

ROBOTICS

Product specification

IRB 6650S



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Workspace 21C version a2
Checked in 2021-09-23
Skribenta version 5.4.005

Product specification

IRB 6650S-90/3.9

IRB 6650S-125/3.5

IRB 6650S-200/3.0

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Revision: AA

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Overview of this product specification

About this product specification

It describes the performance of the manipulator or a complete family of manipulators in terms of:

- The structure and dimensional prints
- The fulfilment of standards, safety and operating requirements
- The load diagrams, mounting of extra equipment, the motion and the robot reach
- The specification of variant and options available

Usage

Product specifications are used to find data and performance about the product, for example to decide which product to buy. How to handle the product is described in the product manual.

Users

It is intended for:

- Product managers and Product personnel
- Sales and Marketing personnel
- Order and Customer Service personnel

References

Reference	Document ID
<i>Product specification - Controller IRC5</i> IRC5 with main computer DSQC1000.	3HAC047400-001
<i>Product specification - Controller software IRC5</i> IRC5 with main computer DSQC1000 and RobotWare 5.6x.	3HAC050945-001
<i>Product specification - Controller software IRC5</i> IRC5 with main computer DSQC1000 and RobotWare 6.	3HAC050945-001
<i>Product manual - IRB 6650S</i>	3HAC020993-001
<i>Product specification - Robot user documentation, IRC5 with RobotWare 6</i>	3HAC052355-001

Revisions

Revision	Description
-	- New Product Specification.
A	- Changes for Calibration data - Work range - Explanation of ISO values (new figure and table) - Stopping distance - User documentation on DVD
B	- General update for 9.1 release

Continues on next page

Overview of this product specification

Continued

Revision	Description
C	- Foundry Plus 2
D	- Updated Foundry Plus 2 text - ISO-Cube
E	- Text for Standards updated - New document structure
F	- Minor corrections and information added
G	<ul style="list-style-type: none"> • Table for ambient temperature adjusted • Minor corrections
H	<ul style="list-style-type: none"> • Machinery directive updated • General corrections
J	<ul style="list-style-type: none"> • Base plate drawing updated • Drawing for reference holes updated • Minor corrections/update
K	<ul style="list-style-type: none"> • Minor corrections/update
L	<ul style="list-style-type: none"> • Minor corrections/update
M	<ul style="list-style-type: none"> • Text for ISO test adjusted • Robot stopping distances and times for category 0 and category 1 stops are moved to a separate document, <i>Product specification - Robot stopping distances according to ISO 10218-1</i>
N	<ul style="list-style-type: none"> • Text for Foundry Plus updated. • Minor corrections/update
P	<ul style="list-style-type: none"> • Minor corrections/update
Q	<ul style="list-style-type: none"> • DressPack LeanID added • Section "SpotWelding cabinet" updated.
R	<ul style="list-style-type: none"> • Warranty information for DressPack added
S	Phrase <i>The values for IRB 6650S-90/3.9 are not yet available</i> is changed to <i>The values for IRB 6650S-90/3.9 are not available</i> , in section Performance according to ISO 9283 on page 59
T	Published in release R17.1. The following updates are done in this revision: <ul style="list-style-type: none"> • Restriction of load diagram added.
U	Published in release R17.2. The following updates are done in this revision: <ul style="list-style-type: none"> • Updated list of applicable standards. • TCP acceleration information added. • Delete option 828-1, 828-2, 768-3 and 782-1 as they were all phased out.
V	Published in release R18.2. The following updates are made in this revision: <ul style="list-style-type: none"> • New dimensions added on illustration, see Mounting of hip load on page 51.
X	Published in release 19C The following updates are made in this revision: <ul style="list-style-type: none"> • Graphics for DressPack changed. See Base on page 79. • Updated information about <i>Absolute Accuracy</i>.
Y	Published in release 20A. The following updates are done in this revision: <ul style="list-style-type: none"> • M8 cable lug description added in DressPack section.
Z	Published in release 20D. The following updates are done in this revision: <ul style="list-style-type: none"> • Warranty section updated.

Continues on next page

Revision	Description
AA	<p>Published in release 21C. The following updates are done in this revision:</p> <ul style="list-style-type: none">• Text regarding fastener quality is updated.• Removed Axis resolution.• Updated information about the option <i>Extended working range</i>.• Removed option (SpotPack phase out) 782-13 Bosch MFDC ProfiNet, 858-1 Bosch Adaptive control, 788-1 Forced air cooling, 789-1 Earth fault protection unit, 790-1 Contactor for weld power, 791-1 Weld power cable, 7 m, 791-2 Weld power cable, 15 m, 809-1 process cable to stationary gun, 7 m, 809-2 process cable to stationary gun, 15 m, 792-1 Type S, 792-2 Type HS, 793-1 Second water return, 797-1 7m, 797-2 15m, 797-3 22m, 797-4 30m.

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1 Description

1.1 Structure

1.1.1 Introduction

Robot family

The IRB 6650S is available in three versions:

The IRB 6650S is ideal for process applications, regardless of industry and offers a unique working envelope. Typical areas can be Spot Welding, Material Handling and Machine Tending.

Software product range

We have added a range of software products - all falling under the umbrella designation of Active Safety - to protect not only personnel in the unlikely event of an accident, but also robot tools, peripheral equipment and the robot itself.

Operating system

The robot is equipped with the IRC5 controller and robot control software, RobotWare. RobotWare supports every aspect of the robot system, such as motion control, development and execution of application programs, communication etc. See Product specification - Controller IRC5 with FlexPendant.

Safety

Safety standards valid for complete robot, manipulator and controller.

Additional functionality

For additional functionality, the robot can be equipped with optional software for application support - for example gluing and welding, communication features - network communication - and advanced functions such as multitasking, sensor control etc. For a complete description on optional software, see the Product specification - Controller software IRC5.

Protection type Foundry Plus 2

Robots with the option Foundry Plus 2 are designed for harsh environments where the robot is exposed to sprays of coolants, lubricants and metal spits that are typical for die casting applications or other similar applications.

Typical applications are spraying insertion and part extraction of die-casting machines, handling in sand casting and gravity casting, etc. (Please refer to Foundry Prime robots for washing applications or other similar applications). Special care must be taken in regard to operational and maintenance requirements for applications in foundry as well as in other applications areas. Please contact ABB Robotics Sales organization if in doubt regarding specific application feasibility for the Foundry Plus 2 protected robot.

The robot is painted with two-component epoxy on top of a primer for corrosion protection. To further improve the corrosion protection additional rust preventive

Continues on next page

1 Description

1.1.1 Introduction

Continued

are applied to exposed and crucial areas, e.g. has the tool flange a special preventive coating. Although, continuous splashing of water or other similar rust formation fluids may cause rust attach on the robots unpainted areas, joints, or other unprotected surfaces. Under these circumstances it is recommended to add rust inhibitor to the fluid or take other measures to prevent potential rust formation on the mentioned.

The entire robot is IP67 compliant according to IEC 60529 - from base to wrist, which means that the electrical compartments are sealed against water and solid contaminants. Among other things all sensitive parts are better protected than the standard offer.

Selected Foundry Plus 2 features:

- Improved sealing to prevent penetration into cavities to secure IP67
- Additional protection of cabling and electronics
- Special covers that protect cavities
- Well-proven connectors
- Nickel coated tool flange
- Rust preventives on screws, washers and unpainted/machined surfaces
- Extended service and maintenance program

The Foundry Plus 2 robot can be cleaned with appropriate washing equipment according to the robot product manual. Appropriate cleaning and maintenance is required to maintain the protection, for example can rust preventive be washed off with wrong cleaning method.

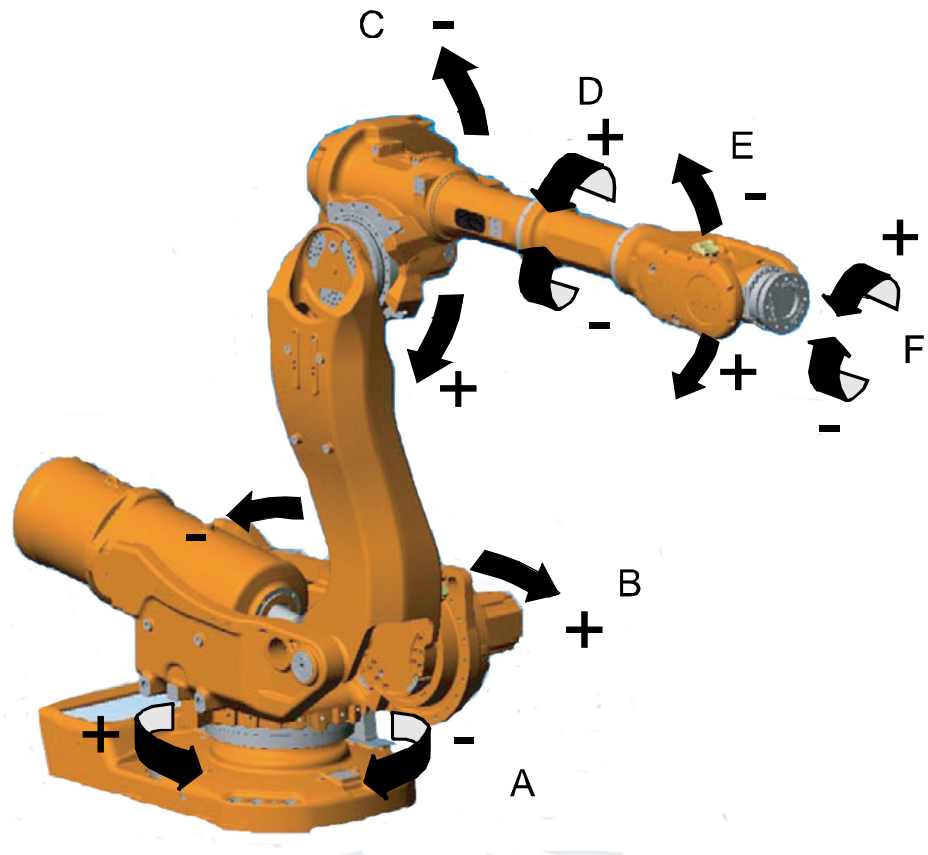
Available robot versions

The option Foundry Plus 2 might not be available for all robot versions.

See [Specification of variants and options on page 135](#) for robot versions and other options not selectable together with Foundry Plus 2.

Continues on next page

Axis movement



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Pos	Description	Pos	Description
A	Axis 1	B	Axis 2
C	Axis 3	D	Axis 4
E	Axis 5	F	Axis 6

1 Description

1.1.2 Different robot versions

1.1.2 Different robot versions

General

The IRB 6650S is available in three versions.

Standard

The following different standard robot types are available:

Robot type	Handling capacity	Handling capacity for LeanID	Reach
IRB 6650S	90 kg	-	3.9 m
IRB 6650S	125 kg	100 kg	3.5 m
IRB 6650S	200 kg	190 kg	3.0 m



Note

If option 780-4, LeanID is selected, the payload will decrease as stated above, for detailed information see [Load diagrams on page 35](#)

1.1.3 Definition of version designation

IRB 6650S Mounting

Handling capacity (kg)/ Reach (m)

	Prefix	Description
Mounting	-	Floor-mounted manipulator
Handling capacity (kg)	yyy	Indicates the maximum handling capacity (kg)
Reach (m)	x.x	Indicates the maximum Reach at wrist center (m)

Manipulator weight

Robot type	Weight
IRB 6650S-90/3.9	2275 kg ^a
IRB 6650S-125/3.5	2250 kg ^a
IRB 6650S-200/3.0	2250 kg ^a

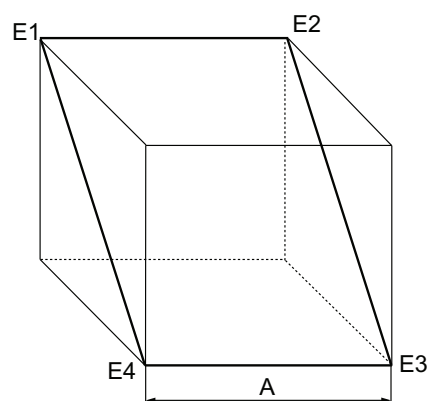
a. Without DressPack

Other technical data

Data	Description	Note
Airborne noise level	The sound pressure level outside the working space.	< 73 dB (A) Leq (acc. to Machinery directive 2006/42/EG)

Power consumption at max load

Type of Movement	IRB 6650S
ISO Cube	2.4 kW



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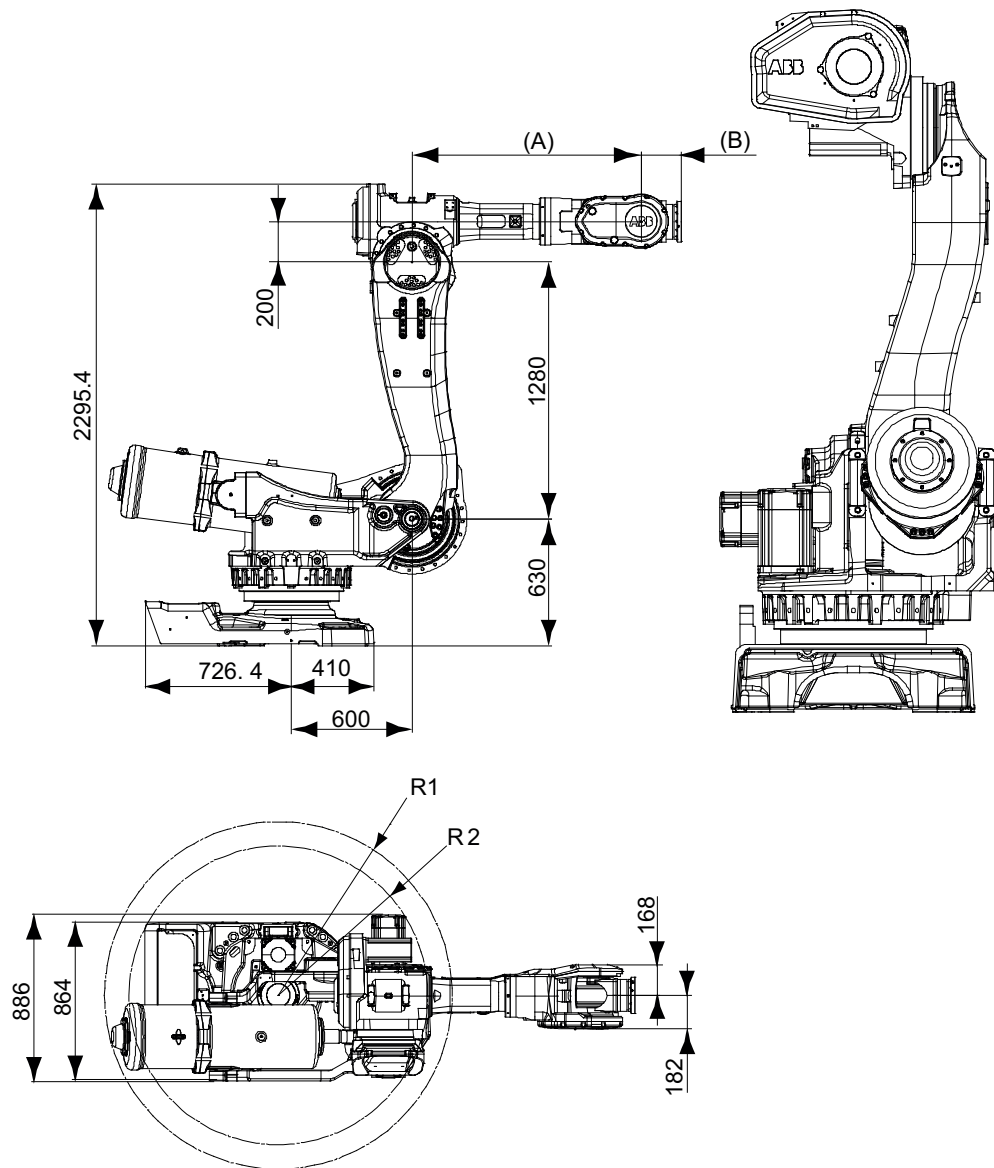
Pos	Description
A	1000 mm

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1 Description

1.1.3 Definition of version designation

Continued



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Robot variant	A	B
IRB 6650S-90/3.9	2042	-
IRB 6650S-125/3.5	1592	200 mm for standard and 349 mm LeanID
IRB 6650S-200/3.0	1142	200 mm for standard and 349 mm LeanID

Pos	Description
R1	R 960 (Rear side, Balancing device)
R2	R 813 (Front side, Motor axis 2)

1.2 Standards

1.2.1 Applicable standards



Note

The listed standards are valid at the time of the release of this document. Phased out or replaced standards are removed from the list when needed.

General

The product is designed in accordance with ISO 10218-1:2011, Robots for industrial environments - Safety requirements -Part 1 Robots, and applicable parts in the normative references, as referred to from ISO 10218-1:2011. In case of deviations from ISO 10218-1:2011, these are listed in the declaration of incorporation which is part of the product delivery.

Normative standards as referred to from ISO 10218-1

Standard	Description
ISO 9283:1998	Manipulating industrial robots - Performance criteria and related test methods
ISO 10218-2	Robots and robotic devices - Safety requirements for industrial robots - Part 2: Robot systems and integration
ISO 12100	Safety of machinery - General principles for design - Risk assessment and risk reduction
ISO 13849-1:2006	Safety of machinery - Safety related parts of control systems - Part 1: General principles for design
ISO 13850	Safety of machinery - Emergency stop - Principles for design
IEC 60204-1:2005	Safety of machinery - Electrical equipment of machines - Part 1: General requirements
IEC 62061:2005	Safety of machinery - Functional safety of safety-related electrical, electronic and programmable electronic control systems

Region specific standards and regulations

Standard	Description
ANSI/RIA R15.06	Safety requirements for industrial robots and robot systems
ANSI/UL 1740	Safety standard for robots and robotic equipment
CAN/CSA Z 434-14	Industrial robots and robot Systems - General safety requirements

Other standards used in design

Standard	Description
ISO 9787:2013	Robots and robotic devices -- Coordinate systems and motion nomenclatures
IEC 61000-6-2	Electromagnetic compatibility (EMC) – Part 6-2: Generic standards – Immunity standard for industrial environments

Continues on next page

1 Description

1.2.1 Applicable standards

Continued

Standard	Description
IEC 61000-6-4 (option 129-1)	Electromagnetic compatibility (EMC) – Part 6-4: Generic standards – Emission standard for industrial environments
ISO 13732-1:2006	Ergonomics of the thermal environment - Part 1
IEC 60974-1:2012 ⁱ	Arc welding equipment - Part 1: Welding power sources
IEC 60974-10:2014 ⁱ	Arc welding equipment - Part 10: EMC requirements
ISO 14644-1:2015 ⁱⁱ	Classification of air cleanliness
IEC 60529:1989 + A2:2013	Degrees of protection provided by enclosures (IP code)

ⁱ Only valid for arc welding robots. Replaces IEC 61000-6-4 for arc welding robots.

ⁱⁱ Only robots with protection Clean Room.

1.3 Installation

1.3.1 Introduction

General

All versions of IRB 6650S are designed for floor mounting (no tilting allowed around X-axis or Y-axis). Depending on the robot version, an end effector with max. weight of 90 to 200 kg including payload, can be mounted on the mounting flange (axis 6). See [Load diagrams on page 35](#) for IRB 6650S generation robots.

Extra Loads

Extra load (valve packages, transformers) of 50 kg, which is included in the load diagrams, can be mounted on the upper arm. An extra load of 500 kg can also be mounted on the frame of axis 1. See [Mounting equipment on page 49](#) on IRB 6650S.

Working Range

The working range of axes 1-3 can be limited by mechanical stops.

1 Description

1.3.2 Operating requirements

1.3.2 Operating requirements

Protection standards

Robot version/ Protection standard	IEC60529
All variants, manipulator	IP67

Explosive environments

The robot must not be located or operated in an explosive environment.

Ambient temperature

Description	Standard/Option	Temperature
Manipulator during operation	Standard	+ 5 °C ⁱ (41 °F) to + 50 °C (122 °F)
For the controller	Standard/Option	See <i>Product specification - Controller IRC5 with FlexPendant</i>
For the spot welding cabinet	Standard	+ 5 °C (41 °F) to + 45 °C (113 °F)
Complete robot during transportation and storage	Standard	- 25 °C (- 13 °F) to + 55 °C (131 °F)
For short periods (not exceeding 24 hours)	Standard	up to + 70 °C (158 °F)

ⁱ At low environmental temperature < 10 ° C is, as with any other machine, a warm-up phase recommended to be run with the robot. Otherwise there is a risk that the robot stops or run with lower performance due to temperature dependent oil and grease viscosity.

Relative humidity

Description	Relative humidity
Complete robot during transportation and storage	Max. 95% at constant temperature
Complete robot during operation	Max. 95% at constant temperature

1.3.3 Mounting the manipulator

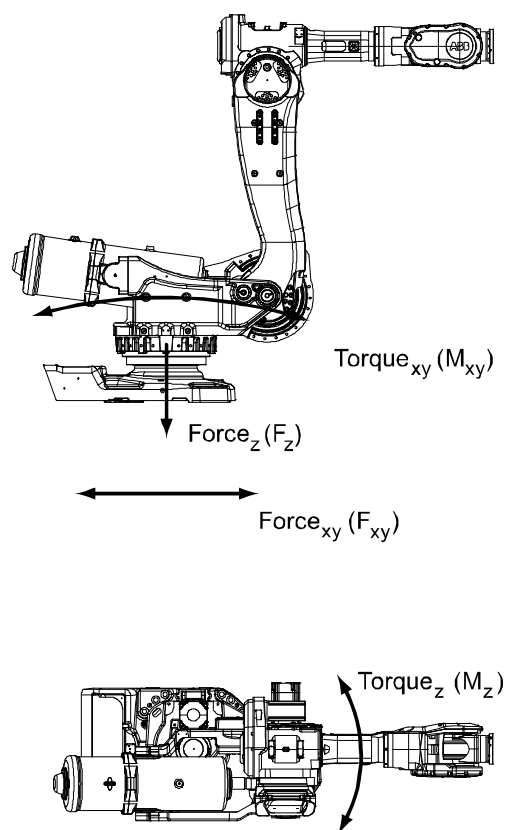
Maximum Load

Maximum load in relation to the base coordinate system.

Floor Mounted

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	± 10.6 kN	± 20.9 kN
Force z	28.2 ± 7.7 kN	28.2 ± 16.4 kN
Torque xy	± 28.2 kNm ± 31 kNm*	± 50.5 kNm ± 55.6 kNm*
Torque z	± 7.9 kNm	± 13.6 kNm

* When using base spacers (option 571-1).



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Note regarding Mxy and Fxy

The bending torque (Mxy) can occur in any direction in the XY-plane of the base coordinate system.

The same applies to the transverse force (Fxy).

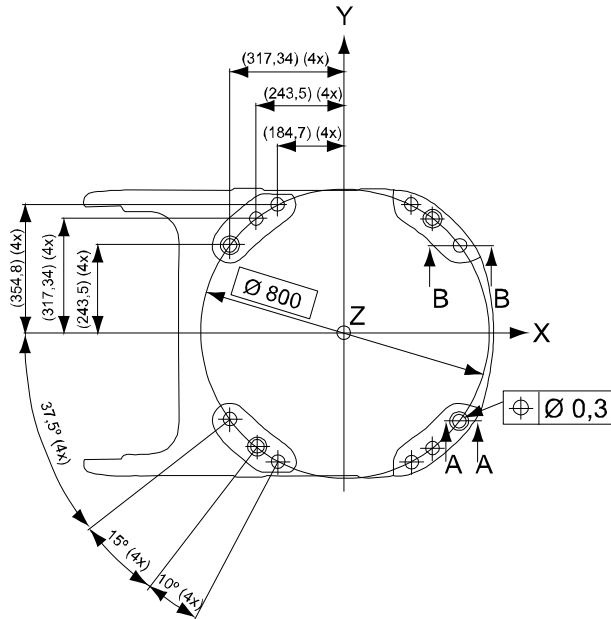
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1 Description

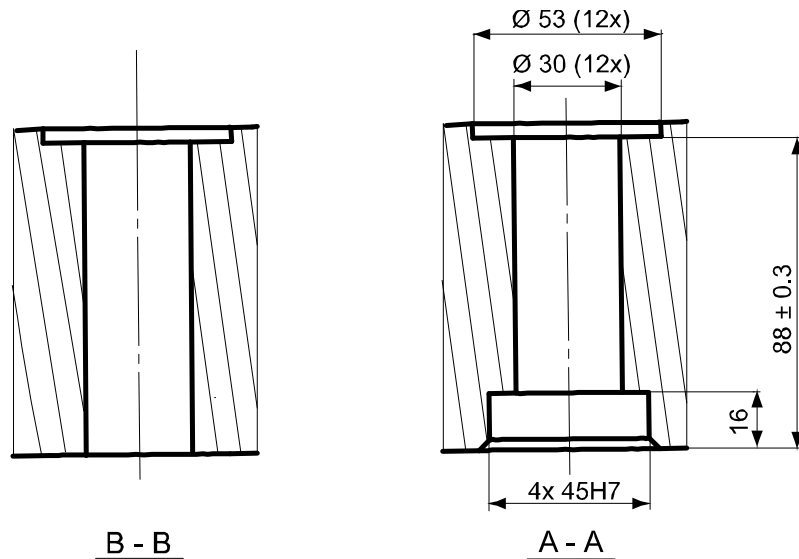
1.3.3 Mounting the manipulator

Continued

Fastening holes robot base - for IRB 6650S



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Recommended screws for fastening the manipulator to the base	M24 x 140 8.8 with 4 mm flat washer
Torque value	725 Nm



Note

Only two guiding sleeves shall be used. The corresponding holes in the base plate shall be circular and oval according to Figures below.

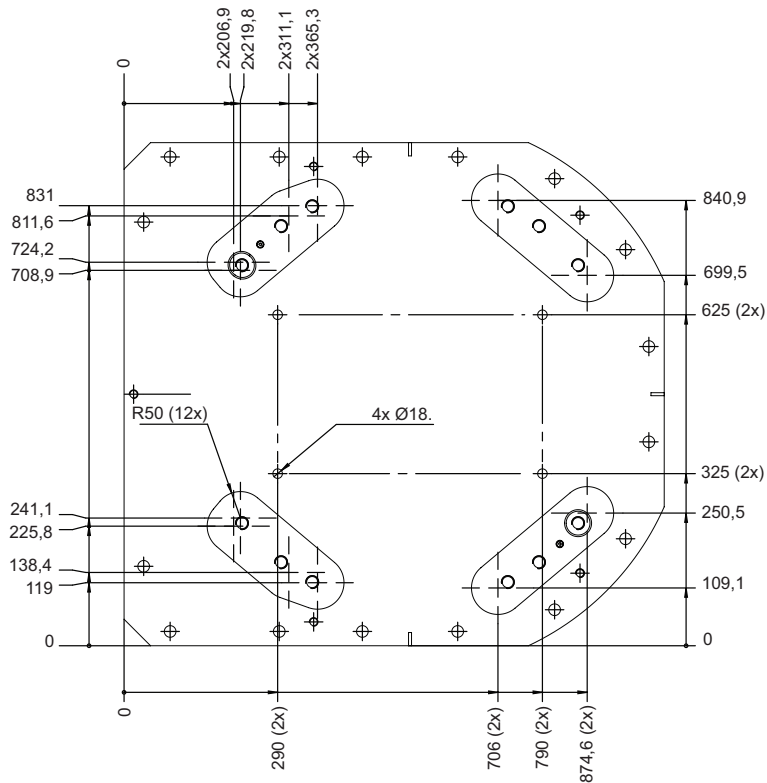
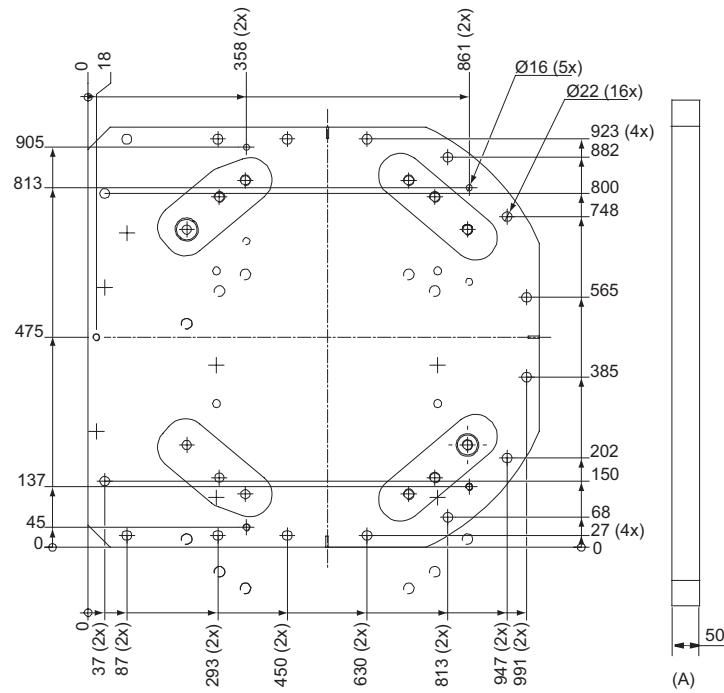
Regarding AbsAcc performance, the chosen guide holes according to Figures below are recommended.

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1 Description

1.3.3 Mounting the manipulator

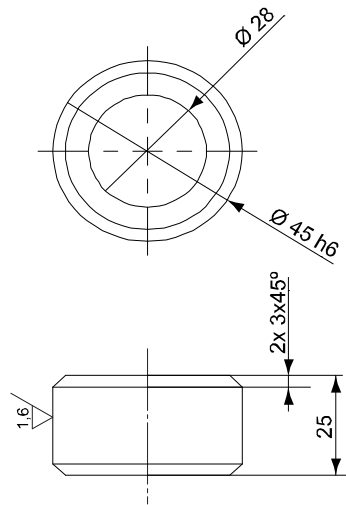
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Pos	Description
A	Color: RAL 9005 Thickness: 80-100 μm

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xx1000001055

Pos	Description
A	Guide sleeve protected from corrosion

1 Description

1.4.1 Calibration methods

1.4 Calibration and references


1.4.1 Calibration methods

Overview

This section specifies the different types of calibration and the calibration methods that are supplied by ABB.

More information is available in the product manual.

Types of calibration

Type of calibration	Description	Calibration method
Standard calibration	<p>The calibrated robot is positioned at calibration position.</p> <p>Standard calibration data is found on the SMB (serial measurement board) or EIB in the robot.</p> <p>For robots with RobotWare 5.04 or older, the calibration data is delivered in a file, calib.cfg, supplied with the robot at delivery. The file identifies the correct resolver/motor position corresponding to the robot home position.</p>	<p>Axis Calibration or Calibration Pendulum¹</p> <p>Levelmeter calibration (alternative method)</p>
Absolute accuracy calibration (optional)	<p>Based on standard calibration, and besides positioning the robot at synchronization position, the Absolute accuracy calibration also compensates for:</p> <ul style="list-style-type: none"> • Mechanical tolerances in the robot structure • Deflection due to load <p>Absolute accuracy calibration focuses on positioning accuracy in the Cartesian coordinate system for the robot.</p> <p>Absolute accuracy calibration data is found on the SMB (serial measurement board) in the robot.</p> <p>For robots with RobotWare 5.05 or older, the absolute accuracy calibration data is delivered in a file, absacc.cfg, supplied with the robot at delivery. The file replaces the calib.cfg file and identifies motor positions as well as absolute accuracy compensation parameters.</p> <p>A robot calibrated with Absolute accuracy has a sticker next to the identification plate of the robot.</p> <p>To regain 100% Absolute accuracy performance, the robot must be recalibrated for absolute accuracy after repair or maintenance that affects the mechanical structure.</p> <div style="border: 1px solid black; padding: 5px; margin-top: 10px;">  <p style="text-align: center; margin: 0;">ABSOLUTE ACCURACY</p> <p style="text-align: right; font-size: small; margin: 0;">3HAC 14257-1</p> </div> <p style="font-size: x-small; margin-top: 5px;">xx0400001197</p>	<p>CalibWare</p>

Continues on next page

Type of calibration	Description	Calibration method
Optimization	<p>Optimization of TCP reorientation performance. The purpose is to improve reorientation accuracy for continuous processes like welding and gluing.</p> <p>Wrist optimization will update standard calibration data for axes 4 and 5.</p>	Wrist Optimization

- ⁱ The robot is calibrated by either Calibration Pendulum or Axis Calibration at factory. Always use the same calibration method as used at the factory. Information about valid calibration method is found on the calibration label or in the calibration menu on the FlexPendant. If no data is found related to standard calibration, Calibration Pendulum is used as default.

Brief description of calibration methods

Calibration Pendulum method

Calibration Pendulum is a standard calibration method for calibration of all ABB robots (except IRB 6400R, IRB 640, IRB 1400H, and IRB 4400S).

Two different routines are available for the Calibration Pendulum method:

- Calibration Pendulum II
- Reference calibration

The calibration equipment for Calibration Pendulum is delivered as a complete toolkit, including the *Operating manual - Calibration Pendulum*, which describes the method and the different routines further.

Axis Calibration method

Axis Calibration is a standard calibration method for calibration of IRB 6650S and is the most accurate method for the standard calibration. It is the recommended method in order to achieve proper performance.

The following routines are available for the Axis Calibration method:

- Fine calibration
- Update revolution counters
- Reference calibration

The calibration equipment for Axis Calibration is delivered as a toolkit.

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

Wrist Optimization method

Wrist Optimization is a method for improving reorientation accuracy for continuous processes like welding and gluing and is a complement to the standard calibration method.

The following routines are available for the Wrist Optimization method:

- Wrist Optimization

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

Continues on next page

1 Description

1.4.1 Calibration methods

Continued

CalibWare - Absolute Accuracy calibration

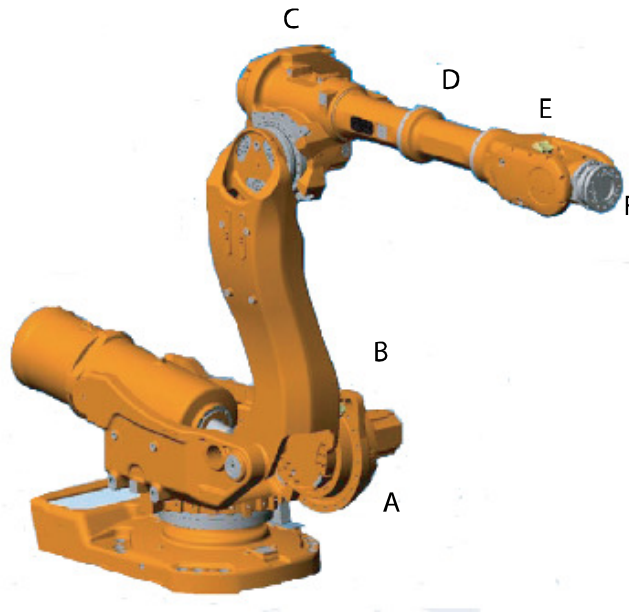
The CalibWare tool guides through the calibration process and calculates new compensation parameters. This is further detailed in the *Application manual - CalibWare Field*.

If a service operation is done to a robot with the option Absolute Accuracy, a new absolute accuracy calibration is required in order to establish full performance. For most cases after replacements that do not include taking apart the robot structure, standard calibration is sufficient.

1.4.2 Fine calibration

General

Fine calibration is made using the Calibration Pendulum, see *Operating manual - Calibration Pendulum* or *Axis calibration, see Product manual - IRB 6650S*.



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Pos	Description	Pos	Description
A	Axis 1	B	Axis 2
C	Axis 3	D	Axis 4
E	Axis 5	F	Axis 6

Calibration

Calibration	Position
Calibration of all axes	All axes are in zero position
Calibration of axis 1 and 2	Axis 1 and 2 in zero position
	Axis 3 to 6 in any position
Calibration of axis 1	Axis 1 in zero position
	Axis 2 to 6 in any position

1 Description

1.4.3 Absolute Accuracy calibration

1.4.3 Absolute Accuracy calibration

Purpose

Absolute Accuracy is a calibration concept that improves TCP accuracy. The difference between an ideal robot and a real robot can be several millimeters, resulting from mechanical tolerances and deflection in the robot structure. *Absolute Accuracy* compensates for these differences.

Here are some examples of when this accuracy is important:

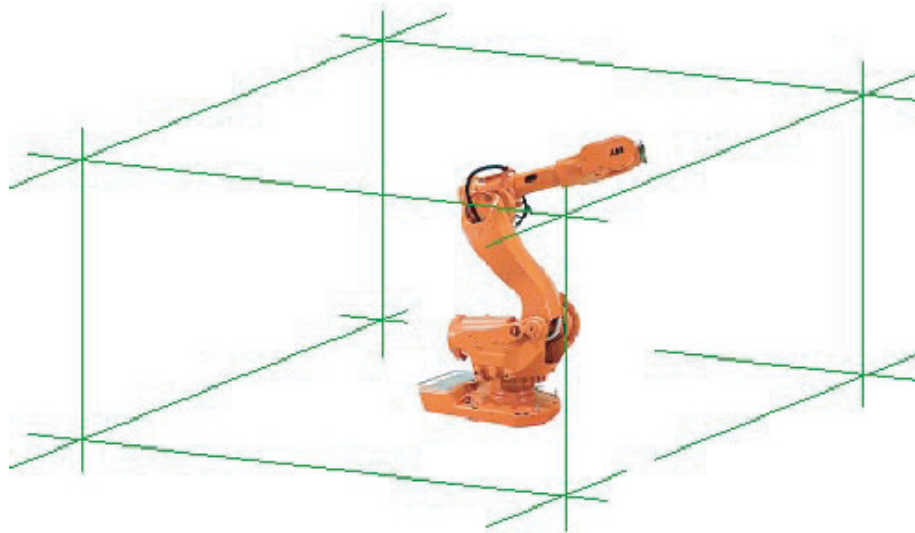
- Exchangeability of robots
- Offline programming with no or minimum touch-up
- Online programming with accurate movement and reorientation of tool
- Programming with accurate offset movement in relation to eg. vision system or offset programming
- Re-use of programs between applications

The option *Absolute Accuracy* is integrated in the controller algorithms and does not need external equipment or calculation.



Note

The performance data is applicable to the corresponding RobotWare version of the individual robot.



xx100000488

What is included

Every *Absolute Accuracy* robot is delivered with:

- compensation parameters saved on the robot's serial measurement board
- a birth certificate representing the *Absolute Accuracy* measurement protocol for the calibration and verification sequence.

Continues on next page

A robot with *Absolute Accuracy* calibration has a label with this information on the manipulator.

Absolute Accuracy supports floor mounted, wall mounted and ceiling mounted installations. Compensation parameters saved in the robot's serial measurement board differ depending on which Absolute Accuracy option is selected.

When is *Absolute Accuracy* being used

Absolute Accuracy works on a robot target in Cartesian coordinates, not on the individual joints. Therefore, joint based movements (e.g. `MoveAbsJ`) will not be affected.

If the robot is inverted, the Absolute Accuracy calibration must be performed when the robot is inverted.

Absolute Accuracy active

Absolute Accuracy will be active in the following cases:

- Any motion function based on robtargets (e.g. `MoveL`) and ModPos on robtargets
- Reorientation jogging
- Linear jogging
- Tool definition (4, 5, 6 point tool definition, room fixed TCP, stationary tool)
- Work object definition

Absolute Accuracy not active

The following are examples of when Absolute Accuracy is not active:

- Any motion function based on a jointtarget (`MoveAbsJ`)
- Independent joint
- Joint based jogging
- Additional axes
- Track motion



Note

In a robot system with, for example, an additional axis or track motion, the Absolute Accuracy is active for the manipulator but not for the additional axis or track motion.

RAPID instructions

There are no RAPID instructions included in this option.

Production data

Typical production data regarding calibration are:

Robot	Positioning accuracy (mm)		
	Average	Max	% Within 1 mm
IRB 6650S-125/3.50 IRB 6650S-200/3.00	0.50	1.20	97

Continues on next page

1 Description

1.4.3 Absolute Accuracy calibration

Continued

Robot	Positioning accuracy (mm)		
	Average	Max	% Within 1 mm
IRB 6650S-90/3.9	a	a	a

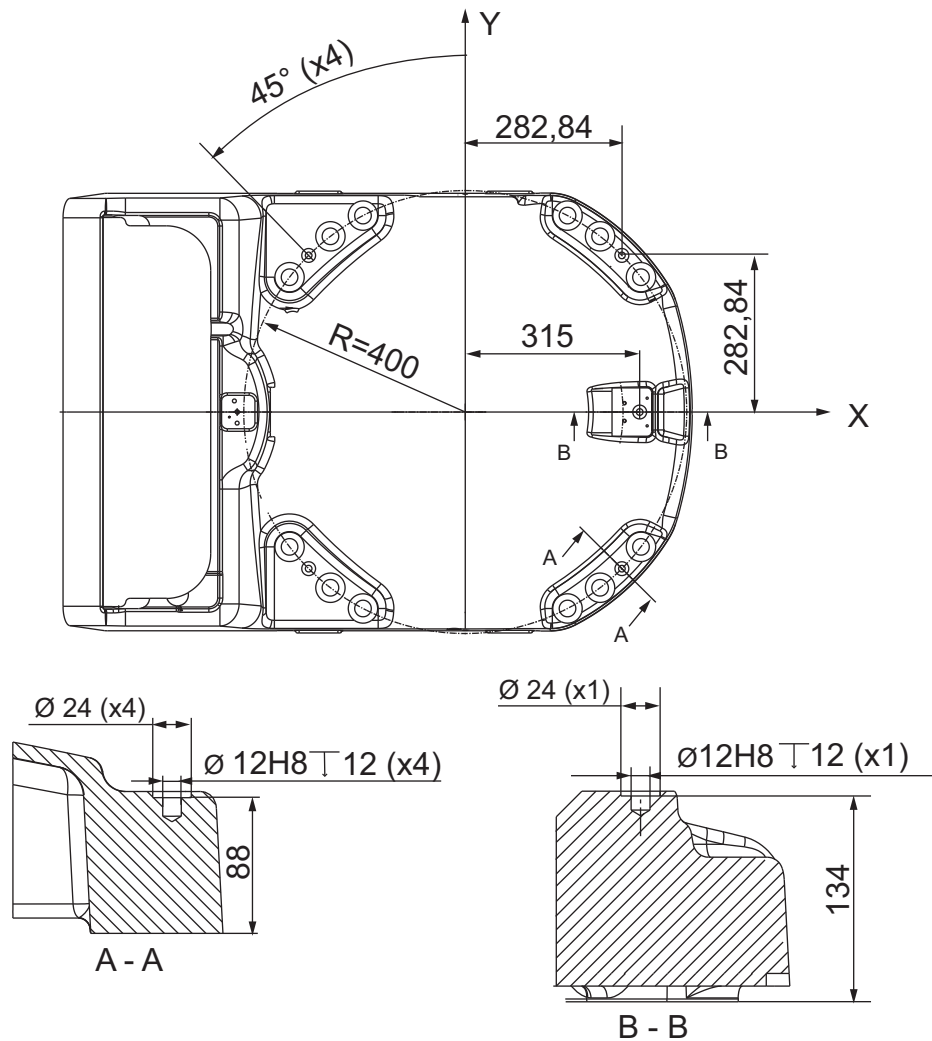
a. For detailed data and data missing in the table, please contact ABB for more information.

1.4.4 Robot references

Base

The holes shown in figure below are used for measuring the robot position when integrated in a production cell.

The holes are not available for option Foundry Plus.



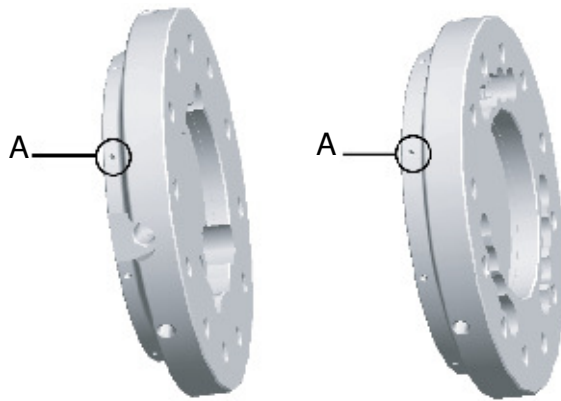
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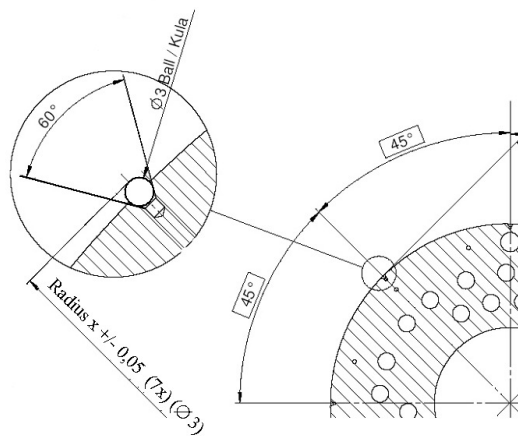
1 Description

1.4.4 Robot references

Continued



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Robot	Radius X (mm) for references on tool flange
IRB 6650S-90/3.90	R=87,5
IRB 6650S-125/3.50	
IRB 6650S-200/3.00	

1.5 Load diagrams

1.5.1 Introduction to Load diagrams

Information



WARNING

It is very important to always define correct actual load data and correct payload of the robot. Incorrect definitions of load data can result in overloading of the robot.

If incorrect load data is used, and/or if loads outside the load diagram are used, the following parts can be damaged due to overload:

- motors
- gearboxes
- mechanical structure



WARNING

In RobotWare, the service routine LoadIdentify can be used to determine correct load parameters. The routine automatically defines the tool and the load. See *Operating manual - IRC5 with FlexPendant*, for detailed information.



WARNING

Robots running with incorrect load data and/or with loads outside the load diagram, will not be covered by robot warranty.

General

The load diagrams include a nominal payload inertia, J_0 of 15 kgm^2 , and an extra load of 50 kg at the upper arm housing.

At different moment of inertia the load diagram will be changed. For robots that are allowed tilted, wall or inverted mounted, the load diagrams as given are valid and thus it is also possible to use RobotLoad within those tilt and axis limits.

Continues on next page

1 Description

1.5.1 Introduction to Load diagrams

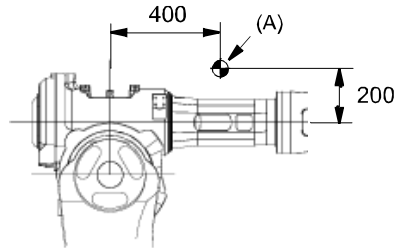
Continued

Control of load case with RobotLoad

To verify a specific load case, use the RobotStudio add-in RobotLoad.

The result from RobotLoad is only valid within the maximum loads and tilt angles.

There is no warning if the maximum permitted arm load is exceeded. For over-load cases and special applications, contact ABB for further analysis.

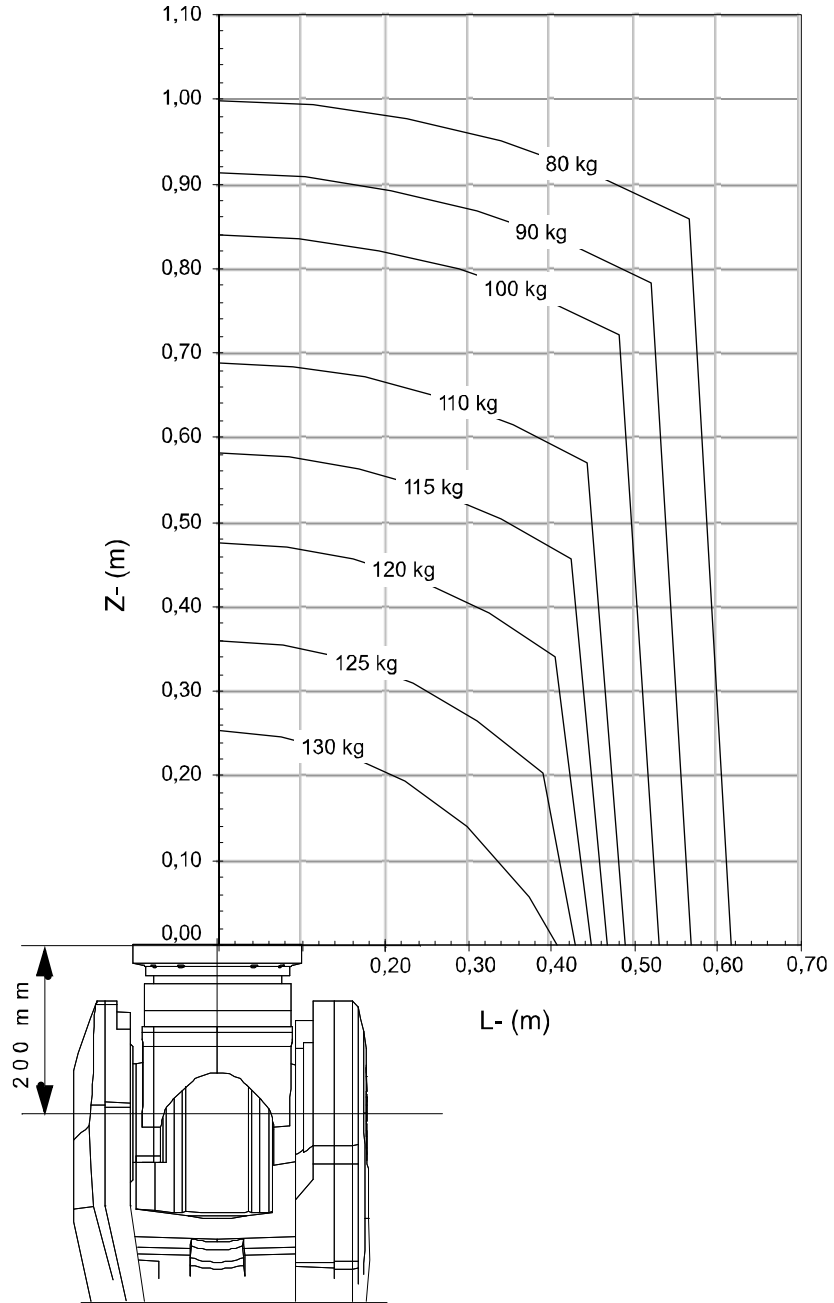


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Pos	Description
A	Center of gravity 50 kg

1.5.2 Load diagrams

IRB 6650S-125/3.5



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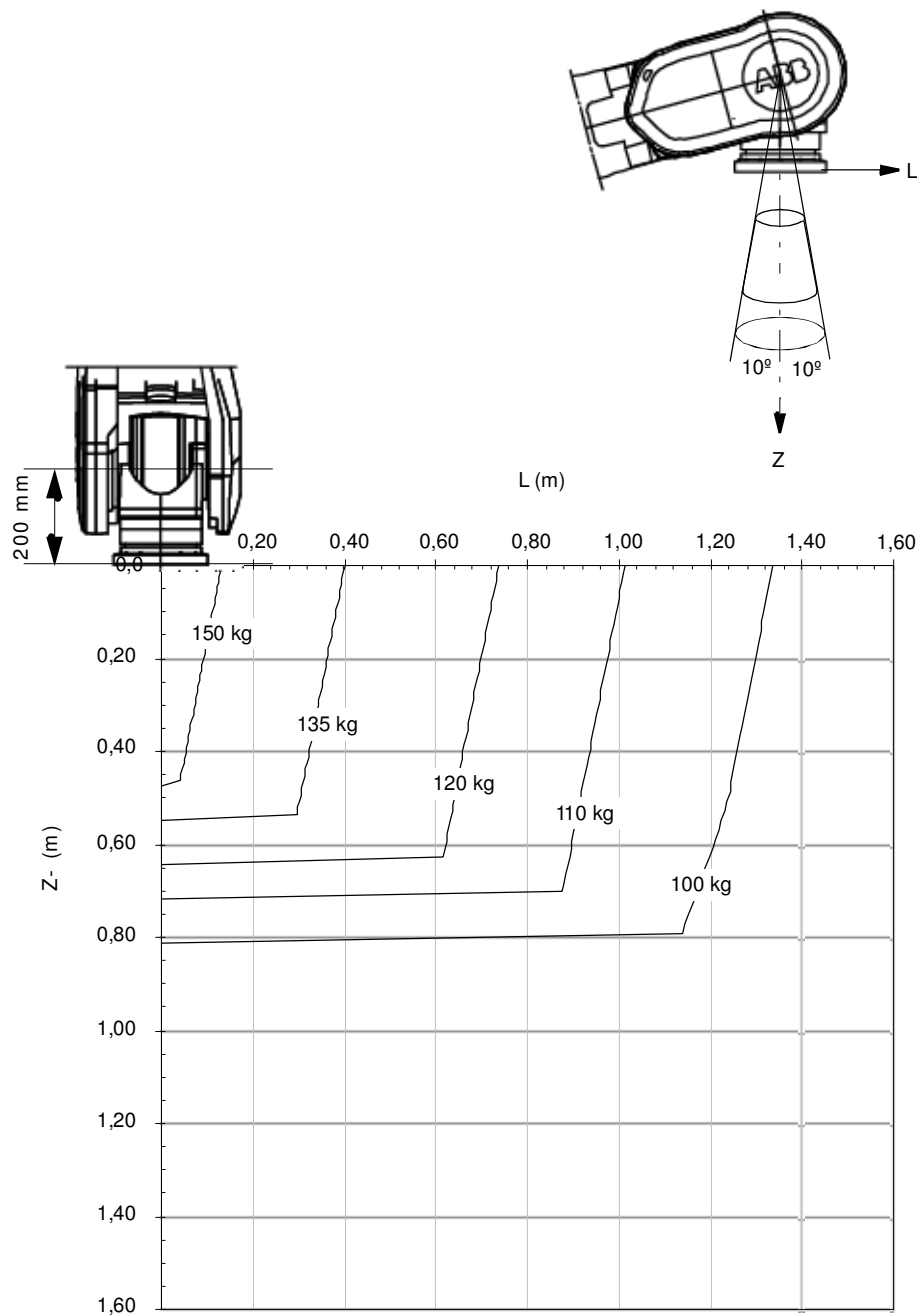
Continues on next page

1 Description

1.5.2 Load diagrams

Continued

IRB 6650S-125/3.5 "Vertical Wrist" ($\pm 10^\circ$)



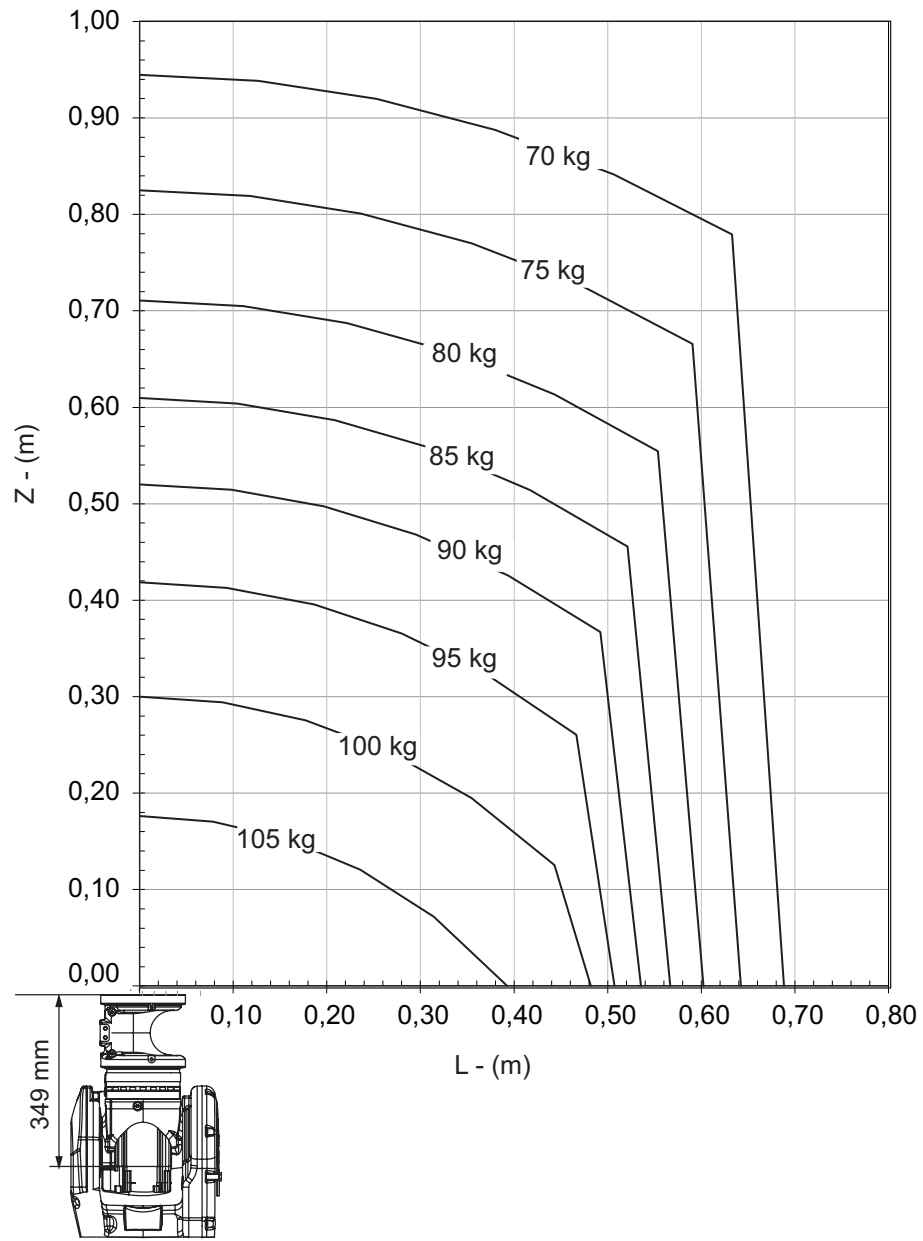
xx1000000550

For wrist down (0° deviation from the vertical line).

	Description
Max load	150 kg
Z _{max}	0,462 m
L _{max}	0,156 m

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IRB 6650S-125/3.5 LeanID, option 780-4



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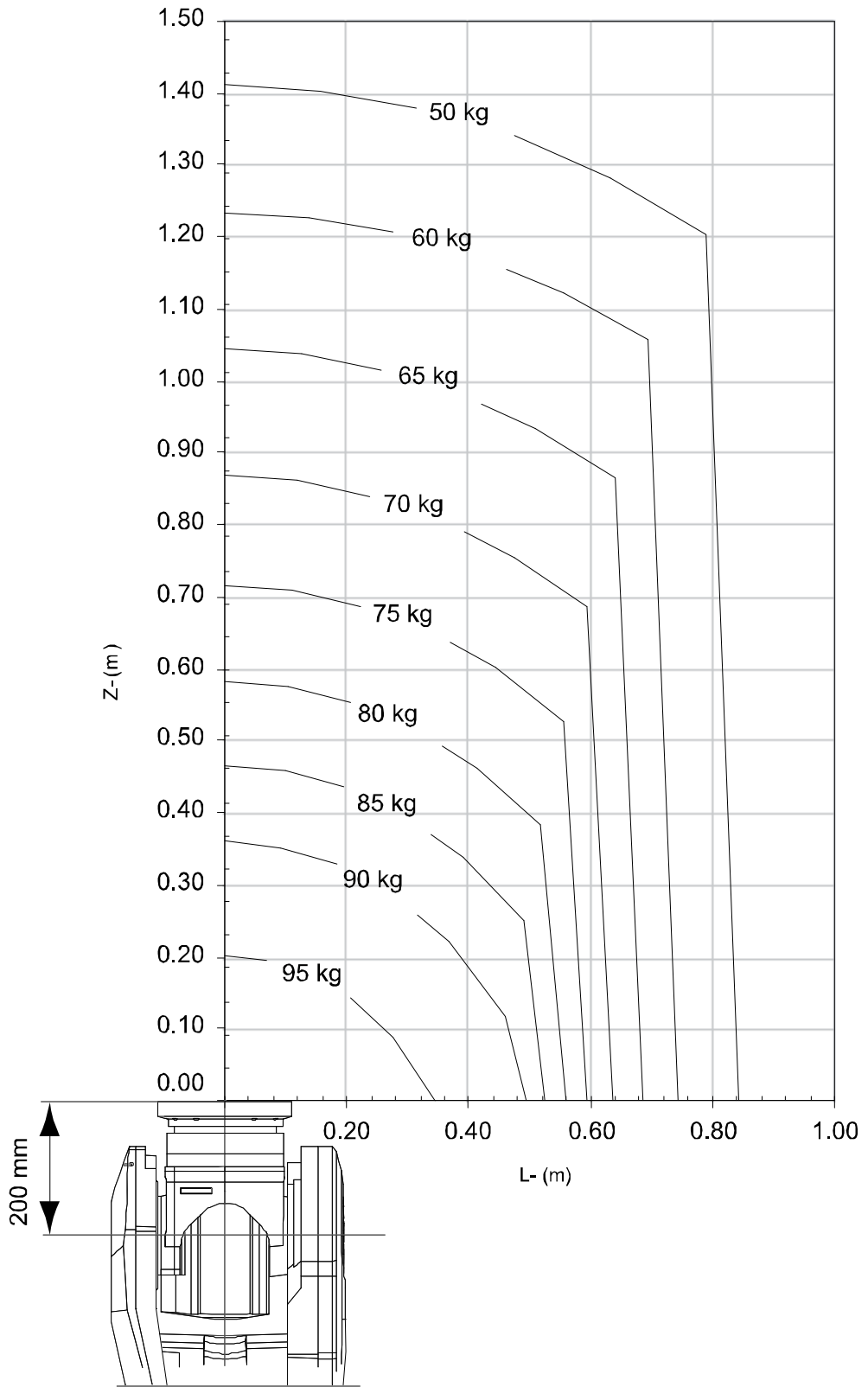
Continues on next page

1 Description

1.5.2 Load diagrams

Continued

IRB 6650S-90/3.9



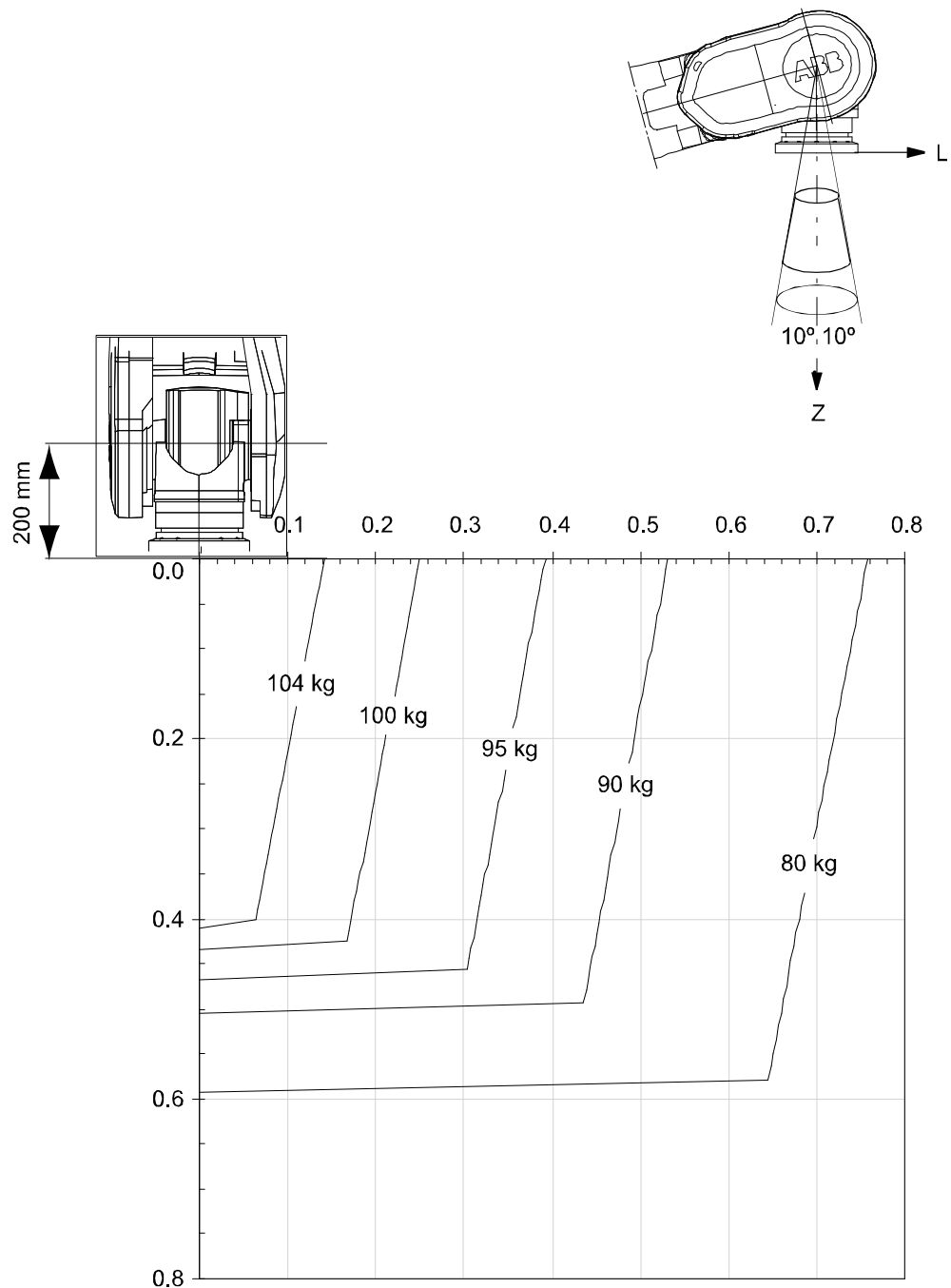
xx100000549

Continues on next page

1 Description

1.5.2 Load diagrams Continued

IRB 6650S-90/3.9 "Vertical Wrist" ($\pm 10^\circ$)



xx1000000551

For wrist down (0° deviation from the vertical line).

	Description
Max load	107 kg
Z _{max}	0,2 m
L _{max}	0,1 m

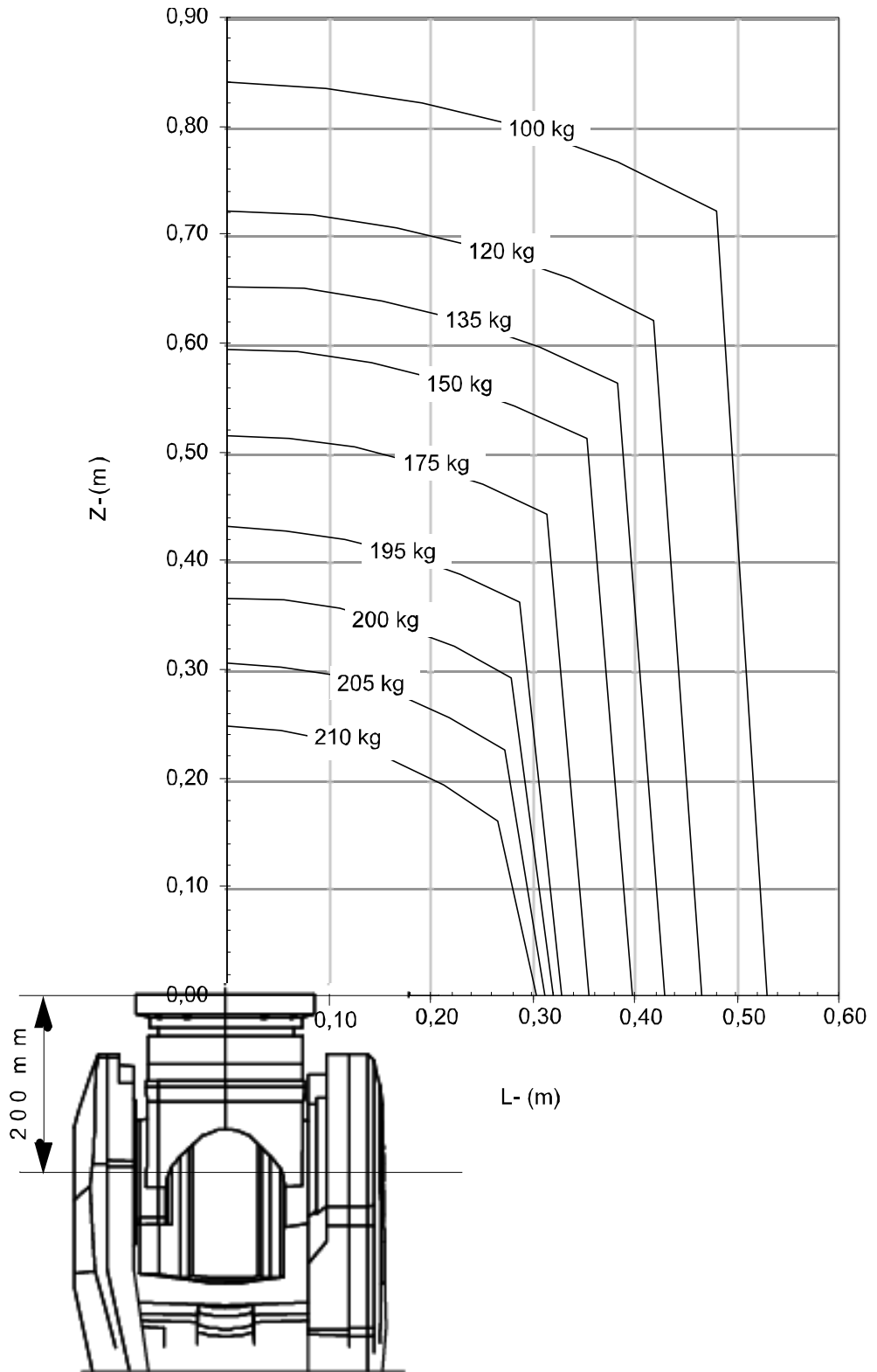
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1 Description

1.5.2 Load diagrams

Continued

IRB 6650S-200/3.0



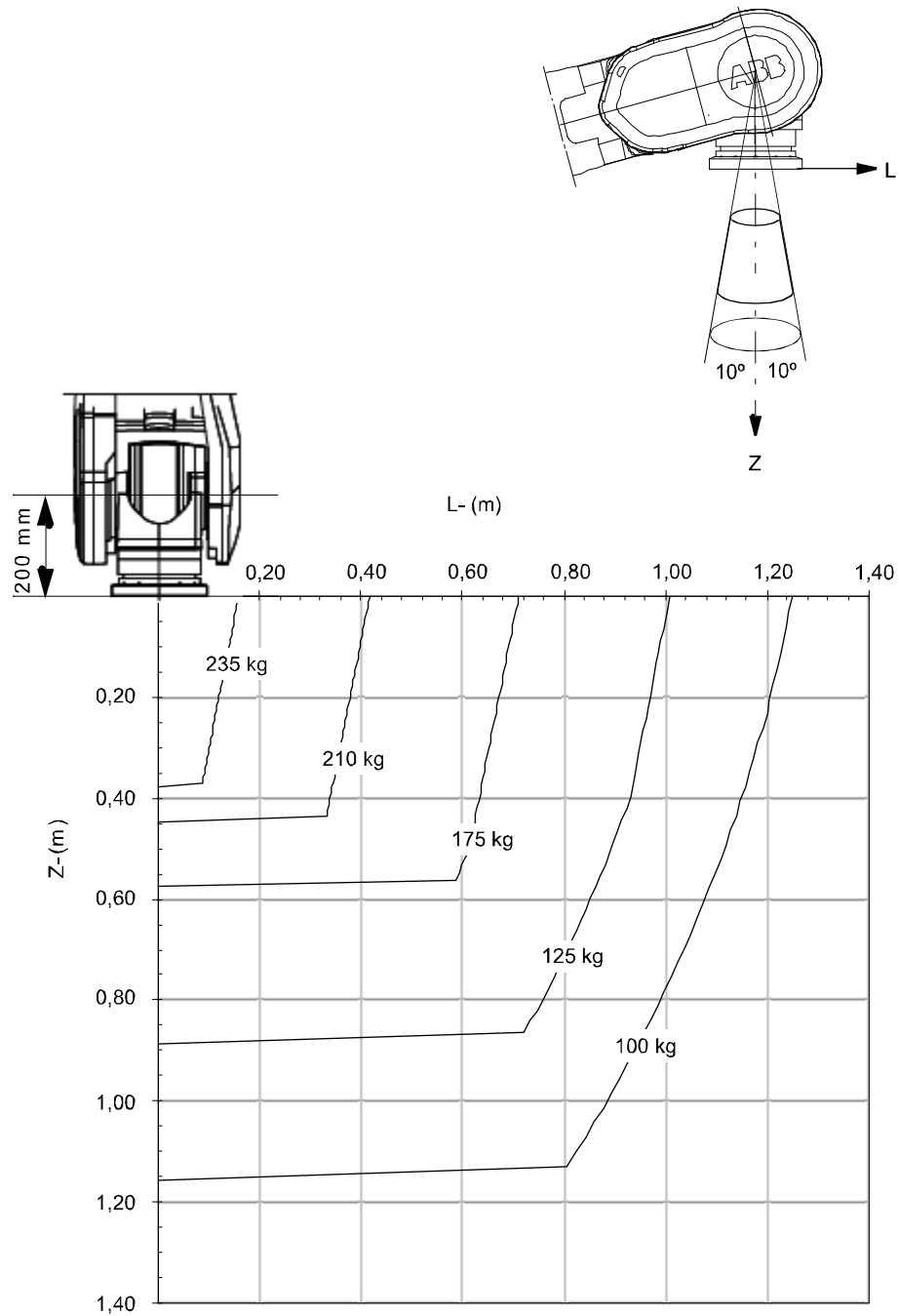
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Continues on next page

1 Description

1.5.2 Load diagrams Continued

IRB 6650S-200/3.0" Vertical Wrist" ($\pm 10^\circ$)



xx100000552

For wrist down (0° deviation from the vertical line).

	Description
Max load	245 kg
Z _{max}	0,345 m
L _{max}	0,098 m

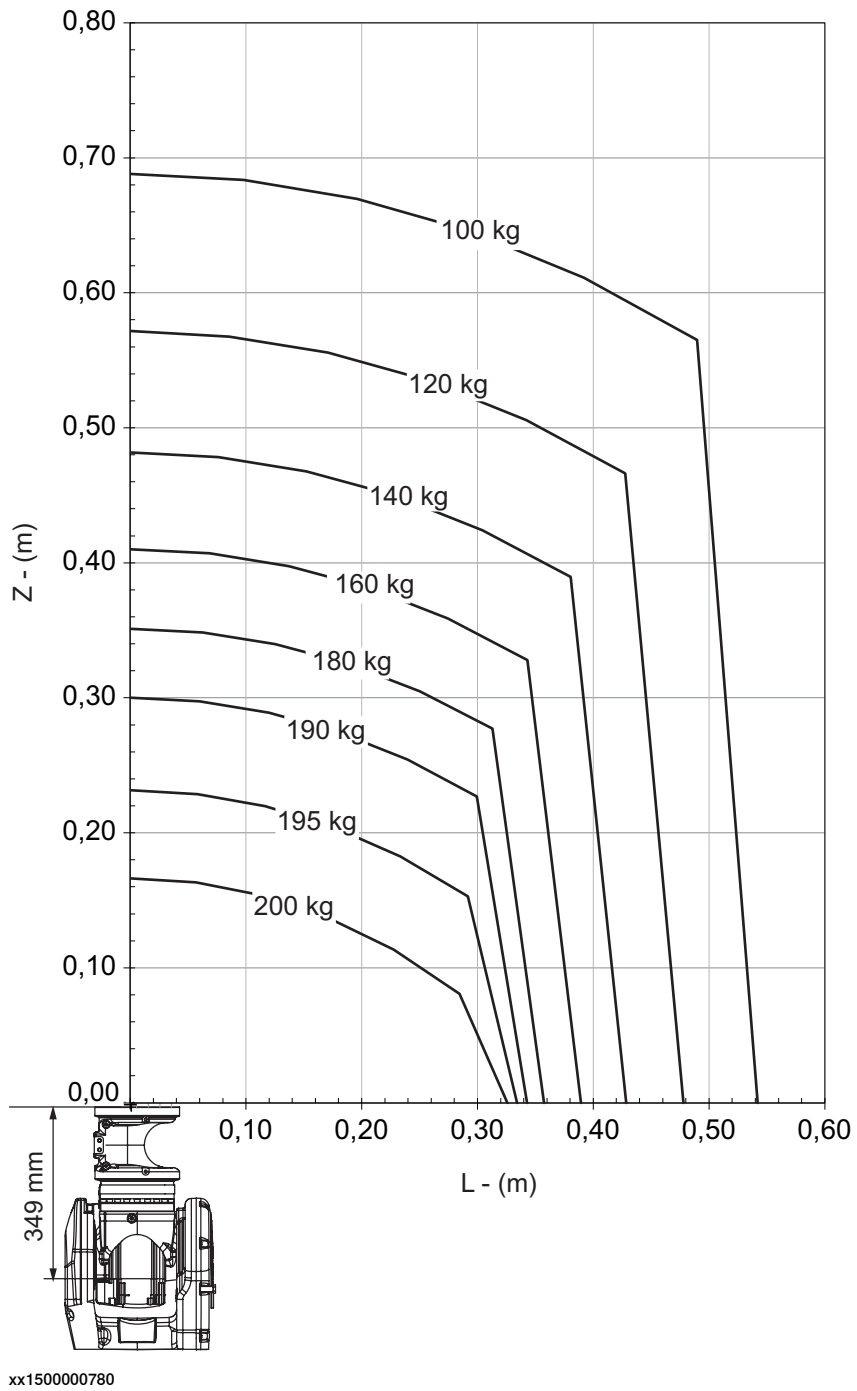
Continues on next page

1 Description

1.5.2 Load diagrams

Continued

IRB 6650S-200/3.0 LeanID, option 780-4



1.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement

1.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement

Note



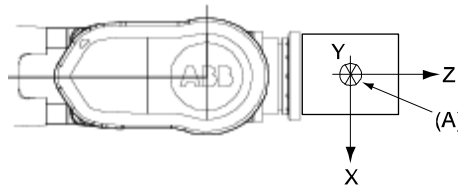
Note

Total load given as: Mass in kg, center of gravity (Z and L) in meter and moment of inertia (J_{0x} , J_{0y} , J_{0z}) in kgm^2 . $L = \sqrt{X^2 + Y^2}$, see Figure below.

Full movement of axis 5 ($\pm 120^\circ$)

Axis	Robot Type	Maximum moment of inertia
5	125/3.5, 200/3.0 and 90/3.9	$Ja5 = \text{Load} \times ((Z + 0,200^i)^2 + L^2) + \max(J_{0x}, J_{0y}) \leq 250 \text{ kgm}^2$
6	125/3.5, 200/3.0 and 90/3.9	$Ja6 = \text{Load} \times L^2 + J_{0z} \leq 185 \text{ kgm}^2$

ⁱ For option 780-4, LeanID=0,349 m



xx0900000774

Pos	Description
A	Center of gravity
	Description
J_{0x} , J_{0y} , J_{0z}	Max. moment of inertia around the X, Y and Z axes at center of gravity.

Limited axis 5, center line down

Axis	Robot Type	Maximum moment of inertia
5	125/3.5, 200/3.0 and 90/3.9	$Ja5 = \text{Load} \times ((Z + 0,200^i)^2 + L^2) + \max(J_{0x}, J_{0y}) \leq 275 \text{ kgm}^2$
6	125/3.5, 200/3.0 and 90/3.9	$Ja6 = \text{Load} \times L^2 + J_{0z} \leq 250 \text{ kgm}^2$

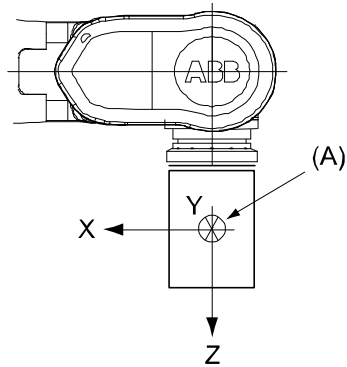
ⁱ For option 780-4, LeanID=0,349 m

Continues on next page

1 Description

1.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement

Continued



xx0900000775

Pos	Description
A	Center of gravity
	Description
J_{ox}, J_{oy}, J_{oz}	Max. moment of inertia around the X, Y and Z axes at center of gravity.

1.5.4 Wrist torque

General

The table below shows the maximum permissible torque due to payload.



Note

The wrist torque values are for reference only, and should not be used for calculating permitted load offset (position of center of gravity) within the load diagram, since those also are limited by main axes torques as well as dynamic loads. Furthermore, arm loads will influence the permitted load diagram. To find the absolute limits of the load diagram, use the RobotStudio add-in RobotLoad.

Robot type	Max wrist torque axis 4 and 5	Max wrist torque axis 6	Max torque valid at load
IRB 6650S-200/3.0	1264 Nm	625 Nm	192 kg
IRB 6650S-125/3.5	1037 Nm	526 Nm	105 kg
IRB 6650S-90/3.9	495 Nm	438 Nm	60 kg

1 Description

1.5.5 Maximum TCP acceleration

1.5.5 Maximum TCP acceleration

General

Higher values can be reached with lower loads than the nominal because of our dynamical motion control QuickMove2. For specific values in the unique customer cycle, or for robots not listed in the table below, we recommend then to use RobotStudio.

Maximum Cartesian design acceleration for nominal loads

Robot type	E-stop Max acceleration at nominal load COG [m/s ²]	Controlled Motion Max acceleration at nominal load COG [m/s ²]
IRB 6650S - 200/3.0	53	21
IRB 6650S - 125/3.5	60	25
IRB 6650S - 90/3.9	48	31



Note

Acceleration levels for emergency stop and controlled motion includes acceleration due to gravitational forces. Nominal load is defined with nominal mass and cog with max offset in Z and L (see the load diagram).

1.6 Mounting equipment

1.6.1 Introduction

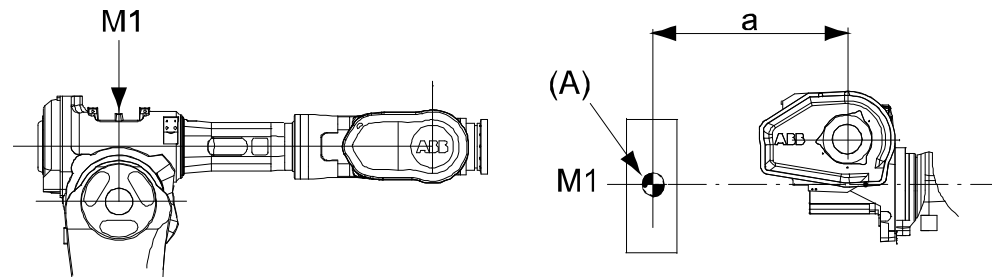
General

Extra loads can be mounted on the upper arm housing, the lower arm, and on the frame. Definitions of distances and masses are shown in the next two Figures. The robot is supplied with holes for mounting extra equipment (see Figure in next chapter). Maximum allowed arm load depends on center of gravity of arm load and robot payload.

Upper arm

Allowed extra load on upper arm housing plus the maximum handling weight(see Figure below):

$M1 \leq 50 \text{ kg}$ with distance $a \leq 500 \text{ mm}$, center of gravity in axis 3 extension.



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Pos	Description
A	Mass center

Continues on next page

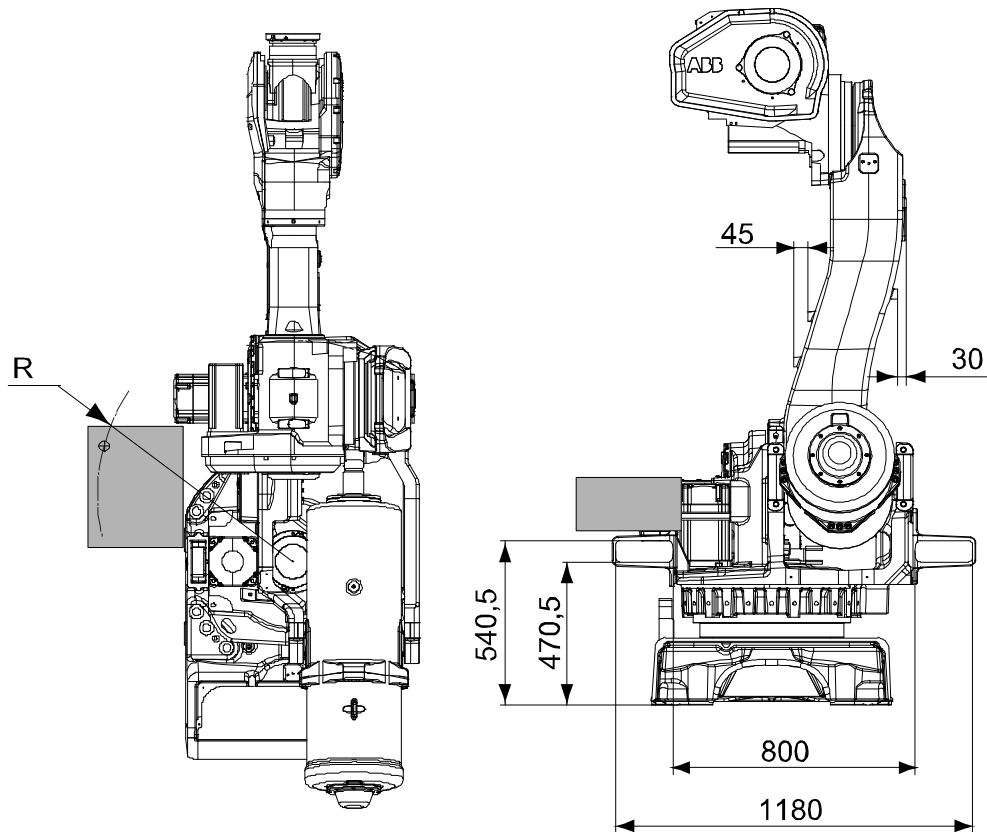
1 Description

1.6.1 Introduction

Continued

Frame (Hip Load)

	Description
Permitted extra load on frame	$J_H = 200 \text{ kgm}^2$
Recommended position (see Figure below)	$J_H = J_{H0} + M4 \times R^2$ where: J_{H0} is the moment of inertia of the equipment R is the radius (m) from the center of axis 1 $M4$ is the total mass (kg) of the equipment including bracket and harness ($\leq 500 \text{ kg}$)



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Pos	Description
A	View from above
B	View from the rear

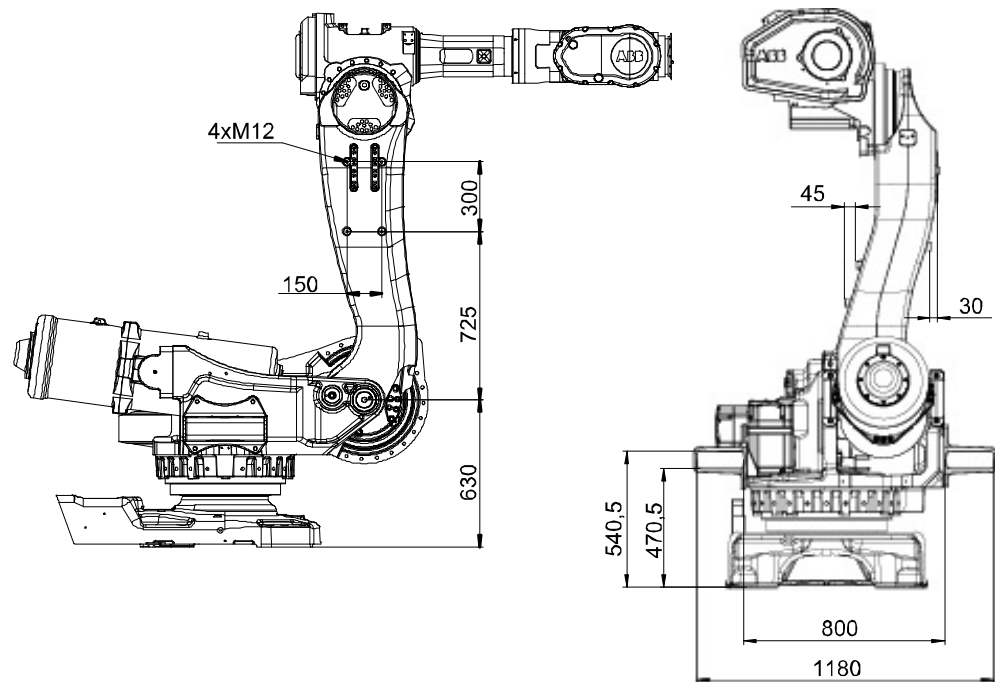
1.6.2 Mounting of hip load

General

The extra load can be mounted on the frame. Holes for mounting see next two Figures. When mounting on the frame all four holes (2x2, Ø 16) on one side must be used.

If loads exceeding 50 kg is required on lower arm, use the calculation program ABB RobotLoad, please contact your local ABB organization.

6650S



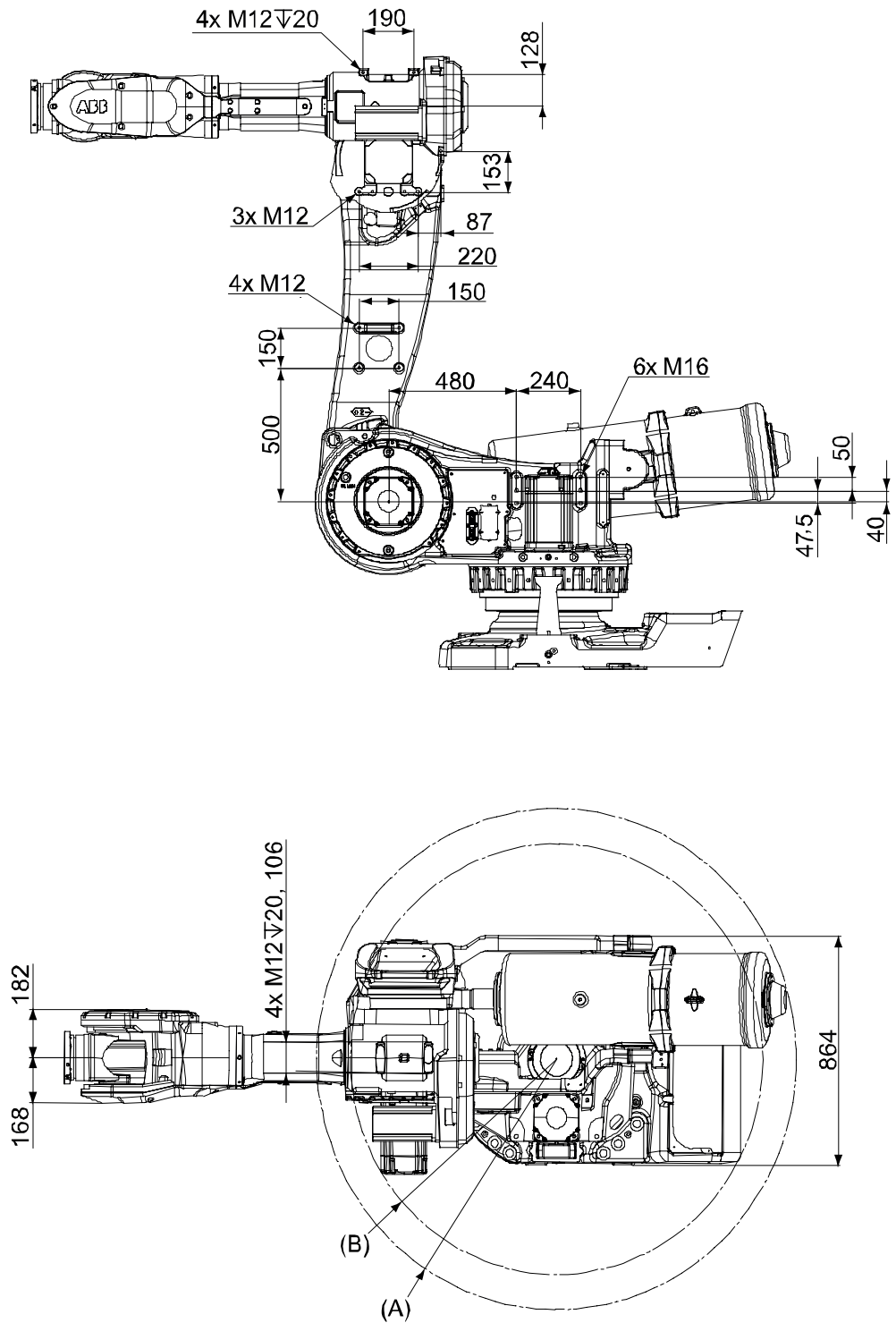
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1 Description

1.6.2 Mounting of hip load

Continued

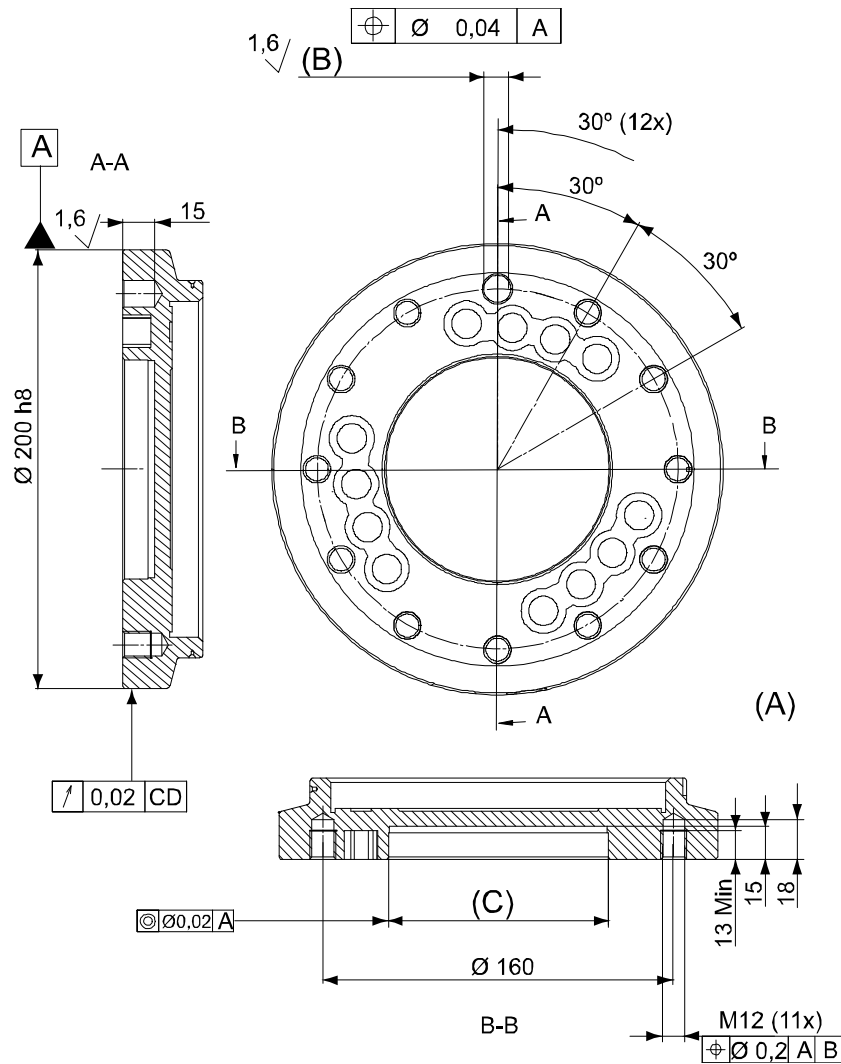


xx1000000498

Pos	Description
A	R 946 (Rear side, Balancing device)
B	R 813 (Front side, Motor axis 2)

Continues on next page

Tool flange also valid for LeanID.



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Pos	Description
A	Minimum thread length for screws in M12-hole is 9 mm.
B	$\varnothing 12\ H7$ Depth 15
C	$\varnothing 100\ H7$ Depth 8 min

Fastener quality

When fitting tools on the tool flange, only use screws with quality 12.9. For other equipment use suitable screws and tightening torque for your application.

1 Description

1.7.1 Introduction

1.7 Maintenance and troubleshooting

1.7.1 Introduction

General

The robot requires only minimum maintenance during operation. It has been designed to make it as easy to service as possible:

- Maintenance-free AC motors are used.
- Oil is used for the gear boxes.
- The cabling is routed for longevity, and in the unlikely event of a failure, its modular design makes it easy to change.

Maintenance

The maintenance intervals depend on the use of the robot, the required maintenance activities also depends on selected options. For detailed information on maintenance procedures, see Maintenance section in the Product Manual.

1.8 Robot motion

1.8.1 Introduction

Type of Motion

Axis	Type of motion	Range of movement, IRB 6650S
1	Rotation Motion	+ 180° to - 180° + 220° to - 220° (option)
2	Arm motion	+ 160° to - 40°
3	Arm motion	+ 70° to - 180°
4	Wrist motion	+ 300° to - 300°
5	Bend motion	+ 120° to - 120°
6	Turn motion	+ 360° to - 360° default ± 96 Rev ⁱ Max. ⁱⁱ

ⁱ Rev. = Revolutions

ⁱⁱ The default working range for axis 6 can be extended by changing parameter values in the software. Option 610-1 "Independent axis" can be used for resetting the revolution counter after the axis has been rotated (no need for "rewinding" the axis).

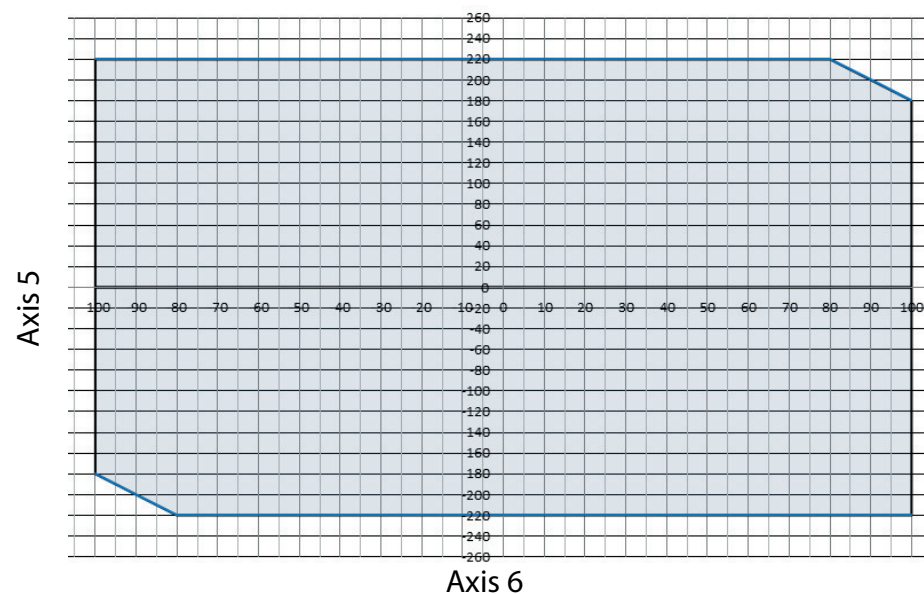


Note

Note! For limitation of range of motion in combination with DressPack see [Introduction on page 55](#).

Working range axis 5 and 6 for LeanID, option 780-4

Allowed working area for axis 6 related to axis 5 position is shown in the figure below.



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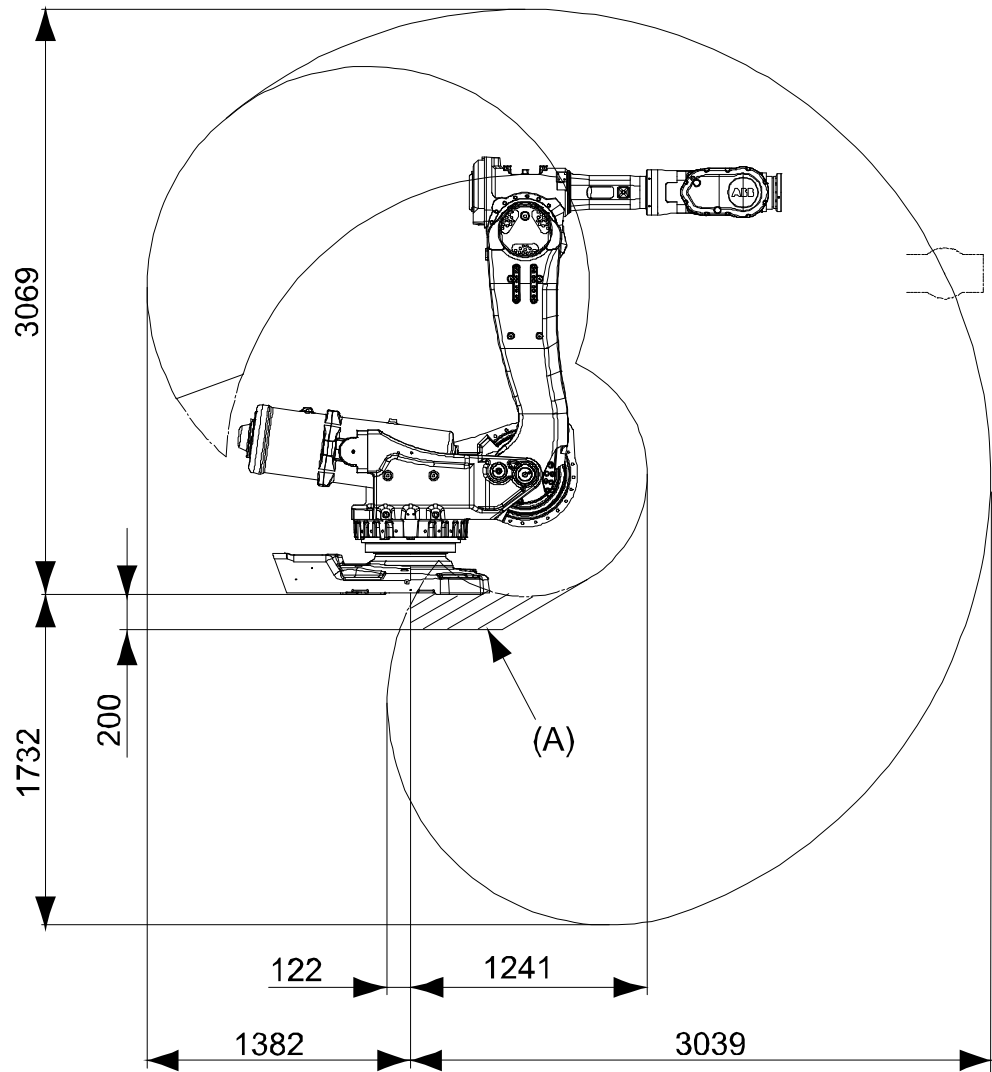
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1 Description

1.8.1 Introduction

Continued

Robot Type	Handling capacity (kg)	Reach (m)
IRB 6650S	200	3.0



xx1000000500

Pos	Description
A	Marked area not available under the robot base.

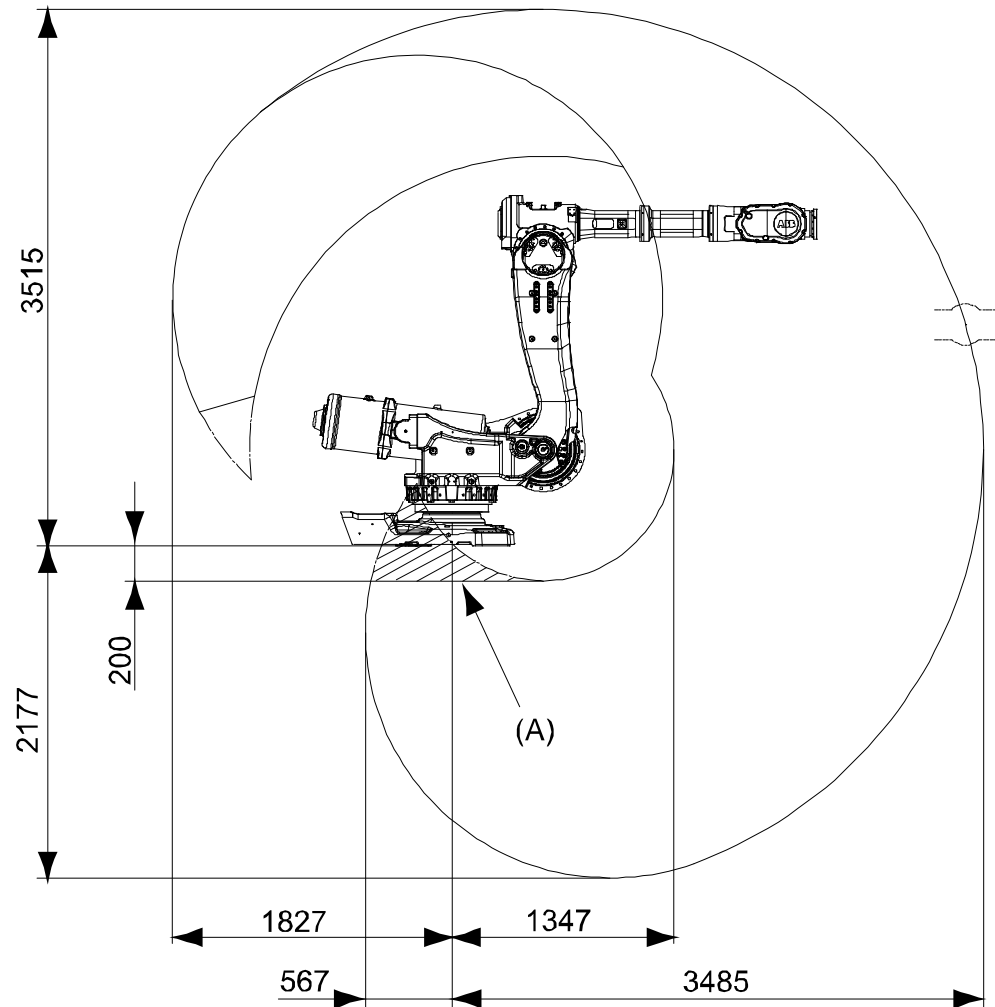
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1 Description

1.8.1 Introduction

Continued

Robot Type	Handling capacity (kg)	Reach (m)
IRB 6650S	125	3.5



xx100000502

Pos	Description
A	Marked area not available under the robot base.

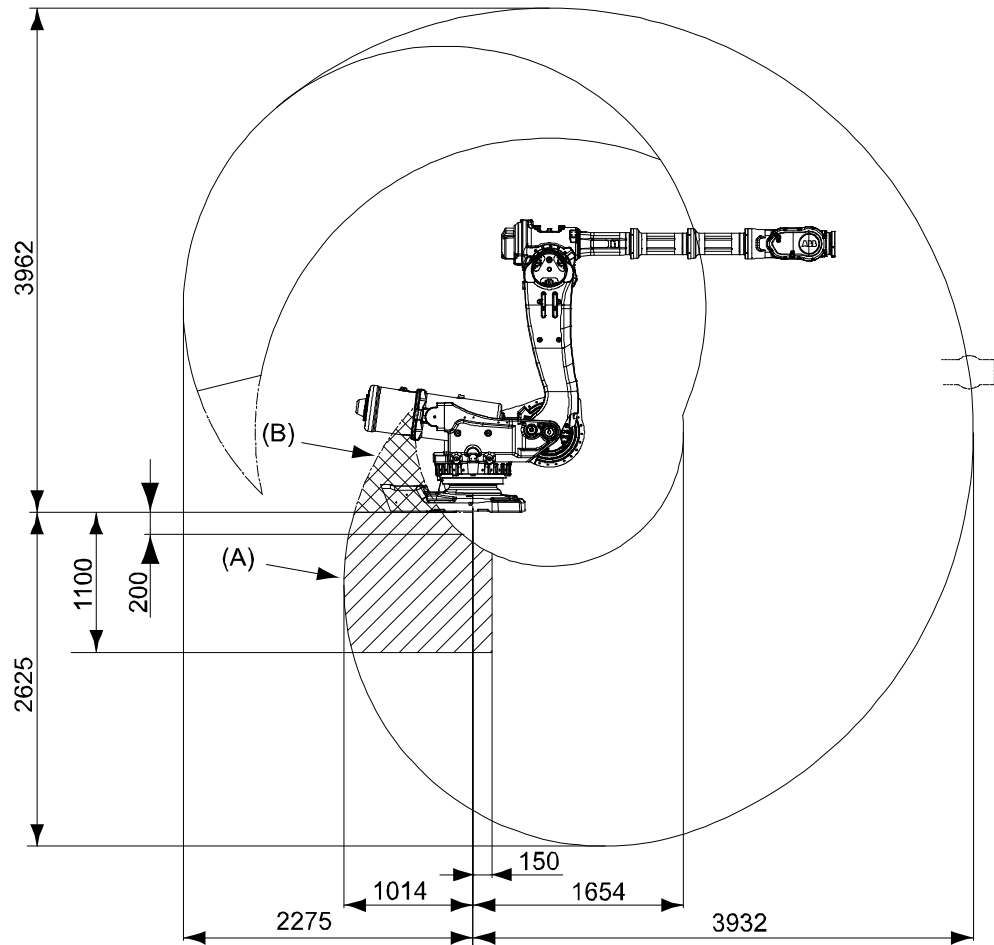
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1 Description

1.8.1 Introduction

Continued

Robot Type	Handling capacity (kg)	Reach (m)
IRB 6650S	90	3.9



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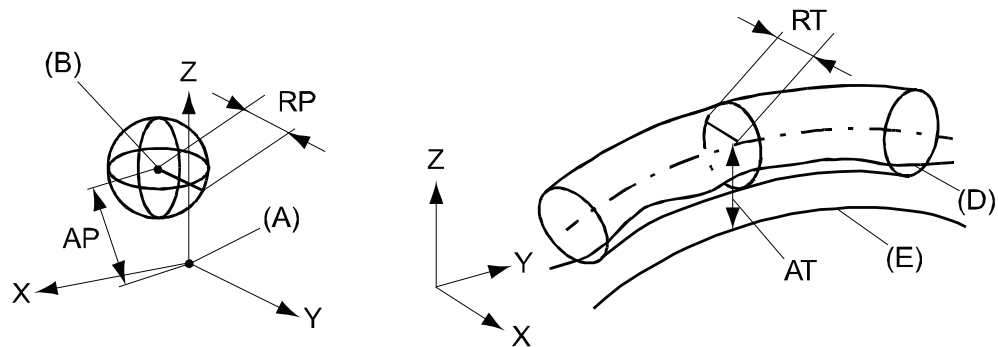
Pos	Description
A and B	Marked area, max. payload 50 kg
B	Marked area not available under the robot base

1.8.2 Performance according to ISO 9283

General

At rated maximum load, maximum offset and 1.6 m/s velocity on the inclined ISO test plane, with all six axes in motion. Values in the table below are the average result of measurements on a small number of robots. The result may differ depending on where in the working range the robot is positioning, velocity, arm configuration, from which direction the position is approached, the load direction of the arm system. Backlashes in gearboxes also affect the result.

The figures for AP, RP, AT and RT are measured according to figure below.



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Pos	Description	Pos	Description
A	Programmed position	E	Programmed path
B	Mean position at program execution	D	Actual path at program execution
AP	Mean distance from programmed position	AT	Max deviation from E to average path
RP	Tolerance of position B at repeated positioning	RT	Tolerance of the path at repeated program execution

IRB 6650S	125/3.5	200/3.0	90/3.9
Pose accuracy, AP ^a (mm)	0.16	0.13	b
Pose repeatability, RP (mm)	0.13	0.14	b
Pose stabilization time, PSt (s) within 0.4 mm of the position	0.33	0.18	b
Path accuracy, AT (mm)	2.58	2.98	b
Path repeatability, RT(mm)	0.90	0.70	b

a. AP according to the ISO test above, is the difference between the taught position (position manually modified in the cell) and the average position obtained during program execution.

b. The values for IRB 6650S-90/3.9 are not available.

The above values are the range of average test results from a number of robots.

1 Description

1.8.3 Velocity

1.8.3 Velocity

Maximum axis speeds

Robot Type	Axis 1	Axis 2	Axis 3	Axis 4	Axis 5	Axis 6
IRB 6650S-90/3.9	100 °/s	90 °/s	90 °/s	150 °/s	120 °/s	235 °/s
IRB 6650S-125/3.5	110 °/s	90 °/s	90 °/s	150 °/s	120 °/s	235 °/s
IRB 6650S-200/3.0	100 °/s	90 °/s	90 °/s	150 °/s	120 °/s	190 °/s

There is a supervision function to prevent overheating in applications with intensive and frequent movements.

1.8.4 Robot stopping distances and times

Introduction

The stopping distances and times for category 0 and category 1 stops, as required by EN ISO 10218-1 Annex B, are listed in *Product specification - Robot stopping distances according to ISO 10218-1 (3HAC048645-001)*.

1 Description

1.9.1 Introduction

1.9 Cooling fan for axis 1 and 2 motor

1.9.1 Introduction

Option 87-1, 88-1

To be used to avoid overheating of motors and gears in applications with intensive motion (high average speed and /or high average torque and/or short wait time) of axis 1 and/or axis 2.

Valid protection for cooling fan is IP54. Fan failure stops the robot. The option is not allowed to select when the robot is placed on a track motion, IRBT.

To determine the use of cooling fans for axis 1 and/or axis 2 motor use the “Gearbox Heat Prediction Tool” in RobotStudio. Reliable facts for the decision of need for fan or not will be achieved by entering the ambient temperature for a specific cycle. Please contact your local ABB organization.

1.10 Servo gun

1.10.1 Introduction

General

The robot can be supplied with hardware and software for control of the following configurations:

- Stationary Gun
- Robot Gun
- Robot Gun and Track Motion
- Track motion

The specific parts related to the servo motor control for electrical welding guns and for track motion configurations are shown in the conceptual pictures below. The major parts and required options are also stated in the configurations lists below each picture.

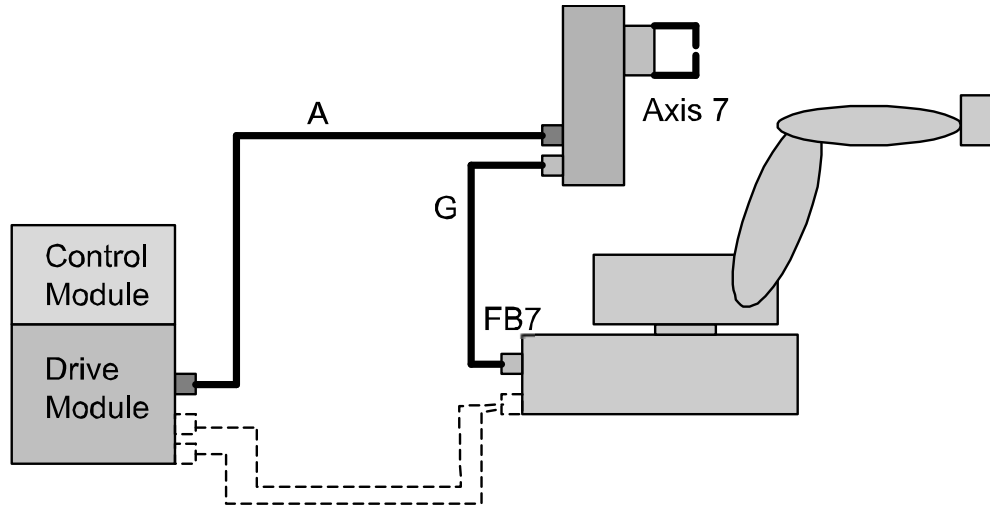
The cables for control of the basic robot are shown in the pictures with dotted lines.

1 Description

1.10.2 Stationary Gun

1.10.2 Stationary Gun

General



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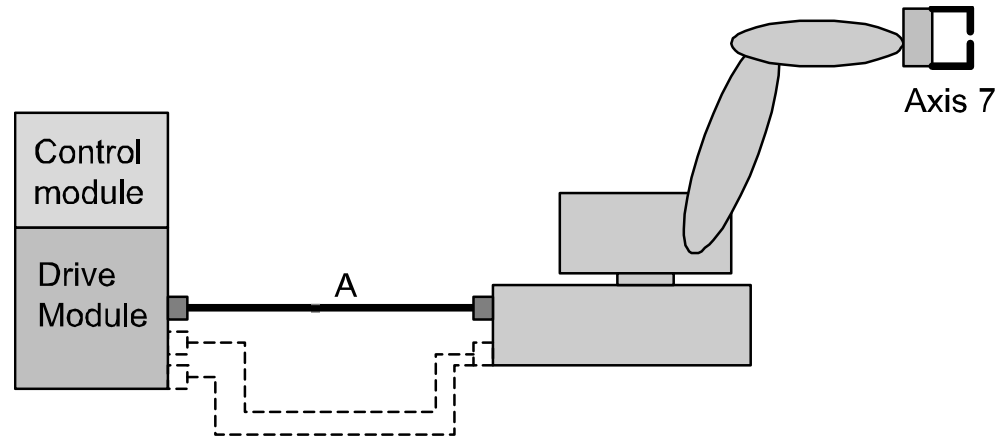
Options

Options according to the table below are required to complete the delivery. For further details on each option see corresponding Product specification.

Option	Description	Product specification
785-5	Stationary gun. This option includes: Cable G (7 m length) for resolver signals from robot base (FB7) to stationary gun/axis 7.	
770-4	First additional drive. Drive unit for 7th axis with corresponding cables assembled inside Drive Module.	Controller IRC5 with FlexPendant
786-1,-2,-3,-4	Connection to first drive. Cable A (7-30 m) between Drive Module and stationary gun/axis 7 for servo drive power.	
635-3, -4 or -5	Spot Servo, Spot Servo Multiple Guns or Spot Servo Equalizing.	Controller software IRC5

1.10.3 Robot Gun

General



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Options

Options according to table below are required to complete the delivery. For further details on each option see corresponding Product specification.

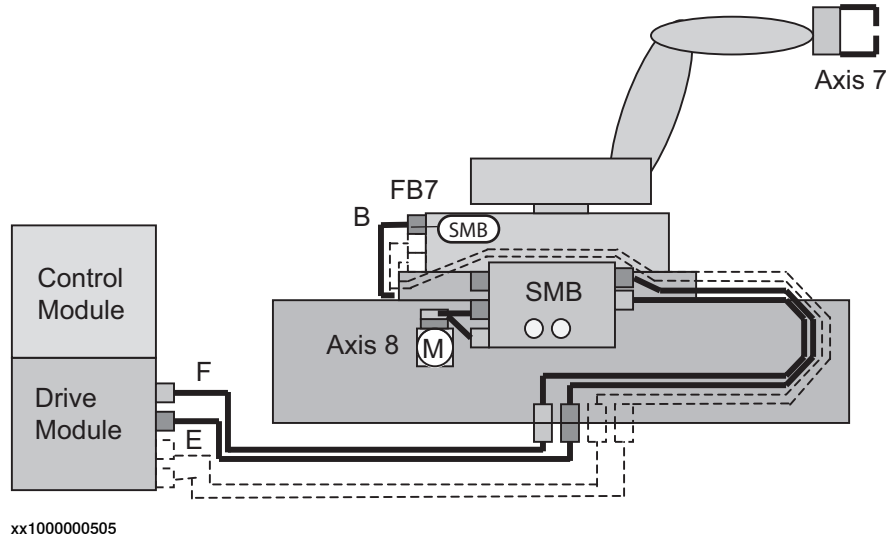
Option	Description	Product specification
785-1	Robot gun. This option includes: Cables within manipulator for servo power signals (servo gun/axis 7).	
770-4	First additional drive. Drive unit for 7th axis with corresponding cables assembled inside Drive Module.	Controller IRC5 with FlexPendant
786-1,-2,-3,-4	Connection to first drive. Cable A (7-30 m) between Drive Module and robot base for servo drive power.	
635-3, -4 or -5	Spot Servo, Spot Servo Multiple Guns or Spot Servo Equalizing.	Controller software IRC5

1 Description

1.10.4 Robot Gun and Track Motion IRBT 6004

1.10.4 Robot Gun and Track Motion IRBT 6004

General



Options

Options according to table below are required to complete the delivery. For further details on each option see corresponding Product specification.

Option	Description	Product specification
785-1+1002-2 ⁱ	Robot Gun - Track Motion. This option includes: Cables within manipulator for servo power signals (servo gun/axis 7).	Track motion IRBT 6004 + IRB 6600
Track motion delivery includes	Serial measurement box (SMB2, Split box) for distribution of servo power to axis 8. The box is placed on the track motion. Cables from serial measurement box to track motion. Cable B for servo power (1,5 m length). Connection to first and second drive. Cable E and F (7-22 m) between Drive Module and serial measurement box for dual servo drive power/resolver signals.	Track motion IRBT 6004/IRBT 7004
907-1	First additional drive. Drive unit for 7th axis with corresponding cables assembled inside Drive Module.	Controller IRC5 with FlexPendant
907-1	Second additional drive. Drive unit for 8th axis with corresponding cables assembled inside Drive Module.	Controller IRC5 with FlexPendant
635-3, -4 or -5	Spot Servo, Spot Servo Multiple Guns or Spot Servo Equalizing.	Controller software IRC5
864-1	Resolver connection, axis 7, on base (FB7).	

ⁱ To specify robot on track equipped with servo gun. Option 1002-2 from specification form for Track Motion.

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2 DressPack

2.1 Introduction

2.1.1 General

DressPack

Includes options for Upper arm, Lower arm and Floor pos C, D and E, see Figure below. These are described separately below but are designed as a complete package for various applications.

The DressPack for the floor contains customer signals.

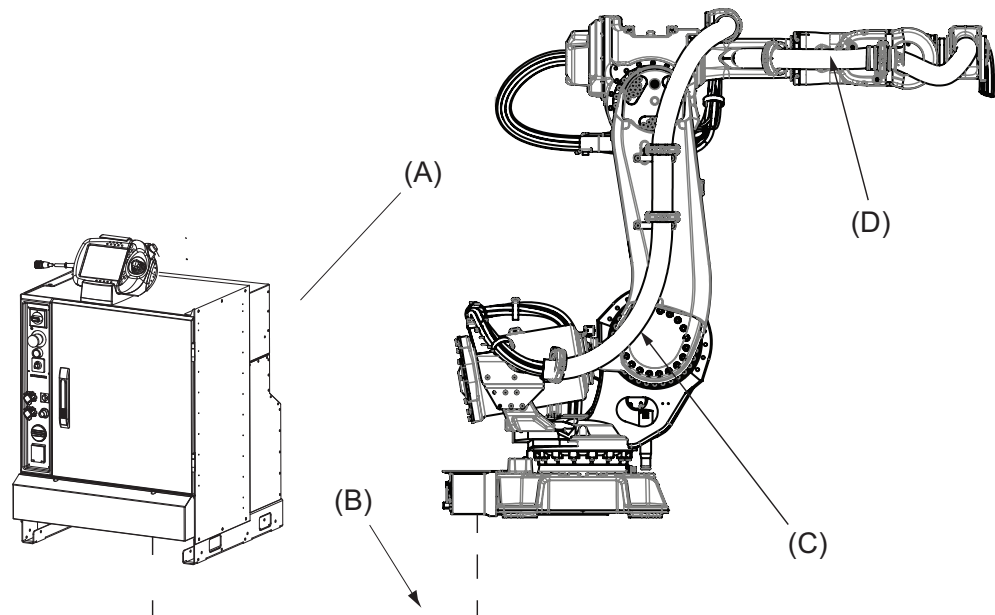
The DressPack for upper and lower arm contains process cable packages including signals, process media (water and/or air) and power feeding (for Spot Welding power) for customer use.

Necessary supports and brackets are also included.

The routing of the process cable package on the robot is available in different configurations.

Spot welding

The package supplies the transformer gun/gripper with necessary media, such as compressed air, cooling water and electrical power. It includes aboved described DressPack + Spot Welding cabinet, Water And Air unit pos A and F (if included) and SoftWare, see Figure below.



xx1000000424

Pos	Description
A	Robot controller, (including 7th axis drive for servo gun)
B	DressPack, Floor

Continues on next page

2 DressPack

2.1.1 General

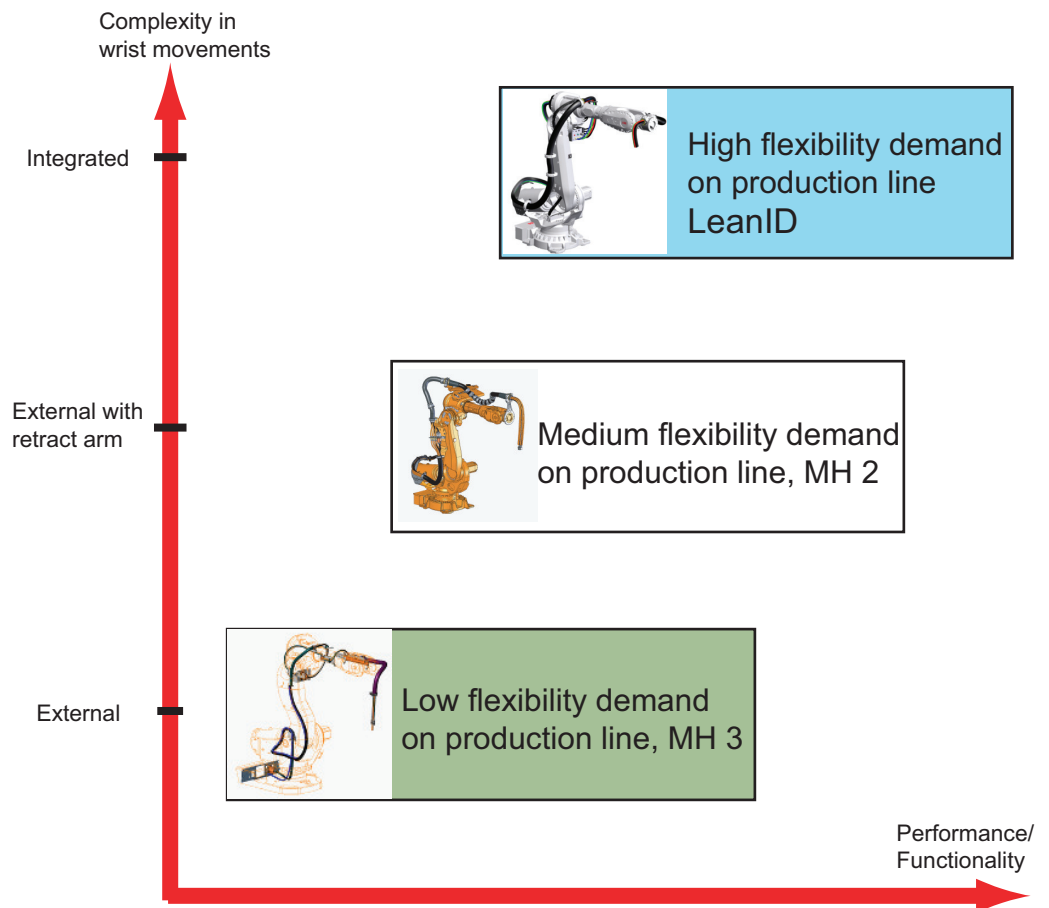
Continued

Pos	Description
C	DressPack, Lower arm
D	DressPack, Upper arm

2.1.2 Product range

DressPack solutions for different user's needs

The robot can be equipped with the well integrated cable and hose packages in the DressPack option. The DressPack is designed in close conjunction with the development of the manipulator and is therefore well synchronized with the robot. As there is a big span between different user's need of flexibility, depending of the complexity of the operation/wrist movements, there are three major levels of dress pack solutions available, see Figure below.



xx150000887

Continues on next page

2 DressPack

2.1.2 Product range

Continued

External with retract arm

This type of dress pack is recommended for production where there are limited complexity in wrist movements. This normally occurs when there are not too many different products running in the same production cell.

Available options are 798-2 and 780-2 for both material handling/spot welding.

Integrated

This type of dress pack is intended for a production where there are many complex wrist movements and the need for flexibility in changing products is high.

Available options are 798-3 and 780-4 for material handling/spot welding, the LeanID concept.

External

This type of dress pack is recommended where there are less complexity in wrist movements. This normally occurs when there are not many different products running in the production cell. This package requires more individual adjustment to optimize towards robot program at set up.

Available options are 798-3 and 780-3 for material handling.

2.1.3 Limitations of robot movements

General

When using DressPack options on the upper arm the robot movements will be limited. The position of bracket installed on axis 6 must be taken in consideration when optimizing the possible robot movements.

- The axis 5 working range is limited to +/- 110 degrees due to the axis 6 bracket attachment (when applicable).
- In bending backwards positions there are limitations due to interference with manipulator or Water and Air unit (if such is mounted).



Note

For more detail information please contact Serop Product support/SEROP/ABB.
E-mail address: serop.product_support@se.abb.com

Restrictions for LeanID, option 780-4

Limitation for axis 5 and 6 depends on how the dresspack is assembled at the tool and how adjustment has been done.

Axis	Working range
Axis 5	100° to -100°
Axis 6	220° to -220°

2 DressPack

2.1.4 Impact on dress pack lifetime

2.1.4 Impact on dress pack lifetime

General

There are some robot movements/positions that shall be avoided in the robot production program. This will improve the lifetime significantly of external upper arm dress pack and wear parts e.g. protection hose, hose reinforcement and protective sleeves.

- The axis 5 movement is not allowed to press the DressPack against the robot upper arm.
- Combined rotation of the wrist axes must be limited so that the DressPack is not wrapped hard against the upper arm.

See the Product Manual for more detailed information and recommended set-up adjustments

2.1.5 Chapter Structure

General

The Chapters for DressPack are structured in the following way.

The DressPack can be delivered in five versions developed for two different applications. Each type is described under separate chapter.

Chapter	Option	Description
2.2	DressPack	DressPack includes general description DressPack with common information.

Material Handling application / DressPack

Chapter	Option	Description
2.3	Type H	DressPack for Material Handling.

Spot Welding application / DressPack

Chapter	Option	Description
2.4	Type S	DressPack for pneumatic transformer guns carried by the robot manipulator.
2.5	HS	DressPack for handling the part against pneumatic transformer guns stationary mounted.
2.6	Type Se	DressPack for electrical servo driven transformer guns carried by the robot manipulator.
2.7	Type HSe	DressPack for handling the part against electrical servo driven transformer guns stationary mounted.

Connector Kits

Chapter	Option	Description
2.10	Connetor Kits	Includes general description of Connector kits for DressPack.

2 DressPack

2.2.1 Introduction

2.2 DressPack

2.2.1 Introduction

Available DressPack configurations for Material Handling

The table below shows the different DressPack configurations available for Material Handling.

	Lower arm	Upper arm
Option 778-1, Material Handling	Option 798-3, Base to axis 3	Option 780-3, Axis 3 to 6 External routing
		Option 780-4 Axis 3 to 6 Internal routing
	Option 798-2, Base to axis 2	Option 780-2, Axis 2 to 6 External routing

Available DressPack configurations for Spot Welding

The table below shows the different DressPack configurations available for Spot Welding.

	Lower arm	Upper arm
Option 778-2, Spot Welding	Option 798-2, Base to axis 2	Option 780-2, Ext. Axis 2 to axis 6 External routing
	Option 798-3, Base to axis 3	Option 780-4, Int. Axis 3 to 6 (LeanID) Internal routing

2.2.2 Build-in features for upper arm DressPack

External

Material handling (option 780-3):

- Internal routing through the rear part of the upper arm.
- Protection hose can easily be replaced if damaged.
- One version for all IRB 6650S versions.
- Adjustment for optimal hose/cable lengths.
- Easy exchange of DressPack

External with retract arm

Spot welding and Material handling (option 780-2):

- Adjustable bracket axis 6 with position marking.
- Adjustable retracting force to optimize the system depending on cycle and hose package.

Internal

Spot welding and Material handling (option 780-4):

- Partly internal routing through the upper arm.
- Suitable for complex movements.
- High demands for flexibility and accessibility.
- Longer life time
- Predictable movements
- Easy exchange of DressPack

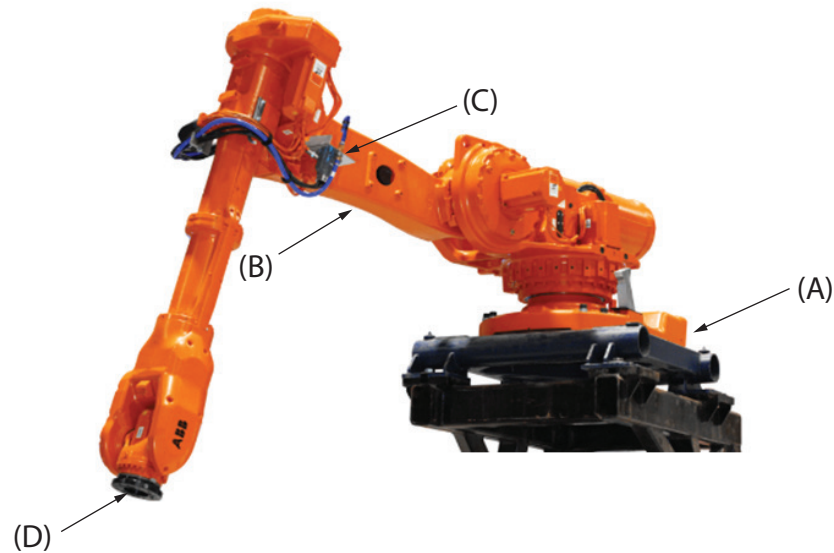
2 DressPack

2.2.3 Interface descriptions for DressPack

2.2.3 Interface descriptions for DressPack

General

Below is an overview showing the different dresspack interfaces. For detailed information see the circuit diagram included in *Product manual - DressPack/SpotPack IRB 6650S/7600*.



xx1300000217

Pos	Location	Options
A	Base	798-2, 798-3 and 864-1
B	Axis 2	798-2
C	Axis 3	798-3
D	Axis 6	780-2, 780-3 and 780-4

Continues on next page

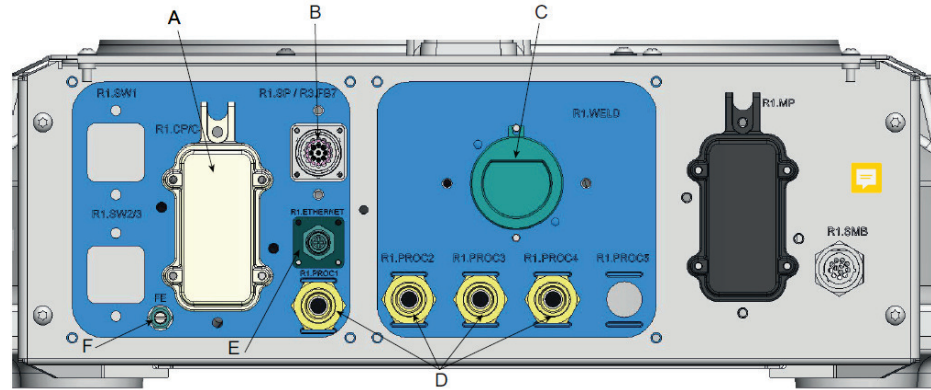
Base

Material handling (option 798-3), see figure below:

- Included are: A, B (if applicable), one D (Proc 1) and E, F (if applicable).

Spot welding (option 798-3), see figure below:

- Included are: A, B (if applicable), C, D (Proc 1-4) and E, F (if applicable).



xx1900001501

For corresponding parts of the tool, see [Axis 6 - Connector kits on page 133](#).

Pos	Description
A	R1.CP/CS
B	R1.SP (Spot Welding Servo gun) or FB7 (Resolver connection)
C	R1.WELD 3x35mm ² . (Spot Welding)
D	R1.PROC 1 (Material Handling/Spot Welding 1/2", M22x1.5, 24 degree seal) R1.PROC 2 - 4 (Spot Welding 1/2", M22x1.5, 24 degree seal)
E	R1.ETHERNET (M12 connector, when EtherNet communication is selected)
F	FE (Functional Earth, when EtherNet communication is selected)

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2 DressPack

2.2.3 Interface descriptions for DressPack

Continued

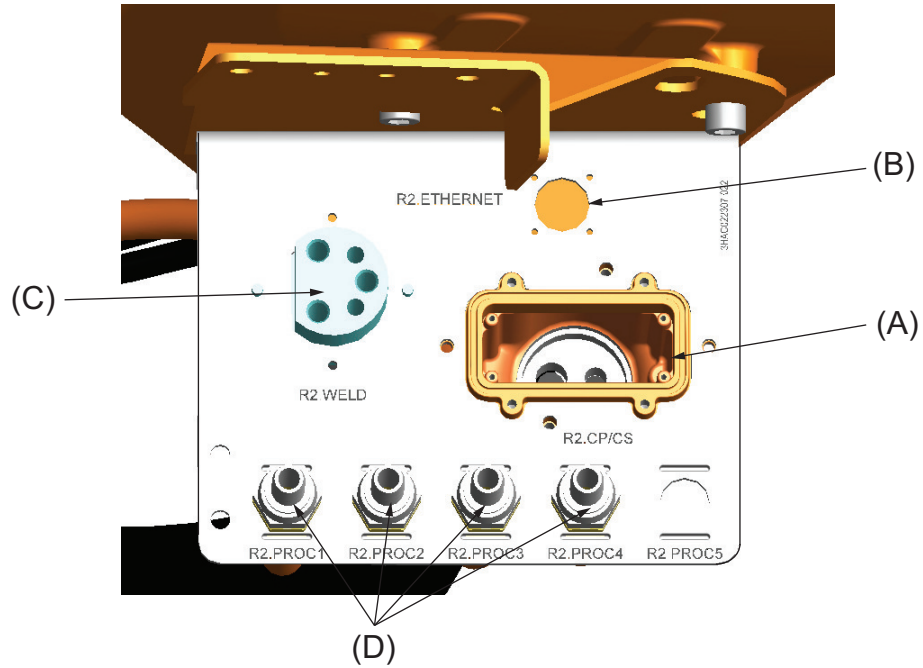
Axis 2

Material handling (option 798-2), see figure below:

- Included are: A, B (if applicable) and one D (Proc 1).

Spot welding (option 798-2), see figure below:

- Included are: A, B (if applicable), C and D (Proc 1-4).



xx1100000957

For corresponding parts of the tool, see [Connection kits on page 129](#).

Pos	Description
A	R2.CP/CS
B	R2.ETHERNET (M12 connector, when EtherNet communication is selected)
C	R2.WELD 3x35 mm2. (Spot Welding)
D	R2.PROC 1 (Material Handling/Spot Welding 1/2", M22x1.5, 24 degree seal) R1.PROC 2 - 4 (Spot Welding 1/2", M22x1.5, 24 degree seal)

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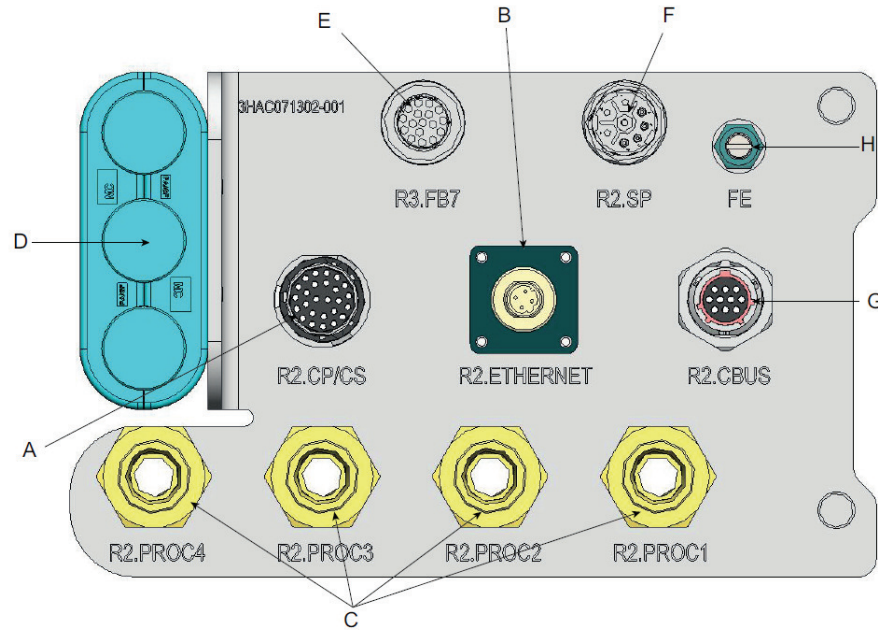
Axis 3

Material Handling (option 798-3), see figure below:

- Included are: A, B/G/H (if applicable) and one C (Proc 1).

Spot welding (option 798-3), see figure below:

- Included are: A, D, B/E/F/G/H (if applicable) and C (Proc 1-4).



xx1900001511

For corresponding parts of the tool, see [Axis 6 - Connector kits on page 133](#).

Pos	Description
A	R2.CP/CS
B	R2.ETHERNET (M12 connector, when EtherNet communication is selected)
C	R2.PROC 1 (Material Handling 1/2", M22x1.5, 24 degree seal) R2.PROC 2-4 (Spot Welding 1/2", M22x1.5, 24 degree seal)
D	R2.WELD 3x35mm ² (Spot Welding)
E	R2.FB7
F	R2.SP (Spot Welding Servo gun)
G	R2.CBUS (UTOW connector when Profibus or DeviceNet communication is selected)
H	FE (Functional Earth, when EtherNet communication is selected)

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2 DressPack

2.2.3 Interface descriptions for DressPack

Continued

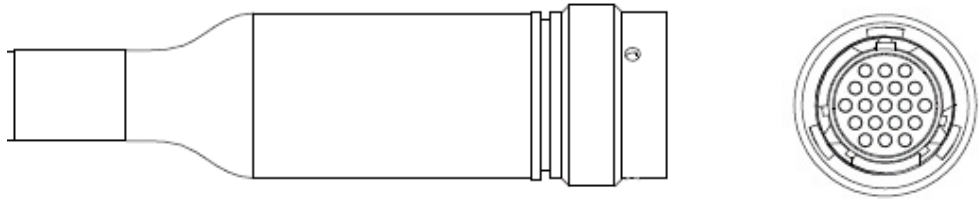
Axis 6

External

Material handling (option 780-3), see figure below:

- Hose and cable free length, min. 1000 mm.
- Air hose ends with free end.

The cable ends with a connector, for corresponding parts of the tool, see [Connection kits on page 129](#):



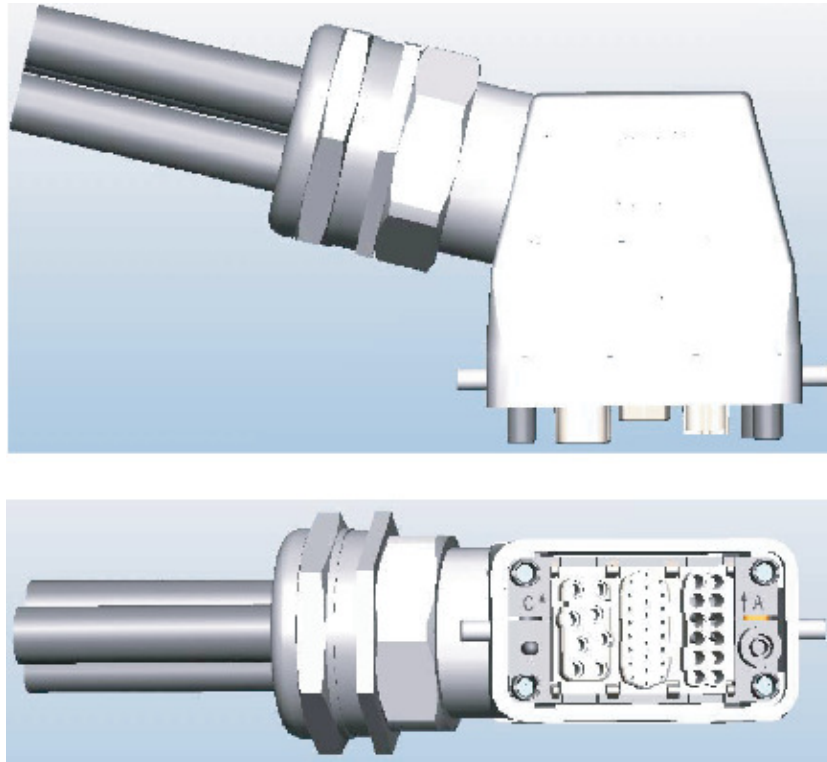
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External with retract arm

Spot welding/Material handling (option 780-2), see figure below:

- Hose and cable free length, min. 1000 mm.
- Hoses and weld power cable (only for spot welding) end with free end.
- All signals are connected with a Harting connector.

The cable ends with a connector, for corresponding parts of the tool, see [Connection kits on page 129](#) and within the Harting product offer.



xx0900000729

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EtherNet connector

Spot welding/Material handling (option 780-2/-3), see figure below:

- Cable free length, min. 1000 m.
- Signals are connected with a M12 connector.

The cable ends with a connector, the different main parts within the connector are described in the list below, for corresponding parts of the tool, see within the Phoenix product offer.

Name	Harting article
PIN connector, R3.ETHERNET	21 03 882 1405
PIN	61 03 000 0094
Sealing cap M12x1	3HAC033600-001 ABB article



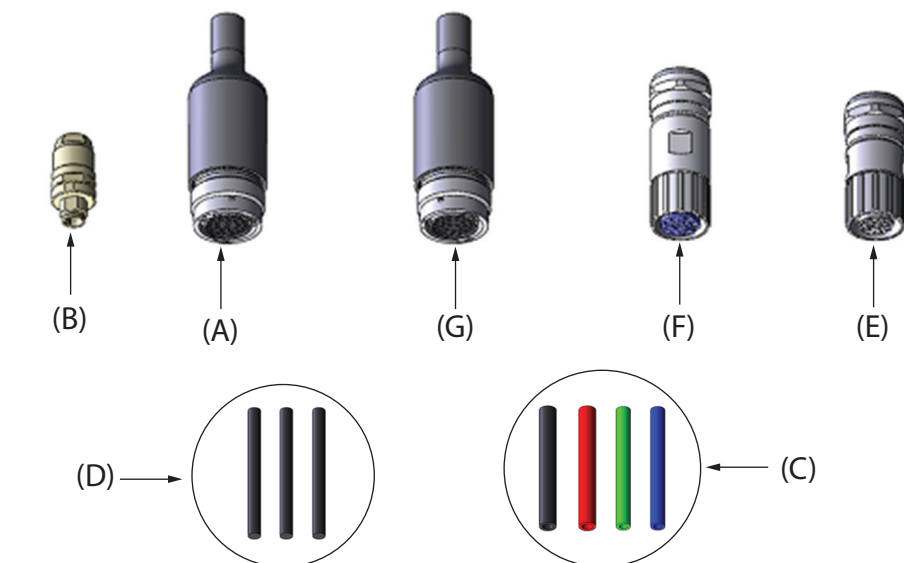
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Integrated

Material Handling/Spot Welding option 780-4 (LeanID), see figure below:

- Hose and cable free length, min. 1160 mm.
- Hoses and weld power cable (only for spot welding) end with free end.

The cable ends with connectors, for corresponding parts of the tool, see [Axis 6 - Connector kits on page 133](#) and within the UTOW product offer.



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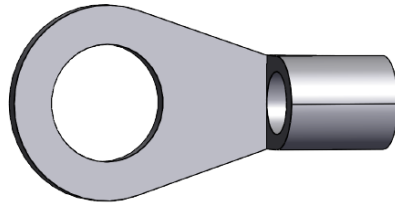
2 DressPack

2.2.3 Interface descriptions for DressPack

Continued

Pos	Description
A	R3.CP/CS (UTOW connector 26p) Customer signals and power
B	R3.ETHERNET (M12 connector) EtherNet signals (when EtherNet communication is selected)
C	R3.PROC 1-2 (1/2", freeend) R3.PROC 2-4 (3/8", free end) Media hoses
D	R3.WELD 3x25mm ² (Free end) Spot Welding power
E	R3.FB7 (M23 connector 17p) Servo motor power (when Spot Welding Servo gun is selected)
F	R3.SP (M23 connector 8p) Servo motor feedback (when Spot Welding Servo gun is selected)
G	R3.CBUS (UTOW connector 10p) BUS signals (when Profibus or DeviceNet communication is selected)

- FE (M8 cable lug) Functional Earth 10mm² (When Parallel and Ethernet communication is selected)

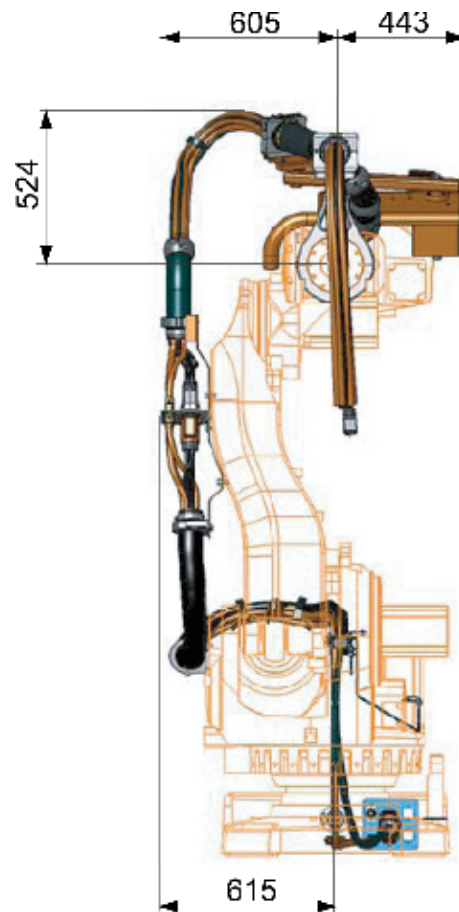


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2.2.4 Dimensions

General

Dimensions are shown in Figures below.



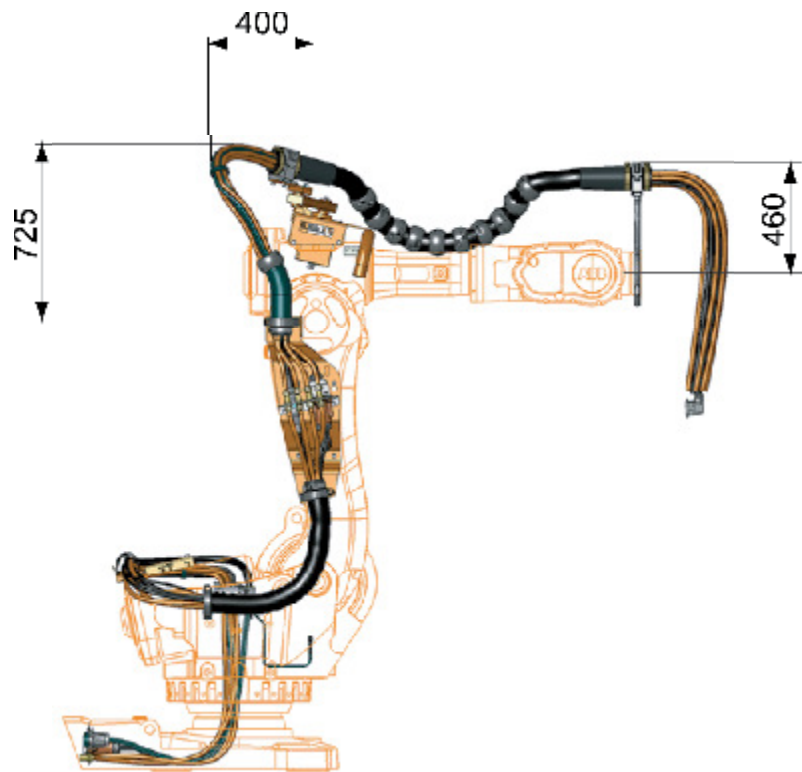
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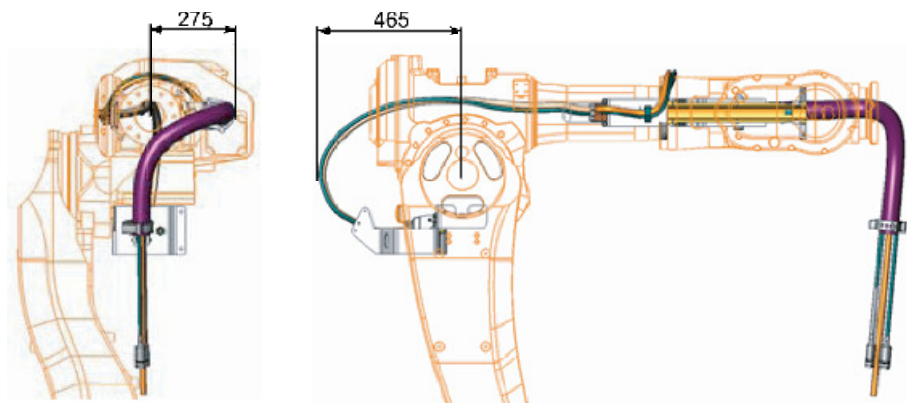
2 DressPack

2.2.4 Dimensions

Continued



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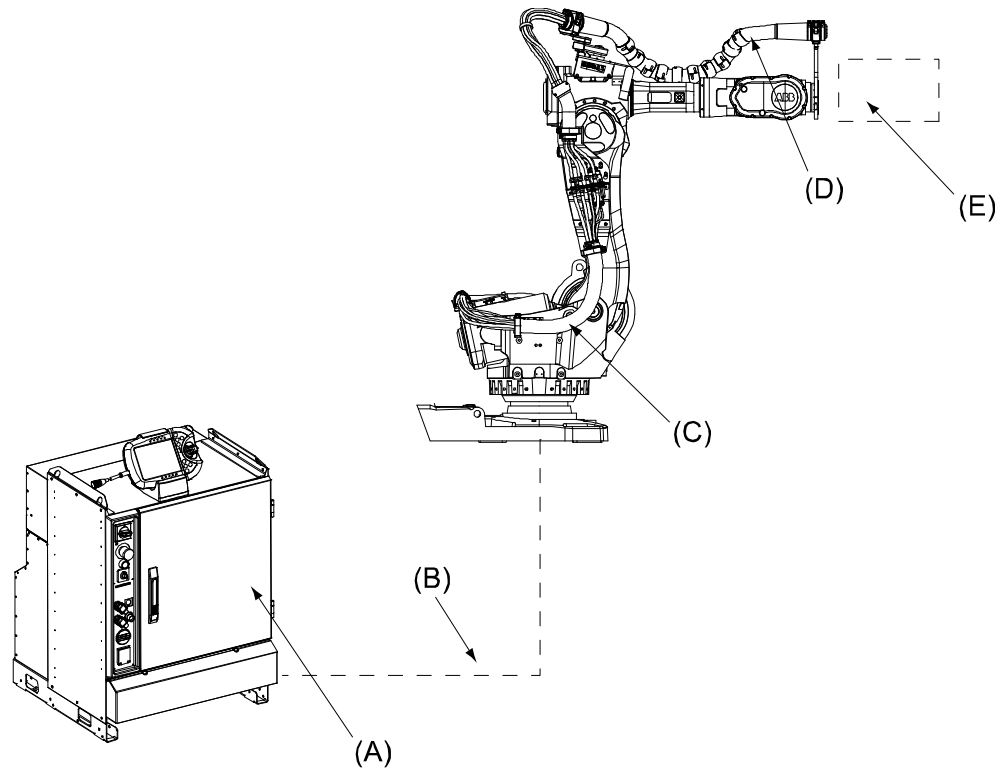
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2.3 Type H

2.3.1 Introduction

General

Variant Type H is designed for Material Handling (MH) application. Included modules are shown in Figure below.



xx100000516

Pos	Name
A	Robot Cabinet IRC5
B	DressPack, Floor
C	DressPack, Lower arm
D	DressPack, Upper arm
E	Robot Gripper

Available configurations with linked option numbers are described below.

Continues on next page

2 DressPack

2.3.1 Introduction

Continued

Option description

Option	Type	Description
16-1	Connection to cabinet	Floor cables and connections inside the I/O section for the DressPack are chosen. The length and configuration of the floor harness is specified under the options below. Option 94-1,-2,-3,-4 for parallel communication. Option 90-2,-3,-4,-5 for parallel communication and field bus communication with Can/DeviceNet. Option 92-2,-3 for parallel communication and field bus communication with Profibus.
455-1	Parallel communication	Offers the signal cables needed for parallel communication in lower and upper arm DressPack. To be combined with option 94-1,-2,-3,-4,-5.
455-4	Parallel and Bus communication	Offers the signal cables needed for the combination of parallel and bus communication in lower and upper arm DressPack. To be combined with option 90-2,-3,-4,-5 or 92-2,-3.
455-8	Parallel and Ethernet	Offers the signal cables needed for the Ethernet communication in combination in lower and upper arm DressPack. To be combined with option 859-1,-2,-3,-4. Requires selection of option 94-X.

The available alternatives and allowed combinations are shown in the schematic table below.

Application Interface connected to Option 16-1, Cabinet	Option 455-1, Parallel communication	Option 94-1,-2,-3,-4 Cable length, Parallel communication	Option 778-1, Material handling
	Option 455-4, Parallel and bus communication	Option 90-2,-3,-4,-5 Option 92,2,-3 Cable length, Parallel and bus communication	
	Option 455-8, Parallel and Ethernet communication	Option 859-1, -2, -3, -4 Cable length, Ethernet communication	

Continued

	Lower arm	Upper arm
Option 778-1, Material Handling	Option 798-3, Base to axis 3	Option 780-3, Axis 3 to 6 External routing
		Option 780-4, Axis 3 to 6 Internal routing
	Option 798-2, Base to axis 2	Option 780-2, Axis 2 to 6 External routing

2.3.2 Configuration result for Type H

General

Depending on the choice of options above the DressPack will have different content. The choice of routing will not affect the content. See tables for signal content below.

DressPack Type H. Parallel communication

- Option 16-1 with Connection to cabinet
- (Option 94-1,-2,-3,-4 to specify cable length)
- Option 455-1. Parallel communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3 or 780-4 (and option 798-3). External/Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^a
Protective earth		1	0,5 mm ²	250 VAC ^b
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2) ^b	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. For option 780-3 50 VAC / 60 VDC.

b. For option 780-3 8 signals instead of 20.

Continues on next page

2 DressPack

2.3.2 Configuration result for Type H

Continued

DressPack Type H. Parallel and field bus communication, Can/DeviceNet

- Option 16-1 with Connection to cabinet
- (Option 90-2,-3,-4,-5 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3 Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3 or 780-4 (and option 798-3). External/Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^a
Protective earth		1	0,5 mm ²	250 VAC ^b
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2) ^b	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	2	0,14 mm ²	Can/DeviceNet spec
Bus signals	At bus board	2	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair	6	6(3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. For option 780-3 50 VAC / 60 VDC.

b. For option 780-2 8 signals instead of 20.

Continues on next page

DressPack Type H. Parallel and field bus communication, Profibus

- Option 16-1 with Connection to cabinet
- (Option 92-2,-3 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3 or 780-4 (and Option 798-3). External/Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^a
Protective earth		1	0,5 mm ²	250 VAC ^b
Customer Signals (CS)				
Signals twisted pair	22	22(11x2) ^b	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	4	0,14 mm ²	Profibus 12 Mbit/s spec
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. For option 780-3 50 VAC / 60VDC.

b. For option 780-3 8 signals instead of 22.

Continues on next page

2 DressPack

2.3.2 Configuration result for Type H

Continued

DressPack Type H, Parallel and field bus communication, Ethernet

- Option 16-1 with Connection to cabinet
- (Option 859-1,-2, -3, -4 to specify cable length)
- (Option 94-1, -2, -3, -4 to specify cable length)
- Option 455-8. Parallel and Ethernet communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3 or 780-4 (and option 798-3). External/Internal routing.

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ⁱ
Protective earth		1	0,5 mm ²	250 VACa
Customer Signals (CS)				
Signals twisted pair	20	20(10x2) ⁱⁱ	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (Ethernet)				
Bus signals	4	4	0,4 mm ²	Ethernet CAT 5e, 100 Mbit ⁱⁱⁱ
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

ⁱ For option 780-3 50 VAC / 60 VDC.

ⁱⁱ For option 780-3 8 signals instead of 20.

ⁱⁱⁱ Ethernet with wire colors according to PROFINET standard, M12-connectors.

Continues on next page

Summary Type H

The following options are required to form a complete DressPack Type H:

- Option 16-1. Connection to cabinet, (Cable length and communication type to be stated)
- Option 455-1, 455-4. Parallel or Parallel and Bus communication
(Communication type to be stated)
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm
(Routing type to be stated)
- Option 780-2. External routing Axis 2 to 6, option 780-3, -4 External routing Axis 3 to 6, DressPack Upper arm (Routing type to be stated)

2 DressPack

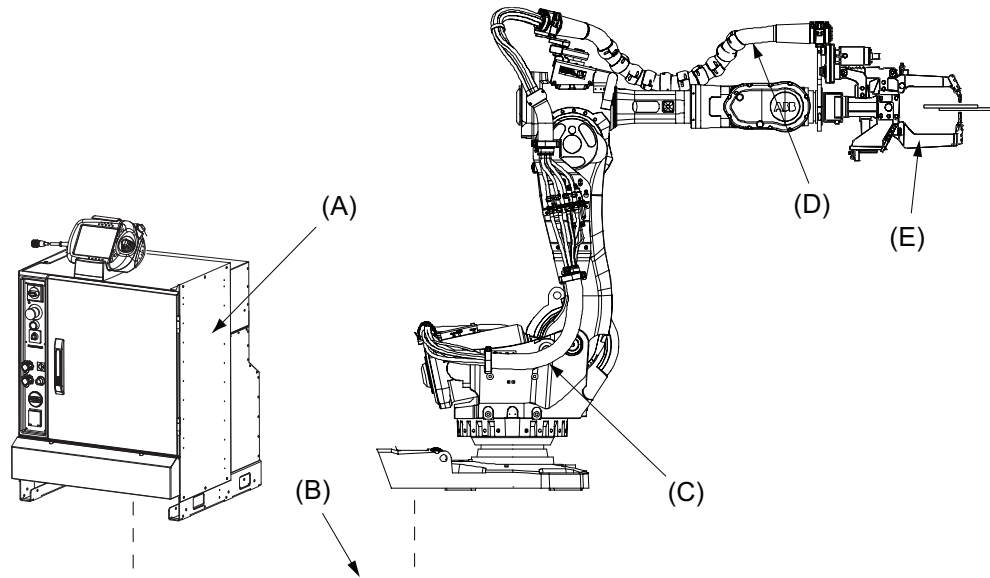
2.4.1 Introduction

2.4 Type S

2.4.1 Introduction

General

Variant Type S is designed for Spot Welding application with robot handled pneumatic gun. Included modules are shown in Figure below. Available configurations with linked option numbers are described below.



xx100000517

Pos	Name
A	Robot Cabinet IRC5
B	DressPack, Floor
C	DressPack, Lower arm
D	DressPack, Upper arm
E	Pneumatic gun

Available configurations and allowed combinations with linked option numbers are described below.

Option Description

Option	Type	Description
16-1	Connection to cabinet	Floor cables and connections inside the I/O section for the DressPack are chosen. The length and configuration of the floor harness is specified under the options below. Option 94-1,-2,-3,-4 for parallel communication Option 90-2,-3,-4,-5 for parallel communication and field bus communication with Can/DeviceNet Option 92-2,-3 for parallel communication and field bus communication with Profibus

Continues on next page

Option	Type	Description
455-1	Parallel communication	Offers the signal cables needed for parallel communication in lower and upper arm DressPack. To be combined with option 94-1,-2,-3,-4.
455-4	Parallel and Bus communication	Offers the signal cables needed for the combination of parallel and bus communication in combination in lower and upper arm DressPack. To be combined with option 90-2,-3,-4,-5 or 92-2,-3.
455-8	Parallel and Ethernet	Offers the signal cables needed for the Ethernet communication in combination in lower and upper arm DressPack. To be combined with option 859-1,-2,-3,-4. Requires selection of option 94-X.

The available alternatives and allowed combinations are shown in the schematic table below.

Application Interface connected to Option 16-1	Option 455-1, Parallel communication	Option 94-1,-2,-3,-4 Cable length, Parallel and Bus communication	Option 778-2, Spot Welding
	Option 455-1, Parallel and Bus communication	Option 90-2,-3,-4,-5 Option 92-2,-3 Cable length, Parallel and Bus communication	
	Option 455-8, Parallel and Ethernet communication	Option 859-1, -2, -3, -4 Cable length, Ethernet communication	

Continued

	Lower arm	Upper arm
Option 778-2, Spot Welding	Option 798-2, Base to axis 2 External routing	Option 780-2, Axis 2 to 6 External routing
	Option 798-3, Base to axis 3 External routing	Option 780-4, Axis 3 to 6 Internal routing

2 DressPack

2.4.2 Configuration result for Type S

2.4.2 Configuration result for Type S

General

Depending on the choice of options above the DressPack will have different content. The choice of routing will not affect the content. See tables for signal content below.

DressPack Type S. Parallel communication

- Option 16-1 with Connection to cabinet
- (Option 94-1,-2,-3,-4 to specify cable length)
- Option 455-1. Parallel communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing.

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/ 230 PSI Max. water pressure 10 bar/ 145 PSI
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20 °C (68 °F)
Protective earth (Lower and Upper arm)		1		

ⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

ⁱⁱ For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

DressPack Type S. Parallel and field bus communication, Can/DeviceNet

- Option 16-1 with Connection to cabinet
- (Option 90-2,-3,-4,-5 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing.

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	1 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	20	20 (10x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	2	0,14 mm ²	Can/DeviceNet spec
Bus signals	At bus board	2	0,23 mm ²	50 V DC, 1 A rms
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/230 PSI Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20 °C (68 °F)
Protective earth (Lower and Upper arm)		1		

ⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

ⁱⁱ For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

2 DressPack

2.4.2 Configuration result for Type S

Continued

DressPack Type S. Parallel and field bus communication, Profibus

- Option 16-1 with Connection to cabinet
- (Option 92-2,-3 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing.

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	22	22 (11x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	4	0,14 mm ²	Profibus 12 Mbit/s spec
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/230 PSI Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20 °C (68 °F)
Protective earth (Lower and Upper arm)		1		

ⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

ⁱⁱ For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

DressPack Type S. Parallel and field bus communication, Ethernet

- Option 16-1 with Connection to cabinet
- (Option 859-1,-2, -3, -4 to specify cable length)
- (Option 94-1, -2, -3, -4 to specify cable length)
- Option 455-8. Parallel and Ethernet communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing.

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	202	20 (10x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (Ethernet)				
Bus signals	4	4	0,4 mm ²	Ethernet CAT 5e, 100 Mbit ⁱ
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱⁱ	Max. air pressure 16 bar/230 PSI Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ⁱⁱⁱ	600 VAC, 150 A rms at 20 °C (68 °F)
Protective earth (Lower and Upper arm)		1		

ⁱ Ethernet with wire colors according to PROFINET standard, M12-connectors.

ⁱⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

ⁱⁱⁱ For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

2 DressPack

2.4.2 Configuration result for Type S

Continued

Required general options for Type S

To enable the Spot welding function package IRB 6650S to perform as intended, general standard robot options are required. These standard options are further described under other chapters and are also mentioned in this chapter.

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply
- Option 635-1. Spot. Software option for pneumatic guns

2.4.3 Summary Type S

General

The following options are the minimum required to form a complete Spot welding function Type S:

DressPack

- Option 16-1. Connection to cabinet, (Cable length and communication type to be stated)
 - Option 455-1, 455-4. Parallel or Parallel and Bus communication (Communication type to be stated)
 - Option 778-2. Spot Welding
 - Option 798-2 or 798-3. DressPack Lower arm
 - Option 780-2 or 780-4. DressPack Upper arm (Routing type to be stated)
-

General options

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply
- Option 635-1. Spot

2 DressPack

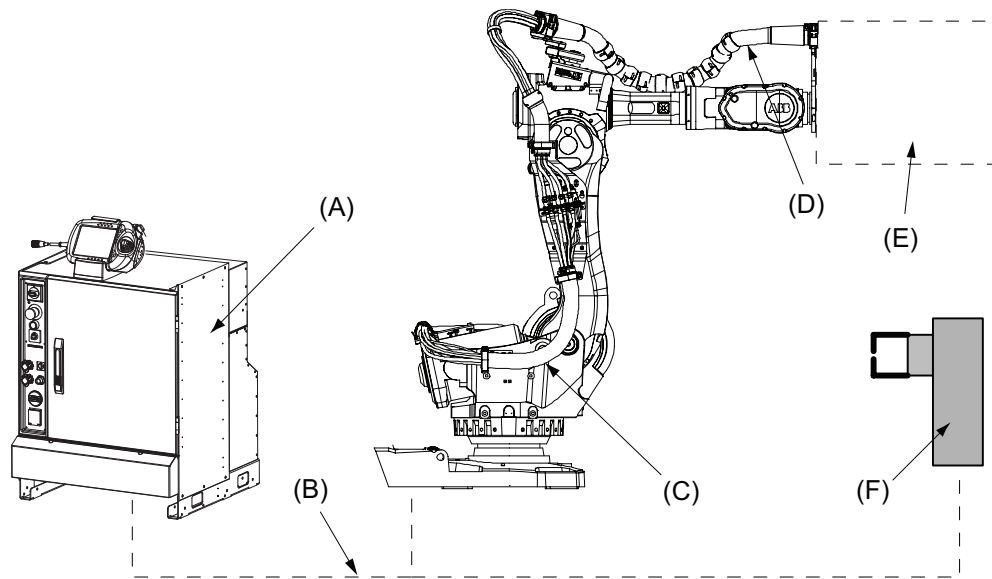
2.5.1 Introduction

2.5 Type HS

2.5.1 Introduction

General

Variant Type HS is designed for handling against a stationary mounted Spot Welding pneumatic gun. Included main modules are shown in Figure below. Available configurations with linked option numbers are described below starting at the DressPack.



xx100000519

Pos	Name
A	Robot Cabinet IRC5
B	DressPack, Floor
C	DressPack, Lower arm
D	DressPack, Upper arm
E	Robot Gripper
F	Stationary gun

Available configurations with linked option numbers are described below.

Option description

Option	Type	Description
16-1	Connection to cabinet	Floor cables and connections inside the I/O section for the DressPack are chosen. The length and configuration of the floor harness is specified under the options below. Option 94-1,-2,-3,-4 for parallel communication. Option 90-2,-3,-4,-5 for parallel communication and field bus communication with Can/DeviceNet. Option 92-2,-3 for parallel communication and field bus communication with Profibus.

Continues on next page

Option	Type	Description
455-1	Parallel communication	Offers the signal cables needed for parallel communication in lower and upper arm DressPack. To be combined with option 94-1,-2,-3,-4,-5.
455-4	Parallel and Bus communication	Offers the signal cables needed for the combination of parallel and bus communication in lower and upper arm DressPack. To be combined with option 90-2,-3,-4,-5 or 92-2,-3.
455-8	Parallel and Ethernet	Offers the signal cables needed for the Ethernet communication in combination in lower and upper arm DressPack. To be combined with option 859-1,-2,-3,-4. Requires selection of option 94-X.

The available alternatives and allowed combinations are shown in the schematic table below.

Application Interface connected to Option 16-1, Cabinet	Option 455-1, Parallel communication	Option 94-1,-2,-3,-4 Cable length, Parallel communication	Option 778-1, Material Handling
	Option 455-4, Parallel and bus communication	Option 90-2,-3,-4,-5 Option 92-2,-3 Cable length, Parallel and bus communication	
	Option 455-8, Parallel and Ethernet communication	Option 859-1, -2, -3, -4 Cable length, Ethernet communication	

Continued

	Lower arm	Upper arm
Option 778-1 Material Handling	Option 798-3, Base to axis 3	Option 780-3, Axis 3 to 6 External routing
		Option 780-4, Axis 3 to 6 Internal routing
	Option 798-2, Base to axis 2	Option 780-2, Axis 2 to 6 External routing

2 DressPack

2.5.2 Configuration result for Type HS

2.5.2 Configuration result for Type HS

General

Depending on the choice of options above the DressPack will have different content. The choice of routing will not affect the content. See tables for signal content below.

DressPack Type HS. Parallel communication

- Option 16-1 with Connection to cabinet
- (Option 94-1,-2,-3,-4 to specify cable length)
- Option 455-1. Parallel communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+21 ^a	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth			0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	20	20(10x2) ^c	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60VAC.

c. For option 780-3 8 signals instead of 20.

Continues on next page

DressPack Type HS. Parallel and field bus communication, Can/DeviceNet

- Option 16-1 with Connection to cabinet
- (Option 90-1,-2,-3,-4 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth		1 ^a	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	208	20 (10x2) ^c	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded		8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	2	0,14 mm ²	Can/DeviceNet spec
Bus signals	At bus board	2	0,23 mm ²	50 V DC, 1 A rms 50 V DC, 1 A rms
Signals twisted pair	6	6(3x2)	0,14 mm ²	
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60 VAC.

c. For option 780-3 8 signals instead of 20.

Continues on next page

2 DressPack

2.5.2 Configuration result for Type HS

Continued

DressPack Type HS. Parallel and field bus communication, Profibus

- Option 16-1 with Connection to cabinet
- (Option 92-1,-2,-3 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth		1 ^a	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	22	22(11x2) ^c	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	4	0,14 mm ²	Profibus 12 Mbit/s spec
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60 VDC.

c. For option 780-3 8 signals instead of 22.

Continues on next page

DressPack Type HS. Parallel and field bus communication, Ethernet

- Option 16-1 with Connection to cabinet
- (Option 859-1,-2,-3, -4 to specify cable length)
- (Option 94-1, -2, -3, -4 to specify cable length)
- Option 455-8. Parallel and Ethernet communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ⁱ
Protective earth		1	0,5 mm ²	250 VACa
Customer Signals (CS)				
Signals twisted pair	20	20(10x2) ⁱⁱ	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (Ethernet)				
Bus signals	4	4	0,4 mm ²	Ethernet CAT 5e, 100 Mbit ⁱⁱⁱ
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

ⁱ For option 780-3 50 VAC / 60 VDC.

ⁱⁱ For option 780-3 8 signals instead of 20.

ⁱⁱⁱ Ethernet with wire colors according to PROFINET standard, M12-connectors.

Continues on next page

2 DressPack

2.5.2 Configuration result for Type HS

Continued

Required general options for Type HS

To enable the Spot welding function package IRB 6650S to perform as intended, general standard robot options are required. These standard options are further described under other chapters and are also mentioned in this chapter.

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply
- Option 635-1. Spot. Software option for pneumatic guns.

2.5.3 Summary Type HS

General

The following options are the minimum required to form a complete Spot welding function Type HS:

DressPack

- Option 16-1. Connection to cabinet, (Cable length and communication type to be stated)
 - Option 455-1, 455-4. Parallel or Parallel and Bus communication (Communication type to be stated)
 - Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm (Routing type to be stated)
 - Option 780-2, 780-3, 780-4. External routing, DressPack Upper arm (Routing type to be stated)
-

General options

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply
- Option 635-1. Spot

2 DressPack

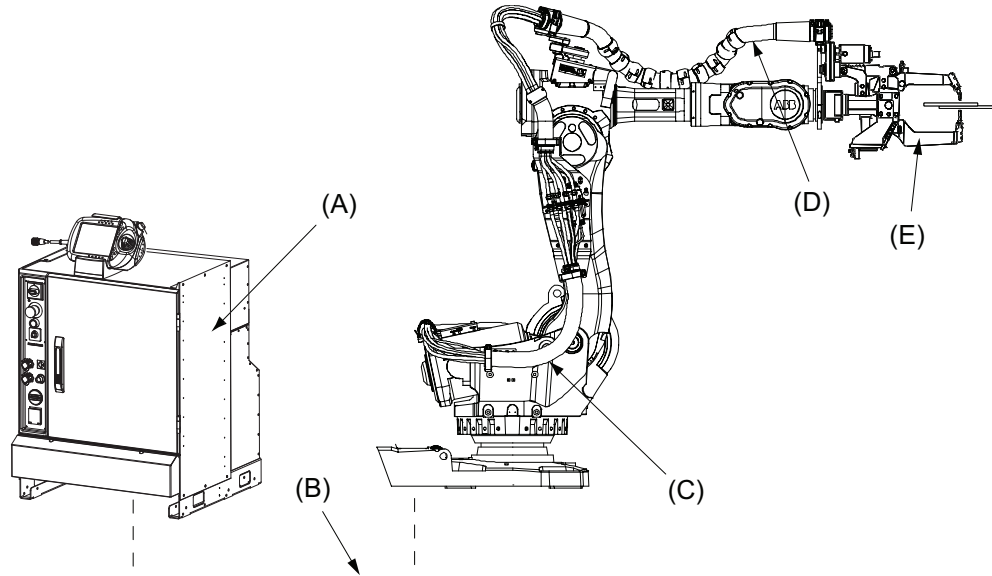
2.6.1 Introduction

2.6 Type Se

2.6.1 Introduction

General

Variant Type Se is designed for Spot Welding application with robot handled servo-controlled tool (electrical gun). Included modules are shown in Figure below. Available configurations with linked option numbers are described below.



xx100000520

Pos	Name
A	Robot Cabinet IRC5 (including 7th axis drive)
B	DressPack, Floor
C	DressPack, Lower arm
D	DressPack, Upper arm
E	Servo gun

Available configurations with linked option numbers are described below. To achieve the specific servo motor connections within the DressPack option 785-1 Robot gun must also to be chosen. See [Robot Gun on page 65](#).

Option description

Option	Type	Description
16-1	Connection to cabinet	Floor cables and connections inside the I/O section for the DressPack are chosen. The length and configuration of the floor harness is specified under the options below. Option 94-1,-2,-3,-4 for parallel communication Option 90-2,-3,-4,-5 for parallel communication and field bus communication with Can/DeviceNet Option 92-2,-3 for parallel communication and field bus communication with Profibus

Continues on next page

Option	Type	Description
455-1	Parallel communication	Offers the signal cables needed for parallel communication in lower and upper arm DressPack. To be combined with option 94-1,-2,-3,-4.
455-4	Parallel and Bus communication	Offers the signal cables needed for the combination of parallel and bus communication in combination in lower and upper arm DressPack. To be combined with option 90-2,-3,-4,-5 or 92-2,-3.
455-8	Parallel and Ethernet	Offers the signal cables needed for the Ethernet communication in combination in lower and upper arm DressPack. To be combined with option 859-1,-2,-3,-4. Requires selection of option 94-X.

The available alternatives and allowed combinations are shown in the schematic table below.

Application Interface connected to Option 16-1, Cabinet	Option 455-1, Parallel communication	Option 94-1,-2,-3,-4 Cable length, Parallel communication	Option 778-2 Spot Welding
	Option 455, Parallel and Bus communication	Option 90-2,-3,-4,-5 Option 92-2,-3 Cable length, Parallel and Bus communication	
	Option 455-8, Parallel and Ethernet communication	Option 859-1, -2, -3, -4 Cable length, Ethernet communication	

Continued

	Lower arm	Upper arm
Option 778-2, Spot Welding	Option 798-2, Base to axis 2 External routing	Option 780-2, Axis 2 to 6 External routing
	Option 798-3, Base to axis 3 External routing	Option 780-4, Axis 3 to 6 (LeanID) Internal routing

2 DressPack

2.6.2 Configuration result for Type Se

2.6.2 Configuration result for Type Se

General

Depending on the choice of options above (combined with option 785-1 Robot gun) the DressPack will have different content. The choice of routing will not affect the content. See tables for signal content below.

DressPack Type Se. Parallel communication

- Option 16-1 with Connection to cabinet
- (Option 94-1,-2,-3,-4 to specify cable length)
- Option 455-1. Parallel communication
- Option 778-2 .Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing

The table below shows the available type of wires/media.

Type Se	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer Signals (CS)				
Signals twisted pair	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	4 (2x2)	0,24 mm ²	50 V DC, 1 A rms
Servo motor signals				
Servo motor power	At drive	3	1,5 mm ²	600 VAC, 12 A rms
Protective earth	At drive	1	1,5 mm ²	600 VAC
Signals twisted pair for resolver	-	6	0,23 mm ²	50 V DC, 1 A rms
Brake	-	2	0,23 mm ²	50 V DC, 1 A rms
Temperature control/PTC	-	2	0,23 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/ 230 PSI. Max. water pressure 10 bar/ 145 PSI
Welding power (WELD)				

Continues on next page

2.6.2 Configuration result for Type Se
Continued

Type Se	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20°C (68°F)
Protective earth (Lower and Upper arm)		1		

i For LeanID 2x1/2" + 2x3/8", only upper arm

ii For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

2 DressPack

2.6.2 Configuration result for Type Se

Continued

DressPack Type Se. Parallel and field bus communication, Can/DeviceNet

- Option 16-1 with Connection to cabinet
- (Option 90-2,-3, -5, -5 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	14	14 (7x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	4	4 (2x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	2	0,14 mm ²	Can/DeviceNet spec
Bus signals	At bus board	2	0,23 mm ²	50 V DC, 1 A rms
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Servo motor signals				
Servo motor power	At drive	3	1,5 mm ²	600 VAC, 12 A rms
Protective earth	At drive	1	1,5 mm ²	600 VAC
Signals twisted pair for resolver	-	6 ^a	0,23 mm ²	50 V DC, 1 A rms
Brake	-	2	0,23 mm ²	50 V DC, 1 A rms
Temperature control/PTC	-	2	0,23 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/230 PSI. Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20°C (68°F)
Protective earth (Lower and Upper arm)		1		

ⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

Continues on next page

- ii For LeanID upper arm 25 mm², only upper arm, 135 A rms
 - a. Interface only at axis 3 or axis 6.

Continues on next page

2 DressPack

2.6.2 Configuration result for Type Se

Continued

DressPack Type Se. Parallel and field bus communication, Profibus

- Option 16-1 with Connection to cabinet
- (Option 92-2,-3 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	1+1	1+1	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	4	4 (2x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	4	0,14 mm ²	Profibus 12 Mbit/s spec
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Servo motor signals				
Servo motor power	At drive	3	1,5 mm ²	600 VAC, 12 A rms
Protective earth	At drive	1	1,5 mm ²	600 VAC
Signals twisted pair for resolver	-	6 ^a	0,23 mm ²	50 V DC, 1 A rms
Brake	-	2	0,23 mm ²	50 V DC, 1 A rms
Temperature control/PTC	-	2	0,23 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱ	Max. air pressure 16 bar/230 PSI. Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² ii	600 VAC, 150 A rms at 20°C (68°F)
Protective earth (Lower and Upper arm)		1		

ⁱ For LeanID 2x1/2" + 2x3/8", only upper arm

ⁱⁱ For LeanID upper arm 25 mm², only upper arm, 135 A rms

Continues on next page

a. Interface only at axis 3 or axis 6.

Continues on next page

2 DressPack

2.6.2 Configuration result for Type Se

Continued

DressPack Type Se. Parallel and field bus communication, Ethernet

- Option 16-1 with Connection to cabinet
- (Option 859-1, -2,-3, -4 to specify cable length)
- (Option 94-1, -2, -3, -4 to specify cable length)
- Option 455-8. Parallel and Ethernet communication
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm
- Option 798-3. External routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-4 (and Option 798-3). Internal routing

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms
Protective earth		1	0,5 mm ²	250 VAC
Customer signals (CS)				
Signals twisted pair	20	20 (10x2)	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (Ethernet)				
Bus signals	4	4	0,4 mm ²	Ethernet CAT 5e, 100 Mbit ⁱ
Servo motor signals				
Servo motor power	At drive	3	1,5 mm ²	600 VAC, 12 A rms
Protective earth	At drive	1	1,5 mm ²	600 VAC
Signals twisted pair for resolver	-	6 ⁱⁱ	0,23 mm ²	50 V DC, 1 A rms
Brake	-	2	0,23 mm ²	50 V DC, 1 A rms
Temperature control/PTC	-	2	0,23 mm ²	50 V DC, 1 A rms
Media				
Water/Air (PROC 1-4)		4	12.5 mm inner diameter ⁱⁱⁱ	Max. air pressure 16 bar/230 PSI. Max. water pressure 10 bar/145 PSI.
Welding power (WELD)				
Lower and Upper arm		2	35 mm ² iv	600 VAC, 150 A rms at 20°C (68°F)
Protective earth (Lower and Upper arm)		1		

ⁱ Ethernet with wire colors according to PROFINET standard, M12-connectors.

ⁱⁱ Interface only at axis 3 or axis 6.

Continues on next page

- iii For LeanID 2x1/2" + 2x3/8", only upper arm
- iv For LeanID upper arm 25 mm², only upper arm, 135 A rms

Required general options for Type Se

To enable the Spot welding function package IRB 6650S to perform as intended, general standard robot options are required. These standard options are further described under other chapters and are also mentioned in this chapter.

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply

Required options for servo gun

To enable the spot welding function package 6650S to run with a servo controlled gun, some additional (additional to those described in previous section "Required general options for Type Se") servo drive options are required. These standard options are described under other chapters and are also mentioned below in this chapter.

- Option 770-4. First additional drive, W Drive
- Option 864-1. Resolver connection, axis 7
- Option 785-1. Robot Gun
- Option 786-1,-2,-3,-4. Connection to first drive (cable length to be stated)
- Option 635-3. Spot Servo. Software option for servo controlled guns.
- (Software option 635-4 and option 635-5 could also be used)

Also option 630-1, Servo tool change, should be added if servo gun tool change is required.

2 DressPack

2.6.3 Summary Type Se

2.6.3 Summary Type Se

General

The following options are the minimum required to form a complete Spot welding function Type Se.

DressPack

- Option 16-1. Connection to cabinet, (Cable length and communication type to be stated)
- Option 455-1, 455-4. Parallel or Parallel and Bus communication (Communication type to be stated)
- Option 778-2. Spot Welding
- Option 798-2. External routing, DressPack Lower arm (Routing type to be stated)
- Option 780-2. External routing, DressPack Upper arm (Routing type to be stated)



Note

See [Robot Gun on page 65](#) for further drive details.

General options

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
 - Option 727-1. 24V 8 Amps power supply
-

Required options for servo gun

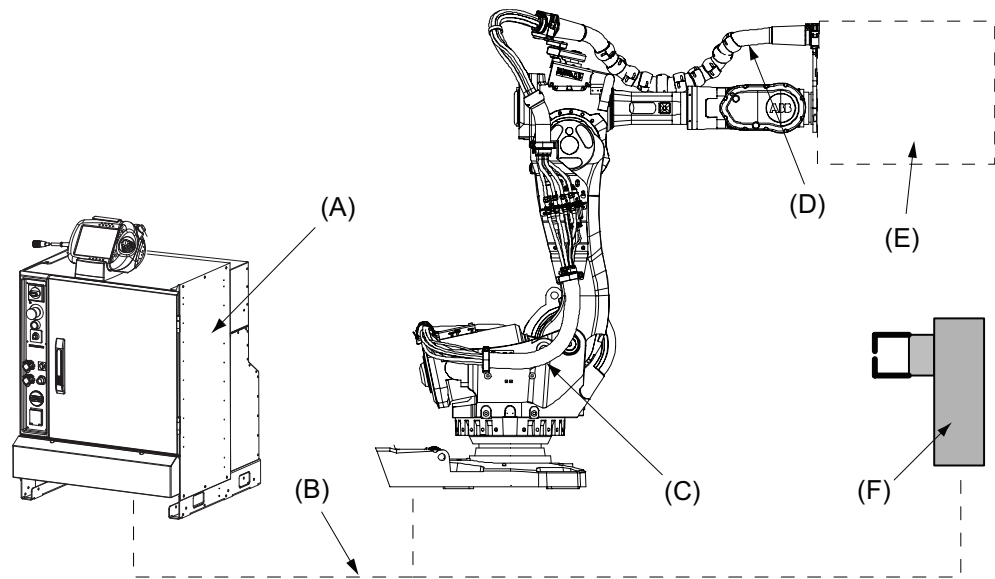
- Option 770-4. First additional drive, W Drive
- Option 785-1. Robot Gun
- Option 786-1,-2,-3,-4. Connection to first drive (cable length to be stated)
- Option 635-3. Spot Servo

2.7 Type HSe

2.7.1 Introduction

General

Variant Type HSe is designed for handling against a stationary mounted Spot Welding servo controlled tool (electrical gun). Included main modules are shown in Figure below. Available configurations with linked option numbers are described below with starting with the DressPack.



xx100000519

Pos	Name
A	Robot Cabinet IRC5 (incl. 7 th axis drive)
B	DressPack, Floor
C	DressPack, Lower arm
D	DressPack, Upper arm
E	Robot Gripper
F	Stationary gun with axis 7

Available configurations with linked option numbers are described below.

Option description

Option	Type	Description
16-1	Connection to cabinet	Floor cables and connections inside the I/O section for the DressPack are chosen. The length and configuration of the floor harness is specified under the options below. Option 94-1,-2,-3,-4 for parallel communication. Option 90-2,-3,-4,-5 for parallel communication and field bus communication with Can/DeviceNet. Option 92-2,-3 for parallel communication and field bus communication with Profibus.

Continues on next page

2 DressPack

2.7.1 Introduction

Continued

Option	Type	Description
455-1	Parallel communication	Offers the signal cables needed for parallel communication in lower and upper arm DressPack. To be combined with option 94-1,-2,-3,-4,-5.
455-4	Parallel and Bus communication	Offers the signal cables needed for the combination of parallel and bus communication in lower and upper arm DressPack. To be combined with option 90-2,-3,-4,-5 or 92-2,-3.
455-8	Parallel and Ethernet	Offers the signal cables needed for the Ethernet communication in combination in lower and upper arm DressPack. To be combined with option 859-1,-2,-3,-4. Requires selection of option 94-X.

The available alternatives and allowed combinations are shown in the schematic table below.

Application Interface connected to Option 16-1, Cabinet	Option 455-1, Parallel communication	Option 94-1,-2,-3,-4 Cable length, Parallel communication	Option 778-1, Material Handling
	Option 455-4, Parallel and bus communication	Option 90-2,-3,-4,-5 Option 92-2,-3 Cable length, Parallel and bus communication	
	Option 455-8, Parallel and Ethernet communication	Option 859-1, -2, -3, -4 Cable length, Ethernet communication	

Continued

	Lower arm	Upper arm
Option 778-1, Material Handling	Option 798-3, Base to axis 3	Option 780-3, -4, Axis 3 to 6 External routing
	Option 798-2, Base to axis 2	Option 780-2, Axis 2 to 6 External routing

2.7.2 Configuration result for Type HSe

General

Depending on the choice of options above the DressPack will have different content. The choice of routing will not affect the content. See tables for signal content below.

DressPack Type HSe. Parallel communication

- Option 16-1 with Connection to cabinet
- (Option 94-1,-2,-3,-4 to specify cable length)
- Option 455-1. Parallel communication
- Option 778-1 Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth		1 ^a	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2) ^c	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60 VDC.

c. For option 780-3 8 signals instead of 20.

Continues on next page

2 DressPack

2.7.2 Configuration result for Type HSe

Continued

DressPack Type HSe. Parallel and field bus communication, Can/DeviceNet

- Option 16-1 with Connection to cabinet
- (Option 90-1,-2,-3,-4 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At Connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth		1 ^a	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2) ^c	0,23 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,23 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	2	0,14 mm ²	Can/DeviceNet spec
Bus signals	At bus board	2	0,23 mm ²	50 V DC, 1 A rms
Signals twisted pair	6	6(3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60 VAC.

c. For option 780-3 8 signals instead of 20.

Continues on next page

DressPack Type HSe. Parallel and field bus communication, Profibus

- Option 16-1 with Connection to cabinet
- (Option 92-1,-2 to specify cable length)
- Option 455-4. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ^b
Protective earth		1 ^a	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	22	22 (11x2) ^c	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (CBus)				
Bus signals	At bus board	4	0,14 mm ²	Profibus 12 Mbit/s spec
Signals twisted pair	6	6 (3x2)	0,14 mm ²	50 V DC, 1 A rms
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

a. Not included in option 780-3.

b. For option 780-3 50 VAC / 60 VDC.

c. For option 780-3 8 signals instead of 22.

Continues on next page

2 DressPack

2.7.2 Configuration result for Type HSe

Continued

DressPack Type HSe. Parallel and field bus communication, Ethernet

- Option 16-1 with Connection to cabinet
- (Option 859-1,-2, -3, -4 to specify cable length)
- (Option 94-1, -2, -3, -4 to specify cable length)
- Option 455-8. Parallel and bus communication
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm

One of the options:

- Option 780-2 (and Option 798-2). External routing with retract arm
- Option 780-3, -4 (and Option 798-3). External routing, DressPack Upper arm

The table below shows the available type of wires/media.

Type	At terminals in cabinet	At connection point. Base, Axis 2/3 or axis 6	Cable/part area	Allowed capacity
Customer Power (CP)				
Utility Power	2+2	2+2	0,5 mm ²	250 VAC, 5 A rms ⁱ
Protective earth		1	0,5 mm ²	250 VAC ^a
Customer Signals (CS)				
Signals twisted pair	20	20 (10x2) ⁱⁱ	0,24 mm ²	50 V DC, 1 A rms
Signals twisted pair and separate shielded	8	8 (4x2)	0,24 mm ²	50 V DC, 1 A rms
Customer bus (Ethernet)				
Bus signals	4	4	0,4 mm ²	Ethernet CAT 5e, 100 Mbit ⁱⁱⁱ
Media				
Air (PROC 1)		1	12,5 mm inner diameter	Max. air pressure 16 bar/230 PSI

ⁱ For option 780-3 50 VAC / 60 VDC.

ⁱⁱ For option 780-3 8 signals instead of 20.

ⁱⁱⁱ Ethernet with wire colors according to PROFINET standard, M12-connectors.

Continues on next page

Required general options for Type HSe

To enable the Spot welding function package IRB 6650S to perform as intended, general standard robot options are required. These standard options are further described under other chapters and are also mentioned in this chapter.

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply

Required options for servo gun

To enable the Spot welding function package 6650S to run with a servo controlled gun, some additional (additional to those described in previous section "Required general options for Type Se") servo drive options are required. These standard options are described under other chapters and are also mentioned below in this chapter.

- Option 770-4. First additional drive, W Drive
- Option 864-1. Resolver connection, axis 7
- Option 785-5. Stationary gun
- Option 786-1,-2,-3,-4. Connection to first drive (cable length to be stated)
- Option 635-3. Spot Servo. Software option for servo controlled guns.
- (Software option 635-5 could also be used)

Also option 630-1, Servo tool change, should be used if servo gun tool change is required.

2 DressPack

2.7.3 Summary Type HSe

2.7.3 Summary Type HSe

DressPack

The following options are the minimum required to form a complete Spot welding function Type HSe:

- Option 16-1. Connection to cabinet, (Cable length and communication type to be stated)
- Option 455-1, 455-4. Parallel or Parallel and Bus communication (Communicationtype to be stated)
- Option 778-1. Material Handling
- Option 798-2 or Option 798-3. Internal routing, DressPack Lower arm (Routing type to be stated)
- Option 780-2, 780-3, 780-4. External routing, DressPack Upper arm (Routing type to be stated)

General options

- Option 716-1. 1 pc. Digital 24 VDC I/O 16 inputs/ 16 outputs
- Option 727-1. 24V 8 Amps power supply

Required options for servo gun

- Option 770-4. First additional drive, W Drive
- Option 785-5. Stationary gun
- Option 786-1. Connection to first drive (other lengths available)
- Option 635-3. Spot Servo. Software option for servo controlled guns

2.8 Connection kits

General

For detailed information on connection location see [Interface descriptions for DressPack on page 78](#)

Below is an example of a connector kit and its parts.



xx130000223

Continues on next page

2 DressPack

2.8 Connection kits

Continued

Base - Connector kits

		DressPack options		Resolver conn., axis 7	Description
Option	Name	798-2	798-3	864-1	
459-1	CP/CS, Proc 1 on base	X	X		
453-1	FB 7			X	

Option 459-1, CP/CS, Proc 1 on base

R1. CP/CS and Proc 1 on base.

This option offers a kit with connectors. This must be assembled by the customer.

The kit contains:

- 1 Hose fittings (Parker Pushlock, (1/2", M22x1,5 Brass, 24 degree seal))
- Connector with:

1 pcs Hood Foundry (Harting)	HAN EMC / M 40
1 pcs Hinged frame (Harting)	Shell size 16
2 pcs Multicontact, female (Harting)	Type HD (25 pin)
1 pcs Multicontact, female (Harting)	Type DD (12 pin)
1 pcs Multicontact, female (Harting)	Type EE (8 pin)
10 pcs Female crimp contacts	For 1,5 mm ²
10 pcs Female crimp contacts	For 0,5 mm ²
10 pcs Female crimp contacts	For 1,0 mm ²
10 pcs Female crimp contacts	For 2,5 mm ²
12 pcs Female crimp contacts	For 0,14– 0,37 mm ²
45 sockets	For 0,2– 0,56 mm ²
Assembly Accessories to complete connector	
Assembly instruction	

Option 453-1, FB 7

R3. FB 7 on base

This option offers a kit with a connector. This must be assembled by the customer.

The kit contains:

- Connector with:

1 pcs Multiple connector (pin)	Souriau
1 pcs Adaptor	8 pin
15 pcs Pin	for 0,13-0,25 mm ²
Assembly Accessories to complete connector	
Assembly instruction	

Continues on next page

Axis 2 - Connector kits

		DressPack option	Description
Option	Name	798-2 (MH/SW 2)	
458-1	CP/CS, Proc 1 axis 3	X	4 module Harting
479-1	Weld, Proc 2-4 axis 3	X	MC

Option 458-1, CP/CS, Proc 1 axis 3

R2. CP/CS and Proc 1 on axis 2/3

This option offers a kit with connectors. This must be assembled by the customer.

The kit contains:

- 1 Hose fittings (Parker Pushlock, (1/2", M22x1,5 Brass, 24 degree seal))
- Connector with:

1 pcs Hood Foundry (Harting)	HAN EMC / M 40
1 pcs Hinged frame (Harting)	Shell size 16
2 pcs Multicontact, male (Harting)	Type HD (25 pin)
1 pcs Multicontact, male (Harting)	Type DD (12 pin)
1 pcs Multicontact, male (Harting)	Type EE (8 pin)
10 pcs Male crimp contacts	For 1,5 mm ²
10 pcs Male crimp contacts	For 0,5 mm ²
10 pcs Male crimp contacts	For 1,0 mm ²
10 pcs Male crimp contacts	For 2,5 mm ²
12 pcs Male crimp contacts	For 0,14 – 0,37 mm ²
45 pin	For 0,2 – 0,56 mm ²
Assembly Accessories to complete connector	
Assembly instruction	

Option 479-1, Weld, Proc 2-4 axis 3

R2. Weld and Proc 2-4 on axis 2/3

This option offers a kit with weld connector and fittings. This must be assembled by the customer.

The kit contains:

- 3 Hose fittings (Parker Pushlock, (1/2", M22x1,5 Brass, 24 degree seal))
- Weld connector with:

1 pcs Welding connector pin with flange (MC)	3x35 mm2 (25 mm2 pin)
1 pcs Cable gland, plastic	Diameter 24-28 mm
Assembly Accessories to complete connector	
Assembly instruction	

Continues on next page

2 DressPack

2.8 Connection kits

Continued

Axis 3 - Connector kits

		DressPack options	Description
Option	Name	798-3	
458-1	CP/CS/CBUS/SP/SS, Proc 1 axis 3	X	UTOW

Option 458-1, CP/CS/CBus/SP/SS, Proc 1 axis 3

CP/CS/CBus/SP/SS, Proc 1 axis 3 on tool side for option 780-3 and 780-4.

This kit offers a kit with connectors to be mounted at toolside of axis 3.

This must be assembled by the customer.

The kit contains:

- 1 Hose fitting (Parker Push lock (1/2", M22x1,5 Brass, 24 degree seal))
- Connector with:

CP/CS	
1 pcs UTOW Pin connector 26p, bulkhead	UTOW71626PH05, Shell size 16
26 pcs Pin	RM18W3K, 0.21-0.93 mm ²
CBUS	
1 pcs UTOW Pin connector 10p, bulkhead	UTOW71210PH05 Shell size 12
10 pcs Pin	RM18W3K, 0.21-0.93 mm ²
Ethernet	
1 pcs Socket connector M12	Harting 2103 88
4 pcs Socket	Harting 61 03 0, 0.13-0.33 mm ²
SP (Servo Power)	
1 pcs Bulkhead contact M23	
4 pcs Crimp pin 1 mm	AWG 24-17
4 pcs Crimp pin 2 mm	AWG 18-14
SS (Servo Signal)	
1 pcs Bulkhead contact M23	
17 pcs Pin	AWG 28-20
Assembly Accessories to complete connector	
Assembly instruction	

Continues on next page

Axis 6 - Connector kits

Option	Name	780-2 (MH/SW 2)	780-3 (MH 3)	480- 4(LeanID)	Description
452-1	Weld, Proc 1-4 axis 6	X		X	MC
543-1	CP/CS/CBUS/SP/SS Proc 1 axis 6	X	X	X	UTOW

Option 543-1, CP/CS/CBus, Proc 1 axis 6

Harting

CP/CS/CBus, Proc 1 axis 6 on tool side for option 780-2.

This kit offers a kit with connectors to be mounted at toolside of axis 6.

This must be assembled by the customer.

The kit contains:

- 1 Hose fitting (Parker Push lock (1/2", M22x1,5 Brass, 24 degree seal))
- Connector with:

1 pcs Hood Foundry (Harting)	HAN
1 pcs Hinged frame (Harting)	Shell size 10
1 pcs Multicontact, male (Harting)	Type HD (25 pin)
1 pcs Multicontact, male (Harting)	Type DD (12 pin)
1 pcs Multicontact, male (Harting)	Type EE (8 pin)
10 pcs Male crimp contacts	For 1,5 mm ²
10 pcs Male crimp contacts	For 0,5 mm ²
10 pcs Male crimp contacts	For 1,0 mm ²
10 pcs Male crimp contacts	For 2,5 mm ²
15 pcs Male crimp contacts	For 0,14 – 0,37 mm ²
30 pins	For 0,2 – 0,56 mm ²
Assembly Accessories to complete connector	
Assembly instruction	

Continues on next page

2 DressPack

2.8 Connection kits

Continued

Souriau

CP/CS/CBus/SP/SS, Proc 1 axis 6 on tool side for option 780-3 and 780-4.

This kit offers a kit with connectors to be mounted at toolside of axis 6.

This must be assembled by the customer.

The kit contains:

- 1 Hose fitting (Parker Push lock (1/2", M22x1,5 Brass, 24 degree seal))
- Connector with:

CP/CS	
1 pcs UTOW Pin connector 26p, bulkhead	UTOW71626PH05, Shell size 16
26 pcs Pin	RM81W3K, 0.21-0.93 mm ²
CBUS	
1 pcs UTOW Pin connector 10p, bulkhead	UTOW71210PH05 Shell size 12
10 pcs Pin	RM18W3K, 0.21-0.93 mm ²
Ethernet	
1 pcs Socket connector M12	Harting 2103 88
4 pcs Socket	Harting 61 03 0, 0.13-0.33 mm ²
SP (Servo Power)	
1 pcs Bulkhead contact M23	
4 pcs Crimp pin 1 mm	AWG 24-17
4 pcs Crimp pin 2 mm	AWG 18-14
SS (Servo Signal)	
1 pcs Bulkhead contact M23	
17 pcs Pin	AWG 28-20
Assembly Accessories to complete connector	
Assembly instruction	

Option 452-1, Weld, Proc 1-4 axis 6

Weld and Proc 1-4 axis 6 on manipulator side

The process cable package from axis 2 to axis 6 (option 780-2) ends with free end for media and for weld power cable. The option 452-1 offers a kit for connectors. This must be assembled by the customer when hoses and power cable has been cut to required length.

The kit contains:

- 4 Hose fittings (Parker Pushlock, (1/2", M22x1,5 Brass, 24 degree seal))
- 1 Multi contact connector (Female) type including:

1 pc Welding connector socket incl. housing	3x35 mm ² (35 mm ² socket)
1 pc Cable gland	
1 pc End housing	
Assembly Accessories to complete connector	
Assembly instruction	

3 Specification of variants and options

3.1 Introduction to variants and options

General

The different variants and options for the IRB 6650S are described in the following sections. The same option numbers are used here as in the specification form.

The variants and options related to the robot controller are described in the product specification for the controller.

3 Specification of variants and options

3.2 Manipulator

3.2 Manipulator

Variants

Option	IRB Type	Handling capacity (kg)/Reach (m)
435-69	6650S	90/3.9
435-50	6650S	125/3.5
435-51	6650S	200/3.0

Manipulator color

Option	Description	Note
209-1	ABB Orange standard	
209-202	ABB Graphite White standard	Standard color
209-4 --192	Colors according to RAL-codes	



Note

Notice that delivery time for painted spare parts will increase for none standard colors.

Protection types

Option	Protection type	Note
287-4	Standard	IP 67
287-3	Foundry Plus 2	See Protection type Foundry Plus 2 on page 11 for a complete description of protection type Foundry Plus 2.

Warranty

For the selected period of time, ABB will provide spare parts and labour to repair or replace the non-conforming portion of the equipment without additional charges. During that period, it is required to have a yearly Preventative Maintenance according to ABB manuals to be performed by ABB. If due to customer restrains no data can be analyzed in the ABB Ability service *Condition Monitoring & Diagnostics* for robots with OmniCore controllers, and ABB has to travel to site, travel expenses are not covered. The Extended Warranty period always starts on the day of warranty expiration. Warranty Conditions apply as defined in the Terms & Conditions.




Note

This description above is not applicable for option *Stock warranty* [438-8]

Option	Type	Description
438-1	Standard warranty	Standard warranty is 12 months from <i>Customer Delivery Date</i> or latest 18 months after <i>Factory Shipment Date</i> , whichever occurs first. Warranty terms and conditions apply.

Continues on next page

Option	Type	Description
438-2	Standard warranty + 12 months	Standard warranty extended with 12 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-4	Standard warranty + 18 months	Standard warranty extended with 18 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-5	Standard warranty + 24 months	Standard warranty extended with 24 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-6	Standard warranty + 6 months	Standard warranty extended with 6 months from end date of the standard warranty. Warranty terms and conditions apply.
438-7	Standard warranty + 30 months	Standard warranty extended with 30 months from end date of the standard warranty. Warranty terms and conditions apply.
438-8	Stock warranty	<p>Maximum 6 months postponed start of standard warranty, starting from factory shipment date. Note that no claims will be accepted for warranties that occurred before the end of stock warranty. Standard warranty commences automatically after 6 months from <i>Factory Shipment Date</i> or from activation date of standard warranty in WebConfig.</p> <p> Note</p> <p>Special conditions are applicable, see <i>Robotics Warranty Directives</i>.</p>

Warranty for DressPack



Note

Option 780-2 upper arm DressPack SW/HM2 is not covered by warranty.



Note

Option 780-3 upper arm DressPack HM3 is not covered by warranty.



Note

Option 780-4 DressPack LeanID is covered by the warranty.

3 Specification of variants and options

3.3 Equipment

3.3 Equipment

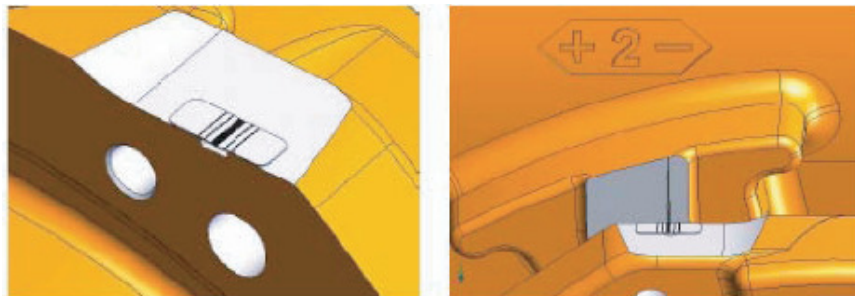
General

Option	Type	Description
213-1	Safety lamp	A safety lamp with an orange fixed light can be mounted on the manipulator. The lamp is active in MOTORS ON mode. The safety lamp is required on a UL/UR approved robot.
159-1	Fork lift device	Lifting device on the manipulator for fork-lift handling. Note. When Cooling Fan for axis 1 motor unit is used, this must be disassembled in order to use fork lift device.
37-1	Base plate	Can be used for IRB 6650S and IRB 7600. See Installation on page 19 , for dimension drawing.
87-1	Cooling fan for axis 1 motor (IP 54)	Cannot be combined with Cooling fan for axis 2 motor option 88-1. For in use recommendations see Cooling fan for axis 1 and 2 motor on page 62 . Not for protection Foundry Plus. Not together with track motion.
88-1	Cooling fan for axis 2 motor (IP 54)	For in use recommendations see Cooling fan for axis 1 and 2 motor on page 62 . Not for protection Foundry Plus. Not together with track motion.
430-1	Upper arm covers	See Figure in Upper arm covers on page 140 . Included in protection Foundry Plus.
804-1	Labels for synchronization markings	For a more accurate marking of the synchronization position of the robot. Assembly instructions are included. See Figures for Synchronize labels, axis 2 - 6.

Synchronize labels

The option contains synchronize labels for each axis.

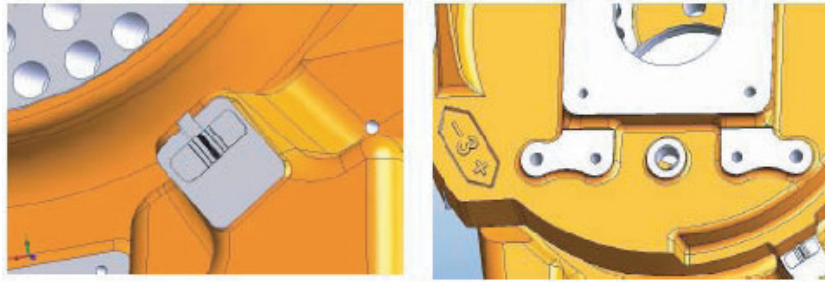
Synchronize labels for Axis 2



xx100000524

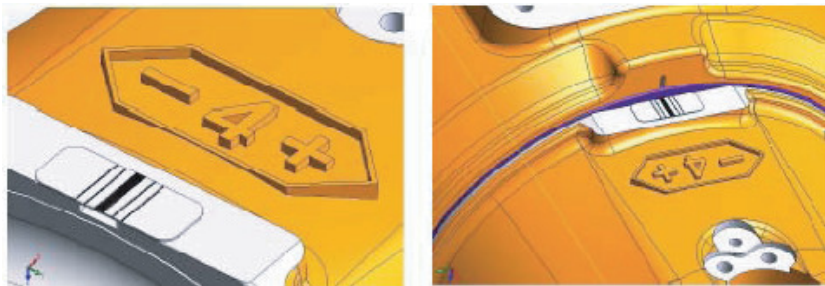
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Synchronize lables for Axis 3



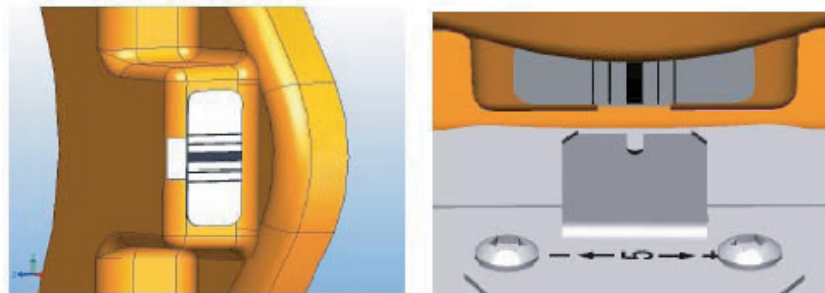
xx1000000525

Synchronize lables for Axis 4



xx1000000526

Synchronize lables for Axis 5



xx1000000527

Synchronize lables for Axis 6



xx1000000528

Continues on next page

3 Specification of variants and options

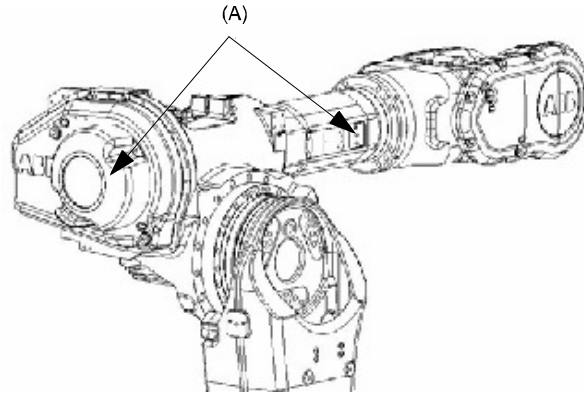
3.3 Equipment

Continued

Resolver connection, axis 7

Option	Description	Note
864-1	On base	Used together with first additional drive, option 907-1.

Upper arm covers



xx100000529

Pos	Description
A	Option 430-1

Electronic Position Switches (EPS)

The mechanical position switches indicating the position of the three main axes are replaced with electronic position switches for up to 7 axes, for increased flexibility and robustness. For more detailed information, see *Product specification - Controller IRC5* and *Application manual - Electronic Position Switches*.

Foundry Plus Cable Guard

The manipulator cables are equipped with an additional protection of aluminized leather against e.g. aluminium spitz and flashes and chips from machining. Process cable for material handling from base to axis 3, option 798-3 has the same protection

Option	Description	Remark
908-1	Foundry Plus Cable Guard	For extra protection of cables. Requires option 287-3 Foundry Plus.

Working Range Limit

To increase the safety of the robot, the working range of axes 1, 2 and 3 can be restricted by extra mechanical stops.

Option	Type	Description
29-1	Axis 1, 15 degrees	Two stops which allow the working range to be restricted in increments of 15°.
29-2	Axis 1, 7.5 degrees	Two stops which allow the working range to be restricted in increments of 7,5°.

Continues on next page

Option	Type	Description
32-1	Axis 2	Six stops which allow the working range to be restricted in increments of 15° at both end positions. Each stop decreases the motion by 15°.
34-1	Axis 3	Six stops which allow the working range to be restricted in increments of 20° at both end positions. Each stop decreases the motion by 20°.

Extended work range

Option	Type	Description
561-1	Extended work range axis 1	To extend the working range on axis 1 from ± 180° to ± 220°. When the option is used the mechanical stop shall be disassembled. EPS (Electronic Position Switches) functionality (option 810-1 or -2) is required.



CAUTION

The option *Extended work range* enables an extension of the working range for axis 1, through a software configuration. With this option installed, the working range can exceed the range limited by the mechanical stop on axis 1. The working range shall be limited through the option *SafeMove*.

A risk analysis must be done to ensure that no risks remain when using option *Extended work range*, to limit the working range, and before removing the mechanical stops.

For information about the option *SafeMove*, see *Application manual - Functional safety and SafeMove2*.

If the mechanical stop is removed, then the manipulator should have a marking for this, for example, a label. If the robot is delivered with the option *Extended work range*, then such a label is included on delivery.

Standard calibration method

Option	Type	Description
1999-1	Axis calibration	Preferred standard calibration method. Robust, high performance axis calibration using only mechanical calibration stops and software.
1999-2	Calibration Pendulum	Previous standard calibration method only to be used in special cases if customers would like to harmonize calibration with already installed base.



Note

The calibration methods are not interchangeable.

3 Specification of variants and options

3.4 Floor cables

3.4 Floor cables

Manipulator cable length

Option	Lengths
210-2	7 m
210-3	15 m
210-4	22 m
210-5	30 m

3.5 Process DressPack

Connection to

Option	Connection to	Description
16-1	Cabinet	The signals CP/CS are connected to 12-pole screw terminals, Phoenix MSTB 2.5/12-ST-5.08, in the controller. The cable between R1.CP/CS and the controller is supplied. For information about the limited number of signals available, see Type H on page 87 to Type S on page 94

Communication

Option	Type	Description
455-1	Parallel communication	Includes customer power CP, customer signals CS.
455-4	Parallel and bus communication	Includes CP, customer signals and CAN/DeviceNet or Profibus for process cable package.
455-8	Parallel and Ethernet communication	Includes CP, customer signals and PROFINET or Ethernet/IP for process cable package

3 Specification of variants and options

3.6 DressPack Floor

3.6 DressPack Floor

Connection to Parallel/CAN DeviceNet/Profibus/Ethernet

Following information specifies the cable length for Parallel/CANDeviceNet/Profibus for connection to cabinet.

Option	Lengths	Description
94-1/90-2/92-2/859-1	7 m	
94-2/90-3/92-3/859-2	15 m	
90-4/92-4/859-3	22 m	
94-4/90-5/92-5/859-4	30 m	

3.7 DressPack Lower and Upper arm

DressPack process configuration



Note

For more information about the process cable packages, see 1.2 DressPack.

Option	Description	Note
778-1	Material Handling	Includes signals and one air hose.
778-2	Spot Welding	Includes signals, weld power cable, one air hose and three media hoses.

DressPack lower arm

Option	Description	Note
798-2	Routing from base to axis 2	
798-3	Routing from base to axis 3	

DressPack upper arm

Option	Description	Note
780-2	External routing from axis 2 to axis 6	Requires option 798-2.
780-3	External routing from axis 3 to axis 6	Requires option 778-1 and 798-3.
780-4	Internal routing from axis 3 to axis 6	Requires option 798-3.



Note

If option 780-4, LeanID, is selected the payload will decrease, for detailed information see Load diagrams.

3 Specification of variants and options

3.8 Connection Kits

3.8 Connection Kits

General

The connectors fit to the connectors at the manipulator base, axis 2/3 and 6 respectively.

Content

The kit consists of connectors, pins and sockets. For technical description, see [Connection kits on page 129](#).

Option	Type	Description
459-1	R1.CP/CS and PROC1	For the Customer Power/Customer Signal connector and one Process connector on the manipulator base. Sockets for bus communication are included.
453-1	R3.FB7	For the 7-axis connector on the manipulator base.
458-1	R2.CP/CS and PROC1	For the Customer Power/Customer Signal connector and one Process connector at axis 2/3. Pins for bus communication are included.
452-1	WELD and PROC1-4 axis 6	Weld connector and four Process connectors at axis 6, the manipulator side.
543-1	CP/CS/BUS, PROC1 axis 6	Connector for customer power/customer signal/customer bus at axis 6 tool side.

3.9 Servo Gun

Content

For technical description see [Servo gun on page 63](#).

Option	Lengths
785-1	For robot handled Servo Gun.
785-5	For Stationary Servo Gun.

Connection to first drive

Following information specifies the cable length for Connection to first drive. For further information see [Servo gun on page 63](#).

Option	Lengths
786-1	7 m
786-2	15 m
786-3	22 m
786-4	30 m

3 Specification of variants and options

3.10 User documentation

3.10 User documentation

User documentation

The user documentation describes the robot in detail, including service and safety instructions.



Tip

All documents can be found via myABB Business Portal, www.abb.com/myABB.

4 Accessories

4.1 Introduction to accessories

General

There is a range of tools and equipment available, especially designed for the manipulator.

Basic software and software options for robot and PC

For more information, see *Product specification - Controller IRC5* and *Product specification - Controller software IRC5*.

Robot peripherals

- Track Motion
- Motor Units

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