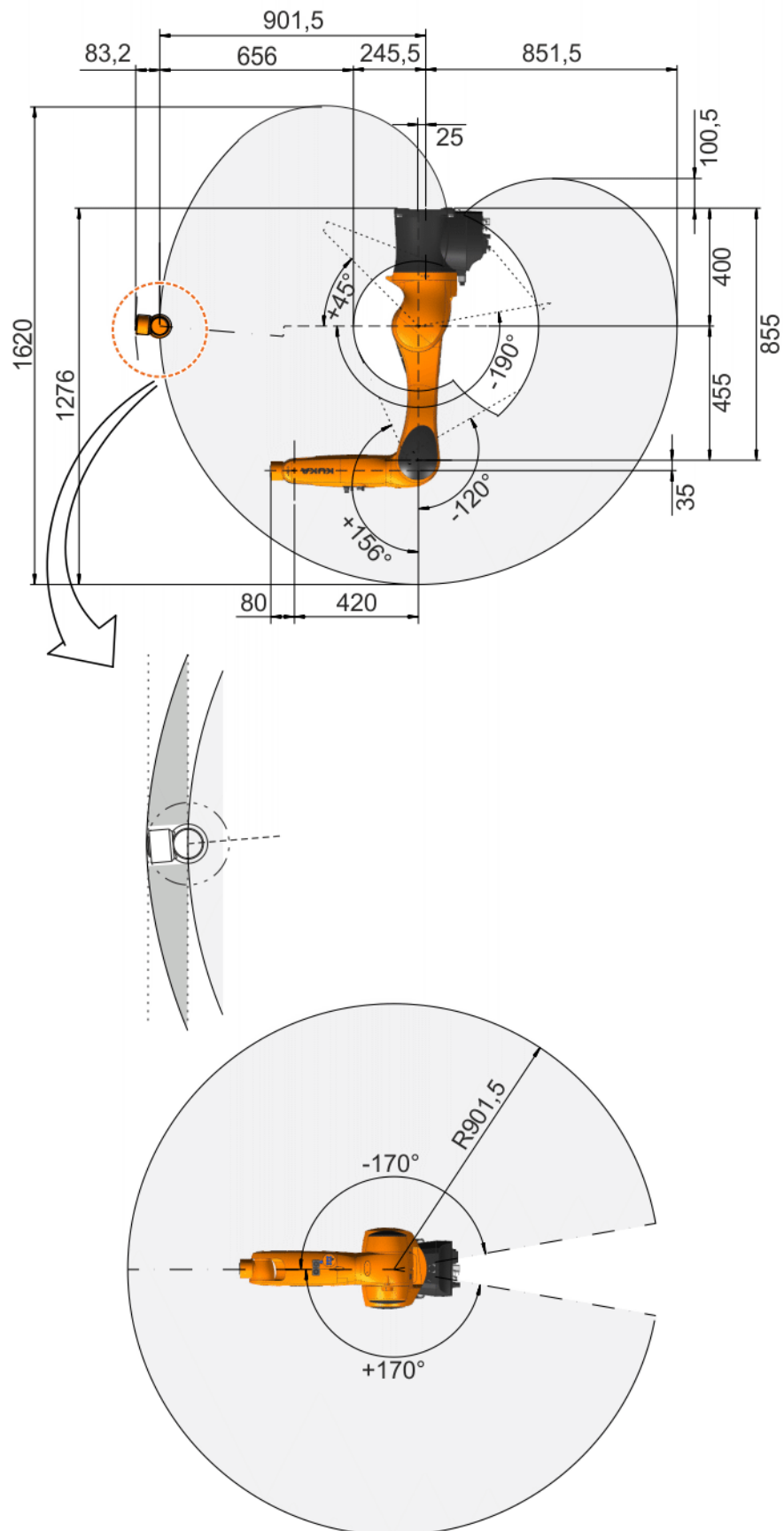


Fig. 4-4: Working envelope, KR 6 R900 sixx C

4.3 Payloads, KR 6 sixx

Payloads

A distinction is made between the nominal and maximum payload. At the nominal payload, the manipulator is rated for optimal cycle times and accuracy.

Robot	KR 6 R900 sixx KR 6 R900 sixx W KR 6 R900 sixx C
In-line wrist	IW 6/10 R900
Nominal payload	3 kg
Max. payload	6 kg
Distance of the load center of gravity L_{xy}	60 mm
Distance of the load center of gravity L_z	80 mm
Max. total load	6 kg
Supplementary load	The sum of all loads mounted on the robot must not exceed the maximum total load.

Load center of gravity P

For all payloads, the load center of gravity refers to the distance from the face of the mounting flange on axis 6. Refer to the payload diagram for the nominal distance.

Payload diagram

Permissible mass inertia at the design point (L_x , L_y , L_z) is 0.045 kgm².

The following figure (>>> Fig. 4-5) shows payload diagram for the following robots:

- KR 6 R900 sixx
- KR 6 R900 sixx W
- KR 6 R900 sixx C

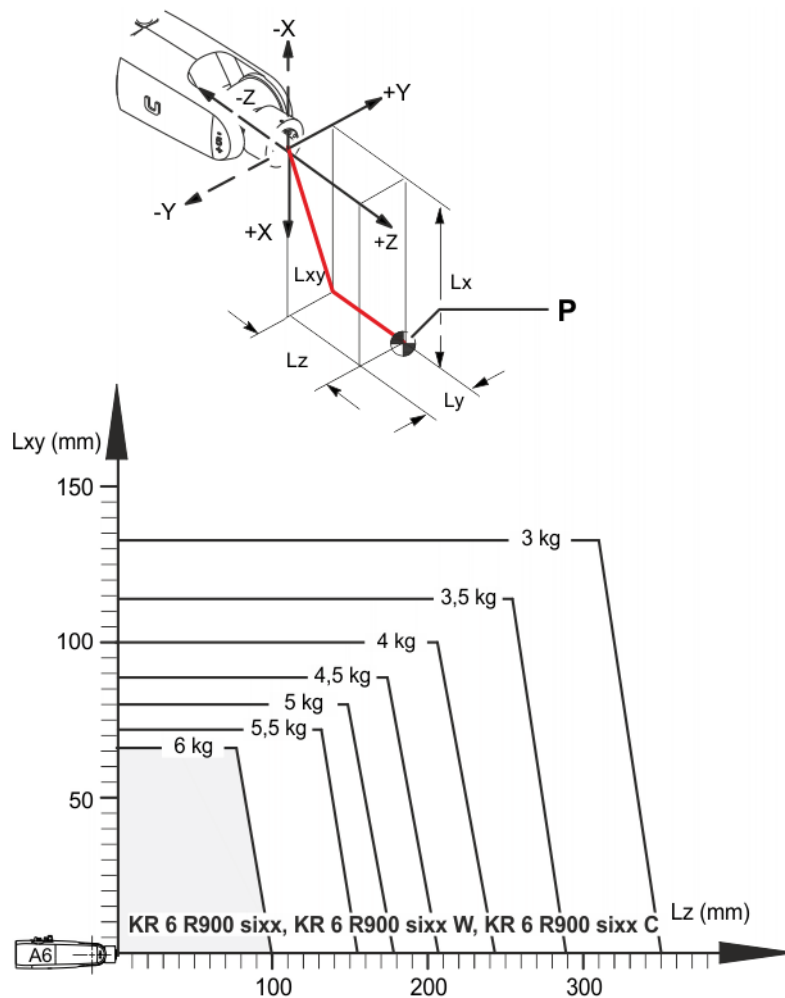


Fig. 4-5: Payload diagram

NOTICE This loading curve corresponds to the maximum load capacity. Both values (payload and mass moment of inertia) must be checked in all cases. Exceeding this capacity will reduce the service life of the robot and overload the motors and the gears; in any such case the KUKA Roboter GmbH must be consulted beforehand. The values determined here are necessary for planning the robot application. For commissioning the robot, additional input data are required in accordance with operating and programming instructions of the KUKA System Software. The mass inertia must be verified using KUKA.Load. It is imperative for the load data to be entered in the robot controller!

Mounting flange

Mounting flange	ISO 9409-1: 2004
Screw grade	12.9
Screw size	M5
Grip length	1.5 x nominal diameter
Depth of engagement	min. 5.5 mm, max. 6.5 mm
Locating element	5 H7

The mounting flange is depicted (>>> Fig. 4-6) with axis 6 in the zero position. The symbol X_m indicates the position of the locating element (bushing) in the zero position.

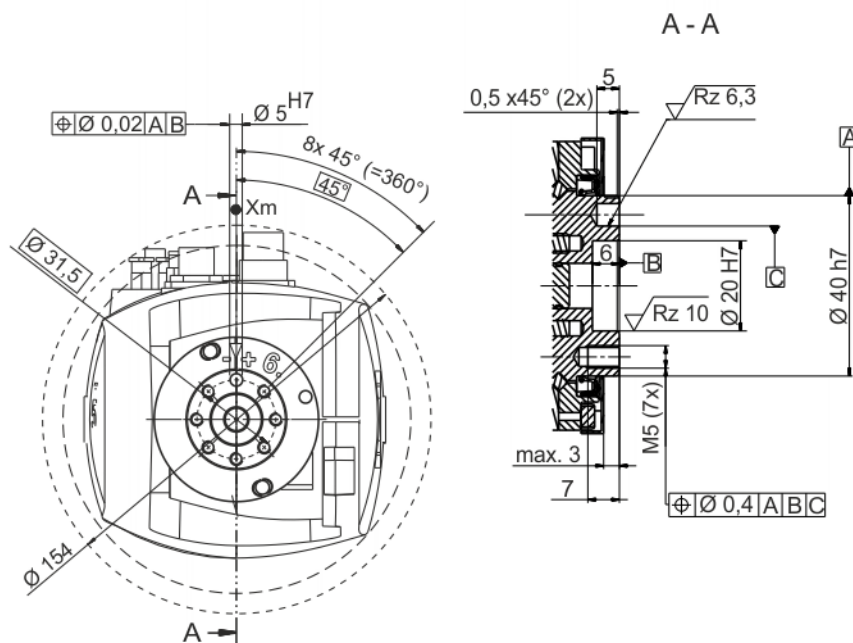


Fig. 4-6: Mounting flange

Supplementary load

The robot can carry supplementary loads on the arm, on the wrist, on the link arm and on the rotating column. The fastening holes are used for fastening the covers or external energy supply systems. When mounting the supplementary loads, be careful to observe the maximum permissible total load. The dimensions and positions of the installation options can be seen in the following diagram.



The sum of all loads mounted on the robot must not exceed the maximum total load.

The following figure (>>> Fig. 4-7) shows the dimensions and position of the installation options on the arm and in-line wrist for the following robots:

- KR 6 R900 sixx
- KR 6 R900 sixx W
- KR 6 R900 sixx C

Maße / Dimensions: mm

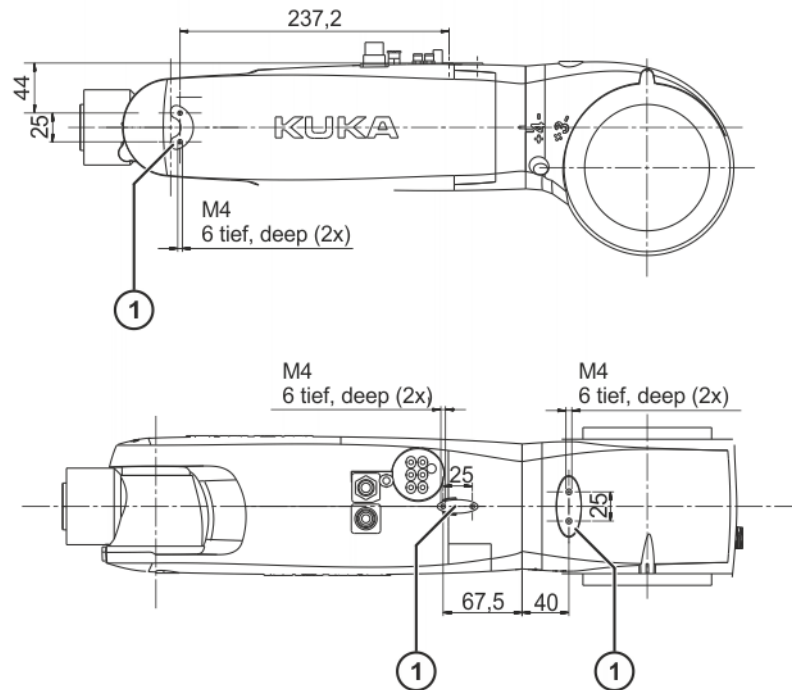


Fig. 4-7: Supplementary load on arm and in-line wrist

- 1 Support bracket for supplementary load

The following figure (>>> Fig. 4-8) shows the dimensions and position of the installation options on the link arm and rotating column for the following robots:

- KR 6 R900 sixx
- KR 6 R900 sixx W
- KR 6 R900 sixx C

Maße / Dimensions: mm

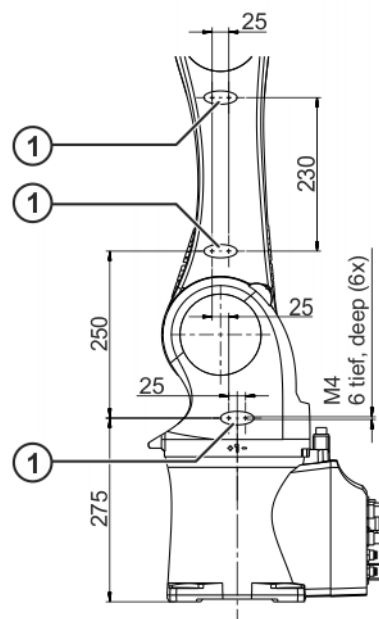


Fig. 4-8: Supplementary load on link arm and rotating column

- 1 Support bracket for supplementary load

4.4 Mounting base data, KR 6 sixx

Loads acting on the mounting base

The specified forces and moments already include the maximum payload and the inertia force (weight) of the robot.

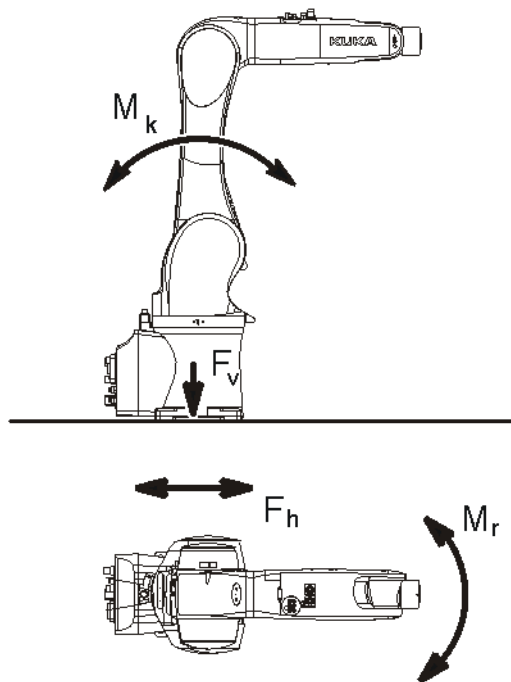


Fig. 4-9: Loads acting on the foundation

Type of load	Force/torque/mass	
	Normal operation	Maximum load
F_v = vertical force	$F_{vmax} = 967 \text{ N}$	$F_{vmax} = 1297 \text{ N}$
F_h = horizontal force	$F_{hmax} = 1223 \text{ N}$	$F_{hmax} = 1362 \text{ N}$
M_k = tilting moment	$M_{kmax} = 788 \text{ Nm}$	$M_{kmax} = 1152 \text{ Nm}$
M_r = torque	$M_{rmax} = 367 \text{ Nm}$	$M_{rmax} = 880 \text{ Nm}$
Total mass for load acting on the mounting base	KR 6 R900 sixx: 58 kg	
Robot	KR 6 R900 sixx: 52 kg	
Total load for mounting base load (suppl. load on arm + rated payload)	KR 6 R900 sixx: 6 kg	

NOTICE The mounting base loads specified in the table are the maximum loads that may occur. They must be referred to when dimensioning the mounting bases and must be adhered to for safety reasons. The supplementary loads on the base frame and rotating column are not taken into consideration in the calculation of the mounting base load. These supplementary loads must be taken into consideration for F_v .

4.5 Basic data, KR 10 sixx

Basic data

Type	KR 10 R900 sixx KR 10 R900 sixx W KR 10 R900 sixx C KR 10 R1100 sixx KR 10 R1100 sixx W KR 10 R1100 sixx C
Number of axes	6
Volume of working envelope	KR 10 R900 sixx: 2.85 m ³ KR 10 R900 sixx W: 2.85 m ³ KR 10 R900 sixx C: 2.85 m ³ KR 10 R1100 sixx: 5.20 m ³ KR 10 R1100 sixx W: 5.20 m ³ KR 10 R1100 sixx C: 5.20 m ³
Pose repeatability (ISO 9283)	KR 10 R900 sixx: ±0.03 mm KR 10 R900 sixx W: ±0.03 mm KR 10 R900 sixx C: ±0.03 mm KR 10 R1100 sixx: ±0.05 mm KR 10 R1100 sixx W: ±0.05 mm KR 10 R1100 sixx C: ±0.05 mm
Working envelope reference point	Intersection of axes 4 and 5
Weight	KR 10 R900 sixx: approx. 52 kg KR 10 R900 sixx W: approx. 52 kg KR 10 R900 sixx C: approx. 52 kg KR 10 R1100 sixx: approx. 55 kg KR 10 R1100 sixx W: approx. 55 kg KR 10 R1100 sixx C: approx. 55 kg
Principal dynamic loads	See Loads acting on the foundation
Protection classification of the robot	IP 54 ready for operation, with connecting cables plugged in (according to EN 60529)
Protection classification of the in-line wrist	IP 54
Sound level	< 70 dB (A) outside the working envelope
Mounting position	Floor, wall, ceiling
Surface finish, paint-work	Base (stationary) and covers on link arm: black (RAL 9011); moving parts: KUKA orange 2567

Ambient conditions

Operation	278 K to 318 K (+5 °C to +45 °C) No condensation permissible.
Storage and transportation	-40 °C to +60 °C (233 K to 333 K)
Ambient conditions	Relative air humidity ≤ 90% DIN EN 60721-3-3, Class 3K3
Altitude	<ul style="list-style-type: none"> ■ up to 1000 m above mean sea level with no reduction in power ■ 1000 m ... 4000 m above mean sea level with a reduction in power of 5%/1000 m

The maintenance intervals and the specified service life are based on typical gear unit temperatures and axis motions. If special functions or applications result in atypical gear unit temperatures or axis motions, this can lead to increased wear. In this case, the maintenance intervals or service life may be shortened. If you have any questions, please contact KUKA Customer Support.

Connecting cables

Cable designation	Connector designation robot controller - robot	Interface with robot
Motor cable	X20 - X30	Han Yellock 30
Data cable	X21 - X31	Han Q12
CAT5 data cable (can be ordered as an option)	X65/X66 - XPN1	M12 connector
Connecting cable, external axes A7 and A8 (can be ordered as an option)	XP7 - XP7.1 XP8 - XP8.1	Connector M17 in each case
Ground conductor, equipotential bonding (can be ordered as an option)		Ring cable lug M4

Only resolvers can be connected to the connections XP7.1 and XP8.1.

	Cable lengths
Standard	4 m
Option	1 m, 7 m, 15 m, 25 m

For detailed specifications of the connecting cables, see (>>> 8.6 "Description of the connecting cables" Page 112).

4.6 Axis data, KR 10 sixx

Axis data

The following axis data are valid for the robots:

- KR 10 R900 sixx
- KR 10 R900 sixx W
- KR 10 R900 sixx C
- KR 10 R1100 sixx
- KR 10 R1100 sixx W
- KR 10 R1100 sixx C

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-170°	300 °/s
2	+45° to -190°	225 °/s
3	+156° to -120°	225 °/s
4	+/-185°	381 °/s
5	+/-120°	311 °/s
6	+/-350°	492 °/s

The direction of motion and the arrangement of the individual axes may be noted from the diagram (>>> Fig. 4-10).

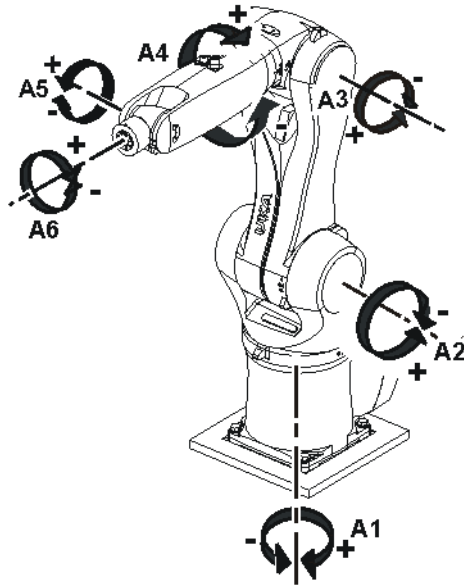


Fig. 4-10: Direction of rotation of robot axes

Working envelope

The following diagram (>>> Fig. 4-11) shows the shape and size of the working envelope for the robot:

- KR 10 R900 sixx

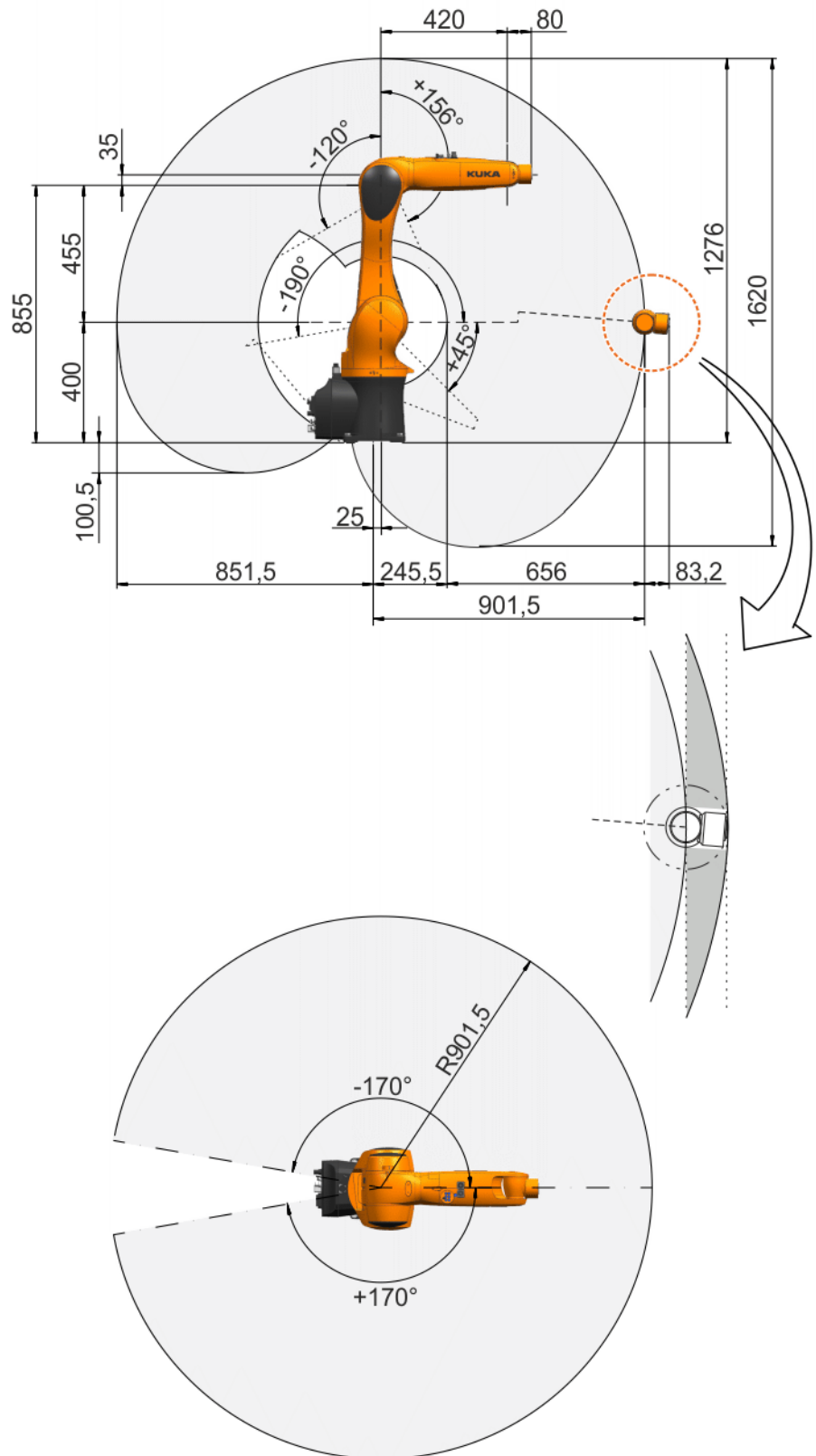


Fig. 4-11: Working envelope, KR 10 R900 sixx

The following diagram (>>> Fig. 4-12) shows the shape and size of the working envelope for the robot:

- KR 10 R900 sixx W

Maße / Dimensions: mm

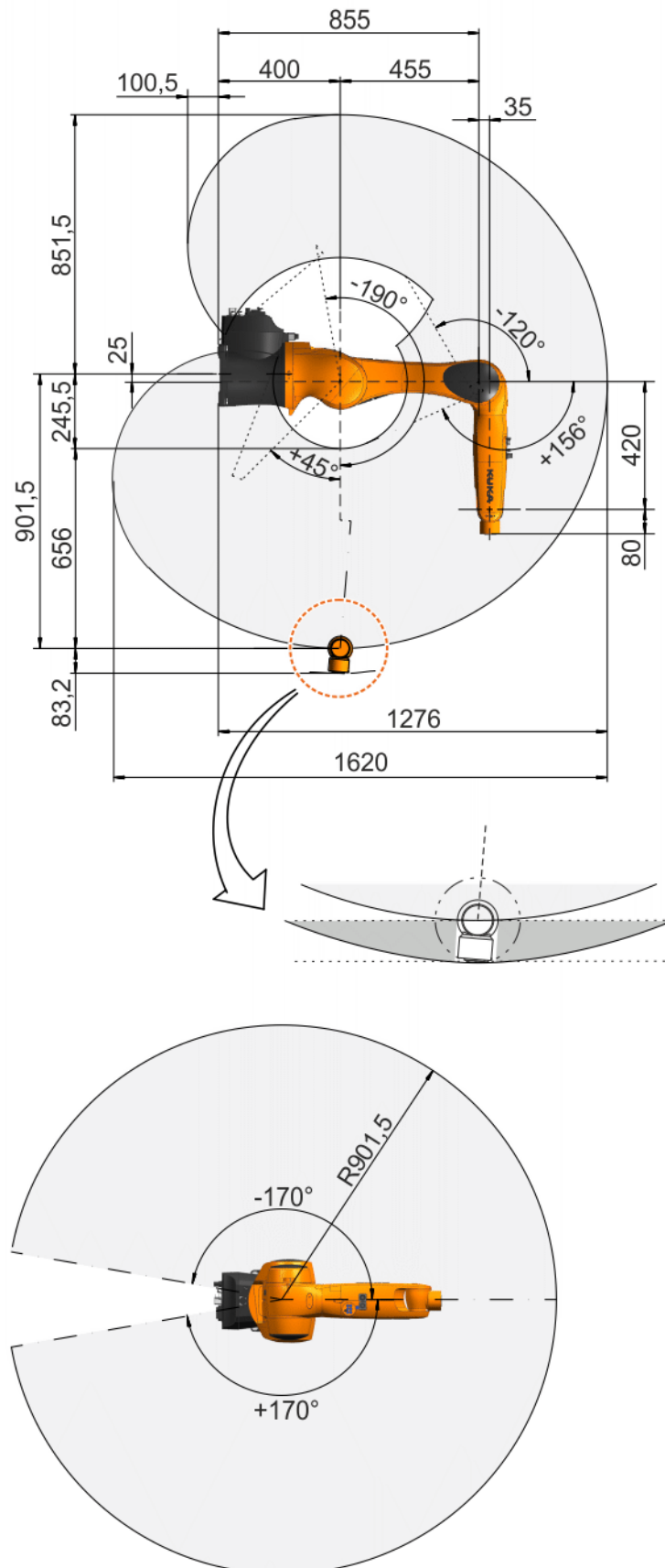


Fig. 4-12: Working envelope, KR 10 R900 sixx W

The following diagram (>>> Fig. 4-13) shows the shape and size of the working envelope for the robot:

■ KR 10 R900 sixx C

Maße / Dimensions: mm

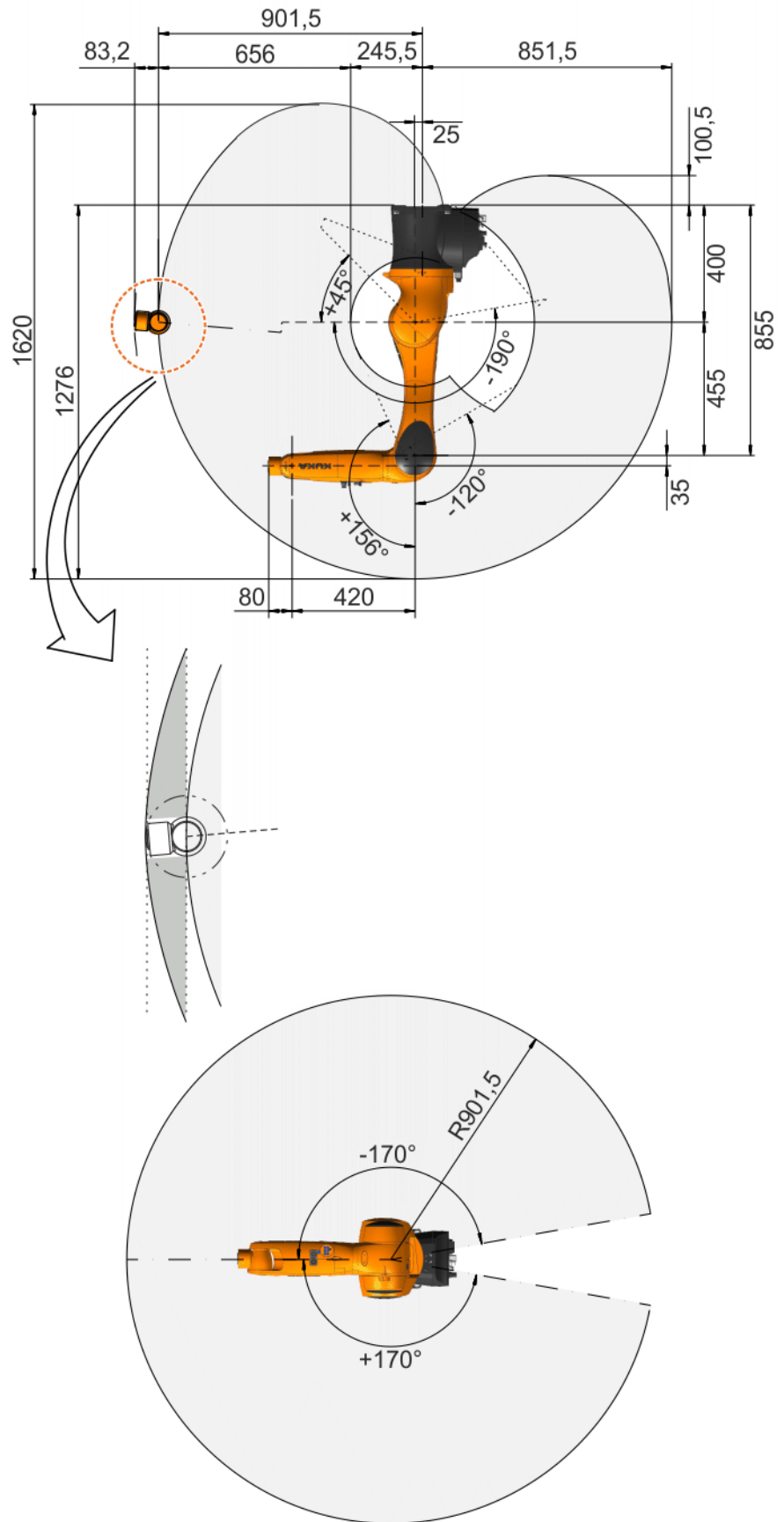


Fig. 4-13: Working envelope, KR 10 R900 sixx C

The following diagram (>>> Fig. 4-14) shows the shape and size of the working envelope for the robot:

- KR 10 R1100 sixx

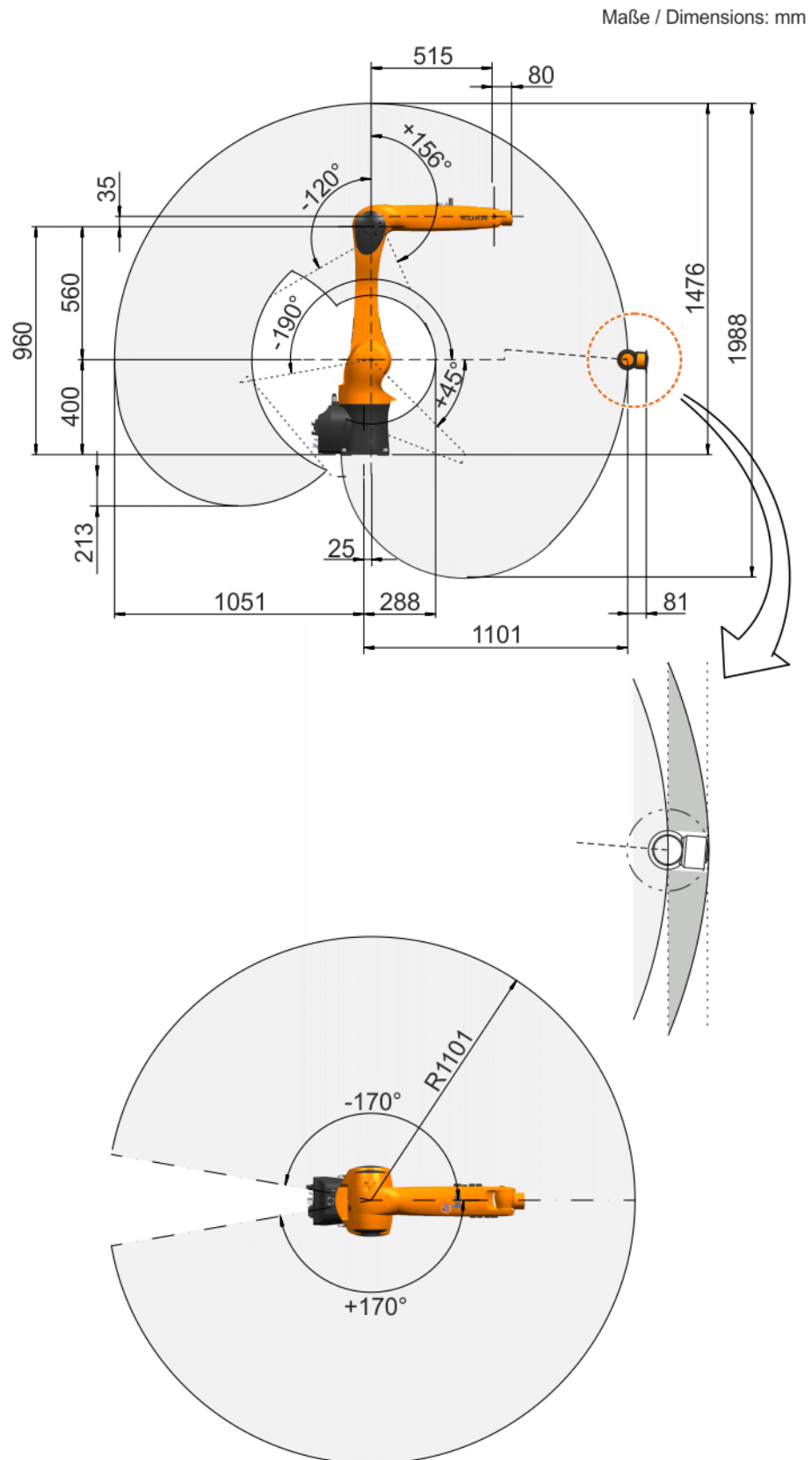


Fig. 4-14: Working envelope, KR 10 R1100 sixx

The following diagram (>>> Fig. 4-15) shows the shape and size of the working envelope for the robot:

- KR 10 R1100 sixx W

Maße / Dimensions: mm

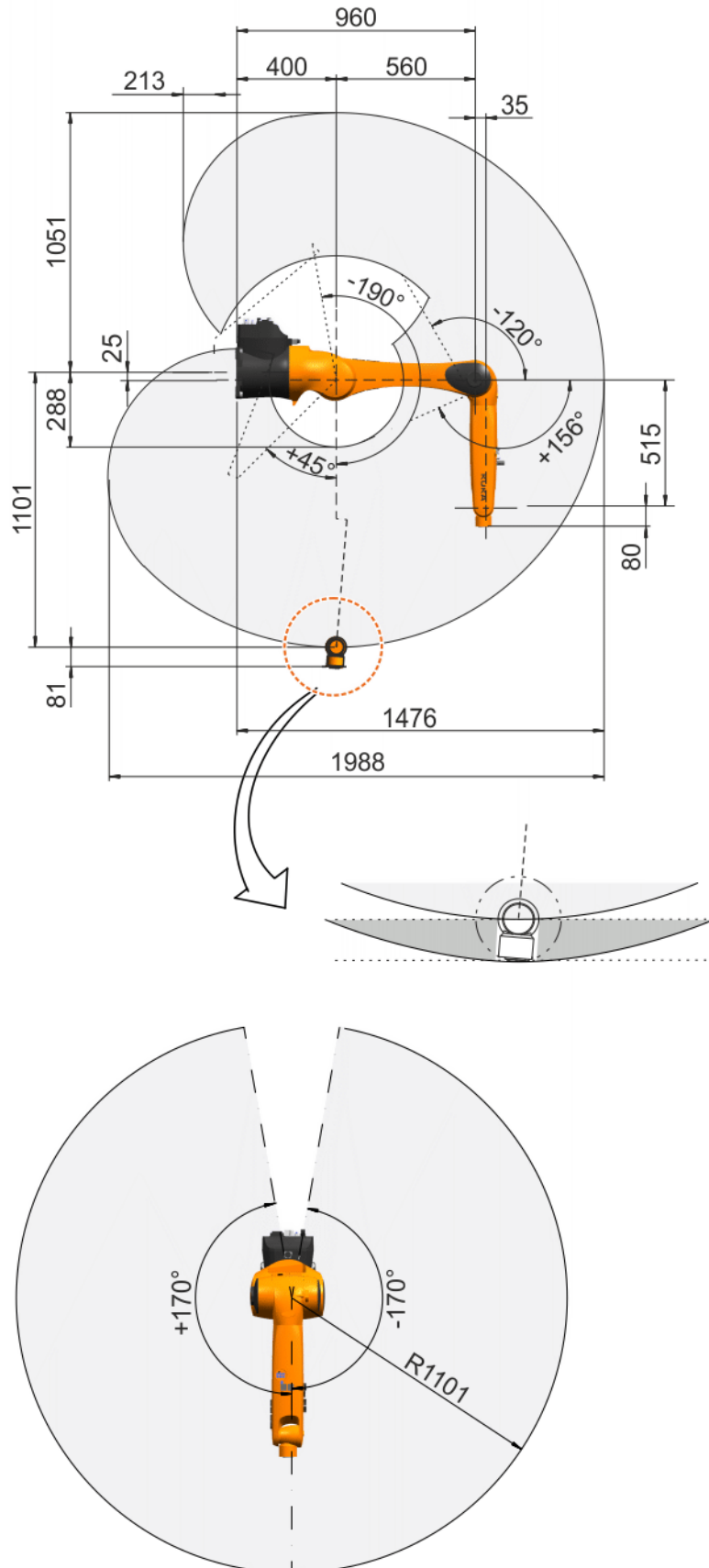


Fig. 4-15: Working envelope, KR 10 R1100 sixx W

The following diagram (>>> Fig. 4-16) shows the shape and size of the working envelope for the robot:

■ KR 10 R1100 sixx C

Maße / Dimensions: mm

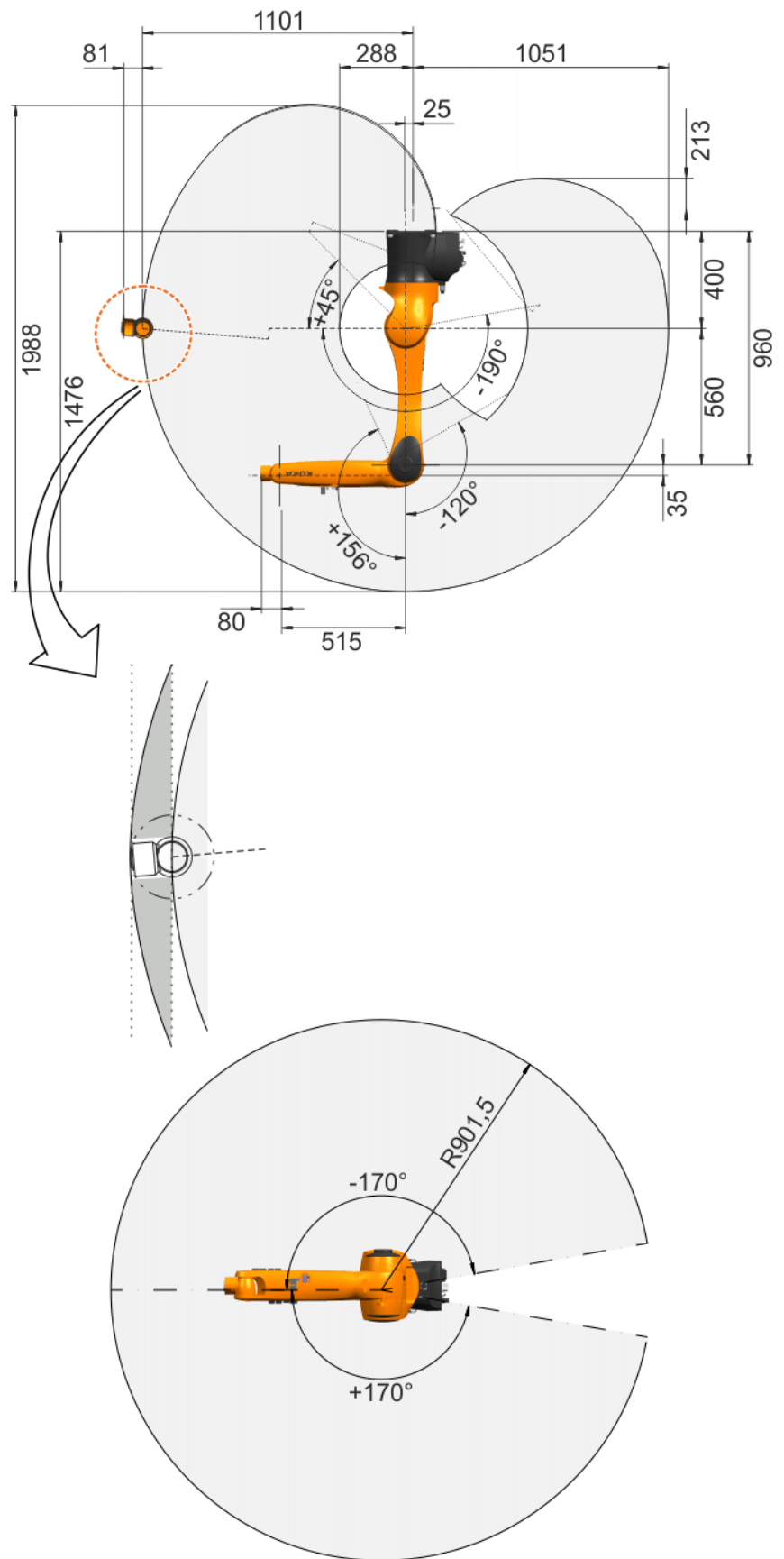


Fig. 4-16: Working envelope, KR 10 R1100 sixx C

4.7 Payloads, KR 10 sixx

Payloads

A distinction is made between the nominal and maximum payload. At the nominal payload, the manipulator is rated for optimal cycle times and accuracy.

Robot	KR 10 R900 sixx KR 10 R900 sixx W KR 10 R900 sixx C KR 10 R1100 sixx KR 10 R1100 sixx W KR 10 R1100 sixx C
In-line wrist	IW 10 R1100
Nominal payload	5 kg
Max. payload	10 kg
Distance of the load center of gravity L_{xy}	100 mm
Distance of the load center of gravity L_z	80 mm
Max. total load	10 kg
Supplementary load	The sum of all loads mounted on the robot must not exceed the maximum total load.

Load center of gravity P

For all payloads, the load center of gravity refers to the distance from the face of the mounting flange on axis 6. Refer to the payload diagram for the nominal distance.

Payload diagram

Permissible mass inertia at the design point (L_x , L_y , L_z) is 0.045 kgm².

The following figure (>>> Fig. 4-17) shows payload diagram for the following robots:

- KR 10 R900 sixx
- KR 10 R900 sixx W
- KR 10 R900 sixx C

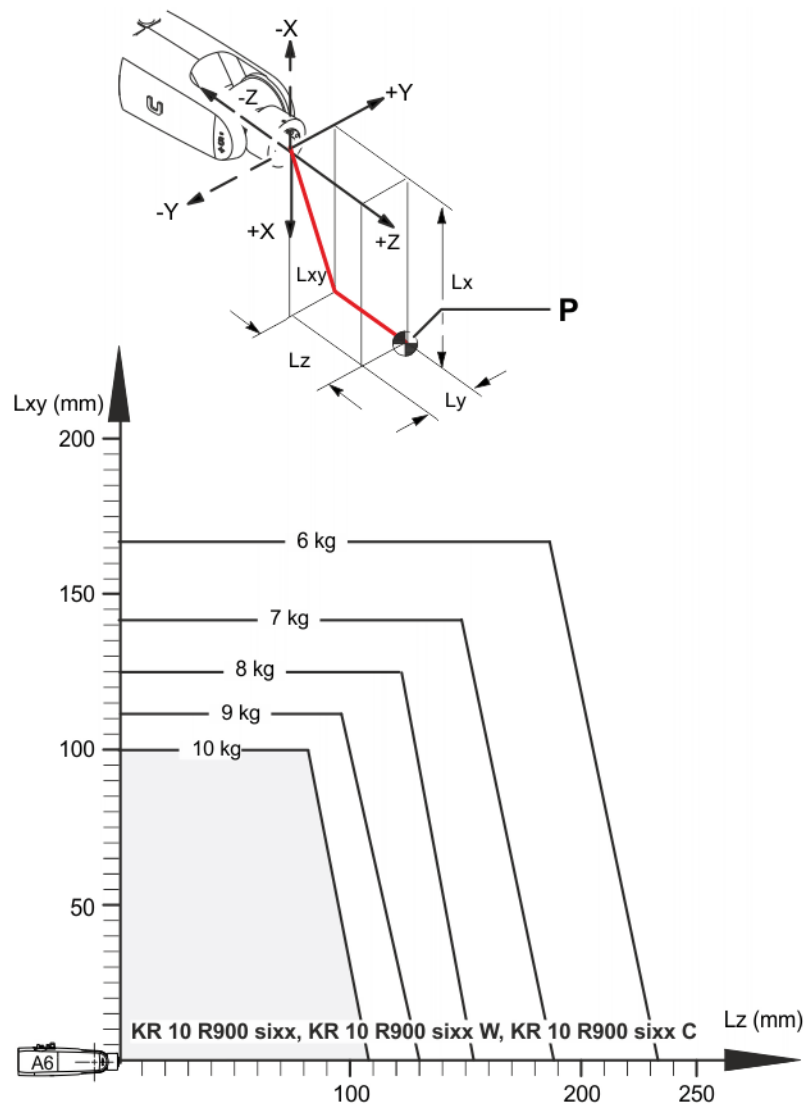


Fig. 4-17: Payload diagram, KR 10 R900 sixx

The following figure (>>> Fig. 4-18) shows payload diagram for the following robots:

- KR 10 R1100 sixx
- KR 10 R1100 sixx W
- KR 10 R1100 sixx C

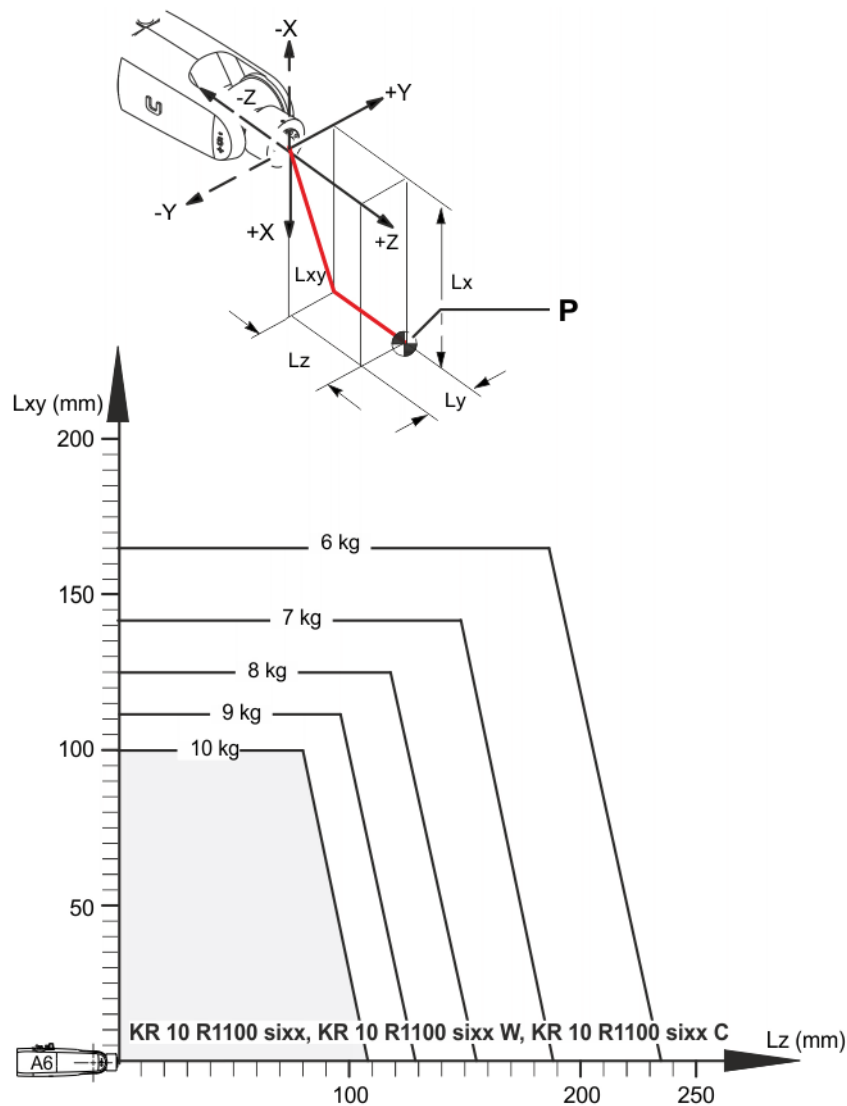


Fig. 4-18: Payload diagram, KR 10 R1100 sixx

NOTICE

This loading curve corresponds to the maximum load capacity. Both values (payload and mass moment of inertia) must be checked in all cases. Exceeding this capacity will reduce the service life of the robot and overload the motors and the gears; in any such case the KUKA Roboter GmbH must be consulted beforehand. The values determined here are necessary for planning the robot application. For commissioning the robot, additional input data are required in accordance with operating and programming instructions of the KUKA System Software. The mass inertia must be verified using KUKA.Load. It is imperative for the load data to be entered in the robot controller!

Mounting flange

Mounting flange	ISO 9409-1: 2004
Screw grade	12.9
Screw size	M5
Grip length	1.5 x nominal diameter
Depth of engagement	min. 5.5 mm, max. 6.5 mm
Locating element	5 H7

The mounting flange is depicted (>>> Fig. 4-19) with axis 6 in the zero position. The symbol X_m indicates the position of the locating element (bushing) in the zero position.

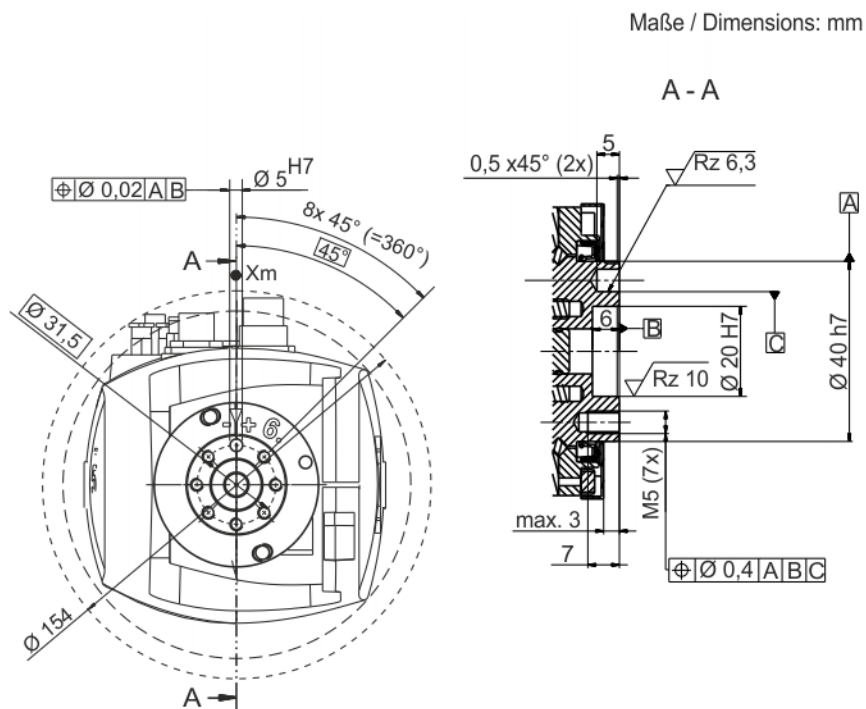


Fig. 4-19: Mounting flange

Supplementary load

The robot can carry supplementary loads on the arm, on the wrist, on the link arm and on the rotating column. The fastening holes are used for fastening the covers or external energy supply systems. When mounting the supplementary loads, be careful to observe the maximum permissible total load. The dimensions and positions of the installation options can be seen in the following diagram.



The sum of all loads mounted on the robot must not exceed the maximum total load.

The following figure (>>> Fig. 4-20) shows the dimensions and position of the installation options on the arm and in-line wrist for the following robots:

- KR 10 R900 sixx
- KR 10 R900 sixx W
- KR 10 R900 sixx C

Maße / Dimensions: mm

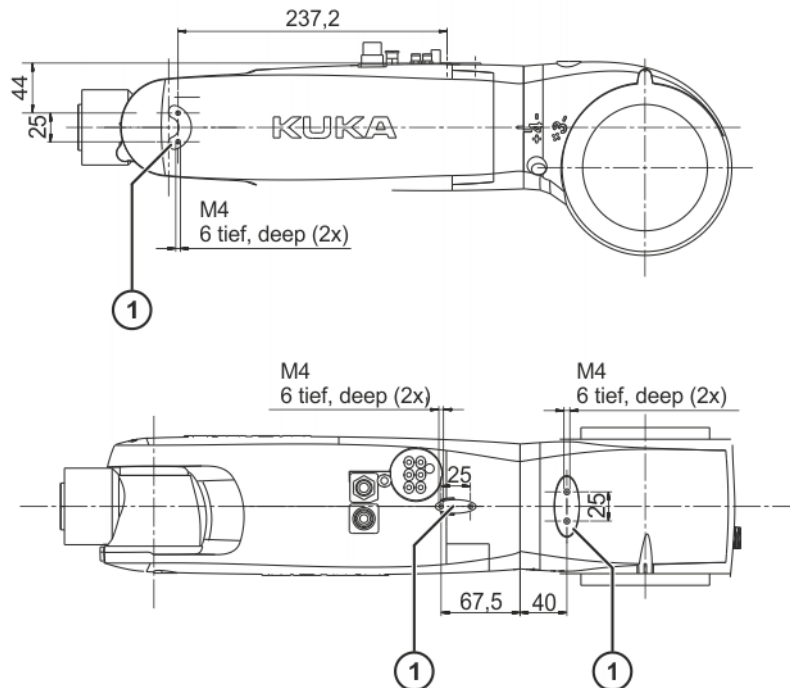


Fig. 4-20: Supplementary load on arm and in-line wrist

- 1 Support bracket for supplementary load

The following figure (>>> Fig. 4-21) shows the dimensions and position of the installation options on the link arm and rotating column for the following robots:

- KR 10 R900 sixx
- KR 10 R900 sixx W
- KR 10 R900 sixx C

Maße / Dimensions: mm

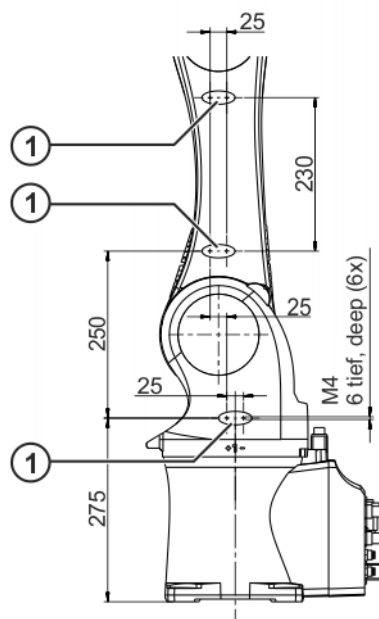


Fig. 4-21: Supplementary load on link arm and rotating column

- 1 Support bracket for supplementary load

The following figure (>>> Fig. 4-22) shows the dimensions and position of the installation options on the arm and in-line wrist for the following robots:

- KR 10 R1100 sixx
- KR 10 R1100 sixx W
- KR 10 R1100 sixx C

Maße / Dimensions: mm

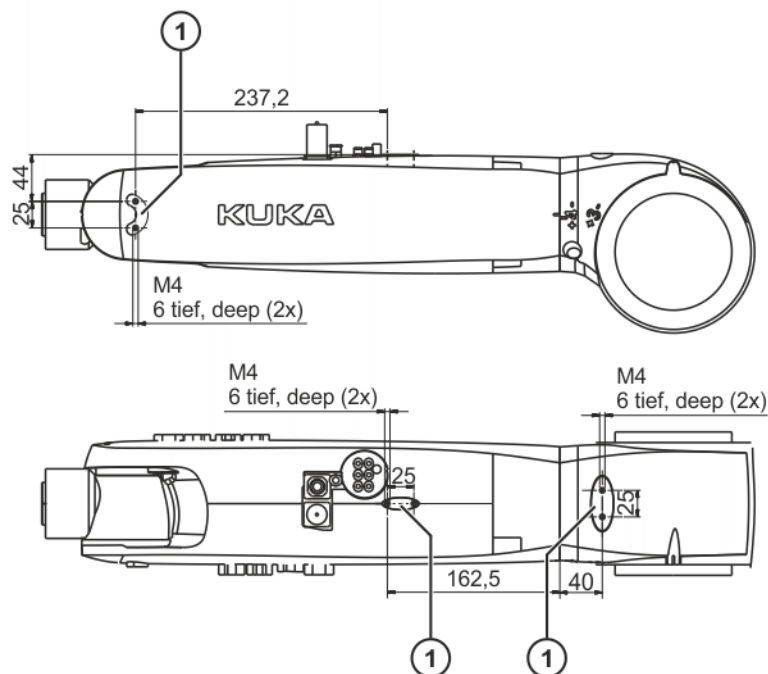


Fig. 4-22: Supplementary load on arm and in-line wrist

- 1 Support bracket for supplementary load

The following figure (>>> Fig. 4-23) shows the dimensions and position of the installation options on the link arm and rotating column for the following robots:

- KR 10 R1100 sixx
- KR 10 R1100 sixx W
- KR 10 R1100 sixx C

Maße / Dimensions: mm

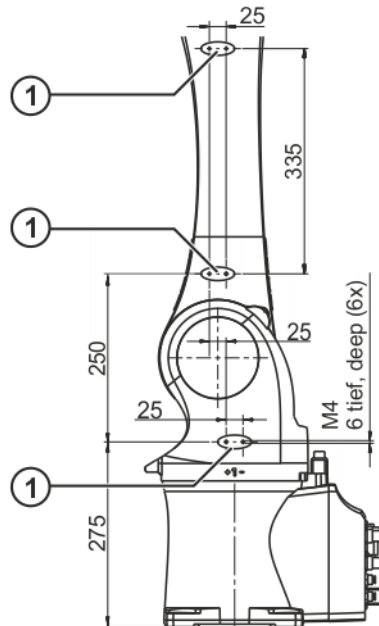


Fig. 4-23: Supplementary load on link arm and rotating column

- 1 Support bracket for supplementary load

4.8 Mounting base data, KR 10 sixx

Loads acting on the mounting base

The specified forces and moments already include the maximum payload and the inertia force (weight) of the robot.

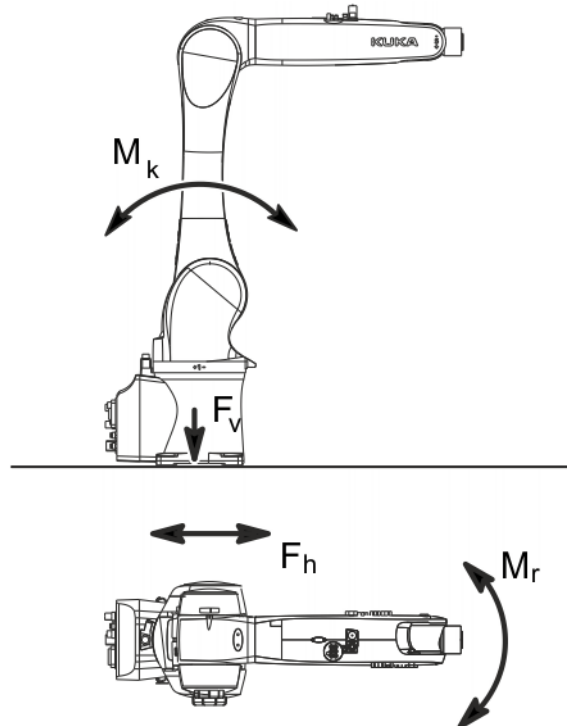


Fig. 4-24: Loads acting on the mounting base

Type of load	Force/torque/mass	
	Normal operation	Maximum load
F_v = vertical force	$F_{vmax} = 967 \text{ N}$	$F_{vmax} = 1297 \text{ N}$
F_h = horizontal force	$F_{hmax} = 1223 \text{ N}$	$F_{hmax} = 1362 \text{ N}$
M_k = tilting moment	$M_{kmax} = 788 \text{ Nm}$	$M_{kmax} = 1152 \text{ Nm}$
M_r = torque	$M_{rmax} = 367 \text{ Nm}$	$M_{rmax} = 880 \text{ Nm}$
Total mass for load acting on the mounting base	KR 10 R900 sixx: 62 kg KR 10 R1100 sixx: 65 kg	
Robot	KR 10 R900 sixx: 52 kg KR 10 R1100 sixx: 55 kg	
Total load for mounting base load (suppl. load on arm + rated payload)	KR 10 R900 sixx: 10 kg KR 10 R1100 sixx: 10 kg	

NOTICE

The mounting base loads specified in the table are the maximum loads that may occur. They must be referred to when dimensioning the mounting bases and must be adhered to for safety reasons.

The supplementary loads on the base frame and rotating column are not taken into consideration in the calculation of the mounting base load. These supplementary loads must be taken into consideration for F_v .

4.9 Plates and labels

Plates and labels The following plates and labels are attached to the robot. They must not be removed or rendered illegible. Illegible plates and labels must be replaced.

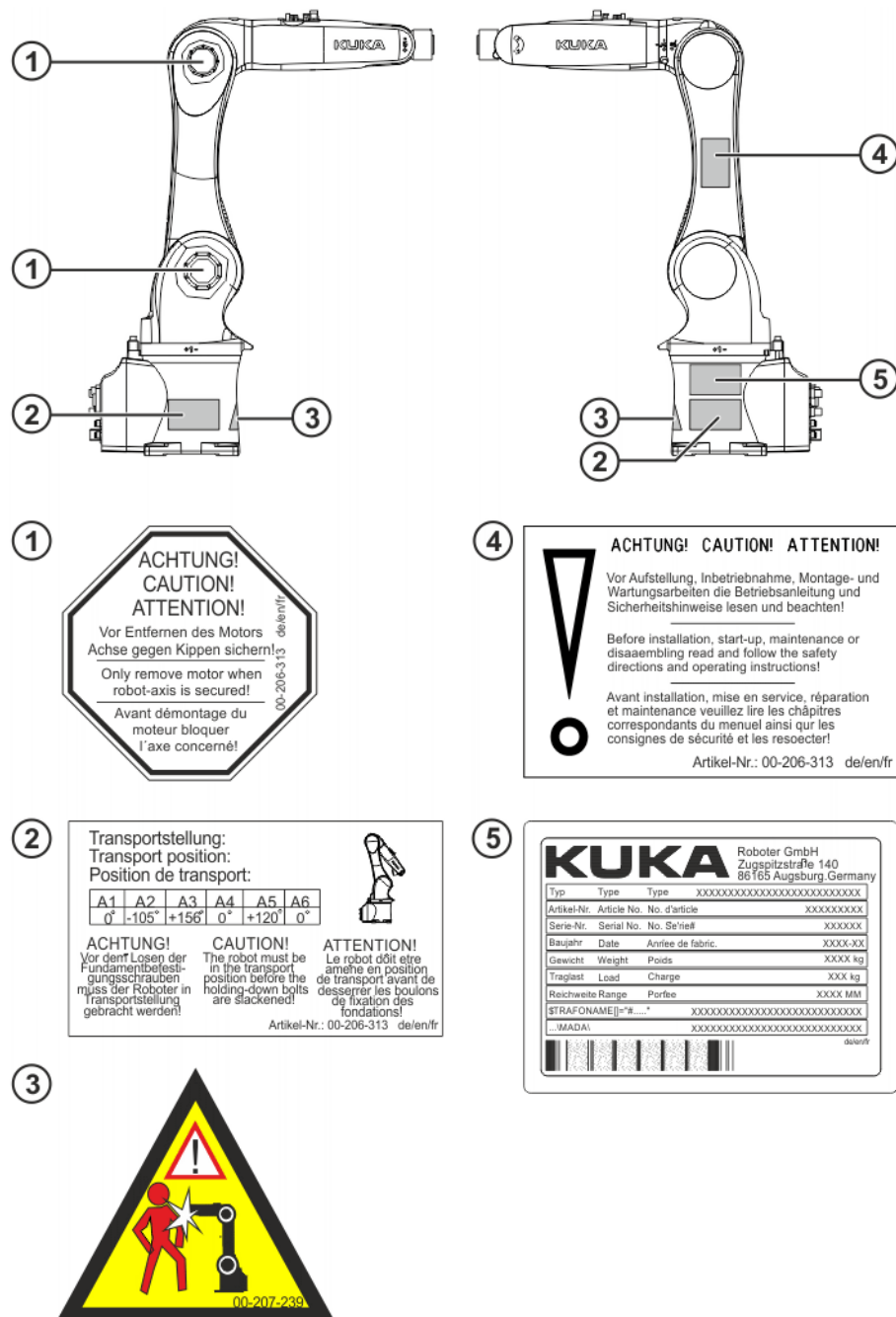


Fig. 4-25: Plates and labels

4.10 Stopping distances and times

4.10.1 General information

Information concerning the data:

- The stopping distance is the angle traveled by the robot from the moment the stop signal is triggered until the robot comes to a complete standstill.
- The stopping time is the time that elapses from the moment the stop signal is triggered until the robot comes to a complete standstill.
- The data are given for the main axes A1, A2 and A3. The main axes are the axes with the greatest deflection.
- Superposed axis motions can result in longer stopping distances.

- Stopping distances and stopping times in accordance with DIN EN ISO 10218-1, Annex B.
- Stop categories:
 - Stop category 0 » STOP 0
 - Stop category 1 » STOP 1 according to IEC 60204-1
- The values specified for Stop 0 are guide values determined by means of tests and simulation. They are average values which conform to the requirements of DIN EN ISO 10218-1. The actual stopping distances and stopping times may differ due to internal and external influences on the braking torque. It is therefore advisable to determine the exact stopping distances and stopping times where necessary under the real conditions of the actual robot application.
- Measuring technique
The stopping distances were measured using the robot-internal measuring technique.
- The wear on the brakes varies depending on the operating mode, robot application and the number of STOP 0 triggered. It is therefore advisable to check the stopping distance at least once a year.

4.10.2 Terms used

Term	Description
m	Mass of the rated load and the supplementary load on the arm.
Phi	Angle of rotation (°) about the corresponding axis. This value can be entered in the controller via the KCP and is displayed on the KCP.
POV	Program override (%) = velocity of the robot motion. This value can be entered in the controller via the KCP and is displayed on the KCP.
Extension	Distance (l in %) (>>> Fig. 4-26) between axis 1 and the intersection of axes 4 and 5. With parallelogram robots, the distance between axis 1 and the intersection of axis 6 and the mounting flange.
KCP	The KCP teach pendant has all the operator control and display functions required for operating and programming the robot system.

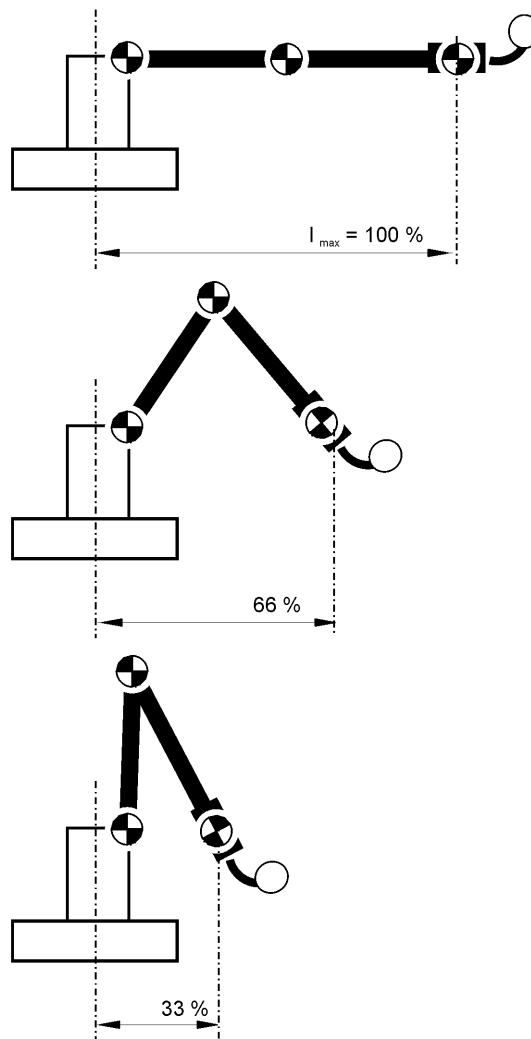


Fig. 4-26: Extension

4.10.3 Stopping distances and times, KR 6 R900 sixx

The following values are valid for the following robots:

- KR 6 R900 sixx
- KR 6 R900 sixx C

4.10.3.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension $l = 100\%$
- Program override POV = 100%
- Mass $m =$ maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	113.59	0.507
Axis 2	126.76	0.684
Axis 3	68.10	0.370

4.10.3.2 Stopping distances and stopping times for STOP 1, axis 1

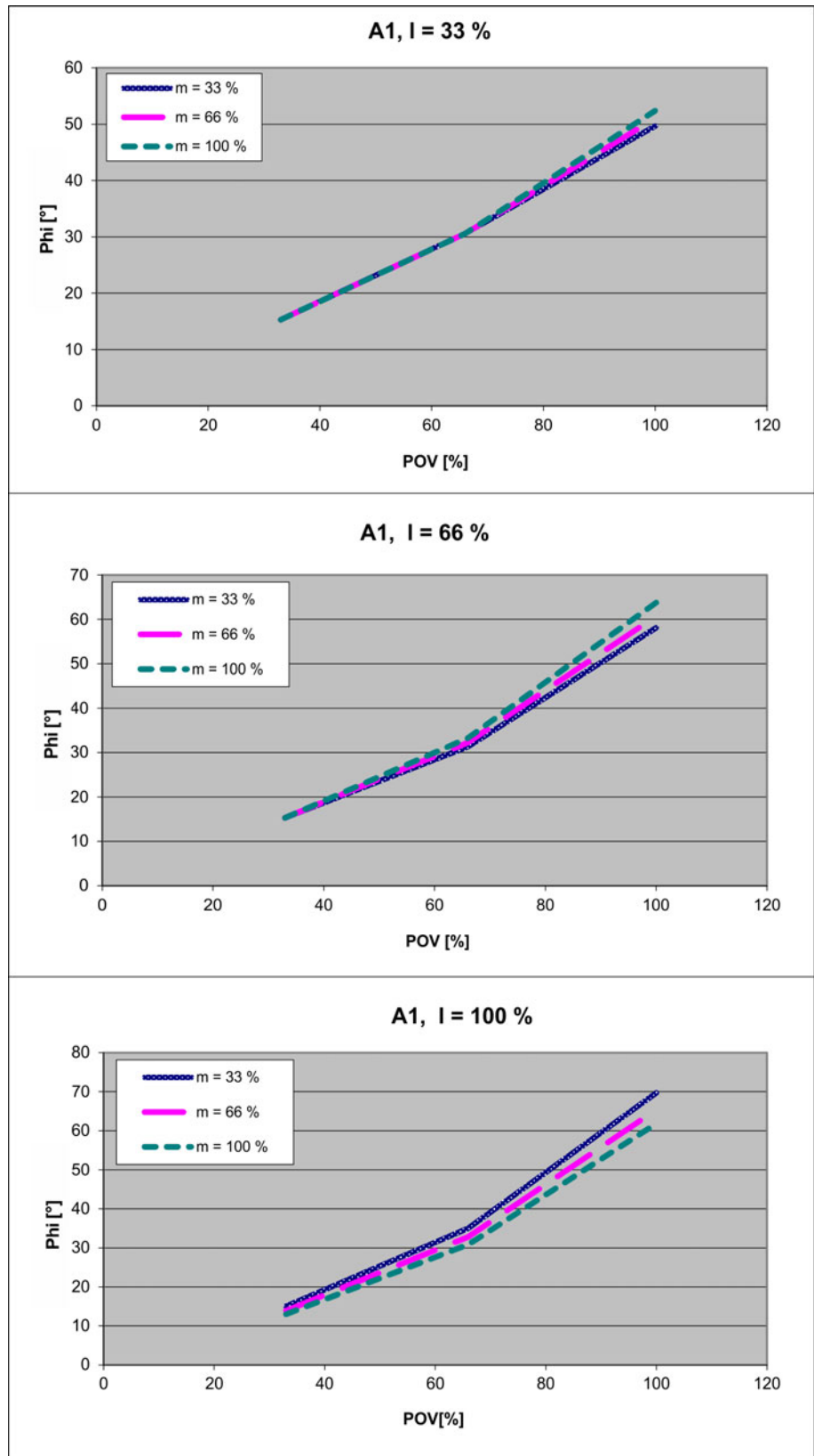


Fig. 4-27: Stopping distances for STOP 1, axis 1

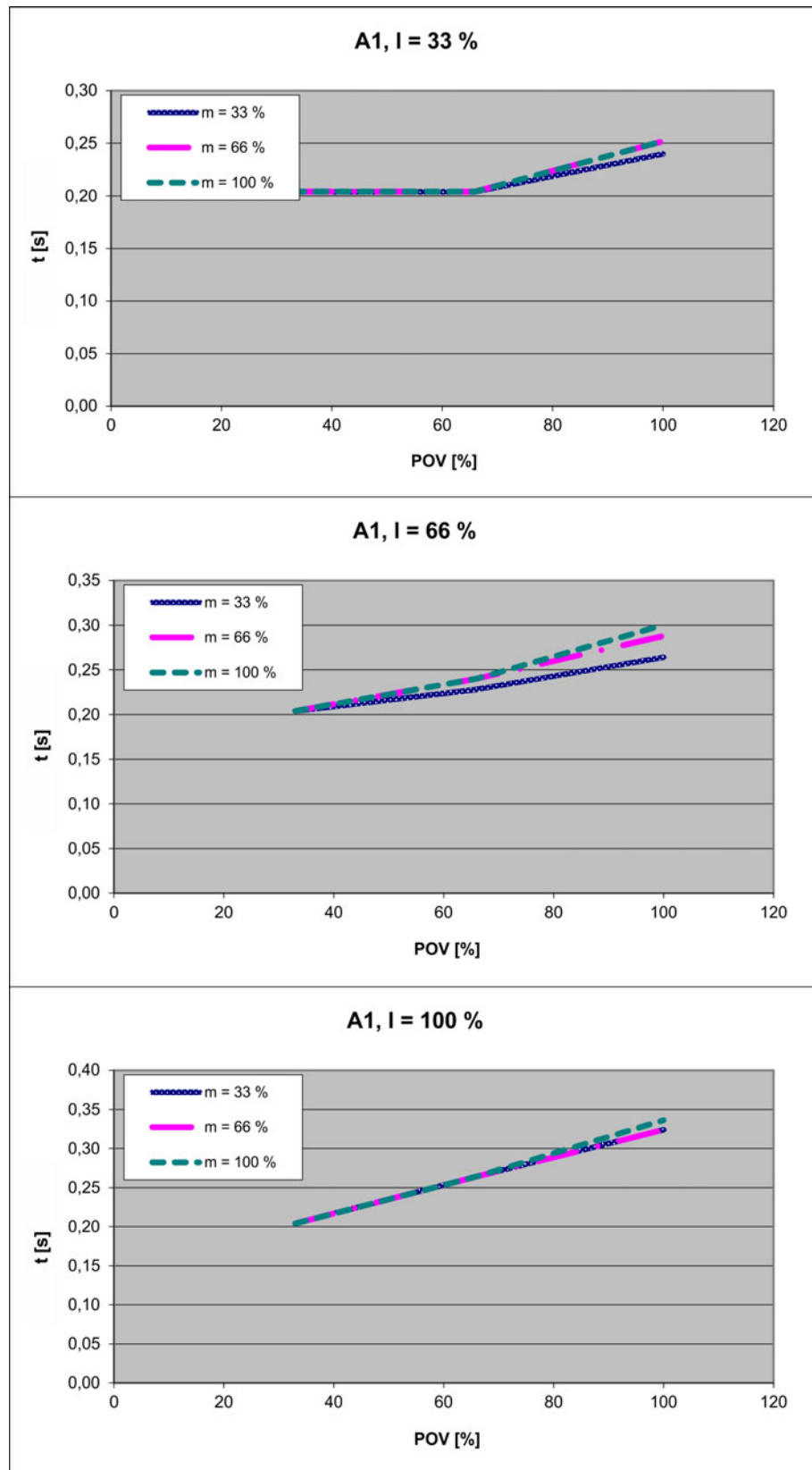


Fig. 4-28: Stopping times for STOP 1, axis 1

4.10.3.3 Stopping distances and stopping times for STOP 1, axis 2

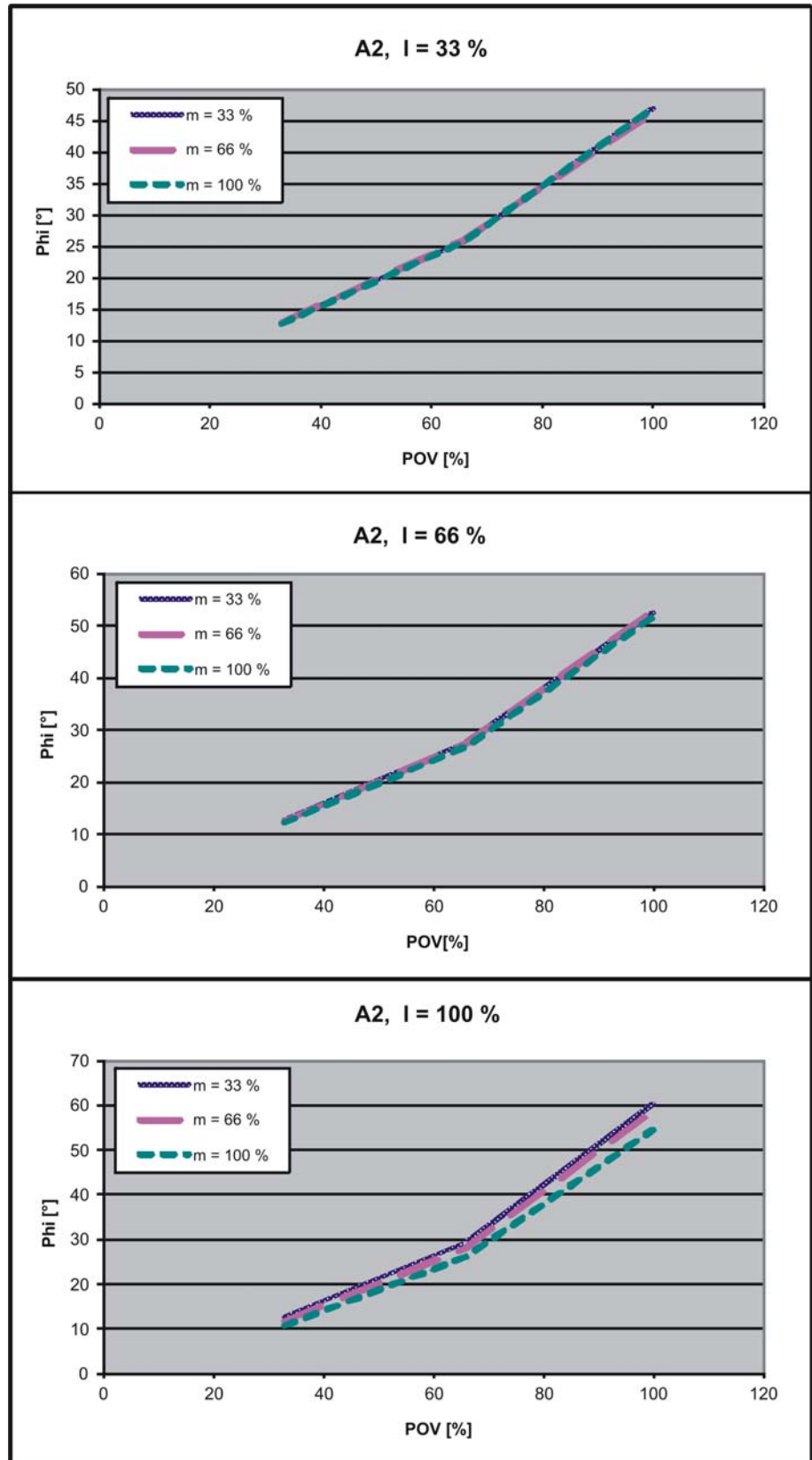


Fig. 4-29: Stopping distances for STOP 1, axis 2

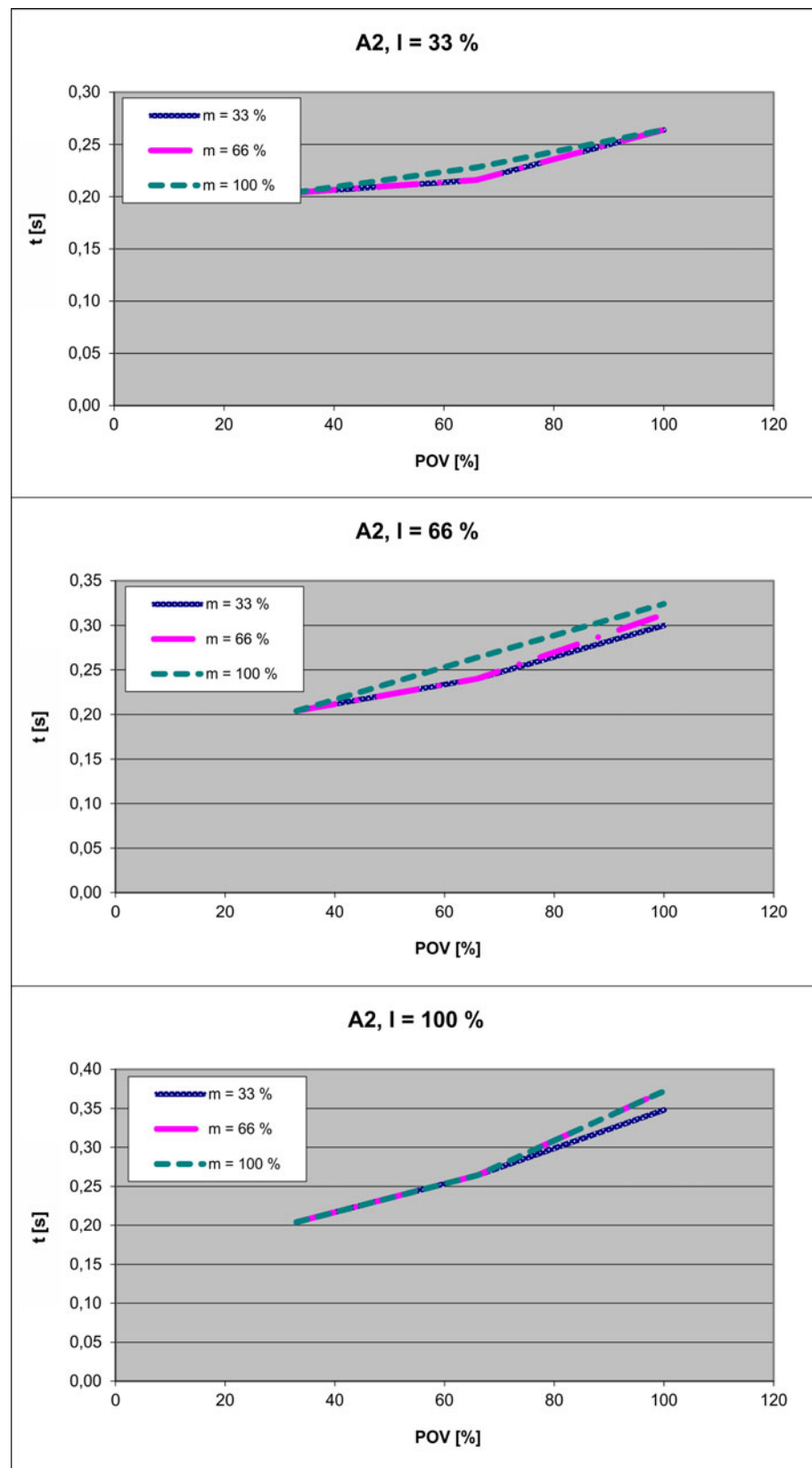


Fig. 4-30: Stopping times for STOP 1, axis 2

4.10.3.4 Stopping distances and stopping times for STOP 1, axis 3

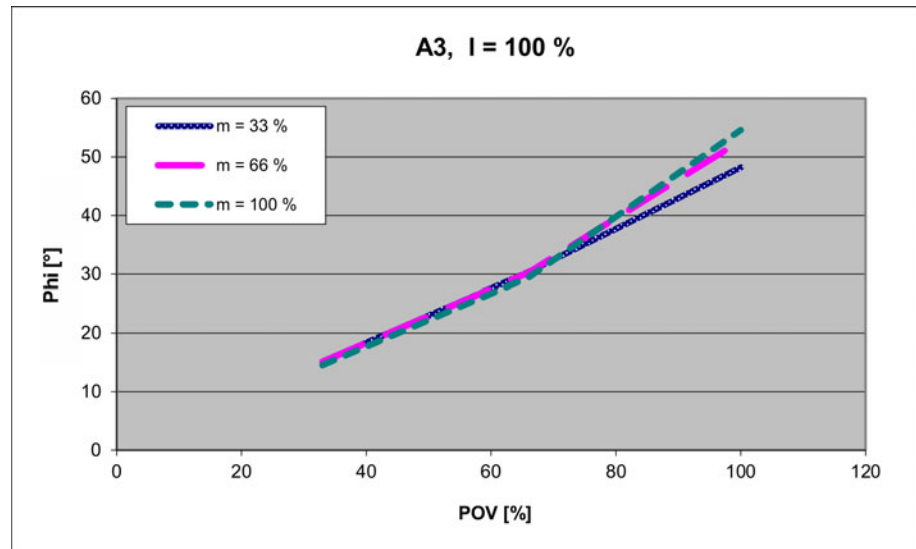


Fig. 4-31: Stopping distances for STOP 1, axis 3

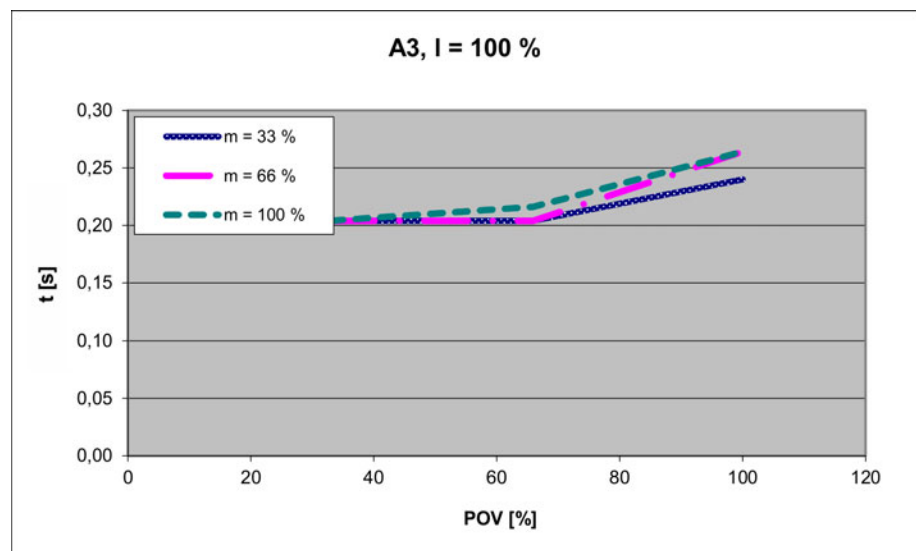


Fig. 4-32: Stopping times for STOP 1, axis 3

4.10.4 Stopping distances and times, KR 6 R900 sixx W

The following values are valid for the following robots:

- KR 6 R900 sixx W

4.10.4.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension I = 100%
- Program override POV = 100%
- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	163.11	0.745
Axis 2	67.78	0.404
Axis 3	60.96	0.387

4.10.4.2 Stopping distances and stopping times for STOP 1, axis 1

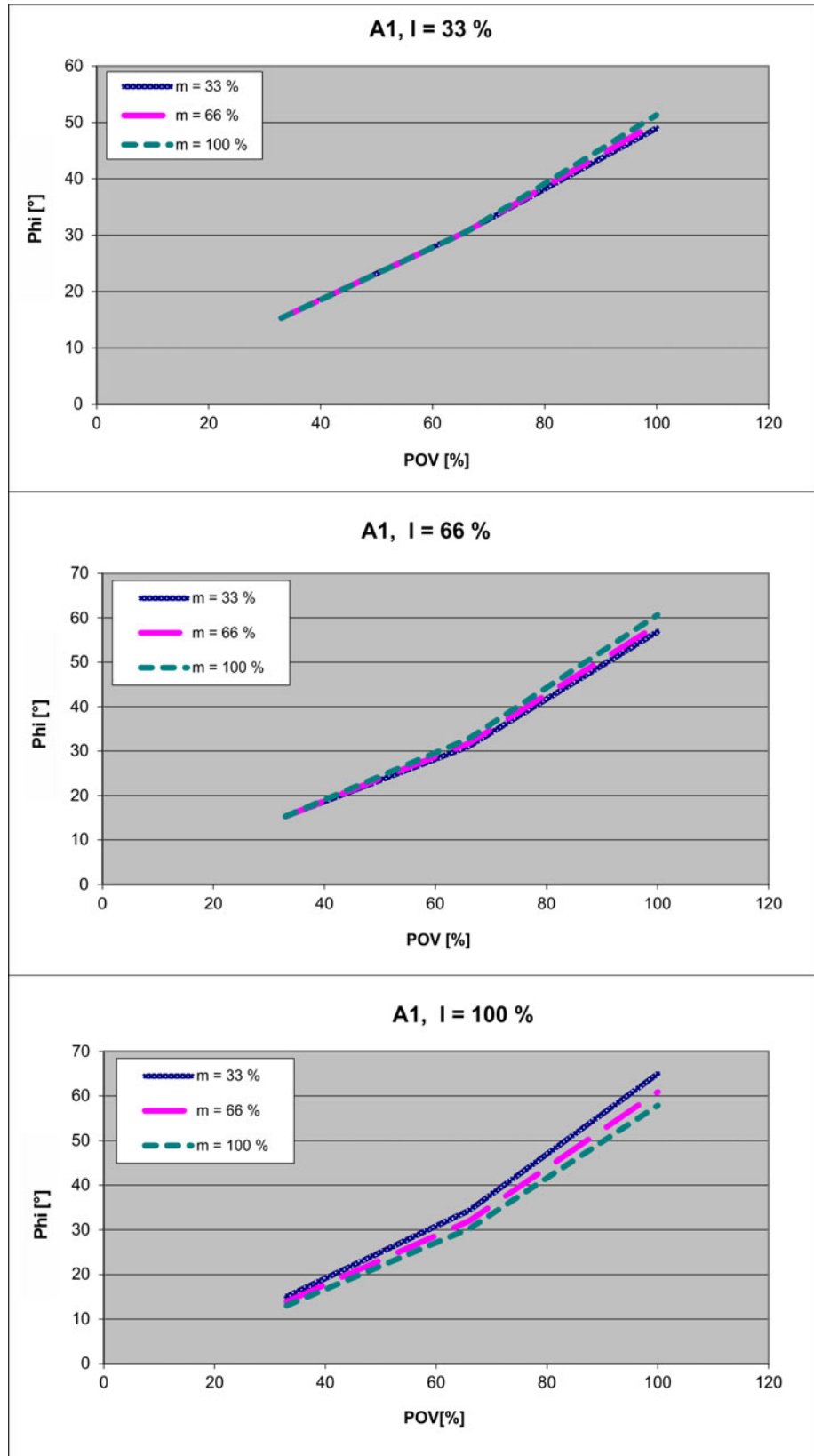


Fig. 4-33: Stopping distances for STOP 1, axis 1

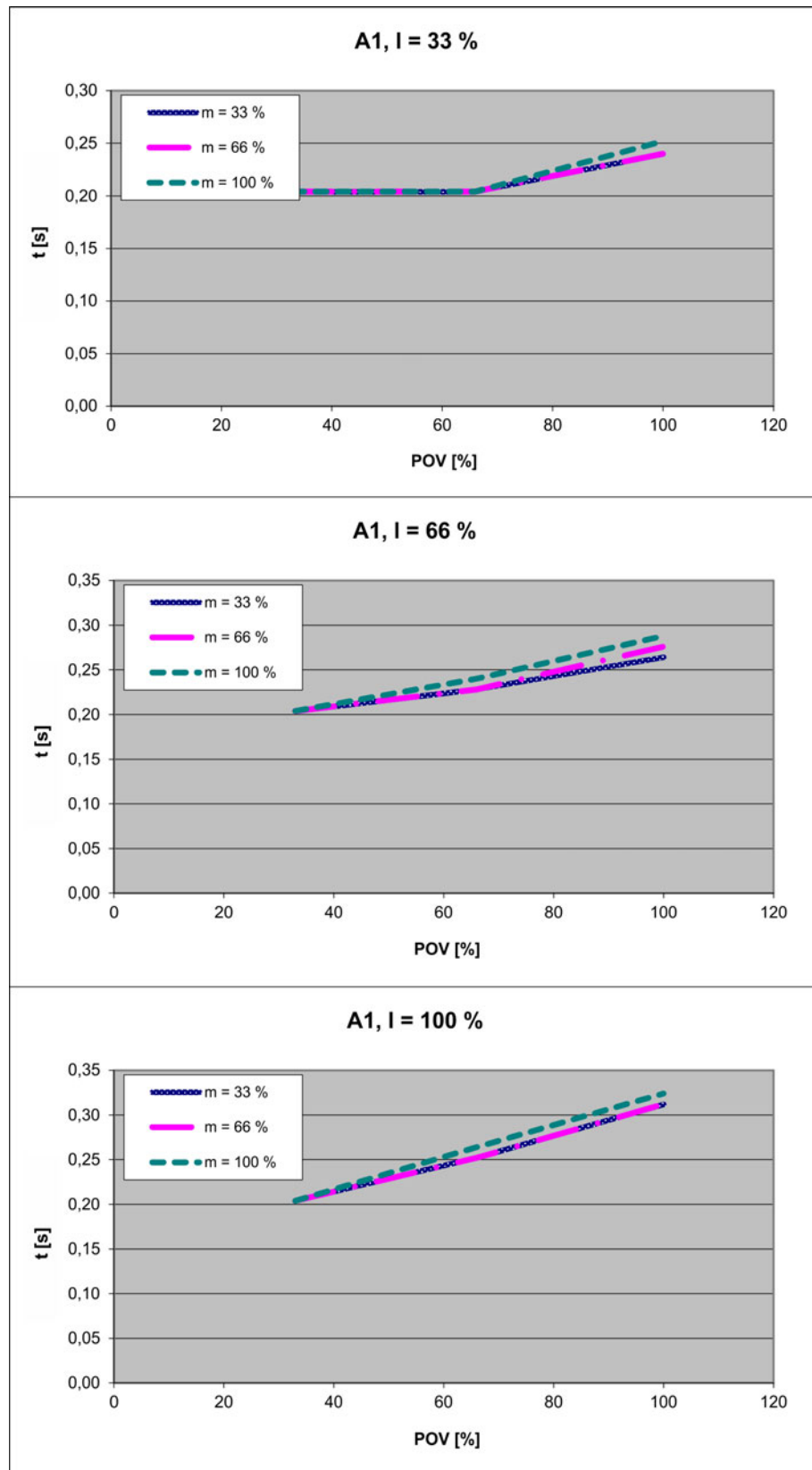


Fig. 4-34: Stopping times for STOP 1, axis 1

4.10.4.3 Stopping distances and stopping times for STOP 1, axis 2

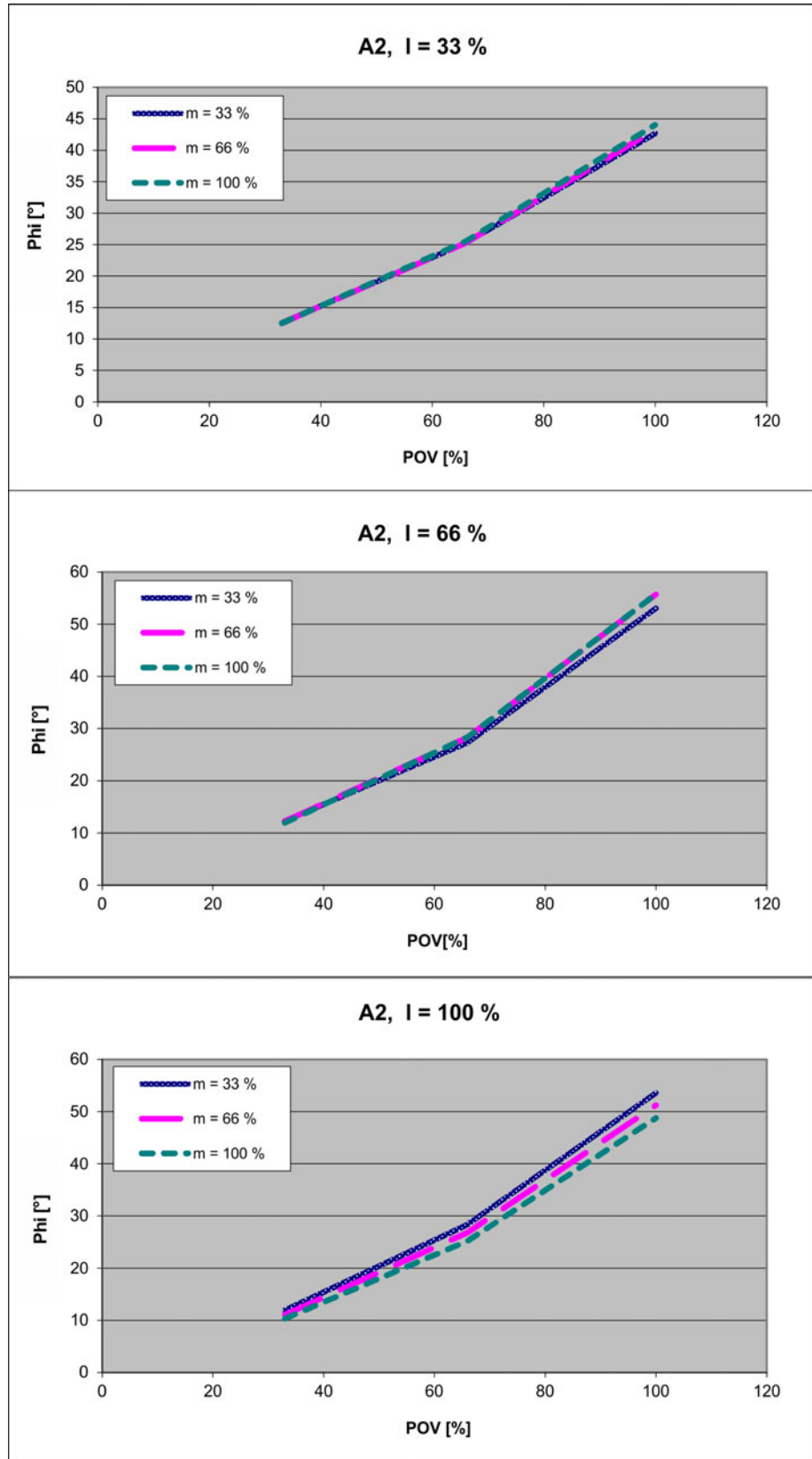


Fig. 4-35: Stopping distances for STOP 1, axis 2

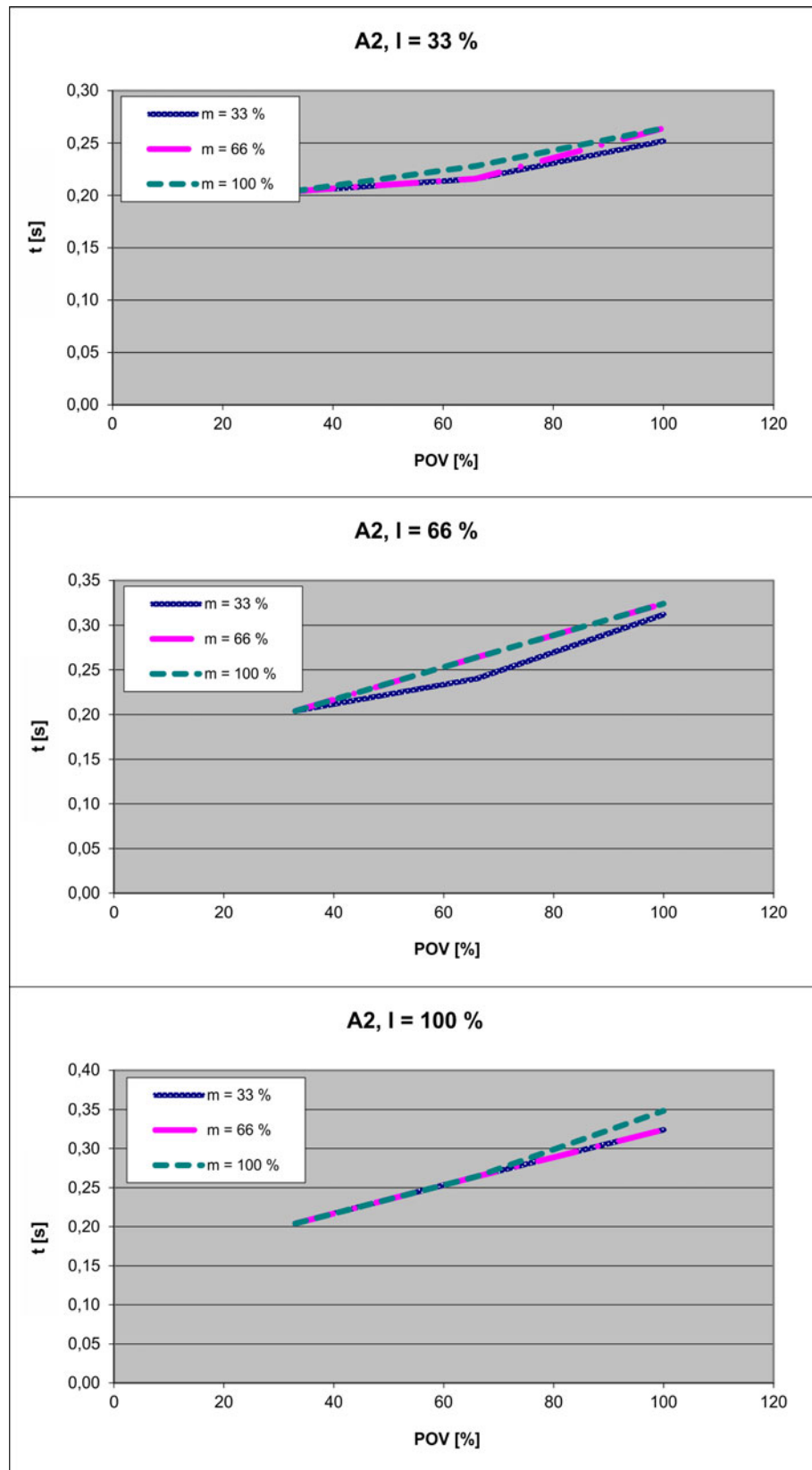


Fig. 4-36: Stopping times for STOP 1, axis 2

4.10.4.4 Stopping distances and stopping times for STOP 1, axis 3

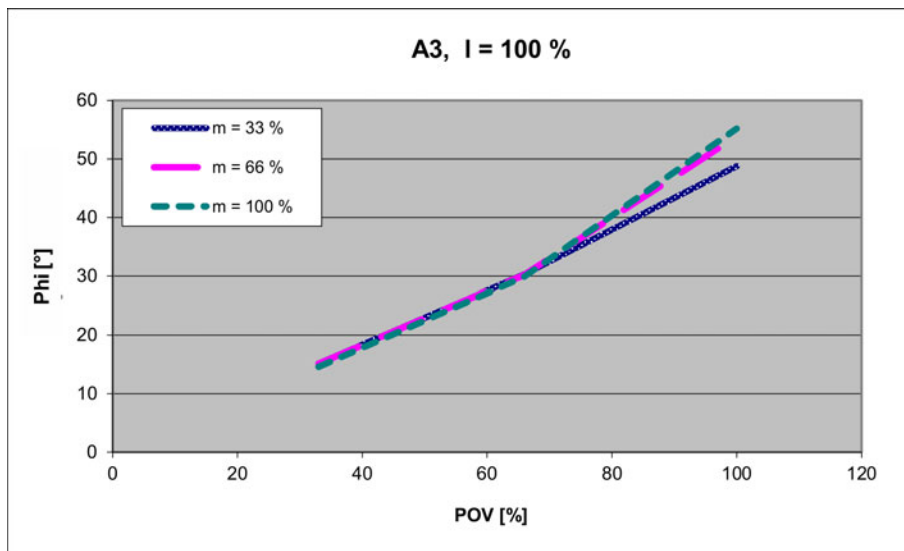


Fig. 4-37: Stopping distances for STOP 1, axis 3

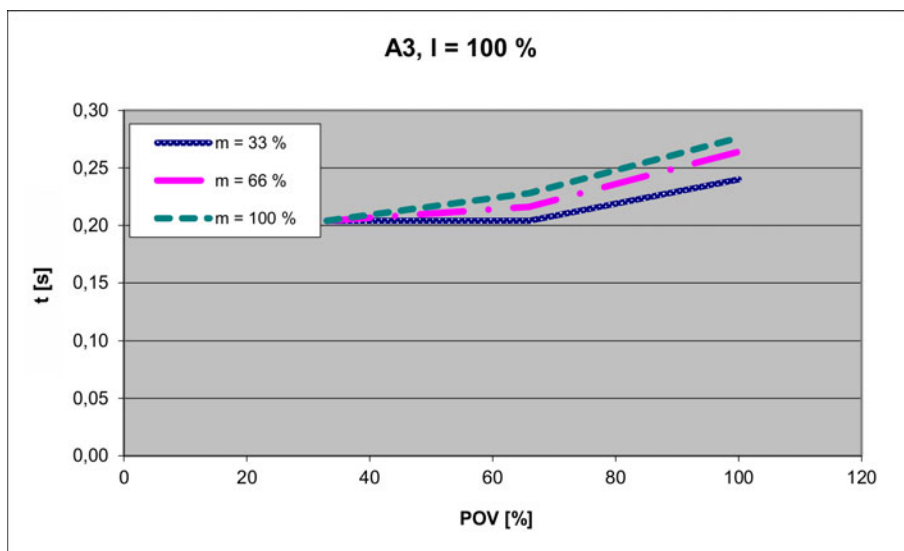


Fig. 4-38: Stopping times for STOP 1, axis 3

4.10.5 Stopping distances and times, KR 10 R900 sixx and KR 10 R1100 sixx

The following values are preliminary values and are valid for the following robots.

- KR 10 R900 sixx
- KR 10 R900 sixx C
- KR 10 R1100 sixx
- KR 10 R1100 sixx C

4.10.5.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension I = 100%
- Program override POV = 100%

- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	106.21	0.536
Axis 2	96.06	0.647
Axis 3	46.99	0.373

4.10.5.2 Stopping distances and stopping times for STOP 1, axis 1

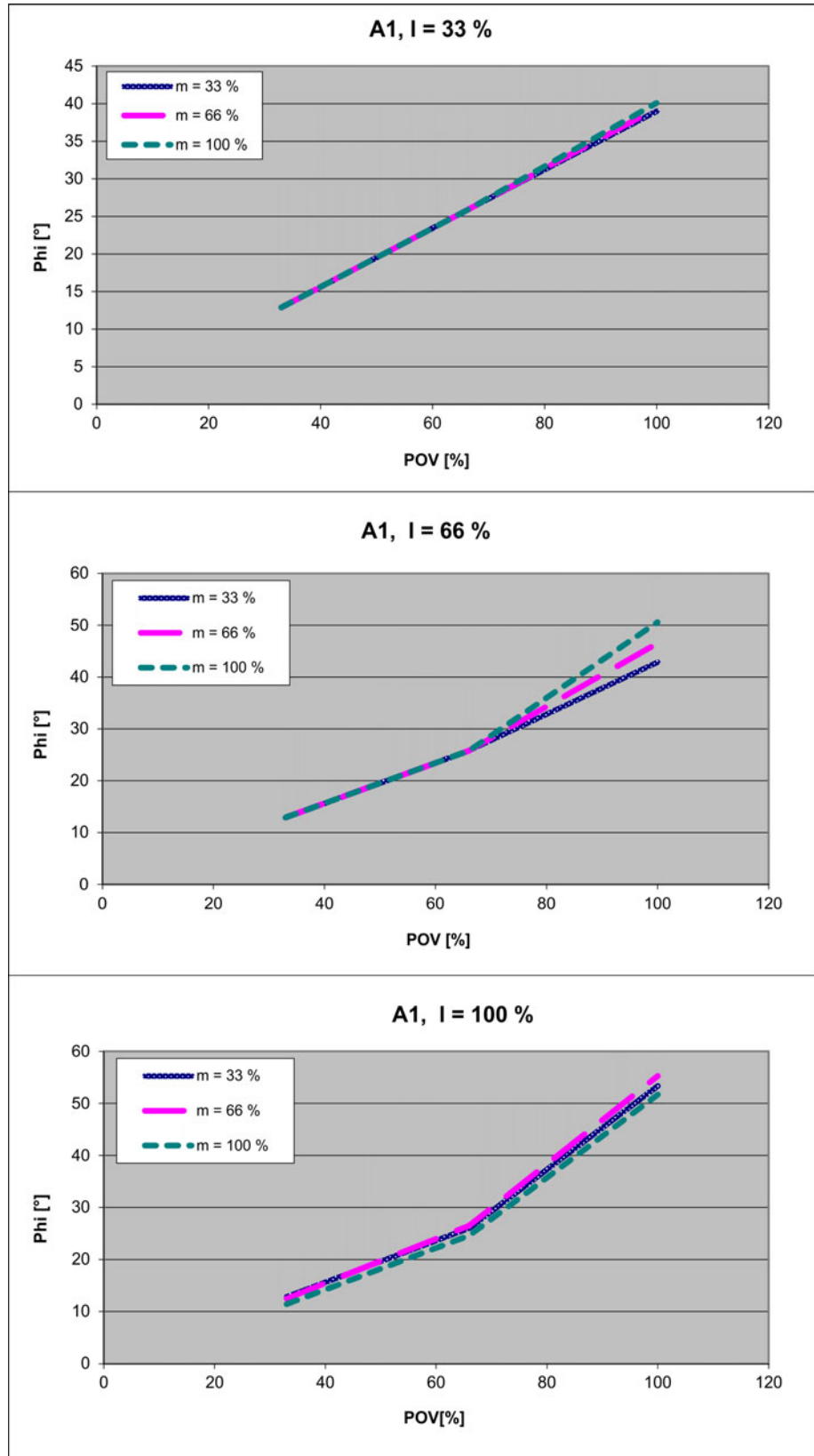


Fig. 4-39: Stopping distances for STOP 1, axis 1

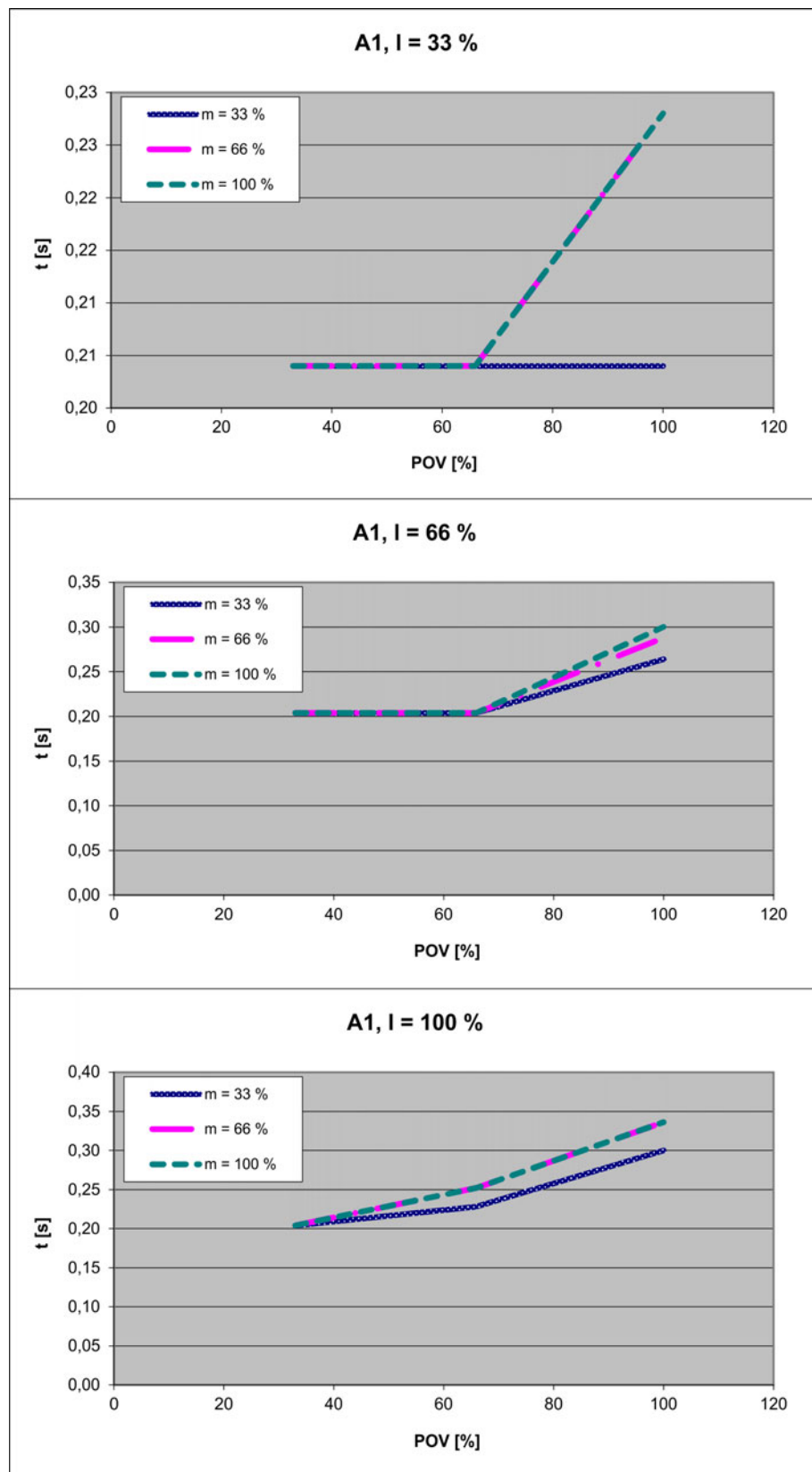


Fig. 4-40: Stopping times for STOP 1, axis 1

4.10.5.3 Stopping distances and stopping times for STOP 1, axis 2

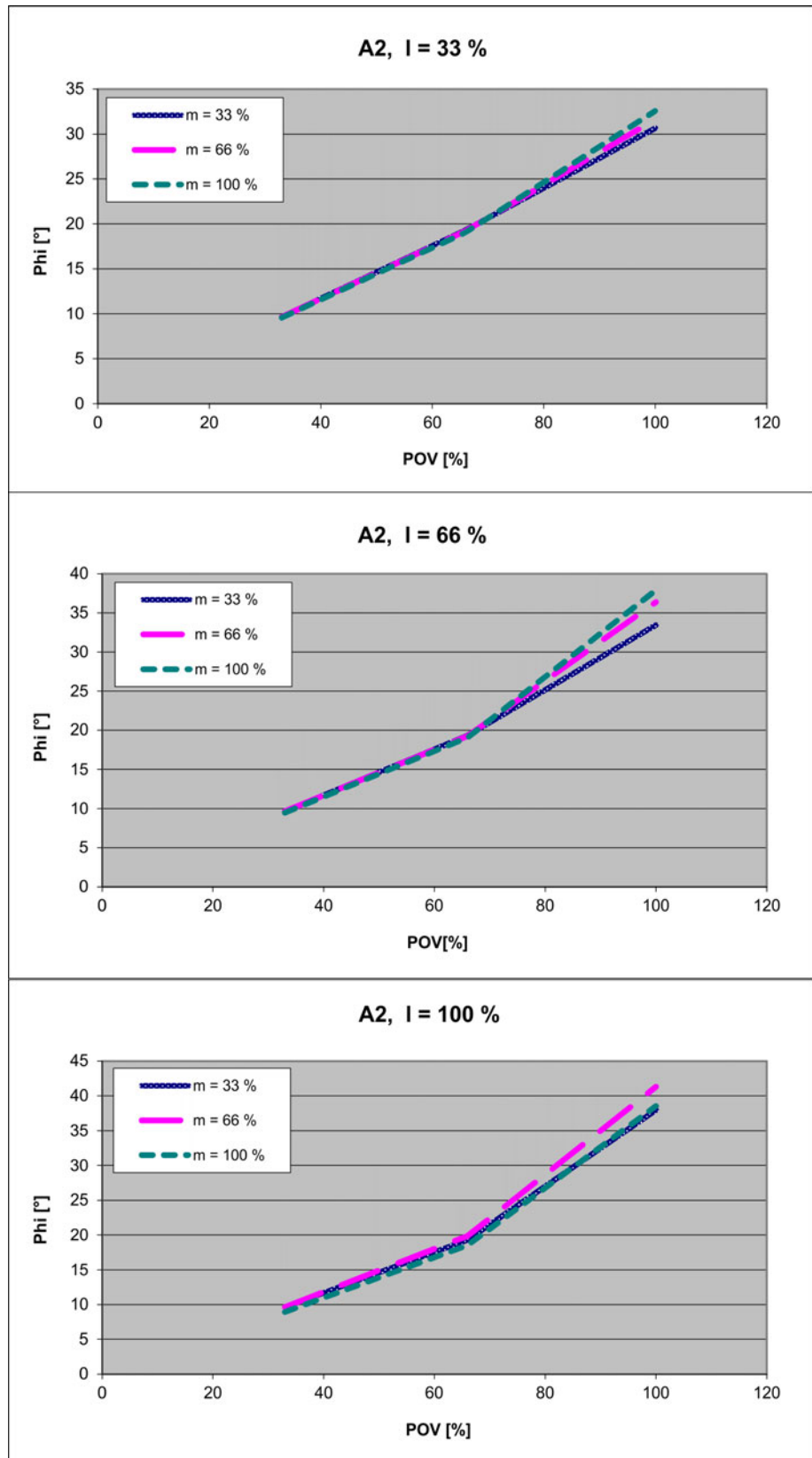


Fig. 4-41: Stopping distances for STOP 1, axis 2

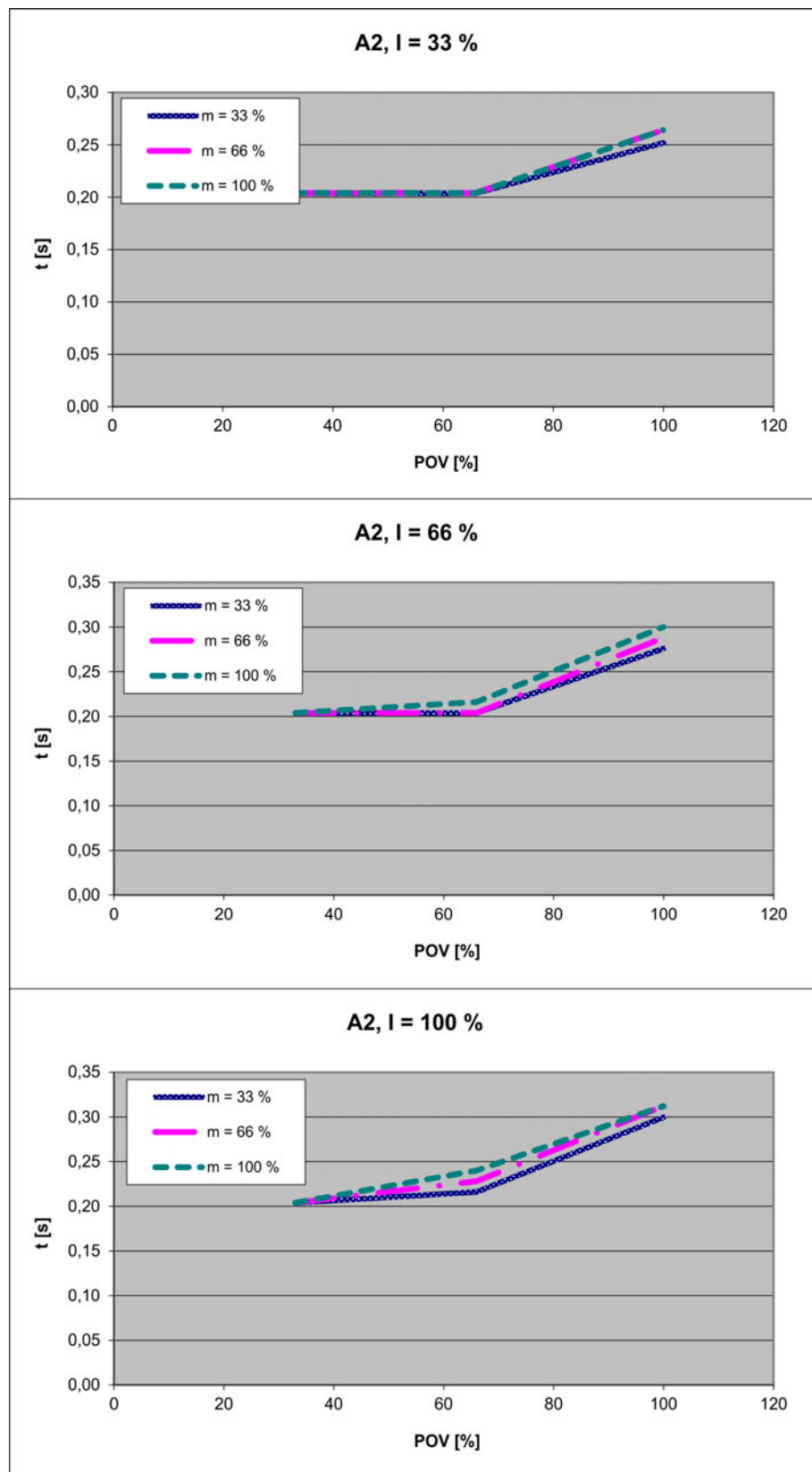


Fig. 4-42: Stopping times for STOP 1, axis 2

4.10.5.4 Stopping distances and stopping times for STOP 1, axis 3

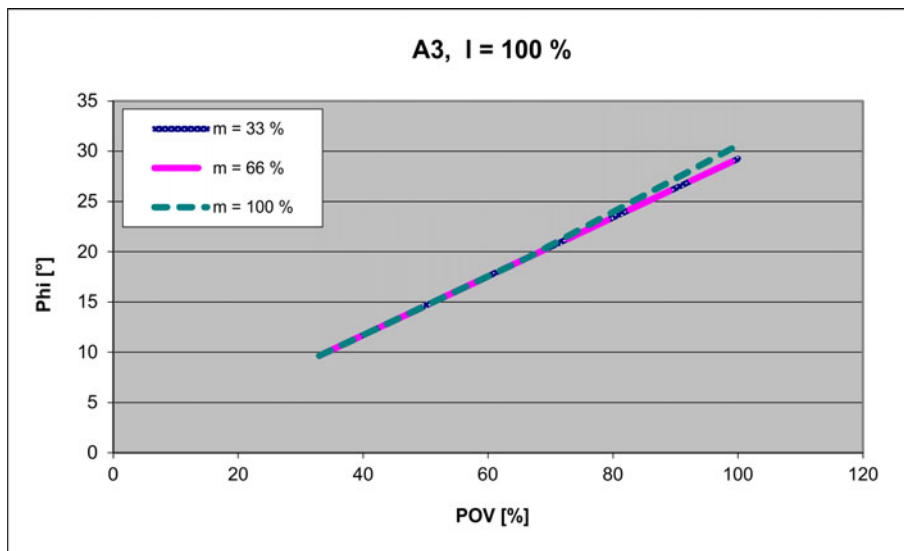


Fig. 4-43: Stopping distances for STOP 1, axis 3

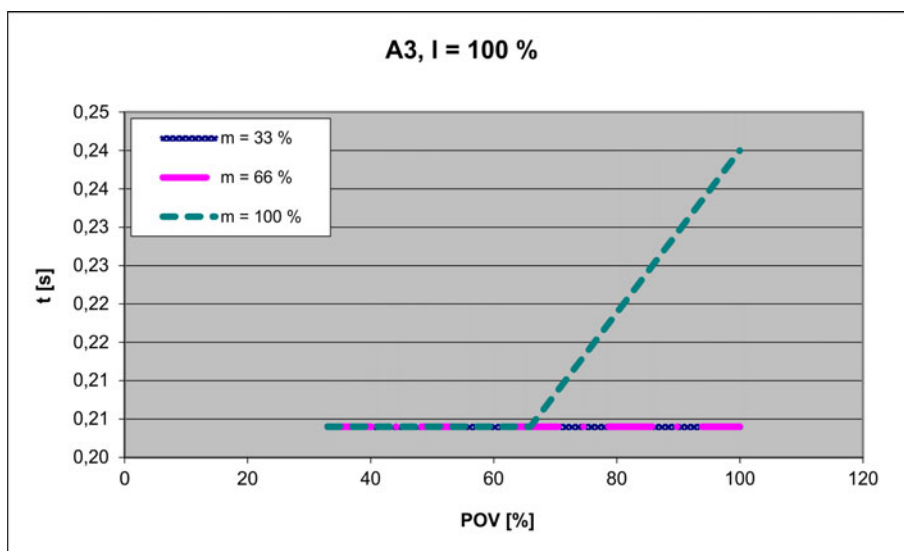


Fig. 4-44: Stopping times for STOP 1, axis 3

4.10.6 Stopping distances and times, KR 10 R900 sixx W and KR 10 R1100 sixx W

The following values are preliminary values and are valid for the following robots.

- KR 10 R900 sixx W
- KR 10 R1100 sixx W

4.10.6.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension I = 100%
- Program override POV = 100%
- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	163.11	0.745
Axis 2	67.78	0.404
Axis 3	60.96	0.387

4.10.6.2 Stopping distances and stopping times for STOP 1, axis 1

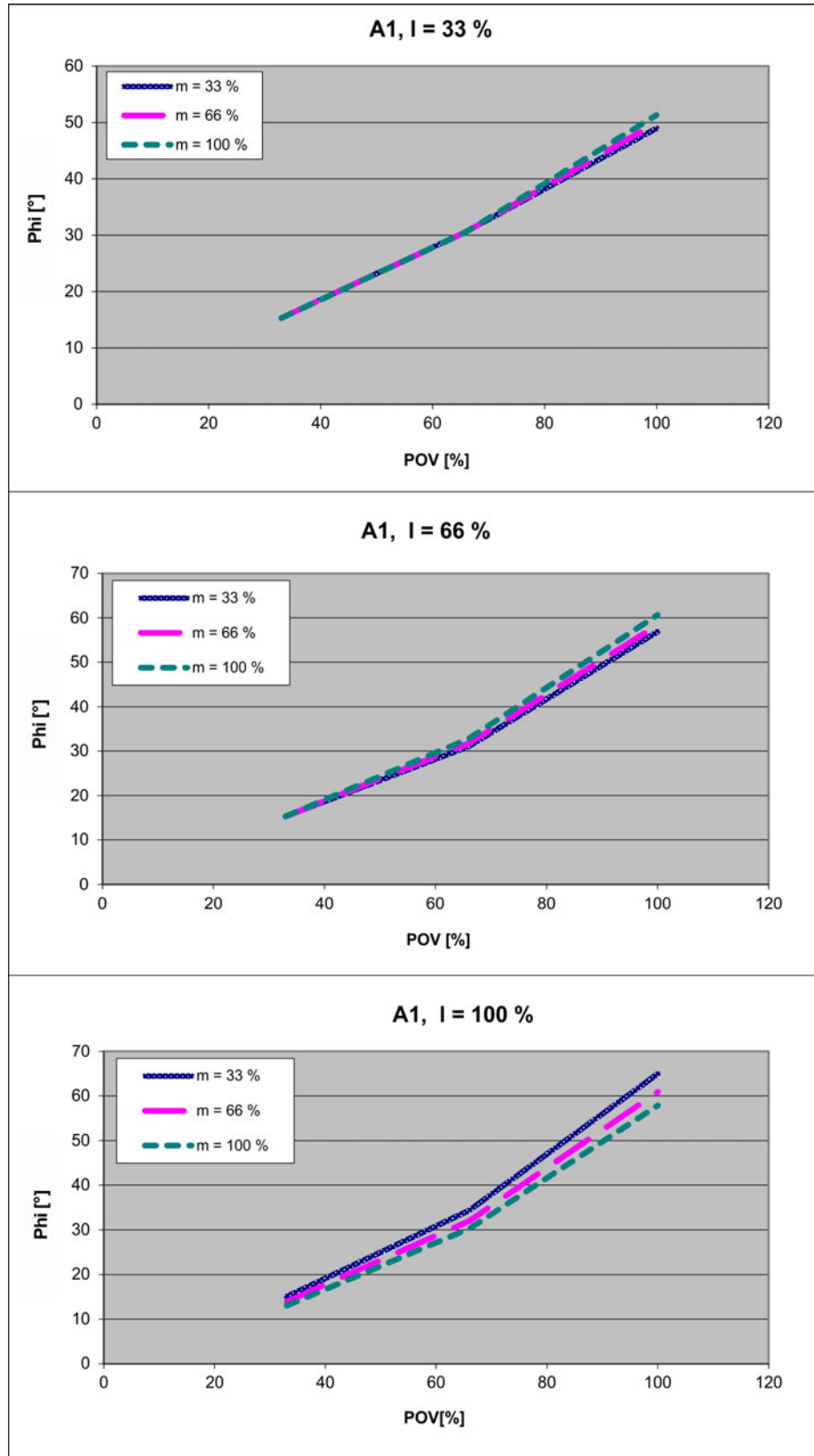


Fig. 4-45: Stopping distances for STOP 1, axis 1

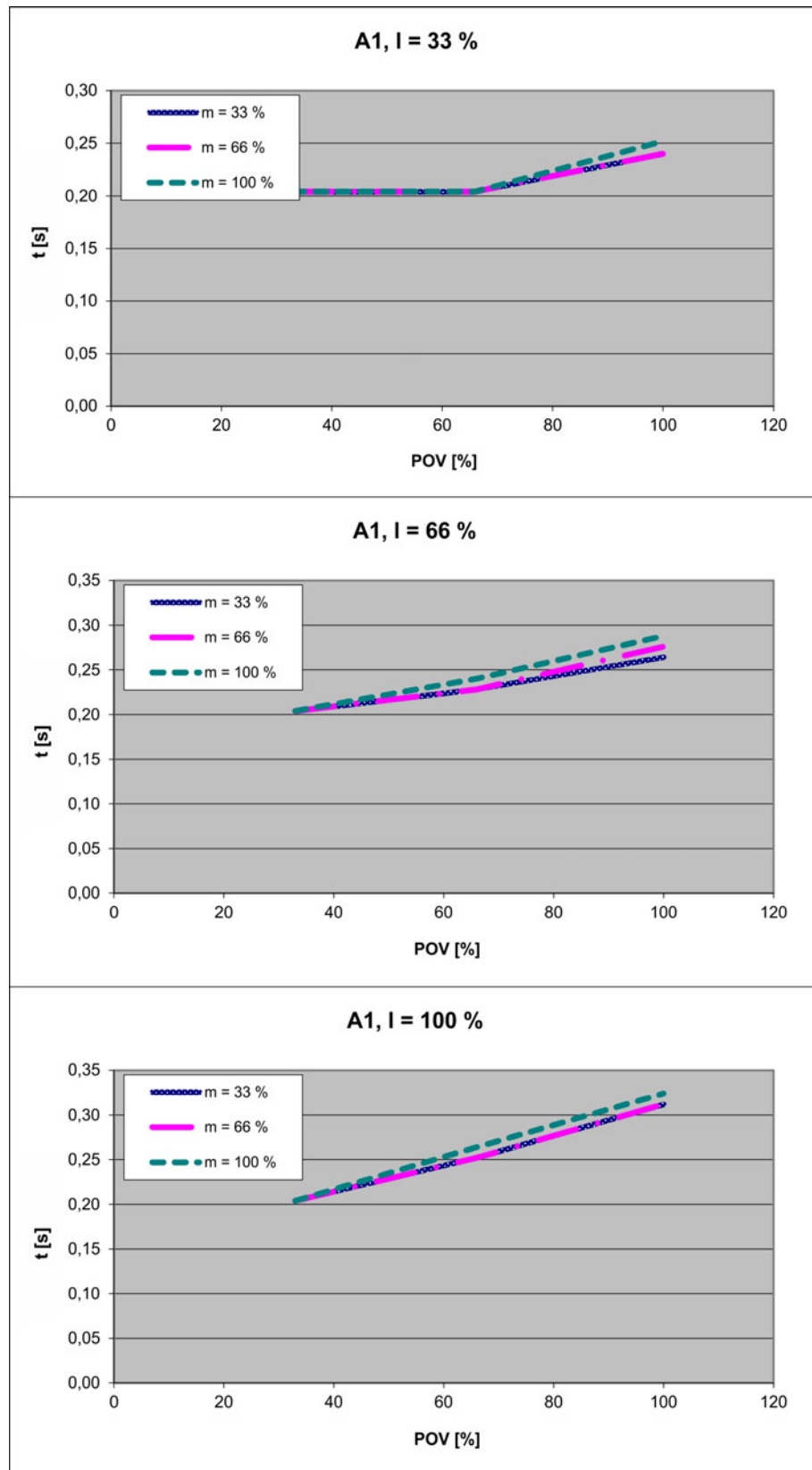


Fig. 4-46: Stopping times for STOP 1, axis 1

4.10.6.3 Stopping distances and stopping times for STOP 1, axis 2

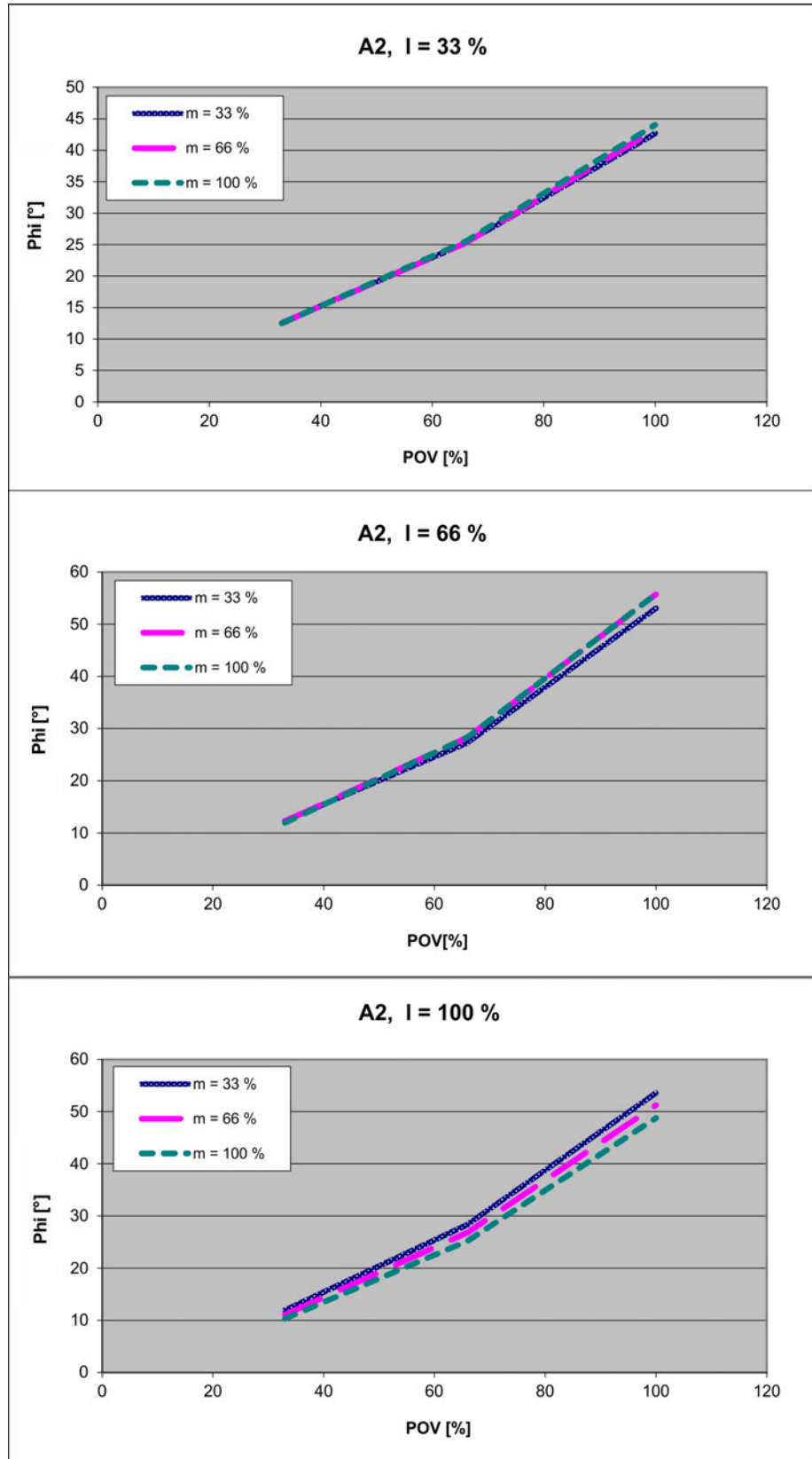


Fig. 4-47: Stopping distances for STOP 1, axis 2

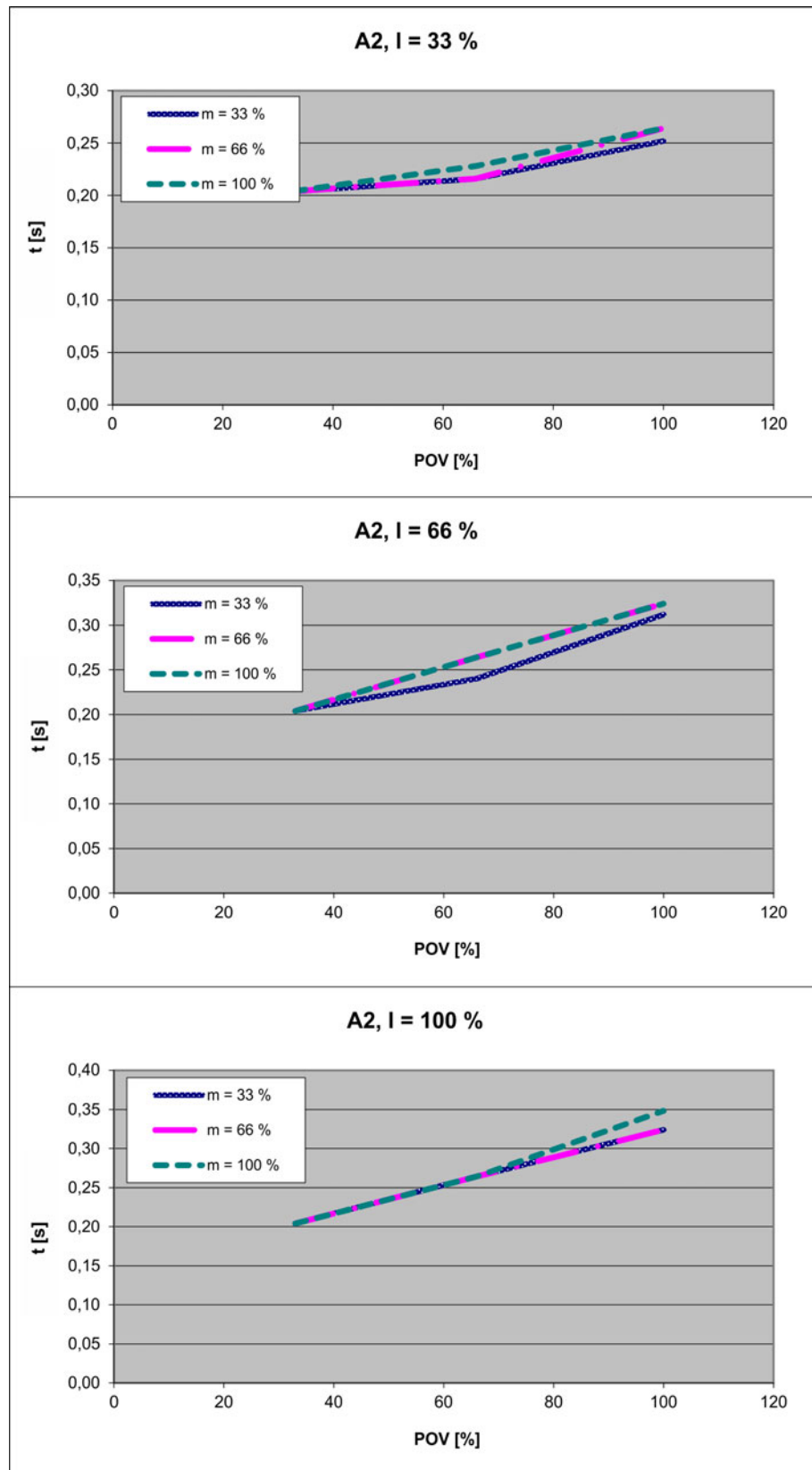


Fig. 4-48: Stopping times for STOP 1, axis 2

4.10.6.4 Stopping distances and stopping times for STOP 1, axis 3

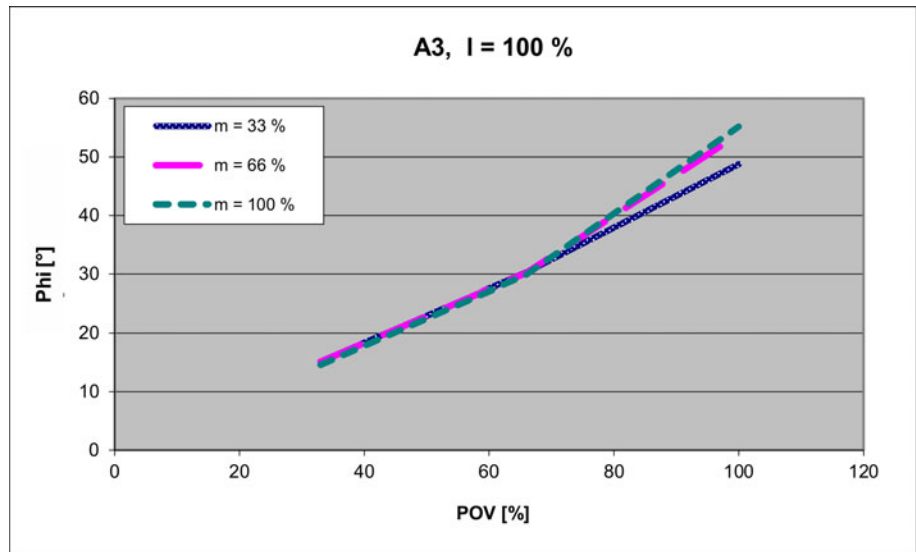


Fig. 4-49: Stopping distances for STOP 1, axis 3

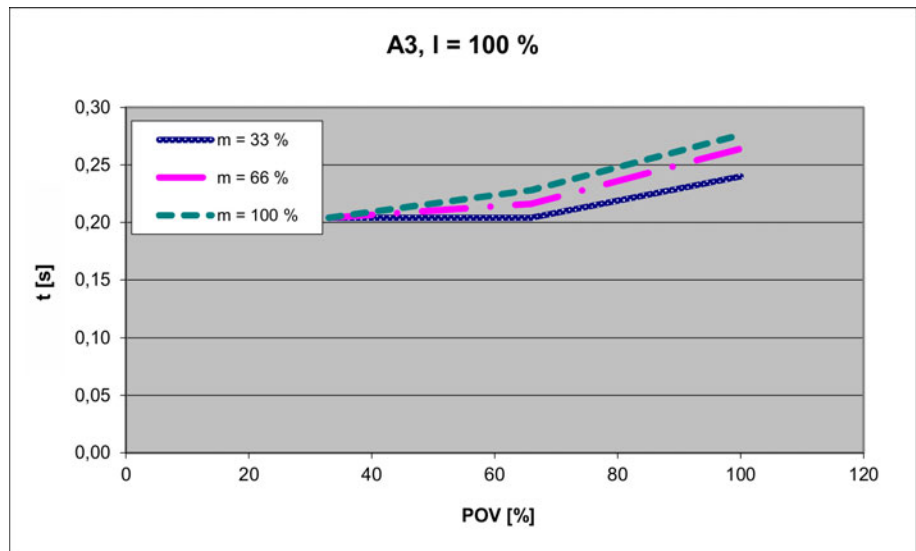



Fig. 4-50: Stopping times for STOP 1, axis 3

5 Safety

5.1 General



- This “Safety” chapter refers to a mechanical component of an industrial robot.
- If the mechanical component is used together with a KUKA robot controller, the “Safety” chapter of the operating instructions or assembly instructions of the robot controller must be used!

This contains all the information provided in this “Safety” chapter. It also contains additional safety information relating to the robot controller which must be observed.

- Where this “Safety” chapter uses the term “industrial robot”, this also refers to the individual mechanical component if applicable.

5.1.1 Liability

The device described in this document is either an industrial robot or a component thereof.

Components of the industrial robot:

- Manipulator
- Robot controller
- Teach pendant
- Connecting cables
- External axes (optional)
e.g. linear unit, turn-tilt table, positioner
- Software
- Options, accessories

The industrial robot is built using state-of-the-art technology and in accordance with the recognized safety rules. Nevertheless, misuse of the industrial robot may constitute a risk to life and limb or cause damage to the industrial robot and to other material property.

The industrial robot may only be used in perfect technical condition in accordance with its designated use and only by safety-conscious persons who are fully aware of the risks involved in its operation. Use of the industrial robot is subject to compliance with this document and with the declaration of incorporation supplied together with the industrial robot. Any functional disorders affecting safety must be rectified immediately.

Safety information

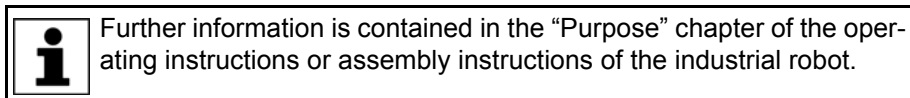
Safety information cannot be held against KUKA Roboter GmbH. Even if all safety instructions are followed, this is not a guarantee that the industrial robot will not cause personal injuries or material damage.

No modifications may be carried out to the industrial robot without the authorization of KUKA Roboter GmbH. Additional components (tools, software, etc.), not supplied by KUKA Roboter GmbH, may be integrated into the industrial robot. The user is liable for any damage these components may cause to the industrial robot or to other material property.

In addition to the Safety chapter, this document contains further safety instructions. These must also be observed.

5.1.2 Intended use of the industrial robot

The industrial robot is intended exclusively for the use designated in the “Purpose” chapter of the operating instructions or assembly instructions.



Using the industrial robot for any other or additional purpose is considered impermissible misuse. The manufacturer cannot be held liable for any damage resulting from such use. The risk lies entirely with the user.

Operating the industrial robot and its options within the limits of its intended use also involves observance of the operating and assembly instructions for the individual components, with particular reference to the maintenance specifications.

Misuse

Any use or application deviating from the intended use is deemed to be impermissible misuse. This includes e.g.:

- Transportation of persons and animals
- Use as a climbing aid
- Operation outside the permissible operating parameters
- Use in potentially explosive environments
- Operation without additional safeguards
- Outdoor operation
- Underground operation

5.1.3 EC declaration of conformity and declaration of incorporation

This industrial robot constitutes partly completed machinery as defined by the EC Machinery Directive. The industrial robot may only be put into operation if the following preconditions are met:

- The industrial robot is integrated into a complete system.
 - Or: The industrial robot, together with other machinery, constitutes a complete system.
 - Or: All safety functions and safeguards required for operation in the complete machine as defined by the EC Machinery Directive have been added to the industrial robot.
- The complete system complies with the EC Machinery Directive. This has been confirmed by means of an assessment of conformity.

Declaration of conformity

The system integrator must issue a declaration of conformity for the complete system in accordance with the Machinery Directive. The declaration of conformity forms the basis for the CE mark for the system. The industrial robot must be operated in accordance with the applicable national laws, regulations and standards.

The robot controller is CE certified under the EMC Directive and the Low Voltage Directive.

Declaration of incorporation

The industrial robot as partly completed machinery is supplied with a declaration of incorporation in accordance with Annex II B of the EC Machinery Directive 2006/42/EC. The assembly instructions and a list of essential requirements complied with in accordance with Annex I are integral parts of this declaration of incorporation.

The declaration of incorporation declares that the start-up of the partly completed machinery remains impermissible until the partly completed machinery

has been incorporated into machinery, or has been assembled with other parts to form machinery, and this machinery complies with the terms of the EC Machinery Directive, and the EC declaration of conformity is present in accordance with Annex II A.

The declaration of incorporation, together with its annexes, remains with the system integrator as an integral part of the technical documentation of the complete machinery.

5.1.4 Terms used

Term	Description
Axis range	Range of each axis, in degrees or millimeters, within which it may move. The axis range must be defined for each axis.
Stopping distance	Stopping distance = reaction distance + braking distance The stopping distance is part of the danger zone.
Workspace	The manipulator is allowed to move within its workspace. The workspace is derived from the individual axis ranges.
Operator (User)	The user of the industrial robot can be the management, employer or delegated person responsible for use of the industrial robot.
Danger zone	The danger zone consists of the workspace and the stopping distances.
Service life	The service life of a safety-relevant component begins at the time of delivery of the component to the customer. The service life is not affected by whether the component is used in a robot controller or elsewhere or not, as safety-relevant components are also subject to ageing during storage.
KCP	The KCP (KUKA Control Panel) teach pendant has all the operator control and display functions required for operating and programming the industrial robot. The KCP variant for the KR C4 is called KUKA smartPAD. The general term "KCP", however, is generally used in this documentation.
KUKA smartPAD	See KCP
Manipulator	The robot arm and the associated electrical installations
Safety zone	The safety zone is situated outside the danger zone.
Stop category 0	The drives are deactivated immediately and the brakes are applied. The manipulator and any external axes (optional) perform path-oriented braking. Note: This stop category is called STOP 0 in this document.
Stop category 1	The manipulator and any external axes (optional) perform path-maintaining braking. The drives are deactivated after 1 s and the brakes are applied. Note: This stop category is called STOP 1 in this document.
Stop category 2	The drives are not deactivated and the brakes are not applied. The manipulator and any external axes (optional) are braked with a normal braking ramp. Note: This stop category is called STOP 2 in this document.
System integrator (plant integrator)	System integrators are people who safely integrate the industrial robot into a complete system and commission it.
T1	Test mode, Manual Reduced Velocity (≤ 250 mm/s)
T2	Test mode, Manual High Velocity (> 250 mm/s permissible)
External axis	Motion axis which is not part of the manipulator but which is controlled using the robot controller, e.g. KUKA linear unit, turn-tilt table, Posiflex.

5.2 Personnel

The following persons or groups of persons are defined for the industrial robot:

- User
- Personnel



All persons working with the industrial robot must have read and understood the industrial robot documentation, including the safety chapter.

User

The user must observe the labor laws and regulations. This includes e.g.:

- The user must comply with his monitoring obligations.
- The user must carry out instructions at defined intervals.

Personnel

Personnel must be instructed, before any work is commenced, in the type of work involved and what exactly it entails as well as any hazards which may exist. Instruction must be carried out regularly. Instruction is also required after particular incidents or technical modifications.

Personnel includes:

- System integrator
- Operators, subdivided into:
 - Start-up, maintenance and service personnel
 - Operating personnel
 - Cleaning personnel



Installation, exchange, adjustment, operation, maintenance and repair must be performed only as specified in the operating or assembly instructions for the relevant component of the industrial robot and only by personnel specially trained for this purpose.

System integrator

The industrial robot is safely integrated into a complete system by the system integrator.

The system integrator is responsible for the following tasks:

- Installing the industrial robot
- Connecting the industrial robot
- Performing risk assessment
- Implementing the required safety functions and safeguards
- Issuing the declaration of conformity
- Attaching the CE mark
- Creating the operating instructions for the complete system

Operator

The operator must meet the following preconditions:

- The operator must be trained for the work to be carried out.
- Work on the industrial robot must only be carried out by qualified personnel. These are people who, due to their specialist training, knowledge and experience, and their familiarization with the relevant standards, are able to assess the work to be carried out and detect any potential hazards.

Example

The tasks can be distributed as shown in the following table.

Tasks	Operator	Programmer	System integrator
Switch robot controller on/off	x	x	x
Start program	x	x	x
Select program	x	x	x
Select operating mode	x	x	x
Calibration (tool, base)		x	x
Master the manipulator		x	x
Configuration		x	x
Programming		x	x
Start-up			x
Maintenance			x
Repair			x
Shutting down			x
Transportation			x



Work on the electrical and mechanical equipment of the industrial robot may only be carried out by specially trained personnel.

5.3 Workspace, safety zone and danger zone

Workspaces are to be restricted to the necessary minimum size. A workspace must be safeguarded using appropriate safeguards.

The safeguards (e.g. safety gate) must be situated inside the safety zone. In the case of a stop, the manipulator and external axes (optional) are braked and come to a stop within the danger zone.

The danger zone consists of the workspace and the stopping distances of the manipulator and external axes (optional). It must be safeguarded by means of physical safeguards to prevent danger to persons or the risk of material damage.

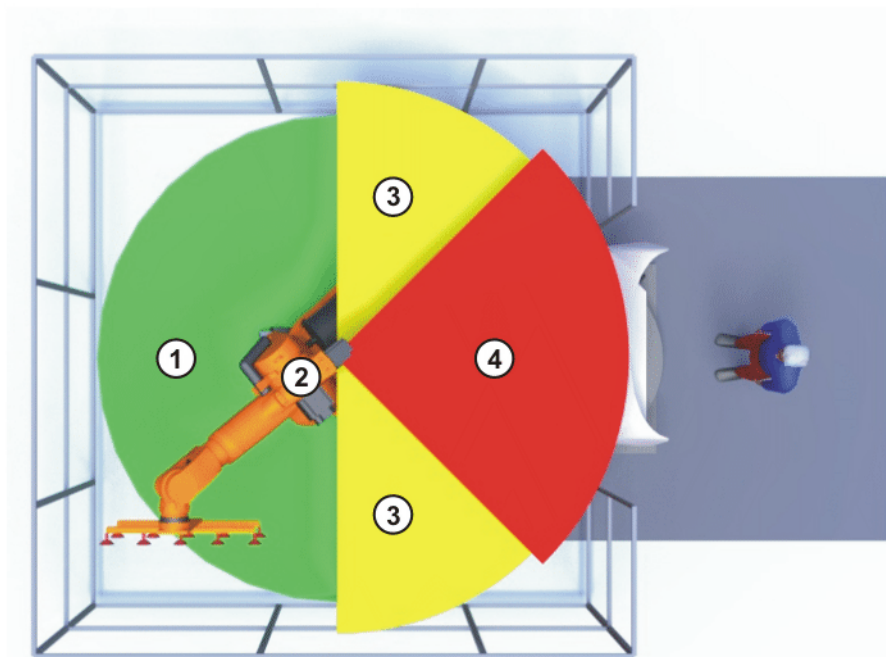


Fig. 5-1: Example of axis range A1

- | | | | |
|---|-------------|---|-------------------|
| 1 | Workspace | 3 | Stopping distance |
| 2 | Manipulator | 4 | Safety zone |

5.4 Overview of protective equipment

The protective equipment of the mechanical component may include:

- Mechanical end stops
- Mechanical axis range limitation (optional)
- Axis range monitoring (optional)
- Release device (optional)
- Labeling of danger areas

Not all equipment is relevant for every mechanical component.

5.4.1 Mechanical end stops

Depending on the robot variant, the axis ranges of the main and wrist axes of the manipulator are partially limited by mechanical end stops.

Additional mechanical end stops can be installed on the external axes.

NOTICE


If the manipulator or an external axis hits an obstruction or a mechanical end stop or axis range limitation, this can result in material damage to the industrial robot. The manipulator must be taken out of operation and KUKA Roboter GmbH must be consulted before it is put back into operation (>>> 10 "KUKA Service" Page 131).

5.4.2 Mechanical axis range limitation (optional)

Some manipulators can be fitted with mechanical axis range limitation in axes A1 to A3. The adjustable axis range limitation systems restrict the working range to the required minimum. This increases personal safety and protection of the system.


In the case of manipulators that are not designed to be fitted with mechanical axis range limitation, the workspace must be laid out in such a way that there is no danger to persons or material property, even in the absence of mechanical axis range limitation.

If this is not possible, the workspace must be limited by means of photoelectric barriers, photoelectric curtains or obstacles on the system side. There must be no shearing or crushing hazards at the loading and transfer areas.

 This option is not available for all robot models. Information on specific robot models can be obtained from KUKA Roboter GmbH.

5.4.3 Axis range monitoring (optional)

Some manipulators can be fitted with dual-channel axis range monitoring systems in main axes A1 to A3. The positioner axes may be fitted with additional axis range monitoring systems. The safety zone for an axis can be adjusted and monitored using an axis range monitoring system. This increases personal safety and protection of the system.


 This option is not available for all robot models. Information on specific robot models can be obtained from KUKA Roboter GmbH.


5.4.4 Options for moving the manipulator without the robot controller

Description The following options are available for moving the manipulator after an accident or malfunction:

- Release device (optional)
The release device can be used for the main axis drive motors and, depending on the robot variant, also for the wrist axis drive motors.
- Brake release device (option)
The brake release device is designed for robot variants whose motors are not freely accessible.
- Moving the wrist axes directly by hand
In the case of the low payload category, no release device for the wrist axes is available. A release device is not necessary, as the wrist axes can be moved directly by hand.


The options are only for use in exceptional circumstances and emergencies, e.g. for freeing people.

 Information on the availability of options for specific robot models can be obtained from KUKA Roboter GmbH.

 **CAUTION** The motors reach temperatures during operation which can cause burns to the skin. Contact must be avoided. Appropriate safety precautions must be taken, e.g. protective gloves must be worn.

Procedure


Moving the manipulator with the release device:


 **SAFETY INSTRUCTIONS** The following procedure must be followed exactly!

1. Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.

2. Remove the protective cap from the motor.
3. Push the release device onto the corresponding motor and move the axis in the desired direction.


The directions are indicated with arrows on the motors. It is necessary to overcome the resistance of the mechanical motor brake and any other loads acting on the axis.

 **WARNING** Moving an axis with the release device can damage the motor brake. This can result in personal injury and material damage. After using the release device, the motor must be exchanged.

 **WARNING** If a robot axis has been moved by the release device, all robot axes must be remastered. Serious injuries or damage to property may otherwise result.

Procedure

Moving the manipulator with the brake release device:

 **WARNING** Use of the brake release device may result in unexpected robot motions, especially sagging of the axes. During use of the brake release device, attention must be paid to motion of this kind in order to be able to prevent physical injuries or damage to property. Standing under moving axes is not permitted.

SAFETY INSTRUCTIONS The following procedure must be followed exactly!

1. Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.
2. Connect the brake release device to the base frame of the robot:
Unplug connector X30 from interface A1. Plug connector X20 of the brake release device into interface A1.
3. Select the brakes to be released (main axes, wrist axes) via the selection switch on the brake release device.
4. Press the button on the hand-held device.
The brakes of the main axes or wrist axes are released and the robot can be moved manually.



Further information about the brake release device can be found in the documentation for the brake release device.

5.4.5 Labeling on the industrial robot

All plates, labels, symbols and marks constitute safety-relevant parts of the industrial robot. They must not be modified or removed.

Labeling on the industrial robot consists of:

- Identification plates
- Warning labels
- Safety symbols
- Designation labels
- Cable markings
- Rating plates



Further information is contained in the technical data of the operating instructions or assembly instructions of the components of the industrial robot.

5.5 Safety measures

5.5.1 General safety measures

The industrial robot may only be used in perfect technical condition in accordance with its intended use and only by safety-conscious persons. Operator errors can result in personal injury and damage to property.

It is important to be prepared for possible movements of the industrial robot even after the robot controller has been switched off and locked. Incorrect installation (e.g. overload) or mechanical defects (e.g. brake defect) can cause the manipulator or external axes to sag. If work is to be carried out on a switched-off industrial robot, the manipulator and external axes must first be moved into a position in which they are unable to move on their own, whether the payload is mounted or not. If this is not possible, the manipulator and external axes must be secured by appropriate means.

⚠ DANGER In the absence of operational safety functions and safeguards, the industrial robot can cause personal injury or material damage. If safety functions or safeguards are dismantled or deactivated, the industrial robot may not be operated.

⚠ WARNING Standing underneath the robot arm can cause death or serious injuries. For this reason, standing underneath the robot arm is prohibited!

⚠ CAUTION The motors reach temperatures during operation which can cause burns to the skin. Contact must be avoided. Appropriate safety precautions must be taken, e.g. protective gloves must be worn.

KCP

The user must ensure that the industrial robot is only operated with the KCP by authorized persons.

If more than one KCP is used in the overall system, it must be ensured that each KCP is unambiguously assigned to the corresponding industrial robot. They must not be interchanged.

⚠ WARNING The operator must ensure that decoupled KCPs are immediately removed from the system and stored out of sight and reach of personnel working on the industrial robot. This serves to prevent operational and non-operational EMERGENCY STOP devices from becoming interchanged. Failure to observe this precaution may result in death, severe injuries or considerable damage to property.

External keyboard, external mouse

An external keyboard and/or external mouse may only be used if the following conditions are met:

- Start-up or maintenance work is being carried out.
- The drives are switched off.
- There are no persons in the danger zone.

The KCP must not be used as long as an external keyboard and/or external mouse are connected.

The external keyboard and/or external mouse must be removed as soon as the start-up or maintenance work is completed or the KCP is connected.

Faults

The following tasks must be carried out in the case of faults in the industrial robot:

- Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.
- Indicate the fault by means of a label with a corresponding warning (tag-out).
- Keep a record of the faults.
- Eliminate the fault and carry out a function test.

Modifications

After modifications to the industrial robot, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.

New or modified programs must always be tested first in Manual Reduced Velocity mode (T1).

After modifications to the industrial robot, existing programs must always be tested first in Manual Reduced Velocity mode (T1). This applies to all components of the industrial robot and includes modifications to the software and configuration settings.

5.5.2 Transportation

Manipulator

The prescribed transport position of the manipulator must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the robot.

Robot controller

The prescribed transport position of the robot controller must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the robot controller.

Avoid vibrations and impacts during transportation in order to prevent damage to the robot controller.

External axis (optional)

The prescribed transport position of the external axis (e.g. KUKA linear unit, turn-tilt table, positioner) must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the external axis.

5.5.3 Start-up and recommissioning

Before starting up systems and devices for the first time, a check must be carried out to ensure that the systems and devices are complete and operational, that they can be operated safely and that any damage is detected.

The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.



The passwords for logging onto the KUKA System Software as “Expert” and “Administrator” must be changed before start-up and must only be communicated to authorized personnel.



DANGER The robot controller is preconfigured for the specific industrial robot. If cables are interchanged, the manipulator and the external axes (optional) may receive incorrect data and can thus cause personal injury or material damage. If a system consists of more than one manipulator, always connect the connecting cables to the manipulators and their corresponding robot controllers.



If additional components (e.g. cables), which are not part of the scope of supply of KUKA Roboter GmbH, are integrated into the industrial robot, the user is responsible for ensuring that these components do not adversely affect or disable safety functions.

NOTICE

If the internal cabinet temperature of the robot controller differs greatly from the ambient temperature, condensation can form, which may cause damage to the electrical components. Do not put the robot controller into operation until the internal temperature of the cabinet has adjusted to the ambient temperature.

Function test

The following tests must be carried out before start-up and recommissioning:

It must be ensured that:

- The industrial robot is correctly installed and fastened in accordance with the specifications in the documentation.
- There are no foreign bodies or loose parts on the industrial robot.
- All required safety equipment is correctly installed and operational.
- The power supply ratings of the industrial robot correspond to the local supply voltage and mains type.
- The ground conductor and the equipotential bonding cable are sufficiently rated and correctly connected.
- The connecting cables are correctly connected and the connectors are locked.

Machine data

It must be ensured that the rating plate on the robot controller has the same machine data as those entered in the declaration of incorporation. The machine data on the rating plate of the manipulator and the external axes (optional) must be entered during start-up.



WARNING The industrial robot must not be moved if incorrect machine data are loaded. Death, severe injuries or considerable damage to property may otherwise result. The correct machine data must be loaded.

5.5.4 Manual mode

Manual mode is the mode for setup work. Setup work is all the tasks that have to be carried out on the industrial robot to enable automatic operation. Setup work includes:

- Jog mode
- Teach
- Programming
- Program verification

The following must be taken into consideration in manual mode:

- If the drives are not required, they must be switched off to prevent the manipulator or the external axes (optional) from being moved unintentionally. New or modified programs must always be tested first in Manual Reduced Velocity mode (T1).
- The manipulator, tooling or external axes (optional) must never touch or project beyond the safety fence.
- Workpieces, tooling and other objects must not become jammed as a result of the industrial robot motion, nor must they lead to short-circuits or be liable to fall off.

- All setup work must be carried out, where possible, from outside the safeguarded area.

If the setup work has to be carried out inside the safeguarded area, the following must be taken into consideration:

In **Manual Reduced Velocity mode (T1)**:

- If it can be avoided, there must be no other persons inside the safeguarded area.

If it is necessary for there to be several persons inside the safeguarded area, the following must be observed:

- Each person must have an enabling device.
- All persons must have an unimpeded view of the industrial robot.
- Eye-contact between all persons must be possible at all times.
- The operator must be so positioned that he can see into the danger area and get out of harm's way.

In **Manual High Velocity mode (T2)**:

- This mode may only be used if the application requires a test at a velocity higher than Manual Reduced Velocity.
- Teaching and programming are not permissible in this operating mode.
- Before commencing the test, the operator must ensure that the enabling devices are operational.
- The operator must be positioned outside the danger zone.
- There must be no other persons inside the safeguarded area. It is the responsibility of the operator to ensure this.

5.5.5 Automatic mode

Automatic mode is only permissible in compliance with the following safety measures:

- All safety equipment and safeguards are present and operational.
- There are no persons in the system.
- The defined working procedures are adhered to.

If the manipulator or an external axis (optional) comes to a standstill for no apparent reason, the danger zone must not be entered until an EMERGENCY STOP has been triggered.

5.5.6 Maintenance and repair

After maintenance and repair work, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety functions must also be tested.

The purpose of maintenance and repair work is to ensure that the system is kept operational or, in the event of a fault, to return the system to an operational state. Repair work includes troubleshooting in addition to the actual repair itself.

The following safety measures must be carried out when working on the industrial robot:

- Carry out work outside the danger zone. If work inside the danger zone is necessary, the user must define additional safety measures to ensure the safe protection of personnel.

- Switch off the industrial robot and secure it (e.g. with a padlock) to prevent it from being switched on again. If it is necessary to carry out work with the robot controller switched on, the user must define additional safety measures to ensure the safe protection of personnel.
- If it is necessary to carry out work with the robot controller switched on, this may only be done in operating mode T1.
- Label the system with a sign indicating that work is in progress. This sign must remain in place, even during temporary interruptions to the work.
- The EMERGENCY STOP systems must remain active. If safety functions or safeguards are deactivated during maintenance or repair work, they must be reactivated immediately after the work is completed.

⚠ WARNING

Before work is commenced on live parts of the robot system, the main switch must be turned off and secured against being switched on again by unauthorized personnel. The incoming power cable must be deenergized. The robot controller and mains supply lead must then be checked to ensure that it is deenergized. If the KR C4 or VKR C4 robot controller is used: It is not sufficient, before commencing work on live parts, to execute an EMERGENCY STOP or a safety stop, or to switch off the drives, as this does not disconnect the robot system from the mains power supply in the case of the drives of the new generation. Parts remain energized. Death or severe injuries may result.

Faulty components must be replaced using new components with the same article numbers or equivalent components approved by KUKA Roboter GmbH for this purpose.

Cleaning and preventive maintenance work is to be carried out in accordance with the operating instructions.

Robot controller

Even when the robot controller is switched off, parts connected to peripheral devices may still carry voltage. The external power sources must therefore be switched off if work is to be carried out on the robot controller.

The ESD regulations must be adhered to when working on components in the robot controller.

Voltages in excess of 50 V (up to 600 V) can be present in various components for several minutes after the robot controller has been switched off! To prevent life-threatening injuries, no work may be carried out on the industrial robot in this time.

Water and dust must be prevented from entering the robot controller.

Counterbalancing system

Some robot variants are equipped with a hydropneumatic, spring or gas cylinder counterbalancing system.

The hydropneumatic and gas cylinder counterbalancing systems are pressure equipment and, as such, are subject to obligatory equipment monitoring. Depending on the robot variant, the counterbalancing systems correspond to category 0, II or III, fluid group 2, of the Pressure Equipment Directive.

The user must comply with the applicable national laws, regulations and standards pertaining to pressure equipment.

Inspection intervals in Germany in accordance with Industrial Safety Order, Sections 14 and 15. Inspection by the user before commissioning at the installation site.

The following safety measures must be carried out when working on the counterbalancing system:

- The manipulator assemblies supported by the counterbalancing systems must be secured.

- Work on the counterbalancing systems must only be carried out by qualified personnel.

Hazardous substances

The following safety measures must be carried out when handling hazardous substances:

- Avoid prolonged and repeated intensive contact with the skin.
- Avoid breathing in oil spray or vapors.
- Clean skin and apply skin cream.



To ensure safe use of our products, we recommend that our customers regularly request up-to-date safety data sheets from the manufacturers of hazardous substances.

5.5.7 Decommissioning, storage and disposal

The industrial robot must be decommissioned, stored and disposed of in accordance with the applicable national laws, regulations and standards.

5.6 Applied norms and regulations

Name	Definition	Edition
2006/42/EC	Machinery Directive: Directive 2006/42/EC of the European Parliament and of the Council of 17 May 2006 on machinery, and amending Directive 95/16/EC (recast)	2006
2004/108/EC	EMC Directive: Directive 2004/108/EC of the European Parliament and of the Council of 15 December 2004 on the approximation of the laws of the Member States relating to electromagnetic compatibility and repealing Directive 89/336/EEC	2004
97/23/EC	Pressure Equipment Directive: Directive 97/23/EC of the European Parliament and of the Council of 29 May 1997 on the approximation of the laws of the Member States concerning pressure equipment (Only applicable for robots with hydropneumatic counterbalancing system.)	1997
EN ISO 13850	Safety of machinery: Emergency stop - Principles for design	2008
EN ISO 13849-1	Safety of machinery: Safety-related parts of control systems - Part 1: General principles of design	2008
EN ISO 13849-2	Safety of machinery: Safety-related parts of control systems - Part 2: Validation	2008
EN ISO 12100	Safety of machinery: General principles of design, risk assessment and risk reduction	2010
EN ISO 10218-1	Industrial robots: Safety	2011

Name	Definition	Edition
EN 614-1	Safety of machinery: Ergonomic design principles - Part 1: Terms and general principles	2006
EN 61000-6-2	Electromagnetic compatibility (EMC): Part 6-2: Generic standards; Immunity for industrial environments	2005
EN 61000-6-4	Electromagnetic compatibility (EMC): Part 6-4: Generic standards; Emission standard for industrial environments	2007
EN 60204-1	Safety of machinery: Electrical equipment of machines - Part 1: General requirements	2006

6 Planning

6.1 Mounting base

Description The mounting base with centering is used when the robot is fastened to the floor, i.e. directly on a concrete foundation.

The mounting base consists of:

- Bedplate
- Chemical anchors (resin-bonded anchors) with Dynamic Set
- Fasteners

This mounting variant requires a level and smooth surface on a concrete foundation with adequate load bearing capacity. The concrete foundation must be able to accommodate the forces occurring during operation. The minimum dimensions must be observed.

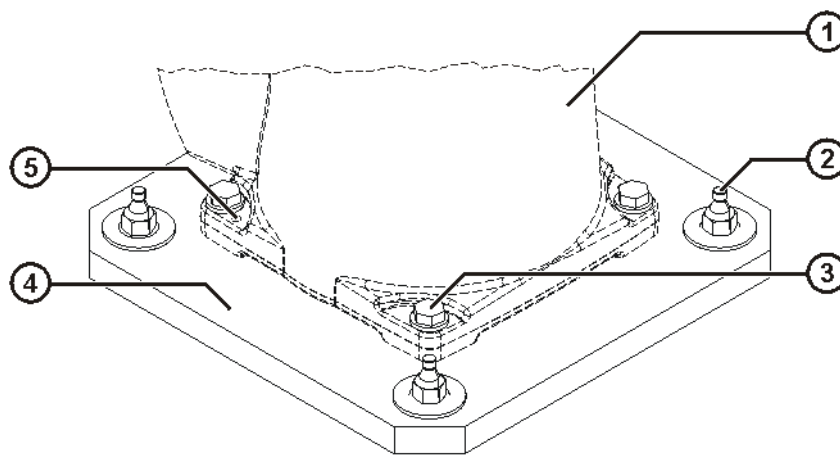


Fig. 6-1: Mounting base

- | | |
|---|------------|
| 1 Robot base frame | 4 Bedplate |
| 2 Chemical anchor (resin-bonded anchor) | 5 Pin |
| 3 Hexagon bolt | |

Grade of concrete for foundations When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. There must be no layers of insulation or screed between the bedplates and the concrete foundation. The quality of the concrete must meet the requirements of the following standard:

- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2008

Dimensioned drawing The following illustration (>>> Fig. 6-2) provides all the necessary information on the mounting base, together with the required foundation data.

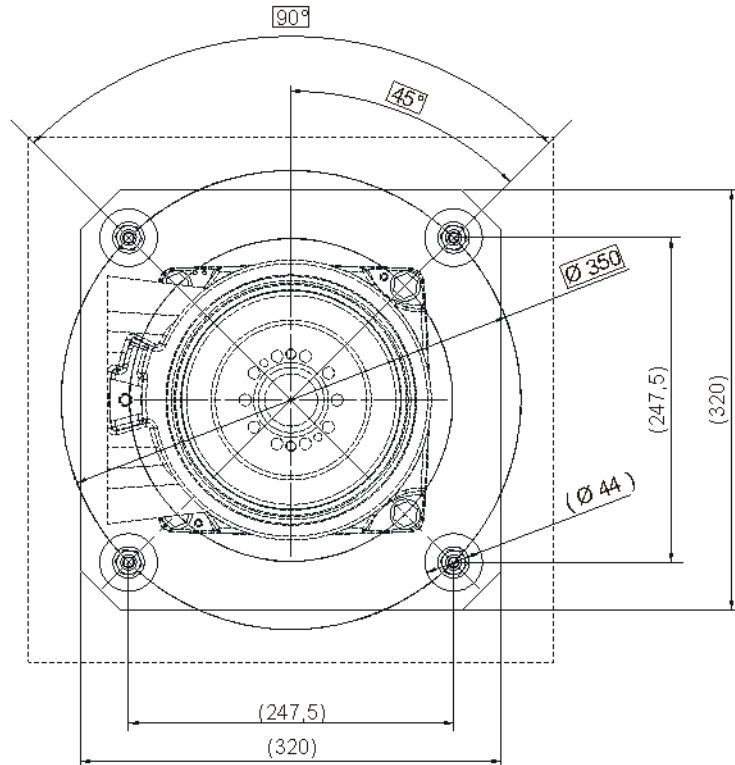


Fig. 6-2: Dimensioned drawing, mounting base

To ensure that the anchor forces are safely transmitted to the foundation, observe the dimensions for concrete foundations specified in the following illustration (>>> Fig. 6-3).

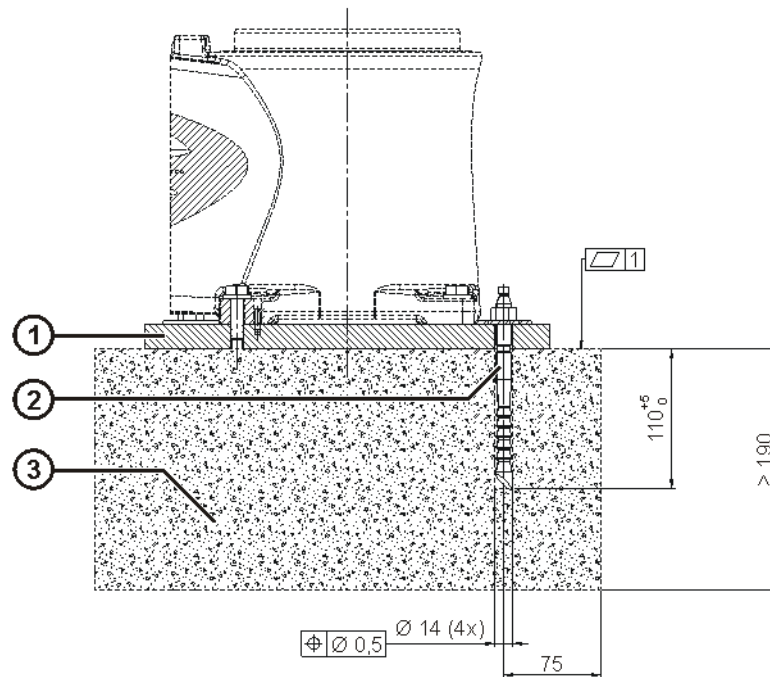


Fig. 6-3: Cross-section of foundations

1 Bedplate

- 2 Chemical anchors (resin-bonded anchors) with Dynamic Set
- 3 Concrete foundation

6.2 Machine frame mounting

Description

The machine frame mounting assembly is used when the robot is fastened on a steel structure, a booster frame (pedestal) or a KUKA linear unit. This assembly is also used if the robot is installed on the wall or ceiling. It must be ensured that the substructure is able to withstand safely the forces occurring during operation (foundation loads). The following diagram contains all the necessary information that must be observed when preparing the mounting surface (>>> Fig. 6-4).

The machine frame mounting assembly consists of:

- Pin
- Hexagon bolts with conical spring washers

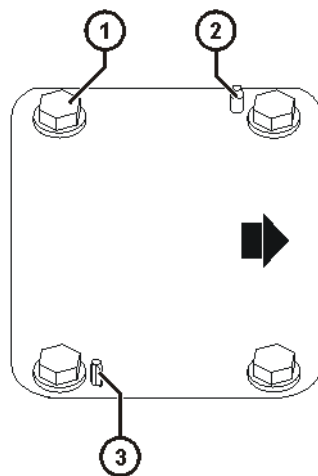


Fig. 6-4: Machine frame mounting

- 1 Hexagon bolt
- 2 Cylindrical pin
- 3 Flat-sided pin

Dimensioned drawing

The following illustration (>>> Fig. 6-5) provides all the necessary information on machine frame mounting, together with the required foundation data.

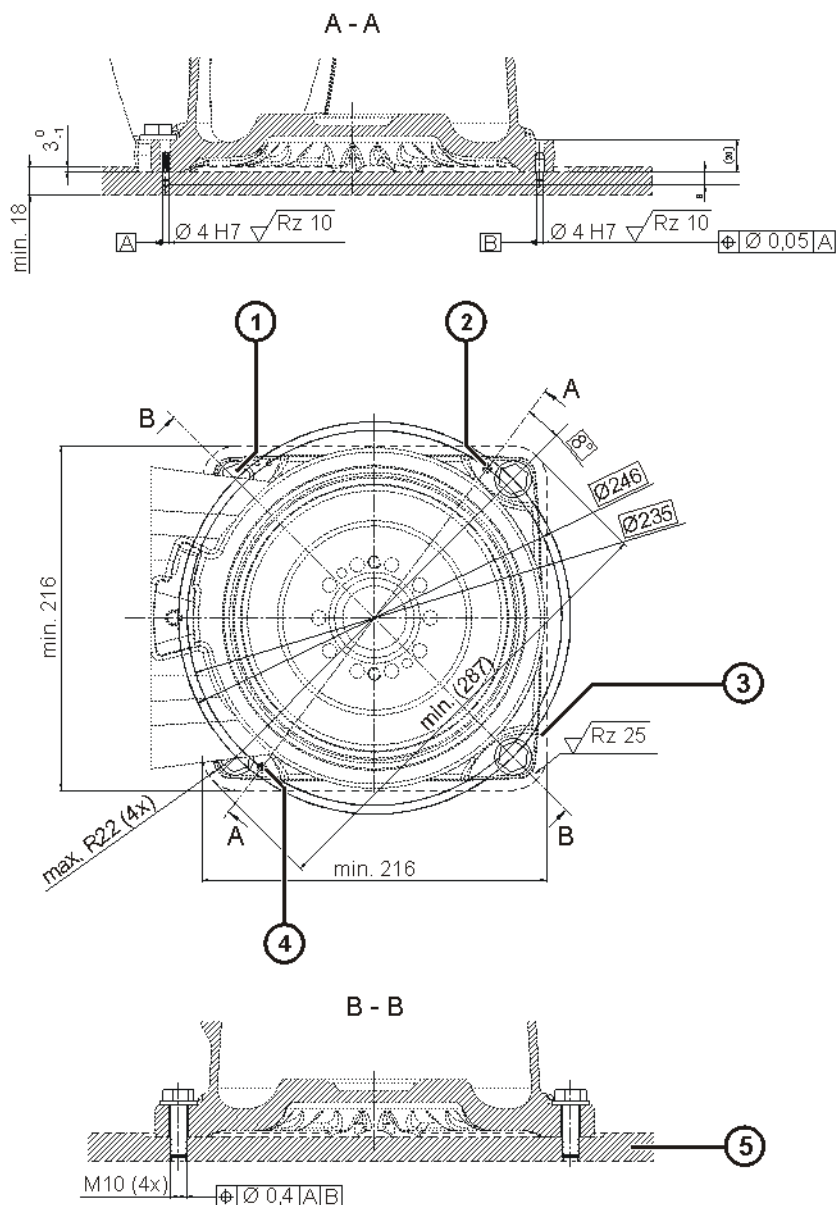


Fig. 6-5: Machine frame mounting, dimensioned drawing

- | | |
|---------------------|-------------------|
| 1 Hexagon bolt (4x) | 4 Flat-sided pin |
| 2 Cylindrical pin | 5 Steel structure |
| 3 Mounting surface | |

6.3 Connecting cables and interfaces

Connecting cables

The connecting cables comprise all the cables for transferring energy and signals between the robot and the robot controller. They are connected to the robot junction boxes with connectors. The set of connecting cables comprises:

- Motor cable
- Data cable
- CAT5 data cable (optional)
- Connecting cable, external axes A7 and A8 (optional)
- Ground conductor (optional)

Depending on the specification of the robot, various connecting cables are used. The standard cable length is 4 m. Cable lengths of 1 m, 7 m, 15 m and 25 m are available as an option. The maximum length of the connecting cables must not exceed 25 m. Thus if the robot is operated on a linear unit which has its own energy supply chain these cables must also be taken into account.



For the connecting cables, a ground conductor is always required to provide a low-resistance connection between the robot and the control cabinet in accordance with DIN EN 60204. The ground conductor is not part of the scope of supply and can be ordered as an option. The connection must be made by the customer. The tapped holes for connecting the ground conductor are located on the base frame of the robot.

The following points must be observed when planning and routing the connecting cables:

- The bending radius for fixed routing must not be less than 50 mm for motor cables and 30 mm for control cables.
- Protect cables against exposure to mechanical stress.
- Route the cables without mechanical stress – no tensile forces on the connectors
- Cables are only to be installed indoors.
- Observe permissible temperature range (fixed installation) of 263 K (-10 °C) to 343 K (+70 °C).
- Route the motor cables and the control cables separately in metal ducts; if necessary, additional measures must be taken to ensure electromagnetic compatibility (EMC).

Interface A1

Interface A1 is located at the rear of the base frame. The connections for the motor and data cables are shown in the following illustration.

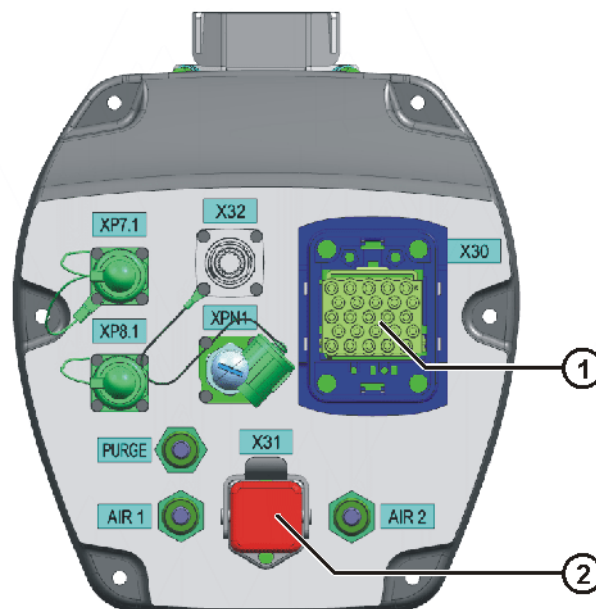


Fig. 6-6: Interface A1

- 1 Connection, motor cable X30
- 2 Connection, data cable, X31

6.4 Customer interfaces

Interface A1 Interface A1 is located at the rear of the base frame.

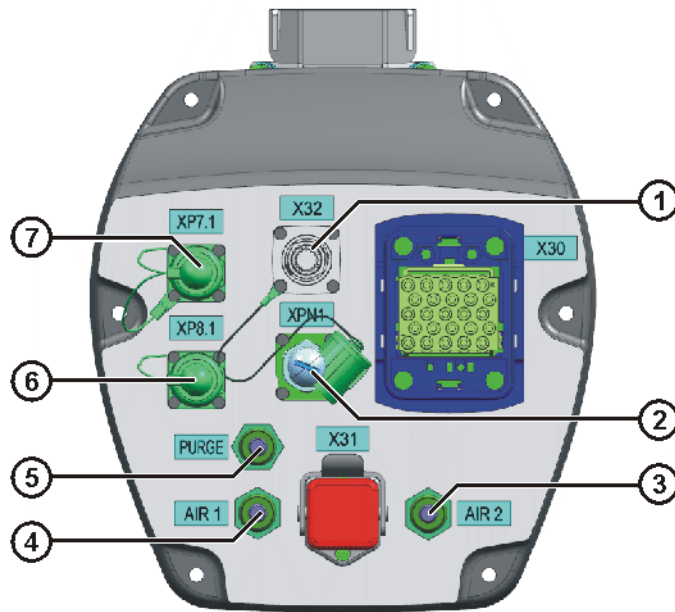


Fig. 6-7: Customer interface A1

- 1 MicroEMD connection X32
- 2 Connection for data cable CAT5 XPN1
- 3 Air line connection AIR2
- 4 Air line connection AIR1
- 5 Pressurization connection
- 6 Connection for external axis A8 (XP8.1)
- 7 Connection for external axis A7 (XP7.1)

Interface A4

Interface A4 is located on top of the in-line wrist.

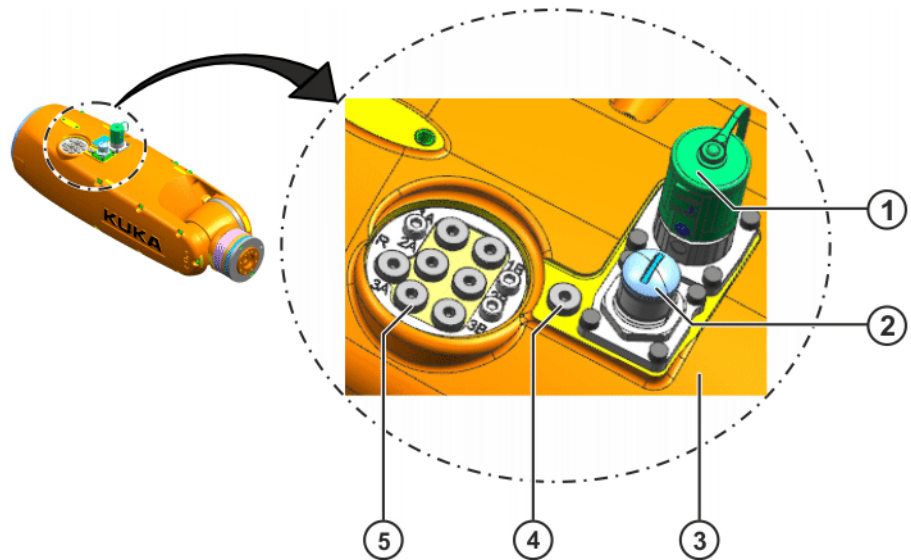


Fig. 6-8: Interface A4, example

- 1 Connection X41
- 2 Connection XPN41
- 3 In-line wrist
- 4 Air line AIR2
- 5 Air connections

The optional connector bypack is required for use of the air connections. This option contains a silencer and several plug-in couplings (>>> Fig. 6-9).

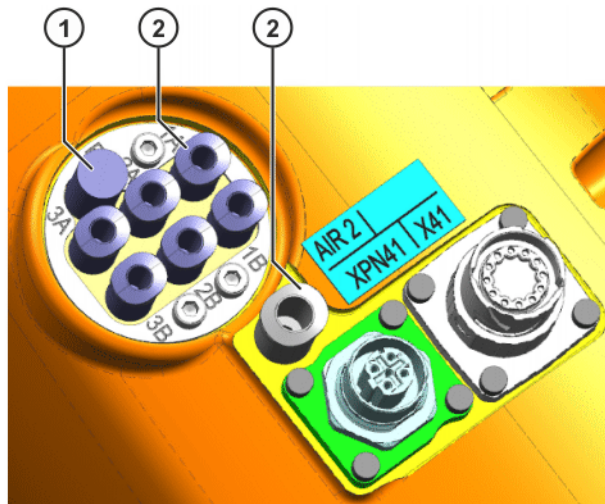


Fig. 6-9: Connector bypack option

1 Silencer

2 Push-in fitting

The robot has three bistable 4/2-way solenoid valves integrated into the in-line wrist. The valve unit is activated via the internal energy supply system:

Designation	Limit values
Valve type	4/2-way solenoid valve
Max. pressure	7 bar
Switching frequency	10 Hz
Operating temperature	+5 °C to +45 °C (278 K to 318 K) condensation-free
Threaded union	M5
Media	Air, oil-free, dry, filtered in accordance with: ISO 8573.1-1, 1.2 to 16.2 Degree of filtration: max. 5 µm
Operating voltage	24 V DC
Current	25 mA

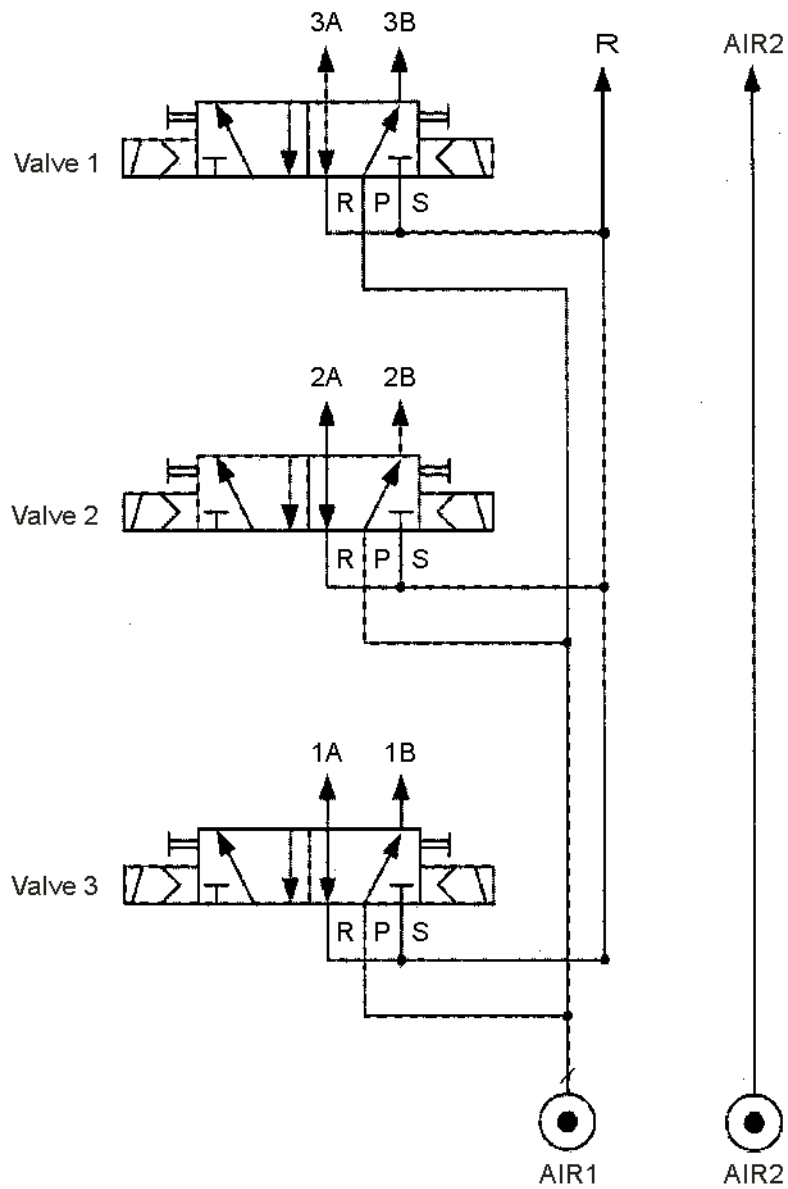


Fig. 6-10: Valve diagram

Valve activation

Designation	Values
Digital outputs (for valve activation)	6 (DO7 to DO12): <ul style="list-style-type: none"> ■ Valve 1: DO7/DO10 ■ Valve 2: DO8/DO11 ■ Valve 3: DO9/DO12 not short circuit proof
Rated voltage	24 V DC (-15%/+20%)
Output current	max. 25 mA

i The inputs and outputs are not preconfigured and must be configured in WorkVisual.
 Further information about mapping inputs and outputs can be found in the **WorkVisual** documentation.

Connection X41

Designation	Values
Digital outputs (for customer interface X41)	2 (DO13, DO14) short-circuit proof
Rated voltage	24 V DC (-15%/+20%)
Output current	Max. 0.5 A
Short-circuit current	Max. 2 A
Load type	Ohmic, inductive Lamp load
Digital inputs (for customer interface X41)	6 (DI1 to DI6)
Signal voltage "0"	-3 V ... +5 V EN 61131-2, type 3
Signal voltage "1"	15 V ... 30 V EN 61131-2, type 3
Input current	typically 3 mA EN 61131-2, type 3
Input filter	typically 0.3 ms
Power supply	24 V / 3 A

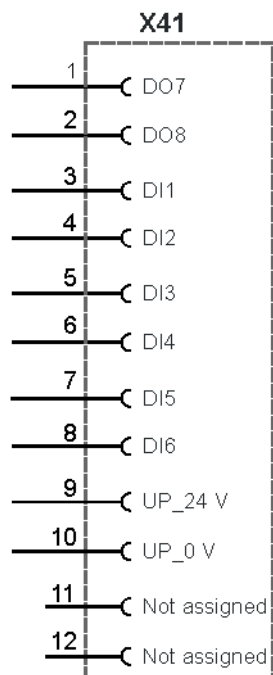


Fig. 6-11: Wiring diagram, connection X41

**Connection
XPN41**

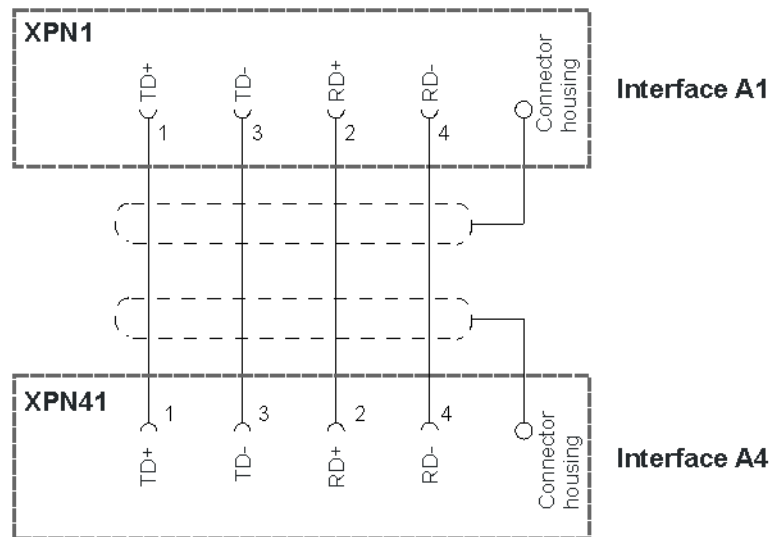


Fig. 6-12: Wiring diagram, connection XPN41

Connection AIR2

Customer-specific air connection with the following values:

Designation	Limit values
Max. pressure	7 bar
Vacuum	Atmospheric pressure minus 0.95 bar

7 Transportation

7.1 Transporting the manipulator

Description Move the robot into its transport position each time it is transported. It must be ensured that the robot is stable while it is being transported. The robot must remain in its transport position until it has been fastened to the foundation. Before the robot is lifted, it must be ensured that it is free from obstructions. Remove all transport safeguards, such as nails and screws, in advance. First remove any corrosion or glue on contact surfaces.

Transport position The robot must be in the transport position before it can be transported (>>> Fig. 7-1). The robot is in the transport position when the axes are in the following positions:

Axis	A1	A2	A3	A4	A5	A6
Angle	0°	-105°	+156°	0°	+120°	0°

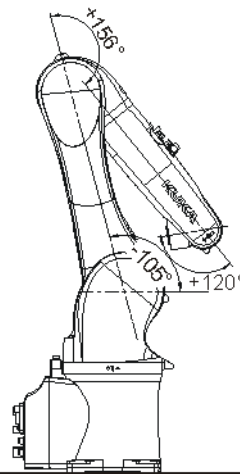


Fig. 7-1: Transport position

Transport dimensions The transport dimensions for the robot can be noted from the following figures. The position of the center of gravity and the weight vary according to the specific configuration. The specified dimensions refer to the robot without equipment.

The following transport dimensions (>>> Fig. 7-2) are valid for the robots:

- KR 6 R900 sixx
- KR 6 R900 sixx W
- KR 6 R900 sixx C
- KR 10 R900 sixx
- KR 10 R900 sixx W
- KR 10 R900 sixx C

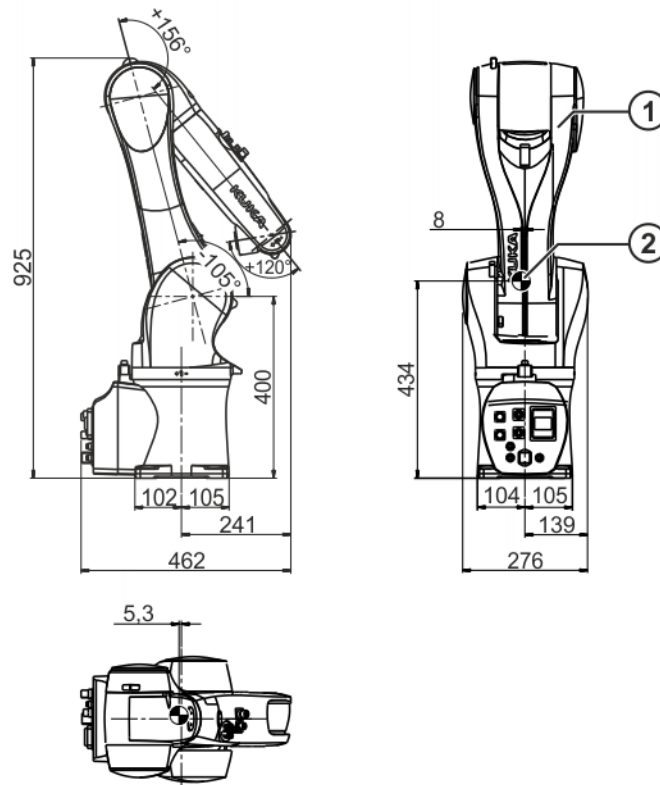


Fig. 7-2: Transport dimensions

1 Robot

2 Center of gravity

The following transport dimensions (>>> Fig. 7-3) are valid for the robots:

- KR 10 R1100 sixx
- KR 10 R1100 sixx W
- KR 10 R1100 sixx C

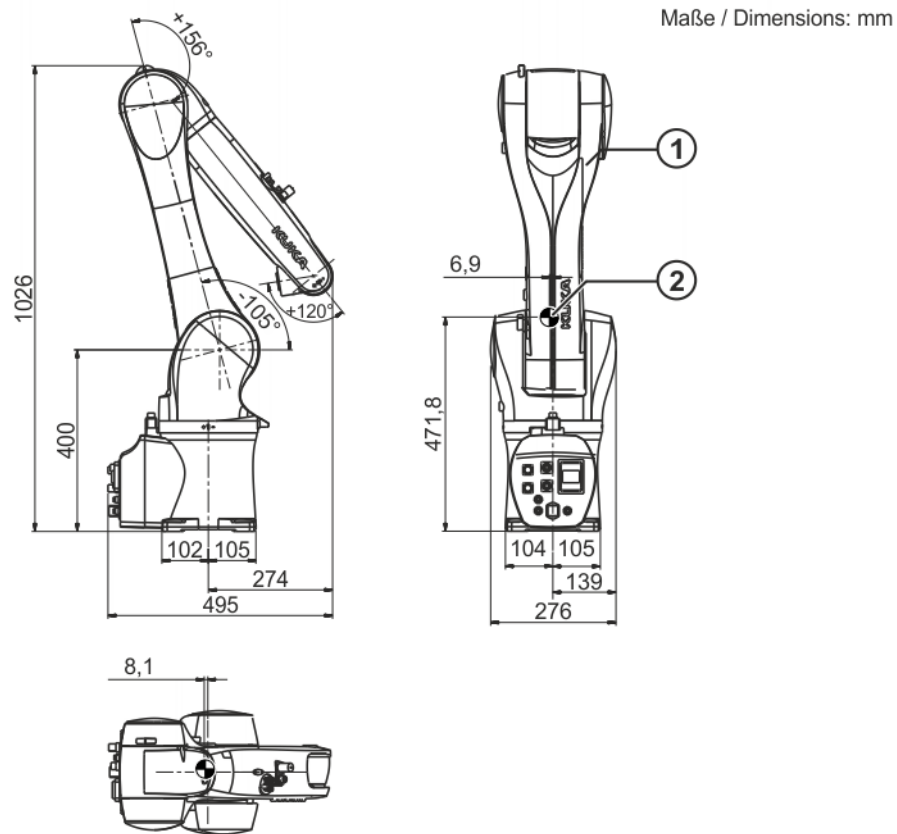


Fig. 7-3: Transport dimensions

1 Robot

2 Center of gravity

Transportation using lifting tackle

⚠ WARNING Use of unsuitable handling equipment may result in damage to the robot or injury to persons. Only use authorized handling equipment with a sufficient load-bearing capacity. Only transport the robot in the manner specified here.

The robot is transported using lifting tackle (>>> Fig. 7-4). The robot must be in the transport position. The loops of the lifting tackle are passed around the link arm and rotating column. All ropes must be long enough and must be routed in such a way that the robot is not damaged. Installed tools and pieces of equipment can cause undesirable shifts in the center of gravity.

⚠ WARNING The robot may tip during transportation. Risk of personal injury and damage to property.
If the robot is being transported using lifting tackle, special care must be exercised to prevent it from tipping. Additional safeguarding measures must be taken. It is forbidden to pick up the robot in any other way using a crane!

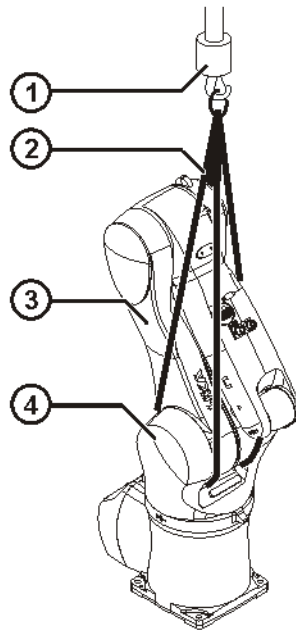


Fig. 7-4: Transportation using lifting tackle

- | | |
|------------------|-------------------|
| 1 Crane | 3 Link arm |
| 2 Lifting tackle | 4 Rotating column |

8 Start-up and recommissioning

8.1 Installing the mounting base

Description These instructions apply to the “mounting base with centering” variant. The robot is fastened to an appropriate concrete foundation using a bedplate and resin-bonded anchors.

If the surface of the concrete foundation is not sufficiently smooth and even, the differences must be evened out with a suitable leveling compound.

When using a Dynamic Set and resin-bonded anchors, use only components and resin capsules from the same manufacturer. No diamond tools or core drills may be used for drilling the anchor holes; for preference, drilling tools supplied by the anchor manufacturer are to be used. Observe also the manufacturer’s instructions for the use of resin-bonded anchors.

Precondition

- The concrete foundation must have the required dimensions and cross-section.
- The surface of the foundation must be smooth and even.
- The mounting base assembly must be complete.
- Have the leveling compound readily at hand.

Special tools The following special tools are required:

- Drill with a \varnothing 14 mm bit
- Setting tool approved by the anchor manufacturer

Procedure

1. Determine the position of the plate on the foundation in relation to the working envelope.
2. Set the bedplate down on the foundation in its installation position.

NOTICE If the bedplate is not fully seated on the concrete ceiling, fill the gap with leveling compound. To do this, lift the bedplate again and apply sufficient leveling compound to the underside. Then set the bedplate down again and align it, removing any excess leveling compound.

3. Check that the bedplate is horizontal. The maximum permissible deviation is 3°.
4. Allow the leveling compound to cure for about 3 hours. The curing time is longer at temperatures below 293 K (20 °C).
5. Drill 4 anchor holes through the holes of the bedplates into the foundation (>>> Fig. 8-1).
6. Clean the anchor holes.
7. Insert 4 resin capsules one after the other.
8. Clamp the setting tool with the chemical anchor rod in the drill and insert it into the anchor hole at max. 750 rpm⁻¹. The chemical anchor rod is set correctly if the resin is completely mixed and the anchor hole in the concrete is completely filled to the upper edge.

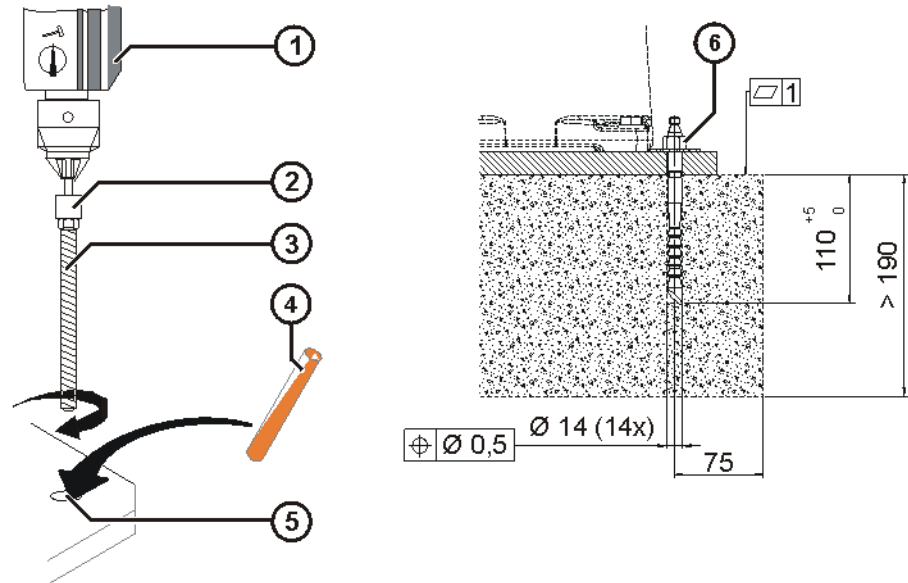


Fig. 8-1: Installation of resin-bonded anchors

- | | |
|-----------------------|--------------------------------|
| 1 Drill | 4 Resin capsule |
| 2 Setting tool | 5 Anchor hole |
| 3 Chemical anchor rod | 6 Hexagon nut with lock washer |
9. Repeat step 8 for all chemical anchors.
 10. Allow the resin to cure. See table, or as specified by manufacturer. These values are guide values.

Temperature	Time
≥293 K (+20 °C)	20 minutes
≥283 K (+10 °C)	30 minutes
≥273 K (0 °C)	1 hour

11. Fit 4 lock washers and 4 hexagon nuts one after the other. Tighten the hexagon nuts with a torque wrench in diagonally opposite sequence. Gradually increase the tightening torque to a value of 80 Nm.
 12. Retighten the hexagon nuts after 100 hours of operation.
 The mounting base is now ready for the robot to be installed.

8.2 Installing the machine frame mounting assembly

- Description** The machine frame mounting is used for installing robots on a steel structure prepared by the customer.
- Precondition**
- The mounting surface is prepared as shown in the diagram (>>> Fig. 6-5).
 - The substructure is checked for sufficient safety.
 - The machine frame mounting assembly is complete.
- Procedure**
1. Clean the mounting surface of the robot (>>> Fig. 8-2).
 2. Check the hole pattern.
 3. Insert 2 pins into the hole pattern.
 4. Provide 4 M10x35 hexagon bolts together with conical spring washers.

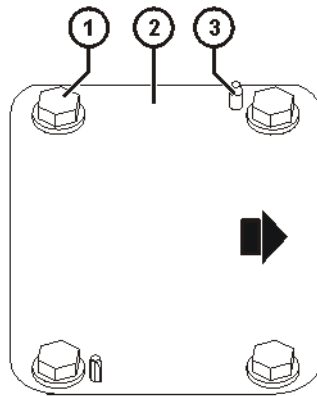


Fig. 8-2: Installation of the machine frame mounting assembly

- | | | | |
|---|-------------------|---|-----|
| 1 | Hexagon bolt (8x) | 3 | Pin |
| 2 | Mounting surface | | |

The mounting base is now ready for the robot to be installed.

8.3 Installing a floor-mounted robot

- Description** This description is valid for the installation of floor-mounted robots.
- 4 hexagon bolts with conical spring washers are used for fastening the robot to the bedplate or to a machine frame. A cylindrical pin and a flat-sided pin are provided to ensure correct positioning.
- The installation and start-up of the robot controller, the tools mounted and the applications are not described here.
- Precondition**
- The mounting base is installed.
 - The installation site is accessible with a crane.
 - Any tools or other system components which would hinder the work have been removed.
 - The robot is in the transport position.
 - The connecting cables and ground conductors are routed to the robot and installed.
- Procedure**
1. Check that the pins are undamaged and fitted securely (>>> Fig. 8-3).
 2. Bring the robot to the installation site with the crane.
 3. Carefully lower the robot vertically onto the mounting surface. Ensure that an entirely vertical position is maintained in order to prevent damage to the pins.
 4. Insert 4 M10x35 hexagon bolts together with conical spring washers.
 5. Tighten 4 M10x35 hexagon bolts with the torque wrench in diagonally opposite sequence. Gradually increase the tightening torque to 45 Nm.
 6. Remove the lifting tackle.
 7. Connect motor cable X30 and data cable X31.
 8. Connect the ground conductor between the robot controller and the robot to the ground conductor connection.
 9. Connect the ground conductor between the system component and the robot to the ground conductor connection.
 10. Check the equipotential bonding in accordance with VDE 0100 and EN 60204-1.



Further information is contained in the operating and assembly instructions of the robot controller.

11. Mount tooling, if present.
12. Retighten the 4 hexagon bolts with a torque wrench after 100 hours of operation.

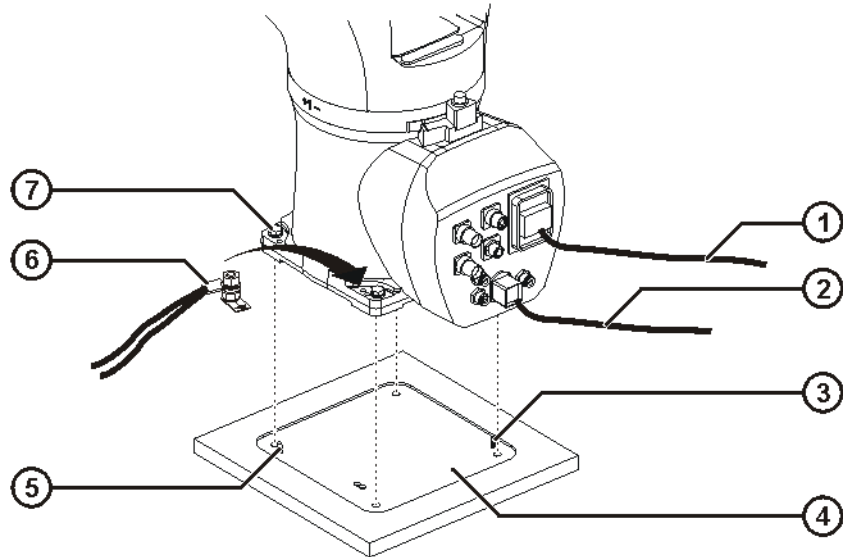


Fig. 8-3: Installing floor-mounted robots

- | | | | |
|---|------------------|---|------------------|
| 1 | Motor cable | 5 | Cylindrical pin |
| 2 | Data cable | 6 | Ground conductor |
| 3 | Flat-sided pin | 7 | Hexagon bolt |
| 4 | Mounting surface | | |

Put the robot system into operation in accordance with the “Start-up” chapter of the operating and programming instructions for the KUKA System Software (KSS) and the “Start-up” chapter of the operating instructions for the robot controller.

8.4 Installing a wall-mounted robot

Description

This description is valid for the installation of wall-mounted robots with the mounting variant “Machine frame mounting”. For installation on the wall, the robot must be fastened to the Load Lifting Attachment. The robot is fastened to the wall using the Load Lifting Attachment. The Load Lifting Attachment must then be removed.

The installation and start-up of the robot controller, the tools mounted and the applications are not described here.

Precondition

- The machine frame mounting assembly is installed.
- The installation site is accessible with a crane and fork lift truck.
- Any tools or other system components which would hinder the work have been removed.
- The robot is in the transport position.
- 2 instructed persons are required for performing this task.

Procedure

1. Bring the robot to the installation site with the crane and set it down.
2. Carefully push the Load Lifting Attachment onto the base frame of the robot from the front (>>> Fig. 8-4).

3. Remove the lifting tackle.
4. Fasten the robot to the front of the Load Lifting Attachment with 2 M12x30 Allen screws and washers; $M_A = 40 \text{ Nm}$.

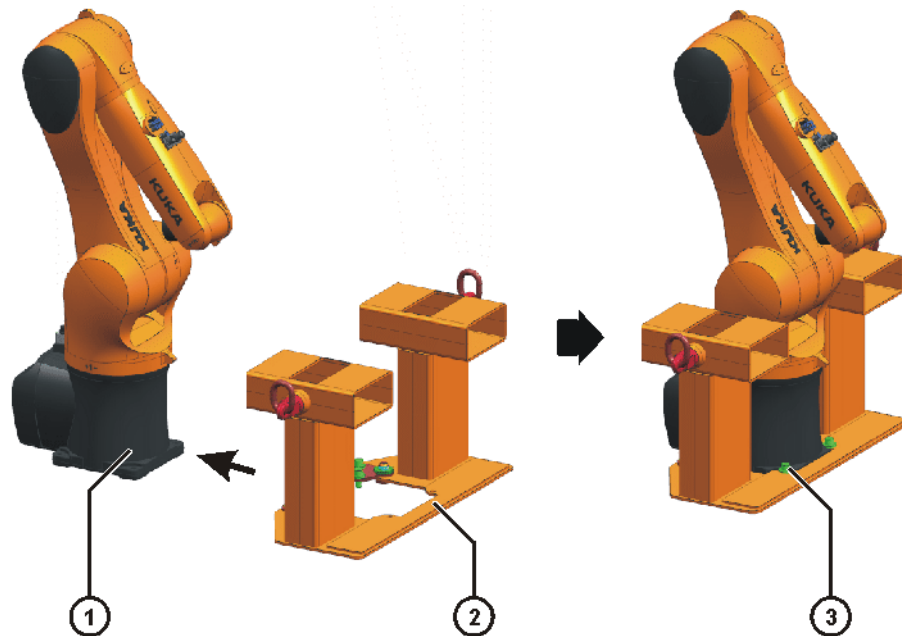


Fig. 8-4: Pushing on the Load Lifting Attachment and fastening it at the front

- 1 Base frame
- 2 Load Lifting Attachment
- 3 M12x30 Allen screw (front)

5. Position swivel holders on base frame (>>> Fig. 8-5).
6. Fasten the swivel holders to the rear of the base frame with 2 M12x30 Allen screws and washers; $M_A = 40 \text{ Nm}$.
7. Lock the swivel holders to the Load Lifting Attachment with 2 M12x30 Allen screws and washers.



Fig. 8-5: Positioning and fastening the swivel holders

- 1 Swivel holder
- 2 M12x30 Allen screw (rear)
- 3 M12x30 Allen screw (locking screw)

8. Attach lifting tackle to the 2 rotating swivel eyebolts on the Load Lifting Attachment and to the crane.
9. Person 1:
Slowly and carefully lift the robot with the crane.
Person 2:
Secure the robot against toppling during the lifting operation.

WARNING

Ensure that the robot does not topple during the lifting operation. Serious injuries and damage to property may otherwise result.

10. Slowly rotate the robot through 90°. The arm must point downward.
11. Lift the Load Lifting Attachment with a fork lift truck (>>> Fig. 8-6).
The fork lift truck must remain in the fork slots of the Load Lifting Attachment during installation in order to prevent slipping.

NOTICE

When picking up the Load Lifting Attachment with the fork lift truck, the width of the fork slots (140 mm) must be taken into consideration. Damage to property may otherwise result.

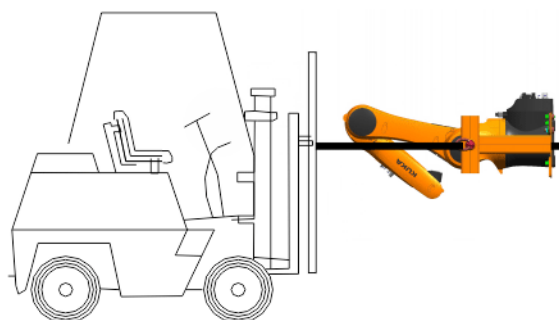


Fig. 8-6: Lifting the Load Lifting Attachment with a fork lift truck

12. Position the robot on the wall using the fork lift truck. Ensure that an entirely horizontal position is maintained in order to prevent damage to the pins.
13. Unscrew 2 M12x30 Allen screws (top Allen screws) and washers from the top of the base frame (>>> Fig. 8-7).
14. Unscrew 2 M12x30 Allen screws (locking screws) and washers from the Load Lifting Attachment.

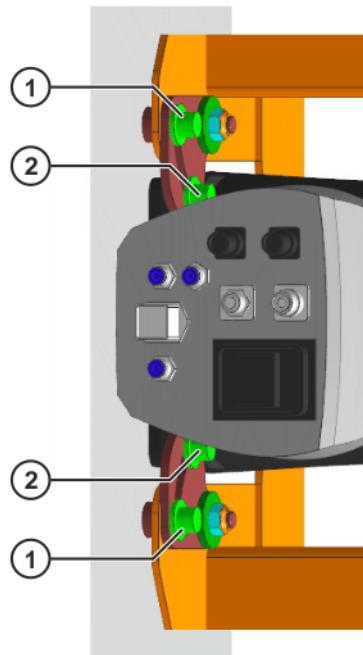


Fig. 8-7: Removing the top screws

- 1 M12x30 Allen screw (top)
- 2 M12x30 Allen screw (locking screw)

15. Rotate the swivel holders outwards (>>> Fig. 8-8).

16. Fasten the robot to the wall with 2 M10x35 hexagon bolts (top hexagon bolts) and washers at the top.

Tighten the hexagon bolts alternately with torque wrench. Gradually increase the tightening torque to 45 Nm.

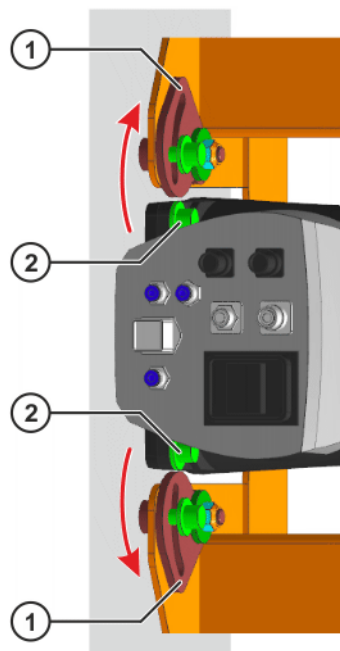


Fig. 8-8: Rotating the swivel holders outwards

- 1 Swivel holder
- 2 M10x35 hexagon bolt (top)

17. Unscrew 2 M12x30 Allen screws (bottom Allen screws) and washers from the bottom of the base frame.

18. Carefully separate the Load Lifting Attachment from the bottom of the base frame with the fork lift truck.
19. Fasten the robot to the wall with 2 M10x35 hexagon bolts and washers on the bottom of the base frame.
Tighten the hexagon bolts alternately with torque wrench. Gradually increase the tightening torque to 45 Nm.
20. Connect motor cable X30 and data cable X31 (>>> Fig. 8-9).
21. Connect the ground conductor between the robot controller and the robot to the ground conductor connection.

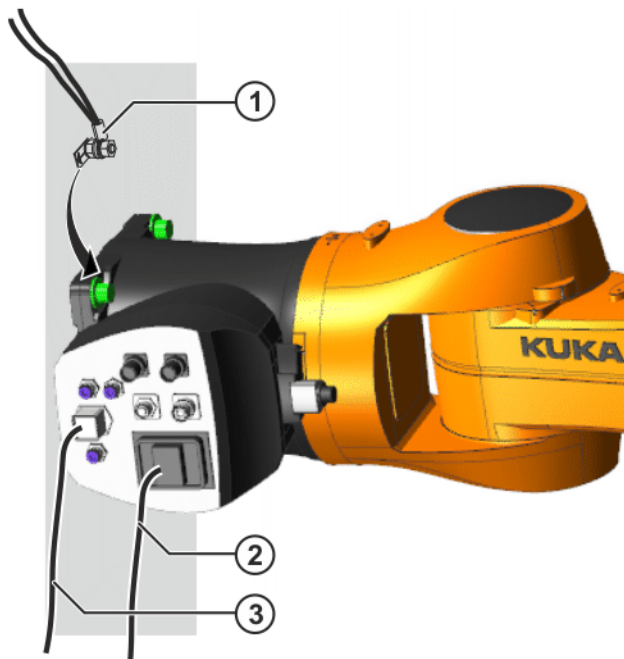


Fig. 8-9: Connecting the cables

- | | | | |
|---|------------------|---|------------|
| 1 | Ground conductor | 3 | Data cable |
| 2 | Motor cable | | |

22. Check the equipotential bonding in accordance with VDE 0100 and EN 60204-1.



Further information is contained in the operating and assembly instructions of the robot controller.

23. Connect the ground conductor between the system component and the robot to the ground conductor connection.
24. Mount tooling, if present.
25. Retighten the 4 hexagon bolts with a torque wrench after 100 hours of operation.

Put the robot system into operation in accordance with the "Start-up" chapter of the operating and programming instructions for the KUKA System Software (KSS) and the "Start-up" chapter of the operating instructions for the robot controller.

8.5 Installing a ceiling-mounted robot

Description

This description is valid for the installation of ceiling-mounted robots with the mounting variant "Machine frame mounting". For installation on the ceiling, the robot must be fastened to the Load Lifting Attachment. The robot is fastened

to the ceiling using the Load Lifting Attachment. The Load Lifting Attachment must then be removed.

The installation and start-up of the robot controller, the tools mounted and the applications are not described here.

Precondition

- The machine frame mounting assembly is installed.
- The installation site is accessible with a crane and fork lift truck.
- Any tools or other system components which would hinder the work have been removed.
- The robot is in the transport position.
- 2 instructed persons are required for performing this task.

Procedure

1. Bring the robot to the installation site with the crane and set it down.
2. Carefully push the Load Lifting Attachment onto the base frame of the robot from the front (>>> Fig. 8-10).
3. Remove the lifting tackle.
4. Fasten the robot to the front of the Load Lifting Attachment with 2 M12x30 Allen screws and washers; $M_A = 40 \text{ Nm}$.

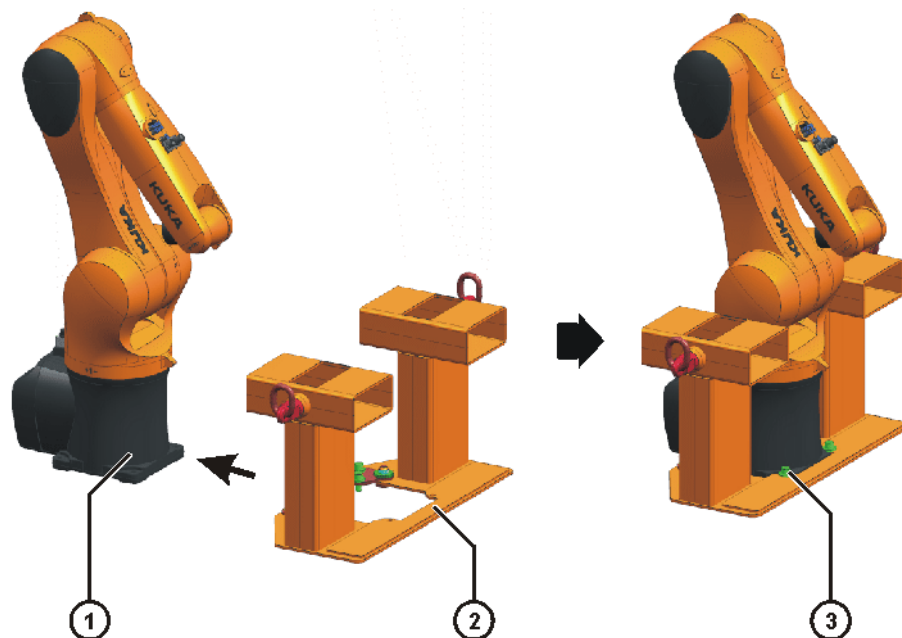


Fig. 8-10: Pushing on the Load Lifting Attachment and fastening it at the front

- 1 Base frame
 - 2 Load Lifting Attachment
 - 3 M12x30 Allen screw (front)
5. Position swivel holders on base frame (>>> Fig. 8-11).
 6. Fasten the swivel holders to the rear of the base frame with 2 M12x30 Allen screws and washers; $M_A = 40 \text{ Nm}$.
 7. Lock the swivel holders to the Load Lifting Attachment with 2 M12x30 Allen screws and washers.



Fig. 8-11: Positioning and fastening the swivel holders

- 1 Swivel holder
 - 2 M12x30 Allen screw (rear)
 - 3 M12x30 Allen screw (locking screw)
8. Attach lifting tackle to the 2 rotating swivel eyebolts on the Load Lifting Attachment and to the crane.
 9. Person 1:
Slowly and carefully lift the robot with the crane.
Person 2:
Secure the robot against toppling during the lifting operation.

WARNING Ensure that the robot does not topple during the lifting operation. Serious injuries and damage to property may otherwise result.

10. Slowly rotate the robot through 180° and lower it.
11. Lift the Load Lifting Attachment with a fork lift truck (>>> Fig. 8-12).
The fork lift truck must remain in the fork slots of the Load Lifting Attachment during installation in order to prevent slipping.

NOTICE When picking up the Load Lifting Attachment with the fork lift truck, the width of the fork slots (140 mm) must be taken into consideration. Damage to property may otherwise result.

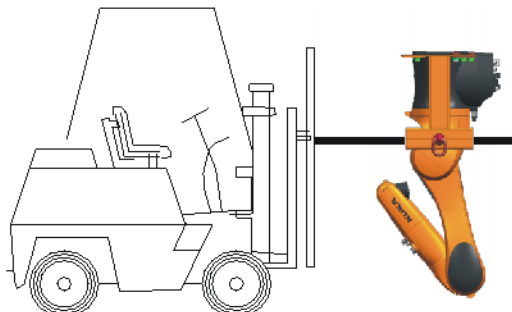


Fig. 8-12: Lifting the Load Lifting Attachment with a fork lift truck

12. Position the robot on the ceiling using the fork lift truck. Ensure that an entirely vertical position is maintained in order to prevent damage to the pins.
13. Unscrew 2 M12x30 Allen screws (rear Allen screws) and washers from the rear of the base frame (>>> Fig. 8-13).

14. Unscrew 2 M12x30 Allen screws (locking screws) and washers from the Load Lifting Attachment.

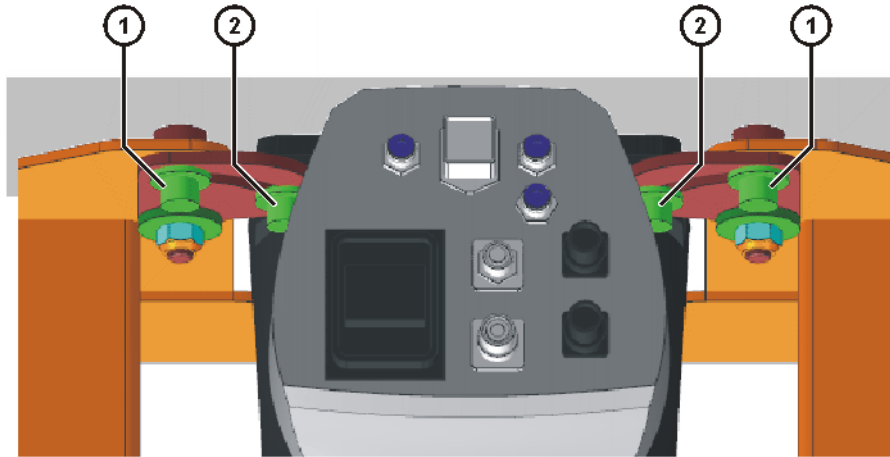


Fig. 8-13: Removing screws from the rear

- 1 M12x30 Allen screw (rear)
- 2 M12x30 Allen screw (locking screw)

15. Rotate the swivel holders outwards (>>> Fig. 8-14).
16. Fasten the robot to the ceiling with 2 M10x35 hexagon bolts (rear hexagon bolts) and washers at the rear.
- Tighten the hexagon bolts alternately with torque wrench. Gradually increase the tightening torque to 45 Nm.

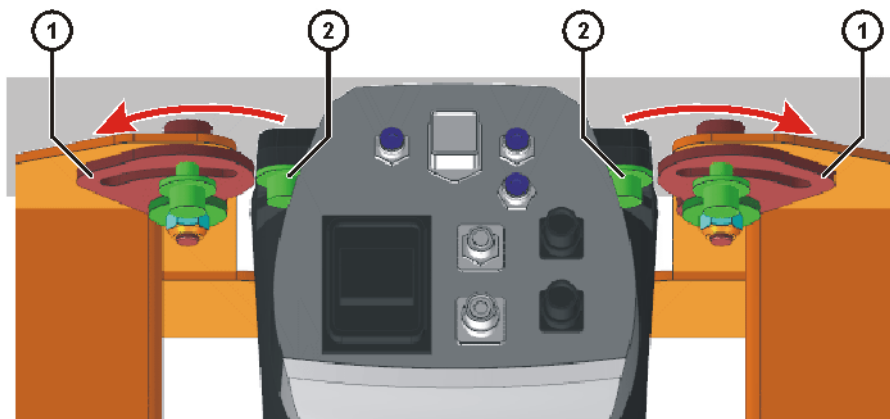


Fig. 8-14: Rotating the swivel holders outwards

- 1 Swivel holder
- 2 M10x35 hexagon bolt (rear)

17. Unscrew 2 M12x30 Allen screws (front Allen screws) and washers from the front of the base frame.
18. Carefully push the Load Lifting Attachment down from the back of the base frame with the fork lift truck.
19. Fasten the robot to the ceiling with 2 M10x35 hexagon bolts and washers at the front of the base frame.
- Tighten the hexagon bolts alternately with torque wrench. Gradually increase the tightening torque to 45 Nm.
20. Connect motor cable X30 and data cable X31 (>>> Fig. 8-15).
21. Connect the ground conductor between the robot controller and the robot to the ground conductor connection.



Fig. 8-15: Connecting the cables

- | | | | |
|---|------------------|---|------------|
| 1 | Ground conductor | 3 | Data cable |
| 2 | Motor cable | | |

22. Check the equipotential bonding in accordance with VDE 0100 and EN 60204-1.



Further information is contained in the operating and assembly instructions of the robot controller.

23. Connect the ground conductor between the system component and the robot to the ground conductor connection.
24. Mount tooling, if present.
25. Retighten the 4 hexagon bolts with a torque wrench after 100 hours of operation.

Put the robot system into operation in accordance with the “Start-up” chapter of the operating and programming instructions for the KUKA System Software (KSS) and the “Start-up” chapter of the operating instructions for the robot controller.

8.6 Description of the connecting cables

Configuration

The connecting cables are used to transfer power and signals between the robot controller and the robot.

The connecting cables comprise:

- Motor cable
- Data cable
- CAT5 data cable (optional)
- Connecting cable, external axes A7 and A8 (optional)
- Ground conductor (optional)

Interface

For connection of the connecting cables between the robot controller and the robot, the following connectors are available at the interfaces:

Cable designation	Connector designation robot controller - robot	Interface with robot
Motor cable	X20 - X30	Han Yellock 30
Data cable	X21 - X31	Han Q12
CAT5 data cable (can be ordered as an option)	X65/X66 - XPN1	M12 connector
Connecting cable, external axes A7 and A8 (can be ordered as an option)	XP7 - XP7.1 XP8 - XP8.1	Connector M17 in each case
Ground conductor, equipotential bonding (can be ordered as an option)		Ring cable lug M4

Only resolvers can be connected to the connections XP7.1 and XP8.1.



For the connecting cables, a ground conductor is always required to provide a low-resistance connection between the robot and the control cabinet in accordance with DIN EN 60204. The ground conductor is not part of the scope of supply and can be ordered as an option. The connection must be made by the customer. The tapped holes for connecting the ground conductor are located on the base frame of the robot.

Standard connecting cable

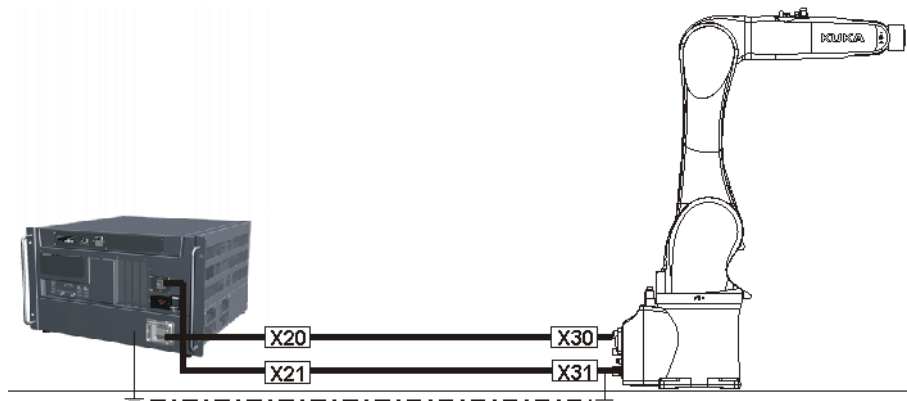


Fig. 8-16: Connecting cables, overview



Wiring diagram

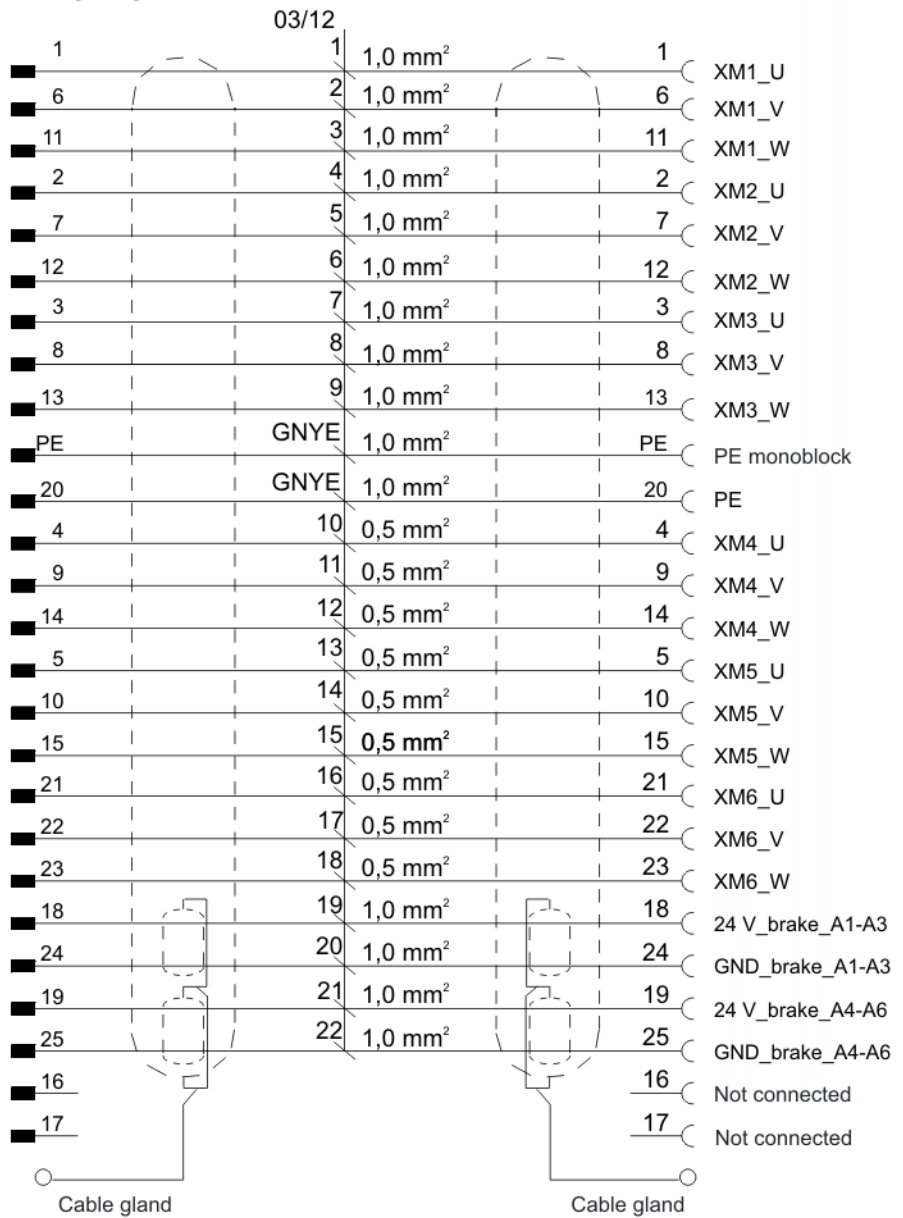


Fig. 8-17: Connecting cable, motor cable, X20 - X30



Wiring diagram

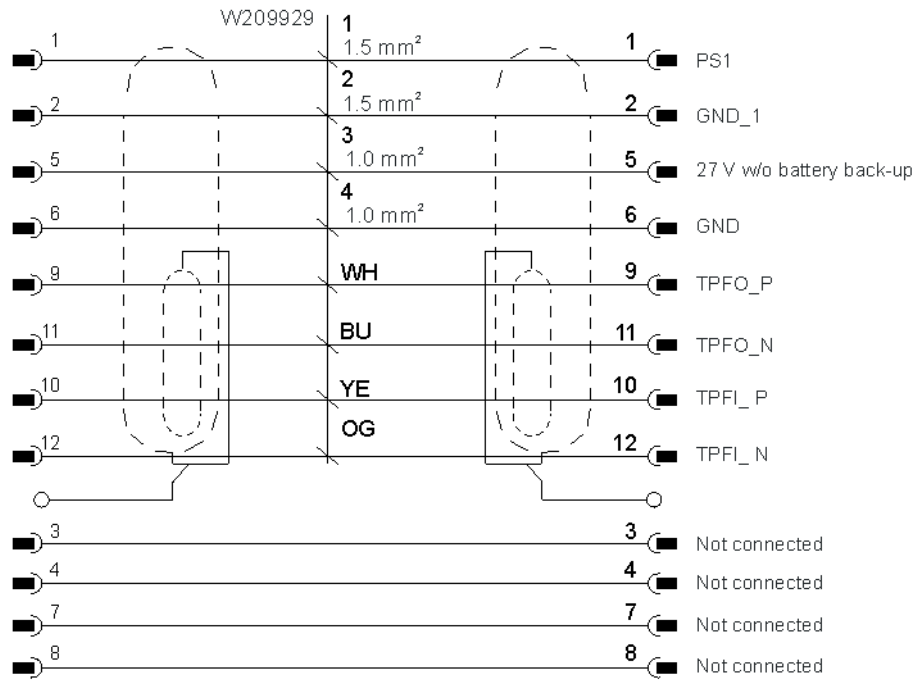


Fig. 8-18: Connecting cable, data cable X21 - X31

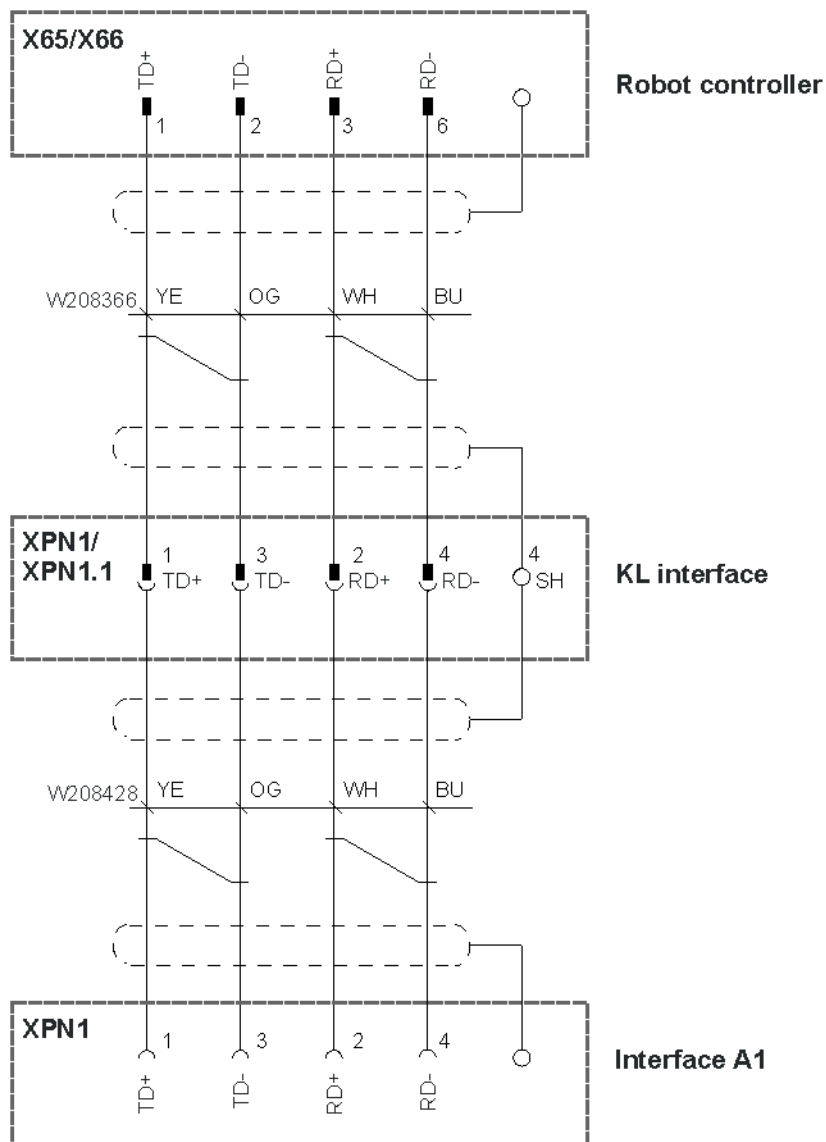


Fig. 8-19: Connecting cable, data cable CAT5 X65/X66 - XPN1

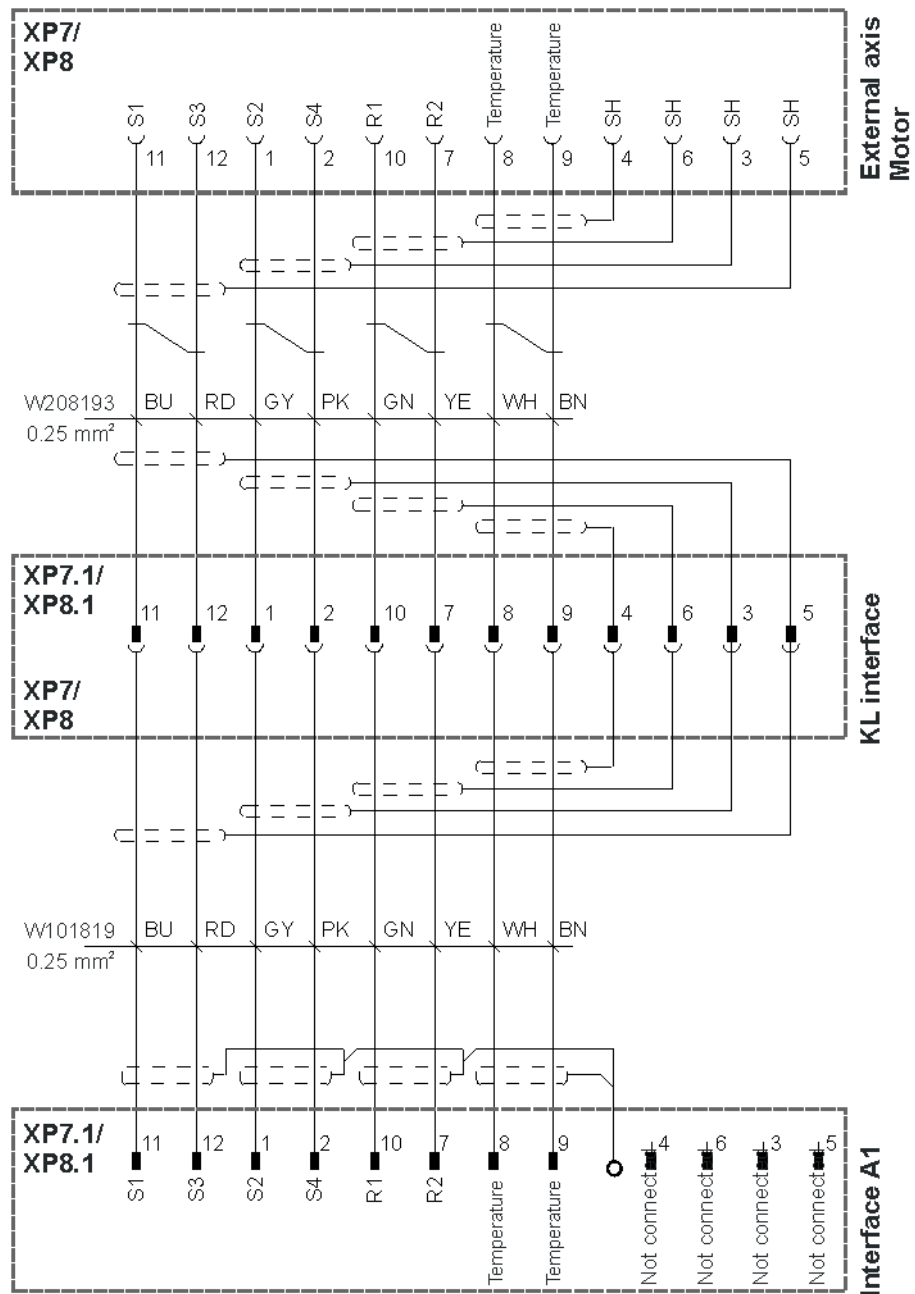


Fig. 8-20: Connecting cable, external axes A7 and A8

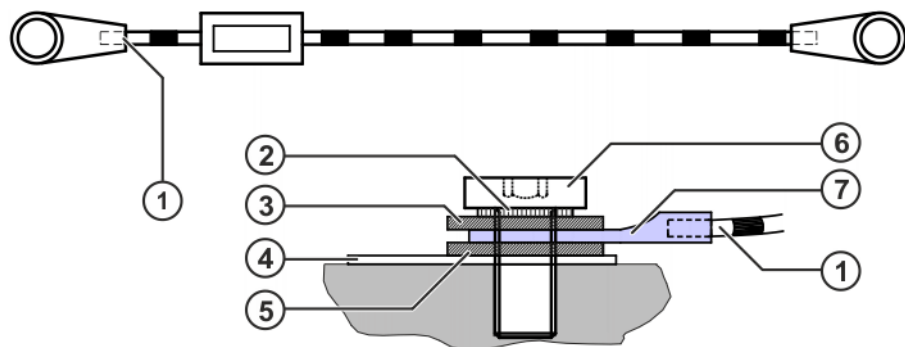



Fig. 8-21: Connecting cable, ground conductor


- 1 Ground conductor
- 2 Lock washer

- 3 Conical spring washer
- 4 Ground plate
- 5 Plain washer
- 6 M4x12 Allen screw
- 7 Ground conductor connection, M4 ring cable lug

8.7 Moving the manipulator without the robot controller

 **WARNING** Use of the brake release device may result in unexpected robot motions, especially sagging of the axes. During use of the brake release device, attention must be paid to motion of this kind in order to be able to prevent physical injuries or damage to property. Standing under moving axes is not permitted.

Procedure

 **SAFETY INSTRUCTIONS** The following procedure must be followed exactly!

1. Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.
2. Connect the brake release device to the base frame of the robot:
Unplug connector X30 from interface A1. Plug connector X20 of the brake release device into interface A1.
3. Select the brakes to be released (main axes, wrist axes) via the selection switch on the brake release device.
4. Press the button on the hand-held device.
The brakes of the main axes or wrist axes are released and the robot can be moved manually.

9 Appendix

9.1 Tightening torque

Tightening torque The following tightening torques are valid for screws and nuts where no other specifications are given.

Screw size	Strength class		
	8.8	10.9	12.9
M1.6	0.17 Nm	0.24 Nm	0.28 Nm
M2	0.35 Nm	0.48 Nm	0.56 Nm
M2.5	0.68 Nm	0.93 Nm	1.10 Nm
M3	1.2 Nm	1.6 Nm	2.0 Nm
M4	2.8 Nm	3.7 Nm	4.4 Nm
M5	5.6 Nm	7.5 Nm	9.0 Nm
M6	9.5 Nm	12.5 Nm	15.0 Nm
M8	23.0 Nm	31.0 Nm	36.0 Nm
M10	45.0 Nm	60.0 Nm	70.0 Nm
M12	78.0 Nm	104.0 Nm	125.0 Nm
M14	125.0 Nm	165.0 Nm	195.0 Nm
M16	195.0 Nm	250.0 Nm	305.0 Nm
M20	370.0 Nm	500.0 Nm	600.0 Nm
M24	640.0 Nm	860.0 Nm	1030.0 Nm
M30	1330.0 Nm	1700.0 Nm	2000.0 Nm

Tighten M5 domed cap nuts with a torque of 4.2 Nm.

9.2 Safety data sheets

9.2.1 Safety data sheet for Flexolub®-A1 lubricant

The following extract from the safety data sheet according to 1907/2006/EEC must be observed.

9.2.1.1 Designation of substance/formulation and manufacturer

Name of substance/preparation	
Product name:	Flexolub®-A1
Use:	Gear lubricant for Harmonic Drive gear units

Manufacturer designation	
Company:	Harmonic Drive AG
Address:	Hoenbergstrasse 14, D-65555 Limburg a. d. Lahn
Country:	Germany
Tel.:	+49 (0)6431 5008 0
Fax:	+49 (0)6431 5008 119

9.2.1.2 Composition / Information about the components

Chemical characterization:	Combination of ester oils, lithium soap and additives.
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9.2.1.3 Possible hazards

Hazard designation not applicable.

9.2.1.4 First aid measures

Contact with eyes:	Flush with plenty of water. If irritation continues, seek medical attention and present this safety data sheet.
Skin contact:	Remove contaminated clothing. Wash affected areas of skin with soap and water. If grease has penetrated into the skin due to improper handling of a high-pressure lubrication gun, seek medical attention immediately and present this safety data sheet.
Inhalation:	Remove affected person to fresh air. If breathing stops, initiate artificial respiration. Seek medical assistance and present this safety data sheet.
Ingestion:	Do not induce vomiting. If the person is unconscious, do not give anything by mouth. Consult a physician immediately and present this safety data sheet.
Notes to physician:	Treatment should in general be symptomatic and directed at relieving any effects. Note regarding high-pressure applications. Injection into the skin due to contact with a product under high pressure constitutes a major medical emergency. Within a few hours the tissue swells up and becomes discolored and extremely painful, with severe subcutaneous necrosis. Surgical treatment is absolutely imperative. Comprehensive opening of the wound and the tissue beneath it is necessary in order to reduce tissue loss and to prevent or limit lasting damage. The high pressure can cause the product to penetrate extensive areas of tissue layers.

9.2.1.5 Fire-fighting measures

Suitable extinguishing agents:	In the event of a fire, use a dry-chemical extinguisher with ABC or BC powder, or a foam or carbon dioxide extinguisher.
Unsuitable extinguishing agents:	Do not use water.
Protection of fire-fighters:	In the case of fire, hazardous gases may develop. Respiratory protection is necessary during fire-fighting measures.

9.2.1.6 Measures after unintended release

Environmental precautions and clean-up methods:	Wipe up small amounts with a cleaning cloth or absorb with oil-binding agents and dispose of in accordance with (>>> 9.2.1.13 "Disposal information" Page 122). Contain large amounts of spilled product with sand or other inert material. Prevent from entering sewers, streams and waterways. Safeguard entrances to the drainage system. Slip hazard! Avoid fire and naked lights. No smoking!
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9.2.1.7 Handling and storage

Handling:	Store in a dry place at room temperature in tightly sealed containers. When using the product, avoid the formation of oil mist if at all possible.
Storage:	<p>The product can be kept for at least 5 years in the original, unopened containers under the specified storage conditions.</p> <p>If the lubricant is to be used at higher temperatures, suitable fume extraction or adequate ventilation must be provided in the place of work.</p> <p>The standard safety precautions used in the mineral oil industry are to be observed.</p>

9.2.1.8 Exposure limits and personal protective equipment

Protective measures	
Hygiene measures:	Keep away from food, drink and tobacco products. Wash hands before breaks and at the end of work. Store work clothes separately. Change contaminated clothing. The usual precautions when handling chemicals must be observed.
Respiratory protection:	Not necessary if used correctly for the intended purpose. Avoid breathing in vapors (oil mist).
Hand protection:	In the case of prolonged or repeated skin contact, wear protective gloves (e.g. made of latex, wearing time > 30 min.; butyl rubber, wearing time > 8 hours).
Eye protection:	Not necessary if used correctly for the intended purpose.

9.2.1.9 Physical and chemical properties

General information	
Physical state:	Fluid
Color:	Magenta
Odor:	Weak

Important information on health and environmental protection and on safety	
Boiling point:	> 250 °C
Density:	0.95 g/cm ³ at 20 °C
Vapor pressure:	< 0.1 mbar at 20 °C 0.12 mbar at 55 °C
Viscosity of base oil:	25 mm ² /s at 40 °C; DIN EN ISO 3104 5.2 mm ² /s at 100 °C
Drop point:	> 200 °C; DIN ISO 2176
Solubility:	Insoluble in water
pH value:	Not determined
Flash point:	> 200 °C; DIN ISO 2592
Ignition temperature:	> 300 °C
Explosion limit:	Not known

9.2.1.10 Stability and reactivity

Thermal decomposition:	> 220 °C
Hazardous decomposition products:	None known if handled and stored correctly. In the case of improper use above the decomposition temperature, or in the event of a fire, harmful vapors may arise (carbon monoxide).
Hazardous reactions:	With strong oxidants (e.g. liquid or compressed oxygen), very strong acids, very strong alkalis.

9.2.1.11 Toxicological information

Oral toxicity: (analogy observation)	LD ₅₀ > 2,000 mg/kg (rat).
Epidermal toxicity: (analogy observation)	One ingredient of the grease may cause weak skin irritation in the case of frequent or excessive contact.

No health problems expected if used for the intended purpose.

9.2.1.12 Ecological information

Water hazard classification 1 (WGK):	Minor water hazard (classification acc. to German Administrative Regulation on the Classification of Substances Hazardous to Water into Water Hazard Classes (VwVwS), dated May 1999). Prevent from entering the soil, surface waters, groundwater or the drainage system.
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9.2.1.13 Disposal information

The product must be disposed of in an authorized incineration plant in accordance with the applicable regulations on hazardous waste.

Contains no halogen compounds or heavy metals.

LAGA waste code:	542 02: for waste grease. 542 09: for solid materials contaminated with grease or oil.
EWC waste code:	12 01 12: for used waxes and greases. 15 02 99 D1: for used absorbent and filter materials, cleaning rags and protective clothing with harmful contaminants. 17 02 99 D1: for used wood, glass and plastics with harmful contaminants (e.g. lubricant residues in plastic tubes).

9.2.1.14 Transport information

ADR/RID	Not hazardous	
Hazard number (Kemler code):	-	Substance code (UN no.): -
Packaging group:	-	Hazard label: -
Class:	-	
GGVSee/IMDG code	Not hazardous	
IMDG code:	-	UN no.: -

Class:	-	Packaging group: -
Label:	-	
ICAO/IATA	Not hazardous	
ICAO/IATA class:	-	UN/ID no.: -
Packing list:	-	

9.2.1.15 Regulations

No labeling required according to the German Dangerous Substances Order and corresponding EC directives.

The product does not contain any volatile organic compounds listed in the Swiss VOC List, Appendix I (dated 12 November 1997) or VOC (TRGS 220; 31. BlmSCH).

Not classified in the German Ordinance on Industrial Safety and Health (BetrSichV / formerly VbF class).

Fire classification:	
Water hazard classification (WGK):	1

9.2.1.16 Other information

Notes for the reader

The information given here is based on the current state of our knowledge and experience. The safety data sheet describes products with regard to safety requirements. The information given does not represent a warranty of characteristics. All data refer to the product in the delivery condition.

This safety data sheet supersedes all previous versions for this product.

9.2.2 Safety data sheet for OBEEN FS 2 lubricant

The following extract from the safety data sheet according to 91/155/EEC must be observed.

9.2.2.1 Designation of substance/formulation and manufacturer

Name of substance/preparation	
Product name:	Obeen FS 2
SDS no.:	DE-08257, UK-3757
Use:	Lubricant for food machinery

Manufacturer designation	
Company:	Deutsche BP Aktiengesellschaft, Industrial Lubricants & Services
Address:	Erkelenzer Strasse 20, D-41179 Mönchengladbach
Country:	Germany
Tel.:	+49 (0)2161 909-319
Fax:	+49 (0)2161 909-392
Emergency hotline:	Carechem: +44 (0)208 762 8322
e-mail address:	MSDSadvice@bp.com

9.2.2.2 Composition / Information about the components

Chemical characterization:	Synthetic lubricant and additives. Thickeners.
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Chemical description	CAS no.	%	EINECS / ELINCS	Classification
Amines, C11-14 branched alkyl, monohexyl and dihexyl-phosphate	80939-62-4	0.1 - 1	279-632-6	Xi; R36/38 N; R51/53
1H-imidazole-1-ethanol, 2-(8-heptadecenyl)-4,5-dihydro-	95-38-5	0.1 - 1	202-414-9	Xn; R22 C; R34 N; R50/53
N-oleyl sarcosine	110-25-8	0.1 - 1	203-749-3	Xi; R38, R41 N; R50/53

Refer to Section (>>> 9.2.2.16 "Other information" Page 128) for the full text of the above R-phrases.

The occupational exposure limit values, where available, are specified in Section (>>> 9.2.2.8 "Exposure limits and personal protective equipment" Page 125).

9.2.2.3 Possible hazards

The preparation is classified as **hazardous** in accordance with Directive 1999/45/EC in its altered and adapted version.

Physical / chemical hazards:	Not classified as dangerous.
Human health hazards:	Not classified as dangerous.
Environmental hazards:	Harmful to aquatic organisms, may cause long-term adverse effects in the aquatic environment.

Effects and symptoms	
Eyes:	May cause mild eye irritation.
Skin:	Prolonged or repeated contact can dry out the skin and lead to irritation and/or dermatitis.
Inhalation:	Vapors and aerosols may cause irritation of the mucous membranes of the nose and throat.
Ingestion:	Ingestion may cause gastrointestinal irritation and diarrhea.

9.2.2.4 First aid measures

Contact with eyes:	In case of contact, rinse eyes immediately with plenty of water for at least 15 minutes. If irritation occurs, consult a doctor.
Skin contact:	Wash affected areas of skin with soap and water, or use suitable cleaning agent. Change clothing and shoes if they become contaminated with product. Wash clothing before reuse. Clean shoes thoroughly before reuse. If irritation occurs consult a doctor.
Inhalation:	Take affected person into fresh air. Consult a doctor if symptoms persist.
Ingestion:	Do not induce vomiting unless explicitly directed to do so by medical personnel. Never give anything by mouth to an unconscious person. If large quantities of this product have been swallowed, call a physician immediately.

9.2.2.5 Fire-fighting measures

Suitable extinguishing agents:	In the event of a fire: use water spray (mist), foam, dry chemicals or CO ₂ . This substance is harmful to aquatic organisms.
Unsuitable extinguishing agents:	Do not use water jets.
Special instructions for extinguishing work:	Contaminated extinguishing water must be contained and prevented from entering surface waters or the sewage or drainage system.
Hazardous decomposition products:	These products are carbon oxides (CO, CO ₂). Certain metal oxides.
Unusual fire/explosion hazards:	This product is not inherently explosive in accordance with the applicable rules.
Special fire-fighting measures:	Not specified.
Protection of fire-fighters:	Fire-fighters must wear self-contained positive pressure breathing apparatus (SCBA) and full protective gear.

9.2.2.6 Measures after unintended release

Personal safety precautions:	Contact emergency personnel immediately. Keep unnecessary personnel away. Use suitable protective equipment, see (>>> 9.2.2.8 "Exposure limits and personal protective equipment" Page 125). Follow all fire-fighting procedures see (>>> 9.2.2.5 "Fire-fighting measures" Page 125).
Environmental precautions and clean-up methods:	If no emergency personnel are available, contain spilled material. Remove solid or absorbed material using a tool and place in a suitable, labeled waste container. Prevent spilled material from coming into contact with soil and surface waters. For disposal information, see (>>> 9.2.2.13 "Disposal information" Page 127).
Personal protection in the event of a large spill:	Before handling this product, consult a specialist regarding protective equipment. Wear splash goggles, full suit, boots and gloves.

9.2.2.7 Handling and storage

Handling:	Prevent contact with skin or clothing. Spilled and leaked product must be prevented from coming into contact with soil and surface waters. Wash thoroughly after handling.
Storage:	Keep containers tightly sealed. Keep containers in a cool, well-ventilated area.
VCI storage class:	11

9.2.2.8 Exposure limits and personal protective equipment

Ingredient name:	Threshold limit values acc. to ACGIH TLV (USA, 1/2005)
Aluminum (benzoato-o)hydroxy(octadecanoato-o)	TWA: 2 mg/m ³ 8 hour(s). Form: Soluble Where no exposure limits exist in law, the ACGIH values are included for information and as reference. Further information can be obtained from the supplier.

Protective measures	
Limitation and monitoring of exposure in the workplace:	Provide extractor ventilation or other engineering controls to keep the airborne concentrations of vapors below their respective occupational exposure limits.
Hygiene measures:	Wash hands after handling the product and before eating, smoking, using lavatory, and at the end of day.
Respiratory protection:	Not essential. Sufficient ventilation is recommended in industry. If ventilation is insufficient, respiratory protection is useful.
Hand protection:	Wear protective gloves if prolonged or repeated contact is likely. Chemical-resistant protective gloves. Recommended: nitrile gloves. The right choice of protective gloves is dependent on the chemicals to be handled, the working conditions, and the condition of the gloves themselves (even the best chemical-resistant protective gloves start to leak after repeated contact with chemicals). Most protective gloves only provide protection for a short period of time, after which they must be disposed of and replaced. As the specific working conditions and the chemicals concerned differ from case to case, appropriate safety measures must be developed for each individual application. Protective gloves should therefore be selected in consultation with the supplier/manufacturer, giving full consideration to the specific working conditions.
Eye protection:	Protective goggles with side shields to guard against splashing.
Skin and body:	Wear appropriate clothing to avoid prolonged skin contact.

9.2.2.9 Physical and chemical properties

Physical state:	Solid (paste)
Color:	Amber
Odor:	Light
Melting point/range:	>230 °C
Density:	<1000 kg/m ³ (<1 g/cm ³) at 20 °C
Solubility:	Insoluble in water

9.2.2.10 Stability and reactivity

Incompatible with various substances:	Reactive or incompatible with oxidizing materials.
Hazardous polymerization:	Will not occur.

9.2.2.11 Toxicological information

Carcinogenic effect:	No component of this product at levels greater than 0.1% is identified as a carcinogen by ACGIH, the International Agency for Research on Cancer (IARC) or the European Commission (EC).
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9.2.2.12 Ecological information

Persistence / degradability:	Inherently biodegradable.
Mobility:	The product is non-volatile. Paste. Insoluble in water.
Environmental hazards:	Harmful to aquatic organisms. May cause long-term adverse effects in the aquatic environment.

9.2.2.13 Disposal information

Disposal information	
Disposal information / waste specifications:	Spilled and leaked product must be prevented from coming into contact with soil and surface waters. Consult an environmental professional to determine if local, regional or national regulations would classify spilled or contaminated materials as hazardous waste. Use only approved transporters, recyclers, treatment, storage or disposal facilities.

Unused product	
European Waste Catalog (EWC):	Waste code 12 01 12: Used waxes and greases

Used/contaminated product	
European Waste Catalog (EWC):	Waste code 12 01 12: Used waxes and greases

Packaging	
European Waste Catalog (EWC):	Waste code 15 01 10: Packaging containing the residue of hazardous materials or contaminated by hazardous materials.

Use of the product for purposes other than those specified and/or impurities can necessitate the use of a different waste code number for the waste producer.

Hazardous waste	
This product is listed as a hazardous substance by the EU Directive on hazardous waste. Dispose of in accordance with all national and local regulations and statutory provisions in force.	

9.2.2.14 Transport information

Classification:	Not hazardous as defined by the transport regulations (ADR/RID, ADNR, IMDG, ICAO/IATA).
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9.2.2.15 Regulations

EU regulations:	EC Directives 1999/45/EC and 67/548/EEC.
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Labeling requirements	
Risk (R) phrases:	R52/53 - Harmful to aquatic organisms, may cause long-term adverse effects in the aquatic environment.
Safety (S) phrases:	S61 - Avoid release to the environment. Refer to special instructions/safety data sheet.

List of relevant R phrases
R22 - Harmful if swallowed.
R34 - Causes burns.
R36/38 - Irritating to eyes and skin.
R38 - Irritating to skin.
R41 - Risk of serious damage to eyes.
R50/53 - Very toxic to aquatic organisms, may cause long-term adverse effects in the aquatic environment.
R51/53 - Toxic to aquatic organisms, may cause long-term adverse effects in the aquatic environment.
R52/53 - Harmful to aquatic organisms, may cause long-term adverse effects in the aquatic environment.

Miscellaneous provisions	
Inventories:	AUSTRALIAN INVENTORY (AICS): In compliance. CANADIAN INVENTORY (DSL): Not determined. CHINESE INVENTORY (IECSC): Not determined. EC INVENTORY (EINECS/ELINCS): In compliance. JAPANESE INVENTORY (ENCS): Not determined. KOREAN INVENTORY (ECL): Not determined. PHILIPPINE INVENTORY (PICCS): Not determined. US INVENTORY (TSCA): In compliance.
Technical Guideline on Air:	Class III
Classification acc. to the German Administrative Regulation on the Classification of Substances Hazardous to Water into Water Hazard Classes (VwVwS):	2 (water hazard)

9.2.2.16 Other information

History	
Date of issue:	06/07/2005.
Date of previous issue:	01/09/2004.
Created by:	Product Stewardship

Notes for the reader

All reasonably practicable steps have been taken to ensure this data sheet and the health, safety and environmental information contained in it is accurate as of the date of issue stated under History. No warranty or representation, express or implied, is made as to the accuracy or completeness of the data and information in this data sheet.

The data and advice given are valid if the product is sold for the application(s) specified. The product should not be used for purposes other than the applications specified without prior consultation with us.

It is the user's obligation to evaluate and use this product safely and to comply with all applicable laws and regulations.

The BP Group accepts no responsibility for any damage or injury resulting from uses other than the stated product use of the material, from any failure to adhere to recommendations, or from hazards inherent in the nature of the material. Those purchasing the product for supply to third parties for use at work have a duty to take all necessary steps to ensure that any person handling or using the product is provided with the information on this data sheet. Employers have a duty to tell employees and others who may be affected of any hazards described in this sheet and of any precautions that should be taken.

10 KUKA Service

10.1 Requesting support

Introduction The KUKA Roboter GmbH documentation offers information on operation and provides assistance with troubleshooting. For further assistance, please contact your local KUKA subsidiary.

Information The following information is required for processing a support request:

- Model and serial number of the robot
- Model and serial number of the controller
- Model and serial number of the linear unit (if applicable)
- Model and serial number of the energy supply system (if applicable)
- Version of the KUKA System Software
- Optional software or modifications
- Archive of the software
 - For KUKA System Software V8: instead of a conventional archive, generate the special data package for fault analysis (via **KrcDiag**).
- Application used
- Any external axes used
- Description of the problem, duration and frequency of the fault

10.2 KUKA Customer Support

Availability KUKA Customer Support is available in many countries. Please do not hesitate to contact us if you have any questions.

Argentina Ruben Costantini S.A. (Agency)
Luis Angel Huergo 13 20
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2400 San Francisco (CBA)
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Tel. +54 3564 421033
Fax +54 3564 428877
ventas@costantini-sa.com

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Tel. +61 3 9244-3500
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