

ROBOTICS

Product manual

IRB 910SC



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Original instructions.

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Table of contents

Overview of this manual	9
Product documentation	13
How to read the product manual	15
1 Safety	17
1.1 Safety information	17
1.1.1 Limitation of liability	17
1.1.2 Requirements on personnel	18
1.2 Safety signals and symbols	19
1.2.1 Safety signals in the manual	19
1.2.2 Safety symbols on manipulator labels	21
1.3 Robot stopping functions	27
1.4 Installation and commissioning	28
1.5 Operation	31
1.5.1 Unexpected movement of robot arm	31
1.6 Maintenance and repair	32
1.6.1 Maintenance and repair	32
1.6.2 Emergency release of the robot axes	35
1.6.3 Brake testing	36
1.7 Troubleshooting	37
1.8 Decommissioning	38
2 Installation and commissioning	39
2.1 Introduction to installation and commissioning	39
2.2 Unpacking	40
2.2.1 Pre-installation procedure	40
2.2.2 Dimensions	44
2.2.3 Working range	46
2.2.4 Risk of tipping/stability	50
2.2.5 The unit is sensitive to ESD	52
2.3 On-site installation	53
2.3.1 Lifting robot with lifting accessories	53
2.3.2 Manually releasing the brakes	61
2.3.3 Orienting and securing the robot	63
2.3.4 Loads fitted to the robot, stopping time and braking distances	65
2.3.5 Fitting equipment on the robot	66
2.4 Restricting the working range	68
2.4.1 Axes with restricted working range	68
2.4.2 Mechanically restricting the working range	69
2.5 Electrical connections	71
2.5.1 Robot cabling and connection points	71
2.5.2 Customer connections	73
2.6 Start of robot in cold environments	75
3 Maintenance	77
3.1 Introduction	77
3.2 Service Information System (SIS)	78
3.3 Maintenance schedule	79
3.3.1 Specification of maintenance intervals	79
3.3.2 Maintenance schedule	80
3.4 Inspection activities	82
3.4.1 Inspecting the cabling	82
3.4.2 Inspecting the information labels	83
3.4.3 Inspecting the ball screw spline unit	86
3.4.4 Inspecting axis-1 and axis-2 mechanical stops	89
3.4.5 Inspecting the timing belts	92

Table of contents

3.5	Replacement/changing activities	100
3.5.1	Replacing the battery pack	100
3.6	Lubrication activities	111
3.6.1	Lubricating the ball screw spline unit	111
3.7	Cleaning activities	114
3.7.1	Cleaning the IRB 910SC	114
4	Repair	117
4.1	Introduction	117
4.2	General procedures	118
4.2.1	Cut the paint or surface on the robot before replacing parts	118
4.2.2	Mounting instructions for sealings	119
4.3	Cable harness	122
4.3.1	Replacing the main cable package	122
4.3.2	Replacing the EIB unit	146
4.3.3	Replacing the PCB board	156
4.3.4	Replacing the EIB mounting plate	164
4.3.5	Replacing the floor cables	183
4.3.6	Replacing the brake release harness	191
4.4	Upper arm	196
4.4.1	Replacing the upper arm	196
4.4.2	Replacing the ball screw spline unit	229
4.4.3	Replacing the axis-3 timing belt	246
4.4.4	Replacing the axis-4 timing belts	256
4.4.5	Replacing the axis-2 mechanical stop	271
4.5	Lower arm and base	276
4.5.1	Replacing the lower arm	276
4.5.2	Replacing the base	285
4.5.3	Replacing the axis-1 mechanical stop	296
4.6	Drive units	299
4.6.1	Replacing the axis-1 drive unit	299
4.6.2	Replacing the axis-2 drive unit	308
4.6.3	Replacing the axis-3 drive unit	319
4.6.4	Replacing the axis-4 drive unit	333
5	Calibration	345
5.1	Introduction to calibration	345
5.1.1	Introduction and calibration terminology	345
5.1.2	Calibration methods	346
5.1.3	When to calibrate	348
5.2	Synchronization marks and axis movement directions	349
5.2.1	Synchronization marks and synchronization position for axes	349
5.2.2	Calibration movement directions for all axes	350
5.3	Updating revolution counters	351
5.4	Calibrating the robot	355
5.4.1	Calibration position	355
5.4.2	Calibrating axis 1	356
5.4.3	Calibrating axis 2	361
5.4.4	Calibrating axis 3 and axis 4	366
5.5	Verifying the calibration	372
5.6	Checking the synchronization position	373
6	Decommissioning	375
6.1	Introduction	375
6.2	Environmental information	376
7	Reference information	377
7.1	Introduction	377

7.2	Applicable standards	378
7.3	Unit conversion	380
7.4	Specification of screws	381
7.5	Screw joints	382
7.6	Weight specifications	385
7.7	Standard toolkit	386
7.8	Special tools	387
7.9	Lifting accessories and lifting instructions	389
8	Spare parts	391
8.1	Spare part lists and illustrations	391
9	Circuit diagrams	393
9.1	Circuit diagrams	393
Index		395

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Overview of this manual

About this manual

This manual contains instructions for:

- mechanical and electrical installation of the robot
 - maintenance of the robot
 - mechanical and electrical repair of the robot.
-

Usage

This manual should be used during:

- installation, from lifting the robot to its work site and securing it to the foundation, to making it ready for operation
 - maintenance work
 - repair work and calibration.
-

Who should read this manual?

This manual is intended for:

- installation personnel
 - maintenance personnel
 - repair personnel.
-

Prerequisites

A maintenance/repair/installation craftsman working with an ABB Robot must:

- be trained by ABB and have the required knowledge of mechanical and electrical installation/repair/maintenance work.
-

Product manual scope

The manual covers covers all variants and designs of the IRB 910SC. Some variants and designs may have been removed from the business offer and are no longer available for purchase.

Organization of chapters

The manual is organized in the following chapters:

Chapter	Contents
Safety, service	Safety information that must be read through before performing any installation or service work on robot. Contains general safety aspects as well as more specific information on how to avoid personal injuries and damage to the product.
Installation and commissioning	Required information about lifting and installation of the robot.
Maintenance	Step-by-step procedures that describe how to perform maintenance of the robot. Based on a maintenance schedule that may be used to plan periodical maintenance.
Repair	Step-by-step procedures that describe how to perform repair activities of the robot. Based on available spare parts.

Continues on next page

Overview of this manual

Continued

Chapter	Contents
Calibration information	Procedures that do not require specific calibration equipment. General information about calibration.
Decommissioning	Environmental information about the robot and its components.
Reference information	Useful information when performing installation, maintenance or repair work. Includes lists of necessary tools, additional documents, safety standards, etc.
Spare parts and exploded views	Reference to the spare part list for the robot.
Circuit diagram	Reference to the circuit diagram for the robot.

References

Documentation referred to in the manual, is listed in the table below.

Document name	Document ID
<i>Product manual, spare parts - IRB 910SC</i>	<i>3HAC056433-001</i>
<i>Product specification - IRB 910SC</i>	<i>3HAC056431-001</i>
<i>Circuit diagram - IRB 910SC</i>	<i>3HAC056159-002</i>
<i>Product manual - IRC5 Compact</i>	<i>3HAC047138-001</i>
<i>Operating manual - IRC5 with FlexPendant</i>	<i>3HAC050941-001</i>
<i>Technical reference manual - Lubrication in gearboxes</i>	<i>3HAC042927-001</i>
<i>Technical reference manual - System parameters</i>	<i>3HAC050948-001</i>
<i>Operating manual - Emergency safety information</i>	<i>3HAC027098-001</i>
<i>Safety manual for robot - Manipulator and IRC5 or OmniCore controllerⁱ</i>	<i>3HAC031045-001</i>

ⁱ This manual contains all safety instructions from the product manuals for the manipulators and the controllers.

Revisions

Revision	Description
-	First edition.

Continues on next page

Revision	Description
A	<p>The following updates are done in this revision:</p> <ul style="list-style-type: none"> • Working range of axis 4 has been updated. See Working range on page 48. • The force and torque values under endurance load and maximum load have been updated. See Loads on foundation, robot on page 41. • The interval of lubricating the ball screw spline unit is modified to every 100 km. See Activities and intervals, standard equipment on page 80. • The grease for lubrication the ball screw spline unit is changed from AFB-LF to AFA. See "Required consumables" in Lubricating the ball screw spline unit on page 111 and Replacing the ball screw spline unit on page 229. • The spare part numbers of base and lifting labels have been changed. • The instruction label of lifting the robot has been changed. See Location of labels on page 83. • Washers and locking liquid Loctite 243 are used when refitting the base rear cover and floor cables, and at the same time, the tightening torque of related screws changes from 4.5 Nm to 2 Nm. • The tightening torque of the screws on base bottom cover is added, which is 2 Nm. • A caution reminding not to mix axis-1 and axis-2 drive units has been added in procedures of refitting the drive units. • Screws for fitting the calibration pins of axes 1 and 2 have been removed. See Calibrating axis 1 on page 357 and Calibrating axis 2 on page 362.
B	<ul style="list-style-type: none"> • Information about customer connectors has been added. See Customer connections on page 73. • Dimension drawing for fitting the end effector is updated. See Fitting of end effector to the ball screw spline shaft on page 66. • Information about the grease used for lubricating the ball screw spline is updated. • Locking liquid Loctite 243 is not required when refitting the base rear cover and floor cables. • Calibration tools are not provided as a package so that the calibration toolkit is removed. • Fixing calibration block of axes 3 and 4 is fixed to the upper arm so that related repairing procedures are removed. • Minor corrections.
C	<p>Published in release R17.1. The following updates are done in this revision:</p> <ul style="list-style-type: none"> • The spare part number of the lower cover of the upper arm is changed from 3HAC055203-001 to 3HAC060106-001. • Upper and lower axis-3 and axis-4 stop blocks on the ball screw spline unit are added as spare parts. • Unnecessary screws on the lower cover of the upper arm are removed so that related figures are updated. • Every 100 miles column in Maintenance schedule is removed, the maintenance interval of inspecting the timing belt is updated • The Protection class is changed from IP30 to IP20.

Continues on next page

Revision	Description
D	<p>Published in release R17.2. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Information about coupled axes in Updating revolution counters on page 351. Caution about removing metal residues added in sections about SMB/EIB boards. Information about minimum resonance frequency added. Updated list of applicable standards. Added text regarding overhaul in section specification of maintenance intervals. Section Start of robot in cold environments on page 75 added.
E	<p>Published in release R18.1. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Added sections in General procedures on page 118. Safety restructured. Added information about SIS function for ball screw spline unit in Troubleshooting on page 78. Information about myABB Business Portal added.
F	<p>Published in release R18.2. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Added equipment fitting note and updated the end effector dimension figure. Moved the robot dimension information to section Unpacking on page 40. Added customer connector information. Added replacement of brake release harness. Changed timing belt tension of axis 3 and axis 4.
G	<p>Published in release R18.2. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Updated references.
H	<p>Published in release 19B. The following updates are made in this revision:</p> <ul style="list-style-type: none"> New touch up color Graphite White available. See Cut the paint or surface on the robot before replacing parts on page 118. Corrected customer connector at the upper arm from R4.CP/CS to R3.CP/CS.
J	<p>Published in release 20A. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Clarified and added information in mounting instructions for rotating sealings, see Mounting instructions for sealings on page 119. Added AbsAcc label information. See Inspecting the information labels on page 83.
K	<p>Published in release 20D. The following updates are made in this revision:</p> <ul style="list-style-type: none"> Option 610-1 Independent axis is removed so that description about maximum revolution of axis 4 is removed.
L	<p>Published in release 21B. The following updates are done in this revision:</p> <ul style="list-style-type: none"> Text regarding fastener quality is updated, see Fastener quality on page 67. Text regarding diameter of air hoses is updated, see Customer connections on page 73. Added grounding point information, see Robot cabling and connection points on page 71.
M	<p>Published in release 21C. The following updates are done in this revision:</p> <ul style="list-style-type: none"> Updated the naming of timing belt tension adjustment tools, from acoustic tensiometer and tensiometer to sonic tension meter and dynamometer, respectively.

Continues on next page

Product documentation

Categories for user documentation from ABB Robotics

The user documentation from ABB Robotics is divided into a number of categories. This listing is based on the type of information in the documents, regardless of whether the products are standard or optional.

**Tip**

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

Product manuals

Manipulators, controllers, DressPack/SpotPack, and most other hardware is delivered with a **Product manual** that generally contains:

- Safety information.
- Installation and commissioning (descriptions of mechanical installation or electrical connections).
- Maintenance (descriptions of all required preventive maintenance procedures including intervals and expected life time of parts).
- Repair (descriptions of all recommended repair procedures including spare parts).
- Calibration.
- Decommissioning.
- Reference information (safety standards, unit conversions, screw joints, lists of tools).
- Spare parts list with corresponding figures (or references to separate spare parts lists).
- References to circuit diagrams.

Technical reference manuals

The technical reference manuals describe reference information for robotics products, for example lubrication, the RAPID language, and system parameters.

Application manuals

Specific applications (for example software or hardware options) are described in **Application manuals**. An application manual can describe one or several applications.

An application manual generally contains information about:

- The purpose of the application (what it does and when it is useful).
- What is included (for example cables, I/O boards, RAPID instructions, system parameters, software).
- How to install included or required hardware.
- How to use the application.
- Examples of how to use the application.

Continues on next page

Operating manuals

The operating manuals describe hands-on handling of the products. The manuals are aimed at those having first-hand operational contact with the product, that is production cell operators, programmers, and troubleshooters.

How to read the product manual

Reading the procedures

The procedures contain all information required for the installation or service activity and can be printed out separately when needed for a certain service procedure.

Safety information

The manual includes a separate safety chapter that must be read through before proceeding with any service or installation procedures. All procedures also include specific safety information when dangerous steps are to be performed.

Read more in the chapter [Safety on page 17](#).

Illustrations

The product is illustrated with general figures that does not take painting or protection type in consideration.

Likewise, certain work methods or general information that is valid for several product models, can be illustrated with illustrations that show a different product model than the one that is described in the current manual.

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1 Safety

1.1 Safety information

1.1.1 Limitation of liability

Limitation of liability

Any information given in this manual regarding safety must not be construed as a warranty by ABB that the industrial robot will not cause injury or damage even if all safety instructions are complied with.

The information does not cover how to design, install and operate a robot system, nor does it cover all peripheral equipment that can influence the safety of the robot system.

In particular, liability cannot be accepted if injury or damage has been caused for any of the following reasons:

- Use of the robot in other ways than intended.
- Incorrect operation or maintenance.
- Operation of the robot when the safety devices are defective, not in their intended location or in any other way not working.
- When instructions for operation and maintenance are not followed.
- Non-authorized design modifications of the robot.
- Repairs on the robot and its spare parts carried out by in-experienced or non-qualified personnel.
- Foreign objects.
- Force majeure.

Spare parts and equipment

ABB supplies original spare parts and equipment which have been tested and approved. The installation and/or use of non-original spare parts and equipment can negatively affect the safety, function, performance, and structural properties of the robot. ABB is not liable for damages caused by the use of non-original spare parts and equipment.

1 Safety

1.1.2 Requirements on personnel

1.1.2 Requirements on personnel

General

Only personnel with appropriate training are allowed to install, maintain, service, repair, and use the robot. This includes electrical, mechanical, hydraulics, pneumatics, and other hazards identified in the risk assessment.

Persons who are under the influence of alcohol, drugs or any other intoxicating substances are not allowed to install, maintain, service, repair, or use the robot.

The plant liable must make sure that the personnel is trained on the robot, and on responding to emergency or abnormal situations.

Personal protective equipment

Use personal protective equipment, as stated in the instructions.

1.2 Safety signals and symbols

1.2.1 Safety signals in the manual







Introduction to safety signals

This section specifies all safety signals used in the user manuals. Each signal consists of:

- A caption specifying the hazard level (DANGER, WARNING, or CAUTION) and the type of hazard.
- Instruction about how to reduce the hazard to an acceptable level.
- A brief description of remaining hazards, if not adequately reduced.

Hazard levels

The table below defines the captions specifying the hazard levels used throughout this manual.


Symbol	Designation	Significance
	DANGER	Signal word used to indicate an imminently hazardous situation which, if not avoided, will result in serious injury.
	WARNING	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in serious injury.
	ELECTRICAL SHOCK	Signal word used to indicate a potentially hazardous situation related to electrical hazards which, if not avoided, could result in serious injury.
	CAUTION	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in slight injury.
	ELECTROSTATIC DISCHARGE (ESD)	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in severe damage to the product.
	NOTE	Signal word used to indicate important facts and conditions.

Continues on next page

1 Safety

1.2.1 Safety signals in the manual

Continued

Symbol	Designation	Significance
	TIP	Signal word used to indicate where to find additional information or how to do an operation in an easier way.

1.2.2 Safety symbols on manipulator labels

Introduction to symbols

This section describes safety symbols used on labels (stickers) on the manipulator. Symbols are used in combinations on the labels, describing each specific warning. The descriptions in this section are generic, the labels can contain additional information such as values.



Note

The symbols on the labels on the product must be observed. Additional symbols added by the integrator must also be observed.




Types of symbols

Both the manipulator and the controller are marked with symbols, containing important information about the product. This is important for all personnel handling the robot, for example during installation, service, or operation.

The safety labels are language independent, they only use graphics. See [Symbols on safety labels on page 21](#).

The information labels can contain information in text.

Symbols on safety labels

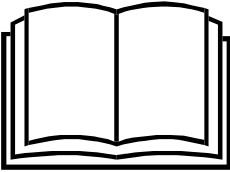
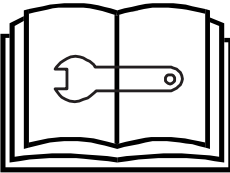
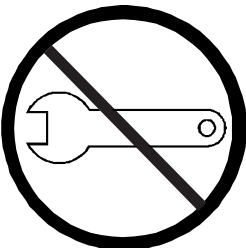
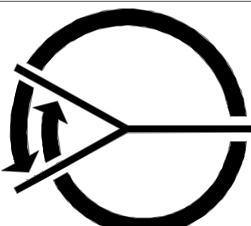

Symbol	Description
 xx0900000812	Warning! Warns that an accident <i>may</i> occur if the instructions are not followed that can lead to serious injury, possibly fatal, and/or great damage to the product. It applies to warnings that apply to danger with, for example, contact with high voltage electrical units, explosion or fire risk, risk of poisonous gases, risk of crushing, impact, fall from height, etc.
 xx0900000811	Caution! Warns that an accident may occur if the instructions are not followed that can result in injury and/or damage to the product. It also applies to warnings of risks that include burns, eye injury, skin injury, hearing damage, crushing or slipping, tripping, impact, fall from height, etc. Furthermore, it applies to warnings that include function requirements when fitting and removing equipment where there is a risk of damaging the product or causing a breakdown.
 xx0900000839	Prohibition Used in combinations with other symbols.

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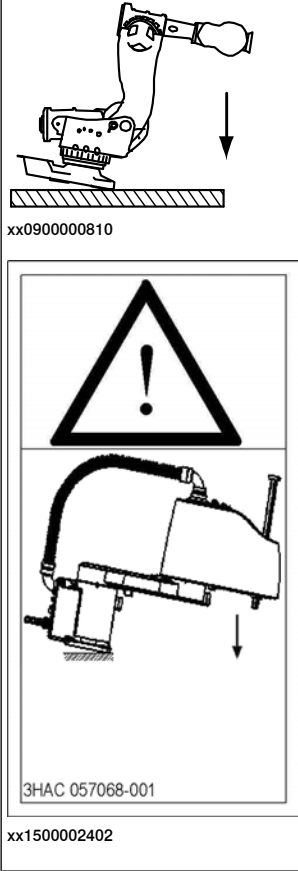

1 Safety

1.2.2 Safety symbols on manipulator labels

Continued

Symbol	Description
 xx0900000813	See user documentation Read user documentation for details. Which manual to read is defined by the symbol: <ul style="list-style-type: none">• No text: <i>Product manual</i>.• EPS: <i>Application manual - Electronic Position Switches</i>.
 xx0900000816	Before disassembly, see product manual
 xx0900000815	Do not disassemble Disassembling this part can cause injury.
 xx0900000814	Extended rotation This axis has extended rotation (working area) compared to standard.
 xx0900000808	Brake release Pressing this button will release the brakes. This means that the robot arm can fall down.



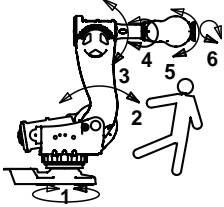
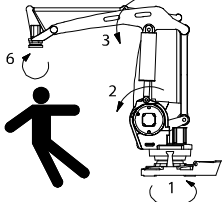
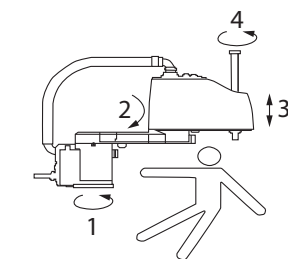
Continues on next page

Symbol	Description
 <p>xx0900000810</p> <p>3HAC 057068-001</p> <p>xx1500002402</p>	<p>Tip risk when loosening bolts The robot can tip over if the bolts are not securely fastened.</p>
 <p>xx0900000817</p>	<p>Crush Risk of crush injuries.</p>

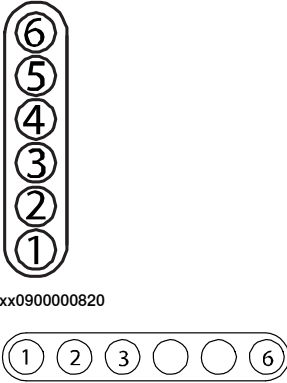

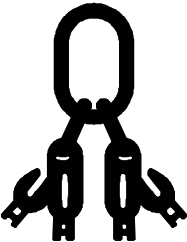



1 Safety

1.2.2 Safety symbols on manipulator labels

Continued

Symbol	Description
 xx0900000818  xx1300001087	Heat Risk of heat that can cause burns. (Both signs are used)
 xx0900000819  xx1000001141  xx1500002616	Moving robot The robot can move unexpectedly.

Continues on next page



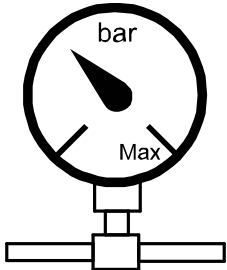
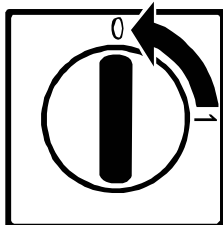

Symbol	Description
 <p>xx0900000820</p> <p>xx1000001140</p>	<p>Brake release buttons</p>
 <p>xx0900000821</p>	<p>Lifting bolt</p>
 <p>xx1000001242</p>	<p>Chain sling with shortener</p>
 <p>xx0900000822</p>	<p>Lifting of robot</p>
 <p>xx0900000823</p>	<p>Oil Can be used in combination with prohibition if oil is not allowed.</p>
 <p>xx0900000824</p>	<p>Mechanical stop</p>

Continues on next page

1 Safety

1.2.2 Safety symbols on manipulator labels

Continued

Symbol	Description
 xx1000001144	No mechanical stop
 xx0900000825	Stored energy Warns that this part contains stored energy. Used in combination with <i>Do not disassemble</i> symbol.
 xx0900000826	Pressure Warns that this part is pressurized. Usually contains additional text with the pressure level.
 xx0900000827	Shut off with handle Use the power switch on the controller.
 xx1400002648	Do not step Warns that stepping on these parts can cause damage to the parts.

1.3 Robot stopping functions

Protective stop and emergency stop

The protective stops and emergency stops are described in the product manual for the controller.

For more information see:

- *Product manual - IRC5 Compact*

1 Safety

1.4 Installation and commissioning

1.4 Installation and commissioning

National or regional regulations

The integrator of the robot system is responsible for the safety of the robot system.

The integrator is responsible that the robot system is designed and installed in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

The integrator of the robot system is required to perform a risk assessment.

Layout

The robot integrated to a robot system shall be designed to allow safe access to all spaces during installation, operation, maintenance, and repair.

If robot movement can be initiated from an external control panel then an emergency stop must also be available.

If the manipulator is delivered with mechanical stops, these can be used for reducing the working space.

A perimeter safeguarding, for example a fence, shall be dimensioned to withstand the following:

- The force of the manipulator.
- The force of the load handled by the robot if dropped or released at maximum speed.
- The maximum possible impact caused by a breaking or malfunctioning rotating tool or other device fitted to the robot.

The maximum TCP speed and the maximum velocity of the robot axes are detailed in the section *Robot motion* in the product specification for the respective manipulator.

Consider exposure to hazards, such as slipping, tripping, and falling.

Hazards due to the working position and posture for a person working with or near the robot shall be considered.

Consider hazards from other equipment in the robot system, for example, that guards remain active until identified hazards are reduced to an acceptable level.

Allergenic material

See [Environmental information on page 376](#) for specification of allergenic materials in the product, if any.

Securing the robot to the foundation

The robot must be properly fixed to its foundation/support, as described in the respective product manual.

When the robot is installed at a height, hanging, or other than mounted directly on the floor, there will be additional hazards.

Electrical safety

The mains power must be installed to fulfill national regulations.

Continues on next page

The power supply wiring to the robot must be sufficiently fused and if necessary, it must be possible to disconnect it manually from the mains power.

The power to the robot must be turned off with the main switch and the mains power disconnected when performing work inside the controller cabinet. Lock and tag shall be considered.

Harnesses between controller and manipulator shall be fixed and protected to avoid tripping and wear.

Wherever possible, power on/off or rebooting the robot controller shall be performed with all persons outside the safeguarded space.



Note

Use a CARBON DIOXIDE (CO₂) extinguisher in the event of a fire in the robot.

Safety devices

The integrator is responsible for that the safety devices necessary to protect people working with the robot system are designed and installed correctly.

When integrating the robot with external devices to a robot system:

- The integrator of the robot system must ensure that emergency stop functions are interlocked in accordance with applicable standards.
- The integrator of the robot system must ensure that safety functions are interlocked in accordance with applicable standards.

Other hazards



WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.



WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

The risk assessment should also consider other hazards arising from the application, such as, but not limited to:

- Water
- Compressed air
- Hydraulics

End-effector hazards require particular attention for applications which involve close human collaboration with the robot.

Continues on next page

1 Safety

1.4 Installation and commissioning

Continued

Pneumatic or hydraulic related hazards



Note

The pressure in the complete pneumatic or hydraulic systems must be released before service and maintenance.

All components in the robot system that remain pressurized after switching off the power to the robot must be marked with clearly visible drain facilities and a warning sign that indicates the hazard of stored energy.

Loss of pressure in the robot system may cause parts or objects to drop.

Dump valves should be used in case of emergency.

Shot bolts should be used to prevent tools, etc., from falling due to gravity.

All pipes, hoses, and connections have to be inspected regularly for leaks and damage. Damage must be repaired immediately.

Verify the safety functions

Before the robot system is put into operation, verify that the safety functions are working as intended and that any remaining hazards identified in the risk assessment are mitigated to an acceptable level.

1.5 Operation

1.5.1 Unexpected movement of robot arm

Unexpected movement of robot arm



WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.



WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

1 Safety

1.6.1 Maintenance and repair

1.6 Maintenance and repair

1.6.1 Maintenance and repair

General

Corrective maintenance must only be carried out by personnel trained on the robot. Maintenance or repair must be done with all electrical, pneumatic, and hydraulic power switched off, that is, no remaining hazards.

Hazards due to stored mechanical energy in the manipulator for the purpose of counterbalancing axes must be considered before maintenance or repair.

Never use the robot as a ladder, which means, do not climb on the controller, manipulator, including motors, or other parts. There are hazards of slipping and falling. The robot might be damaged.


Make sure that there are no loose screws, turnings, or other unexpected parts remaining after work on the robot has been performed.

When the work is completed, verify that the safety functions are working as intended.

Hot surfaces

Surfaces can be hot after running the robot, and touching these may result in burns. Allow the surfaces to cool down before maintenance or repair.

Allergic reaction

Warning	Description	Elimination/Action
 Allergic reaction	When working with lubricants there is a risk of an allergic reaction.	Make sure that protective gear like goggles and gloves are always worn.


Gearbox lubricants (oil or grease)

When handling oil, grease, or other chemical substances the safety information of the respective manufacturer must be observed.








Note

Take special care when handling hot lubricants.

Warning	Description	Elimination/Action
 Hot oil or grease	Changing and draining gearbox oil or grease may require handling hot lubricant heated up to 90 °C.	Make sure that protective gear like goggles and gloves are always worn during this activity.

Continues on next page

Warning	Description	Elimination/Action
 Allergic reaction	When working with lubricants there is a risk of an allergic reaction.	Make sure that protective gear like goggles and gloves are always worn.
 Possible pressure build-up in gearbox	When opening the oil or grease plug, there may be pressure present in the gearbox, causing lubricant to spray from the opening.	Open the plug carefully and keep away from the opening. Do not overfill the gearbox when filling.
 Do not overfill	Overfilling of gearbox lubricant can lead to internal over-pressure inside the gearbox which in turn may: <ul style="list-style-type: none"> • damage seals and gaskets • completely press out seals and gaskets • prevent the robot from moving freely. 	Make sure not to overfill the gearbox when filling it with oil or grease. After filling, verify that the level is correct.
 Specified amount depends on drained volume	The specified amount of oil or grease is based on the total volume of the gearbox. When changing the lubricant, the amount refilled may differ from the specified amount, depending on how much has previously been drained from the gearbox.	After filling, verify that the level is correct.
 Contaminated oil in gearboxes	For lifetime reasons always drain as much oil as possible from the gearbox. The magnetic oil plugs will gather residual metal chips.	

Hazards related to batteries

Under rated conditions, the electrode materials and liquid electrolyte in the batteries are sealed and not exposed to the outside.

There is a hazard in case of abuse (mechanical, thermal, electrical) which leads to the activation of safety valves and/or the rupture of the battery container. As a result under certain circumstances, electrolyte leakage, electrode materials reaction with moisture/water or battery vent/explosion/fire may follow.

Do not short circuit, recharge, puncture, incinerate, crush, immerse, force discharge or expose to temperatures above the declared operating temperature range of the product. Risk of fire or explosion.

Operating temperatures are listed in [Operating conditions, robot on page 43](#).

See safety instructions for the batteries in *Material/product safety data sheet - Battery pack (3HAC043118-001)*.

Continues on next page

1 Safety

1.6.1 Maintenance and repair

Continued

Unexpected movement of robot arm



WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.



WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

Related information

See also the safety information related to installation and operation.

1.6.2 Emergency release of the robot axes

Description

In an emergency situation, the brakes on a robot axis can be released manually by pushing a brake release button.

How to release the brakes is described in the section:

- [Manually releasing the brakes on page 61](#).

The robot may be moved manually on smaller robot models, but larger models may require using an overhead crane or similar equipment.

Increased injury

Before releasing the brakes, make sure that the weight of the manipulator does not result in additional hazards, for example, even more severe injuries on a trapped person.



DANGER

When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways.

Make sure no personnel is near or beneath the robot.

1 Safety

1.6.3 Brake testing

1.6.3 Brake testing

When to test

During operation, the holding brake of each axis normally wears down. A test can be performed to determine whether the brake can still perform its function.

How to test

The function of the holding brake of each axis motor may be verified as described below:

- 1 Run each axis to a position where the combined weight of the manipulator and any load is maximized (maximum static load).
- 2 Switch the motor to the MOTORS OFF.
- 3 Inspect and verify that the axis maintains its position.

If the manipulator does not change position as the motors are switched off, then the brake function is adequate.



Note

It is recommended to run the service routine *BrakeCheck* as part of the regular maintenance, see the operating manual for the robot controller.

For robots with the option SafeMove, the *Cyclic Brake Check* routine is recommended. See the manual for SafeMove in [References on page 10](#).

1.7 Troubleshooting

General

When troubleshooting requires work with power switched on, special considerations must be taken:

- Safety circuits might be muted or disconnected.
- Electrical parts must be considered as *live*.
- The manipulator can move unexpectedly at any time.



DANGER

Troubleshooting on the controller while powered on must be performed by personnel trained by ABB or by ABB field engineers.

A risk assessment must be done to address both robot and robot system specific hazards.



WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.



WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

Related information

See also the safety information related to installation, operation, maintenance, and repair.

1 Safety

1.8 Decommissioning

1.8 Decommissioning

General

See section [Decommissioning on page 375](#).

Unexpected movement of robot arm



WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.



WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

2 Installation and commissioning

2.1 Introduction to installation and commissioning

General

This chapter contains assembly instructions and information for installing the IRB 910SC at the working site.

See also the product manual for the robot controller.

The installation must be done by qualified installation personnel in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

Safety information

Before any installation work is commenced, all safety information must be observed. There are general safety aspects that must be read through, as well as more specific safety information that describes the danger and safety risks when performing the procedures. Read the chapter [Safety on page 17](#) before performing any installation work.



Note

Always connect the IRB 910SC and the robot to protective earth and residual current device (RCD) before connecting to power and starting any installation work.

For more information see:

- *Product manual - IRC5 Compact*

2 Installation and commissioning

2.2.1 Pre-installation procedure

2.2 Unpacking

2.2.1 Pre-installation procedure

Introduction


This section is intended for use when unpacking and installing the robot for the first time. It also contains information useful during later re-installation of the robot.

Prerequisites for installation personnel

Installation personnel working with an ABB product must:

- be trained by ABB and have the required knowledge of mechanical and electrical installation/maintenance/repair work
- conform to all national and local codes.

Checking the pre-requisites for installation

	Action
1	Make a visual inspection of the packaging and make sure that nothing is damaged.
2	Remove the packaging.
3	Check for any visible transport damage.  Note Stop unpacking and contact ABB if transport damages are found.
4	Clean the unit with a lint-free cloth, if necessary.
5	Make sure that the lifting accessory used (if required) is suitable to handle the weight of the robot as specified in: Weight, robot on page 41
6	If the robot is not installed directly, it must be stored as described in: Storage conditions, robot on page 42
7	Make sure that the expected operating environment of the robot conforms to the specifications as described in: Operating conditions, robot on page 43
8	Before taking the robot to its installation site, make sure that the site conforms to: <ul style="list-style-type: none">• Loads on foundation, robot on page 41• Protection classes, robot on page 43• Requirements, foundation on page 42
9	Before moving the robot, please observe the stability of the robot: Risk of tipping/stability on page 50
10	When these prerequisites are met, the robot can be taken to its installation site as described in section: On-site installation on page 53
11	Install required equipment, if any.

Continues on next page

Weight, robot

The table shows the weight of the robot.

Robot model	Weight
IRB 910SC	IRB 910SC-3/0.45: 24.5 kg
	IRB 910SC-3/0.55: 25 kg
	IRB 910SC-3/0.65: 25.5 kg

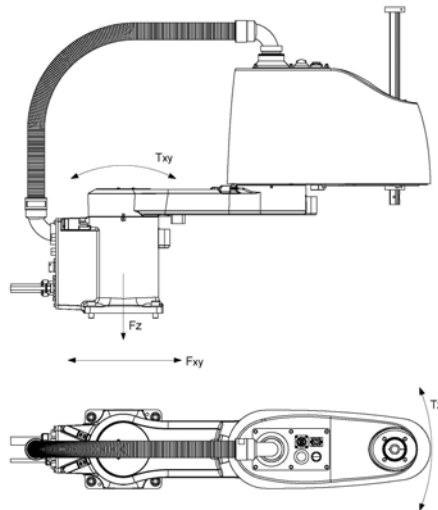


Note

The weight does not include tools and other equipment fitted on the robot.

Loads on foundation, robot

The illustration shows the directions of the robots stress forces.



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F_{xy}	Force in any direction in the XY plane
F_z	Force in the Z plane
T_{xy}	Bending torque in any direction in the XY plane
T_z	Bending torque in the Z plane

The table shows the various forces and torques working on the robot during different kinds of operation.



Note

These forces and torques are extreme values that are rarely encountered during operation. The values also never reach their maximum at the same time!

Continues on next page

2 Installation and commissioning

2.2.1 Pre-installation procedure

Continued



WARNING


The robot installation is restricted to the mounting options given in following load table(s).

Floor mounted

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	±651 N	±945 N
Force z	255±392 N	255±441 N
Torque xy	±260 Nm	±418 Nm
Torque z	±121 Nm	±238 Nm

Requirements, foundation

The table shows the requirements for the foundation where the weight of the installed robot is included:

Requirement	Value	Note
Flatness of foundation surface	0.1/500 mm	Flat foundations give better repeatability of the resolver calibration compared to original settings on delivery from ABB. The value for levelness aims at the circumstance of the anchoring points in the robot base. In order to compensate for an uneven surface, the robot can be recalibrated during installation. If resolver/encoder calibration is changed this will influence the absolute accuracy.
Maximum tilt	0°	
Minimum resonance frequency	22 Hz  Note It may affect the manipulator lifetime to have a lower resonance frequency than recommended.	The value is recommended for optimal performance. Due to foundation stiffness, consider robot mass including equipment. ⁱ For information about compensating for foundation flexibility, see <i>Application manual - Controller software IRC5</i> , section <i>Motion Process Mode</i> .

ⁱ The minimum resonance frequency given should be interpreted as the frequency of the robot mass/inertia, robot assumed stiff, when a foundation translational/torsional elasticity is added, i.e., the stiffness of the pedestal where the robot is mounted. The minimum resonance frequency should not be interpreted as the resonance frequency of the building, floor etc. For example, if the equivalent mass of the floor is very high, it will not affect robot movement, even if the frequency is well below the stated frequency. The robot should be mounted as rigid as possible to the floor.

Disturbances from other machinery will affect the robot and the tool accuracy. The robot has resonance frequencies in the region 10 – 20 Hz and disturbances in this region will be amplified, although somewhat damped by the servo control. This might be a problem, depending on the requirements from the applications. If this is a problem, the robot needs to be isolated from the environment.

Storage conditions, robot

The table shows the allowed storage conditions for the robot:

Parameter	Value
Minimum ambient temperature	-25 °C

Continues on next page

Parameter	Value
Maximum ambient temperature	55 °C
Maximum ambient temperature (less than 24 hrs)	70 °C
Maximum ambient humidity	95% at constant temperature (gaseous only)

Operating conditions, robot

The table shows the allowed operating conditions for the robot:

Parameter	Value
Minimum ambient temperature	5 °C ⁱ
Maximum ambient temperature	45 °C
Maximum ambient humidity	95% at constant temperature

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.

Protection classes, robot

The table shows the available protection types of the robot, with the corresponding protection class.

Protection type	Protection class
Manipulator, protection type Standard	IP20

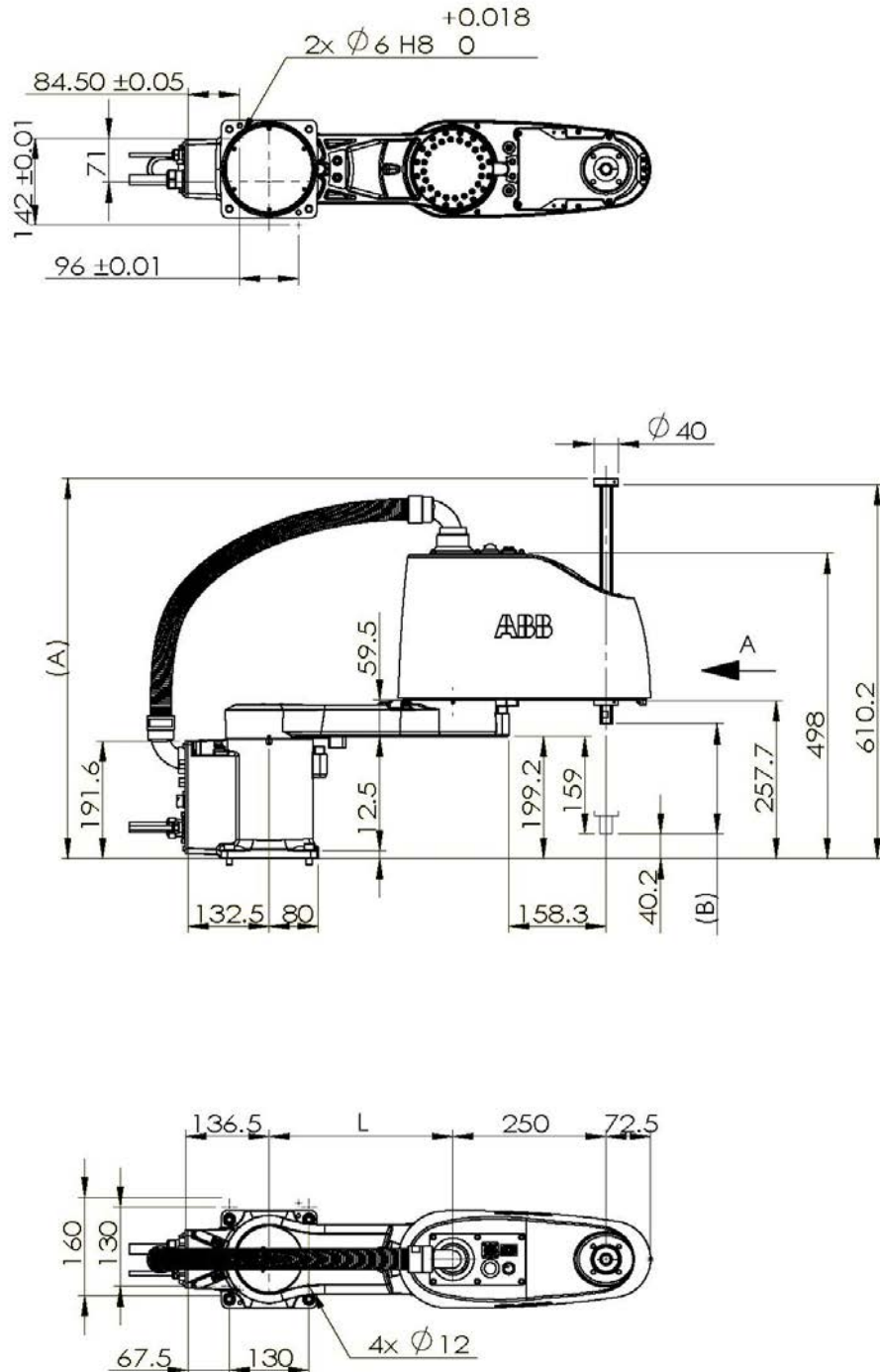
2 Installation and commissioning

2.2.2 Dimensions

2.2.2 Dimensions

Dimensions IRB 910SC

The figure shows the dimension of the robot.



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Continues on next page

Item	Description	Variant		
		IRB 910SC-3/0.45	IRB 910SC-3/0.55	IRB 910SC-3/0.65
L	Length of lower arm	200 mm	300 mm	400 mm
A	Maximum height	620 mm	620 mm	620 mm
B	Z stroke	180 mm	180 mm	180 mm

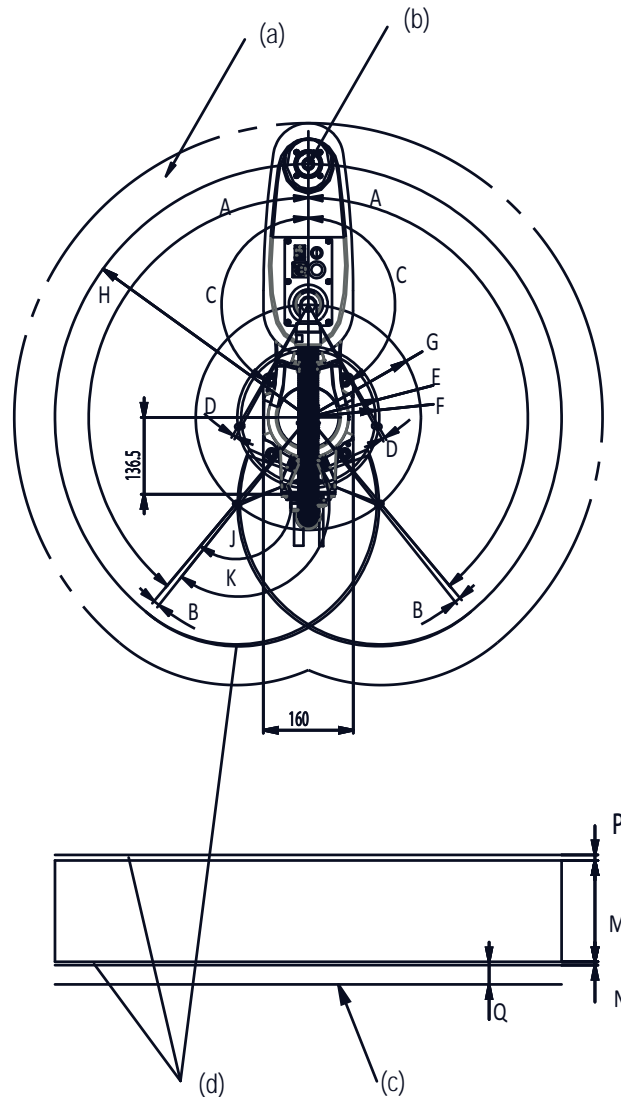
2 Installation and commissioning

2.2.3 Working range

2.2.3 Working range

Illustration, working range and turning radius IRB 910SC-3/0.45

This illustration shows the unrestricted working range and turning radius of IRB 910SC-3/0.45.



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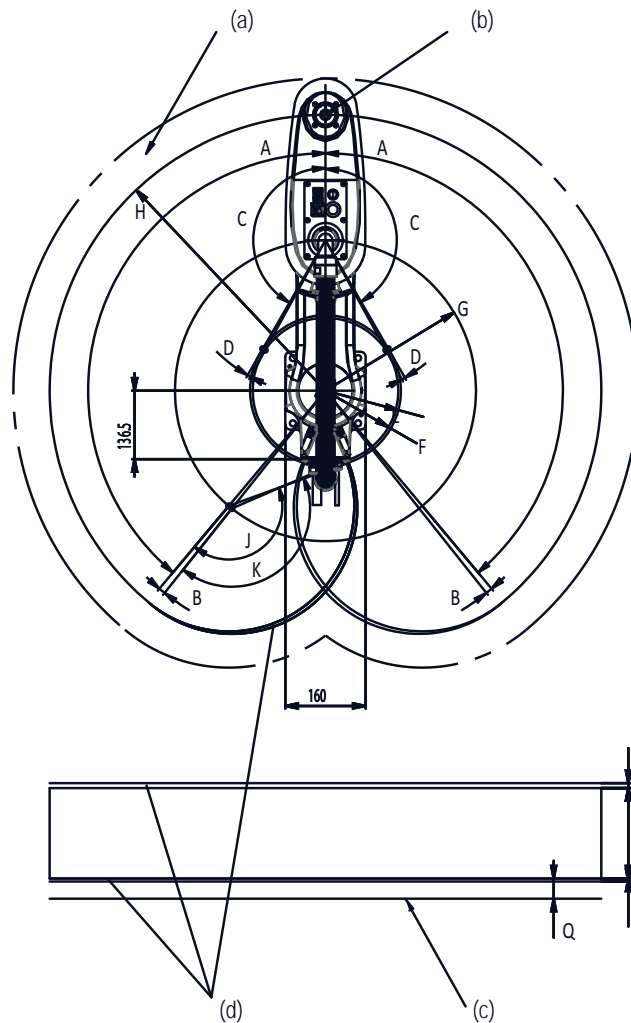
a	Maximum space	F	119 mm
b	Center joint of axis 3	G	200 mm
c	Base mounting face	H	450 mm
d	Area limited by mechanical stop	J	150°
A	140°	K	151.2°
B	1.5°	M	180 mm
C	150°	N	5 mm
D	1.2°	P	2 mm

Continues on next page

E	126 mm	Q	40.2 mm
---	--------	---	---------

Illustration, working range and turning radius IRB 910SC-3/0.55

This illustration shows the unrestricted working range and turning radius of IRB 910SC-3/0.55.



xx1500002475

a	Maximum space	F	145 mm
b	Center joint of axis 3	G	300 mm
c	Base mounting face	H	550 mm
d	Area limited by mechanical stop	J	150°
A	140°	K	151.2°
B	1.5°	M	180 mm
C	150°	N	5 mm
D	1.2°	P	2 mm
E	150 mm	Q	40.2 mm

Continues on next page

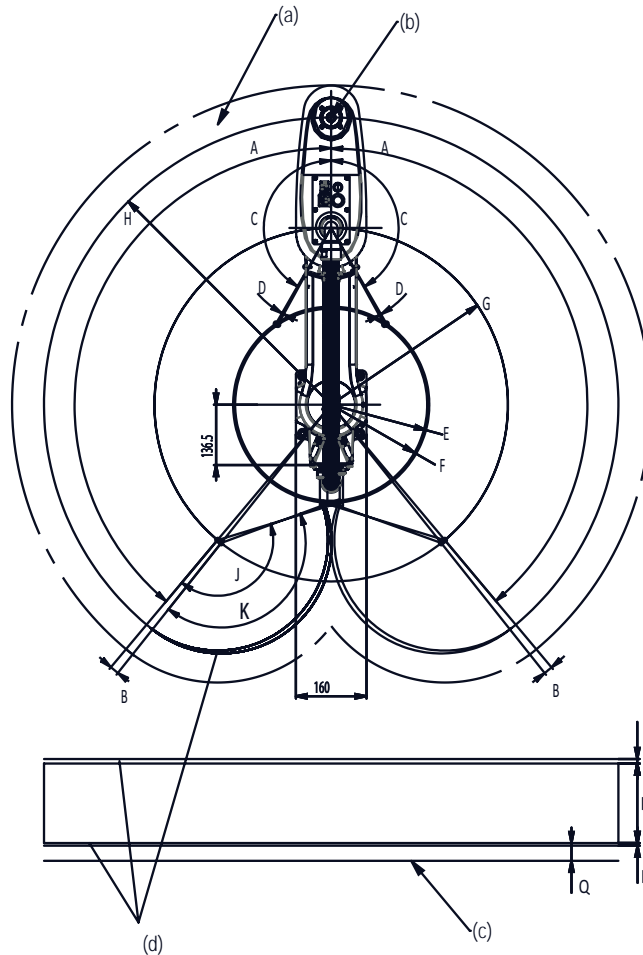
2 Installation and commissioning

2.2.3 Working range

Continued

Illustration, working range and turning radius IRB 910SC-3/0.65

This illustration shows the unrestricted working range and turning radius of IRB 910SC-3/0.65.



xx1500002476

a	Maximum space	F	217 mm
b	Center joint of axis 3	G	400 mm
c	Base mounting face	H	650 mm
d	Area limited by mechanical stop	J	150°
A	140°	K	151.2°
B	1.5°	M	180 mm
C	150°	N	5 mm
D	1.2°	P	2 mm
E	222 mm	Q	40.2 mm

Working range

Axis	Type of motion	Working range
Axis 1	Rotation motion	-140° to +140°

Continues on next page

Axis	Type of motion	Working range
Axis 2	Rotation motion	-150° to +150° ⁱ
Axis 3	Linear motion	-180 mm to 0 mm
Axis 4	Rotation motion	Default: -400° to +400° ⁱⁱ

ⁱ The axis 2 can be restricted to a smaller working range by fitting one more axis-2 mechanical stop block to the upper arm. For how to fit the block, see [Replacing the axis-2 mechanical stop block on page 272](#).

The additional mechanical stop block and related screws are provided in accessory package.

ⁱⁱ The default working range for axis 4 can be extended by changing parameter values in the software.

2 Installation and commissioning

2.2.4 Risk of tipping/stability

2.2.4 Risk of tipping/stability

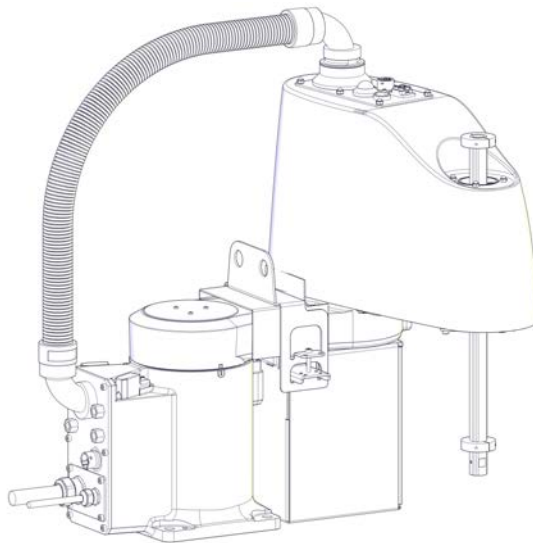
Risk of tipping

Do not change the robot position before securing it to the foundation.
The shipping position is the most stable position.

Shipping and transportation position

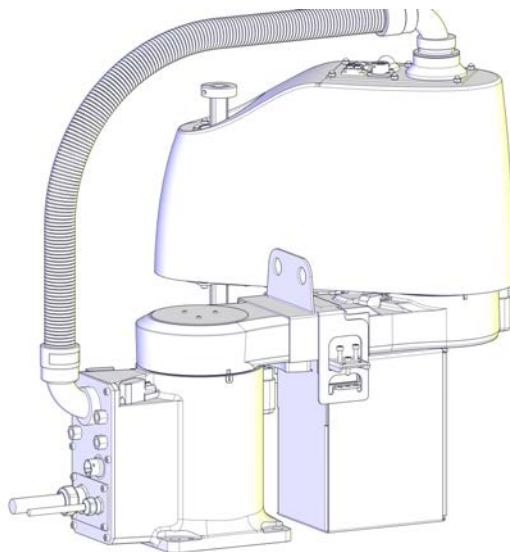
This figure shows the robot in its shipping position and transportation position.

IRB 910SC-3/0.45



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IRB 910SC-3/0.55 and IRB 910SC-3/0.65



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Continues on next page



WARNING

The robot will be mechanically unstable if not properly secured to the foundation.

2 Installation and commissioning

2.2.5 The unit is sensitive to ESD

2.2.5 The unit is sensitive to ESD

Description

ESD (electrostatic discharge) is the transfer of electrical static charge between two bodies at different potentials, either through direct contact or through an induced electrical field. When handling parts or their containers, personnel not grounded may potentially transfer high static charges. This discharge may destroy sensitive electronics.

Safe handling

Use one of the following alternatives:

- Use a wrist strap.

Wrist straps must be tested frequently to ensure that they are not damaged and are operating correctly.

- Use an ESD protective floor mat.

The mat must be grounded through a current-limiting resistor.

- Use a dissipative table mat.

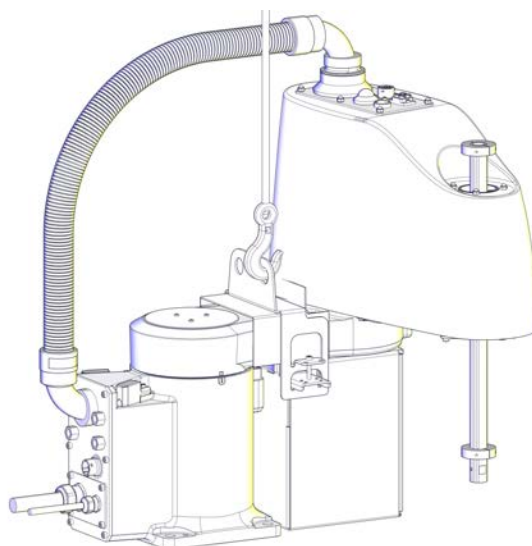
The mat should provide a controlled discharge of static voltages and must be grounded.

2.3 On-site installation

2.3.1 Lifting robot with lifting accessories

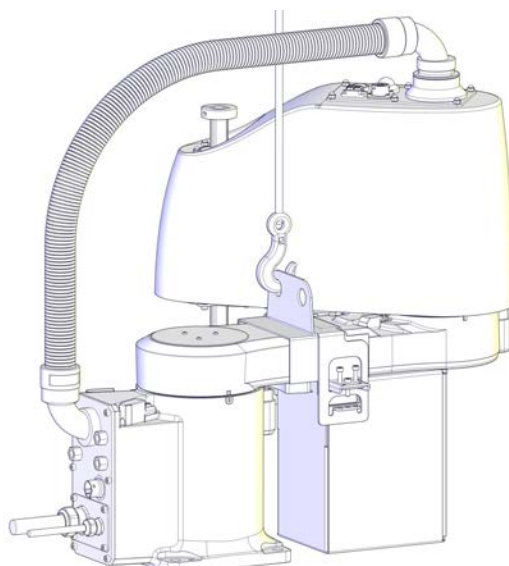
Introduction

IRB 910SC-3/0.45



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IRB 910SC-3/0.55 and IRB 910SC-3/0.65



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Required equipment

Equipment	Article number	Note
Overhead crane	-	

Continues on next page

2 Installation and commissioning


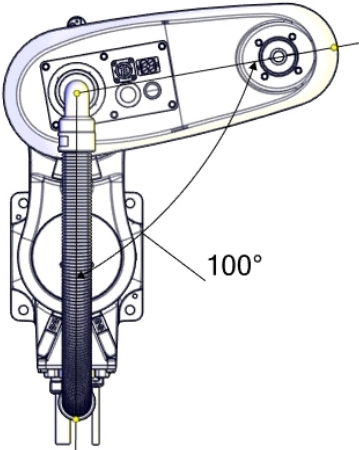
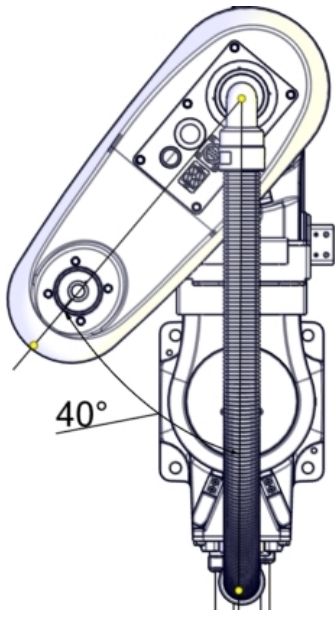
2.3.1 Lifting robot with lifting accessories

Continued

Equipment	Article number	Note
Lifting chain	-	> 50 kg (capacity of lifting chain)
Hook	-	
Lifting accessory, robot	-	Includes lifting accessories and screws.

Lifting the robot

Use this procedure to lift the robot.

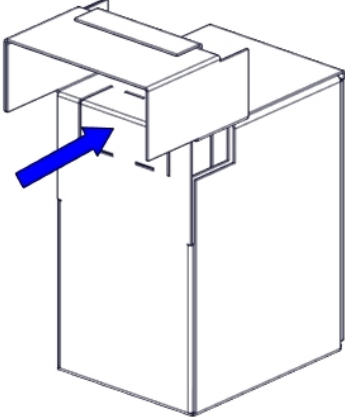

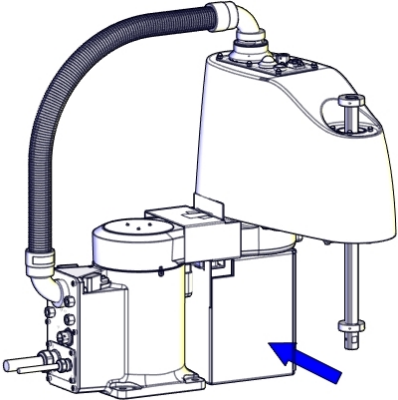
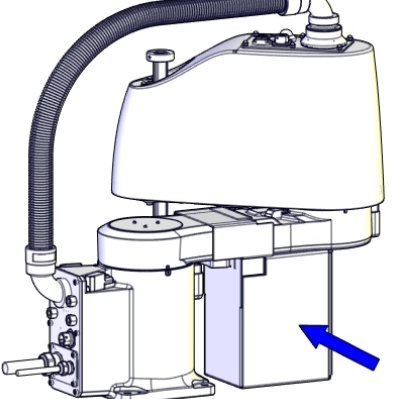
	Action	Note
1	<p>Move the robot to the appropriate lifting position.</p> <p> WARNING</p> <p>The robot is likely to be mechanically unstable if not secured to the foundation!</p>	<p>Valid for IRB 910SC-3/0.45</p>  <p>100°</p> <p>xx1500002483</p> <p>Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p>40°</p> <p>xx1500002488</p>

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2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued

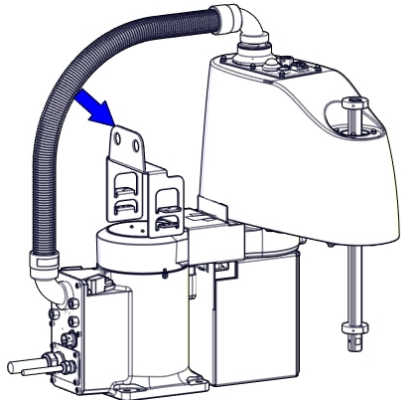
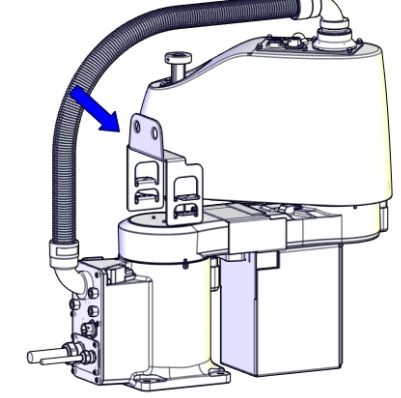
	Action	Note
2	<p data-bbox="507 315 1008 394">Fold the lifting paper box to the required shape and put it to the proper position under the lower arm.</p>  <p data-bbox="507 846 616 864">xx1500002493</p> <p data-bbox="507 887 655 931"> Note</p> <p data-bbox="507 958 1008 1066">For the IRB 910SC-3/0.45, fold the part pointing out in the figure along the folding mark so that a space will be left for the axis-1 mechanical stop block.</p>	<p data-bbox="1023 315 1326 338">Valid for IRB 910SC-3/0.45</p>  <p data-bbox="1023 768 1131 786">xx1500002484</p> <p data-bbox="1023 804 1422 857">Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p data-bbox="1023 1288 1131 1305">xx1500002489</p>

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2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued


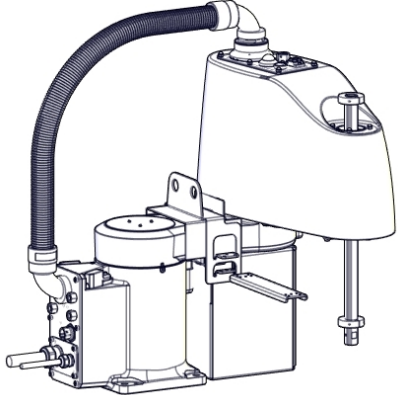
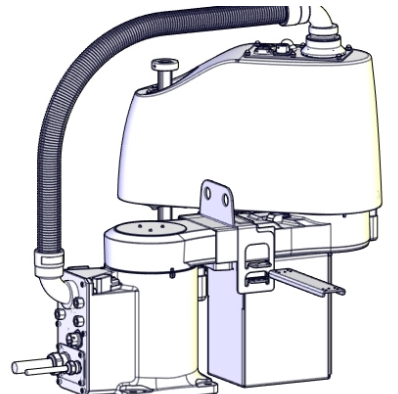
	Action	Note
3	Fit the lifting bracket.	<p data-bbox="991 315 1294 338">Valid for IRB 910SC-3/0.45</p>  <p data-bbox="991 752 1098 770">xx1500002485</p> <p data-bbox="991 786 1394 837">Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p data-bbox="991 1256 1098 1274">xx1500002490</p>

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2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued

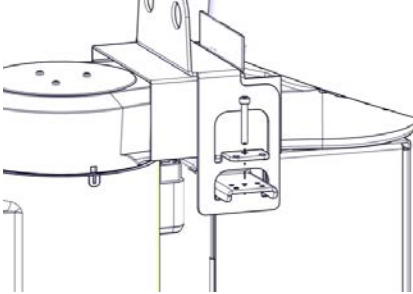
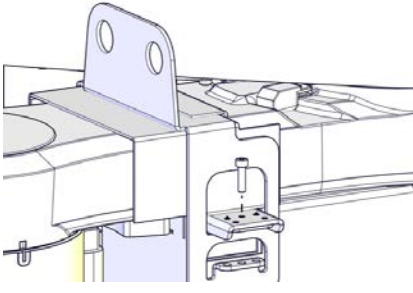
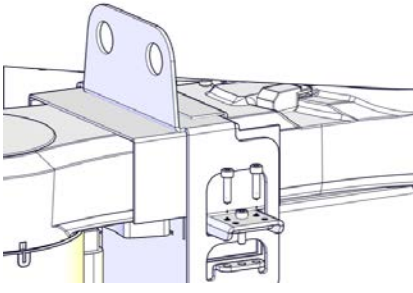


	Action	Note
4	<p>Insert the metal plate through the bracket and the paper box.</p> <p> Note</p> <p>IRB 910SC-3/0.45: Use lower lug on the bracket.</p> <p>IRB 910SC-3/0.55 and IRB 910SC-3/0.65: Use upper lug on the bracket.</p>	<p>Valid for IRB 910SC-3/0.45</p>  <p>xx1500002771</p> <p>Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p>xx1500002772</p>

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2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued

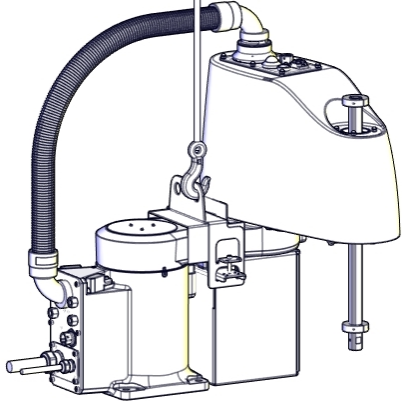
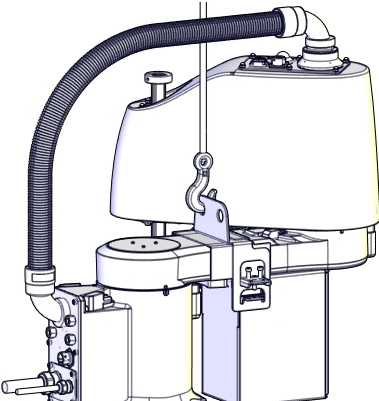
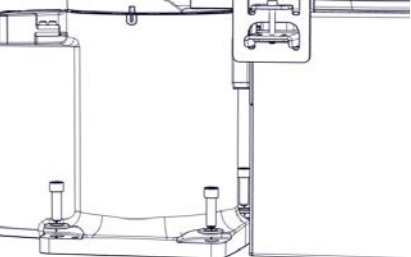
	Action	Note
5	<p>Secure the metal plate with screw(s). IRB 910SC-3/0.45: One screw at each side. IRB 910SC-3/0.55 and IRB 910SC-3/0.65: One screw at one side only.</p>	<p>Valid for IRB 910SC-3/0.45</p>  <p>xx1500002486</p> <p>Screw: M4x30 (2 pcs) Tightening torque: 0.3-0.4 Nm</p> <p>Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p>xx1500003067</p> <p>Screw: M4x12 (1 pcs) Tightening torque: 0.2-0.3 Nm</p>
6	<p>For IRB 910SC-3/0.55 and IRB 910SC-3/0.65 Fasten two screws at each side to clamp the metal plate and the bracket.</p>	<p>Screw: M4x12 (4 pcs) Tightening torque: 0.2-0.3 Nm</p>  <p>xx1500002491</p>
7	<p> CAUTION</p> <p>The IRB 910SC robot weighs 25.5 kg at a maximum. All lifting accessories used must be sized accordingly!</p>	
8	<p> WARNING</p> <p>Personnel must not, under any circumstances, be present under the suspended load!</p>	

Continues on next page

2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued

	Action	Note
9	Attach the lifting chain to the robot.	<p>Lifting capacity for the lifting chain is specified in Required equipment on page 53.</p> <p>Valid for IRB 910SC-3/0.45</p>  <p>xx1500002495</p> <p>Valid for IRB 910SC-3/0.55 and IRB 910SC-3/0.65</p>  <p>xx1500002494</p>
10	Carefully stretch the chain by lifting the crane slowly. This prevents the robot from falling down when it is unfastened or the support is removed. Do not overstretch the chain if the robot is fastened because there is a risk of the robot being damaged.	
11	Remove the robot attachment screws (if the robot is fastened).	<p>Screw: M10x25 (4 pcs)</p>  <p>xx1500002773</p>

Continues on next page

2 Installation and commissioning

2.3.1 Lifting robot with lifting accessories

Continued

	Action	Note
12	Raise the overhead crane to lift the robot.	

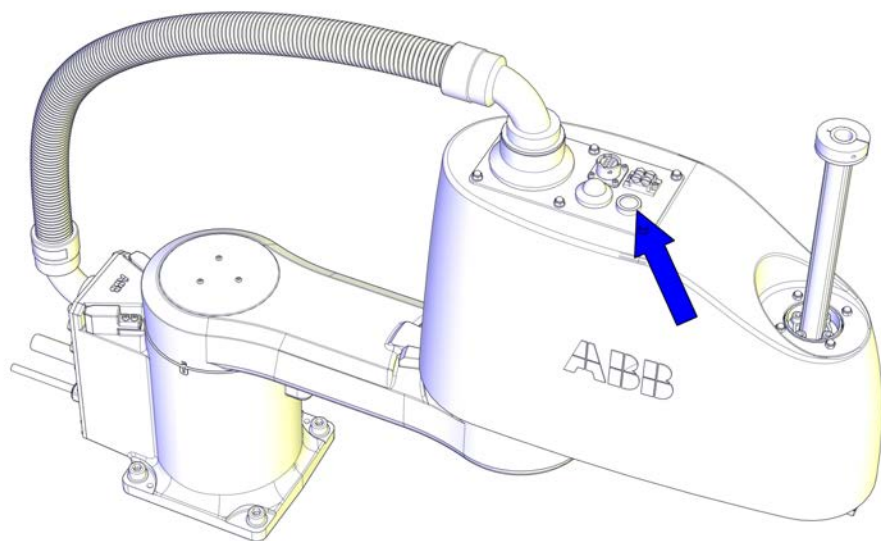
2.3.2 Manually releasing the brakes

Introduction to manually releasing the brakes

This section describes how to release the holding brakes for the motors of each axis.

Location of brake release unit

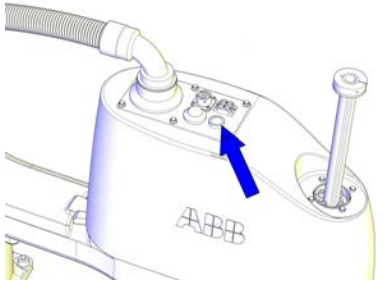
The internal brake release unit is located as shown in the figure.



xx1500002173

Releasing the brakes

This procedure details how to release the holding brakes when the robot is equipped with an internal brake release unit.


	Action	Note
1	<p>The internal brake release unit is equipped with a button for controlling the axes brakes. If the robot is not connected to the controller, power must be supplied to the connector R1.MP according to the section Supplying power to connector R1.MP on page 62.</p>	 <p>xx1500002774</p>

Continues on next page

2 Installation and commissioning



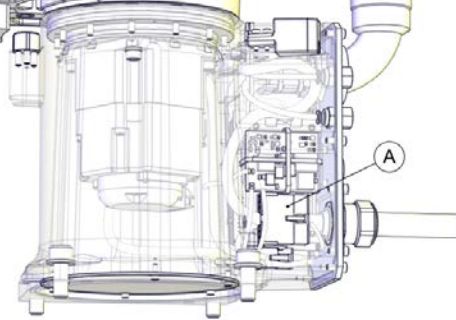
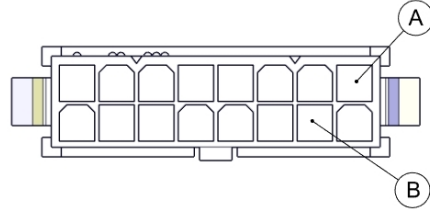
2.3.2 Manually releasing the brakes

Continued

	Action	Note
2	 <p>DANGER</p> <p>When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways!</p> <p>Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.</p>	
3	<p>Release the holding brake on all robot axes by pressing the button on the internal brake release unit.</p> <p>The brake will function again as soon as the button is released.</p>	

Supplying power to connector R1.MP

If the robot is not connected to the controller, power must be supplied to connector R1.MP on the robot in order to enable the brake release buttons.

	Action	Note						
1	 <p>DANGER</p> <p>Incorrect connections, such as supplying power to the wrong pin, may cause all brakes to be released simultaneously!</p>							
2	<p>Supply +24V on pin 15 and 0V on pin 8.</p>  <p>Note</p> <p>Do not interchange the 24V and 0V pins. If they are mixed up, damage can be caused to the brake release unit and to the system board.</p>	 <p>xx1500002477</p> <table border="1" data-bbox="938 1547 1404 1592"> <tr> <td>A</td> <td>R1.MP</td> </tr> </table>  <p>xx1500002478</p> <table border="1" data-bbox="938 1935 1404 2018"> <tr> <td>A</td> <td>0V (8)</td> </tr> <tr> <td>B</td> <td>+24V (15)</td> </tr> </table>	A	R1.MP	A	0V (8)	B	+24V (15)
A	R1.MP							
A	0V (8)							
B	+24V (15)							

2.3.3 Orienting and securing the robot

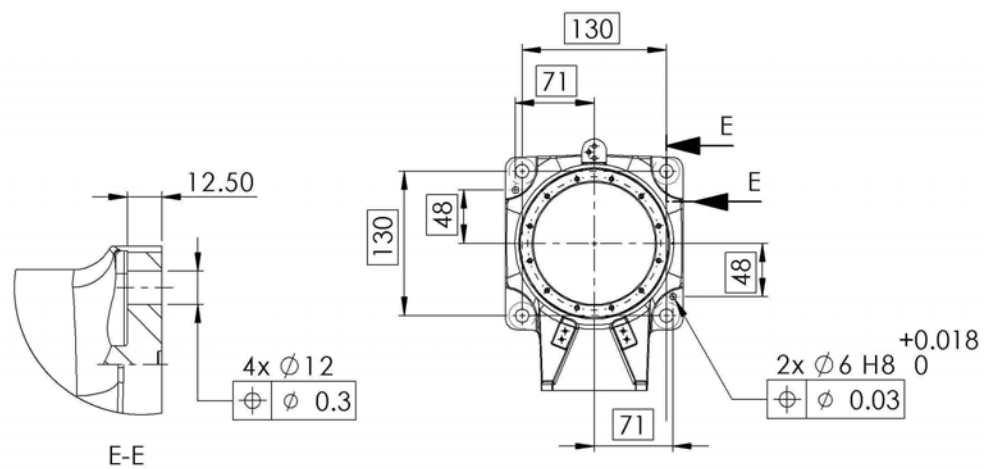
Introduction

This section details how to orient and secure the robot to the foundation or base plate in order to run the robot safely. The requirements made on the foundation are shown in sections:

- [Loads on foundation, robot on page 41](#)
- [Requirements, foundation on page 42.](#)

Hole configuration, base

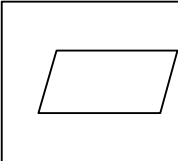
The illustration shows the hole configuration used when securing the robot.



xx1500002521

Specification, attachment screws and pins

The table specifies the type of securing screws and washers to be used to secure the robot directly to the foundation. It also specifies the type of pins to be used.

Suitable screws	M10x25
Quantity	4 pcs
Quality	8.8
Suitable washer	20x10.5x2
Guide pins	2 pcs, D6x20, ISO 2338 - 6m6x20 - A1
Tightening torque	45 Nm
Level surface requirements	<div style="display: flex; align-items: center; justify-content: center;">  <div style="margin-left: 20px; font-size: 24px; font-weight: bold;">0.1</div> </div> <p style="font-size: 8px; margin-top: 5px;">xx1500000627</p>

Continues on next page



2 Installation and commissioning

2.3.3 Orienting and securing the robot

Continued

Orienting and securing the robot

Use this procedure to orient and secure the robot.

	Action	Information
1	Make sure the installation site for the robot conforms to the specifications in section: <ul style="list-style-type: none">• Pre-installation procedure on page 40.	
2	Prepare the installation site with attachment holes.	The hole configuration of the base is shown in the figure in Hole configuration, base on page 63 .
3	 CAUTION The IRB 910SC robot weighs 25.5 kg at a maximum. All lifting accessories used must be sized accordingly!	
4	 CAUTION When the robot is put down after being lifted or transported, there is a risk of it tipping, if not properly secured.	
5	Lift the robot to its installation site.	See Lifting robot with lifting accessories on page 53 .
6	Fit two pins to the holes in the base.	2 pcs, D6x20, ISO 2338 - 6m6x20 - A1
7	Guide the robot gently, using the attachment screws while lowering it into its mounting position.	Make sure the robot base is correctly fitted onto the pins.
8	Fit the securing screws and washers in the attachment holes of the base.	Screws: M10x25, quality: 8.8
9	Tighten the bolts in a criss-cross pattern to ensure that the base is not distorted.	Tightening torque: 45 Nm

Securing robot on a mounting plate

When bolting a mounting plate or frame to a concrete floor, follow the general instructions for expansion-shell bolts.

Screw joints must be able to withstand the stress loads defined in section [Loads on foundation, robot on page 41](#).

2.3.4 Loads fitted to the robot, stopping time and braking distances

General

Any loads mounted on the robot must be defined correctly and carefully (with regard to the position of center of gravity and mass moments of inertia) in order to avoid jolting movements and overloading motors, gears and structure.



CAUTION

Incorrectly defined loads may result in operational stops or major damage to the robot.

References

Load diagrams, permitted extra loads (equipment) and their positions are specified in the product specification. The loads must be defined in the software.

- *Operating manual - IRC5 with FlexPendant*

Stopping time and braking distances

The performance of the motor brake depends on if there are any loads attached to the robot. For more information, see product specification for the robot.

2 Installation and commissioning

2.3.5 Fitting equipment on the robot

2.3.5 Fitting equipment on the robot

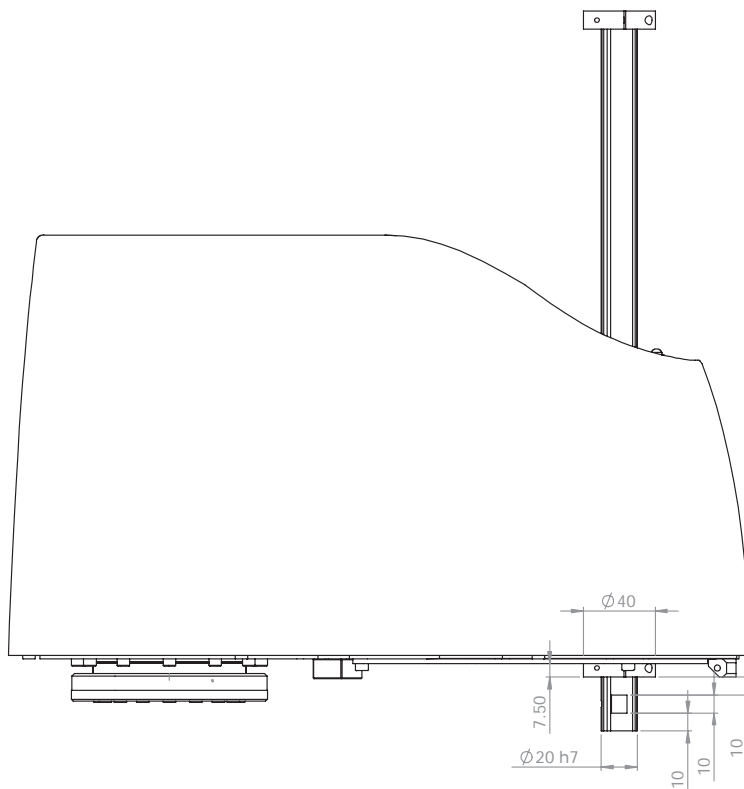
Fitting of end effector to the ball screw spline shaft

An end effector can be attached to the lower end of the shaft of the ball screw spline unit. The dimensions for fitting the end effector is shown in the following figure.



Note

Mounting of other equipment on the IRB 910SC may damage the gearboxes.



xx1700001187

Continues on next page



xx1500002523

A	Flat cut
B	Conical hole
C	Stop block diameter
D	Through hole
E	Shaft diameter

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.

2 Installation and commissioning

2.4.1 Axes with restricted working range

2.4 Restricting the working range

2.4.1 Axes with restricted working range

General

When installing the robot, make sure that it can move freely within its entire working space. If there is a risk that it may collide with other objects, its working space should be limited.

The working range of the following axes may be restricted:

- Axis 1, hardware (mechanical stop)
- Axis 2, hardware (mechanical stop)
- Axes 3 and 4, hardware (stop block)

This section describes how to install hardware that restricts the working range.



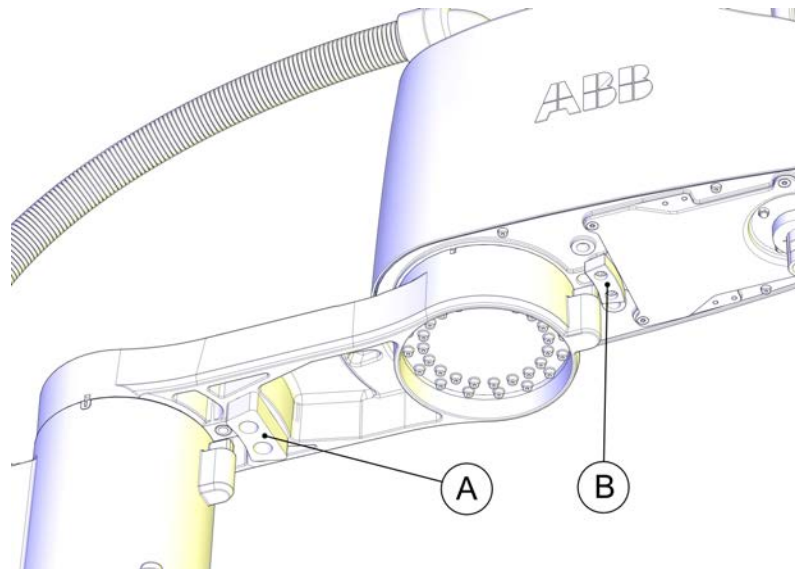
Note

Adjustments must also be made in the robot configuration software (system parameters). References to relevant manuals are included in the installation procedures.

2.4.2 Mechanically restricting the working range

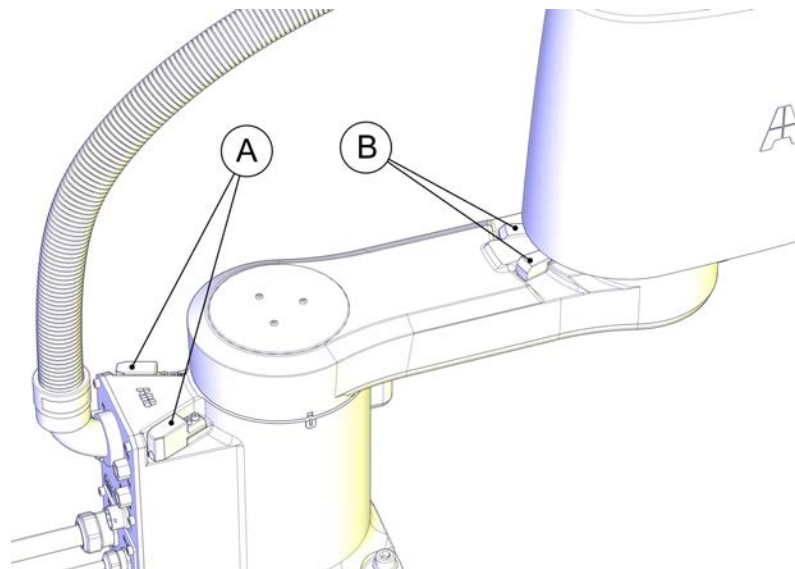
Location of mechanical stops

The figures shows where the mechanical stops are placed on the robot.



xx1500002811

A	Mechanical stop block, axis 1 (lower arm)
B	Mechanical stop block, axis 2 (upper arm)



xx1500002814

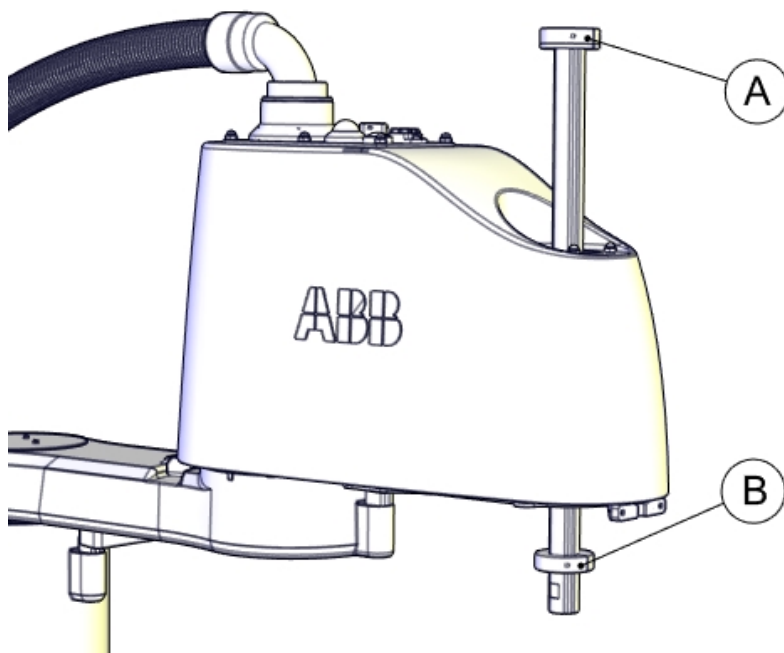
A	Mechanical stop rubbers, axis 1 (base)
B	Mechanical stop rubbers, axis 2 (lower arm)

Continues on next page

2 Installation and commissioning

2.4.2 Mechanically restricting the working range

Continued



xx1500002813

A	Upper stop block, axes 3 and 4 (upper arm)
B	Lower stop block, axes 3 and 4 (upper arm)

2.5 Electrical connections

2.5.1 Robot cabling and connection points

Introduction

Connect the robot and controller to each other after securing them to the foundation. The lists below specify which cables to use for each respective application. IRB 910SC works with IRC5 Compact controller only.

Main cable categories

All cables between the robot and controller are divided into the following categories:

Cable category	Description
Robot cables	Handles power supply to and control of the robot's motors as well as feedback from the encoder interface board. Specified in the table Robot cables on page 71 .
Customer cables (option)	Handles communication with equipment fitted on the robot by the customer (low voltage signals). The customer cables also handle Ethernet communication. See <i>Product manual - IRC5 Compact</i> .

Robot cables

These cables are included in the standard delivery. They are completely pre-manufactured and ready to plug in.

Cable sub-category	Description	Connection point, cabinet	Connection point, robot
Robot cable, power	Transfers drive power from the drive units in the control cabinet to the robot motors.	XS1	R1.MP
Robot cable, signals	Transfers encoder data from and power supply to the encoder interface board.	XS2	R1.EIB

Robot cable, power

Power cable length	Article number
3 m	3HAC057784-001
7 m	3HAC057785-001
15 m	3HAC057786-001

Robot cable, signals

Signal cable length	Article number
3 m	3HAC057787-001
7 m	3HAC057788-001
15 m	3HAC057789-001

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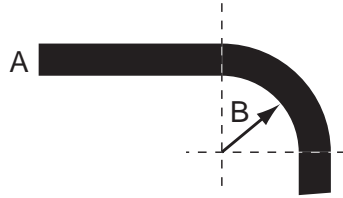
2 Installation and commissioning

2.5.1 Robot cabling and connection points

Continued

Bending radius for static floor cables

The minimum bending radius is 10 times the cable diameter for static floor cables.

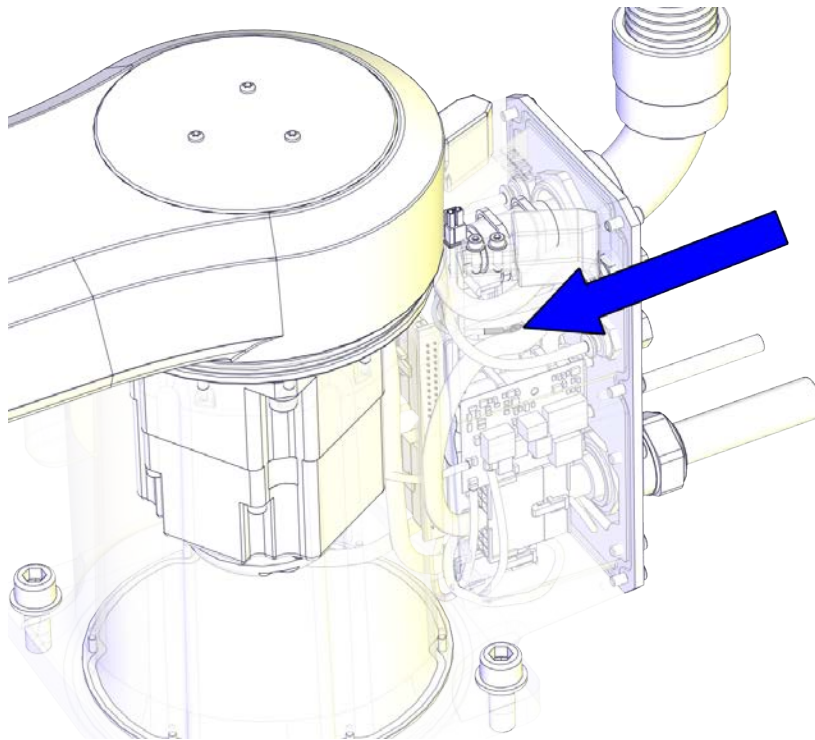


xx1600002016

A	Diameter
B	Diameter x10

Grounding and bonding point on manipulator

There is a grounding/bonding point on the manipulator base. The grounding/bonding point is used for potential equalizing between control cabinet, manipulator and any peripheral devices.



xx2100000706

Customer cables - CP/CS cable (option)

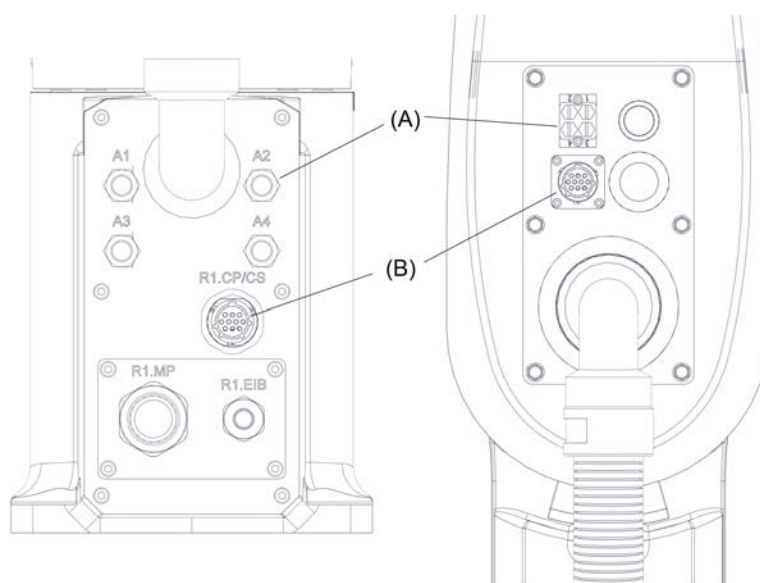
CP/CS cable length	Article number
3 m (IRC5C)	3HAC049186-001
7 m (IRC5C)	3HAC049186-004
15 m (IRC5C)	3HAC049186-005

2.5.2 Customer connections

Introduction to customer connections

The cables for customer connection are integrated in the robot and the connectors are placed at the upper arm and base. There is one connector R3.CP/CS at the upper arm. Corresponding connector R1.CP/CS is located at the base.

Hose for compressed air is also integrated into the manipulator. There are 4 inlets at the base (R1/8") and 4 outlets (M5) on the upper arm.



xx1500002751

Position	Connection	Description	Number	Value
A	Air	Max. 5 bar	4	Outer diameter of air hose: 4 mm
B	(R1)R3.CP/CS	Customer power/signal	10	49 V, 500 mA

Connectors

The tables describes the connectors on base and upper arm.

Connectors, base

Position	Description	Art. no.
Robot	Pin connector 10p, bulkhead	3HAC022117-002
Customer connector	Connector set R1.CP/CS	3HAC037038-001

Connectors, upper arm

Position	Description	Art. no.
Robot	Socket connector 10p, flange mounted	3HAC023624-002
Customer connector	Connector set R3.CP/CS	3HAC037070-001

Continues on next page

2 Installation and commissioning

2.5.2 Customer connections

Continued

Air, connector

Position	Description	Art. no.
Robot	4xM5	
Customer cable	Air connector	3HAC032049-001

2.6 Start of robot in cold environments

Introduction

This section describes how to start the robot in a cold environment if it is not starting the normal way.

Problems with starting the robot

Event message from Motion Supervision

Use this procedure if an event message indicates a problem with Motion supervision at start-up. More information about Motion Supervision is found in *Technical reference manual - System parameters*.

	Action	Note
1	Turn off Motion Supervision.	
2	Start the robot.	
3	When the robot has reached normal working temperature, the Motion Supervision can be turned on again.	

Robot stopping with other event message

Use this procedure if the robot is not starting.

	Action	Note
1	Start the robot with its normal program but with reduced speed.	The speed can be regulated with the RAPID instruction <code>VelSet</code> .

Adjusting the speed and acceleration during warm-up

Depending on how cold the environment is and what program is being used, the speed might need to be ramped up until reached maximum. The table shows examples of how to adjust the speed:

Work cycles	AccSet	Speed/velocity
3 Work cycles	20, 20	v100 (100 mm/s)
5 Work cycles	40, 40	v400 (400 mm/s)
5 Work cycles	60, 60	v600 (600 mm/s)
5 Work cycles	100, 100	v1000 (1000 mm/s)
More than 5 Work cycles	100, 100	Max.

If the program consists of large wrist movements, it is possible that the reorientation velocity, which is always high in predefined velocities, needs to be included in the ramping up.

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3 Maintenance

3.1 Introduction

Structure of this chapter

This chapter describes all the maintenance activities recommended for the IRB 910SC.

It is based on the maintenance schedule found at the beginning of the chapter. The schedule contains information about required maintenance activities including intervals, and refers to procedures for the activities.

Each procedure contains all the information required to perform the activity, including required tools and materials.

The procedures are gathered in different sections and divided according to the maintenance activity.

Safety information

Observe all safety information before conducting any service work.

There are general safety aspects that must be read through, as well as more specific safety information that describes the danger and safety risks when performing the procedures. Read the chapter [Safety on page 17](#) before performing any service work.

The maintenance must be done by qualified personnel in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

**Note**

If the IRB 910SC is connected to power, always make sure that the IRB 910SC is connected to protective earth and a residual current device (RCD) before starting any maintenance work.

For more information see:

- *Product manual - IRC5 Compact*
- [Robot cabling and connection points on page 71.](#)

3 Maintenance

3.2 Service Information System (SIS)

3.2 Service Information System (SIS)

General

Service Information System (SIS) is a software function within the robot controller, which simplifies maintenance of the robot system. It supervises the operating time and mode of the robot, and alerts the operator when a maintenance activity is scheduled.

Troubleshooting

The SIS function *Gearbox* is available for estimating the service interval (remaining lifetime) of the gearboxes of a robot. Such information of the ball screw spline unit of the IRB 910SC is reported as **axis 3** in the SIS system. When a service message is reported for axis 3 of the IRB 910SC, an inspection on the ball screw spline unit is required.

For more information about the SIS function, see *Operating manual - Service Information System*.

3.3 Maintenance schedule

3.3.1 Specification of maintenance intervals

Introduction

The intervals are specified in different ways depending on the type of maintenance activity to be carried out and the working conditions of the IRB 910SC:

- Calendar time: specified in months regardless of whether the system is running or not.
- Operating time: specified in operating hours. More frequent running means more frequent maintenance activities.
- SIS: specified by the robot's SIS (Service Information System). A typical value is given for a typical work cycle, but the value will differ depending on how hard each part is run.

The SIS used in M2004 is further described in the *Operating manual - Service Information System*.

Robots with the functionality *Service Information System* activated can show active counters in the device browser in RobotStudio, or on the FlexPendant.

3 Maintenance

3.3.2 Maintenance schedule

3.3.2 Maintenance schedule

Scheduled and non-predictable maintenance

The robot must be maintained regularly to ensure proper function. The maintenance activities and intervals are specified in the table below.

Non-predictable situations also give rise to inspections of the robot. Any damages must be attended to immediately!

Life of each component

The inspection intervals *do not* specify the life of each component.

Activities and intervals, standard equipment

The table below specifies the required maintenance activities and intervals:

Maintenance activities	Regularly ⁱ	Every 100 km	Every 12 months	Every 20,000 hours ⁱⁱ	Reference
Cleaning activities					
Cleaning the robot	x				Cleaning the IRB 910SC on page 114
Inspection activities					
Inspecting the robot	x				Check for abnormal wear or contamination.
Inspecting the robot cabling ⁱⁱⁱ	x ^{iv}				Inspecting the cabling on page 82
Inspecting the information labels			x		Inspecting the information labels on page 83
Inspecting the ball screw spline unit	x ^v				Inspecting the ball screw spline unit on page 86
Inspecting the axis-1 and axis-2 mechanical stops	x ^{vi}				Inspecting axis-1 and axis-2 mechanical stops on page 89
Inspecting the timing belts			x		Inspecting the timing belts on page 92
Replacement/changing activities					
Replacing the battery pack ^{vii}					Replacing the battery pack on page 100
Lubrication activities					
Lubricating the ball screw spline unit		x			Lubricating the ball screw spline unit on page 111
Overhaul					

Continues on next page

Maintenance activities	Regularly ⁱ	Every 100 km	Every 12 months	Every 20,000 hours ⁱⁱ	Reference
Overhaul of complete robot				x	

- i "Regularly" implies that the activity is to be performed regularly, but the actual interval may not be specified by the robot manufacturer. The interval depends on the operation cycle of the robot, its working environment and movement pattern. Generally, the more contaminated environment, the shorter intervals. The more demanding movement pattern (sharper bending cable harness), the shorter intervals.
- ii Operating hours counted by the DTC = Duty time counter.
- iii The robot cabling comprises the cabling between the robot and controller cabinet.
- iv Replace when damage or cracks is detected or life limit is approaching.
- v Inspect immediately if the stop blocks are hit.
- vi Inspect immediately if the mechanical stop is hit.
- vii The battery low alert (38213 **Battery charge low**) is displayed when remaining backup capacity (robot powered off) is less than 2 months. Typical life of a new battery is 36 months if the robot is powered off 2 days/week, or 18 months if the robot is powered off 16 hours/day. The life can be extended (approximately 3 times) for longer production breaks by a battery shutdown service routine. See *Operating manual - IRC5 with FlexPendant*.
See the replacement instruction for more details.

3 Maintenance

3.4.1 Inspecting the cabling

3.4 Inspection activities

3.4.1 Inspecting the cabling

Location of robot cabling

The robot cabling comprises the cabling between the robot and controller cabinet as well as the externally visible cabling from the base to the upper arm.


Required tools and equipment

Visual inspection, no tools are required.

Other tools and procedures may be required if the spare part needs to be replaced. These are specified in the replacement procedure.

Inspection, robot cabling

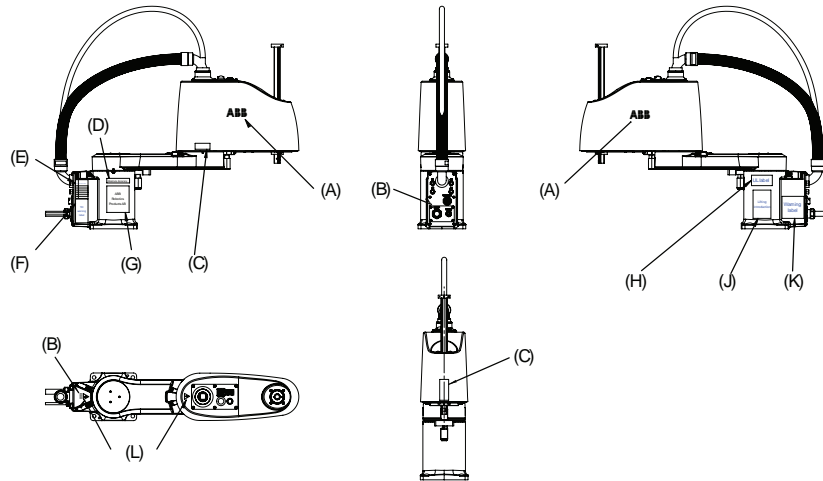
Use this procedure to inspect the robot cabling.

	Action	Note
1	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply to the robot• hydraulic pressure supply to the robot• air pressure supply to the robot Before entering the robot working area.	
2	Visually inspect: <ul style="list-style-type: none">• the control cabling between the robot and control cabinet• the externally visible cabling from the base to the upper arm Look for abrasions, cuts or crush damages.	
3	Replace the cabling if wear or damage is detected.	See Replacing the main cable package on page 122.

3.4.2 Inspecting the information labels

Location of labels

This figure shows the location of the information labels to be inspected. The symbols are described in section *Safety symbols on manipulator labels on page 21*.



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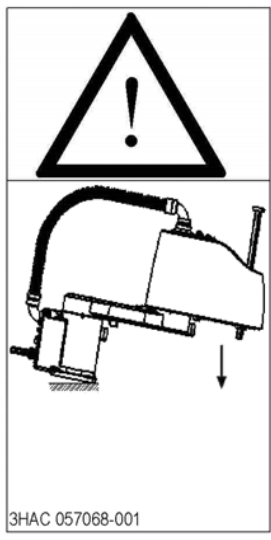
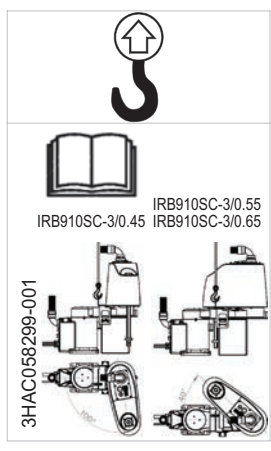


Pos	Description	Illustration
A	ABB logo, large size	
B	ABB logo, small size	
C	Synchronization mark for axis 2	 xx1500002671
	Synchronization mark for axis 3 and 4	 xx1500002672
D	AbsAcc label	
E	Calibration label	

Continues on next page

3 Maintenance

3.4.2 Inspecting the information labels

Continued

F	<p>Warning label Tip risk when loosening bolts</p>	 <p>3HAC 057068-001</p> <p>xx1500002402</p>
G	Rating label	
H	UL label	
J	<p>Instruction label Lifting of robot</p>	 <p>IRB910SC-3/0.55 IRB910SC-3/0.45 IRB910SC-3/0.65</p> <p>3HAC058299-001</p> <p>xx1600000282</p>
K	<p>Instruction label Brake release Moving robot Brake release buttons</p>	 <p>3HAC057070-001</p> <p>xx1500002403</p>
L	<p>Warning label Flash</p>	 <p>xx1300001091</p>

Continues on next page

Required spare parts



Note


The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
ABB logo, small size	3HAC0453-6	
ABB logo, large size	3HAC0453-2	
Warning label	3HAC057068-001	Risk of tipping
Warning sign	3HAC1589-1	Electrical shock
Rating label	3HAB9549-1	
UL label	3HAC037252-001	
Lifting label	3HAC058299-001	
Instruction label	3HAC057070-001	Break release, moving robot
Calibration label	3HAC13488-1	
Calibration mark (axis 2)	3HAC057089-001	
Calibration mark (axis 3 and axis 4)	3HAC057090-001	

Required tools and equipment

Visual inspection, no tools are required.

Inspecting, labels

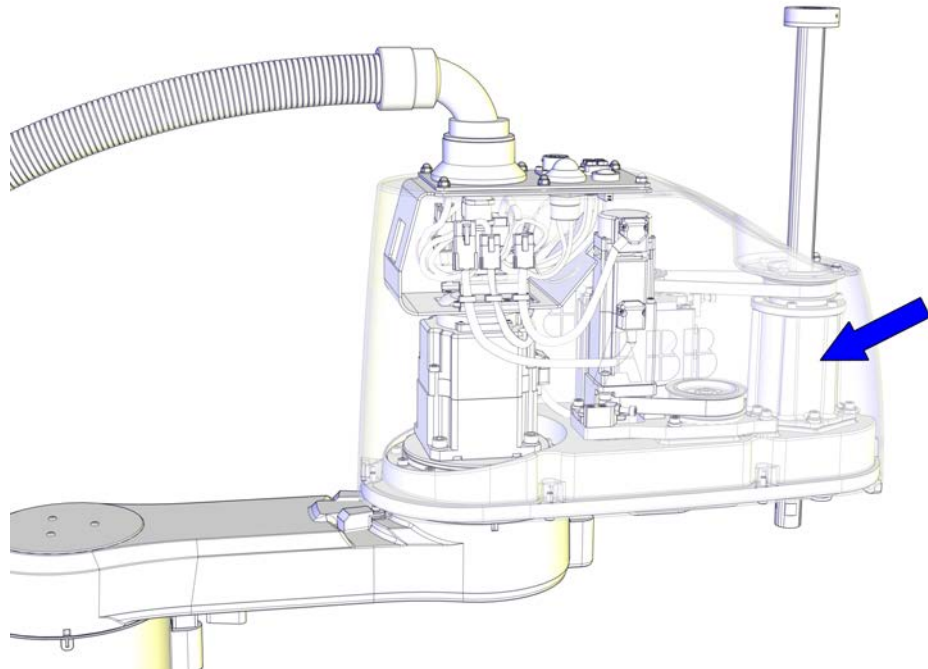
	Action	Note
1	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Inspect the labels, located as shown in the figures.	See the figures in Location of labels on page 83 .
3	Replace any missing or damaged labels.	

3 Maintenance

3.4.3 Inspecting the ball screw spline unit

3.4.3 Inspecting the ball screw spline unit

Location of ball screw spline unit



xx1500002212

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.


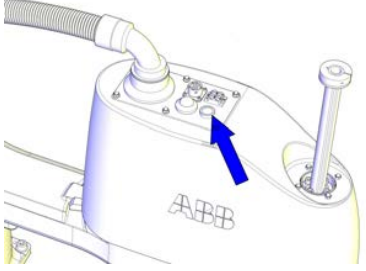
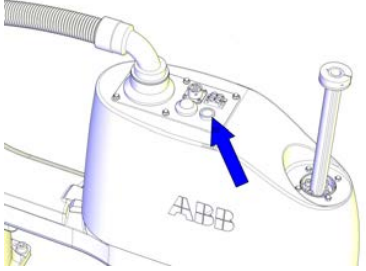
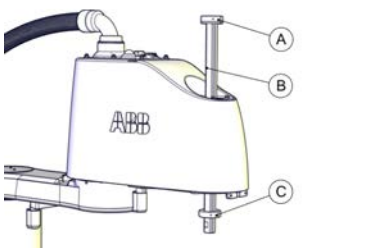
Spare part	Article number	Note
Ball screw spline unit	3HAC056148-001	

Required tools and equipment

Equipment	Note
24 VDC power supply	Used to release the motor brakes.
Other tools and procedures may be required if the spare part needs to be replaced. These are specified in the replacement procedure.	

Continues on next page

Inspecting, ball screw spline unit


	Action	Note						
1	Turn on the electric power to the robot. If the robot is not connected to the controller, power must be supplied to the connector R1.MP according to the section Supplying power to connector R1.MP on page 62 .							
2	 DANGER When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways! Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.							
3	Release the holding brake by pressing the button on the internal brake release unit.	 xx1500002774						
4	Move the upper arm to a position where the axis 3 can be moved in full stroke.							
5	Press the brake release button and move the shaft to its upper and lower limits manually.	 xx1500002774						
6	Visually inspect: <ul style="list-style-type: none"> • the stop blocks on the ball screw spline unit • the shaft of the ball screw spline unit Look for abrasions, cuts or crush damages on the spline, and grease amount on the shaft.	 xx1500002778 <table border="1" data-bbox="1066 1861 1433 1995"> <tr> <td data-bbox="1066 1861 1106 1906">A</td> <td data-bbox="1106 1861 1433 1906">Upper stop block</td> </tr> <tr> <td data-bbox="1066 1906 1106 1951">B</td> <td data-bbox="1106 1906 1433 1951">Shaft</td> </tr> <tr> <td data-bbox="1066 1951 1106 1995">C</td> <td data-bbox="1106 1951 1433 1995">Lower stop block</td> </tr> </table>	A	Upper stop block	B	Shaft	C	Lower stop block
A	Upper stop block							
B	Shaft							
C	Lower stop block							

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3 Maintenance

3.4.3 Inspecting the ball screw spline unit

Continued

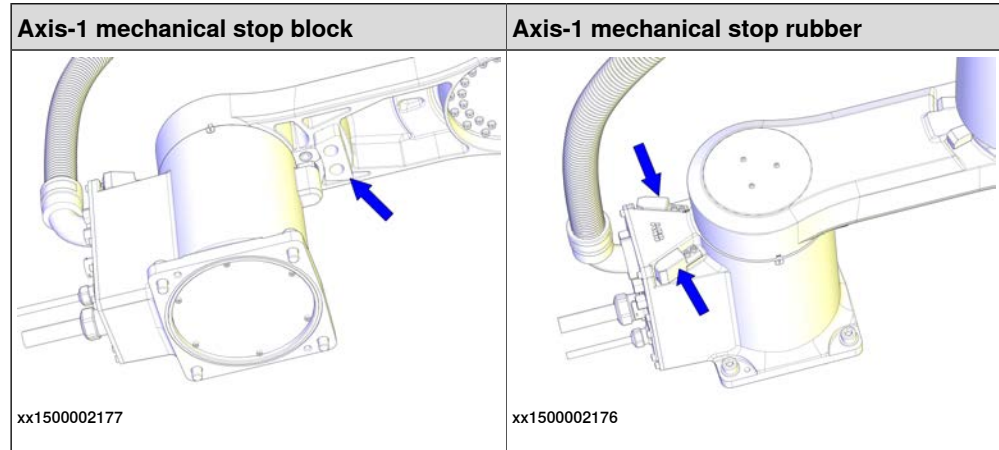
	Action	Note
7	Apply grease to the shaft if it is not enough.	See Lubricating the ball screw spline unit on page 111 .  xx1500002779
8	Replace the ball screw spline unit if wear or damage is detected.	See Replacing the ball screw spline unit on page 229 .

3.4.4 Inspecting axis-1 and axis-2 mechanical stops

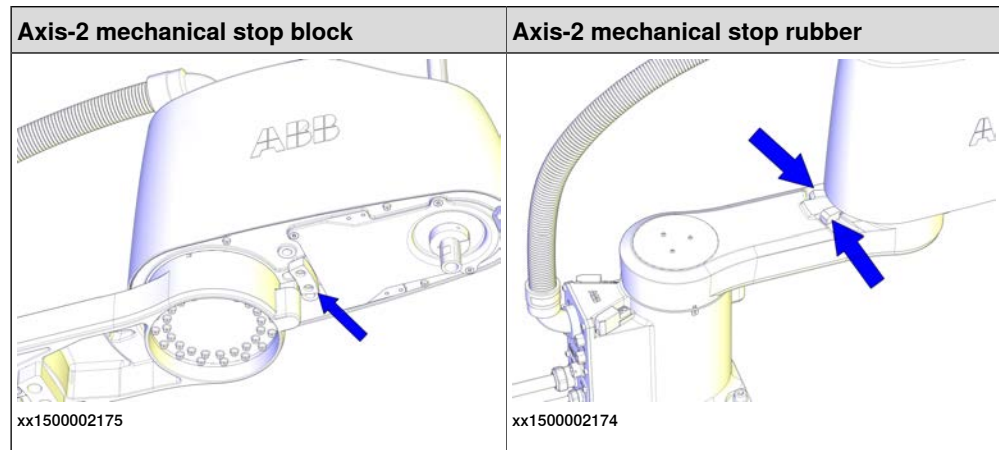
Location of axis-1 and axis-2 mechanical stops

The mechanical stops on axes 1 and 2 are located as shown in the figures.

Axis 1



Axis 2



Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-1 mechanical stop rubber	3HAC056042-001	Replace if damaged.
Axis-1 mechanical stop block	3HAC055164-001	Replace if damaged.
Axis-2 mechanical stop rubber	3HAC056017-001	Replace if damaged.
Axis-2 mechanical stop block	3HAC055185-001	Replace if damaged.

Continues on next page

3 Maintenance

3.4.4 Inspecting axis-1 and axis-2 mechanical stops

Continued


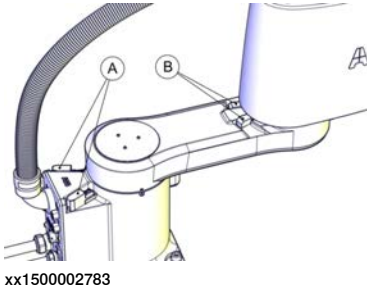
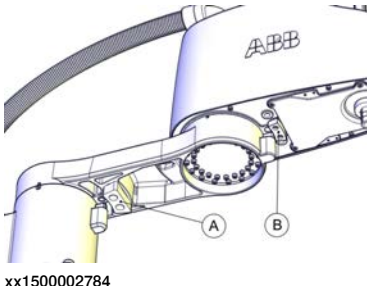
Required tools and equipment

Visual inspection, no tools are required.


Other tools and procedures may be required if the spare part needs to be replaced. These are specified in the replacement procedure.

Inspecting, axis-1 and axis-2 mechanical stops

Use this procedure to inspect mechanical stops on axes 1 and 2.

	Action	Information								
1	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>									
2	Inspect the mechanical stops.	<div style="text-align: right;">  <p>xx1500002783</p> <table border="1" style="width: 100%;"> <tr> <td style="width: 20px;">A</td> <td>Axis-1 mechanical stop rubbers</td> </tr> <tr> <td>B</td> <td>Axis-2 mechanical stop rubbers</td> </tr> </table> </div> <div style="text-align: right; margin-top: 10px;">  <p>xx1500002784</p> <table border="1" style="width: 100%;"> <tr> <td style="width: 20px;">A</td> <td>Axis-1 mechanical stop block</td> </tr> <tr> <td>B</td> <td>Axis-2 mechanical stop block</td> </tr> </table> </div>	A	Axis-1 mechanical stop rubbers	B	Axis-2 mechanical stop rubbers	A	Axis-1 mechanical stop block	B	Axis-2 mechanical stop block
A	Axis-1 mechanical stop rubbers									
B	Axis-2 mechanical stop rubbers									
A	Axis-1 mechanical stop block									
B	Axis-2 mechanical stop block									

Continues on next page

	Action	Information
3	<p>Replace if any mechanical stop is:</p> <ul style="list-style-type: none">• bent• loose• damaged. <p> Note</p> <p>The expected life of gearboxes can be reduced as a result of collisions with the mechanical stop.</p>	

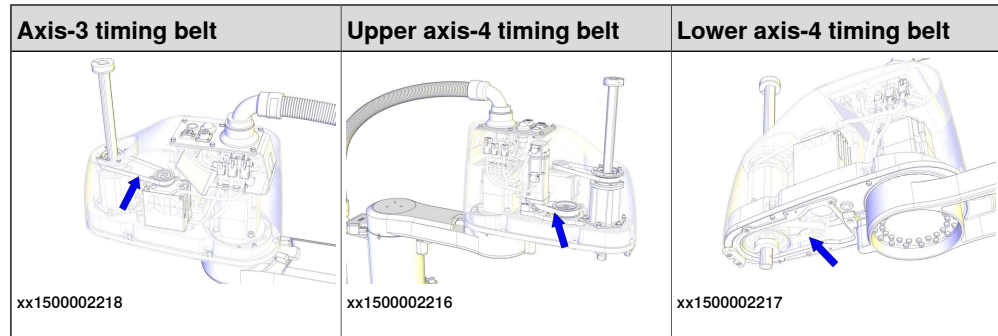
3 Maintenance

3.4.5 Inspecting the timing belts

3.4.5 Inspecting the timing belts

Location of timing belts

The timing belts are located as shown in the figures.



Required tools and equipment

Equipment	Note
Standard toolkit	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	Used for measuring the timing belt tension.
Other tools and procedures may be required if the spare part needs to be replaced. These are specified in the replacement procedure.	

Timing belt tension

The table describes the timing belt tension.

Axis	Timing belt tension
Axis 3	<p>Recommended: 34 N</p> <p>Tension range of new belt: 31.1 to 34.2 N</p> <p>Tension range of used beltⁱ: 21.8 N to 24.9 N</p>
Axis 4	<p>Upper timing belt</p> <p>Recommended: 37 N</p> <p>Tension range of new belt: 34.5 N to 37.9 N</p> <p>Tension range of used beltⁱ: 24.1 N to 27.6 N</p>
	<p>Lower timing belt</p> <p>Recommended: 101 N</p> <p>Tension range of new belt: 92.2 N to 101 N</p> <p>Tension range of used beltⁱ: 64.5 N to 73.7 N</p>

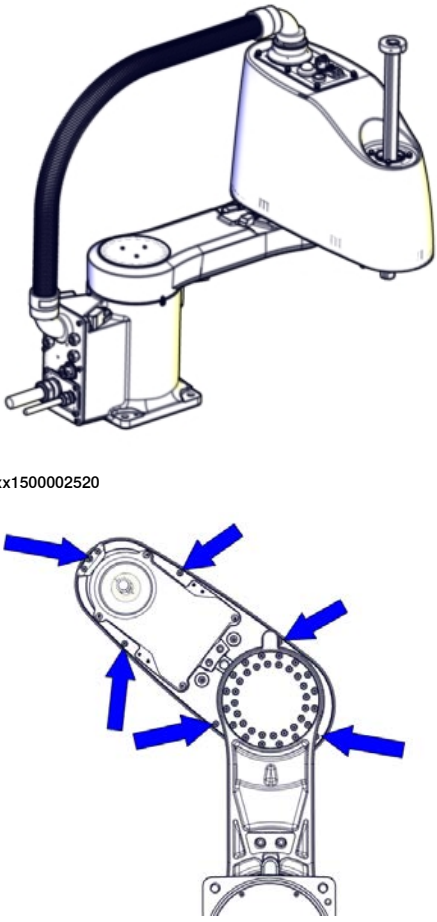

ⁱ Used belt is the one having been installed and used for more than 24 hours.

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Inspecting timing belts

Use this procedure to inspect timing belts.

Preparations before inspecting timing belts

	Action	Note
1	Jog axis 2 to access the cover screws.	 <p>xx1500002520</p> <p>xx1500002782</p>
2	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	


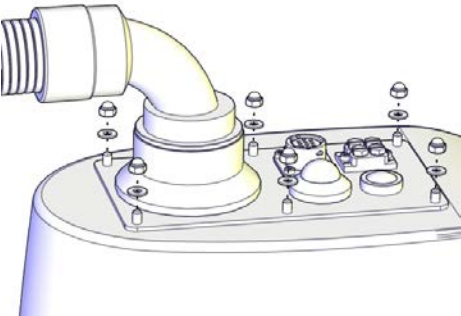

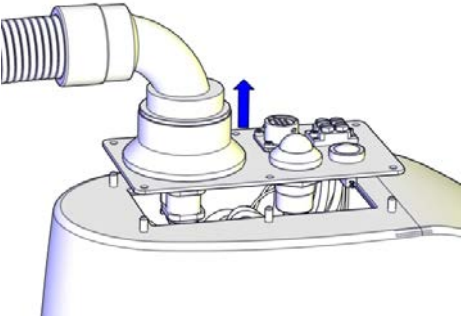
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3 Maintenance


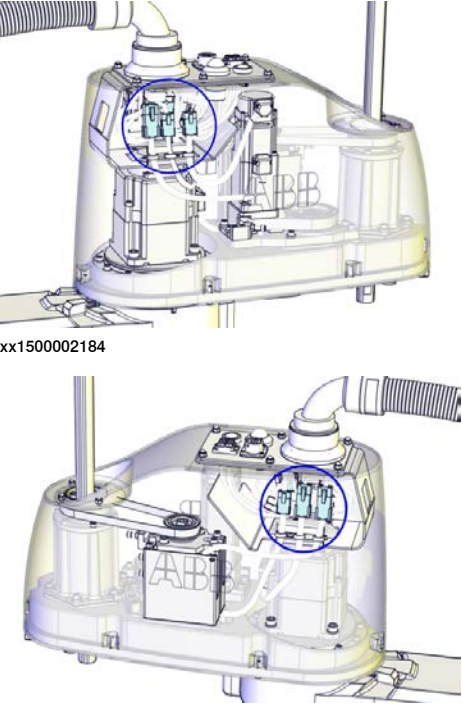
3.4.5 Inspecting the timing belts

Continued



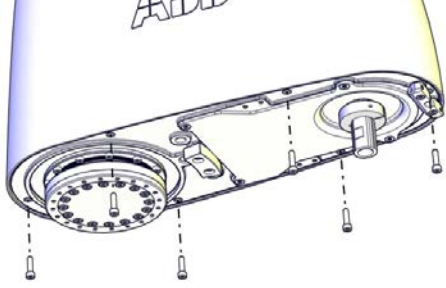
Removing the main cable package from the upper arm

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the dome nuts and washers.	 xx1500002182
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 xx1500002183

Continues on next page

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002184</p> <p>xx1500002185</p>

Removing the upper cover


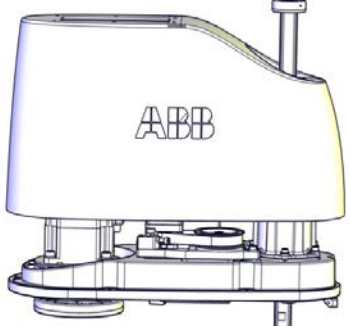
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	 <p>xx1500002220</p>

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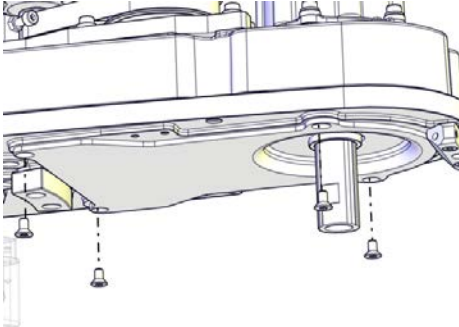

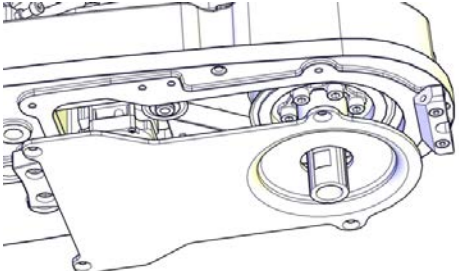
3 Maintenance

3.4.5 Inspecting the timing belts

Continued

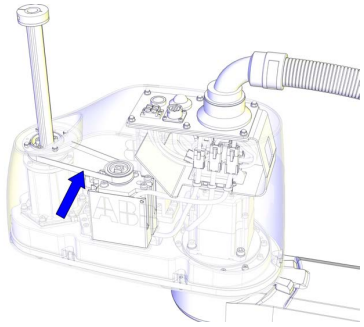
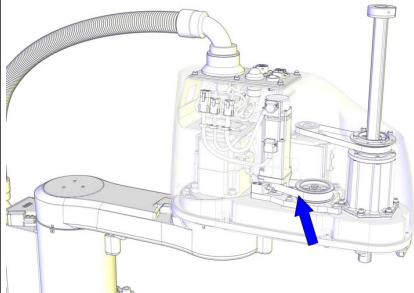
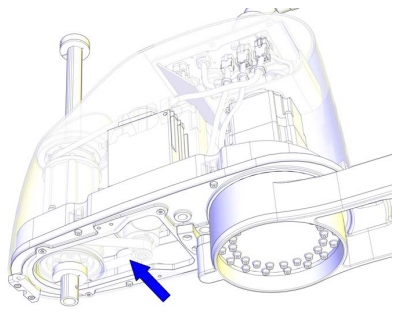
	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 xx1500002221

Removing the lower cover

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the screws.	 xx1500002785
3	Remove the cover.  Tip If only working with lower axis-4 timing belt, no need to remove the stop block of ball screw spline unit before removing the lower cover.	 xx1500002225

Continues on next page

Inspecting timing belts

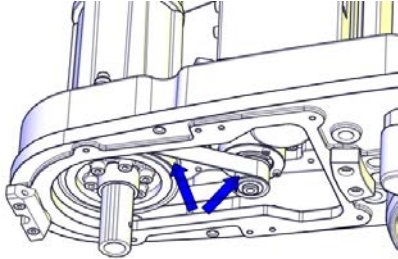
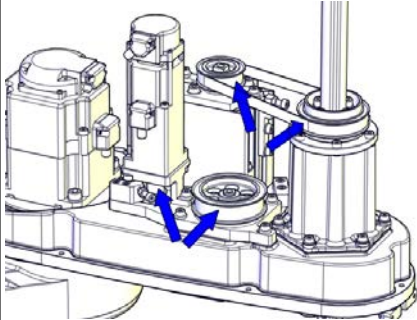
	Action	Information
1	Check the timing belts for damage or wear.	 <p>xx150002218</p>  <p>xx150002216</p>  <p>xx150002217</p>

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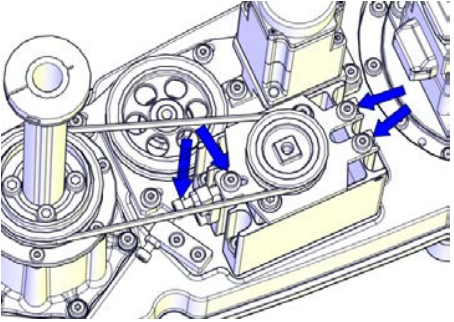
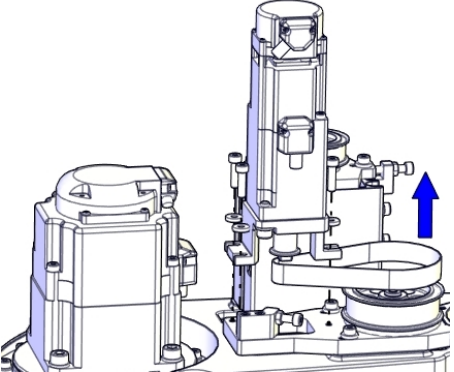
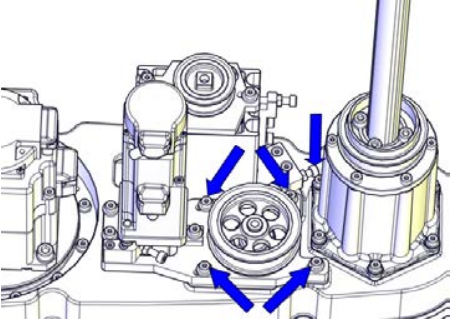
3 Maintenance

3.4.5 Inspecting the timing belts

Continued

	Action	Information
2	Check the timing belt pulleys for damage.	 xx1500002780  xx1500002781
3	If any damage or wear is detected, the part must be replaced!	
4	Check each belt for tension.	Timing belt tensions are specified in Timing belt tension on page 92 .

Continues on next page

	Action	Information
5	<p>If the belt tension is not correct, adjust screws while using a sonic tensiometer to measure the belt tension until a proper belt tension is achieved!</p>	 <p>xx1500002229</p>  <p>xx1500002233</p>  <p>xx1500002231</p>

3 Maintenance

3.5.1 Replacing the battery pack

3.5 Replacement/changing activities

3.5.1 Replacing the battery pack

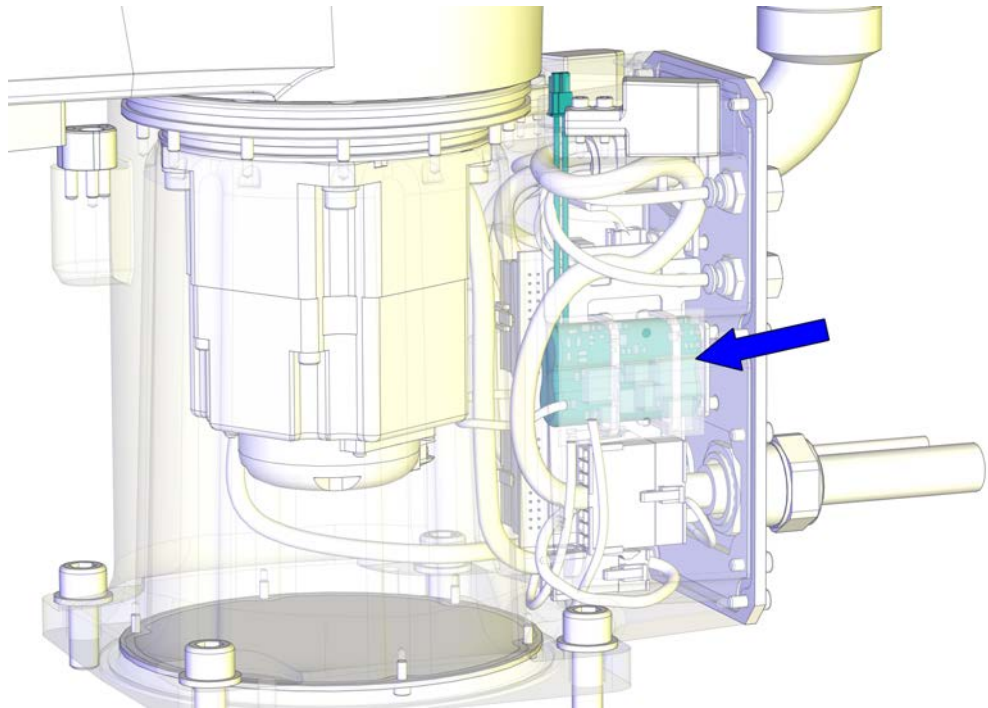


Note

The battery low alert (38213 **Battery charge low**) is displayed when remaining backup capacity (robot powered off) is less than 2 months. Typical life of a new battery is 36 months if the robot is powered off 2 days/week, or 18 months if the robot is powered off 16 hours/day. The life can be extended (approximately 3 times) for longer production breaks by a battery shutdown service routine. See *Operating manual - IRC5 with FlexPendant*.

Location of the battery pack

The battery pack is located as shown in the figure.



xx1500002180

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

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Continued

Spare part	Article number	Note
Battery pack	3HAC051036-001	Battery includes protection circuits. Only replace with a specified spare part or an ABB-approved equivalent.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

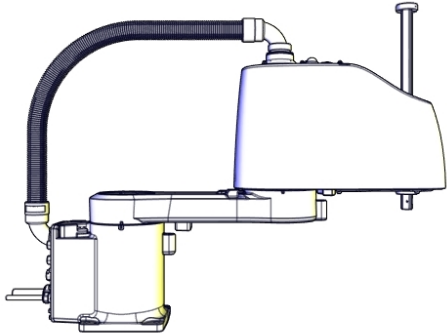

Required consumables

Consumable	Article number	Note
Cable ties	-	

Removing the battery pack

Use these procedures to remove the battery pack.

Preparations before removing the battery pack

	Action	Note
1	Jog all axes to zero position.	 <p>xx1500002227</p>
2	 <p>DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	


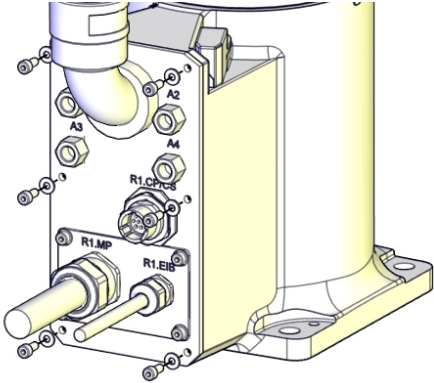


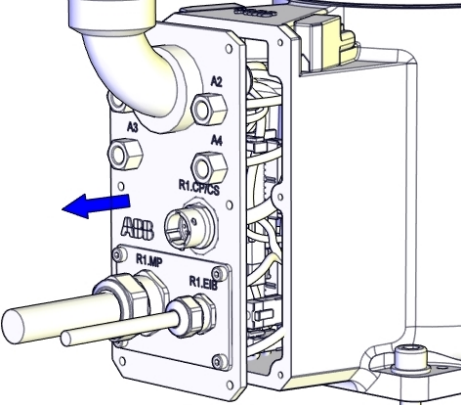

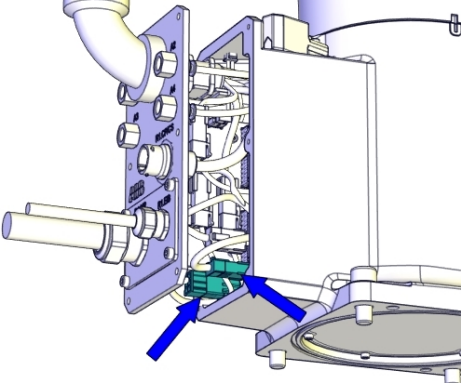
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3 Maintenance

3.5.1 Replacing the battery pack




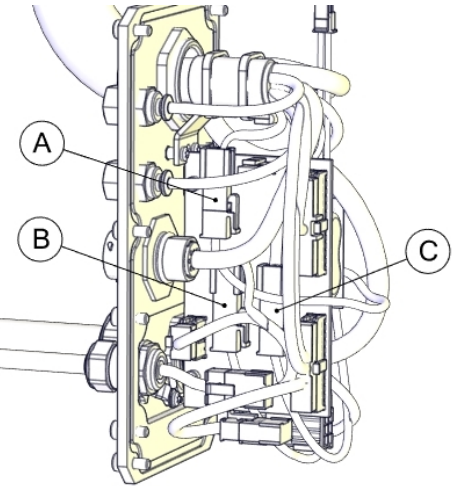
Continued

Removing the main cable package from the base

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws and washers.	 <p>xx1500002186</p>
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>

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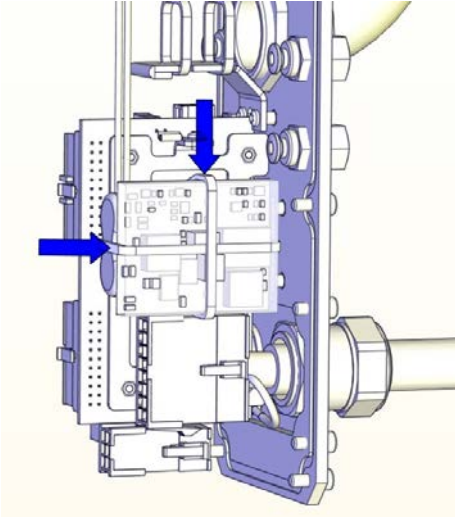
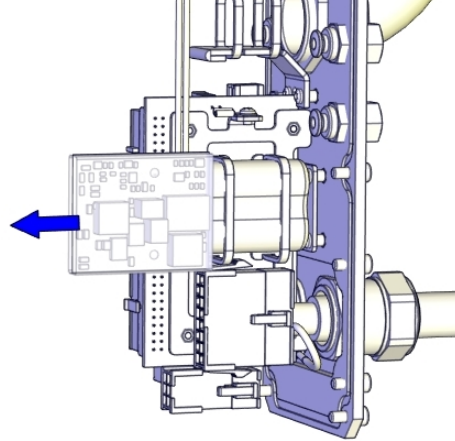
Removing the PCB board

	Action	Note						
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>							
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>							
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="973 1339 1439 1473"> <tbody> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </tbody> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							



3 Maintenance

3.5.1 Replacing the battery pack

Continued

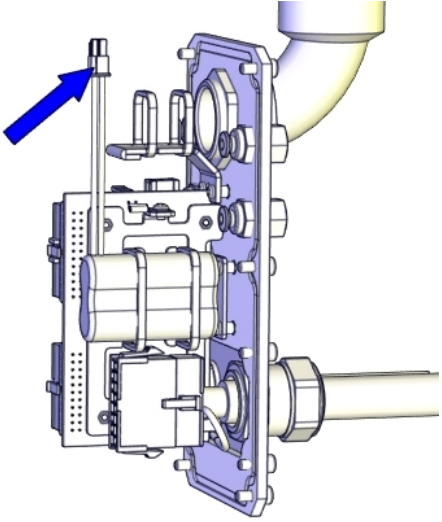
	Action	Note
4	Cut the cable ties.	 <p data-bbox="943 831 1050 853">xx1500002752</p>
5	Remove the PCB board carefully.	 <p data-bbox="943 1346 1050 1368">xx1500002191</p>

Disconnecting the battery cable



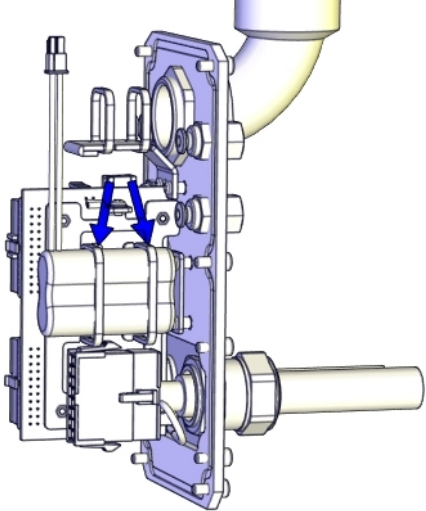
	Action	Note
1	 <p data-bbox="555 1547 667 1576">DANGER</p> <p data-bbox="464 1608 933 1688">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p data-bbox="555 1749 916 1800">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="464 1821 933 1928">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

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Continued

	Action	Note
3	Disconnect the battery cable.	 <p data-bbox="970 840 1082 862">xx1500002192</p>

Removing the battery pack


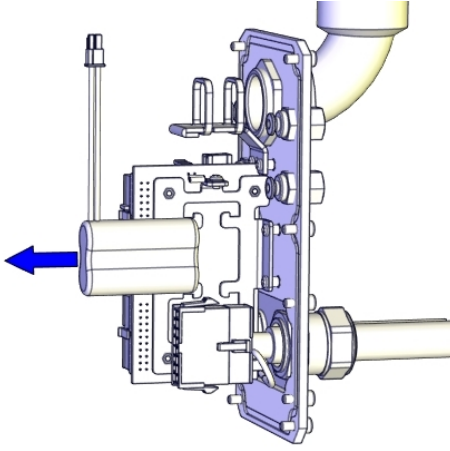
	Action	Note
1	 <p data-bbox="587 1041 694 1070">DANGER</p> <p data-bbox="497 1102 962 1182">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p data-bbox="587 1236 946 1294">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="497 1312 962 1420">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
3	Cut the cable ties.	 <p data-bbox="970 1975 1082 1998">xx1500002193</p>

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3 Maintenance

3.5.1 Replacing the battery pack



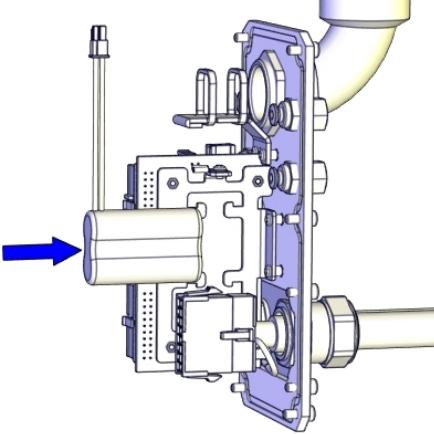
Continued

	Action	Note
4	<p>Remove the battery.</p> <p> Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002194</p>

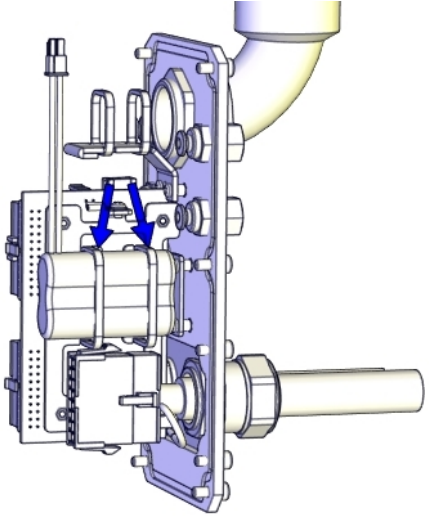
Refitting the battery pack

Use these procedures to refit the battery pack.


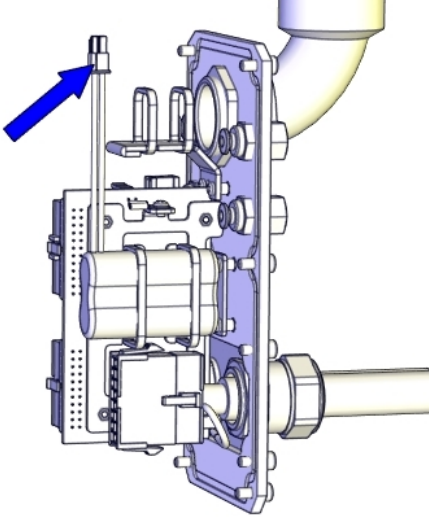
Refitting the battery pack

	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
2	<p>Fit the battery.</p> <p> Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002206</p>

Continues on next page

	Action	Note
3	Secure the battery with cable ties.	 <p data-bbox="970 840 1082 862">xx1500002193</p>

Connecting the battery cable

	Action	Note
1	 <p data-bbox="587 1032 946 1093">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="497 1111 962 1216">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	
2	Connect the battery cable.	 <p data-bbox="970 1780 1082 1803">xx1500002192</p>



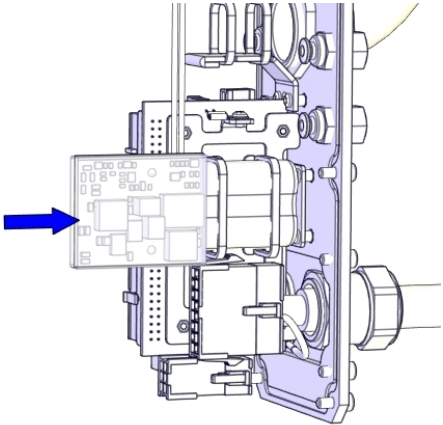
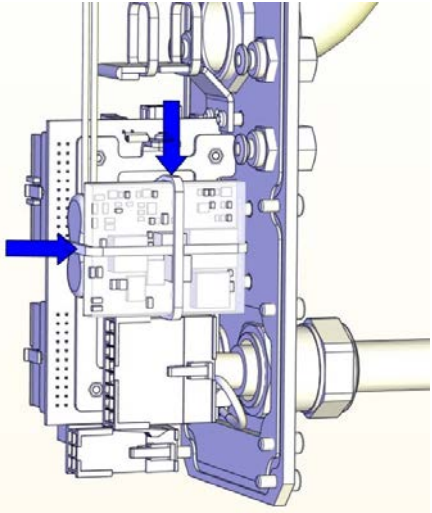
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3 Maintenance


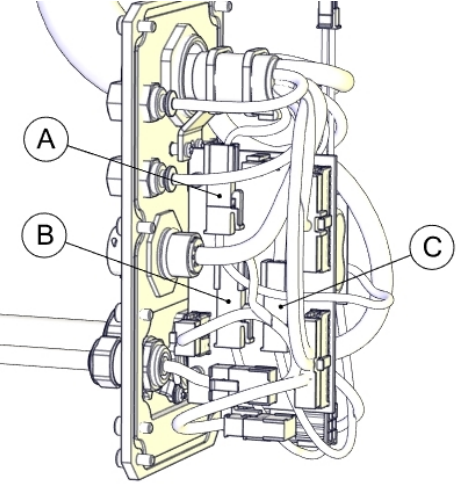
3.5.1 Replacing the battery pack

Continued

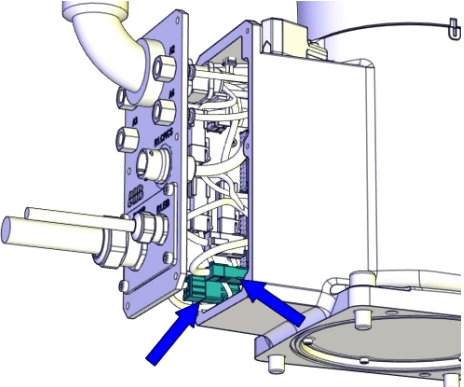
Refitting the PCB board

	Action	Note
1	 ELECTROSTATIC DISCHARGE (ESD) The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i>	
2	Refit the PCB board.  Note The PCB board is protected by shrink hose. Replace the hose if damaged.	PCB board: 3HAC057687-001  xx150002205
3	Secure the PCB board with cable ties. Do not tighten the ties too tight.	 xx150002752

Continues on next page

	Action	Note						
4	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> CAUTION</p> <p>Make sure not to mix the connectors. See the labels on the connectors for correct connection.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="975 837 1441 976"> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
5	Secure the cables with cable ties if needed.							

Refitting the main cable to the base

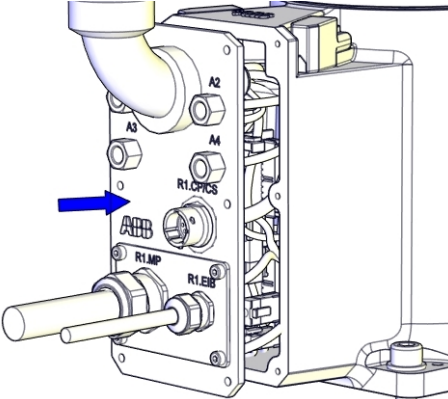
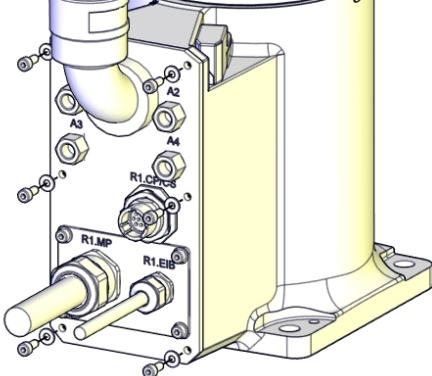
	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p>xx1500002188</p>

Continues on next page


3 Maintenance

3.5.1 Replacing the battery pack

Continued

	Action	Note
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Concluding procedure

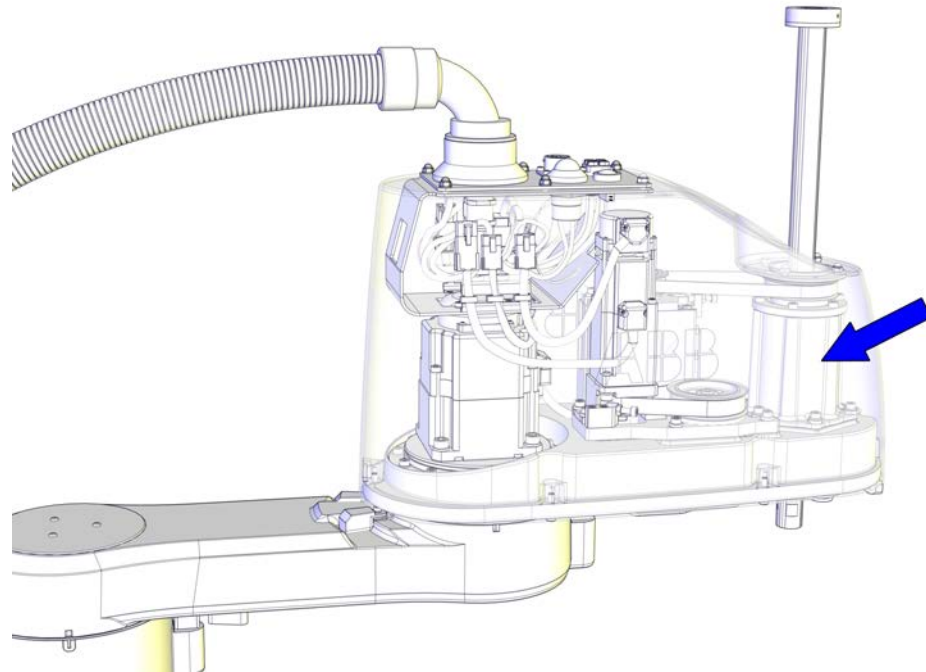
	Action	Note
1	Update the revolution counters.	See Updating revolution counters on page 351 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

3.6 Lubrication activities

3.6.1 Lubricating the ball screw spline unit

Location of the ball screw spline unit

The ball screw spline unit is located as shown in the figure.



xx1500002212

Required tools and equipment

Equipment	Article number	Note
24 VDC power supply	-	Used to release the motor brakes.

Required consumables

Consumable	Article number	Note
Grease	-	THK AFA Used for lubricating the ball screw spline shaft.

Lubricating the ball screw spline unit



Note


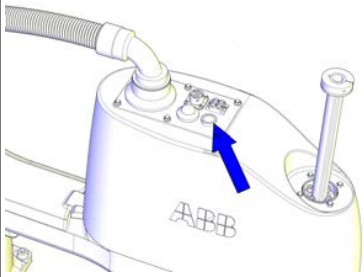
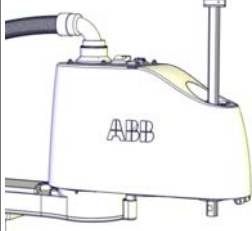
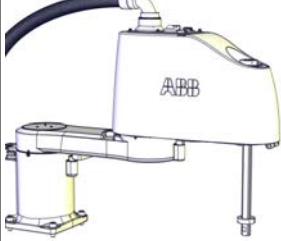
Cover the end effector and peripheral equipment in case the grease drips, before lubricating the ball screw spline unit.

Continues on next page

3 Maintenance

3.6.1 Lubricating the ball screw spline unit

Continued

	Action	Note
1	Turn on the electric power to the robot. If the robot is not connected to the controller, power must be supplied to the connector R1.MP according to the section Supplying power to connector R1.MP on page 62 .	
2	 DANGER When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways! Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.	
3	Release the holding brake by pressing the button on the internal brake release unit.	 <p>xx1500002774</p>
4	Move the upper arm to a position where the axis 3 can be moved in full stroke.	
5	Move the shaft manually to its upper limit while pressing the brake release button.	 <p>xx1500002790</p>
6	Wipe off old grease from the shaft.	
7	Apply new grease and fill the grooves. Wipe off excessive grease.	
8	Move the shaft manually to its lower limit while pressing the brake release button.	 <p>xx1500002791</p>
9	Wipe off old grease from the shaft.	
10	Apply new grease and fill the grooves. Wipe off excessive grease.	

Continues on next page

	Action	Note
11	Move the shaft up and down several times while pressing the brake release button to smooth out the grease on the shaft. Wipe off excessive grease.	

3 Maintenance

3.7.1 Cleaning the IRB 910SC

3.7 Cleaning activities

3.7.1 Cleaning the IRB 910SC



DANGER

Turn off all:

- electric power supply
- hydraulic pressure supply
- air pressure supply

to the robot, before entering the safeguarded space.

General

To secure high uptime it is important that the IRB 910SC is cleaned regularly. The frequency of cleaning depends on the environment in which the product works. Different cleaning methods are allowed depending on the type of protection of the IRB 910SC.



Note

Always verify the protection type of the robot before cleaning.

Special cleaning considerations

This section specifies some special considerations when cleaning the robot.

- Always use cleaning equipment as specified. Any other cleaning equipment may shorten the life of the robot.
- Always check that all protective covers are fitted to the robot before cleaning.
- Never point the water jet at connectors, joints, sealings, or gaskets.
- Do not use compressed air to clean the robot.
- Never use solvents that are not approved by ABB to clean the robot.
- Do not spray from a distance closer than 0.4 m.
- Do not remove any covers or other protective devices before cleaning the robot.

Cleaning methods

The following table defines what cleaning methods are allowed depending on the protection type.

Protection type	Cleaning method			
	Vacuum cleaner	Wipe with cloth	Rinse with water	High pressure water or steam
Standard IP20	Yes	Yes. With light cleaning detergent.	No	No

Continues on next page

Cables

Movable cables need to be able to move freely:

- Remove waste material, such as sand, dust and chips, if it prevents cable movement.
- Clean the cables if they have a crusty surface, for example from dry release agents.

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4 Repair

4.1 Introduction

Structure of this chapter

This chapter describes repair activities for the IRB 910SC. Each procedure contains the information required to perform the activity, for example spare parts numbers, required special tools, and materials.



WARNING

Repair activities not described in this chapter must only be carried out by ABB.

Report replaced units



Note

When replacing a part on the IRB 910SC, report to your local ABB the serial number, the article number, and the revision of both the replaced unit and the replacement unit.

This is particularly important for safety equipment to maintain the safety integrity of the installation.

Safety information

Make sure to read through the chapter [Safety on page 17](#) before commencing any service work.



Note

If the IRB 910SC is connected to power, always make sure that the IRB 910SC is connected to protective earth and a residual current device (RCD) before starting any repair work.

For more information see:

- *Product manual - IRC5 Compact*

4 Repair

4.2.1 Cut the paint or surface on the robot before replacing parts

4.2 General procedures

4.2.1 Cut the paint or surface on the robot before replacing parts

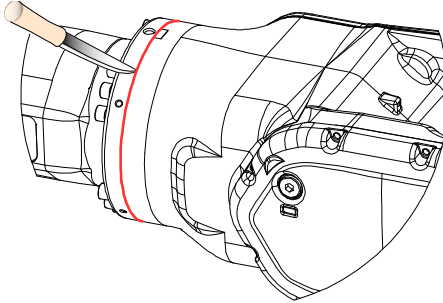
General

Follow the procedures in this section whenever breaking the paint of the robot during replacement of parts.

Required equipment

Equipment	Spare parts	Note
Cleaning agent		Ethanol
Knife		
Lint free cloth		
Touch up paint Standard/Foundry Plus	3HAC067974-001	Graphite White

Removing

	Action	Description
1	Cut the paint with a knife in the joint between the part that will be removed and the structure, to avoid that the paint cracks.	 xx0900000121
2	Carefully grind the paint edge that is left on the structure to a smooth surface.	

4.2.2 Mounting instructions for sealings

General

This section describes how to mount different types of sealings.

Equipment

Consumable	Article number	Note
Grease	3HAC042536-001	Shell Gadus S2

Rotating sealings

The procedure below describes how to fit rotating sealings.



CAUTION

Please observe the following before commencing any assembly of sealings:

- Protect the sealing during transport and mounting, especially the main lip.
- Keep the sealing in its original wrappings or protect it well before actual mounting.
- The fitting of sealings and gears must be carried out on clean workbenches.
- Use a protective sleeve for the main lip during mounting, when sliding over threads, keyways or other sharp edges.

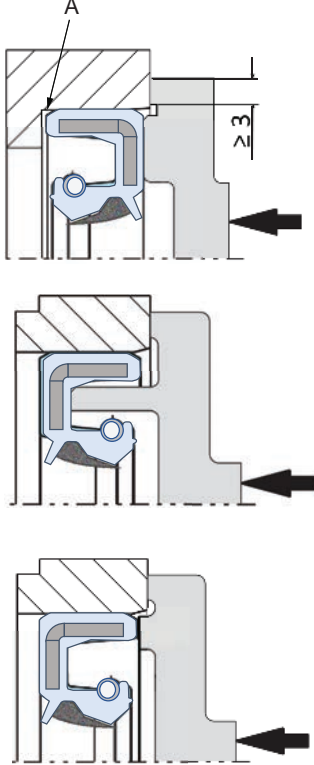
Action	Note
1 Check the sealing to ensure that: <ul style="list-style-type: none"> • The sealing is of the correct type. • There is no damage on the main lip. 	
2 Inspect the shaft surface before mounting. If scratches or damage are found, the shaft must be replaced since it may result in future leakage. Do not try to grind or polish the shaft surface to get rid of the defect.	
3 Lubricate the sealing with grease just before fitting. (Not too early - there is a risk of dirt and foreign particles adhering to the sealing.) Fill 2/3 of the space between the dust lip and the main lip with grease. If the sealing is without dust lip, just lubricate the main lip with a thin layer of grease.	<p>Article number is specified in Equipment on page 119.</p> <p>xx2000000071</p> <p>A Main lip B Grease C Dust lip</p>

Continues on next page

4 Repair

4.2.2 Mounting instructions for sealings

Continued

	Action	Note
4	<p>Mount the sealing correctly with a mounting tool. Never hammer directly on the sealing as this may result in leakage.</p>	 <p>xx2000000072</p> <p>A Gap</p>

Flange sealings and static sealings

The following procedure describes how to fit flange sealings and static sealings.

	Action
1	<p>Check the flange surfaces. They must be even and free from pores. It is easy to check flatness using a gauge on the fastened joint (without sealing compound). If the flange surfaces are defective, the parts may not be used because leakage could occur.</p>
2	<p>Clean the surfaces properly in accordance with the recommendations of ABB.</p>
3	<p>Distribute the sealing compound evenly over the surface, preferably with a brush.</p>
4	<p>Tighten the screws evenly when fastening the flange joint.</p>

O-rings

The following procedure describes how to fit o-rings.

	Action	Note
1	<p>Ensure that the correct o-ring size is used.</p>	
2	<p>Check the o-ring for surface defects, burrs, shape accuracy, or deformation.</p>	<p>Defective o-rings, including damaged or deformed o-rings, may not be used.</p>

Continues on next page

	Action	Note
3	Check the o-ring grooves. The grooves must be geometrically correct and should be free of pores and contamination.	
4	Lubricate the o-ring with grease.	
5	Tighten the screws evenly while assembling.	
6	Check that the o-ring is not squashed outside the o-ring groove.	

4 Repair

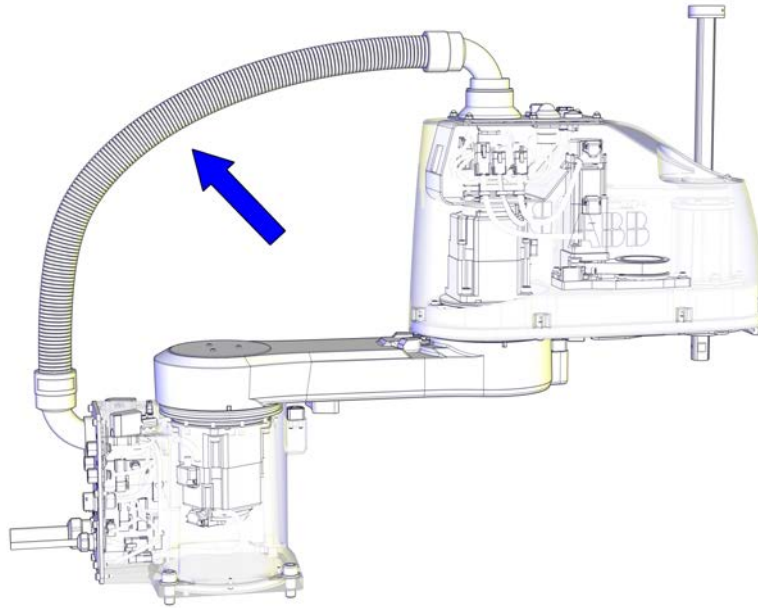
4.3.1 Replacing the main cable package

4.3 Cable harness

4.3.1 Replacing the main cable package

Location of the main cable package

The main cable package is located as shown in the figure.



xx1500002172

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Main cable, 450 mm	3HAC056165-001	
Main cable, 550 mm	3HAC056080-001	
Main cable, 650 mm	3HAC056166-001	
EIB connection cable	3HAC056703-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

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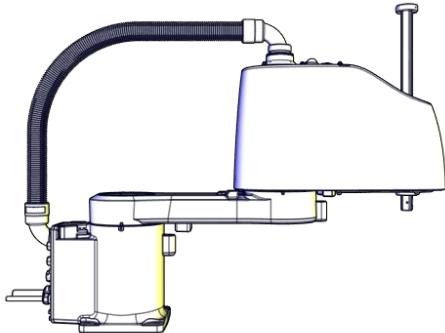

Required consumables

Consumable	Article number	Note
Shrink hose	-	Used for protecting the PCB board.
Cable ties	-	


Removing the main cable package

Use these procedures to remove the main cable package.

Preparations before removing the main cable package

	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the upper arm

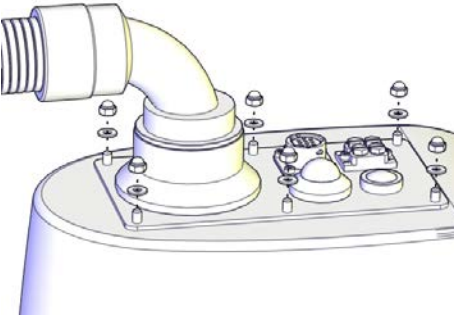

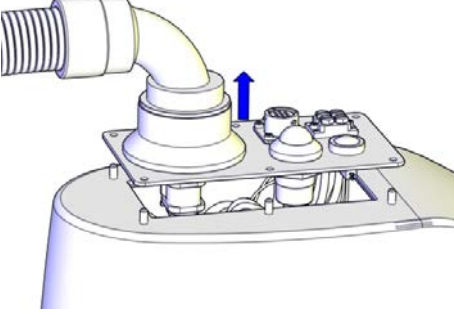

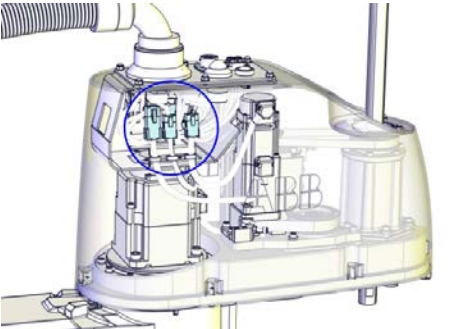
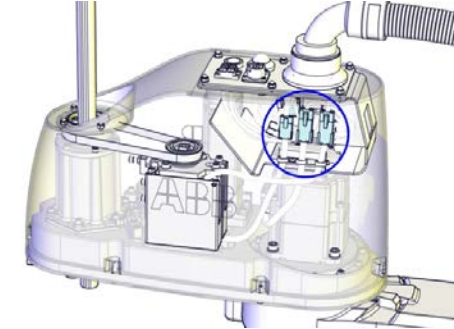
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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4 Repair


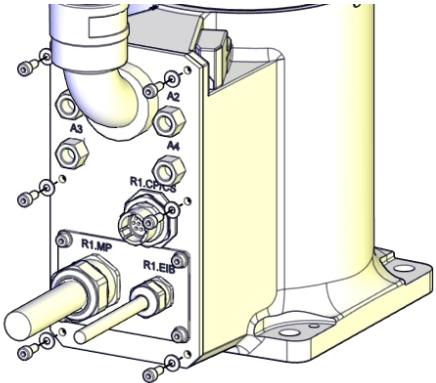


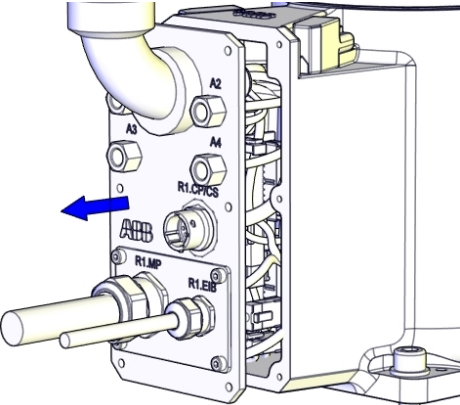

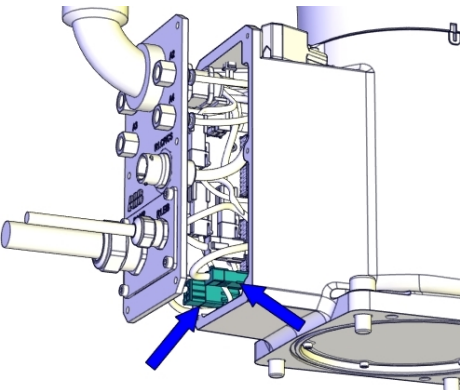
4.3.1 Replacing the main cable package

Continued

	Action	Note
2	Remove the dome nuts and washers.	 xx1500002182
3	Carefully open the user interface plate and pull out the cable package.  CAUTION The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.	 xx1500002183
4	Disconnect the connectors: <ul style="list-style-type: none">• R2.MP2• R2.MP3• R2.MP4• R2.ME2• R2.ME3• R2.ME4  Tip Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.	 xx1500002184  xx1500002185

Continues on next page

Removing the main cable package from the base

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the screws and washers.</p>	 <p>xx1500002186</p>
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>




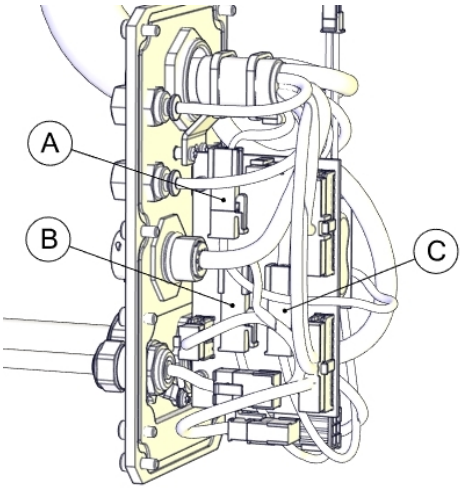
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4 Repair

4.3.1 Replacing the main cable package

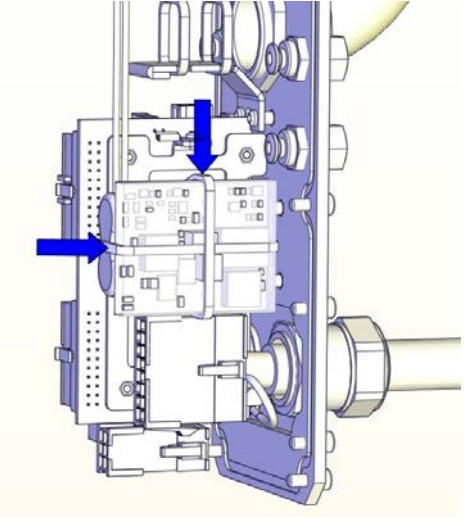
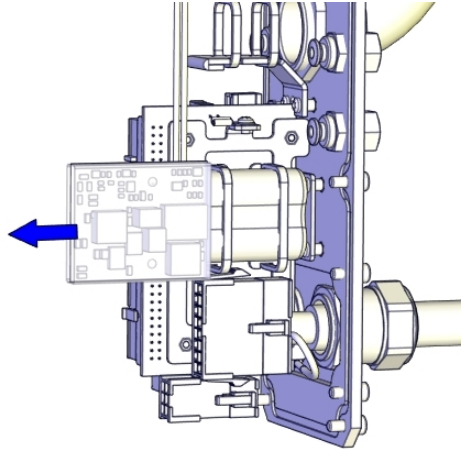
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Removing the PCB board



	Action	Note						
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>							
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>							
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="941 1332 1404 1467"> <tbody> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </tbody> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							

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4.3.1 Replacing the main cable package
Continued

	Action	Note
4	Cut the cable ties.	 <p>xx1500002752</p>
5	Remove the PCB board carefully.	 <p>xx1500002191</p>

Disconnecting the battery cable

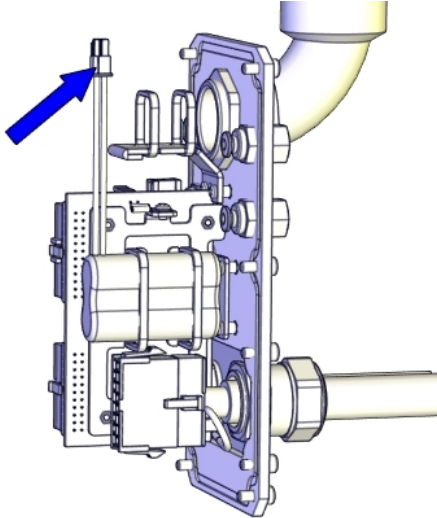
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

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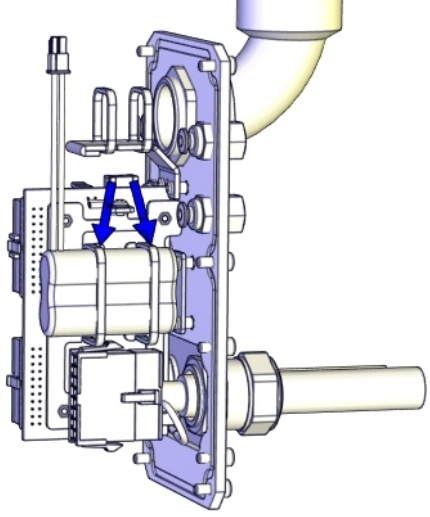
4 Repair

4.3.1 Replacing the main cable package

Continued


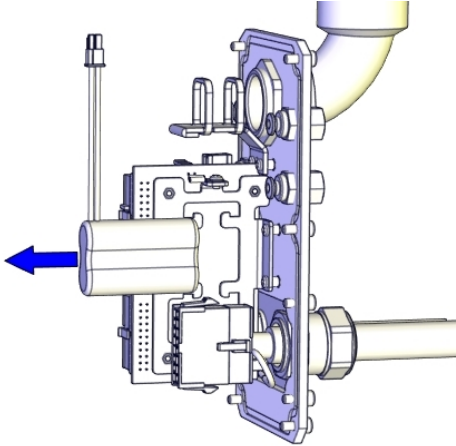
	Action	Note
3	Disconnect the battery cable.	 <p data-bbox="943 840 1050 857">xx1500002192</p>

Removing the battery pack



	Action	Note
1	 <p data-bbox="555 1037 667 1066">DANGER</p> <p data-bbox="464 1099 933 1178">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p data-bbox="555 1234 916 1290">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="464 1312 933 1417">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
3	Cut the cable ties.	 <p data-bbox="943 1982 1050 2000">xx1500002193</p>

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4.3.1 Replacing the main cable package
Continued

	Action	Note
4	<p>Remove the battery.</p> <p> Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002194</p>

Removing the EIB unit

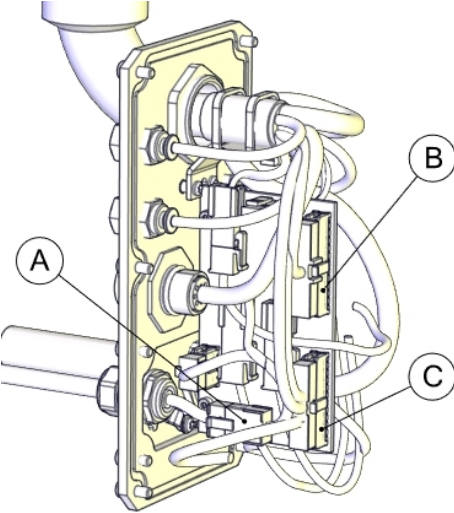
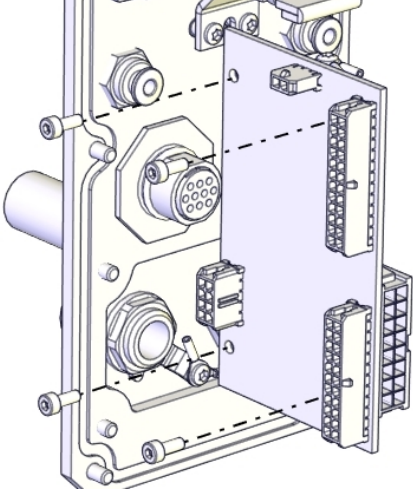
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

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4 Repair

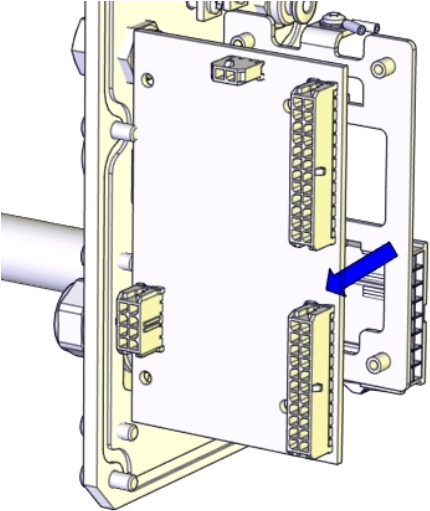
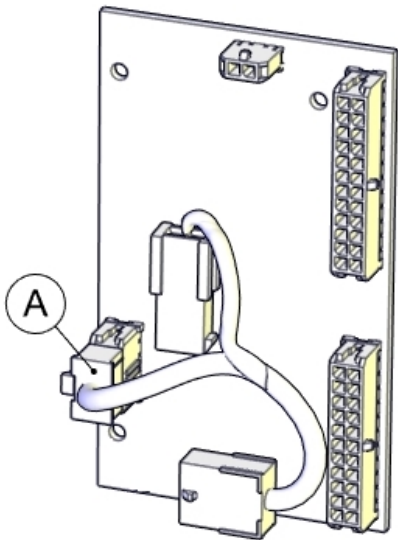
4.3.1 Replacing the main cable package

Continued


	Action	Note						
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none">• R1.EIB• R1.ME4• R1.ME1-3	 <p>xx1500002195</p> <table border="1" data-bbox="943 869 1398 1003"><tr><td>A</td><td>R1.EIB</td></tr><tr><td>B</td><td>R1.ME4</td></tr><tr><td>C</td><td>R1.ME1-3</td></tr></table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							
4	Remove the screws.	 <p>xx1500002792</p>						

Continues on next page

4.3.1 Replacing the main cable package
Continued

	Action	Note		
5	Remove the EIB unit.	 <p>xx1500002196</p>		
6	Disconnect the connector to remove the EIB connection cable. <ul style="list-style-type: none"> • R2.EIB 	 <p>xx1500002197</p> <table border="1" data-bbox="973 1523 1436 1579"> <tr> <td style="width: 20px;">A</td> <td>R2.EIB</td> </tr> </table>	A	R2.EIB
A	R2.EIB			

Removing the EIB mounting plate

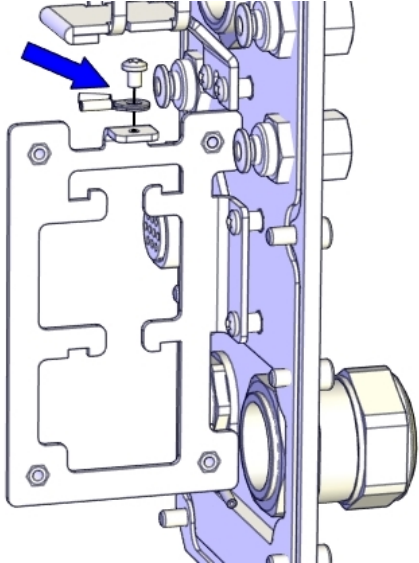
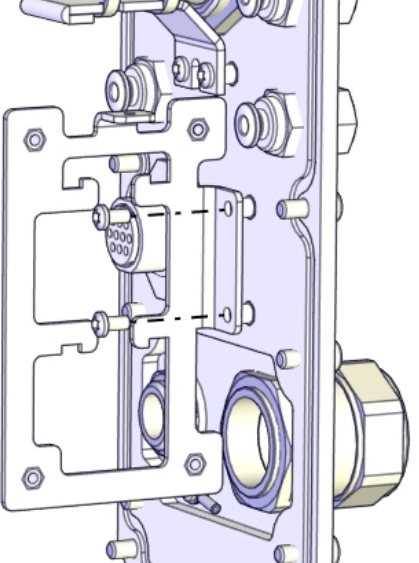
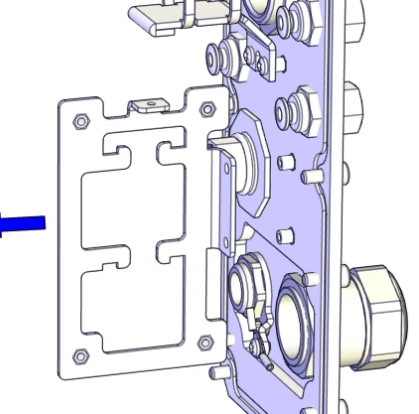
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

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4 Repair


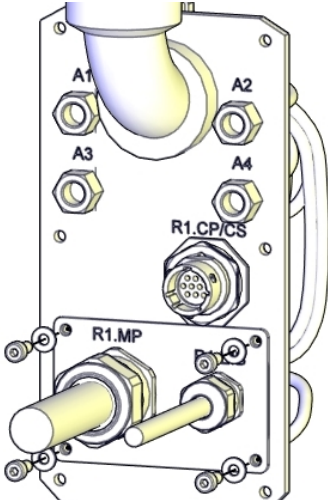
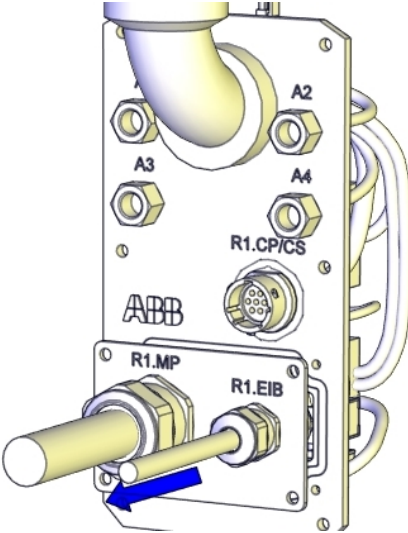
4.3.1 Replacing the main cable package

Continued


	Action	Note
2	Disconnect the earth cable by removing the screw.	 <p>Diagram illustrating the removal of the screw that disconnects the earth cable. A blue arrow points to the screw being removed.</p> <p>xx1500002794</p>
3	Remove the screws.	 <p>Diagram illustrating the removal of the screws that hold the EIB mounting plate in place.</p> <p>xx1500002795</p>
4	Remove the EIB mounting plate.	 <p>Diagram illustrating the removal of the EIB mounting plate. A blue arrow points to the plate being removed.</p> <p>xx1500002198</p>

Continues on next page

Removing the floor cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the screws and washers.	 <p>xx1500002199</p>
3	Pull out the floor cables.	 <p>xx1500002200</p>

Disconnecting the floor cable connector

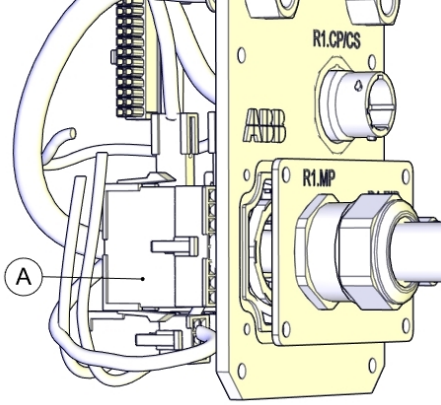
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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4 Repair

4.3.1 Replacing the main cable package

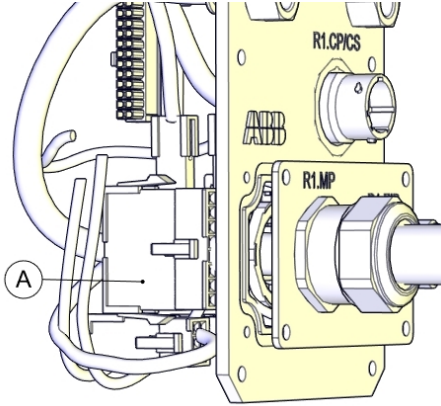
Continued

	Action	Note		
2	Disconnect the connector: <ul style="list-style-type: none">• R1.MP	 <p>xx1500002201</p> <table border="1" data-bbox="943 770 1399 815"><tr><td>A</td><td>R1.MP</td></tr></table>	A	R1.MP
A	R1.MP			

Refitting the main cable package

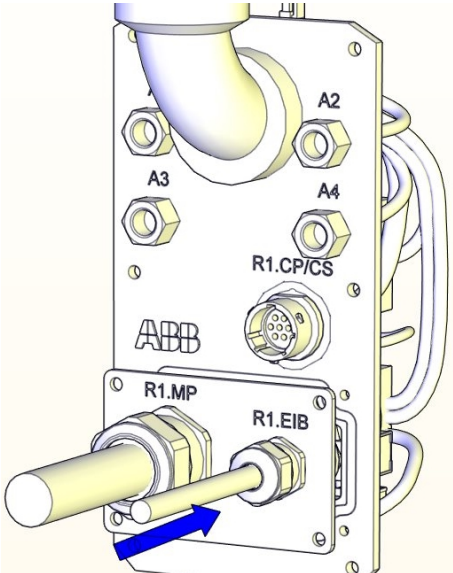
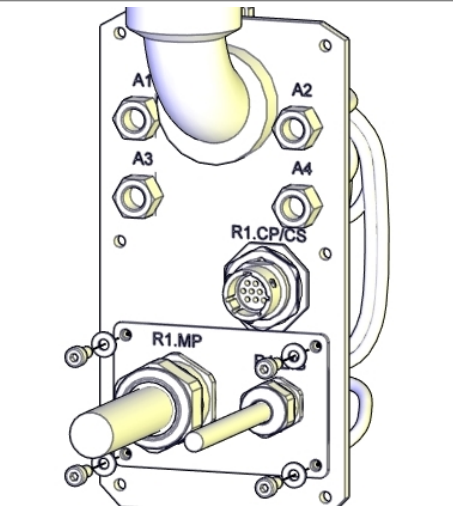
Use these procedures to refit the main cable package.

Reconnecting the floor cable connector

	Action	Note		
1	Reconnect the connector. <ul style="list-style-type: none">• R1.MP	 <p>xx1500002201</p> <table border="1" data-bbox="943 1527 1399 1572"><tr><td>A</td><td>R1.MP</td></tr></table>	A	R1.MP
A	R1.MP			

Continues on next page

Refitting the floor cables

	Action	Note
1	Push the floor cables into place.	 <p>xx1500002208</p>
2	Secure with screws and washers.	 <p>xx1500002199</p> <p>Screw: M4x10 (4 pcs) Tightening torque: 2 Nm</p>

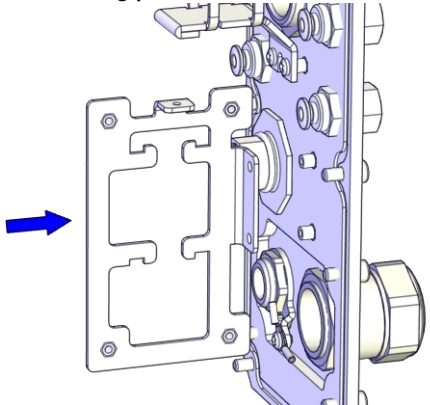
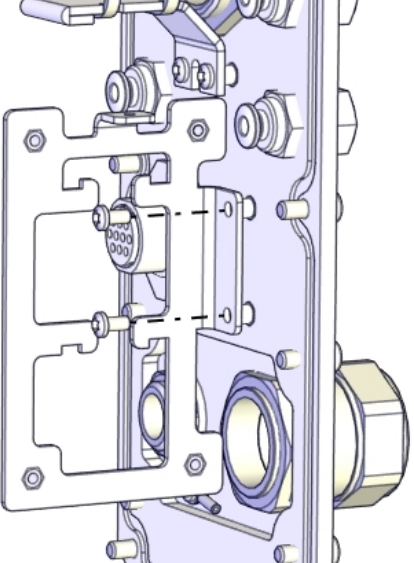
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4 Repair

4.3.1 Replacing the main cable package

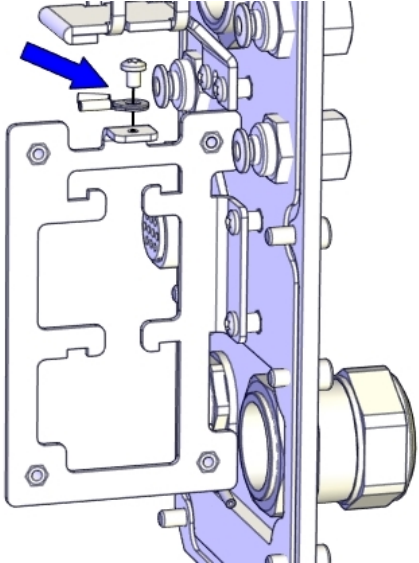
Continued

Refitting the EIB mounting plate


	Action	Note
1	Refit the EIB mounting plate.	<p>EIB mounting plate: 3HAC055165-001</p>  <p>xx1500002796</p>
2	Secure with screws.	 <p>xx1500002795</p> <p>Screw: M3x6 (2 pcs) Tightening torque: 1.5 Nm</p>

Continues on next page

4.3.1 Replacing the main cable package
Continued

	Action	Note
3	Connect the earth cable with the screw.	 <p data-bbox="970 878 1082 898">xx1500002794</p> <p data-bbox="970 913 1198 943">Screw: M3x4 (1 pcs)</p> <p data-bbox="970 949 1262 978">Tightening torque: 0.3 Nm</p>

Refitting the EIB unit


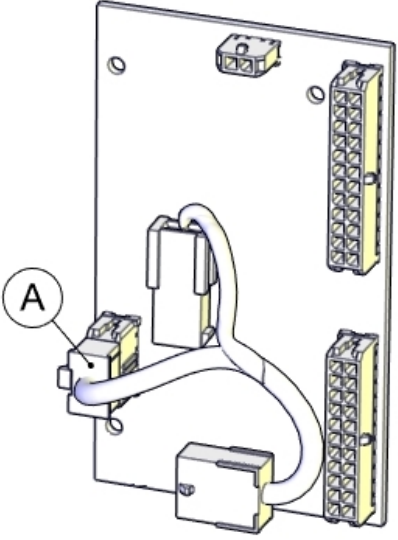
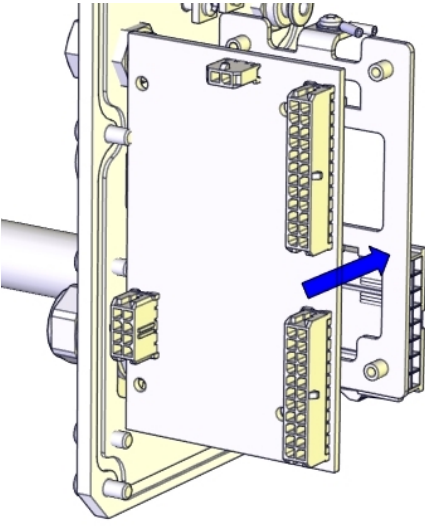
	Action	Note
1	 <p data-bbox="587 1128 946 1189">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="496 1205 962 1317">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	

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4 Repair

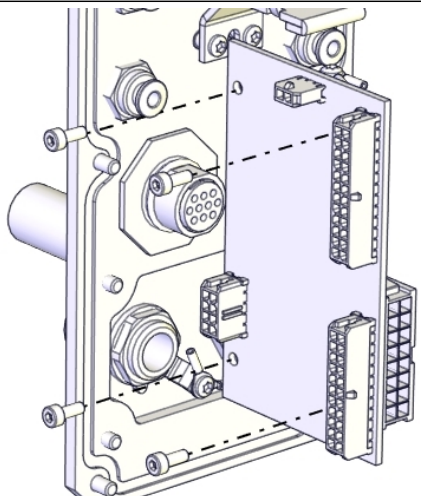

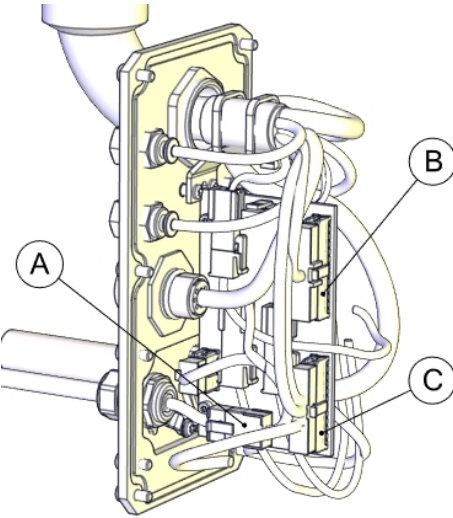
4.3.1 Replacing the main cable package

Continued


	Action	Note		
2	<p>Reconnect the connector to refit the EIB connection cable.</p> <ul style="list-style-type: none">• R2.EIB <p> CAUTION</p> <p>The EIB connection cable has one connector at one end and two connectors at the other end.</p> <p>Make sure not to mix the connectors. See the labels on the connectors for correct connection.</p>	<p>EIB connection cable: 3HAC056703-001</p>  <p>xx1500002197</p> <table border="1" data-bbox="943 983 1401 1032"><tr><td data-bbox="943 983 995 1032">A</td><td data-bbox="1000 983 1401 1032">R2.EIB</td></tr></table>	A	R2.EIB
A	R2.EIB			
3	Refit the EIB unit.	 <p>xx1500002793</p>		

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4.3.1 Replacing the main cable package *Continued*

	Action	Note						
4	<p>Secure with screws.</p>	 <p style="font-size: small; margin-top: 10px;">xx1500002792</p> <p>Screw: M3x8 (4 pcs) Tightening torque: 0.3 Nm</p>						
5	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R1.EIB • R1.ME4 • R1.ME1-3 <p style="text-align: center;"> CAUTION</p> <p>Make sure not to mix the connectors; otherwise, axes may be damaged. See the labels on the connectors for correct connection.</p>	 <p style="font-size: small; margin-top: 10px;">xx1500002195</p> <table border="1" style="width: 100%; border-collapse: collapse; margin-top: 10px;"> <tbody> <tr> <td style="width: 10%; text-align: center;">A</td> <td>R1.EIB</td> </tr> <tr> <td style="text-align: center;">B</td> <td>R1.ME4</td> </tr> <tr> <td style="text-align: center;">C</td> <td>R1.ME1-3</td> </tr> </tbody> </table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							

Refitting the battery pack


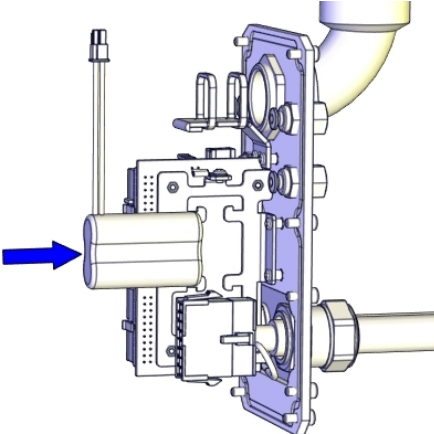
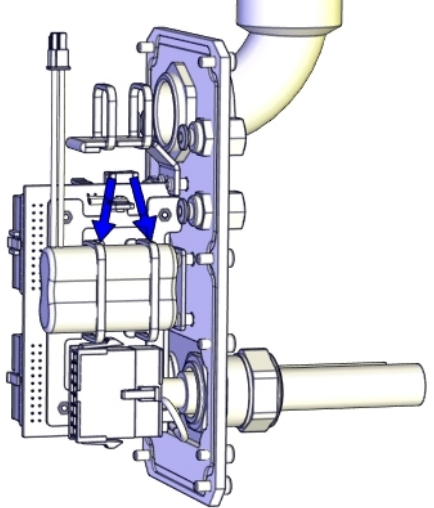
	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

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4 Repair

4.3.1 Replacing the main cable package

Continued

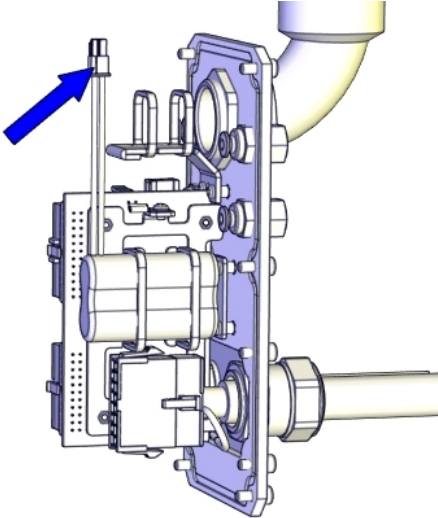
	Action	Note
2	<p>Fit the battery.</p> <p> Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002206</p>
3	<p>Secure the battery with cable ties.</p>	 <p>xx1500002193</p>

Connecting the battery cable



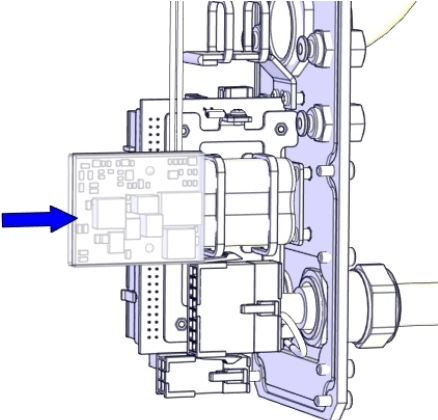
	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	

Continues on next page

4.3.1 Replacing the main cable package
Continued

	Action	Note
2	Connect the battery cable.	 <p data-bbox="970 840 1082 857">xx1500002192</p>

Refitting the PCB board

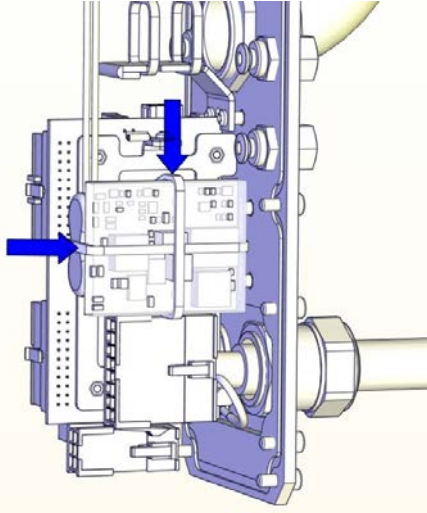

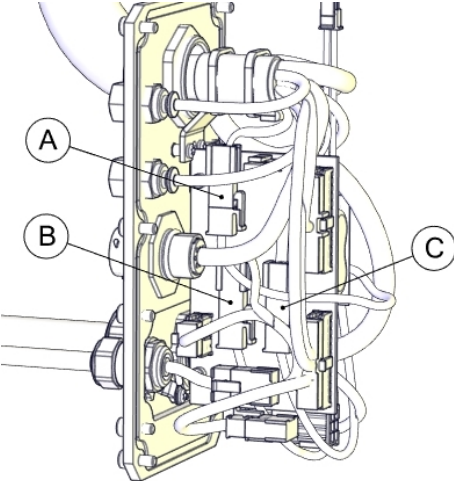
	Action	Note
1	 <p data-bbox="587 1028 946 1088">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="496 1106 962 1211">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	
2	<p data-bbox="496 1249 727 1272">Refit the PCB board.</p>  <p data-bbox="587 1310 644 1335">Note</p> <p data-bbox="496 1364 962 1420">The PCB board is protected by shrink hose. Replace the hose if damaged.</p>	<p data-bbox="970 1249 1302 1272">PCB board: 3HAC057687-001</p>  <p data-bbox="970 1720 1082 1738">xx1500002205</p>

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4 Repair

4.3.1 Replacing the main cable package

Continued

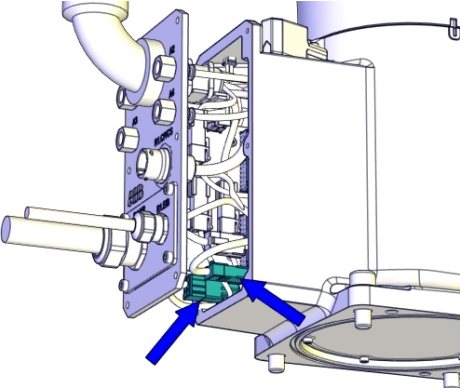
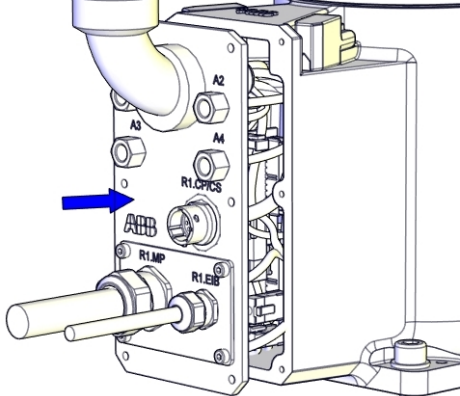
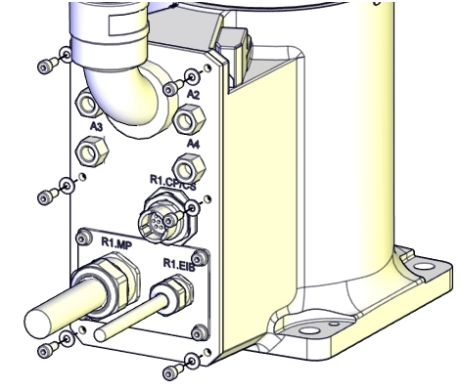
	Action	Note						
3	Secure the PCB board with cable ties. Do not tighten the ties too tight.	 <p data-bbox="936 831 1050 853">xx1500002752</p>						
4	Reconnect the connectors. <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p data-bbox="472 1025 671 1077">  CAUTION </p> <p data-bbox="464 1099 932 1178"> Make sure not to mix the connectors. See the labels on the connectors for correct connection. </p>	 <p data-bbox="936 1373 1050 1395">xx1500002190</p> <table border="1" data-bbox="943 1413 1398 1547"> <tbody> <tr> <td data-bbox="943 1413 986 1458">A</td> <td data-bbox="991 1413 1398 1458">R1.BK1-2</td> </tr> <tr> <td data-bbox="943 1464 986 1509">B</td> <td data-bbox="991 1464 1398 1509">R1.DBP</td> </tr> <tr> <td data-bbox="943 1516 986 1561">C</td> <td data-bbox="991 1516 1398 1561">R2.BK1-2</td> </tr> </tbody> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
5	Secure the cables with cable ties if needed.							

Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

4.3.1 Replacing the main cable package
Continued

	Action	Note
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p>xx1500002188</p>
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Refitting the main cable to the upper arm

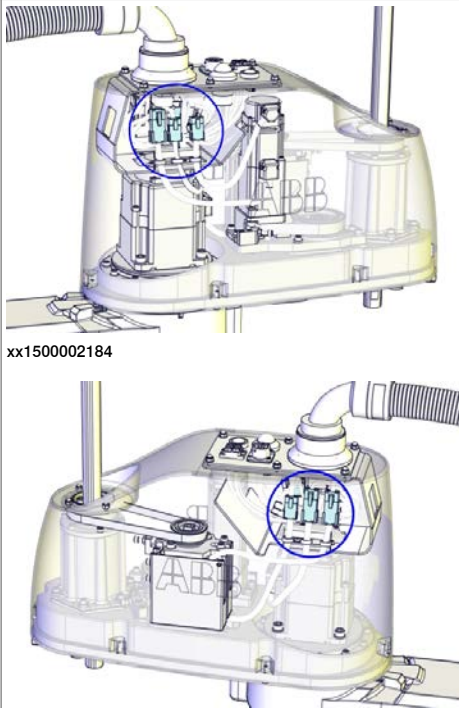
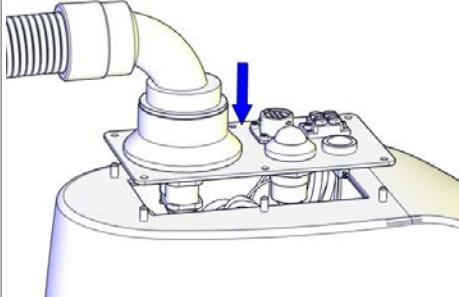
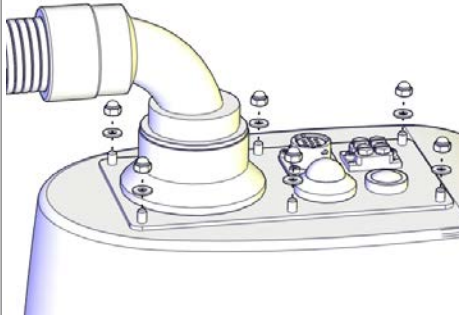
	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

4 Repair


4.3.1 Replacing the main cable package

Continued

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none">• R2.MP2• R2.MP3• R2.MP4• R2.ME2• R2.ME3• R2.ME4	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>

Continues on next page

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

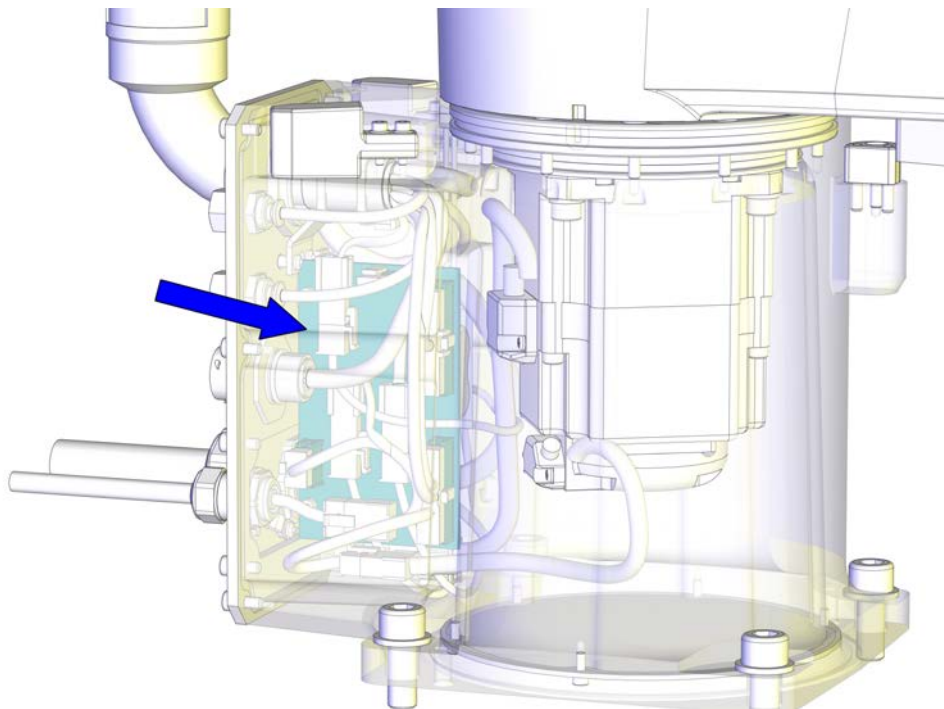
4 Repair

4.3.2 Replacing the EIB unit

4.3.2 Replacing the EIB unit

Location of the EIB unit

The EIB unit is located as shown in the figure.



xx1500002178

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
EIB unit	3HAC045759-001	
EIB connection cable	3HAC056703-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

Required consumables

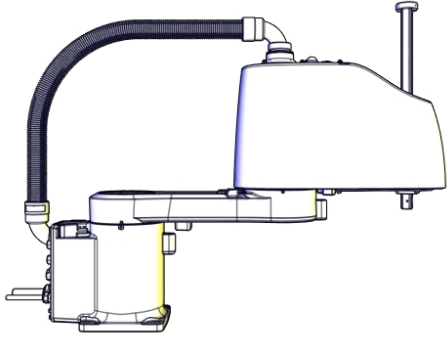

Consumable	Article number	Note
Cable ties	-	

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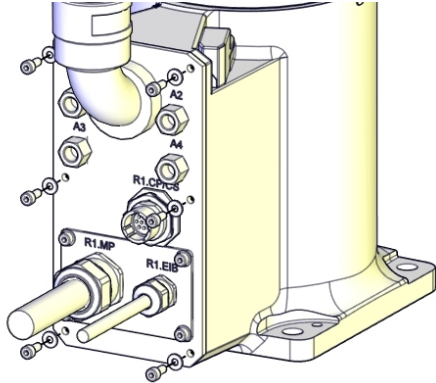
Removing the EIB unit

Use these procedures to remove the EIB unit.

Preparations before removing the EIB unit

	Action	Note
1	Jog all axes to zero position.	 <p>xx1500002227</p>
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the base



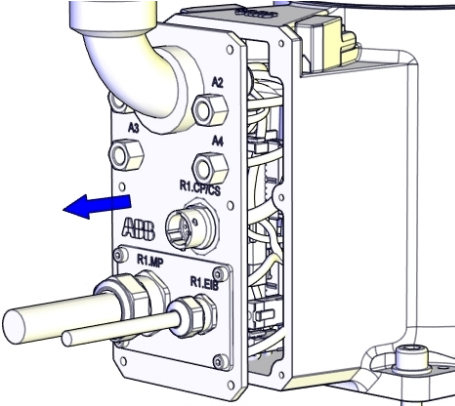

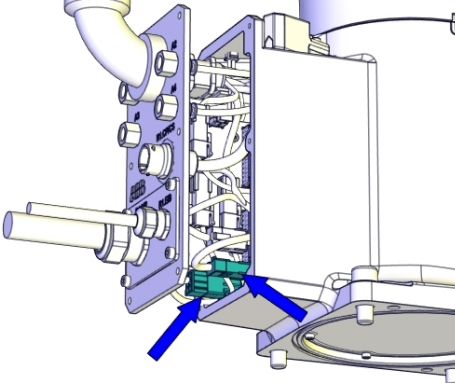
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the screws and washers.	 <p>xx1500002186</p>

Continues on next page



4 Repair

4.3.2 Replacing the EIB unit

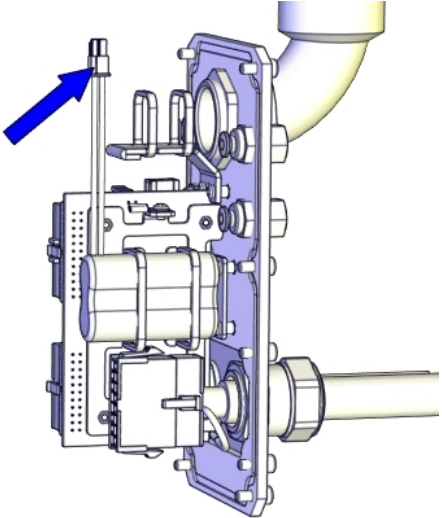
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	Action	Note
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>



Disconnecting the battery cable

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

Continues on next page

	Action	Note
3	Disconnect the battery cable.	 <p>xx1500002192</p>

Removing the EIB unit

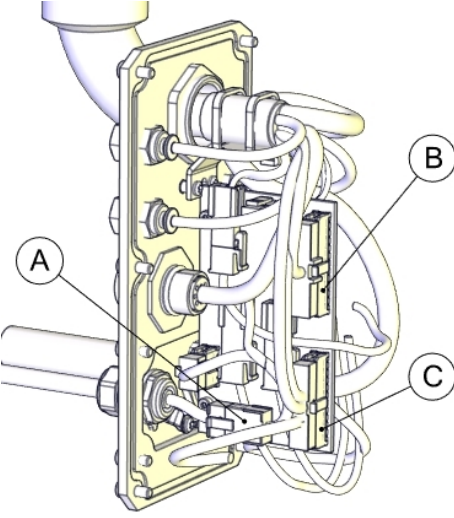
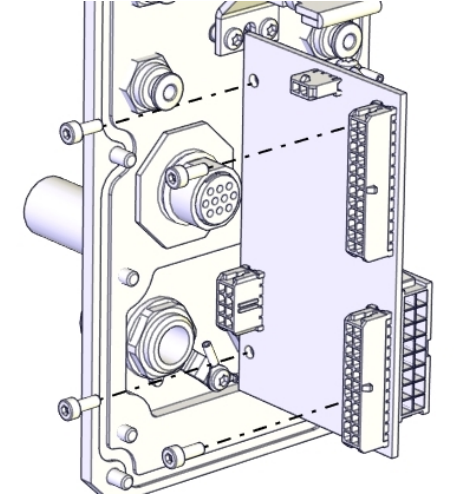
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	

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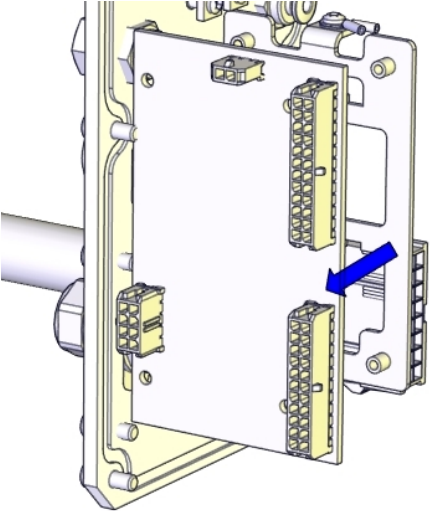
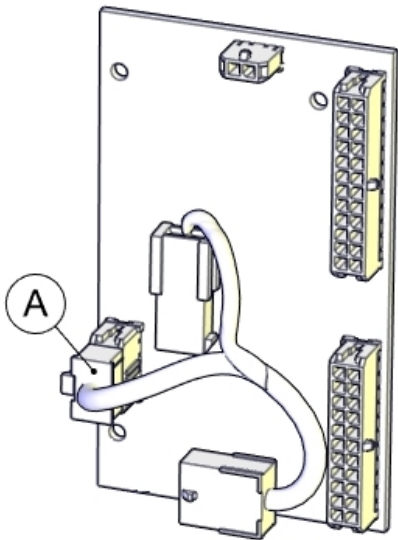
4 Repair

4.3.2 Replacing the EIB unit

Continued

	Action	Note						
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none">• R1.EIB• R1.ME4• R1.ME1-3	 <p>xx1500002195</p> <table border="1" data-bbox="943 869 1398 1003"><tr><td>A</td><td>R1.EIB</td></tr><tr><td>B</td><td>R1.ME4</td></tr><tr><td>C</td><td>R1.ME1-3</td></tr></table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							
4	Remove the screws.	 <p>xx1500002792</p>						

Continues on next page

	Action	Note		
5	Remove the EIB unit.	 <p>xx1500002196</p>		
6	Disconnect the connector to remove the EIB connection cable. <ul style="list-style-type: none"> • R2.EIB 	 <p>xx1500002197</p> <table border="1" data-bbox="973 1523 1433 1579"> <tr> <td data-bbox="973 1523 1029 1579">A</td> <td data-bbox="1029 1523 1433 1579">R2.EIB</td> </tr> </table>	A	R2.EIB
A	R2.EIB			

Continues on next page

4 Repair



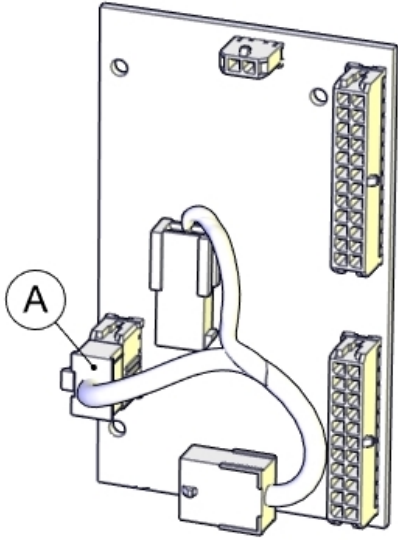
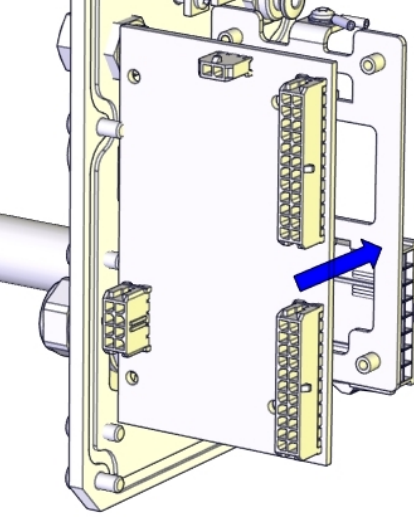
4.3.2 Replacing the EIB unit

Continued

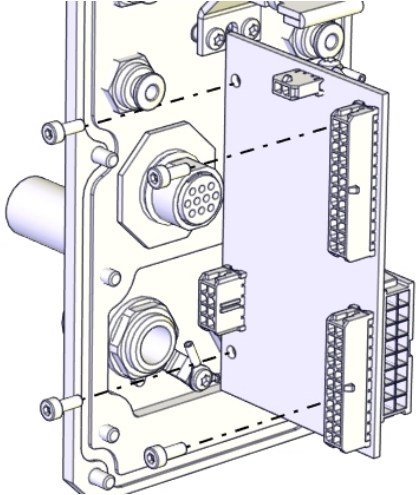

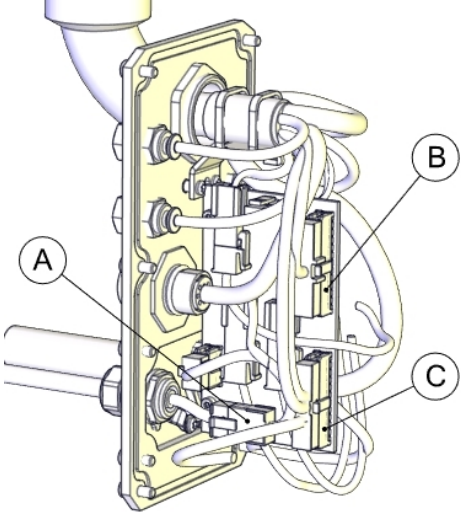
Refitting the EIB unit

Use these procedures to refit the EIB unit.


Refitting the EIB unit

	Action	Note		
1	 ELECTROSTATIC DISCHARGE (ESD) The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i>			
2	Reconnect the connector to refit the EIB connection cable. <ul style="list-style-type: none"> • R2.EIB  CAUTION The EIB connection cable has one connector at one end and two connectors at the other end. Make sure not to mix the connectors. See the labels on the connectors for correct connection.	EIB connection cable: 3HAC056703-001  <small>xx1500002197</small> <table border="1" data-bbox="943 1373 1410 1420"> <tr> <td data-bbox="951 1384 991 1420">A</td> <td data-bbox="995 1384 1410 1420">R2.EIB</td> </tr> </table>	A	R2.EIB
A	R2.EIB			
3	Refit the EIB unit.	 <small>xx1500002793</small>		

Continues on next page

	Action	Note						
4	Secure with screws.	 <p>xx1500002792</p> <p>Screw: M3x8 (4 pcs) Tightening torque: 0.3 Nm</p>						
5	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R1.EIB • R1.ME4 • R1.ME1-3 <p> CAUTION</p> <p>Make sure not to mix the connectors; otherwise, axes may be damaged. See the labels on the connectors for correct connection.</p>	 <p>xx1500002195</p> <table border="1" data-bbox="970 1480 1441 1621"> <tbody> <tr> <td>A</td> <td>R1.EIB</td> </tr> <tr> <td>B</td> <td>R1.ME4</td> </tr> <tr> <td>C</td> <td>R1.ME1-3</td> </tr> </tbody> </table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							

Connecting the battery cable

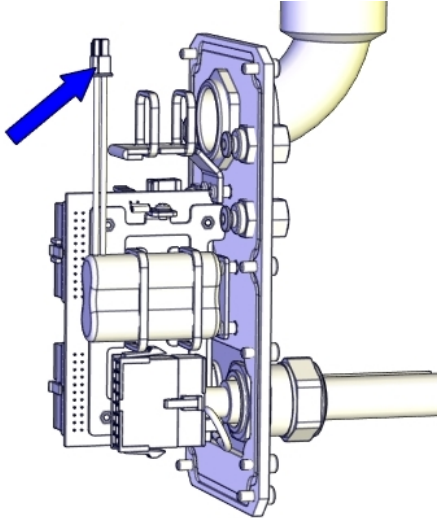
	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

Continues on next page

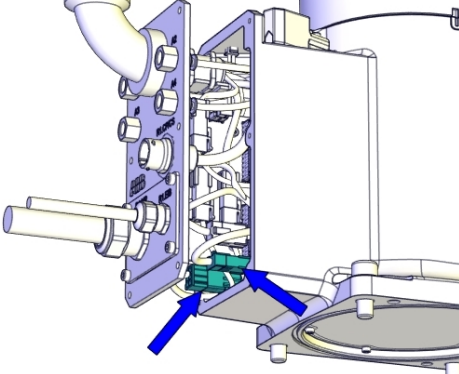
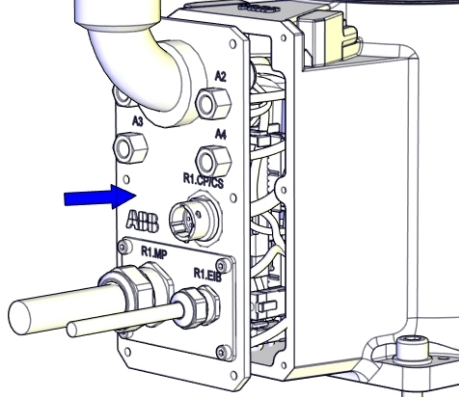
4 Repair

4.3.2 Replacing the EIB unit

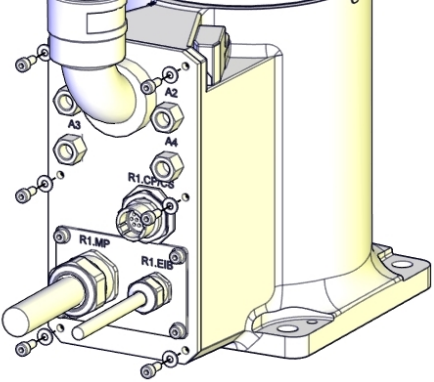
Continued

	Action	Note
2	Connect the battery cable.	 <p data-bbox="943 837 1050 857">xx1500002192</p>


Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p data-bbox="943 1471 1050 1491">xx1500002188</p>
3	Push the main cable package into place.	 <p data-bbox="943 1937 1050 1957">xx1500002204</p>

Continues on next page

	Action	Note
4	Refit the base cover with screws and washers.	 <p data-bbox="970 705 1082 723">xx1500002186</p> <p data-bbox="970 741 1225 770">Screws: M4x10 (6 pcs)</p> <p data-bbox="970 775 1241 804">Tightening torque: 2 Nm</p>

Concluding procedure

	Action	Note
1	Update the revolution counters.	See Updating revolution counters on page 351 .
2	 <p data-bbox="587 1041 699 1070">DANGER</p> <p data-bbox="497 1102 962 1258">Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

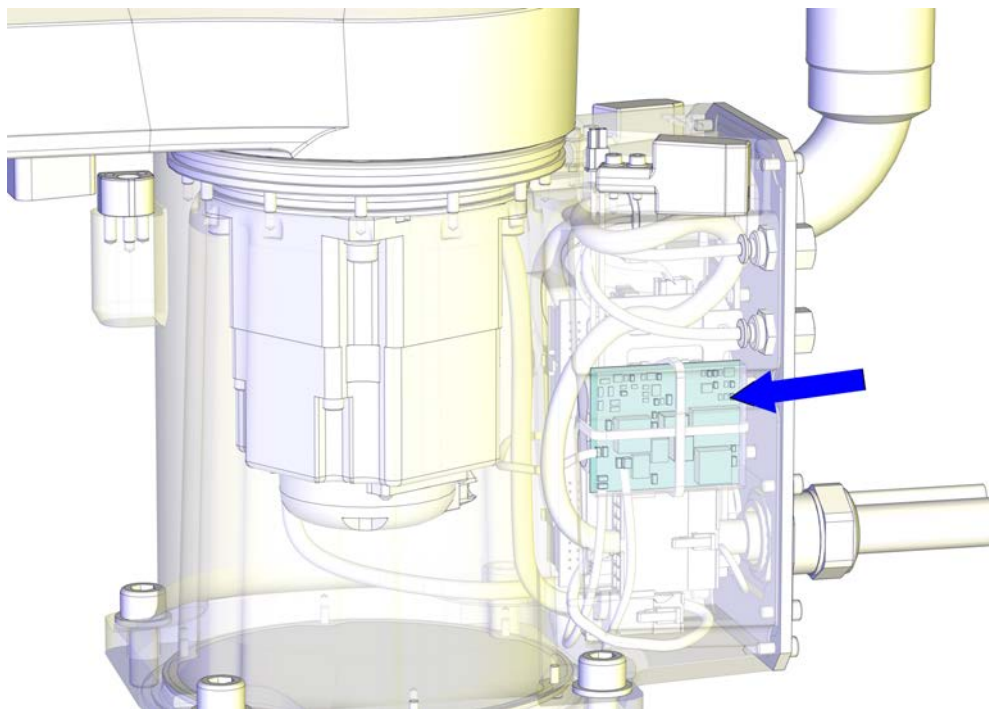
4 Repair

4.3.3 Replacing the PCB board

4.3.3 Replacing the PCB board

Location of the PCB board

The PCB board is located as shown in the figure.



xx1500002179

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
PCB board	3HAC057687-001	

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

Required consumables

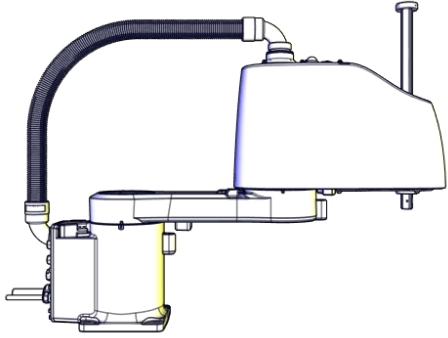

Consumable	Article number	Note
Shrink hose	-	Used for protecting the PCB board.
Cable ties	-	

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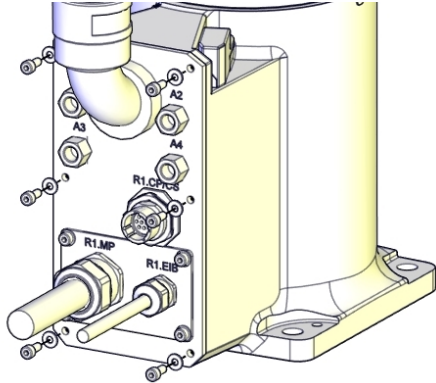
Removing the PCB board

Use these procedures to remove the PCB board.

Preparations before removing the PCB board

	Action	Note
1	Jog all axes to zero position.	 <p>xx1500002227</p>
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the base



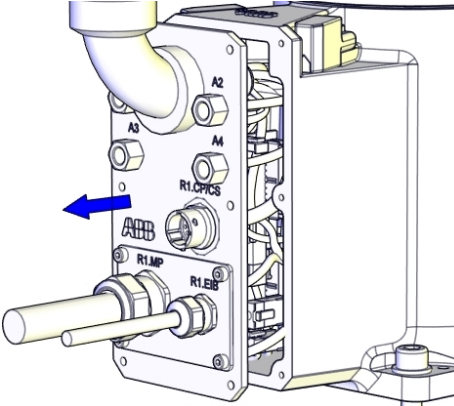

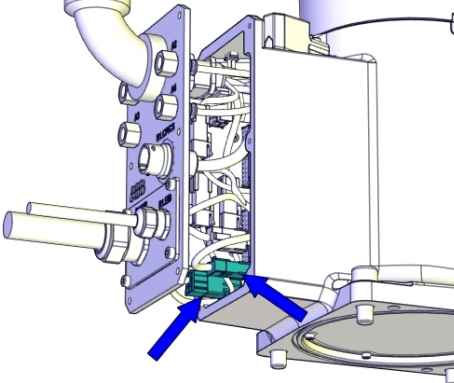
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the screws and washers.	 <p>xx1500002186</p>

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4 Repair

4.3.3 Replacing the PCB board


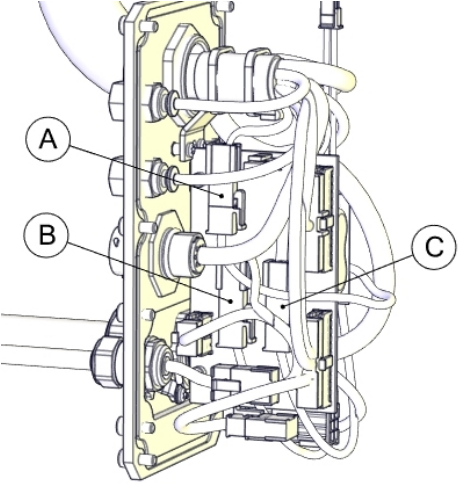
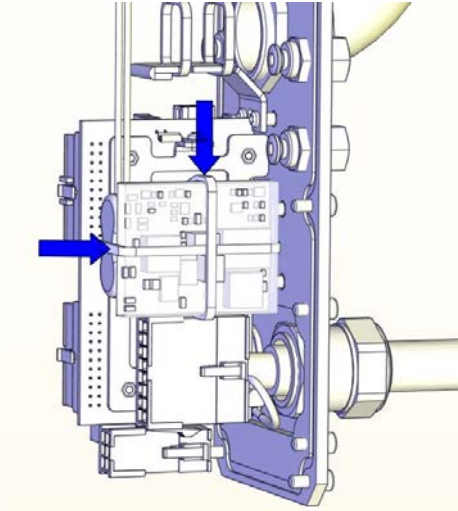
Continued

	Action	Note
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>

Removing the PCB board

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

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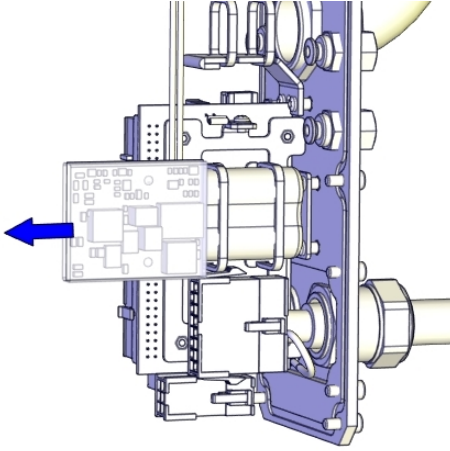
	Action	Note						
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="973 840 1433 974"> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
4	Cut the cable ties.	 <p>xx1500002752</p>						

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4 Repair

4.3.3 Replacing the PCB board



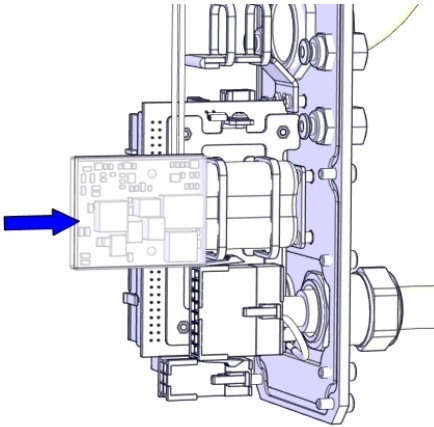
Continued

	Action	Note
5	Remove the PCB board carefully.	 <p data-bbox="943 779 1050 801">xx1500002191</p>

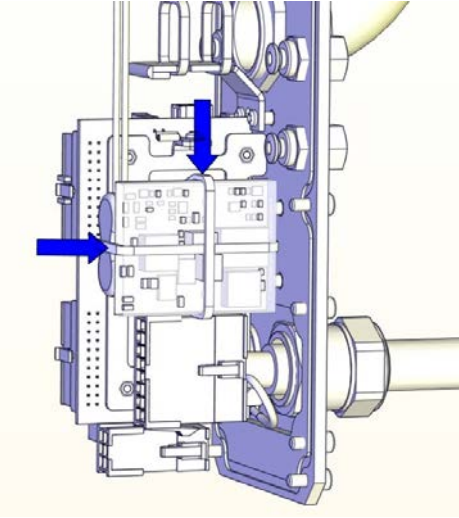

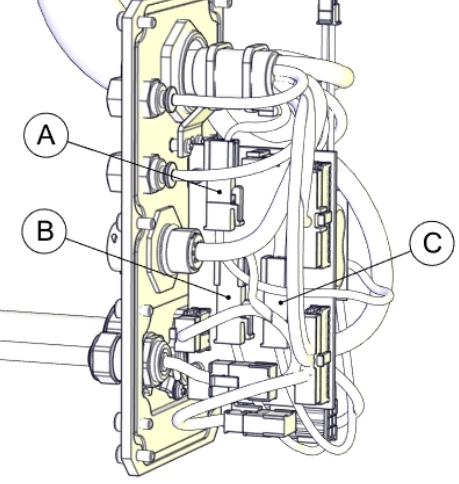
Refitting the PCB board

Use these procedures to refit the PCB board.

Refitting the PCB board

	Action	Note
1	 <p data-bbox="555 1070 917 1131">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="464 1146 932 1256">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
2	<p data-bbox="464 1288 699 1317">Refit the PCB board.</p>  <p data-bbox="555 1350 614 1379">Note</p> <p data-bbox="464 1406 932 1462">The PCB board is protected by shrink hose. Replace the hose if damaged.</p>	<p data-bbox="943 1288 1273 1317">PCB board: 3HAC057687-001</p>  <p data-bbox="943 1760 1050 1783">xx1500002205</p>

Continues on next page

	Action	Note						
3	Secure the PCB board with cable ties. Do not tighten the ties too tight.	 <p>xx1500002752</p>						
4	Reconnect the connectors. <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2  CAUTION Make sure not to mix the connectors. See the labels on the connectors for correct connection.	 <p>xx1500002190</p> <table border="1" data-bbox="975 1413 1436 1552"> <tbody> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </tbody> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
5	Secure the cables with cable ties if needed.							

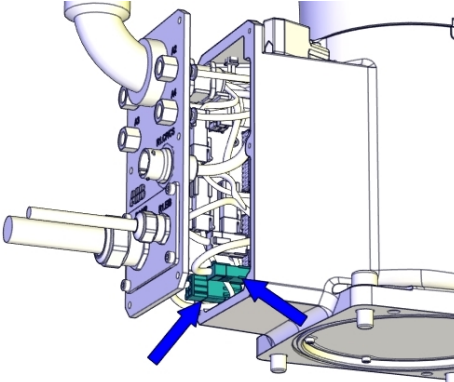
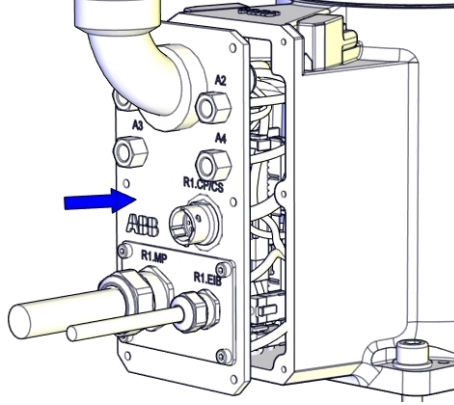
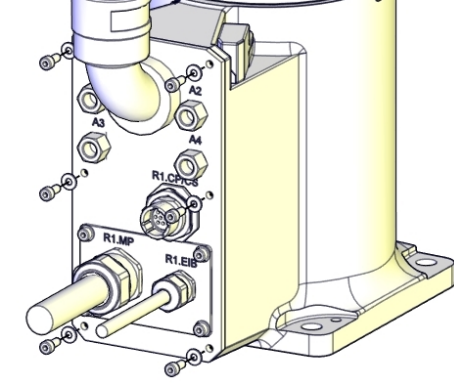
Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	

4 Repair

4.3.3 Replacing the PCB board


Continued

	Action	Note
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p>xx1500002188</p>
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Concluding procedure

	Action	Note
1	Update the revolution counters.	See Updating revolution counters on page 351 .

Continues on next page

	Action	Note
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

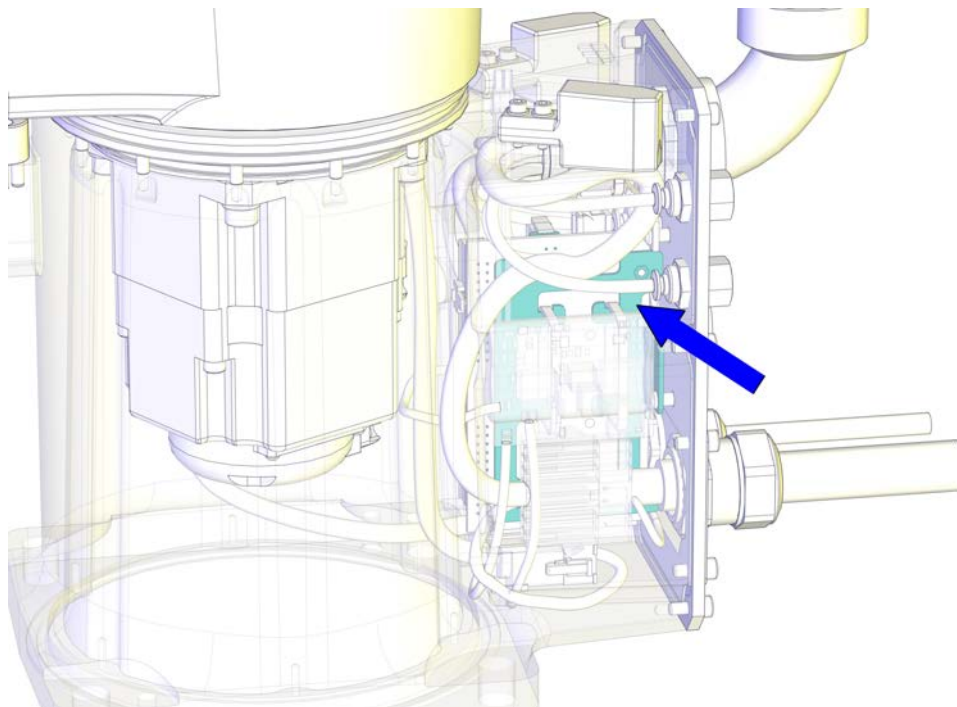
4 Repair

4.3.4 Replacing the EIB mounting plate

4.3.4 Replacing the EIB mounting plate

Location of the EIB mounting plate

The EIB mounting plate is located as shown in the figure.



xx1500002517

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
EIB mounting plate	3HAC055165-001	
EIB connection cable	3HAC056703-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

Required consumables

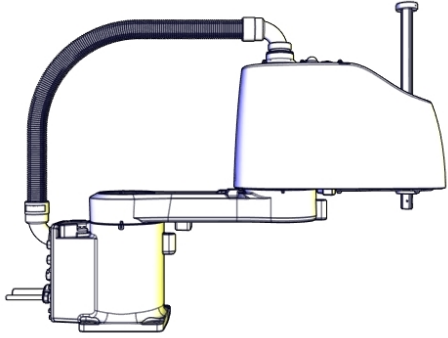

Consumable	Article number	Note
Cable ties	-	

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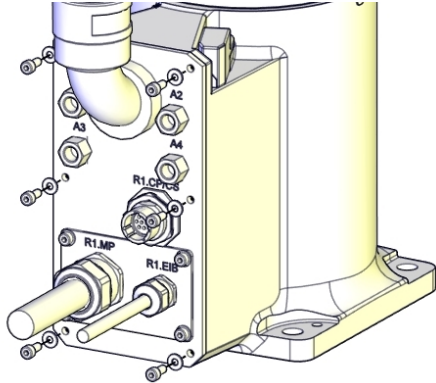
Removing the EIB mounting plate

Use these procedures to remove the EIB mounting plate.

Preparations before removing the EIB mounting plate

	Action	Note
1	Jog all axes to zero position.	 <p>xx1500002227</p>
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the base



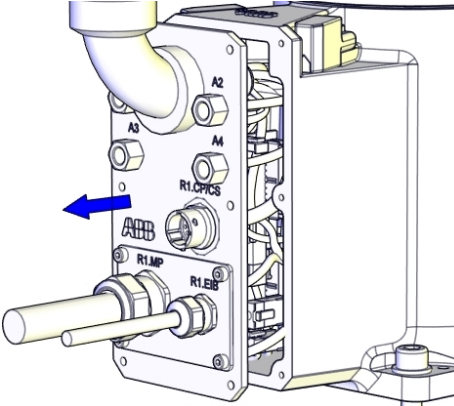

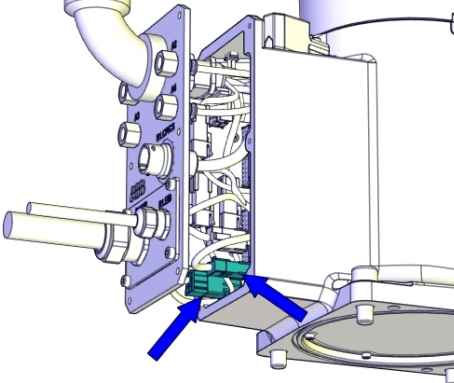
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the screws and washers.	 <p>xx1500002186</p>

Continues on next page



4 Repair

4.3.4 Replacing the EIB mounting plate


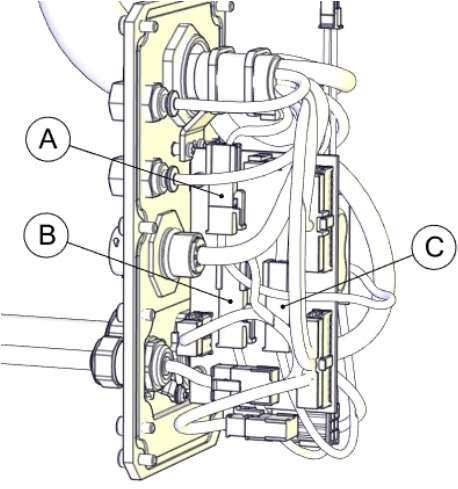
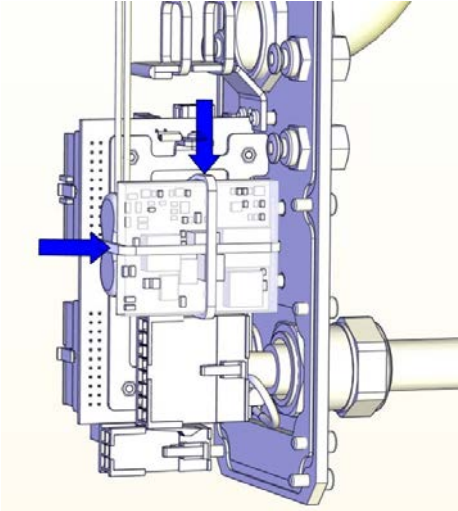
Continued

	Action	Note
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>

Removing the PCB board

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

Continues on next page

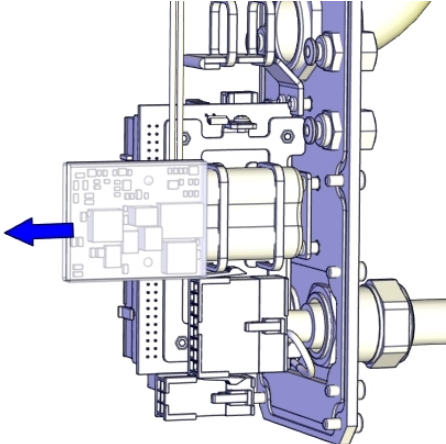
	Action	Note						
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="973 840 1433 974"> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
4	Cut the cable ties.	 <p>xx1500002752</p>						

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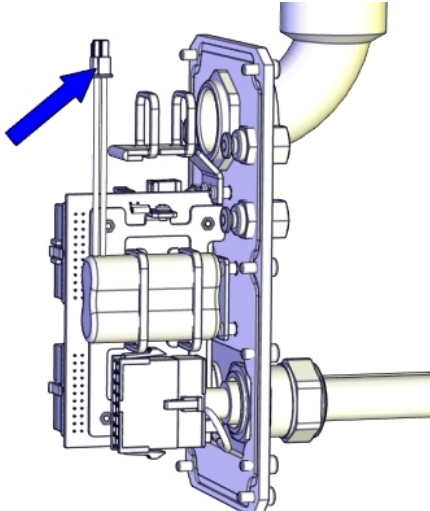
4 Repair

4.3.4 Replacing the EIB mounting plate

Continued



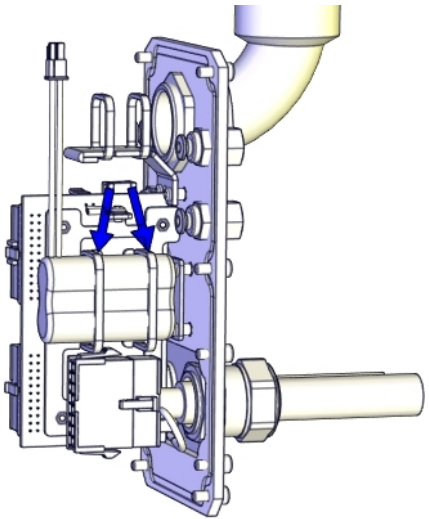

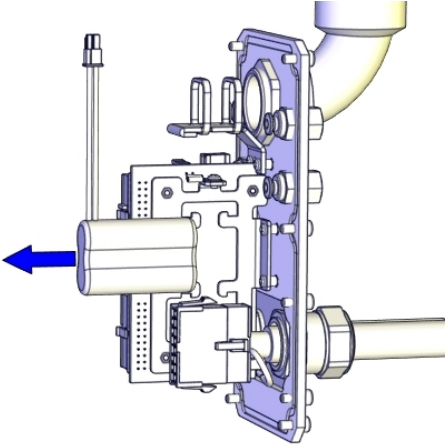
	Action	Note
5	Remove the PCB board carefully.	 <p data-bbox="941 772 1045 795">xx1500002191</p>

Disconnecting the battery cable

	Action	Note
1	 <p data-bbox="550 974 662 996">DANGER</p> <p data-bbox="464 1030 932 1108">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p data-bbox="550 1171 917 1227">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="464 1243 932 1355">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
3	Disconnect the battery cable.	 <p data-bbox="941 1915 1045 1937">xx1500002192</p>

Continues on next page

Removing the battery pack

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	
3	<p>Cut the cable ties.</p>	 <p>xx1500002193</p>
4	<p>Remove the battery.</p>  <p>Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002194</p>



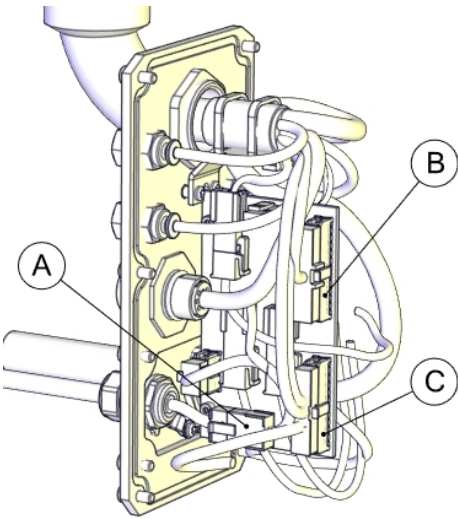
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4 Repair

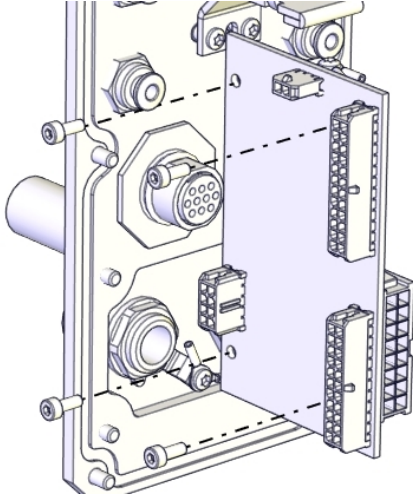
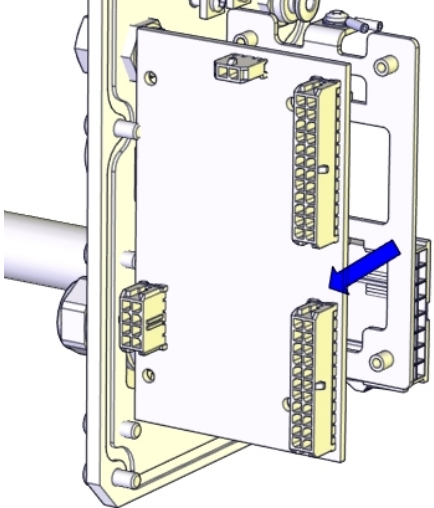
4.3.4 Replacing the EIB mounting plate

Continued

Removing the EIB unit

	Action	Note						
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>							
2	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>							
3	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R1.EIB • R1.ME4 • R1.ME1-3 	 <p>xx1500002195</p> <table border="1" data-bbox="941 1361 1401 1500"> <tbody> <tr> <td>A</td> <td>R1.EIB</td> </tr> <tr> <td>B</td> <td>R1.ME4</td> </tr> <tr> <td>C</td> <td>R1.ME1-3</td> </tr> </tbody> </table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							

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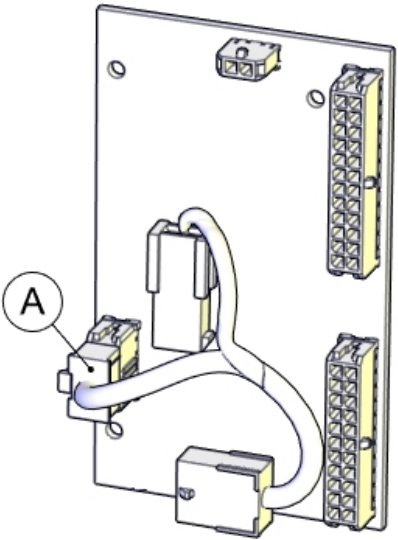
	Action	Note
4	Remove the screws.	 <p>xx1500002792</p>
5	Remove the EIB unit.	 <p>xx1500002196</p>

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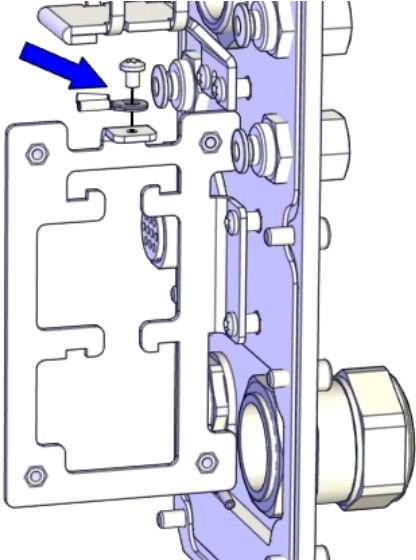
4 Repair

4.3.4 Replacing the EIB mounting plate

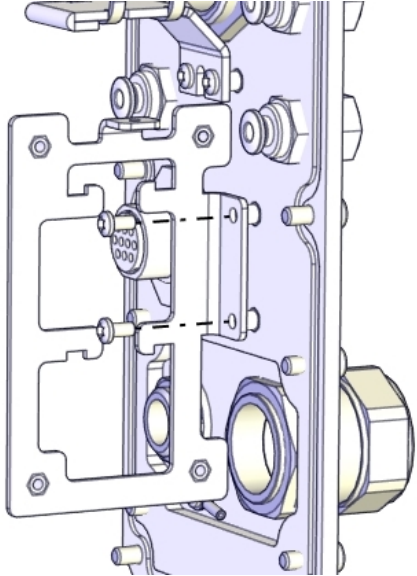
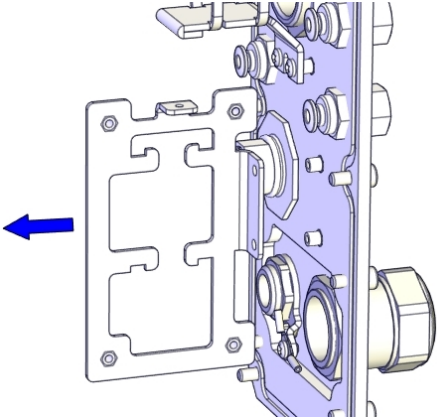
Continued

	Action	Note		
6	Disconnect the connector to remove the EIB connection cable. <ul style="list-style-type: none"> • R2.EIB 	 <p>xx1500002197</p> <table border="1" data-bbox="943 949 1393 996"> <tr> <td data-bbox="943 949 991 996">A</td> <td data-bbox="995 949 1393 996">R2.EIB</td> </tr> </table>	A	R2.EIB
A	R2.EIB			

Removing the EIB mounting plate

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Disconnect the earth cable by removing the screw.	 <p>xx1500002794</p>

Continues on next page

	Action	Note
3	Remove the screws.	 <p>xx1500002795</p>
4	Remove the EIB mounting plate.	 <p>xx1500002198</p>

Continues on next page

4 Repair

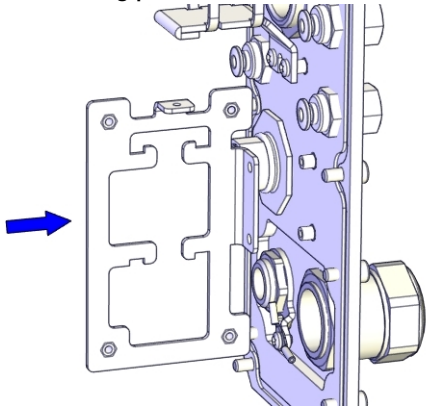
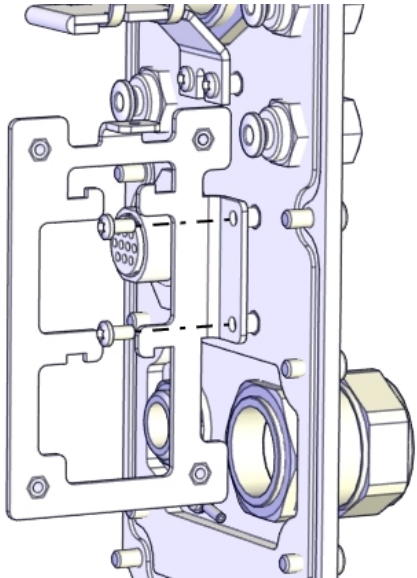
4.3.4 Replacing the EIB mounting plate

Continued

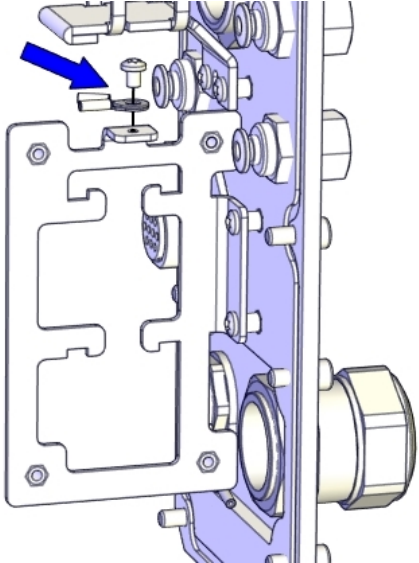
Refitting the EIB mounting plate

Use these procedures to refit the EIB mounting plate.


Refitting the EIB mounting plate

	Action	Note
1	Refit the EIB mounting plate.	<p>EIB mounting plate: 3HAC055165-001</p>  <p>xx1500002796</p>
2	Secure with screws.	 <p>xx1500002795</p> <p>Screw: M3x6 (2 pcs) Tightening torque: 1.5 Nm</p>

Continues on next page

	Action	Note
3	Connect the earth cable with the screw.	 <p>xx1500002794</p> <p>Screw: M3x4 (1 pcs) Tightening torque: 0.3 Nm</p>


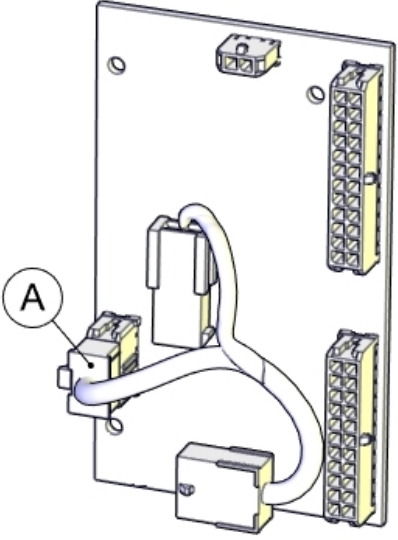
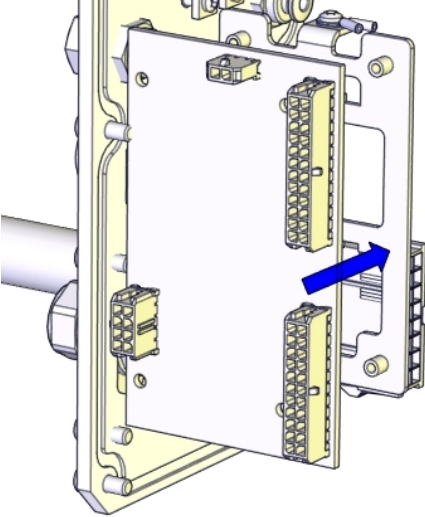
Refitting the EIB unit

	Action	Note
1	 <p>ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section The unit is sensitive to ESD on page 52</p>	

4 Repair

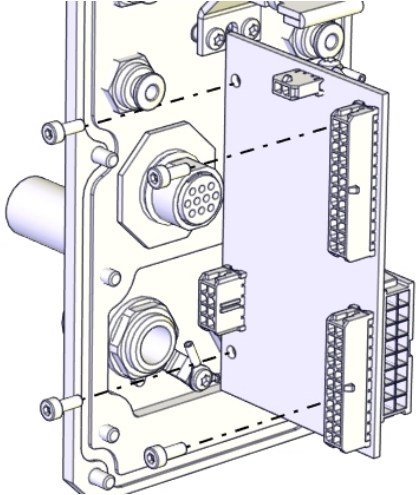

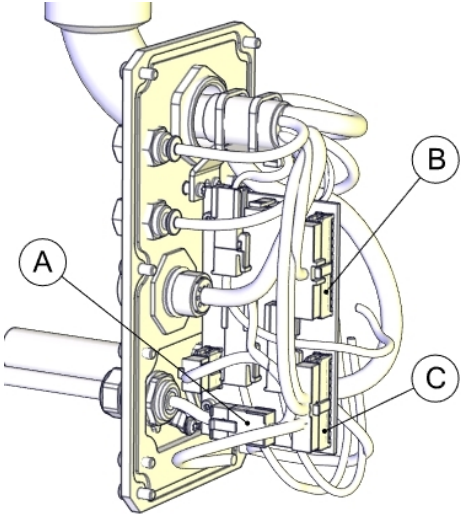
4.3.4 Replacing the EIB mounting plate

Continued


	Action	Note		
2	<p>Reconnect the connector to refit the EIB connection cable.</p> <ul style="list-style-type: none">• R2.EIB <p> CAUTION</p> <p>The EIB connection cable has one connector at one end and two connectors at the other end.</p> <p>Make sure not to mix the connectors. See the labels on the connectors for correct connection.</p>	<p>EIB connection cable: 3HAC056703-001</p>  <p>xx1500002197</p> <table border="1" data-bbox="943 983 1401 1032"><tr><td>A</td><td>R2.EIB</td></tr></table>	A	R2.EIB
A	R2.EIB			
3	Refit the EIB unit.	 <p>xx1500002793</p>		

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4.3.4 Replacing the EIB mounting plate
Continued

	Action	Note						
4	Secure with screws.	 <p>xx1500002792</p> <p>Screw: M3x8 (4 pcs) Tightening torque: 0.3 Nm</p>						
5	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R1.EIB • R1.ME4 • R1.ME1-3 <p> CAUTION</p> <p>Make sure not to mix the connectors; otherwise, axes may be damaged. See the labels on the connectors for correct connection.</p>	 <p>xx1500002195</p> <table border="1" data-bbox="970 1480 1441 1621"> <tbody> <tr> <td>A</td> <td>R1.EIB</td> </tr> <tr> <td>B</td> <td>R1.ME4</td> </tr> <tr> <td>C</td> <td>R1.ME1-3</td> </tr> </tbody> </table>	A	R1.EIB	B	R1.ME4	C	R1.ME1-3
A	R1.EIB							
B	R1.ME4							
C	R1.ME1-3							

Refitting the battery pack


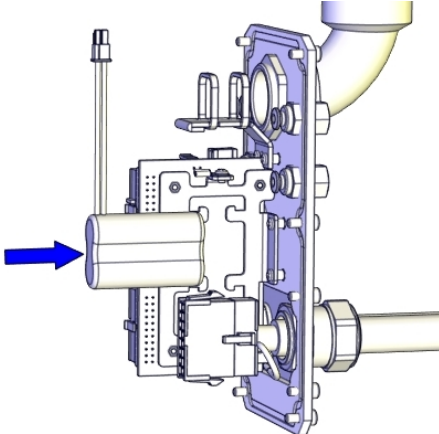
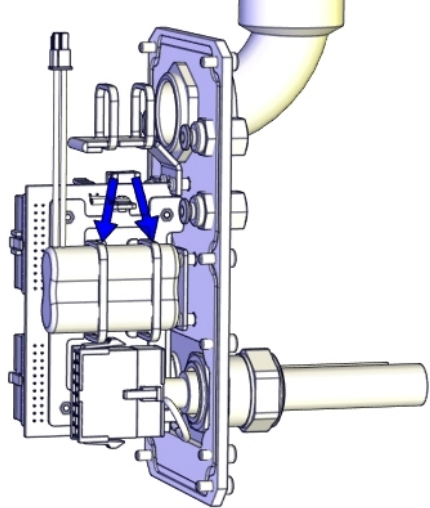
	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	

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4 Repair

4.3.4 Replacing the EIB mounting plate

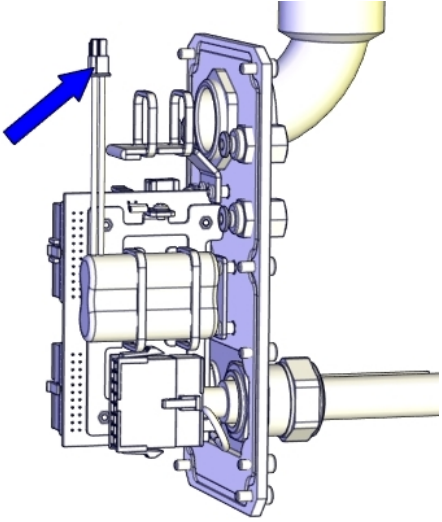
Continued

	Action	Note
2	<p>Fit the battery.</p> <p> Note</p> <p>Battery includes protection circuits. Only replace with a specified spare part or with an ABB- approved equivalent.</p>	 <p>xx1500002206</p>
3	<p>Secure the battery with cable ties.</p>	 <p>xx1500002193</p>



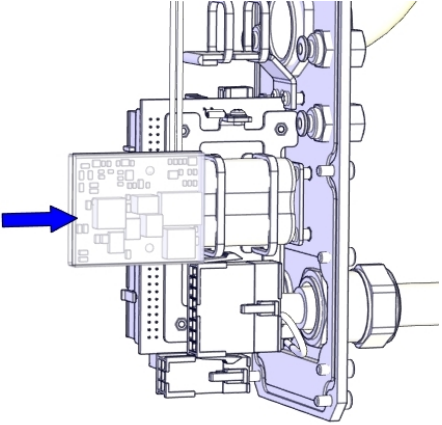
Connecting the battery cable

	Action	Note
1	<p> ELECTROSTATIC DISCHARGE (ESD)</p> <p>The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	

Continues on next page

	Action	Note
2	Connect the battery cable.	 <p data-bbox="970 840 1082 862">xx1500002192</p>

Refitting the PCB board

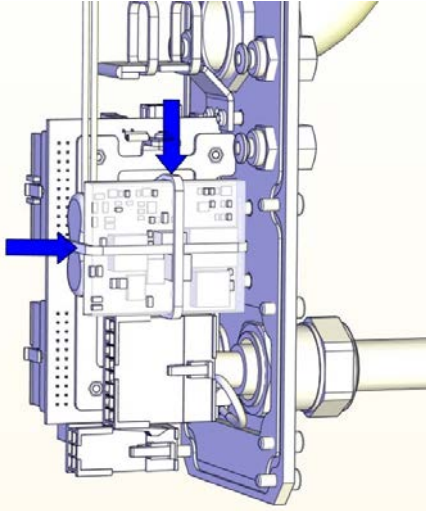

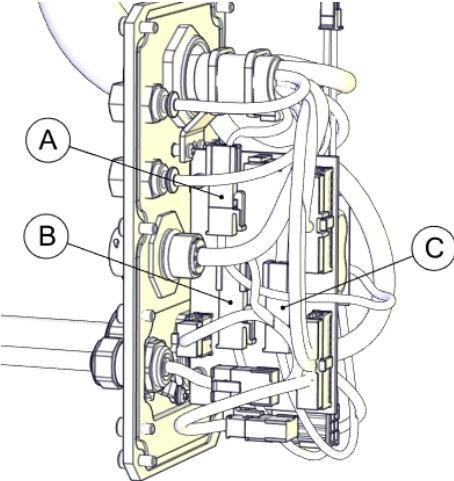
	Action	Note
1	 <p data-bbox="587 1032 946 1088">ELECTROSTATIC DISCHARGE (ESD)</p> <p data-bbox="496 1108 962 1216">The unit is sensitive to ESD. Before handling the unit please read the safety information in the section <i>The unit is sensitive to ESD on page 52</i></p>	
2	<p data-bbox="496 1249 727 1279">Refit the PCB board.</p>  <p data-bbox="587 1312 644 1341">Note</p> <p data-bbox="496 1364 962 1422">The PCB board is protected by shrink hose. Replace the hose if damaged.</p>	<p data-bbox="970 1249 1302 1279">PCB board: 3HAC057687-001</p>  <p data-bbox="970 1720 1082 1742">xx1500002205</p>

Continues on next page

4 Repair

4.3.4 Replacing the EIB mounting plate

Continued

	Action	Note						
3	Secure the PCB board with cable ties. Do not tighten the ties too tight.	 <p>xx1500002752</p>						
4	Reconnect the connectors. <ul style="list-style-type: none"> • R1.BK1-2 • R1.DBP • R2.BK1-2 <p> CAUTION</p> <p>Make sure not to mix the connectors. See the labels on the connectors for correct connection.</p>	 <p>xx1500002190</p> <table border="1" data-bbox="943 1413 1398 1547"> <tbody> <tr> <td>A</td> <td>R1.BK1-2</td> </tr> <tr> <td>B</td> <td>R1.DBP</td> </tr> <tr> <td>C</td> <td>R2.BK1-2</td> </tr> </tbody> </table>	A	R1.BK1-2	B	R1.DBP	C	R2.BK1-2
A	R1.BK1-2							
B	R1.DBP							
C	R2.BK1-2							
5	Secure the cables with cable ties if needed.							

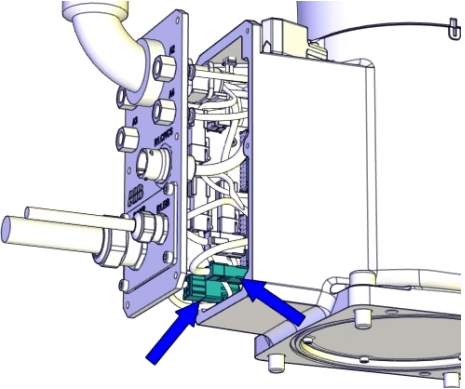
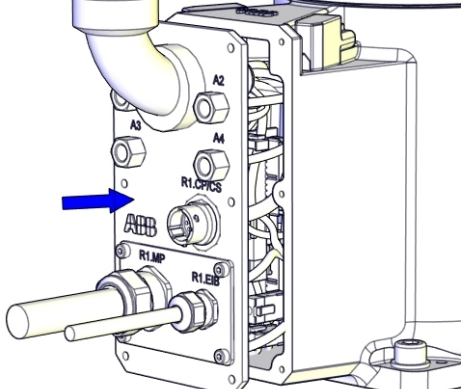
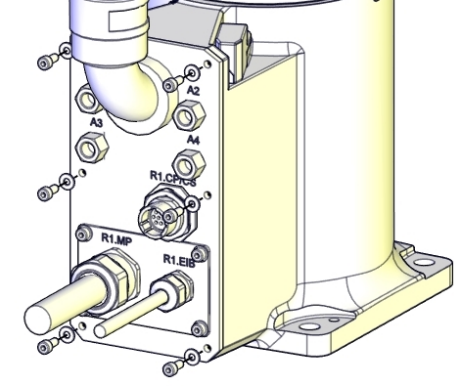
Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

4.3.4 Replacing the EIB mounting plate

Continued

	Action	Note
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p>xx1500002188</p>
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Concluding procedure


	Action	Note
1	Update the revolution counters.	See Updating revolution counters on page 351 .

Continues on next page

4 Repair

4.3.4 Replacing the EIB mounting plate

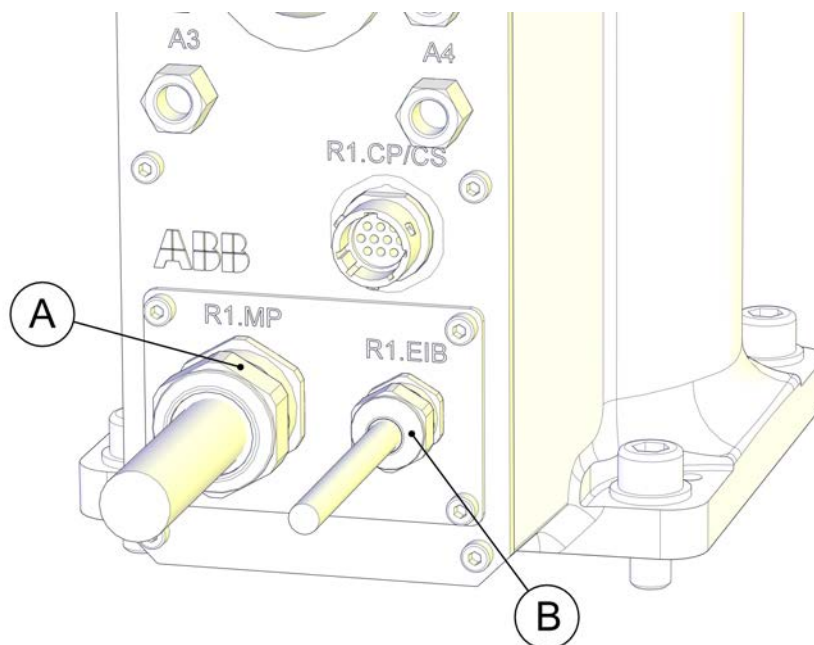
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	Action	Note
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.3.5 Replacing the floor cables

Location of the floor cables

The floor cables are located as shown in the figure.



xx1500002181

A	Power floor cable
B	Signal floor cable

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Power floor cable, 3 m	3HAC057784-001	
Power floor cable, 7 m	3HAC057785-001	
Power floor cable, 15 m	3HAC057786-001	
Signal floor cable, 3 m	3HAC057787-001	
Signal floor cable, 7 m	3HAC057788-001	
Signal floor cable, 15 m	3HAC057789-001	

Continues on next page

4 Repair

4.3.5 Replacing the floor cables

Continued

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

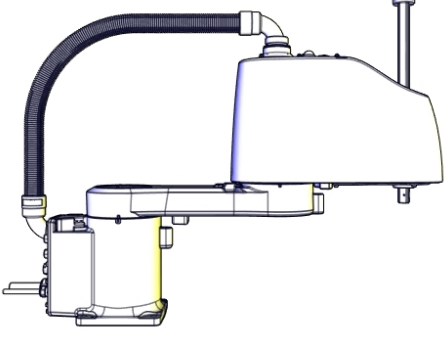

Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the floor cables

Use these procedures to remove the floor cables.

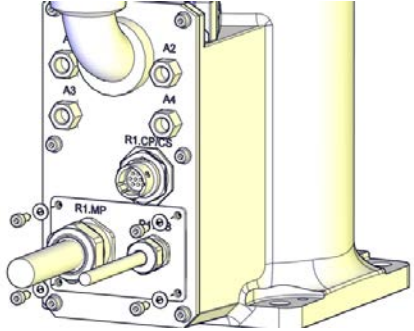
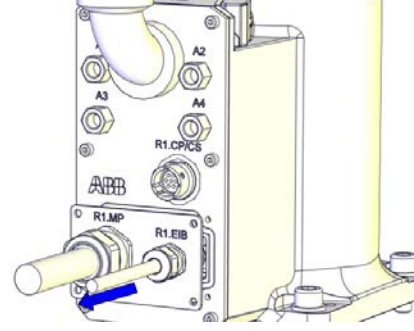
Preparations before removing the floor cables

	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	


Removing the floor cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

	Action	Note
2	Remove the screws and washers.	 <p>xx1500003003</p>
3	Pull out the floor cables.	 <p>xx1500003004</p>

Disconnecting the floor cable connectors

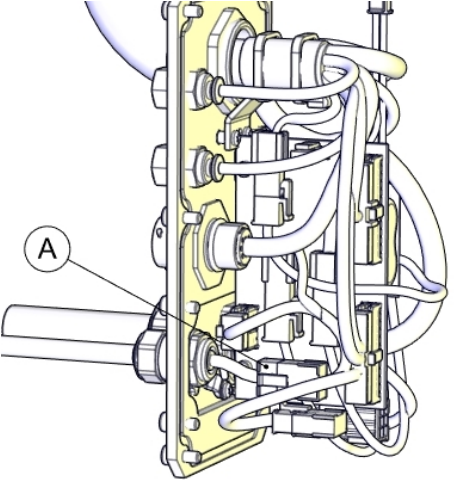
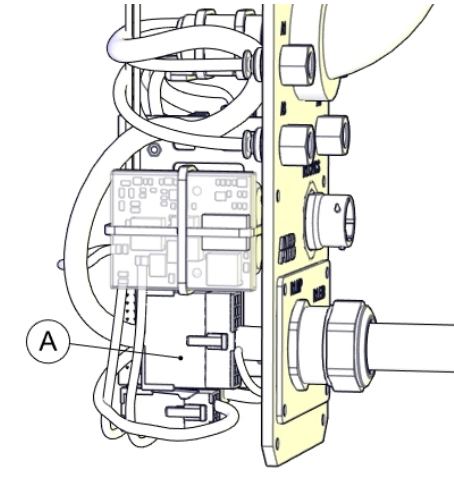
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

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4 Repair

4.3.5 Replacing the floor cables

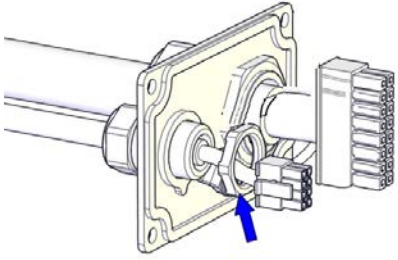
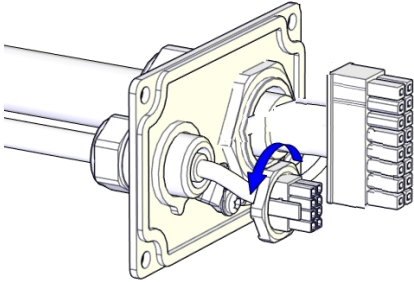
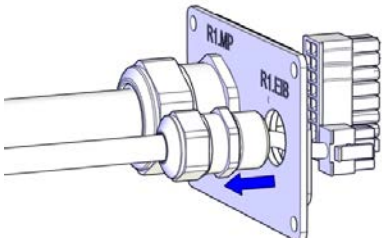
Continued

	Action	Note				
2	Disconnect the connectors. <ul style="list-style-type: none"> • R1.EIB • R1.MP 	 <p>xx1500002202</p> <table border="1" data-bbox="943 853 1398 898"> <tr> <td>A</td> <td>R1.EIB</td> </tr> </table>  <p>xx1500002203</p> <table border="1" data-bbox="943 1435 1398 1480"> <tr> <td>A</td> <td>R1.MP</td> </tr> </table>	A	R1.EIB	A	R1.MP
A	R1.EIB					
A	R1.MP					

Separating the signal floor cable

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

	Action	Note
2	Screw off the hexagonal lock nut.	 <p>xx1500003006</p>
3	Turn the lock nut gently against the connector to pull out the connector.	 <p>xx1500003007</p>
4	Remove the signal floor cable.	 <p>xx1500003008</p>

Refitting the floor cables

Use these procedures to refit the floor cables.

Assembling the signal floor cable

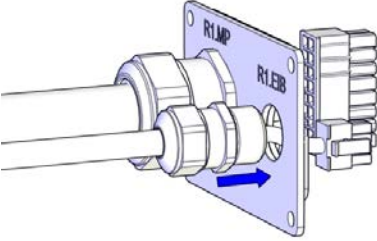
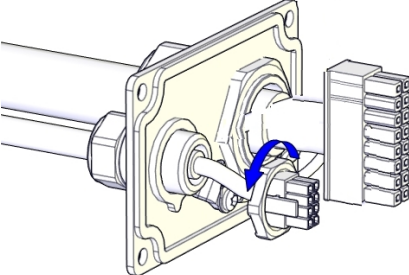
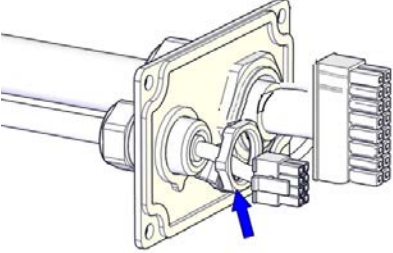
	Action	Note
1	Check the power floor cable. Replace if damaged.	

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4 Repair

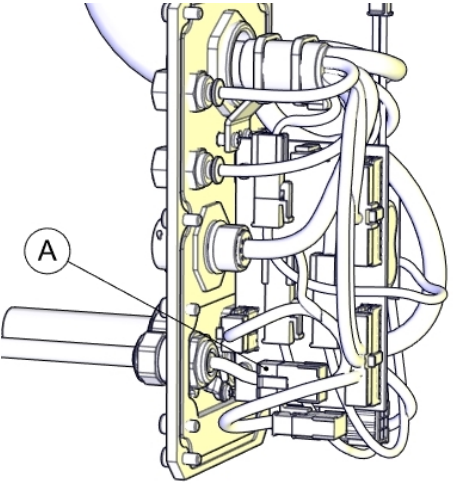
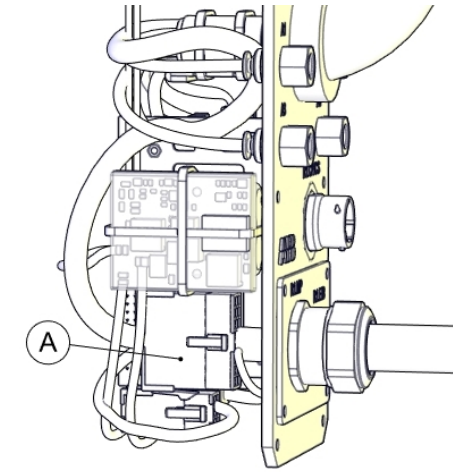
4.3.5 Replacing the floor cables

Continued

	Action	Note
2	Insert the signal floor cable.	 <p>xx1500003009</p>
3	Turn the hexagonal lock nut gently against the connector to enable the connector to move through the lock nut.	 <p>xx1500003007</p> <p>Lock nut: M16</p>
4	Secure the signal floor cable with the lock nut.	 <p>xx1500003006</p> <p>Tightening torque: 20 Nm</p>

Continues on next page

Reconnecting the floor cable connectors

	Action	Note				
1	Reconnect the connectors. <ul style="list-style-type: none"> • R1.EIB • R1.MP 	 <p>xx1500002202</p> <table border="1" data-bbox="973 907 1428 952"> <tr> <td>A</td> <td>R1.EIB</td> </tr> </table>  <p>xx1500002203</p> <table border="1" data-bbox="973 1489 1428 1534"> <tr> <td>A</td> <td>R1.MP</td> </tr> </table>	A	R1.EIB	A	R1.MP
A	R1.EIB					
A	R1.MP					

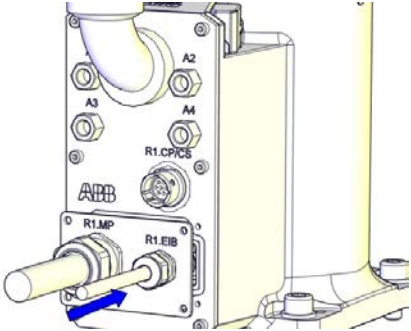
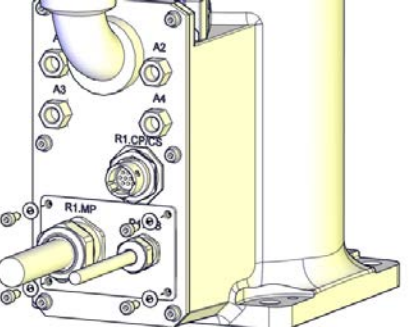
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4 Repair


4.3.5 Replacing the floor cables

Continued

Refitting the floor cables

	Action	Note
1	Push the floor cables into place.	 <p>xx1500003005</p>
2	Secure with screws and washers.	 <p>xx1500003003</p> <p>Screw: M4x10 (4 pcs) Tightening torque: 2 Nm</p>

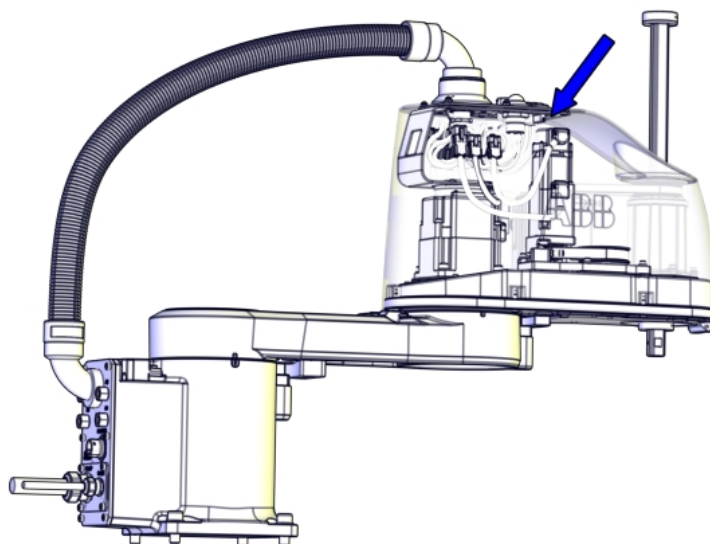
Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

4.3.6 Replacing the brake release harness

Location of the brake release harness

The brake release harness is located as shown in the figure.



xx180001421

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Brake release harness	3HAC038361-001	Includes brake release button and harness.

Required tools and equipment

Equipment, etc.	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .
Trolley	-	

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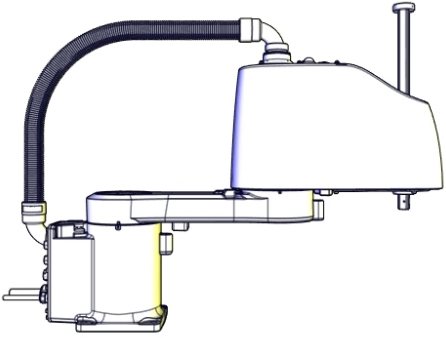

4 Repair

4.3.6 Replacing the brake release harness


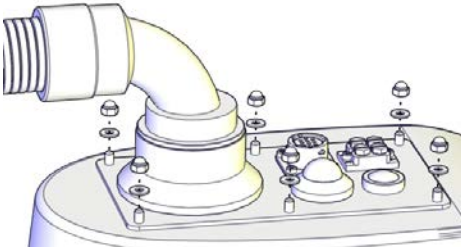
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Removing the brake release harness


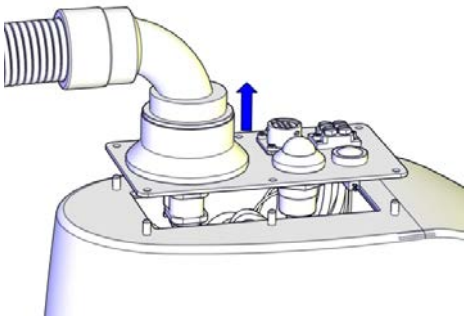

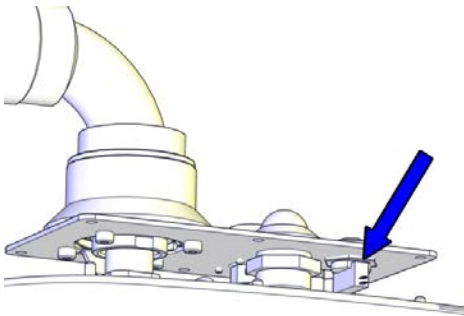
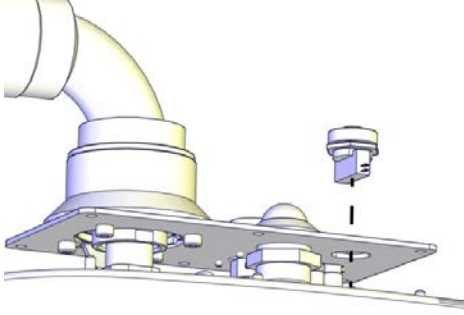
Preparations before removing the brake release harness

	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	

Removing the brake release harness

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the dome nuts and washers.	 xx1500002182

Continues on next page

	Action	Note
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>Do not pull out the plate completely.</p>	 <p>xx1500002183</p>
4	<p>Disconnect the brake release harness connector.</p> <ul style="list-style-type: none"> • R2.BR <p> Tip</p> <p>Take photos of the connector and cable position before disconnection, to have as a reference when reconnecting.</p>	
5	<p>Remove the nut.</p>	 <p>xx1800001422</p>
6	<p>Carefully pull the brake release button out.</p>	 <p>xx1800001423</p>

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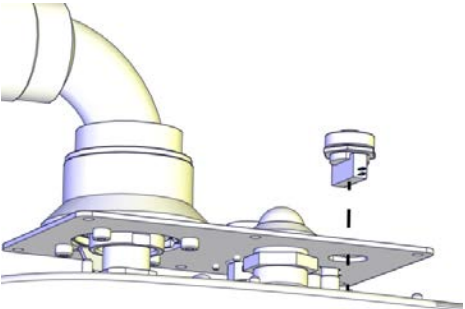
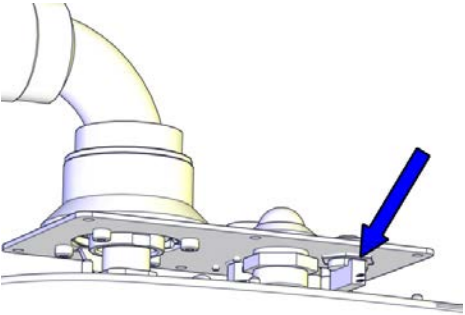
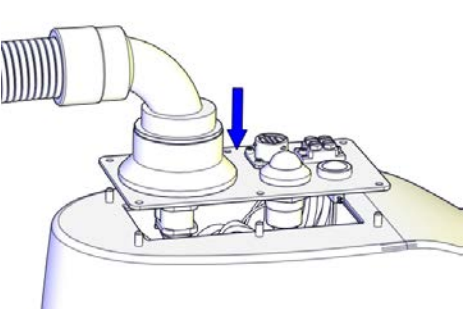
4 Repair

4.3.6 Replacing the brake release harness

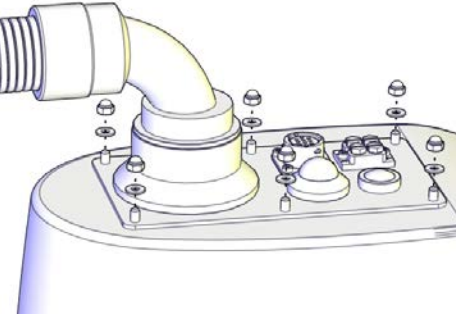
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Refitting the brake release harness


Refitting the brake release harness

	Action	Note
1	<p>Gently push and pull the brake release harness through the mounting hole.</p> <p> CAUTION</p> <p>Be careful not to bend or break the cables.</p>	 <p>xx1800001423</p>
2	Refit the nut.	 <p>xx1800001422</p>
3	Connect the brake release harness connector. <ul style="list-style-type: none">• R2.BR	
4	Push the main cable package into place.	 <p>xx1500002207</p>

Continues on next page

	Action	Note
5	Refit the user interface plate.	 <p data-bbox="975 645 1082 663">xx1500002182</p> <p data-bbox="975 680 1214 707">Dome nut: M4 (6 pcs)</p> <p data-bbox="975 712 1241 739">Tightening torque: 2 Nm</p> <p data-bbox="975 743 1129 770">Washer, 6 pcs</p>

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p data-bbox="587 1012 695 1039">DANGER</p> <p data-bbox="496 1070 963 1227">Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

4 Repair

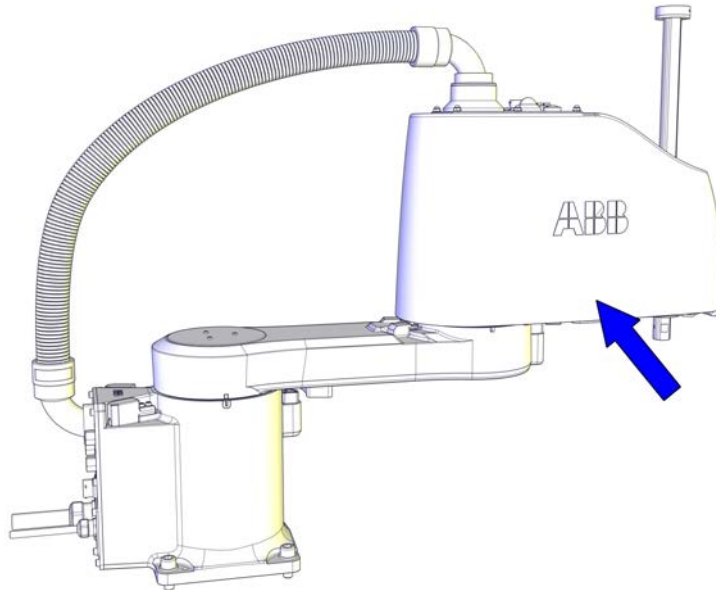
4.4.1 Replacing the upper arm

4.4 Upper arm

4.4.1 Replacing the upper arm

Location of the upper arm

The upper arm is located as shown in the figure.



xx1500002209

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Upper arm body	3HAC057711-001	
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.
Lower cover	3HAC060106-001	Replace if damaged.
Plate for upper arm cable harness	3HAC056086-001	Replace if damaged.
Axis-4 housing with idler	3HAC056121-001	Replace if damaged.
Axis-3 drive unit housing	3HAC055184-001	Replace if damaged.
Adjusting block for axis-3 timing belt	3HAC056650-001	Replace if damaged.

Continues on next page

4.4.1 Replacing the upper arm
Continued

Spare part	Article number	Note
Adjusting block for upper axis-4 timing belt	3HAC056651-001	Replace if damaged.
Adjusting block for lower axis-4 timing belt	3HAC056652-001	Replace if damaged.
Plain washer	3HAC056937-001	Replace if damaged.
Axis-2 mechanical stop block	3HAC055185-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	-	Used for measuring the timing belt tension.
Dynamometer	-	Used for measuring the timing belt tension.

Required consumables

Consumable	Article number	Note
Grease	-	THK AFA Used for lubricating the ball screw spline shaft.
Cable ties	-	

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4 Repair

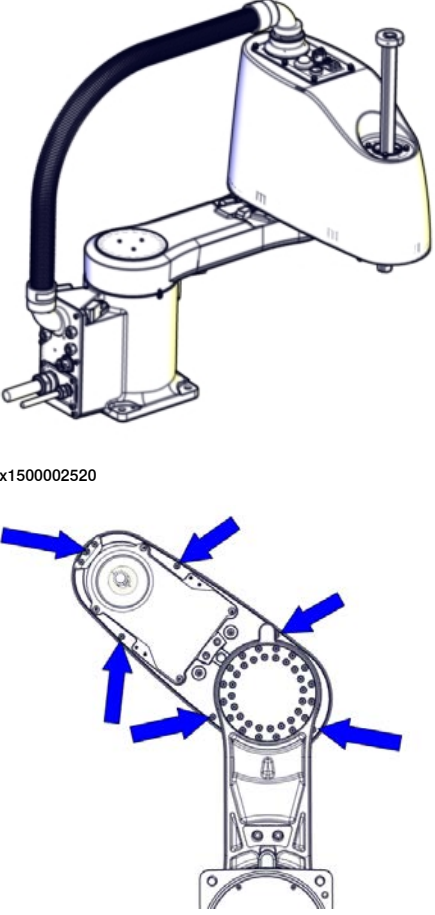

4.4.1 Replacing the upper arm

Continued

Removing the upper arm


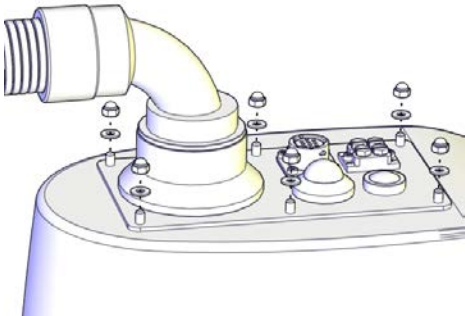

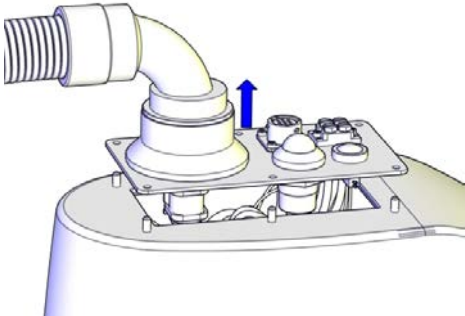
Use these procedures to remove the upper arm from the lower arm.

Preparations before removing the upper arm

	Action	Note
1	Jog axis 2 to access the cover screws.	 <p>xx1500002520</p> <p>xx1500002782</p>
2	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	

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Removing the main cable package from the upper arm


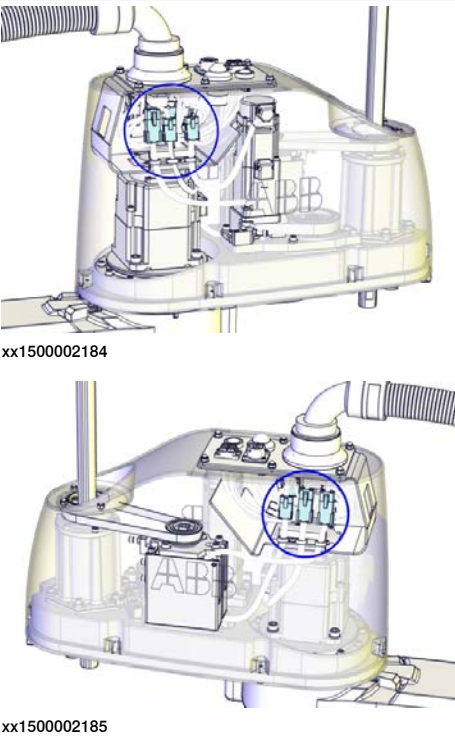
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the dome nuts and washers.</p>	 <p>xx1500002182</p>
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 <p>xx1500002183</p>

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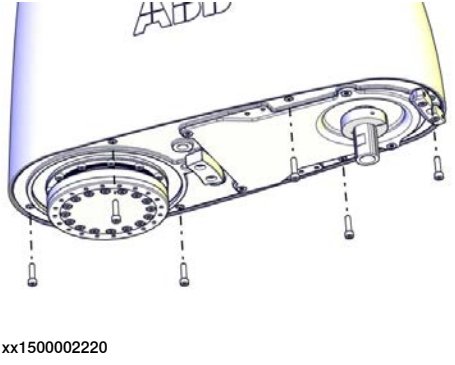
4 Repair

4.4.1 Replacing the upper arm


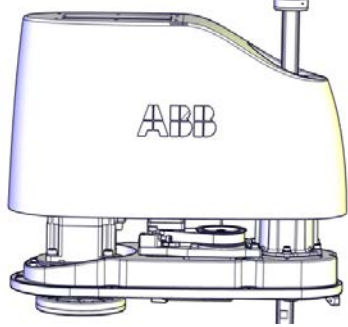
Continued

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	


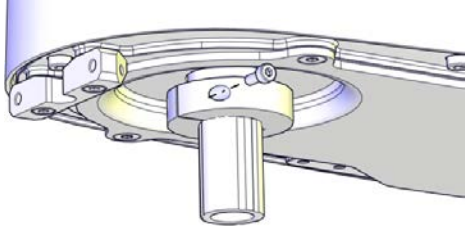
Removing the upper cover

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	

Continues on next page

	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 <p>xx1500002221</p>

Removing the lower stop block

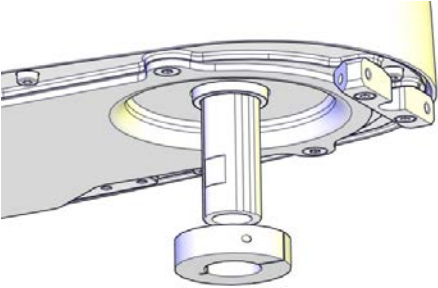
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the lower stop block of ball screw spline unit to replace: <ul style="list-style-type: none"> • lower cover of the upper arm • ball screw spine unit • upper arm body 	
3	Remove the screws.	 <p>xx1500002222</p>

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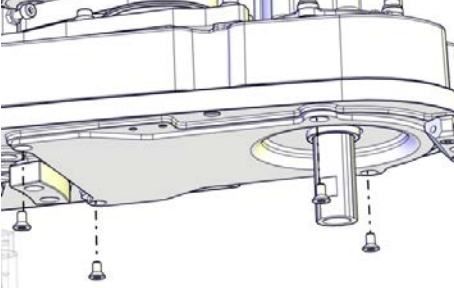

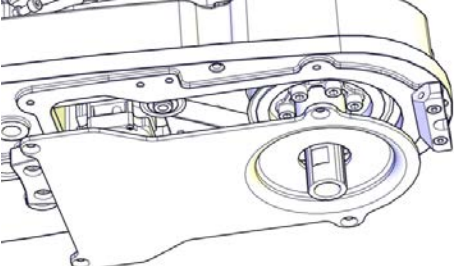
4 Repair

4.4.1 Replacing the upper arm

Continued



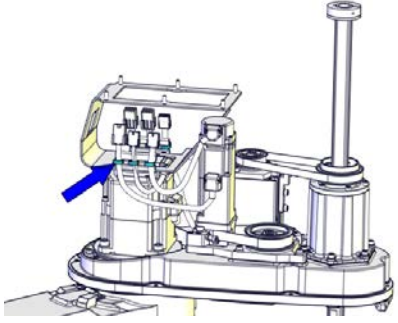
	Action	Note
4	Remove the stop block.	 <p data-bbox="943 645 1050 663">xx150002223</p>

Removing the lower cover


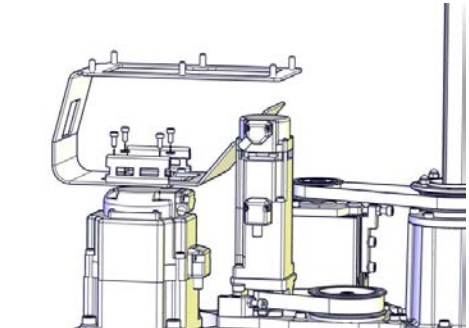
	Action	Note
1	 <p data-bbox="555 842 667 869">DANGER</p> <p data-bbox="464 904 932 981">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws.	 <p data-bbox="943 1346 1050 1364">xx150002785</p>
3	<p data-bbox="464 1400 678 1426">Remove the cover.</p>  <p data-bbox="555 1469 598 1496">Tip</p> <p data-bbox="464 1532 932 1639">If only working with lower axis-4 timing belt, no need to remove the stop block of ball screw spline unit before removing the lower cover.</p>	 <p data-bbox="943 1731 1050 1749">xx150002225</p>

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Removing the drive unit cables

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Cut the cable ties. Be careful not to damage the cabling.</p>  <p>Tip</p> <p>Take photos of the cable position before removing them, to have as a reference when refitting.</p>	 <p>xx1500002226</p>

Removing the cable harness plate

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws and washers.	 <p>xx1500002228</p>
3	Remove the cable harness plate.	

Removing the axis-3 timing belt


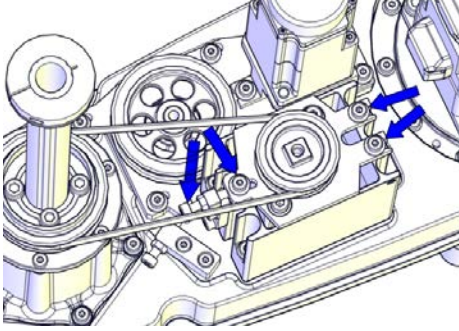
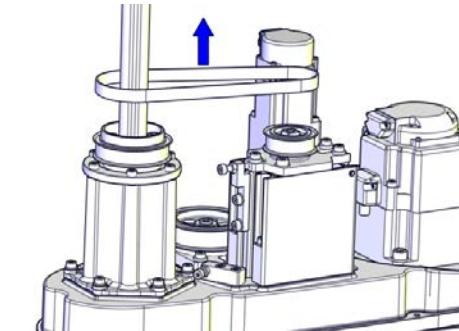
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

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4 Repair

4.4.1 Replacing the upper arm

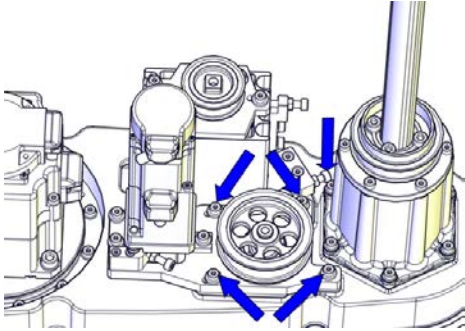
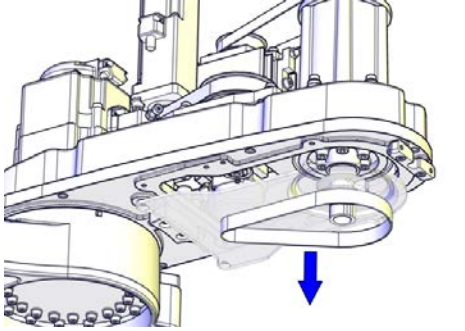
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	Action	Note
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-3 drive unit upwards to slacken the timing belt.	 <small>xx1500002229</small>
4	Remove the timing belt.	 <small>xx1500002230</small>


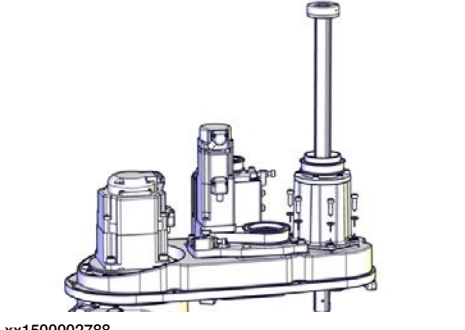
Removing the lower axis-4 timing belt

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	

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	Action	Note
3	Loosen the screws and move the axis-4 housing sideways to slacken the lower axis-4 timing belt.	 <p>xx1500002231</p>
4	Remove the timing belt.	 <p>xx1500002232</p>

Removing the ball screw spline

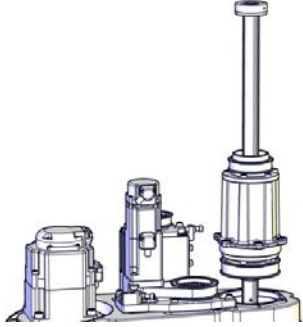
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws.	 <p>xx1500002788</p>

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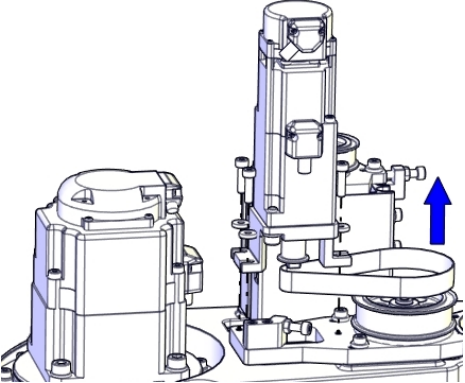
4 Repair

4.4.1 Replacing the upper arm

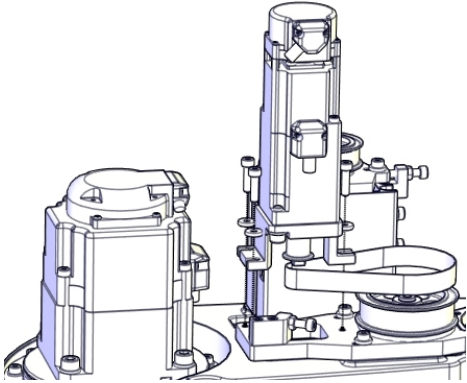
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	Action	Note
3	Remove the ball screw spline unit.	 <p>xx1500002787</p>



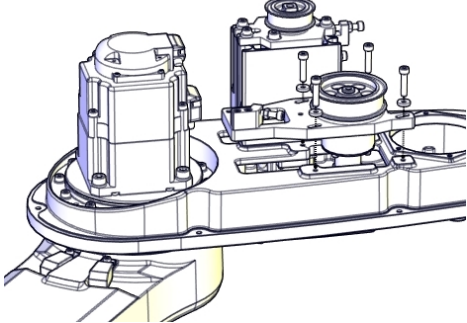
Removing the axis-4 drive unit and upper timing belt

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>WARNING</p> <p>Risk of tipping. Make sure the gravity center is well supported.</p>	
3	Loosen the screws and move the axis-4 drive unit upwards to slacken the upper axis-4 timing belt.	 <p>xx1500002233</p>

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	Action	Note
4	Remove the drive unit and timing belt.	 <p>xx1500002234</p>

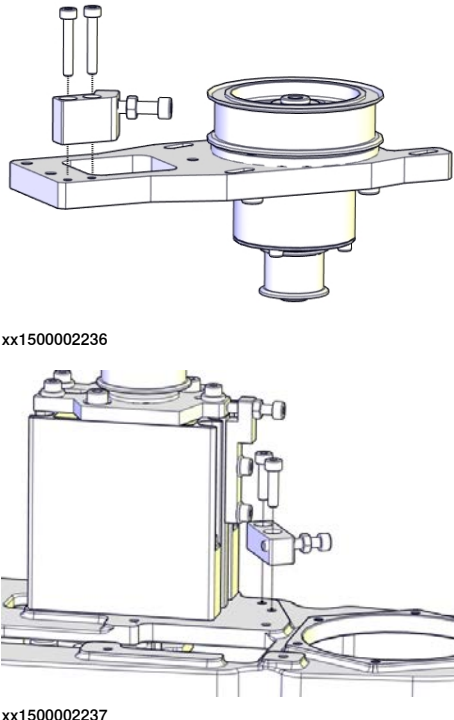
Removing the axis-4 housing with idler

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>WARNING</p> <p>There is a risk of tipping during the removal. Make sure the gravity center is well supported.</p>	
3	Remove the axis-4 housing with idler.	 <p>xx1500002235</p>



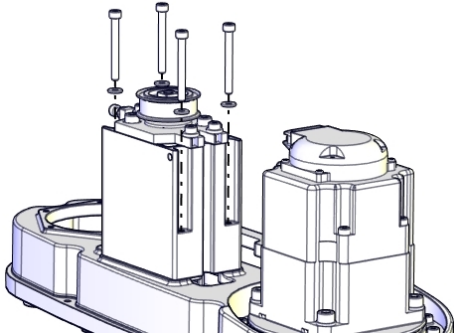
4 Repair

4.4.1 Replacing the upper arm

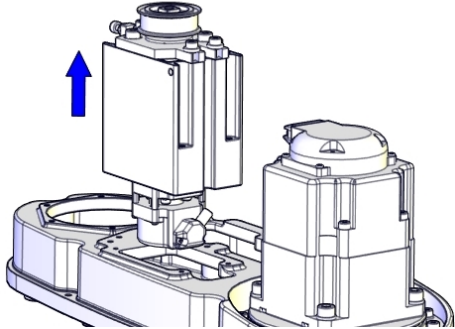
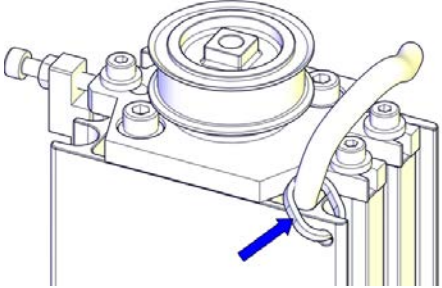

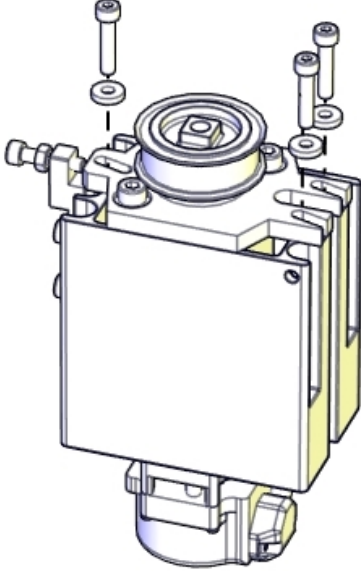
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	Action	Note
4	Remove the adjusting blocks.	 <p data-bbox="943 651 1050 674">xx1500002236</p> <p data-bbox="943 1025 1050 1048">xx1500002237</p>

Removing the axis-3 housing and axis-3 drive unit

	Action	Note
1	 <p data-bbox="555 1227 667 1254">DANGER</p> <p data-bbox="464 1285 932 1361">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p data-bbox="555 1438 683 1464">WARNING</p> <p data-bbox="464 1496 932 1550">Risk of tipping. Make sure the gravity center is well supported.</p>	
3	Remove the screws and washers.	 <p data-bbox="943 1935 1050 1957">xx1500002810</p>

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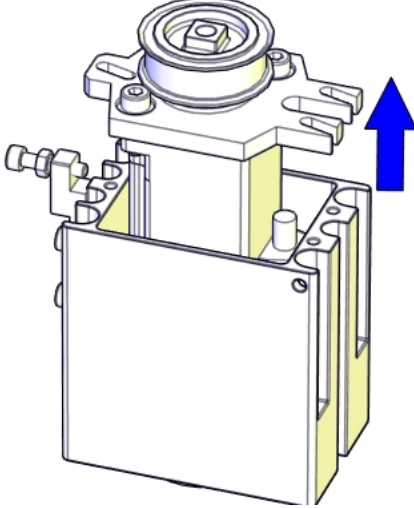
	Action	Note
4	Lift out the axis-3 housing and drive unit.	 <p>xx1500002238</p>
5	Cut the cable tie. Be careful not to damage the cabling.	 <p>xx1500002815</p>
6	<p>Remove the screws.</p> <p> WARNING</p> <p>Do not remove the other screws. They hold the gearbox together. Removing them can damage the gearbox severely.</p>	 <p>xx1500002797</p>

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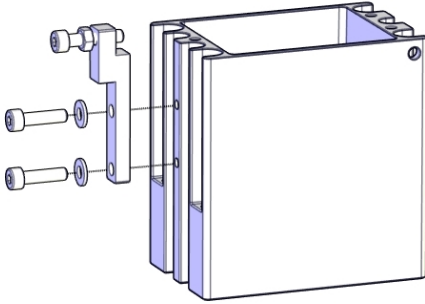
4 Repair

4.4.1 Replacing the upper arm


Continued

	Action	Note
7	Lift out the axis-3 drive unit carefully.	 <p>xx1500002239</p>



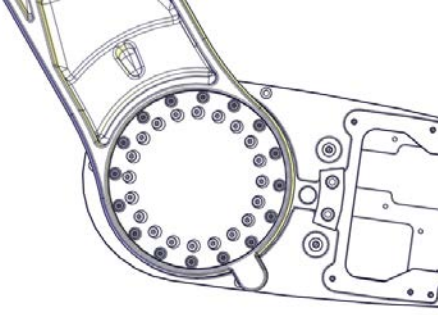
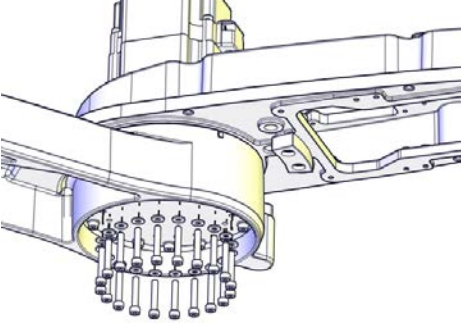
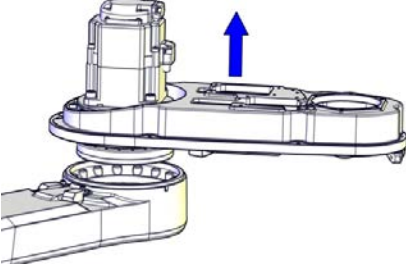
Removing the axis-3 timing belt adjusting block

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the adjusting block.	 <p>xx1500002240</p>


Removing the upper arm body

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

	Action	Note
2	<p> WARNING</p> <p>The upper arm body with the axis-2 drive unit weights 7 kg. Make sure the weight of the upper arm body is properly supported, or it may drop when it is released from the lower arm.</p>	
3	<p>Remove the screws and washers.</p> <p> WARNING</p> <p>Keep the twelve screws in the outer circle fitted. They hold the axis-2 motor flange on the lower arm.</p>  <p>xx1500002242</p>	 <p>xx1500002241</p>
4	<p>Remove the upper arm body and lay it aside on a workbench.</p>	 <p>xx1500002799</p>

Removing the axis-2 drive unit



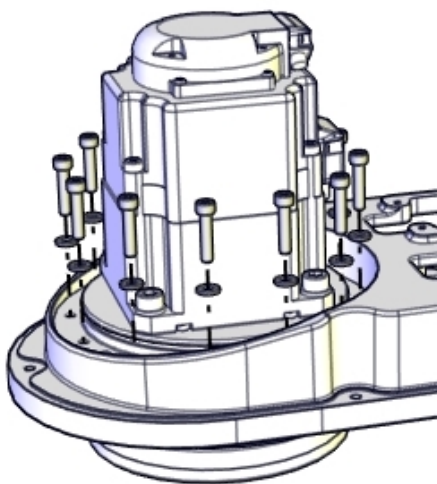
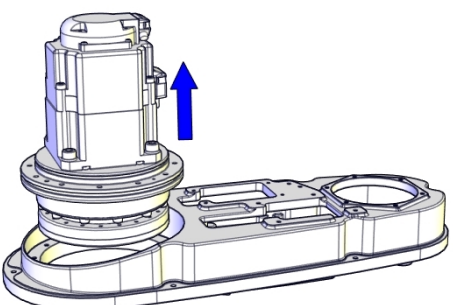

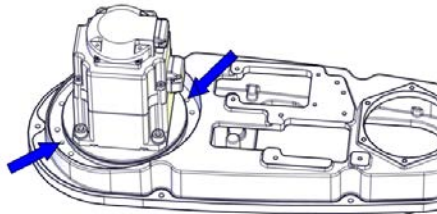
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

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4 Repair


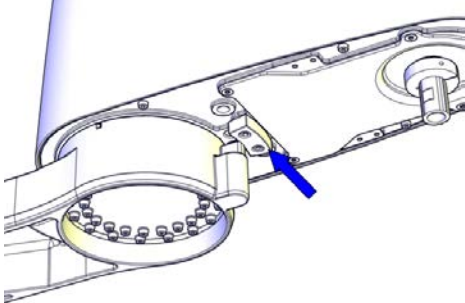
4.4.1 Replacing the upper arm

Continued

	Action	Note
2	<p> WARNING</p> <p>There is a risk of tipping during the removal. Make sure the gravity center is well supported.</p>	
3	<p>Remove the screws.</p> <p> WARNING</p> <p>Do not remove the other screws. They hold the gearbox together. Removing them can damage the gearbox severely.</p>	 <p>xx1500002800</p>
4	<p>Lift out the drive unit.</p>	 <p>xx1500002243</p>
5	<p> Tip</p> <p>If the drive unit is hard to remove, insert two M3 screws and press out the drive unit.</p>	 <p>xx1500002244</p>

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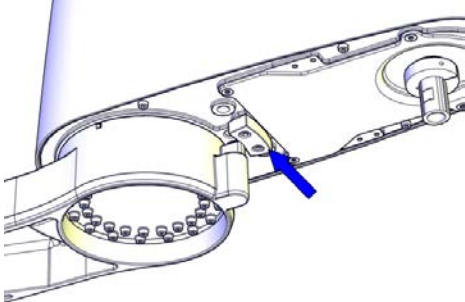
Removing the axis-2 mechanical stop block

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the axis-2 mechanical stop block.	 <p>xx1500003062</p> <p>See Replacing the axis-2 mechanical stop on page 271.</p>

Refitting the upper arm

Use these procedures to refit the upper arm.

Refitting axis-2 mechanical stop block

	Action	Note
1	Refit the axis-2 mechanical stop block with screws.	 <p>xx1500003062</p> <p>See Replacing the axis-2 mechanical stop on page 271.</p>

Refitting the axis-2 drive unit



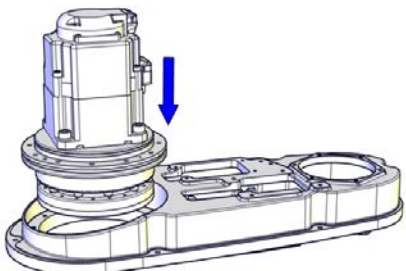
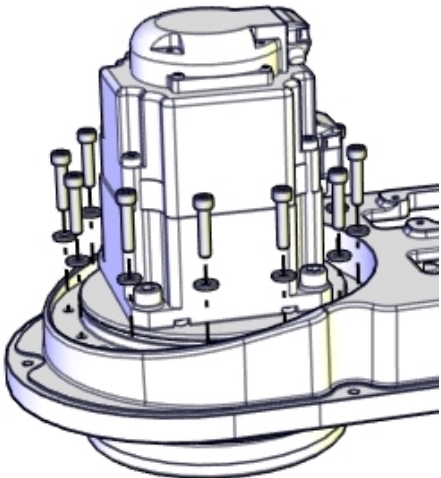
	Action	Note
1	<p>Make sure that:</p> <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	

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4 Repair

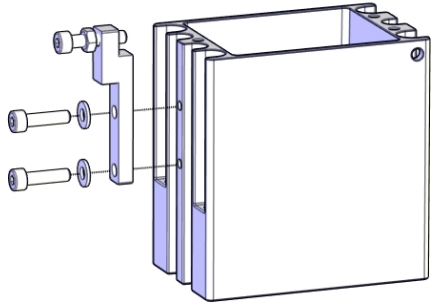
4.4.1 Replacing the upper arm

Continued


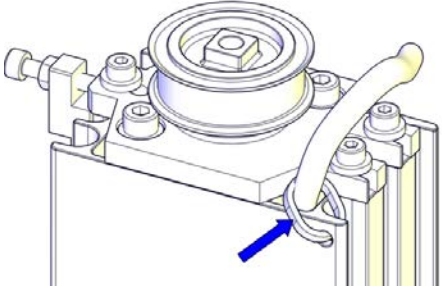
	Action	Note
2	<p>Refit the drive unit.</p> <p> CAUTION</p> <p>Do not mix axis-1 and axis-2 drive units. Always check the mark or label on the drive units before refitting.</p> <p> Note</p> <p>Make sure to refit the drive unit with the motor connectors pointing to the ball screw spline unit location.</p>	<p>Axis-2 drive unit: 3HAC056153-001</p>  <p>xx1500003068</p>
3	<p>Secure with screws and washers.</p>	 <p>xx1500002800</p> <p>Screw: M4x25 (12 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1 (12 pcs)</p>

Continues on next page

Refitting the axis-3 timing belt adjusting block

	Action	Note
1	Refit the adjusting block.	<p>Adjusting block: 3HAC056651-001</p>  <p>xx1500002240</p> <p>Screw: M4x16 (2 pcs) Tightening torque: 4.5 Nm</p>

Refitting the axis-3 housing and axis-3 drive unit

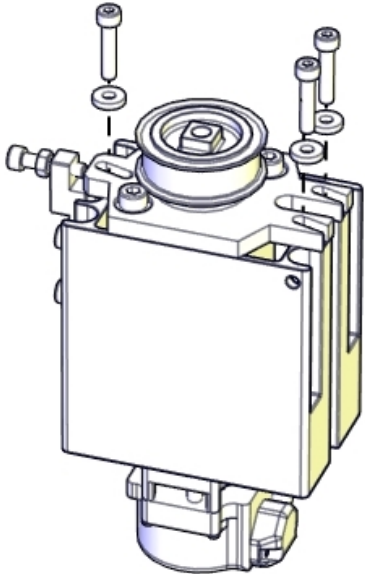

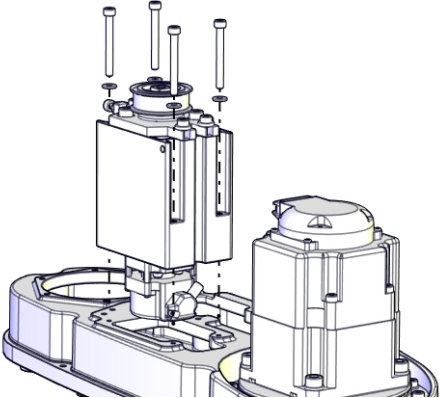
	Action	Note
1	<p>Refit the drive unit with one cabling coming out from the upside and the other coming out from the downside.</p>  <p>Note</p> <p>Make sure to refit the drive unit correctly oriented with the lugs of the drive unit bracket as a reference.</p>	<p>Axis-3 drive unit: 3HAC056111-001 Axis-3 drive unit housing: 3HAC055184-001</p>
2	Secure the upper cabling with a cable tie. Do not tighten the tie too tight.	 <p>xx1500002815</p>

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4 Repair

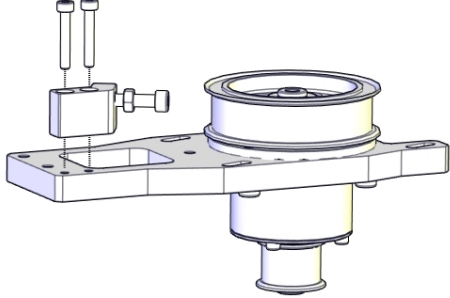
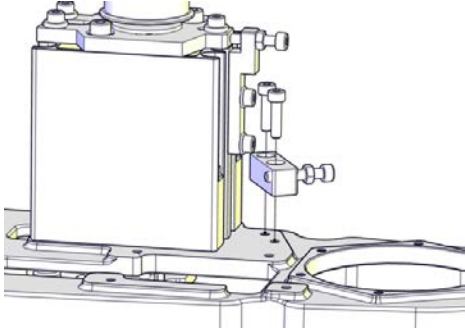
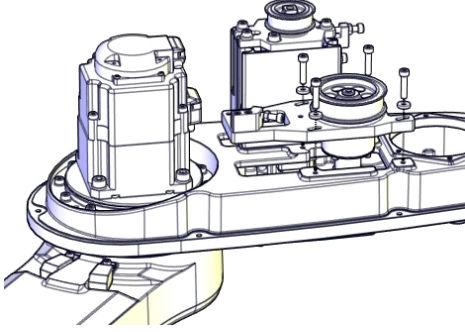

4.4.1 Replacing the upper arm

Continued

	Action	Note
3	Refit drive unit screws and washers just enough to still be able to move the drive unit.	 <p data-bbox="943 920 1050 936">xx1500002797</p> <p data-bbox="943 958 1321 1055">Screw: M4x20 (3 pcs) Tightening torque: 4.5 Nm Washer (3HAC056937-001, 3 pcs)</p> <p data-bbox="943 1070 1410 1196"> Note Only use specified washers, never replace them with other washers.</p>
4	Refit the housing with drive unit.	 <p data-bbox="943 1637 1050 1653">xx1500002798</p> <p data-bbox="943 1675 1235 1771">Screw: M4x40 (4 pcs) Tightening torque: 3.5 Nm Washer: M4 (4 pcs)</p>

Continues on next page

Refitting the axis-4 housing with idler

	Action	Note
1	Refit the adjusting blocks.	<p>Adjusting block for upper timing belt: 3HAC056651-001</p>  <p>xx1500002236</p> <p>Screw: M3x20 (2 pcs)</p> <p>Adjusting block for lower timing belt: 3HAC056652-001</p>  <p>xx1500002237</p> <p>Screw: M4x16 (2 pcs)</p> <p>Tightening torque: 4.5 Nm</p>
2	Refit the housing with idler and fasten the screws and washers just enough to still be able to move the housing sideways.	 <p>xx1500002235</p> <p>Screw: M4x20 (4 pcs)</p> <p>Washer (3HAC056937-001, 4 pcs)</p> <p> Note</p> <p>Only use specified washers, never replace them with other washers.</p>

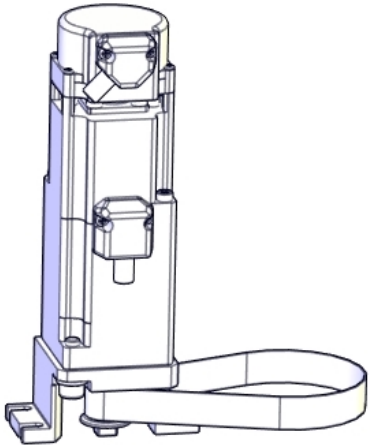

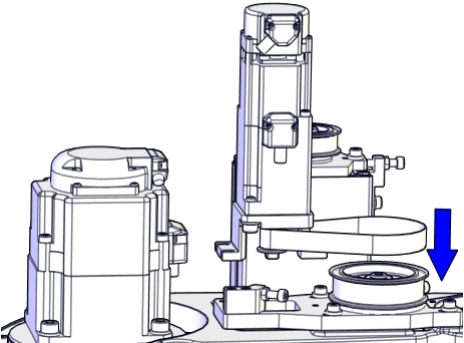
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4 Repair

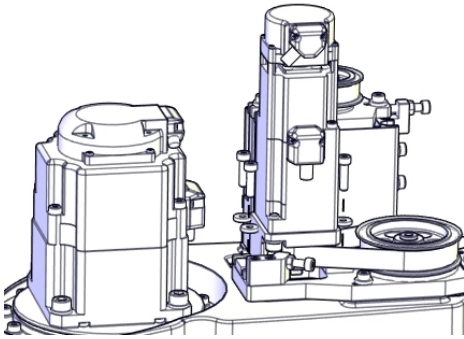

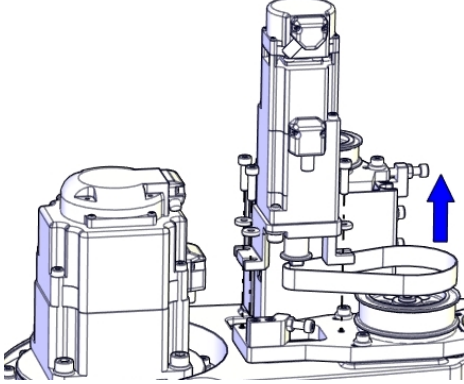
4.4.1 Replacing the upper arm

Continued

Refitting the axis-4 drive unit and upper timing belt

	Action	Note
1	<p>Make sure that:</p> <ul style="list-style-type: none">• all assembly surfaces are clean and undamaged.• the drive unit is clean and undamaged.	
2	Place the timing belt.	<p>Axis-4 drive unit: 3HAC056112-001 Upper axis-4 timing belt: 3HAC055206-001</p>  <p>xx1500002801</p>
3	<p>Refit the drive unit and timing belt.</p> <p> Note</p> <p>Make sure to refit the drive unit with motor connectors pointing against axis-3 drive unit.</p>	 <p>xx1500002802</p>

Continues on next page

	Action	Note
4	Refit screws and washers just enough to still be able to move the drive unit upwards.	 <p>xx1500002803</p> <p>Screw: M4x16 (3 pcs) Washer (3HAC056937-001, 3 pcs)</p> <p> Note</p> <p>Only use specified washers, never replace them with other washers.</p>
5	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p>xx1500002233</p> <p>Belt tension: $F = 37 \text{ N}$ (Recommended) Belt tension range: 24.1 N to 27.6 N (for used timing belt, which has been installed and used for more than 24 hours) 34.5 N to 37.9 N (for new timing belt)</p>

Refitting the ball screw spline unit

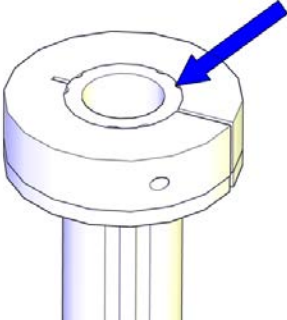
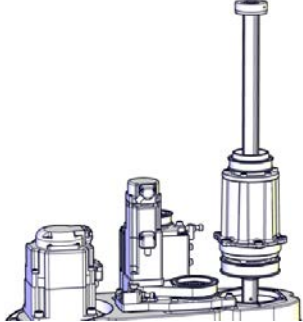
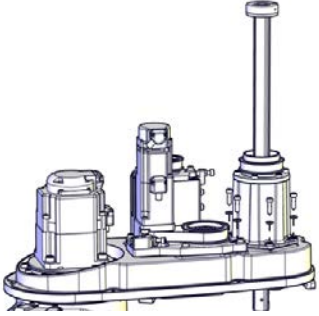
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> all assembly surfaces are clean and undamaged. the ball screw spline unit is well-lubricated and undamaged. 	See Lubricating the ball screw spline unit on page 111 .
2	If a new ball screw spline unit is used, remove the lower stop block to enable fitting of the lower cover.	See "Removing the lower stop block" in Removing the ball screw spline unit on page 231 .

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4 Repair

4.4.1 Replacing the upper arm

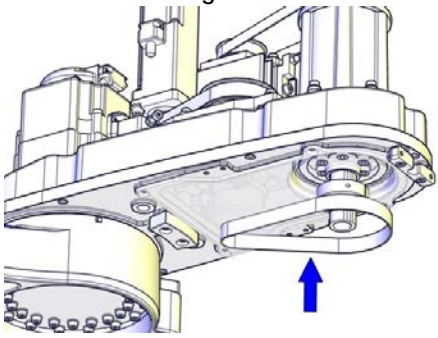
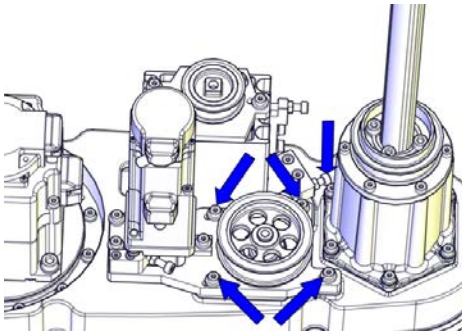
Continued

	Action	Note
3	<p>Check the upper stop block of the ball screw spline unit. Replace if damaged. Make sure the upper surfaces of the shaft and stop block are at the same level.</p>	<p>Upper axis-3 and axis-4 mechanical stop block: 3HAC061259-001</p>  <p>xx1600002115</p>
4	<p>Refit the ball screw spline unit.</p>	<p>Ball screw spline unit: 3HAC056148-001</p>  <p>xx1500002787</p>
5	<p>Secure with screws and washers.</p>	 <p>xx1500002788</p> <p>Screw: M4x16 (6 pcs) Tightening torque: 4.5 Nm Washer: M4 (6 pcs)</p>

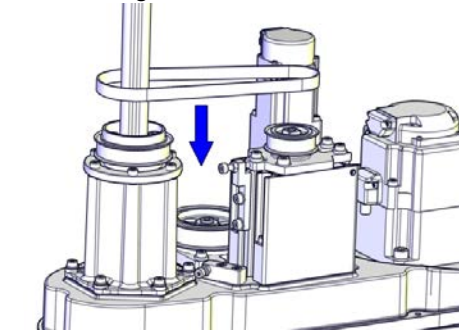
Refitting the lower axis-4 timing belt

	Action	Note
1	<p>Make sure that:</p> <ul style="list-style-type: none"> all assembly surfaces are clean and undamaged. the drive unit is clean and undamaged. 	

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	Action	Note
2	Refit lower axis-4 timing belt. Ensure that the belt runs correctly in the grooves.	<p>Lower axis-4 timing belt: 3HAC055201-001</p>  <p>xx1500002786</p>
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p>xx1500002231</p> <p>Belt tension: $F = 101 \text{ N}$ (Recommended) Belt tension range: 64.5 N to 73.7 N (for used timing belt, which has been installed and used for more than 24 hours) 92.2 N to 101 N (for new timing belt)</p>

Refitting the axis-3 timing belt

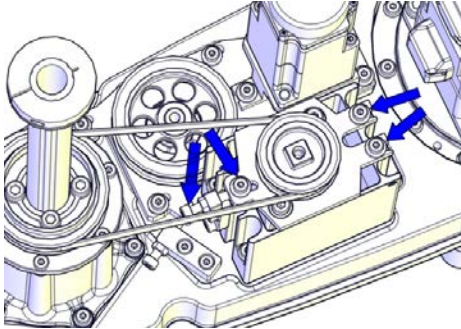
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Refit axis-3 timing belt. Ensure that the belt runs correctly in the grooves.	<p>Axis-3 timing belt: 3HAC055209-001</p>  <p>xx1500002789</p>

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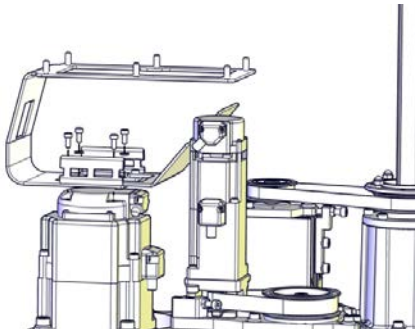
4 Repair

4.4.1 Replacing the upper arm

Continued

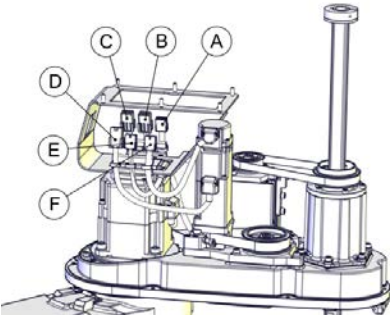
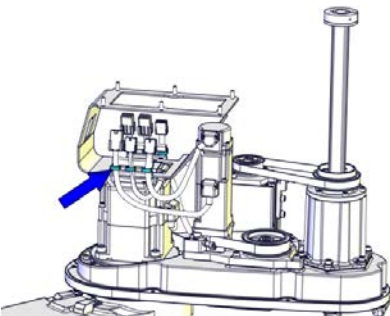
	Action	Note
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p data-bbox="940 645 1050 663">xx1500002229</p> <p data-bbox="940 680 1374 707">Belt tension: $F = 34 \text{ N}$ (Recommended)</p> <p data-bbox="940 714 1153 741">Belt tension range:</p> <p data-bbox="940 748 1406 831">21.8 N to 24.9 N (for used timing belt, which has been installed and used for more than 24 hours)</p> <p data-bbox="940 837 1326 864">31.1 to 34.2 N (for new timing belt)</p>

Refitting the cable harness plate


	Action	Note
1	Refit the cable harness plate.	 <p data-bbox="940 1323 1050 1341">xx1500002228</p> <p data-bbox="940 1359 1166 1386">Screw: M3x8 (4 pcs)</p> <p data-bbox="940 1393 1230 1420">Tightening torque: 1.5 Nm</p> <p data-bbox="940 1426 1158 1453">Washer: M3 (4 pcs)</p>
2	Secure with screws and washers.	

Continues on next page

Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p>xx150003063</p> <table border="1" data-bbox="973 728 1433 1003"> <tbody> <tr> <td>A</td> <td>R2.ME3</td> </tr> <tr> <td>B</td> <td>R2.MP2</td> </tr> <tr> <td>C</td> <td>R2.MP3</td> </tr> <tr> <td>D</td> <td>R2.MP4</td> </tr> <tr> <td>E</td> <td>R2.ME2</td> </tr> <tr> <td>F</td> <td>R2. ME4</td> </tr> </tbody> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p>xx150002226</p>												

Refitting the upper cover


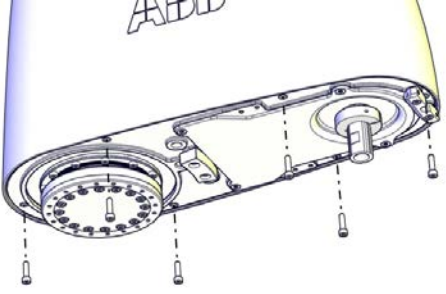
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	<p>Upper cover unit: 3HAC057615-001</p>  <p>xx150002221</p>

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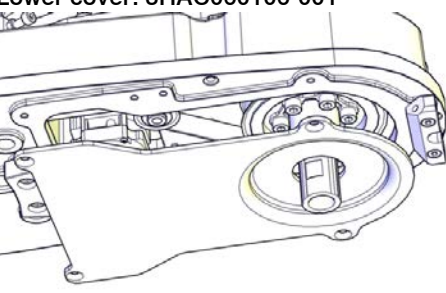
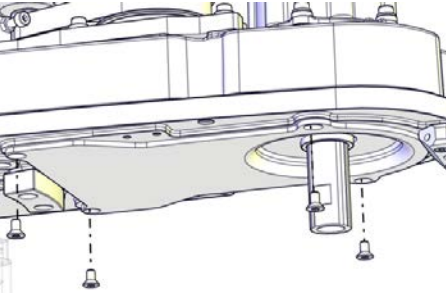
4 Repair

4.4.1 Replacing the upper arm

Continued

	Action	Note
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <p>xx1500002220</p> <p>Screw: M4x16 (6 pcs) Tightening torque: 2 Nm</p>

Refitting the lower cover

	Action	Note
1	Refit the cover.	<p>Lower cover: 3HAC060106-001</p>  <p>xx1500002225</p>
2	Secure with screws.	 <p>xx1500002785</p> <p>Screw: M4x8 (4 pcs) Tightening torque: 2 Nm</p>

Continues on next page

Refitting the lower stop block

	Action	Note						
1	<p>Check the lower stop block of the ball screw spline unit. Replace if damaged.</p>	<p>Lower axis-3 and axis-4 mechanical stop block: 3HAC055208-001</p>						
2	<p>Refit the lower stop block. Make the notch point to the calibration block and 90° away from the flat mark on the shaft. Make sure the distance between the lower surfaces of stop block and shaft is 30 mm.</p>	<div data-bbox="970 465 1412 757"> </div> <p data-bbox="970 801 1082 824">xx1500002908</p> <table border="1" data-bbox="970 840 1437 981"> <tr> <td data-bbox="970 840 1029 884">A</td> <td data-bbox="1029 840 1437 884">Flat mark on the shaft</td> </tr> <tr> <td data-bbox="970 884 1029 929">B</td> <td data-bbox="1029 884 1437 929">Notch</td> </tr> <tr> <td data-bbox="970 929 1029 974">C</td> <td data-bbox="1029 929 1437 974">Calibration block</td> </tr> </table> <div data-bbox="970 996 1437 1272"> </div> <p data-bbox="970 1328 1082 1350">xx1500002224</p>	A	Flat mark on the shaft	B	Notch	C	Calibration block
A	Flat mark on the shaft							
B	Notch							
C	Calibration block							
3	<p>Secure with the screw.</p>	<div data-bbox="970 1377 1437 1608"> </div> <p data-bbox="970 1713 1082 1736">xx1500002222</p> <p data-bbox="970 1751 1257 1818">Screw: M5x8 (1 pcs) Tightening torque: 10 Nm</p> <div data-bbox="970 1832 1029 1888"> </div> <p data-bbox="1061 1848 1125 1870">Note</p> <p data-bbox="970 1904 1437 1960">Only use specified screws, never replace them with other screws.</p>						



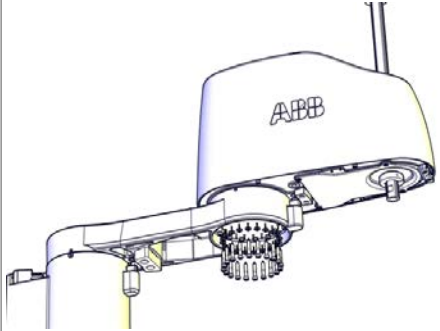
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4 Repair

4.4.1 Replacing the upper arm

Continued

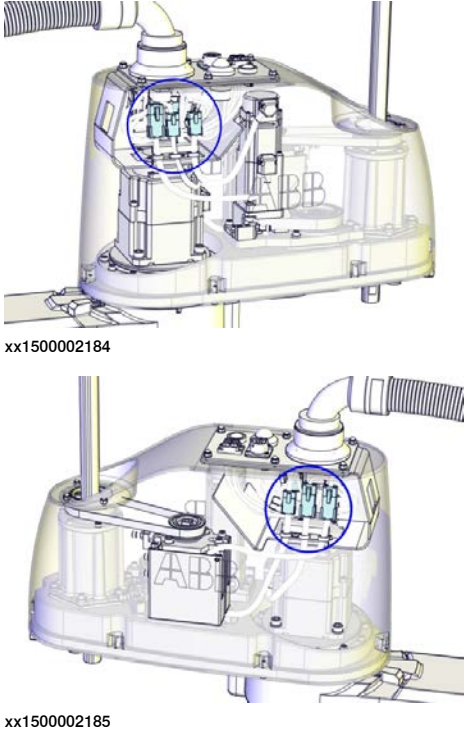
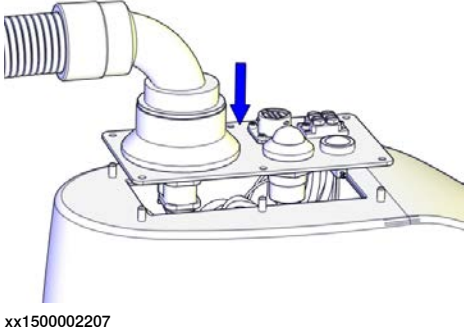
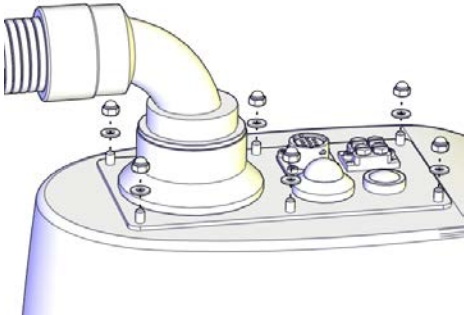
Refitting the upper arm

 Note Two persons working together are required to perform this procedure.	
Action	Note
1  Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Refit the screws that fasten the upper arm to the lower arm.	
2 Make sure the lower arm is secured. Lower the upper arm down onto the right place of the lower arm.	
3 Refit the upper arm screws and washers.	 xx1500002256 Screw: M4x20 (16 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1.3 (16 pcs)

Refitting the main cable to the upper arm

Action	Note
1 Secure the main cable package with cable ties if needed.	

Continues on next page

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>


Continues on next page

4 Repair

4.4.1 Replacing the upper arm

Continued

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.4.2 Replacing the ball screw spline unit

General

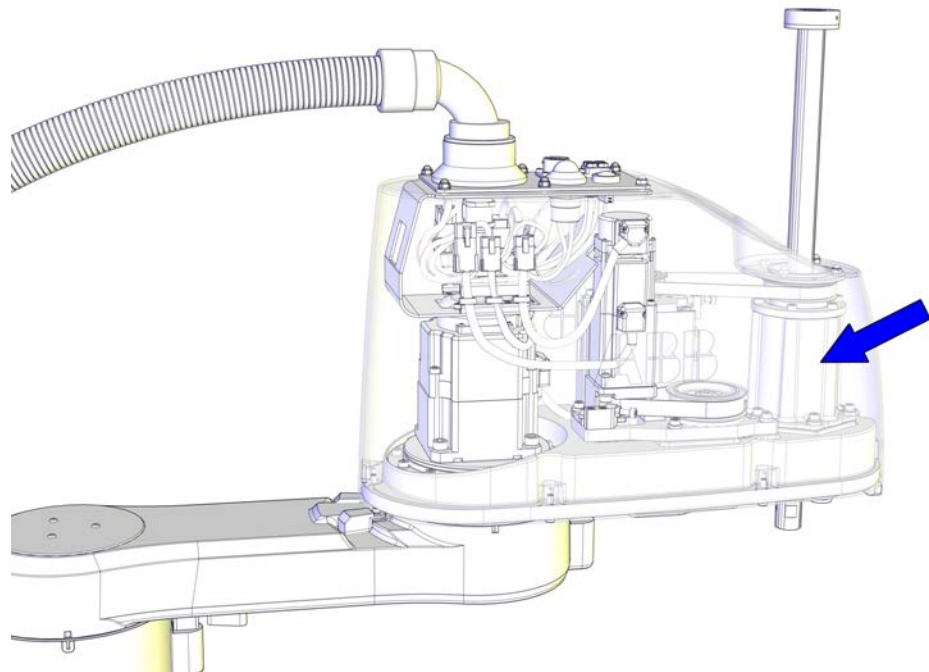


Note

If a collision with the stop blocks on the ball screw spline unit occur, check and retighten all screws before replacement work. Replace damaged or cracked screws.

Location of the ball screw spline unit

The ball screw spline unit is located as shown in the figure.



xx1500002212

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Ball screw spline unit	3HAC056148-001	

Continues on next page

4 Repair

4.4.2 Replacing the ball screw spline unit

Continued

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	-	Used for measuring the timing belt tension.
Dynamometer	-	Used for measuring the timing belt tension.

Required consumables

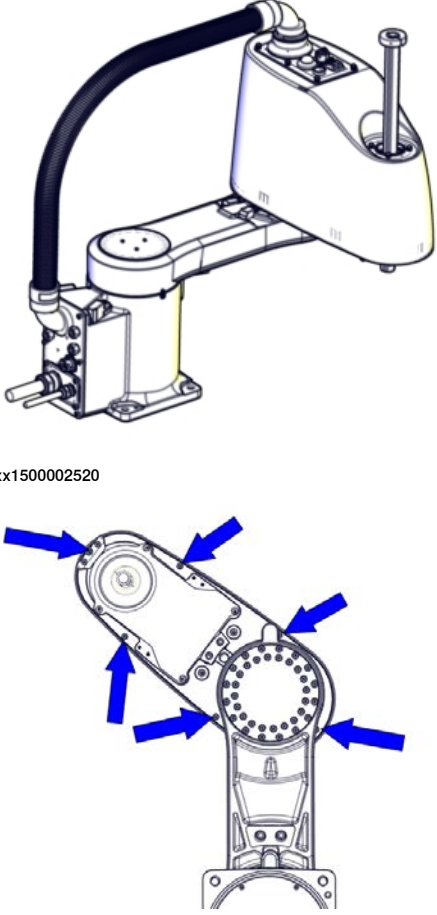

Consumable	Article number	Note
Grease	-	THK AFA Used for lubricating the ball screw spline shaft.
Cable ties	-	

Continues on next page

Removing the ball screw spline unit

Use these procedures to remove the ball screw spline unit.

Preparations before removing the ball screw spline unit

	Action	Note
1	Jog axis 2 to access the cover screws.	 <p>xx1500002520</p> <p>xx1500002782</p>
2	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	


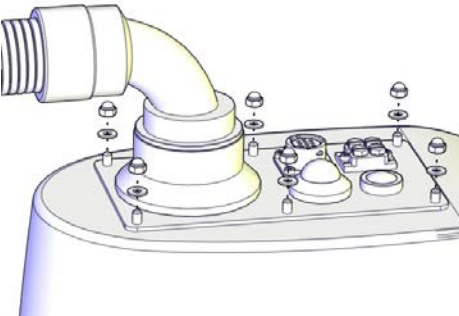

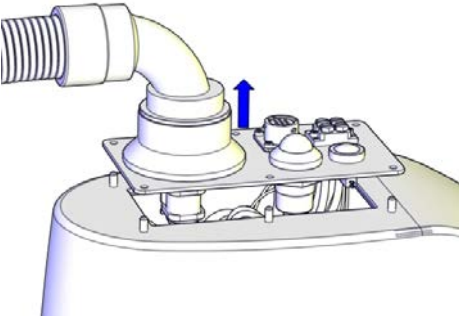
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4 Repair

4.4.2 Replacing the ball screw spline unit


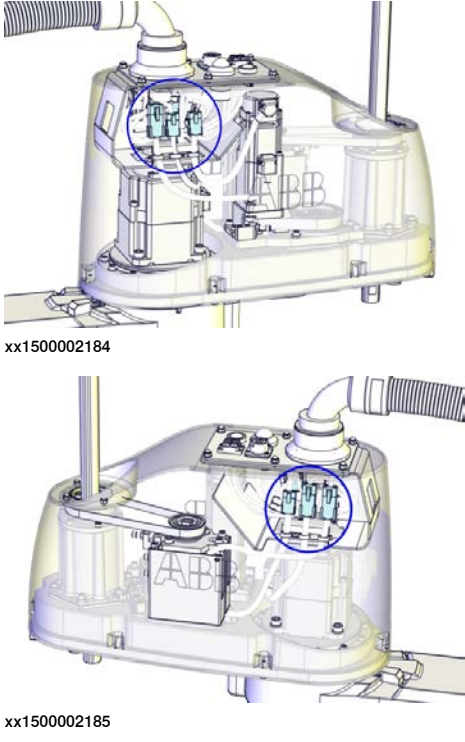
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Removing the main cable package from the upper arm



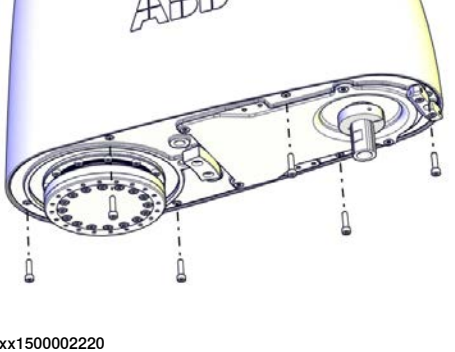
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the dome nuts and washers.	 <p>xx1500002182</p>
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 <p>xx1500002183</p>

Continues on next page

4.4.2 Replacing the ball screw spline unit
Continued

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002184</p> <p>xx1500002185</p>

Removing the upper cover


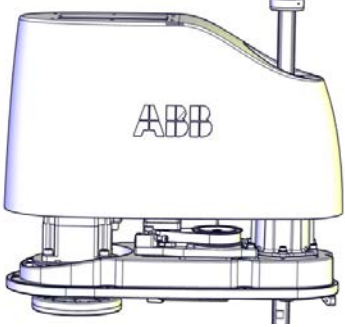
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	 <p>xx1500002220</p>

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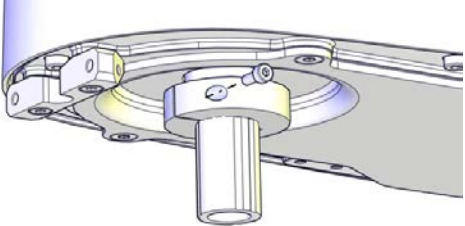
4 Repair

4.4.2 Replacing the ball screw spline unit

Continued

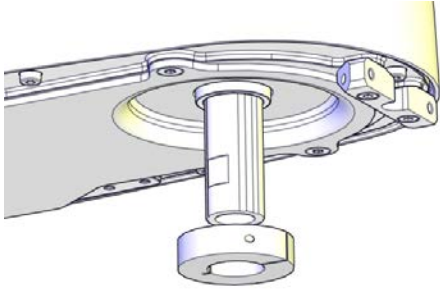
	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 xx1500002221

Removing the lower stop block


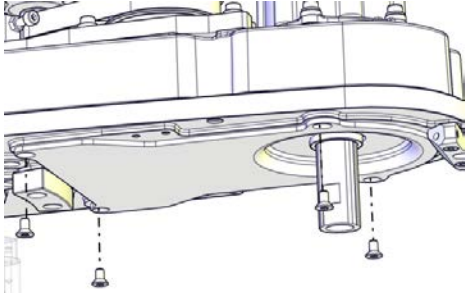

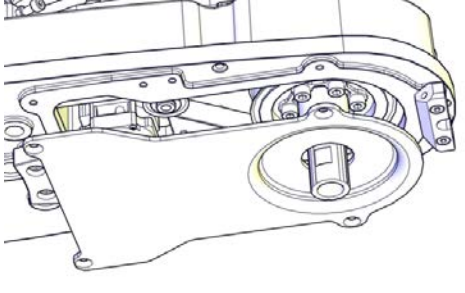
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the lower stop block of ball screw spline unit to replace: <ul style="list-style-type: none">• lower cover of the upper arm• ball screw spine unit• upper arm body	
3	Remove the screws.	 xx1500002222

Continues on next page

4.4.2 Replacing the ball screw spline unit
Continued

	Action	Note
4	Remove the stop block.	 <p>xx1500002223</p>

Removing the lower cover

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws.	 <p>xx1500002785</p>
3	<p>Remove the cover.</p>  <p>Tip</p> <p>If only working with lower axis-4 timing belt, no need to remove the stop block of ball screw spline unit before removing the lower cover.</p>	 <p>xx1500002225</p>



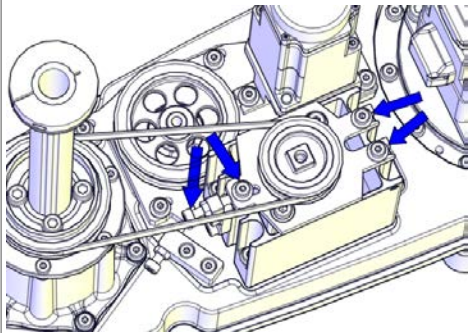
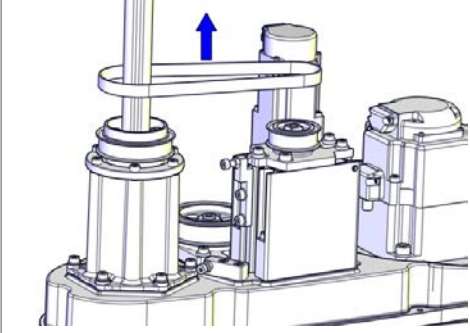
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4 Repair



4.4.2 Replacing the ball screw spline unit

Continued

Removing the axis-3 timing belt

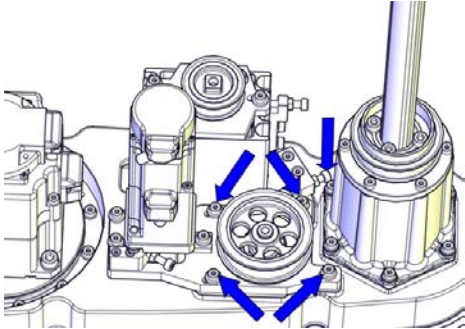
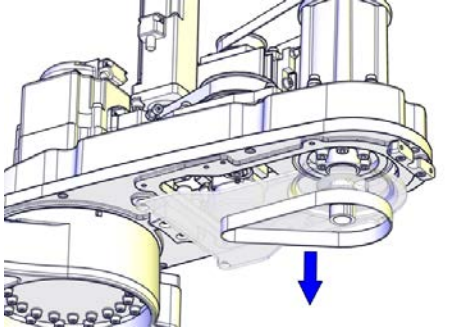
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-3 drive unit upwards to slacken the timing belt.	 <small>xx1500002229</small>
4	Remove the timing belt.	 <small>xx1500002230</small>

Removing the lower axis-4 timing belt


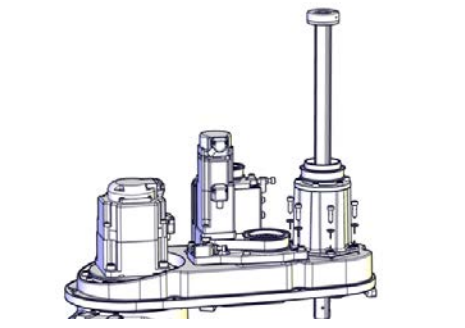
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	

Continues on next page

4.4.2 Replacing the ball screw spline unit
Continued

	Action	Note
3	Loosen the screws and move the axis-4 housing sideways to slacken the lower axis-4 timing belt.	 <p>xx1500002231</p>
4	Remove the timing belt.	 <p>xx1500002232</p>

Removing the ball screw spline

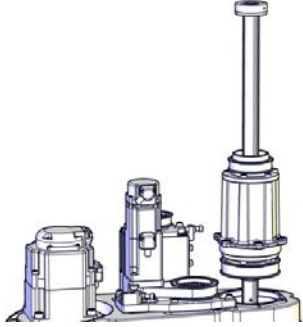
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws.	 <p>xx1500002788</p>

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4 Repair

4.4.2 Replacing the ball screw spline unit

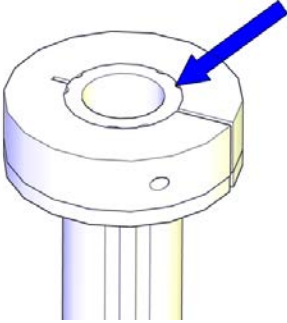
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	Action	Note
3	Remove the ball screw spline unit.	 <p>xx1500002787</p>

Refitting the ball screw spline unit

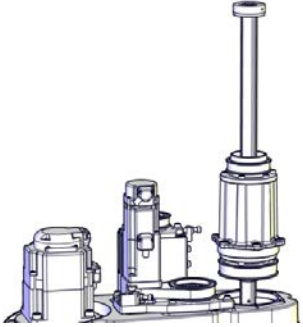
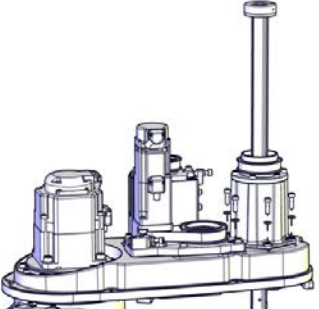
Use these procedures to refit the ball screw spline unit.

Refitting the ball screw spline unit

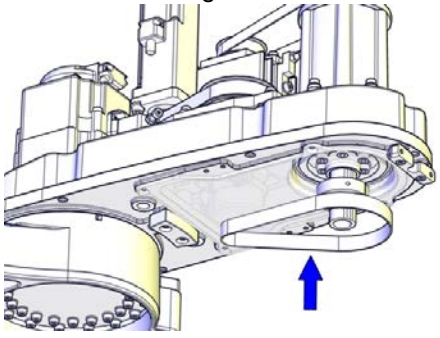
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the ball screw spline unit is well-lubricated and undamaged. 	See Lubricating the ball screw spline unit on page 111 .
2	If a new ball screw spline unit is used, remove the lower stop block to enable fitting of the lower cover.	See "Removing the lower stop block" in Removing the ball screw spline unit on page 231 .
3	Check the upper stop block of the ball screw spline unit. Replace if damaged. Make sure the upper surfaces of the shaft and stop block are at the same level.	Upper axis-3 and axis-4 mechanical stop block: 3HAC061259-001  <p>xx1600002115</p>

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4.4.2 Replacing the ball screw spline unit
Continued

	Action	Note
4	Refit the ball screw spline unit.	Ball screw spline unit: 3HAC056148-001  xx1500002787
5	Secure with screws and washers.	 xx1500002788 Screw: M4x16 (6 pcs) Tightening torque: 4.5 Nm Washer: M4 (6 pcs)

Refitting the lower axis-4 timing belt

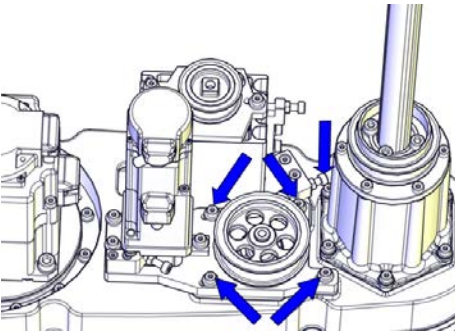
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Refit lower axis-4 timing belt. Ensure that the belt runs correctly in the grooves.	Lower axis-4 timing belt: 3HAC055201-001  xx1500002786

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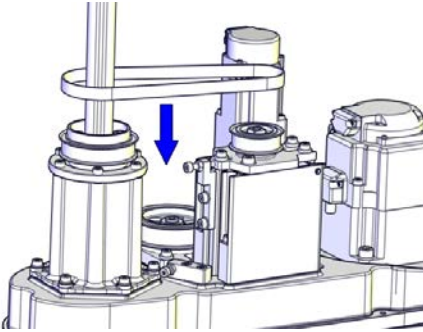
4 Repair

4.4.2 Replacing the ball screw spline unit

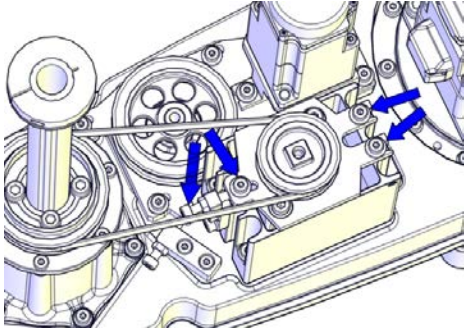
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	Action	Note
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p data-bbox="943 645 1050 667">xx1500002231</p> <p data-bbox="943 680 1390 712">Belt tension: $F = 101\text{ N}$ (Recommended)</p> <p data-bbox="943 719 1155 750">Belt tension range:</p> <p data-bbox="943 757 1406 831">64.5 N to 73.7 N (for used timing belt, which has been installed and used for more than 24 hours)</p> <p data-bbox="943 837 1342 869">92.2 N to 101 N (for new timing belt)</p>

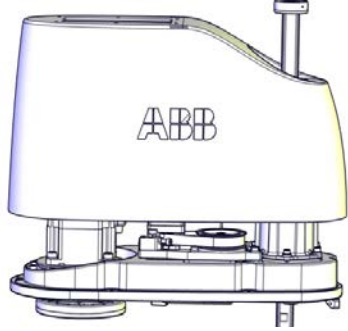

Refitting the axis-3 timing belt

	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Refit axis-3 timing belt. Ensure that the belt runs correctly in the grooves.	Axis-3 timing belt: 3HAC055209-001  <p data-bbox="943 1520 1050 1543">xx1500002789</p>

Continues on next page

	Action	Note
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p data-bbox="970 645 1082 663">xx1500002229</p> <p data-bbox="970 680 1406 707">Belt tension: $F = 34\text{ N}$ (Recommended)</p> <p data-bbox="970 714 1182 741">Belt tension range:</p> <p data-bbox="970 748 1437 831">21.8 N to 24.9 N (for used timing belt, which has been installed and used for more than 24 hours)</p> <p data-bbox="970 837 1358 864">31.1 to 34.2 N (for new timing belt)</p>

Refitting the upper cover

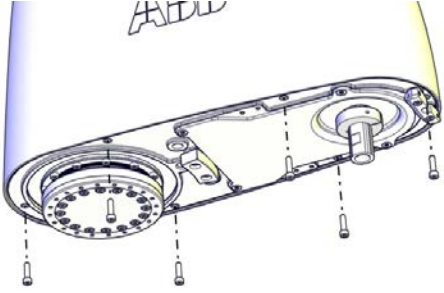
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	<p data-bbox="970 994 1366 1021">Upper cover unit: 3HAC057615-001</p>  <p data-bbox="970 1361 1082 1379">xx1500002221</p>
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	

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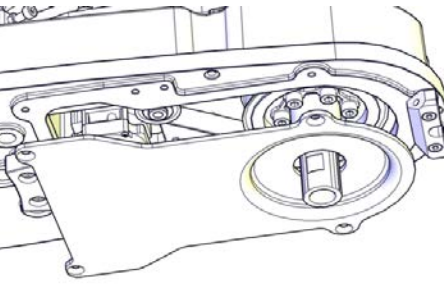
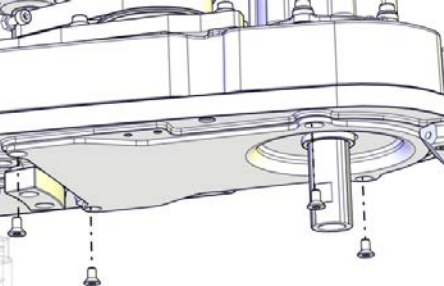
4 Repair

4.4.2 Replacing the ball screw spline unit

Continued

	Action	Note
3	Refit the cover.	 <p data-bbox="948 645 1050 667">xx1500002220</p> <p data-bbox="948 680 1182 712">Screw: M4x16 (6 pcs)</p> <p data-bbox="948 714 1209 745">Tightening torque: 2 Nm</p>

Refitting the lower cover

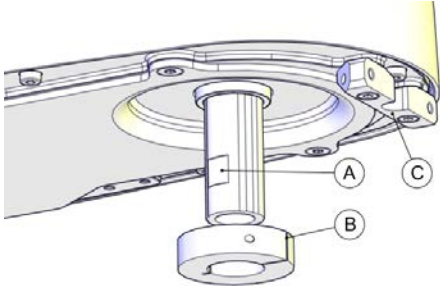
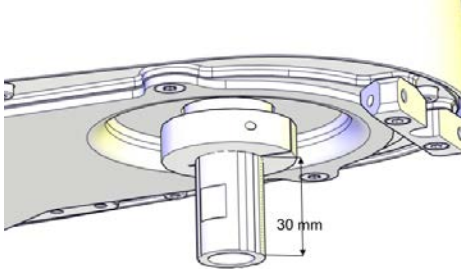
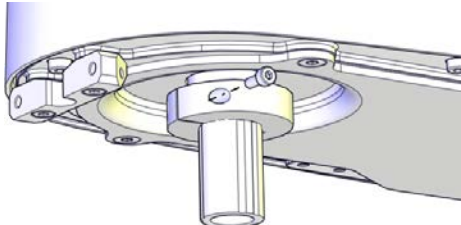

	Action	Note
1	Refit the cover.	 <p data-bbox="948 875 1286 907">Lower cover: 3HAC060106-001</p> <p data-bbox="948 1238 1050 1261">xx1500002225</p>
2	Secure with screws.	 <p data-bbox="948 1626 1050 1648">xx1500002785</p> <p data-bbox="948 1662 1166 1693">Screw: M4x8 (4 pcs)</p> <p data-bbox="948 1695 1209 1727">Tightening torque: 2 Nm</p>

Refitting the lower stop block

	Action	Note
1	Check the lower stop block of the ball screw spline unit. Replace if damaged.	Lower axis-3 and axis-4 mechanical stop block: 3HAC055208-001

Continues on next page

4.4.2 Replacing the ball screw spline unit
Continued

	Action	Note						
2	<p>Refit the lower stop block.</p> <p>Make the notch point to the calibration block and 90° away from the flat mark on the shaft.</p> <p>Make sure the distance between the lower surfaces of stop block and shaft is 30 mm.</p>	 <p>xx1500002908</p> <table border="1" data-bbox="970 683 1433 817"> <tr> <td>A</td> <td>Flat mark on the shaft</td> </tr> <tr> <td>B</td> <td>Notch</td> </tr> <tr> <td>C</td> <td>Calibration block</td> </tr> </table>  <p>xx1500002224</p>	A	Flat mark on the shaft	B	Notch	C	Calibration block
A	Flat mark on the shaft							
B	Notch							
C	Calibration block							
3	<p>Secure with the screw.</p>	 <p>xx1500002222</p> <p>Screw: M5x8 (1 pcs) Tightening torque: 10 Nm</p> <p> Note Only use specified screws, never replace them with other screws.</p>						

Refitting the main cable to the upper arm

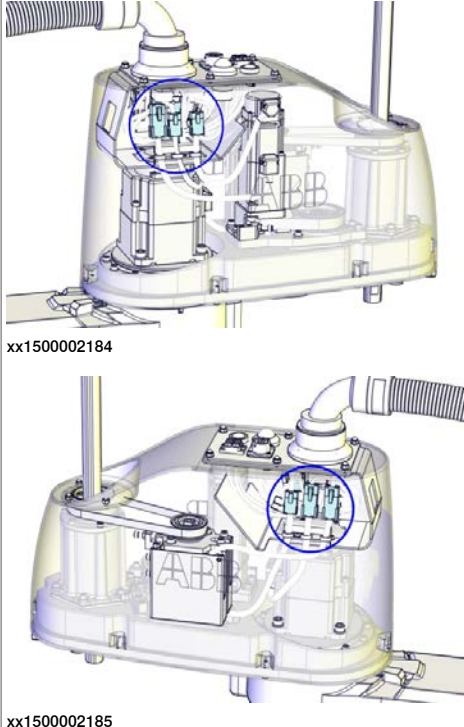
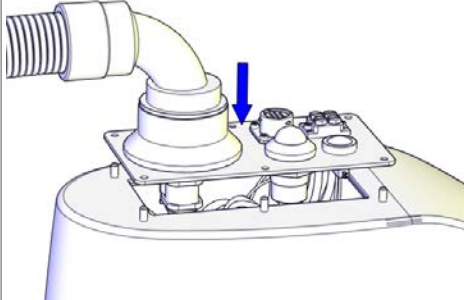
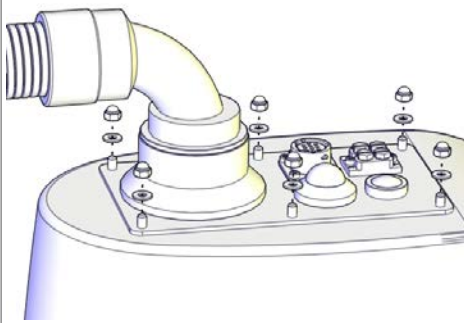
	Action	Note
1	<p>Secure the main cable package with cable ties if needed.</p>	

Continues on next page

4 Repair


4.4.2 Replacing the ball screw spline unit

Continued

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none">• R2.MP2• R2.MP3• R2.MP4• R2.ME2• R2.ME3• R2.ME4	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>

Continues on next page

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

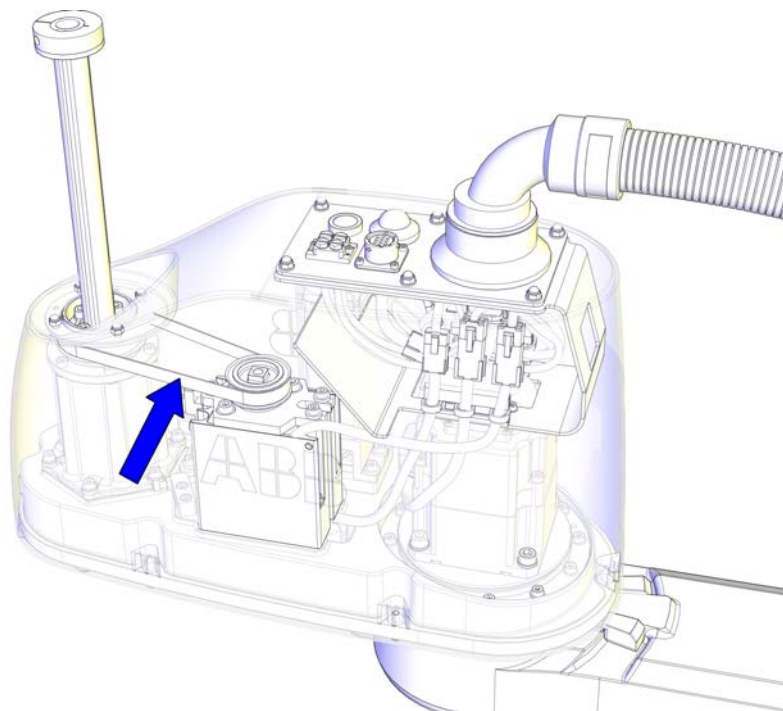
4 Repair

4.4.3 Replacing the axis-3 timing belt

4.4.3 Replacing the axis-3 timing belt

Location of the axis-3 timing belt

The axis-3 timing belt is located as shown in the figure.



xx1500002218

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-3 timing belt	3HAC055209-001	
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.

Required tools and equipment



Note

The spare part numbers that are listed in the table can be out of date. See the latest revision of *Product manual, spare parts - IRB 910SC* on ABB Library.

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4.4.3 Replacing the axis-3 timing belt

Continued

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	-	Used for measuring the timing belt tension.
Dynamometer	-	Used for measuring the timing belt tension.

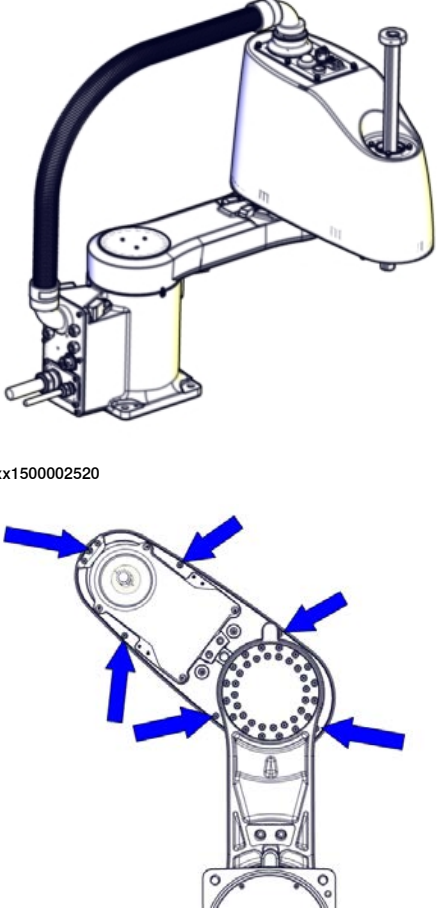
Required consumables

Consumable	Article number	Note
Cable ties	-	

Removing the axis-3 timing belt

Use these procedures to remove the axis-3 timing belt.

Preparations before removing the axis-3 timing belt


Action	Note
1 Jog axis 2 to access the cover screws.	 <p>xx1500002520</p> <p>xx1500002782</p>

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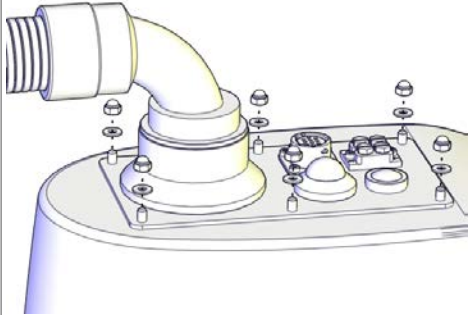

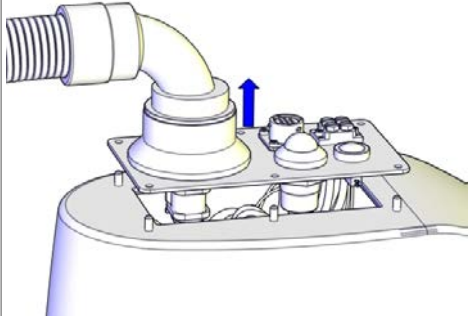
4 Repair

4.4.3 Replacing the axis-3 timing belt


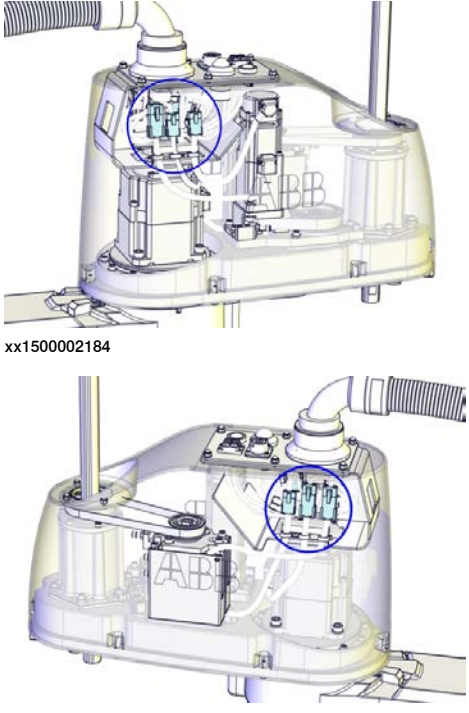
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	Action	Note
2	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	



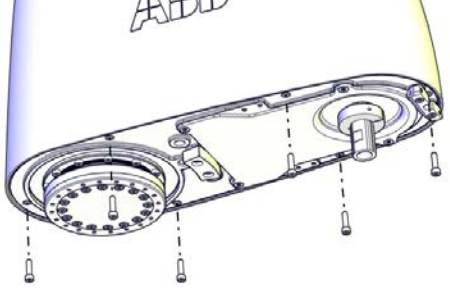
Removing the main cable package from the upper arm

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the dome nuts and washers.	 xx1500002182
3	Carefully open the user interface plate and pull out the cable package.  CAUTION The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.	 xx1500002183

Continues on next page

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	

Removing the upper cover


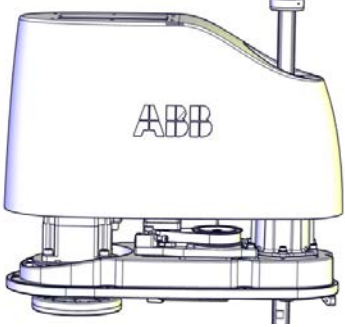
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	

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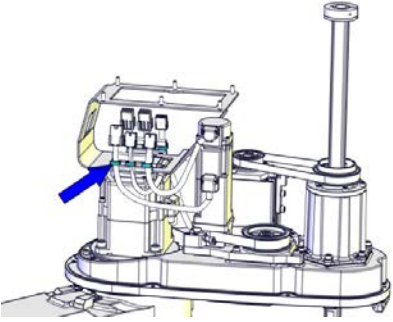
4 Repair

4.4.3 Replacing the axis-3 timing belt


Continued

	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 <small>xx1500002221</small>


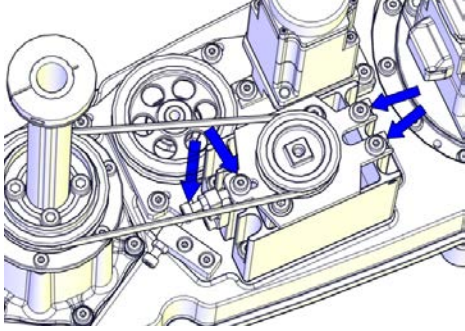
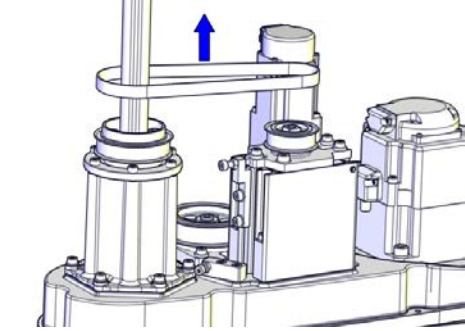
Removing the drive unit cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Cut the cable ties. Be careful not to damage the cabling.  Tip Take photos of the cable position before removing them, to have as a reference when refitting.	 <small>xx1500002226</small>

Removing the axis-3 timing belt

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

	Action	Note
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-3 drive unit upwards to slacken the timing belt.	 <p>xx1500002229</p>
4	Remove the timing belt.	 <p>xx1500002230</p>

Refitting the axis-3 timing belt

Use these procedures to refit the axis-3 timing belt.

Refitting the axis-3 timing belt

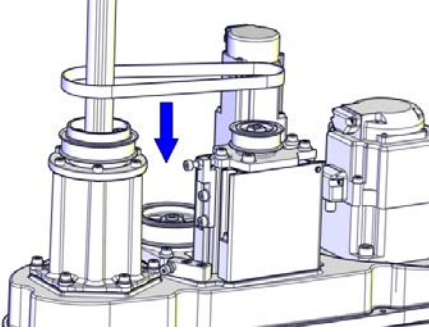
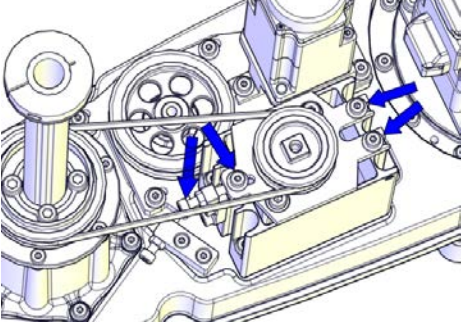
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	

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4 Repair

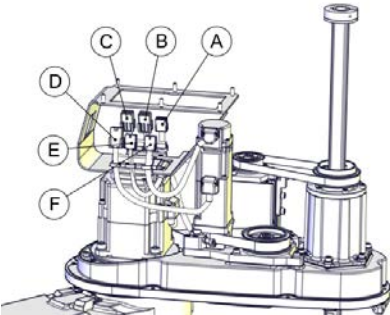
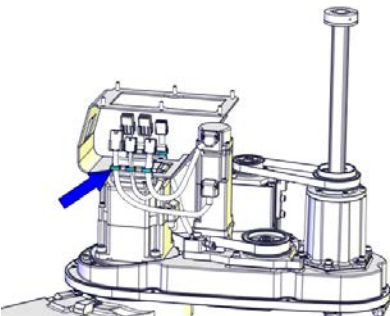
4.4.3 Replacing the axis-3 timing belt

Continued


	Action	Note
2	Refit axis-3 timing belt. Ensure that the belt runs correctly in the grooves.	<p data-bbox="943 315 1337 342">Axis-3 timing belt: 3HAC055209-001</p>  <p data-bbox="943 680 1050 696">xx1500002789</p>
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p data-bbox="943 1070 1050 1086">xx1500002229</p> <p data-bbox="943 1104 1374 1131">Belt tension: $F = 34 \text{ N}$ (Recommended)</p> <p data-bbox="943 1137 1155 1164">Belt tension range:</p> <p data-bbox="943 1171 1406 1249">21.8 N to 24.9 N (for used timing belt, which has been installed and used for more than 24 hours)</p> <p data-bbox="943 1256 1326 1283">31.1 to 34.2 N (for new timing belt)</p>

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Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p>xx150003063</p> <table border="1" data-bbox="973 728 1433 1003"> <tr> <td>A</td> <td>R2.ME3</td> </tr> <tr> <td>B</td> <td>R2.MP2</td> </tr> <tr> <td>C</td> <td>R2.MP3</td> </tr> <tr> <td>D</td> <td>R2.MP4</td> </tr> <tr> <td>E</td> <td>R2.ME2</td> </tr> <tr> <td>F</td> <td>R2. ME4</td> </tr> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p>xx150002226</p>												

Refitting the upper cover


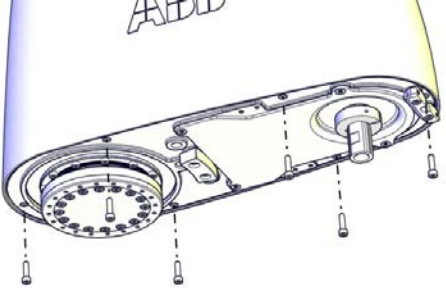
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	<p>Upper cover unit: 3HAC057615-001</p>  <p>xx150002221</p>

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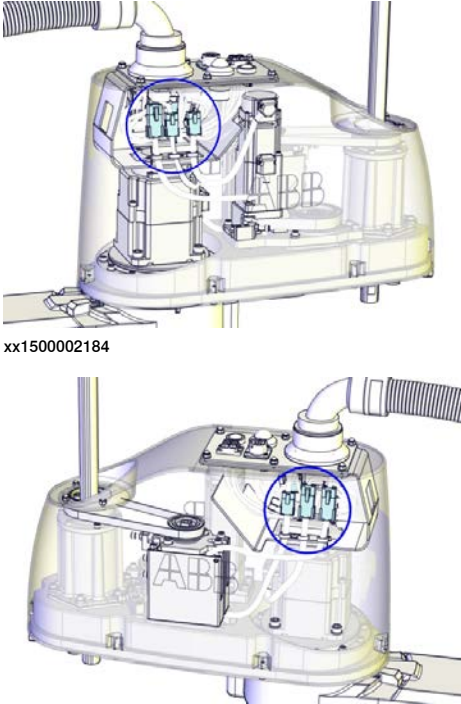
4 Repair

4.4.3 Replacing the axis-3 timing belt

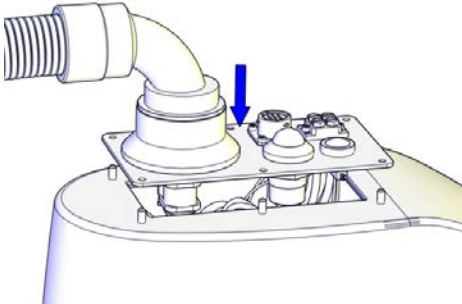
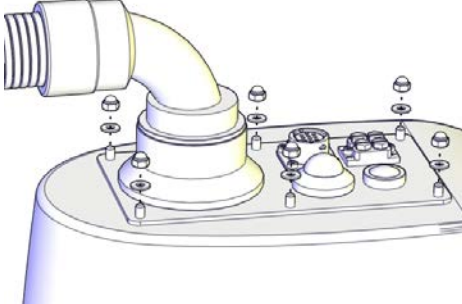
Continued

	Action	Note
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <p data-bbox="943 884 1050 902">xx1500002220</p> <p data-bbox="943 920 1182 947">Screw: M4x16 (6 pcs)</p> <p data-bbox="943 954 1214 981">Tightening torque: 2 Nm</p>


Refitting the main cable to the upper arm

	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p data-bbox="943 1514 1050 1532">xx1500002184</p> <p data-bbox="943 1888 1050 1906">xx1500002185</p>

Continues on next page

	Action	Note
3	Push the main cable package into place.	 <p>xx1500002207</p>
4	Refit the user interface plate.	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

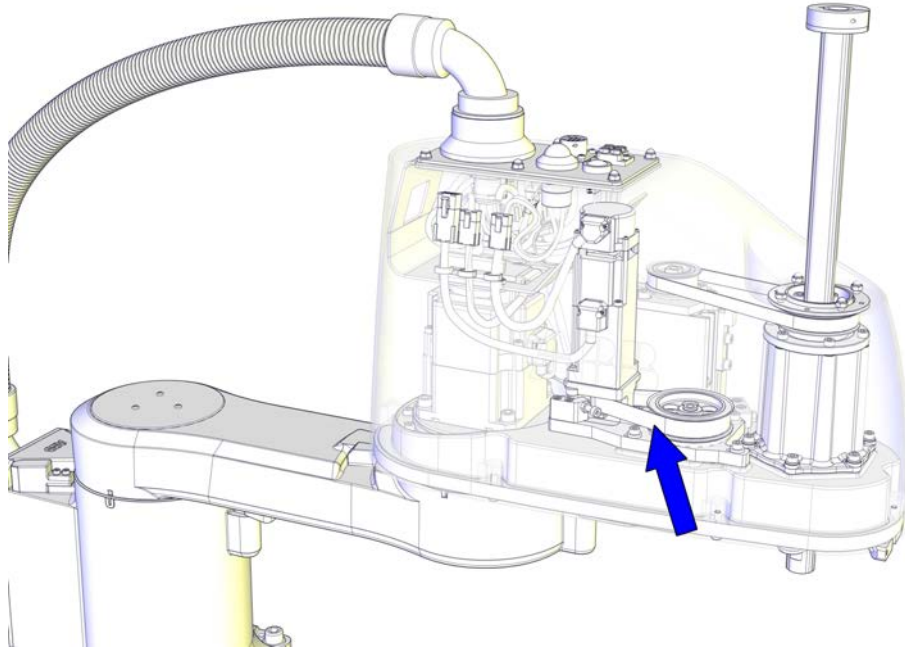
4 Repair

4.4.4 Replacing the axis-4 timing belts

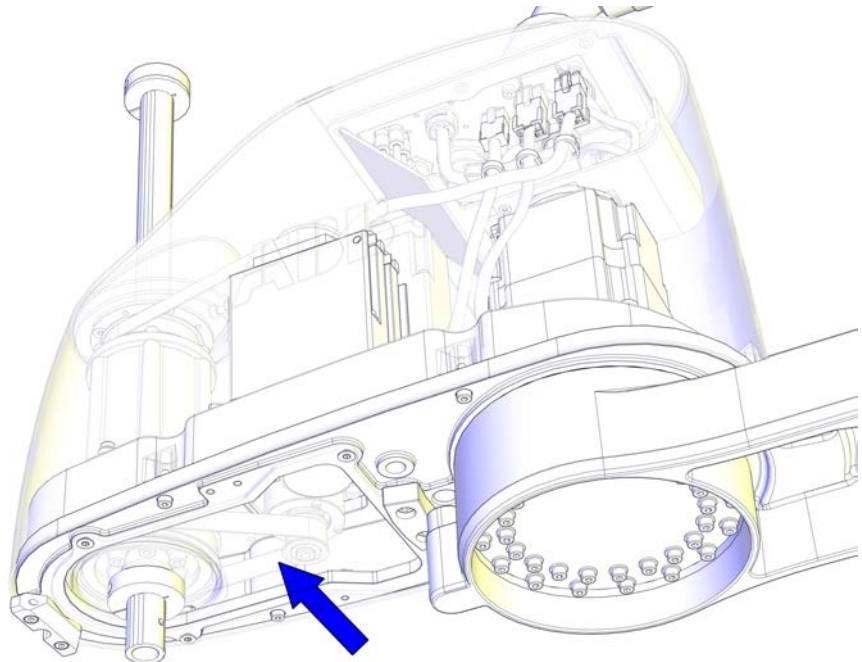
4.4.4 Replacing the axis-4 timing belts

Location of the axis-4 timing belts

The axis-4 timing belts are located as shown in the figures.



xx1500002216



xx1500002217

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Required spare parts

**Note**

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Upper axis-4 timing belt	3HAC055206-001	
Lower axis-4 timing belt	3HAC055201-001	
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.
Plain washer	3HAC056937-001	Replace if damaged.

Required tools and equipment

**Note**

The spare part numbers that are listed in the table can be out of date. See the latest revision of *Product manual, spare parts - IRB 910SC* on ABB Library.

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	-	Used for measuring the timing belt tension.
Dynamometer	-	Used for measuring the timing belt tension.

Required consumables

Consumable	Article number	Note
Cable ties	-	

Continues on next page

4 Repair

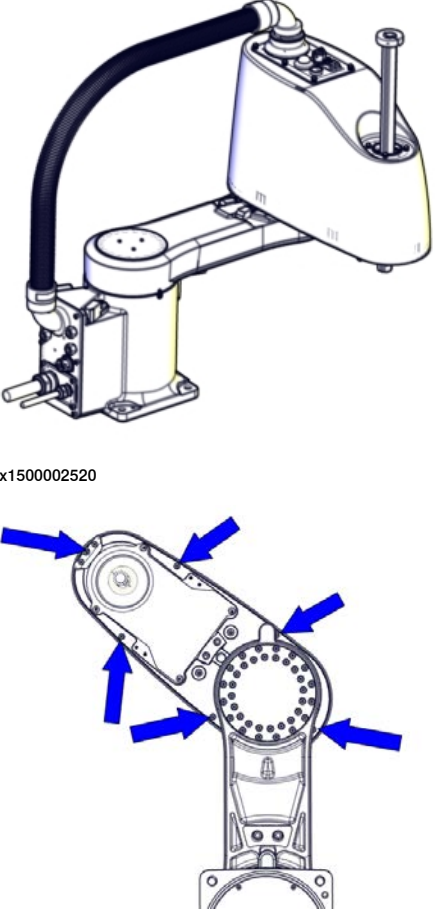

4.4.4 Replacing the axis-4 timing belts

Continued

Removing the axis-4 timing belts


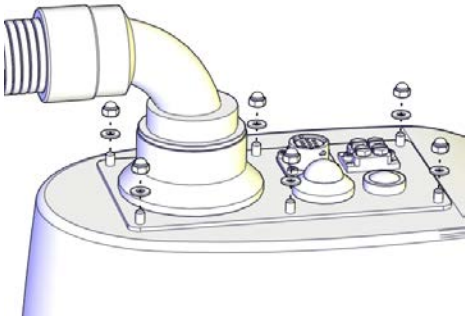

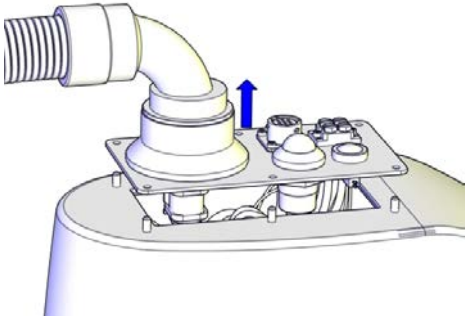
Use these procedures to remove the axis-4 timing belts.

Preparations before removing the axis-4 timing belts

	Action	Note
1	Jog axis 2 to access the cover screws.	 <p data-bbox="943 954 1050 972">xx1500002520</p> <p data-bbox="943 1406 1050 1424">xx1500002782</p>
2	 DANGER Turn off all: <ul data-bbox="501 1585 831 1682" style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	

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Removing the main cable package from the upper arm


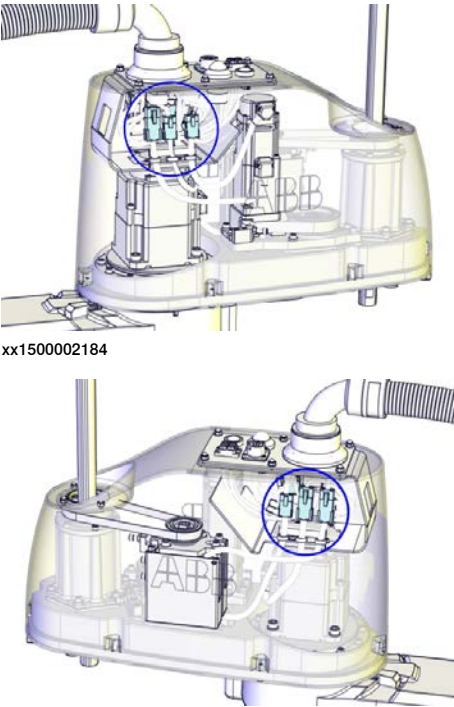
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the dome nuts and washers.</p>	 <p>xx1500002182</p>
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 <p>xx1500002183</p>

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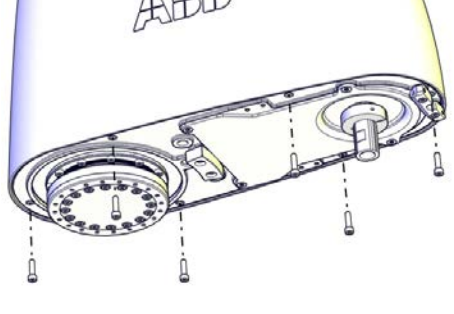
4 Repair

4.4.4 Replacing the axis-4 timing belts


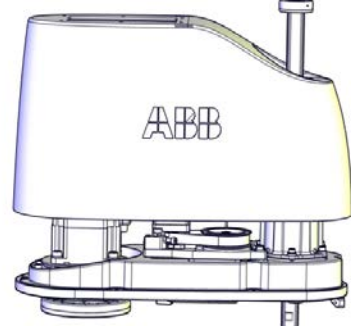
Continued

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002184</p> <p>xx1500002185</p>



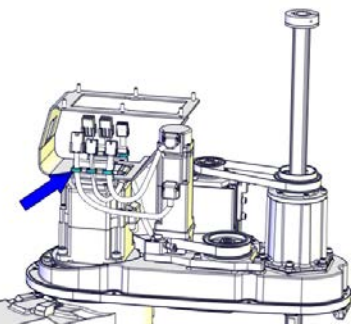
Removing the upper cover

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	 <p>xx1500002220</p>


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	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 <p>xx1500002221</p>

Removing the drive unit cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Cut the cable ties. Be careful not to damage the cabling.  Tip Take photos of the cable position before removing them, to have as a reference when refitting.	 <p>xx1500002226</p>

Removing the lower cover

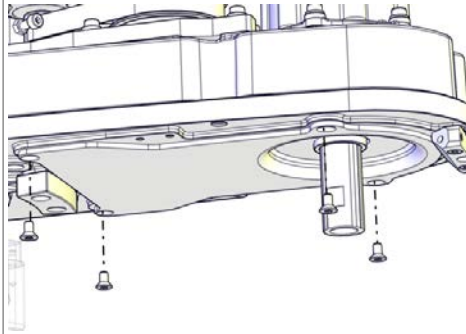

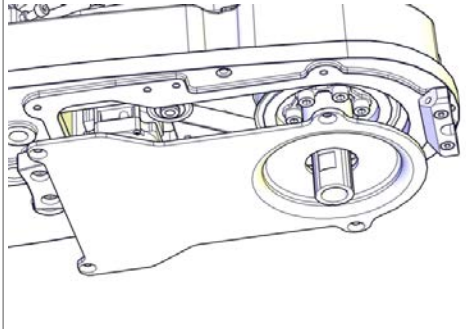
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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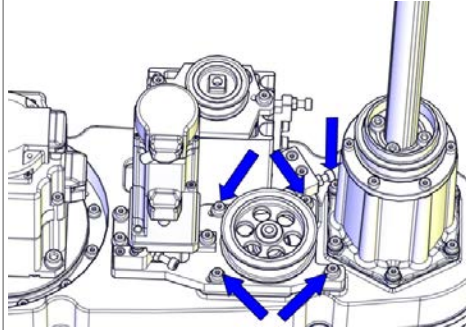
4 Repair

4.4.4 Replacing the axis-4 timing belts

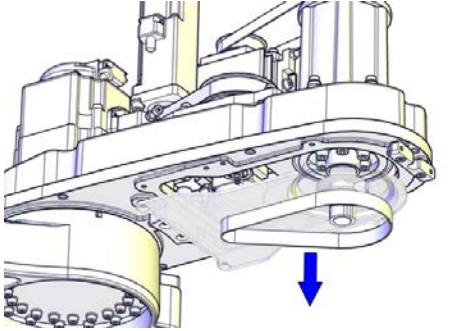
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	Action	Note
2	Remove the screws.	 <p>xx1500002785</p>
3	Remove the cover.  Tip If only working with lower axis-4 timing belt, no need to remove the stop block of ball screw spline unit before removing the lower cover.	 <p>xx1500002225</p>



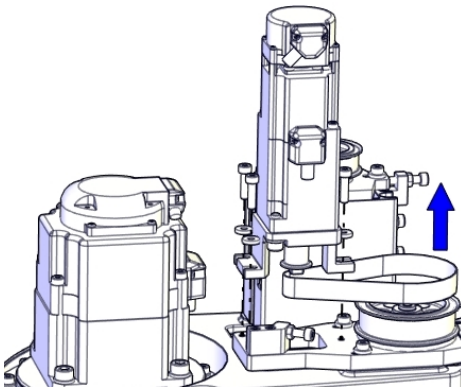
Removing the lower axis-4 timing belt

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-4 housing sideways to slacken the lower axis-4 timing belt.	 <p>xx1500002231</p>

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	Action	Note
4	Remove the timing belt.	 <p>xx1500002232</p>

Removing the axis-4 drive unit and upper timing belt

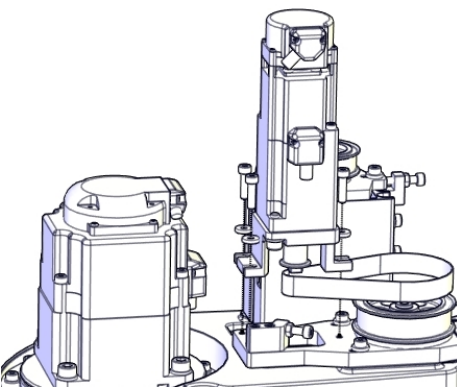
	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	 <p>WARNING</p> <p>Risk of tipping. Make sure the gravity center is well supported.</p>	
3	Loosen the screws and move the axis-4 drive unit upwards to slacken the upper axis-4 timing belt.	 <p>xx1500002233</p>

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4 Repair

4.4.4 Replacing the axis-4 timing belts

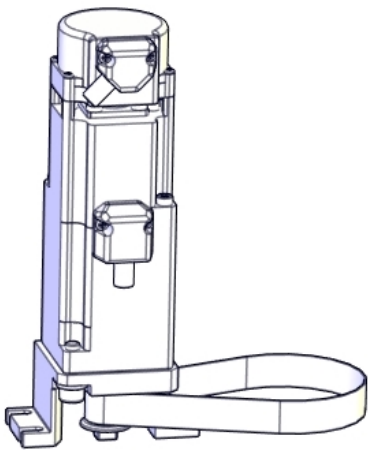
Continued

	Action	Note
4	Remove the drive unit and timing belt.	 <p>xx1500002234</p>


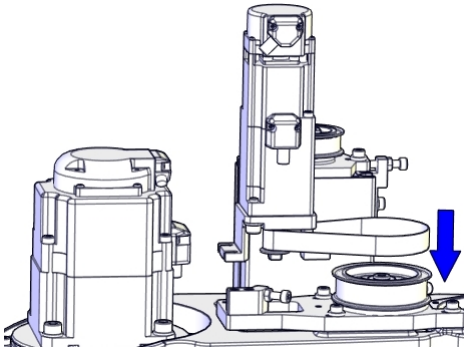
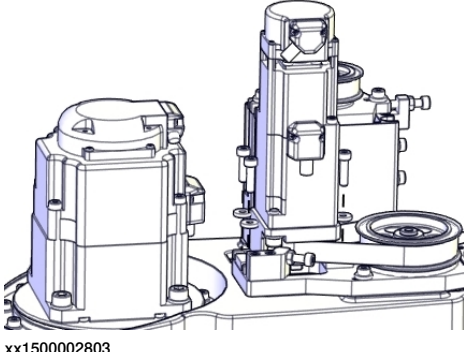

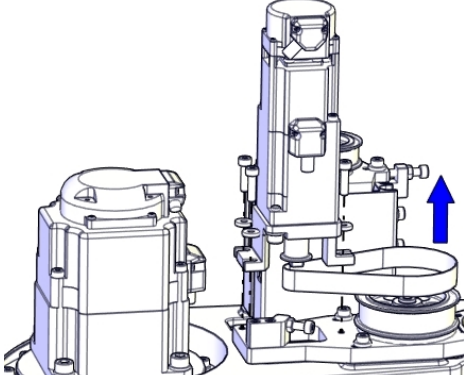
Refitting the axis-4 timing belts

Use these procedures to refit the axis-4 timing belts.

Refitting the axis-4 drive unit and upper timing belt

	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Place the timing belt.	Axis-4 drive unit: 3HAC056112-001 Upper axis-4 timing belt: 3HAC055206-001  <p>xx1500002801</p>

Continues on next page

	Action	Note
3	<p>Refit the drive unit and timing belt.</p> <p> Note</p> <p>Make sure to refit the drive unit with motor connectors pointing against axis-3 drive unit.</p>	 <p>xx1500002802</p>
4	<p>Refit screws and washers just enough to still be able to move the drive unit upwards.</p>	 <p>xx1500002803</p> <p>Screw: M4x16 (3 pcs) Washer (3HAC056937-001, 3 pcs)</p> <p> Note</p> <p>Only use specified washers, never replace them with other washers.</p>
5	<p>Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.</p>	 <p>xx1500002233</p> <p>Belt tension: $F = 37 \text{ N}$ (Recommended) Belt tension range: 24.1 N to 27.6 N (for used timing belt, which has been installed and used for more than 24 hours) 34.5 N to 37.9 N (for new timing belt)</p>

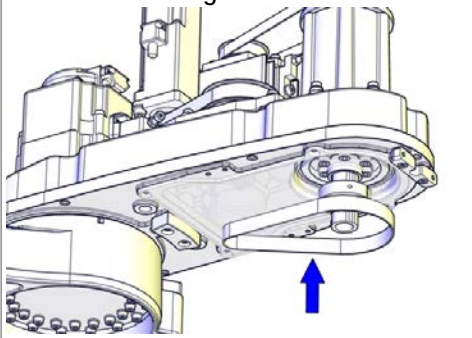
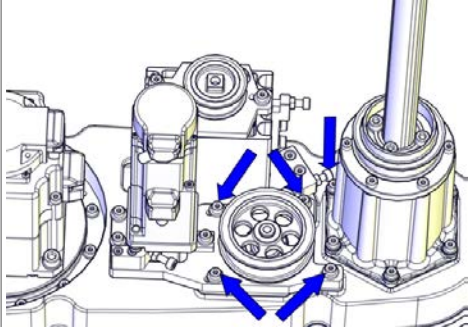
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4 Repair

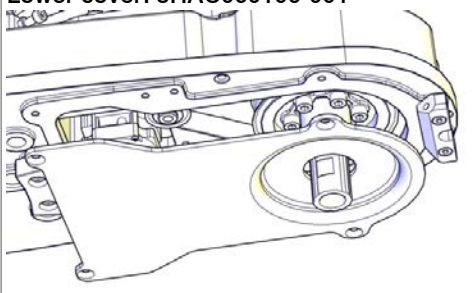
4.4.4 Replacing the axis-4 timing belts

Continued

Refitting the lower axis-4 timing belt

	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Refit lower axis-4 timing belt. Ensure that the belt runs correctly in the grooves.	Lower axis-4 timing belt: 3HAC055201-001  xx1500002786
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 xx1500002231 Belt tension: $F = 101 \text{ N}$ (Recommended) Belt tension range: 64.5 N to 73.7 N (for used timing belt, which has been installed and used for more than 24 hours) 92.2 N to 101 N (for new timing belt)

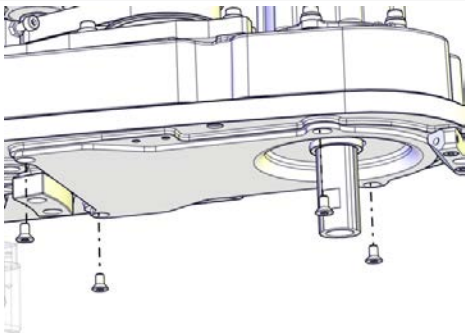
Refitting the lower cover

	Action	Note
1	Refit the cover.	Lower cover: 3HAC060106-001  xx1500002225

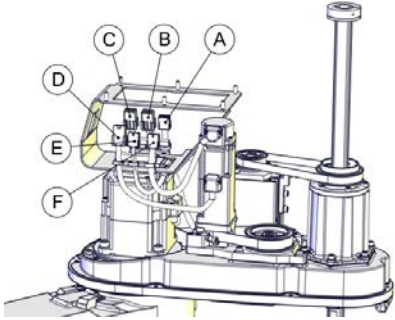
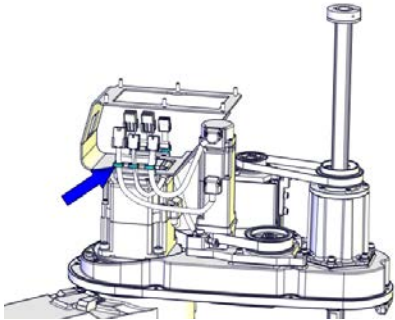
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4.4.4 Replacing the axis-4 timing belts

Continued

	Action	Note
2	Secure with screws.	 <p data-bbox="970 645 1082 667">xx1500002785</p> <p data-bbox="970 680 1198 712">Screw: M4x8 (4 pcs)</p> <p data-bbox="970 714 1241 745">Tightening torque: 2 Nm</p>

Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p data-bbox="970 1205 1082 1227">xx1500003063</p> <table border="1" data-bbox="970 1243 1437 1518"> <tbody> <tr> <td data-bbox="975 1249 1023 1281">A</td> <td data-bbox="1023 1249 1437 1281">R2.ME3</td> </tr> <tr> <td data-bbox="975 1294 1023 1326">B</td> <td data-bbox="1023 1294 1437 1326">R2.MP2</td> </tr> <tr> <td data-bbox="975 1339 1023 1370">C</td> <td data-bbox="1023 1339 1437 1370">R2.MP3</td> </tr> <tr> <td data-bbox="975 1384 1023 1415">D</td> <td data-bbox="1023 1384 1437 1415">R2.MP4</td> </tr> <tr> <td data-bbox="975 1429 1023 1460">E</td> <td data-bbox="1023 1429 1437 1460">R2.ME2</td> </tr> <tr> <td data-bbox="975 1473 1023 1505">F</td> <td data-bbox="1023 1473 1437 1505">R2. ME4</td> </tr> </tbody> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p data-bbox="970 1877 1082 1899">xx1500002226</p>												

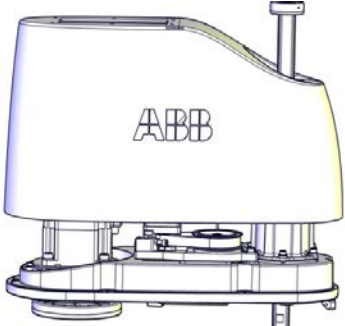

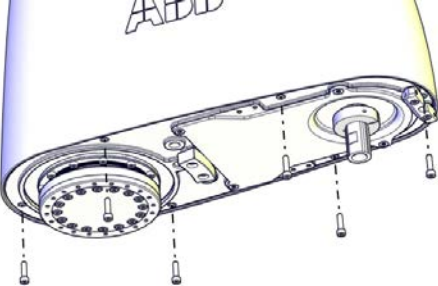
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4 Repair

4.4.4 Replacing the axis-4 timing belts

Continued

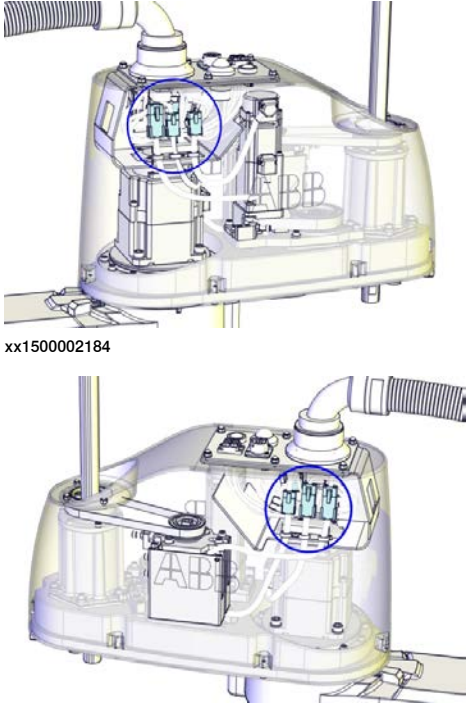
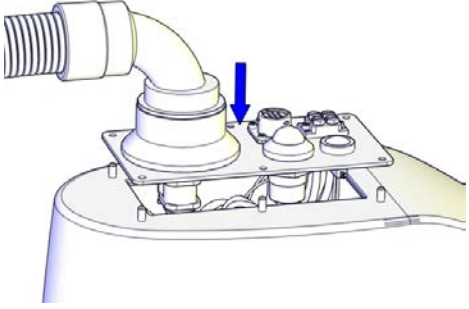
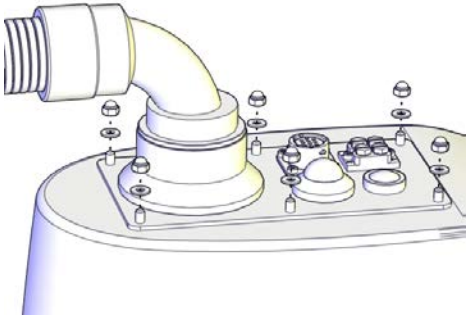
Refitting the upper cover

	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	Upper cover unit: 3HAC057615-001  <small>xx1500002221</small>
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <small>xx1500002220</small> Screw: M4x16 (6 pcs) Tightening torque: 2 Nm

Refitting the main cable to the upper arm

	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>


Continues on next page

4 Repair

4.4.4 Replacing the axis-4 timing belts

Continued

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.4.5 Replacing the axis-2 mechanical stop

General

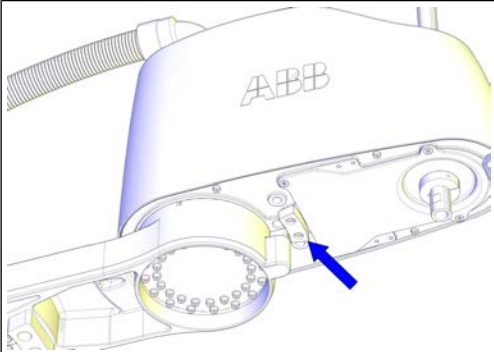
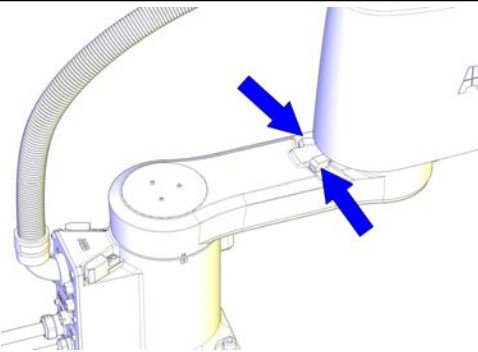


Note

If a collision with the mechanical stops occur, check and retighten all screws before any installation or service work. Replace damaged or cracked screws.

Location of the axis-2 mechanical stop

The axis-2 mechanical stop is located as shown in the figure.

Axis-2 mechanical stop block	Axis-2 mechanical stop rubber
 xx1500002175	 xx1500002174
3HAC055185-001	3HAC056017-001

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-2 mechanical stop rubber	3HAC056017-001	Replace if damaged.
Axis-2 mechanical stop block	3HAC055185-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

Required consumables

Consumable	Article number	Note
Locking liquid	3HAB7116-1	Loctite 243

Continues on next page

4 Repair

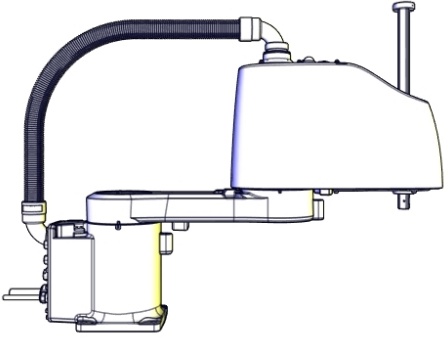

4.4.5 Replacing the axis-2 mechanical stop

Continued


Replacing the axis-2 mechanical stop

Use these procedures to replace the axis-2 mechanical stop.

Preparations before replacing the axis-2 mechanical stop

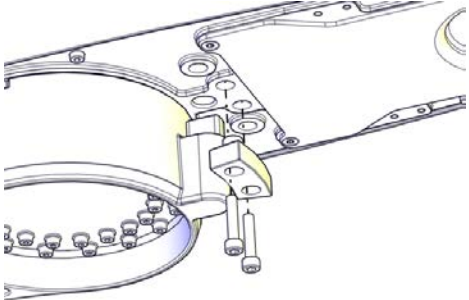

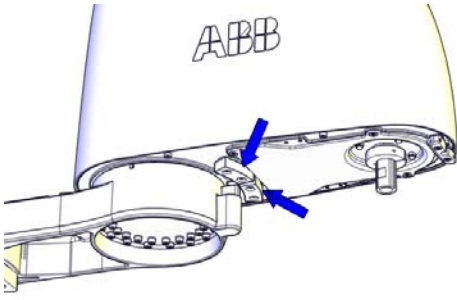
	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	

Replacing the axis-2 mechanical stop block





	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

4.4.5 Replacing the axis-2 mechanical stop
Continued

Action	Note
2 Remove the block by removing the screws.	 xx1500002245 Screw: M5x15 (2 pcs) Tightening torque: 5 Nm
3 Refit and secure the new mechanical stop block.  Tip One more mechanical stop block can be fitted to restrict the working range of axis 2, as shown in the following figure. The block and related screws are provided in accessory package.  xx1500003065	

Replacing the axis-2 mechanical stop rubbers


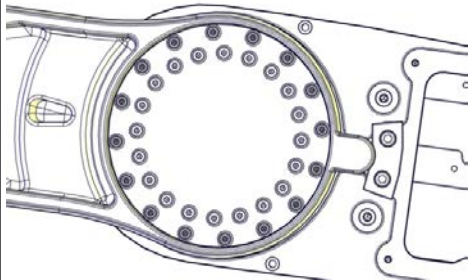
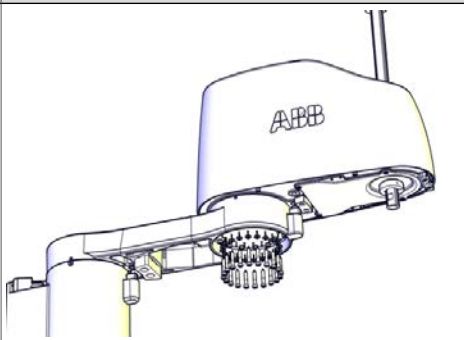
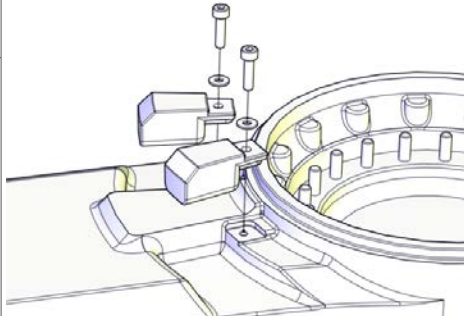
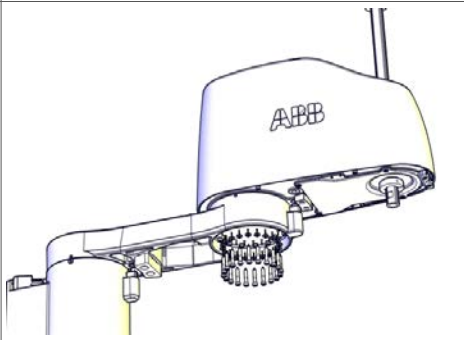
 Note Two persons working together are required to perform this procedure.	
1  DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2  WARNING The upper arm weights 13.2 kg. It may drop by the force of gravity when it is released from the lower arm. Make sure the weight of the upper arm body is properly supported.	
3  Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Remove the screws that fasten the upper arm to the lower arm.	

Continues on next page

4 Repair


4.4.5 Replacing the axis-2 mechanical stop

Continued

	Action	Note
4	<p>Remove the screws and washers.</p> <p> WARNING</p> <p>Keep the twelve screws in the outer circle fitted. They hold the axis-2 motor flange on the lower arm.</p>  <p>xx1500002257</p>	 <p>xx1500002256</p>
5	<p>Remove the upper arm and lay it on a workbench.</p>	
6	<p>Remove the rubbers by removing the screws.</p>	
7	<p>Refit and secure the new mechanical stop rubbers with screws.</p> <p>Lock screws with locking liquid (Loctite 243).</p>	 <p>xx1500002246</p> <p>Screw: M3x6 (2 pcs) Tightening torque: 0.3 Nm</p>
8	<p>Make sure the lower arm is secured. Lower the upper arm down onto the right place of the lower arm.</p>	
9	<p>Refit the upper arm screws and washers.</p>	 <p>xx1500002256</p> <p>Screw: M4x20 (16 pcs) Tightening torque: 4.5 Nm</p>

Continues on next page

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4 Repair

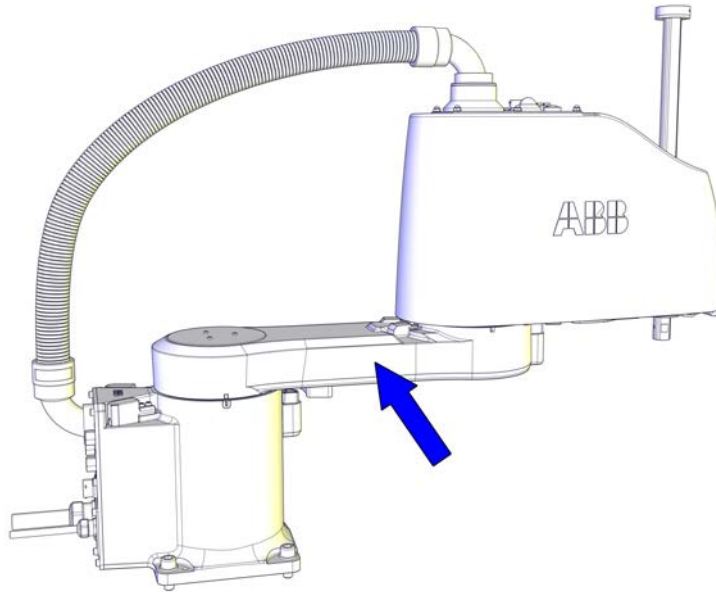
4.5.1 Replacing the lower arm

4.5 Lower arm and base

4.5.1 Replacing the lower arm

Location of the lower arm

The lower arm is located as shown in the figure.



xx1500002210

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Lower arm, 450 mm	3HAC057609-001	Used for IRB 910SC-3/0.45
Lower arm, 550 mm	3HAC057612-001	Used for IRB 910SC-3/0.55
Lower arm, 650 mm	3HAC057613-001	Used for IRB 910SC-3/0.65
Lower arm cover	3HAC056065-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

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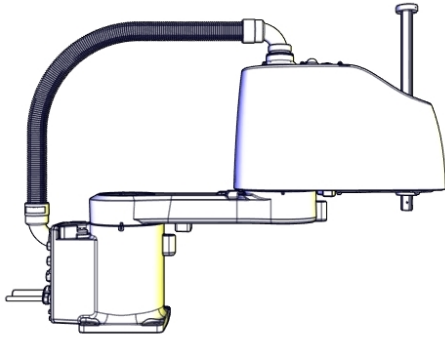

Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the lower arm

Use these procedures to remove the lower arm.

Preparations before removing the lower arm

	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the upper arm

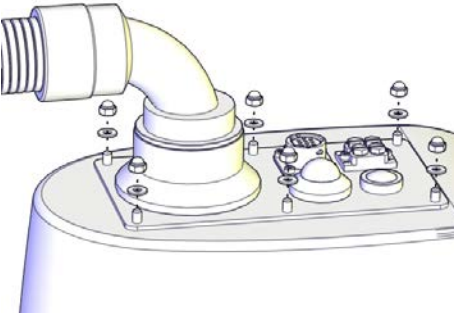

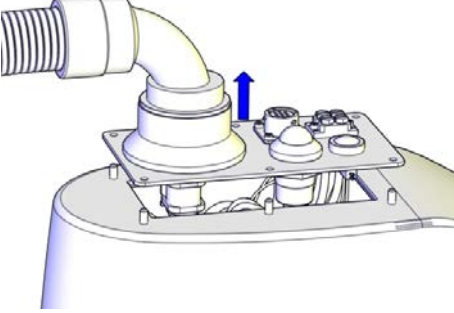

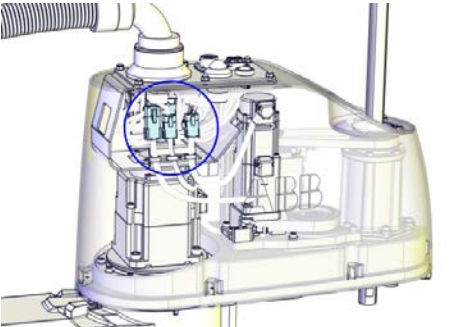
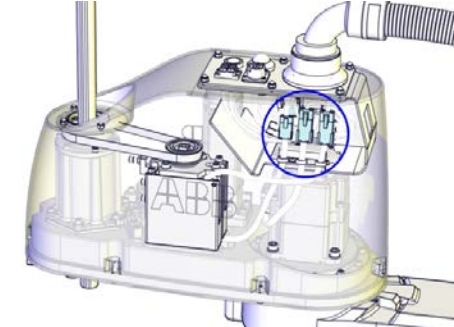
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

4 Repair

4.5.1 Replacing the lower arm

Continued

	Action	Note
2	Remove the dome nuts and washers.	 xx1500002182
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 xx1500002183
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none">• R2.MP2• R2.MP3• R2.MP4• R2.ME2• R2.ME3• R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 xx1500002184  xx1500002185





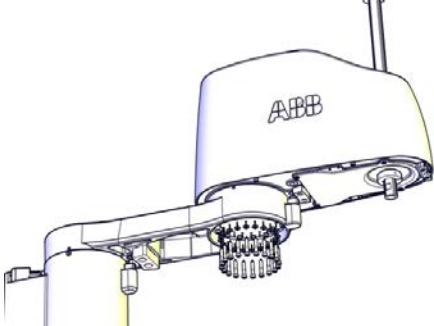
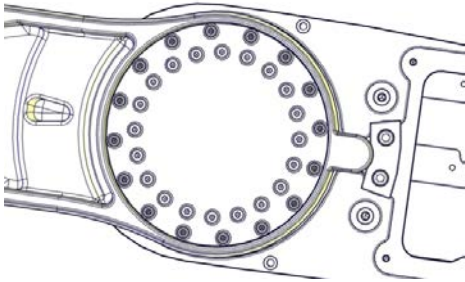
Removing the upper arm




Note

Two persons working together are required to perform this procedure.

Continues on next page

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING The upper arm weights 13.2 kg. It may drop by the force of gravity when it is released from the lower arm. Make sure the weight of the upper arm body is properly supported.	
3	 Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Remove the screws that fasten the upper arm to the lower arm.	
4	Remove the screws and washers.  WARNING Keep the twelve screws in the outer circle fitted. They hold the axis-2 motor flange on the lower arm.	 xx1500002256
5	Remove the upper arm and lay it aside on a workbench.	 xx1500002257

Removing the lower arm


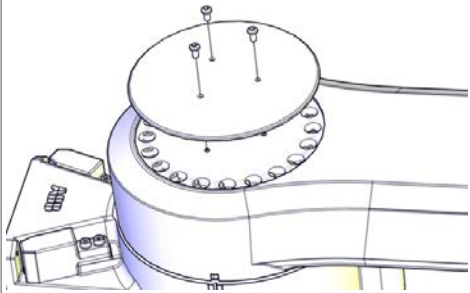

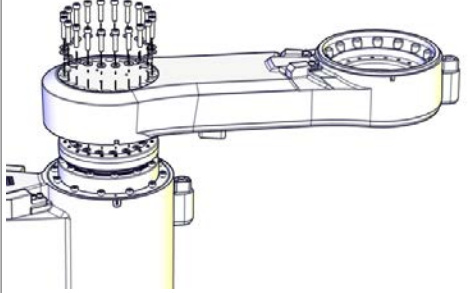
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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4 Repair

4.5.1 Replacing the lower arm

Continued

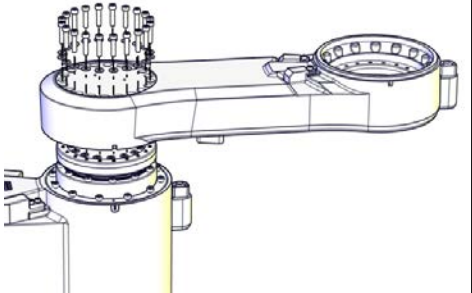
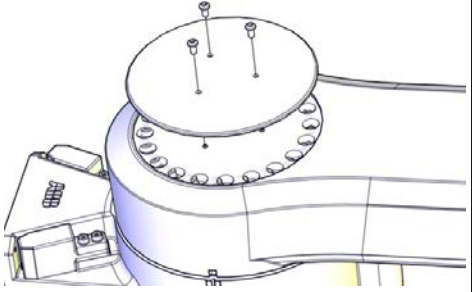
	Action	Note
2	<p>Remove the cover.</p> <p> Tip</p> <p>If the cover is hard to remove, fit a screw to its attachment hole to help press out the cover.</p>	 <p>xx1500002259</p>
3	<p> WARNING</p> <p>The lower arm weights 3.2 kg. It may drop when it is released from the base. Make sure the weight of the lower arm is properly supported.</p>	
4	Remove the screws and washers.	
5	Lay the lower arm aside on a workbench.	 <p>xx1500002260</p>

Continues on next page

Refitting the lower arm

Use these procedures to refit the lower arm.

Refitting the lower arm

	Action	Note
1	Refit the lower arm and tighten screws.	<p>Lower arm, 450 mm: 3HAC057609-001 (For IRB 910SC-3/0.45)</p> <p>Lower arm, 550 mm: 3HAC057612-001 (For IRB 910SC-3/0.65)</p> <p>Lower arm, 650 mm: 3HAC057613-001 (For IRB 910SC-3/0.65)</p>  <p>xx1500002260</p> <p>Screw: M4x20 (16 pcs) Tightening torque: 4.2 Nm Washer: 4.3x9x1.3 (16 pcs)</p>
2	Refit the cover.	<p>Lower arm cover: 3HAC056065-001</p>  <p>xx1500002259</p> <p>Screw: M3x6 (3 pcs) Tightening torque: 1 Nm</p>

Refitting the upper arm



Note


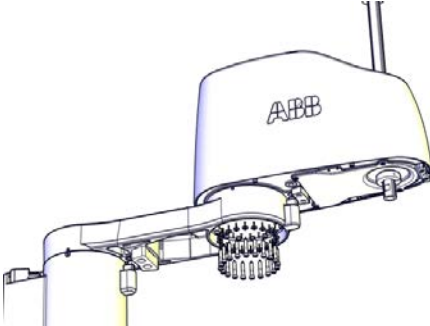
Two persons working together are required to perform this procedure.

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4 Repair

4.5.1 Replacing the lower arm

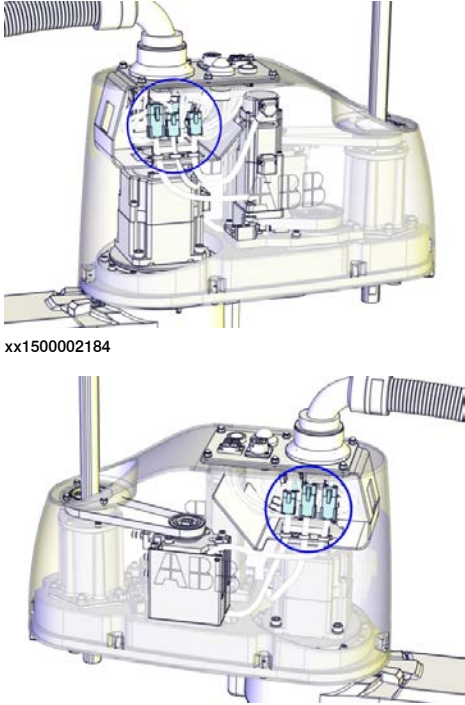
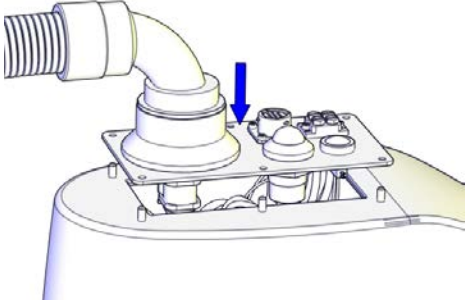
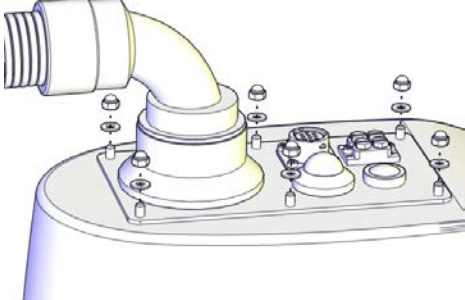
Continued

	Action	Note
1	 Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Refit the screws that fasten the upper arm to the lower arm.	
2	Make sure the lower arm is secured. Lower the upper arm down onto the right place of the lower arm.	
3	Refit the upper arm screws and washers.	 xx1500002256 Screw: M4x20 (16 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1.3 (16 pcs)

Refitting the main cable to the upper arm

	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>


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4 Repair

4.5.1 Replacing the lower arm

Continued

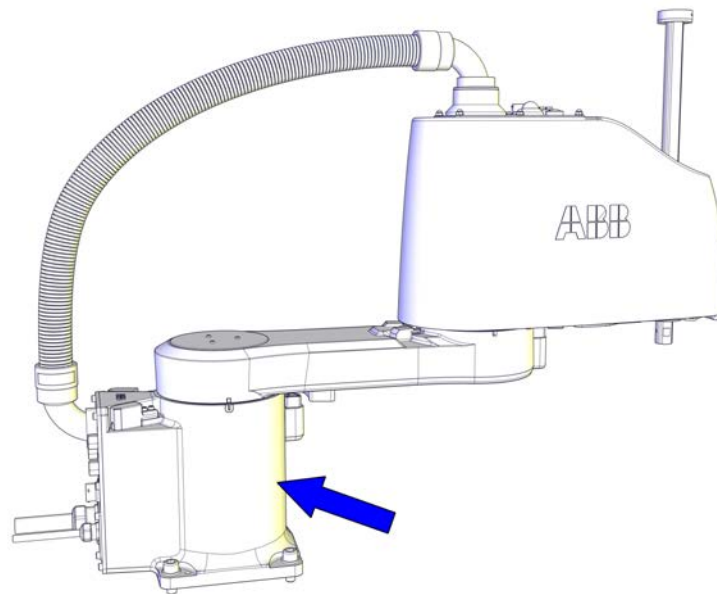
Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.5.2 Replacing the base

Location of the base

The base is located as shown in the figure.



xx1500002211

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Base	3HAC057614-001	
Base bottom cover	3HAC055216-001	Replace if damaged.
Lower arm cover	3HAC056065-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

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4 Repair

4.5.2 Replacing the base

Continued

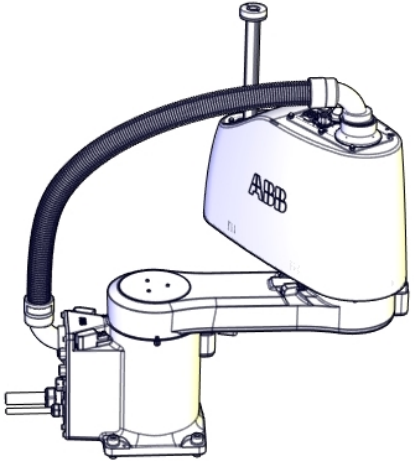

Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the cabling from the base

Use these procedures to remove the cabling from the base.

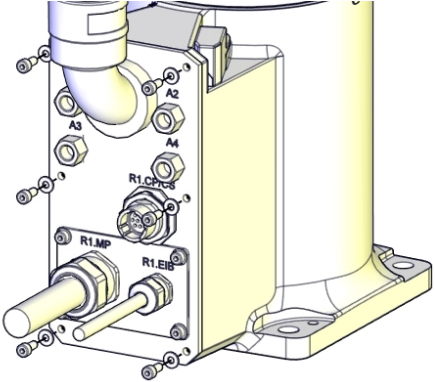


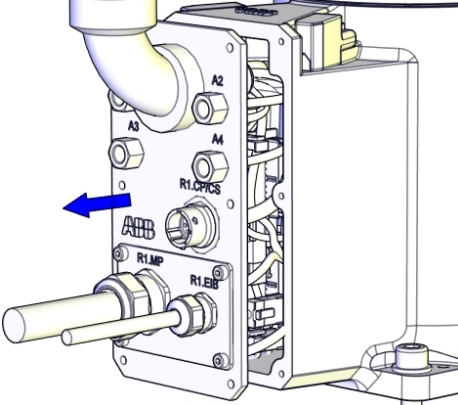

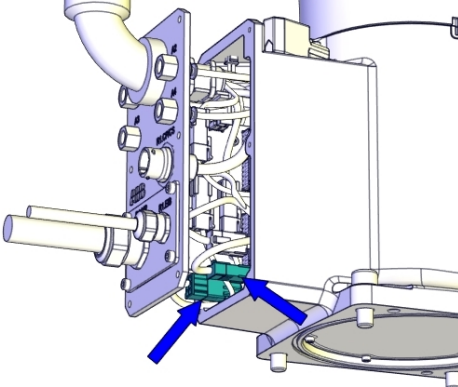
Preparations before replacing the base

	Action	Note
1	Jog axis 2 to easily support the arm system weight.	 <p>xx1500002804</p>
2	 <p>DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	

Removing the main cable package from the base

	Action	Note
1	 <p>DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

Continues on next page

	Action	Note
2	Remove the screws and washers.	 <p>xx1500002186</p>
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>

Replacing the base

Use these procedures to replace the base.

Removing the arm system



Note



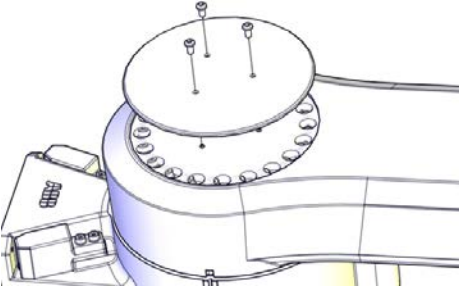



Two persons working together are required to perform this procedure.

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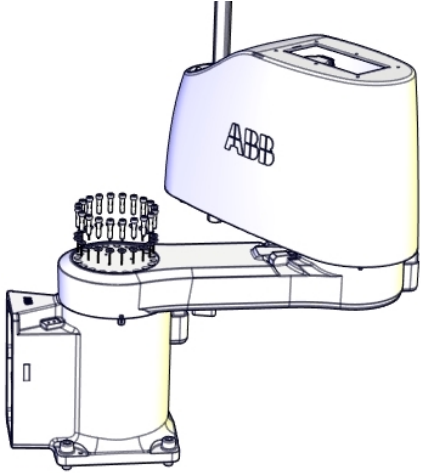
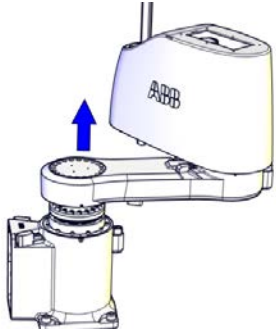
4 Repair

4.5.2 Replacing the base


Continued

	Action	Note
1	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply <p>to the robot, before entering the robot working area.</p>	
2	<p>Remove the cover.</p> <p> Tip</p> <p>If the cover is hard to remove, fit a screw to its attachment hole to help press out the cover.</p>	 <p>xx1500002259</p>
3	<p> WARNING</p> <p>The arm system weights 16.4 kg. The arm system may drop when released from the base. Make sure the weight of the arm system is properly supported.</p>	
4	<p> Note</p> <p>Two persons working together are required to perform this step. Person 1: Hold the arm system. Person 2: Remove the screws that fasten the arm system to the base.</p>	
5	<p> CAUTION</p> <p>Handle the main cable package with care. Minimum bending radius is approximately 10 times of the cable diameter.</p>	

Continues on next page

	Action	Note
6	Remove the screws and washers.	 <p data-bbox="970 795 1082 817">xx150002805</p>
7	Remove the arm system and lay it aside on a workbench.	 <p data-bbox="970 1182 1082 1205">xx150002261</p>

Removing the axis-1 drive unit


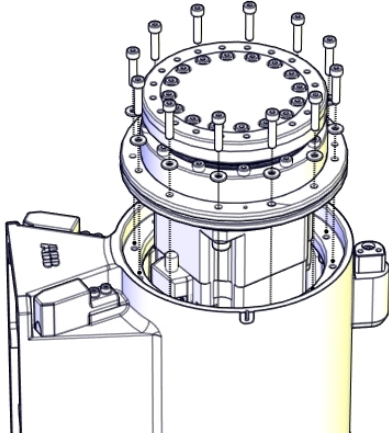

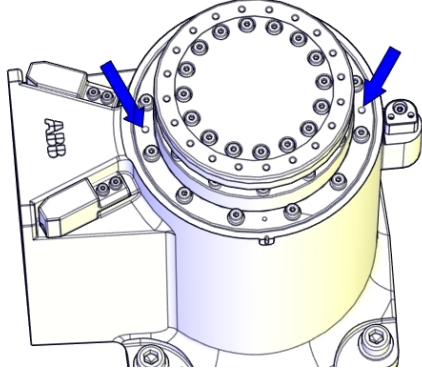
	Action	Note
1	 <p data-bbox="587 1384 699 1415">DANGER</p> <p data-bbox="496 1442 962 1525">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

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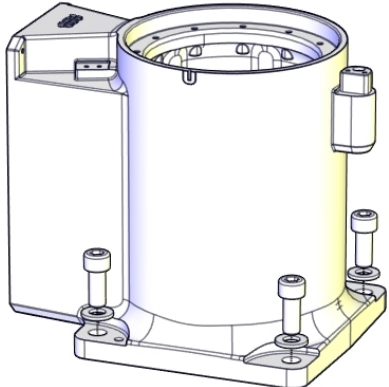
4 Repair

4.5.2 Replacing the base

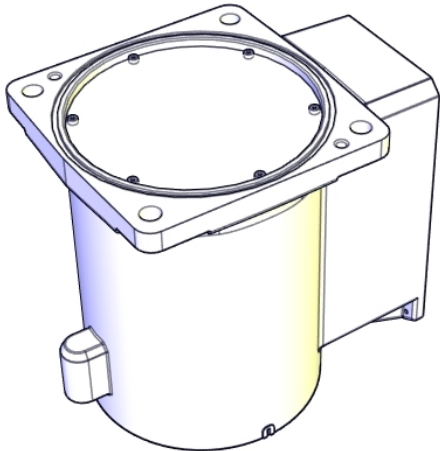
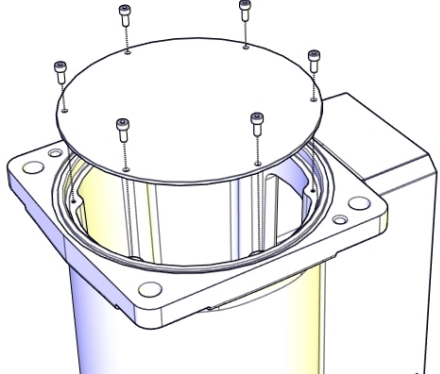
Continued

	Action	Note
2	<p>Remove the screws and washers.</p> <p> WARNING</p> <p>Do not remove the inner circle screws. They are holding the gearbox together and removing them may damage the gearbox severely.</p>	
3	<p>Pull the drive unit out carefully while pulling the motor cables out of the base rear.</p> <p> Tip</p> <p>If the drive unit is hard to remove, insert two M3 screws and press out the drive unit.</p>  <p>xx1500002263</p>	<p>xx1500002262</p>

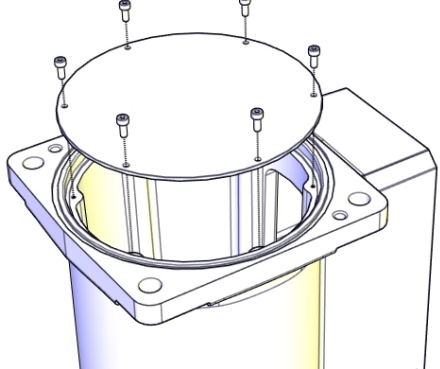
Removing the base

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the attachment screws and washers.</p>	 <p>xx1500002264</p>

Continues on next page

	Action	Note
3	Put the base on its side.	 <p>xx1500002806</p>
4	Remove the bottom cover.	 <p>xx1500002265</p>

Refitting the base

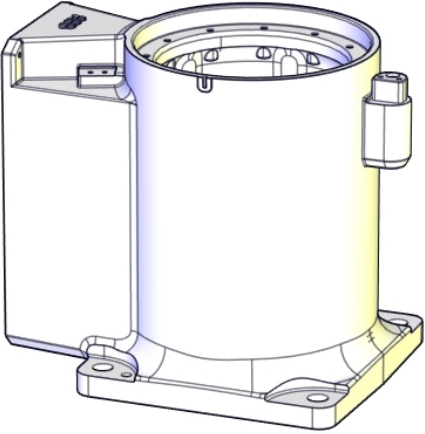
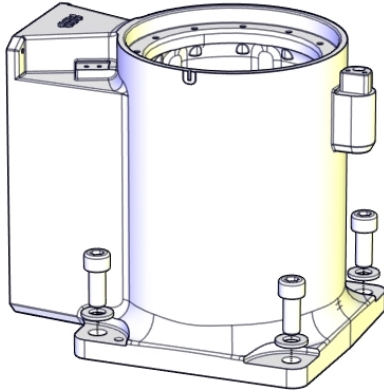
	Action	Note
1	Refit the bottom cover.	<p>Base bottom cover: 3HAC055216-001</p>  <p>xx1500002265</p> <p>Screw: M3x8 (6 pcs) Tightening torque: 2 Nm</p>

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4 Repair

4.5.2 Replacing the base


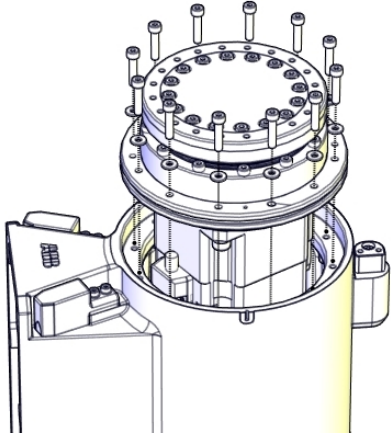
Continued

	Action	Note
2	Put the base in a raised position.	 <p data-bbox="943 770 1050 790">xx1500002807</p>
3	Fasten the attachment screws and washers.	 <p data-bbox="943 1240 1050 1261">xx1500002264</p> <p data-bbox="943 1279 1410 1440"> Attachment screws: M10x25 (4 pcs), quality: 8.8. Washers: 20x10.5x2. Pin: 2 pcs, D6x20, ISO 2338 - 6m6x20 - A1. Tightening Torque: 45 Nm. </p>

Refitting the axis-1 drive unit



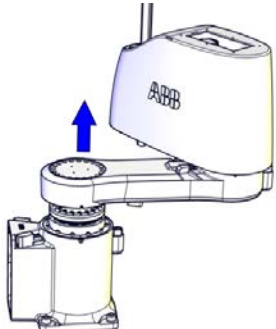
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	

Continues on next page

	Action	Note
2	<p>Carefully insert the complete drive unit while pulling the motor cables out of the base rear.</p> <p> CAUTION</p> <p>Do not mix axis-1 and axis-2 drive units. Always check the mark or label on the drive units before refitting.</p>	<p>Axis-1 drive unit: 3HAC055900-001</p> 
3	<p>Refit the screws and washers.</p>	<p>xx1500002262</p> <p>Screw: M4x20 (12 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1 (12 pcs)</p>

Refitting the arm system

	<p>Note</p>
<p>Two persons working together are required to perform this procedure.</p>	


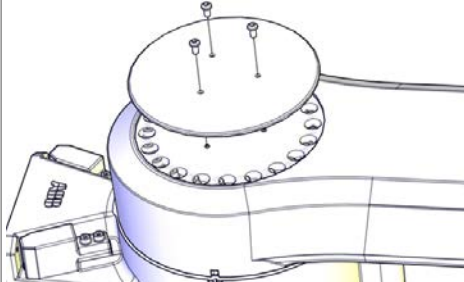
	Action	Note
1	<p> Note</p> <p>Two persons working together are required to perform this step.</p> <p>Person 1: Hold the arm system.</p> <p>Person 2: Refit the screws that fasten the arm system to the base.</p>	
2	<p>Refit the whole arm system.</p> <p> WARNING</p> <p>The arm system weights 16.4 kg. Support the gravity center properly.</p>	 <p>xx1500002261</p> <p>Screw: M4x20 (16 pcs) Tightening torque: 4.2 Nm Washer: 4.3x9x1.3 (16 pcs)</p>

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4 Repair

4.5.2 Replacing the base

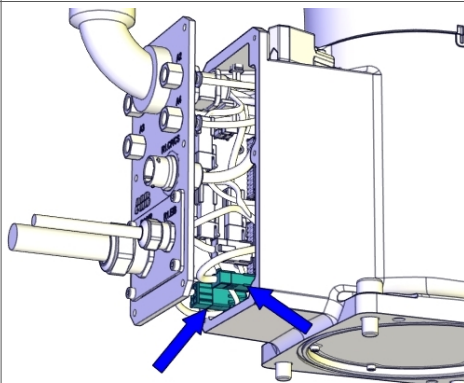
Continued

	Action	Note
3	 CAUTION Handle the main cable package with care. Minimum bending radius is approximately 10x the cable diameter.	
4	Refit the cover.	Lower arm cover: 3HAC056065-001  xx1500002259 Screw: M3x6 (3 pcs) Tightening torque: 1 Nm

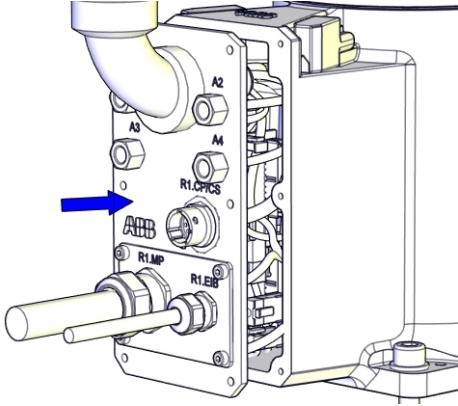
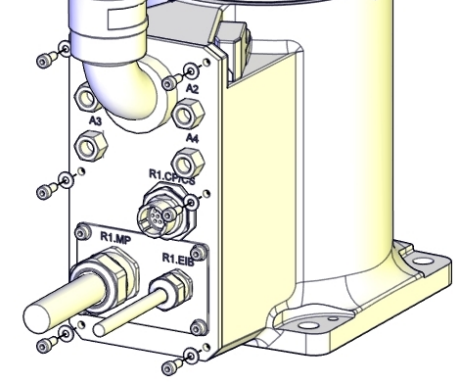
Refitting the cabling to the base

Use these procedures to refit the cabling to the base.


Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	Reconnect the connectors. <ul style="list-style-type: none">• R2.MP1• R2.ME1	 xx1500002188

Continues on next page

	Action	Note
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

4 Repair

4.5.3 Replacing the axis-1 mechanical stop

4.5.3 Replacing the axis-1 mechanical stop

General

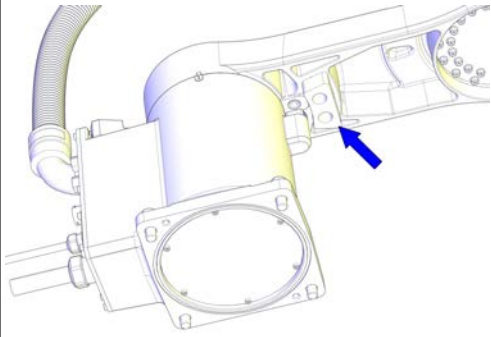
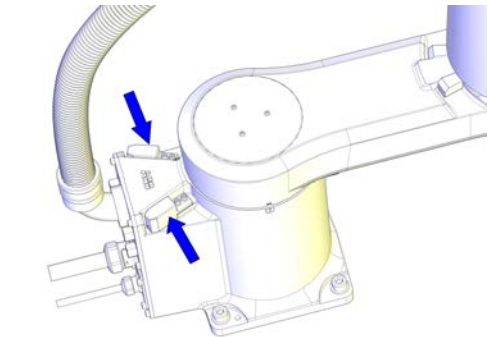


Note

If a collision with the mechanical stops occur, check and retighten all screws before any installation or service work. Replace damaged or cracked screws.

Location of the axis-1 mechanical stop

The axis-1 mechanical stop is located as shown in the figure.

Axis-1 mechanical stop block	Axis-1 mechanical stop rubber
 xx1500002177	 xx1500002176
3HAC055164-001	3HAC056042-001

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-1 mechanical stop rubber	3HAC056042-001	Replace if damaged.
Axis-1 mechanical stop block	3HAC055164-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

Required consumables

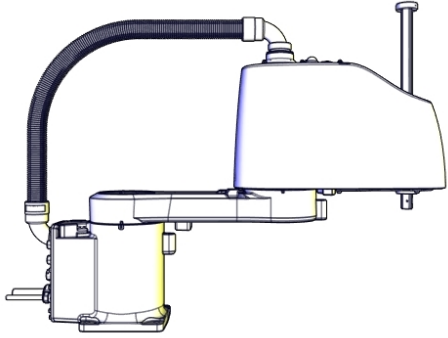

Consumable	Article number	Note
Locking liquid	3HAB7116-1	Loctite 243

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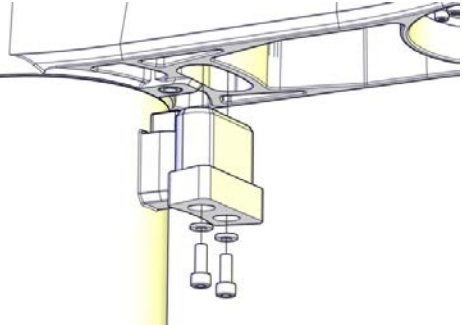
Replacing the axis-1 mechanical stop

Use these procedures to replace the axis-1 mechanical stop.

Preparations before replacing the axis-1 mechanical stop

	Action	Note
1	Jog all axes to zero position.	 <p>xx1500002227</p>
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Replacing the axis-1 mechanical stop block

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the block by removing the screws and washers.	
3	Refit and secure the new mechanical stop block.	


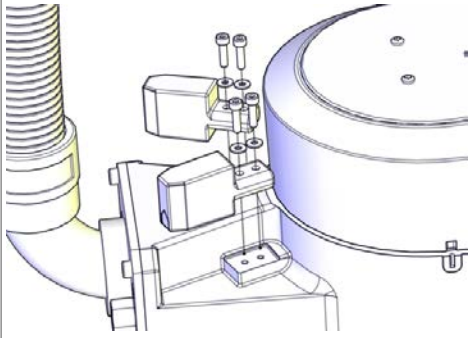
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4 Repair


4.5.3 Replacing the axis-1 mechanical stop

Continued

Replacing the axis-1 mechanical stop rubbers

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Remove the rubbers by removing the screws.	 xx1500002255
3	Refit and secure the new mechanical stop rubbers with screws. Lock screws with locking liquid (Loctite 243).	Screw: M3x12 (4 pcs) Tightening torque: 0.3 Nm

Concluding procedure

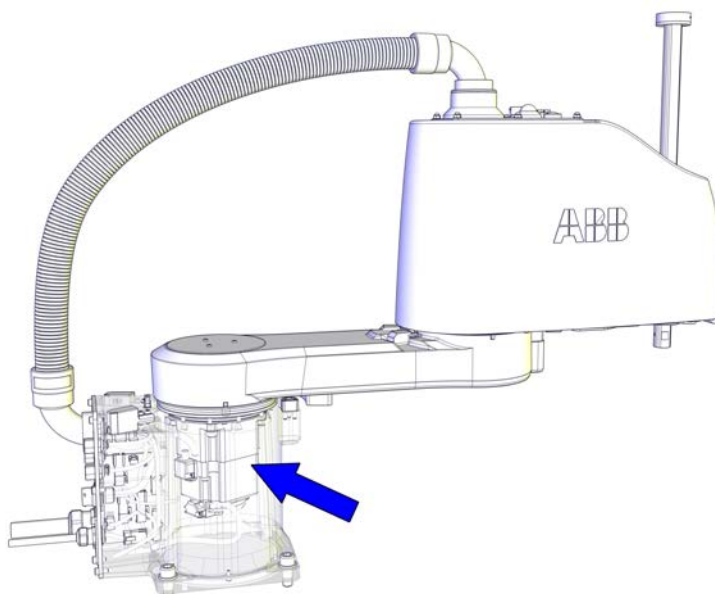
	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.6 Drive units

4.6.1 Replacing the axis-1 drive unit

Location of the axis-1 drive unit

The axis-1 drive unit is located as shown in the figure.



xx1500002213

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-1 drive unit	3HAC055900-001	Includes axis-1 gearbox, motor and motor adapter.
Lower arm cover	3HAC056065-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

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4 Repair

4.6.1 Replacing the axis-1 drive unit

Continued

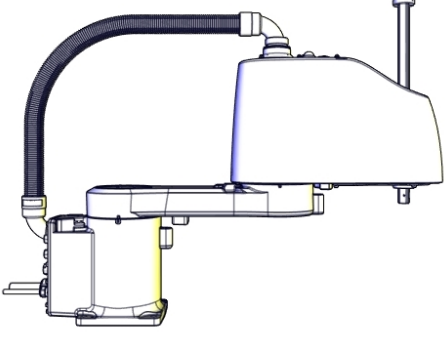

Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the axis-1 drive unit

Use these procedures to remove the axis-1 drive unit.

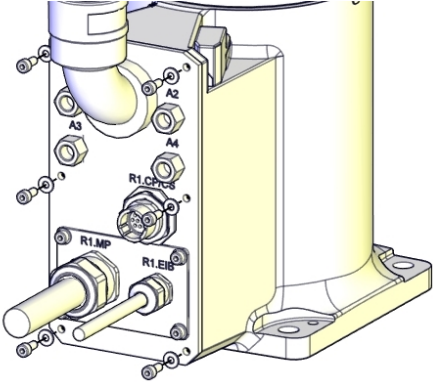


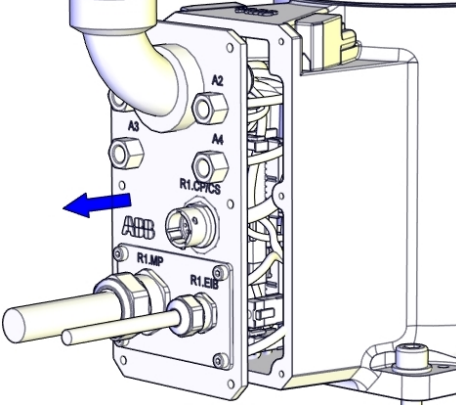

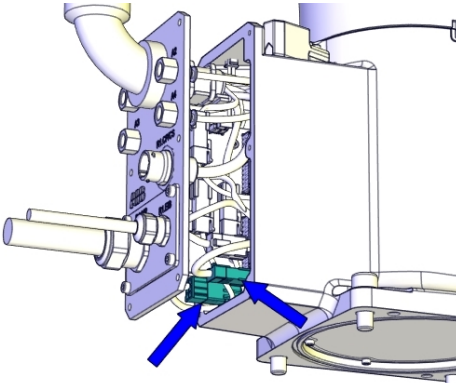
Preparations before removing the axis-1 drive unit

	Action	Note
1	Jog all axes to zero position.	 <small>xx1500002227</small>
2	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the base

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

	Action	Note
2	Remove the screws and washers.	 <p>xx1500002186</p>
3	<p>Carefully open the base cover and pull out the cable package.</p> <p> CAUTION</p> <p>The cover cannot be removed completely until the connectors are disconnected.</p> <p> CAUTION</p> <p>Clean cover from metal residues before opening.</p> <p>Metal residues can cause shortage on the boards which can result in hazardous failures.</p>	 <p>xx1500002187</p>
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002188</p>

Removing the arm system



Note



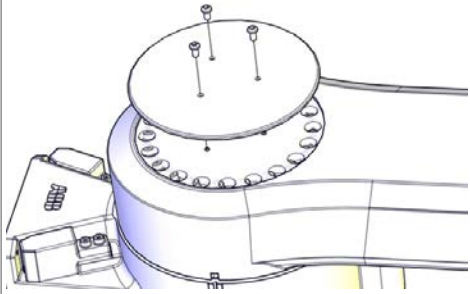



Two persons working together are required to perform this procedure.

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4 Repair

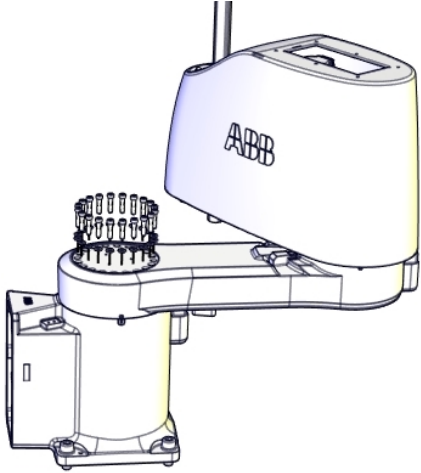
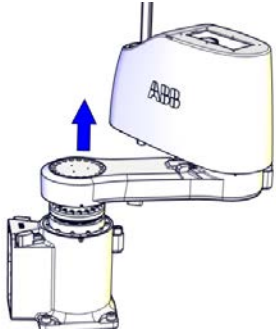
4.6.1 Replacing the axis-1 drive unit

Continued


	Action	Note
1	 DANGER Turn off all: <ul style="list-style-type: none">• electric power supply• hydraulic pressure supply• air pressure supply to the robot, before entering the robot working area.	
2	Remove the cover.  Tip If the cover is hard to remove, fit a screw to its attachment hole to help press out the cover.	 xx1500002259
3	 WARNING The arm system weights 16.4 kg. The arm system may drop when released from the base. Make sure the weight of the arm system is properly supported.	
4	 Note Two persons working together are required to perform this step. Person 1: Hold the arm system. Person 2: Remove the screws that fasten the arm system to the base.	
5	 CAUTION Handle the main cable package with care. Minimum bending radius is approximately 10 times of the cable diameter.	

Continues on next page

4.6.1 Replacing the axis-1 drive unit
Continued

	Action	Note
6	Remove the screws and washers.	 <p data-bbox="970 795 1082 817">xx150002805</p>
7	Remove the arm system and lay it aside on a workbench.	 <p data-bbox="970 1182 1082 1205">xx150002261</p>

Removing the axis-1 drive unit


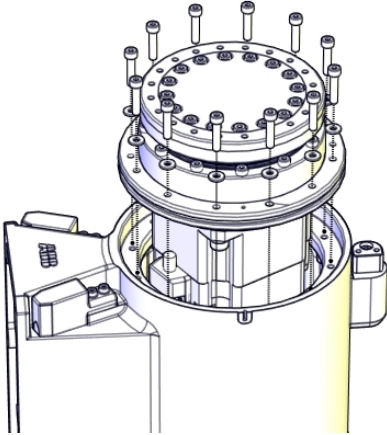

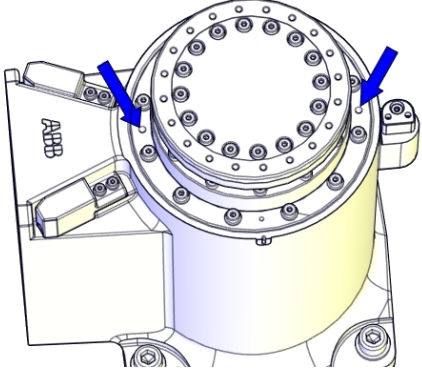
	Action	Note
1	 <p data-bbox="587 1384 699 1415">DANGER</p> <p data-bbox="496 1442 962 1525">Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	

Continues on next page

4 Repair

4.6.1 Replacing the axis-1 drive unit

Continued

	Action	Note
2	<p>Remove the screws and washers.</p> <p> WARNING</p> <p>Do not remove the inner circle screws. They are holding the gearbox together and removing them may damage the gearbox severely.</p>	
3	<p>Pull the drive unit out carefully while pulling the motor cables out of the base rear.</p> <p> Tip</p> <p>If the drive unit is hard to remove, insert two M3 screws and press out the drive unit.</p>  <p>xx1500002263</p>	<p>xx1500002262</p>


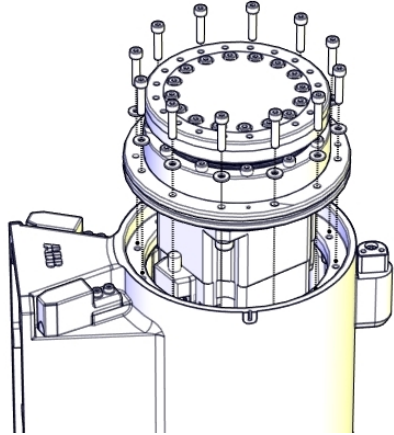
Refitting the axis-1 drive unit

Use these procedures to refit the axis-1 drive unit.


Refitting the axis-1 drive unit



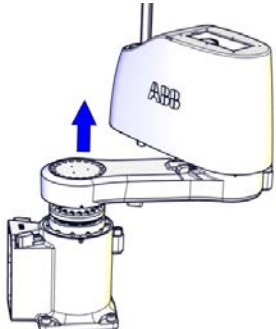
	Action	Note
1	<p>Make sure that:</p> <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	

Continues on next page

	Action	Note
2	<p>Carefully insert the complete drive unit while pulling the motor cables out of the base rear.</p> <p> CAUTION</p> <p>Do not mix axis-1 and axis-2 drive units. Always check the mark or label on the drive units before refitting.</p>	<p>Axis-1 drive unit: 3HAC055900-001</p> 
3	<p>Refit the screws and washers.</p>	<p>xx1500002262</p> <p>Screw: M4x20 (12 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1 (12 pcs)</p>

Refitting the arm system

	<p>Note</p>
<p>Two persons working together are required to perform this procedure.</p>	


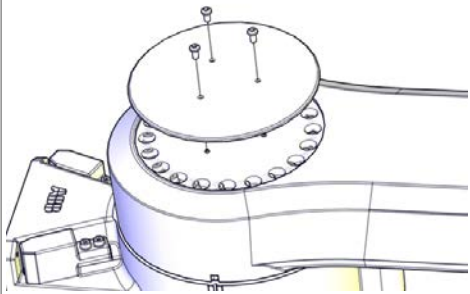
	Action	Note
1	<p> Note</p> <p>Two persons working together are required to perform this step.</p> <p>Person 1: Hold the arm system.</p> <p>Person 2: Refit the screws that fasten the arm system to the base.</p>	
2	<p>Refit the whole arm system.</p> <p> WARNING</p> <p>The arm system weights 16.4 kg. Support the gravity center properly.</p>	 <p>xx1500002261</p> <p>Screw: M4x20 (16 pcs) Tightening torque: 4.2 Nm Washer: 4.3x9x1.3 (16 pcs)</p>

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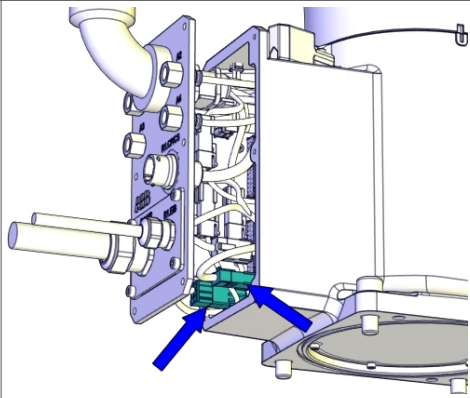
4 Repair

4.6.1 Replacing the axis-1 drive unit

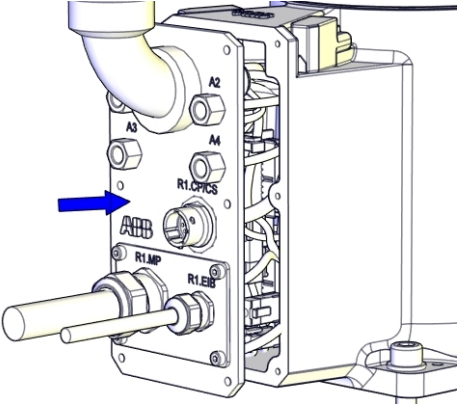
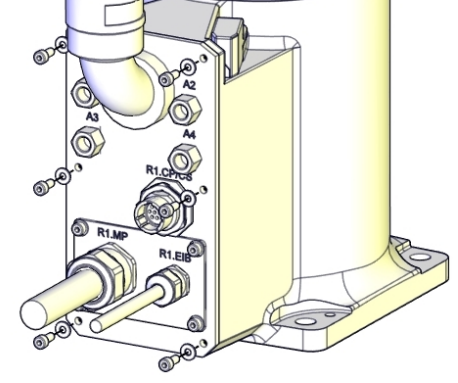
Continued

	Action	Note
3	<p> CAUTION</p> <p>Handle the main cable package with care. Minimum bending radius is approximately 10x the cable diameter.</p>	
4	Refit the cover.	<p>Lower arm cover: 3HAC056065-001</p>  <p>xx1500002259</p> <p>Screw: M3x6 (3 pcs) Tightening torque: 1 Nm</p>


Refitting the main cable to the base

	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP1 • R2.ME1 	 <p>xx1500002188</p>

Continues on next page

	Action	Note
3	Push the main cable package into place.	 <p>xx1500002204</p>
4	Refit the base cover with screws and washers.	 <p>xx1500002186</p> <p>Screws: M4x10 (6 pcs) Tightening torque: 2 Nm</p>

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

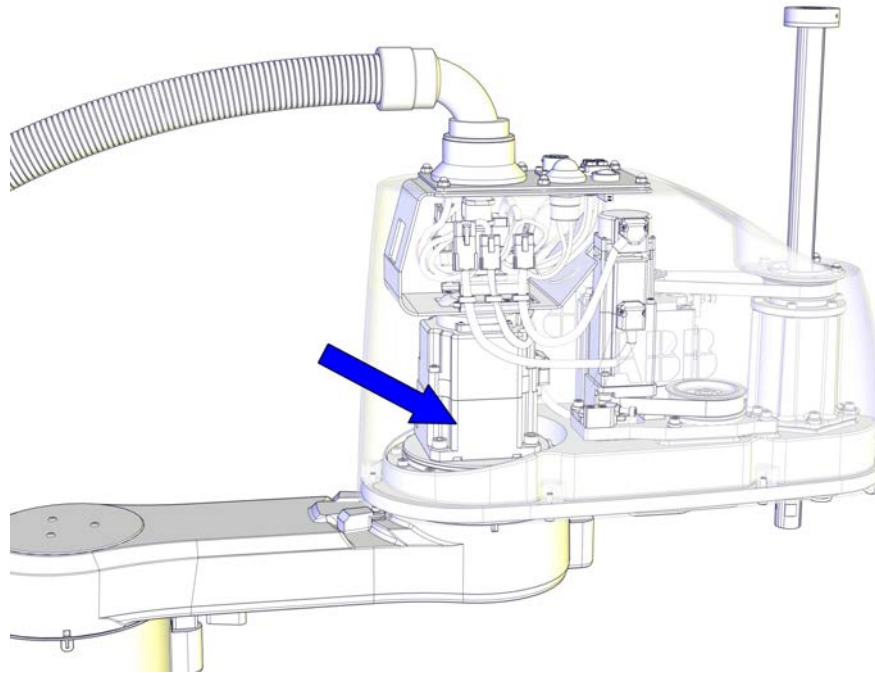
4 Repair

4.6.2 Replacing the axis-2 drive unit

4.6.2 Replacing the axis-2 drive unit

Location of the axis-2 drive unit

The axis-2 drive unit is located as shown in the figure.



xx1500002214

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-2 drive unit	3HAC056153-001	Includes axis-2 gearbox, motor and motor adapter.
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.
Plate for upper arm cable harness	3HAC056086-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section Standard toolkit on page 386 .

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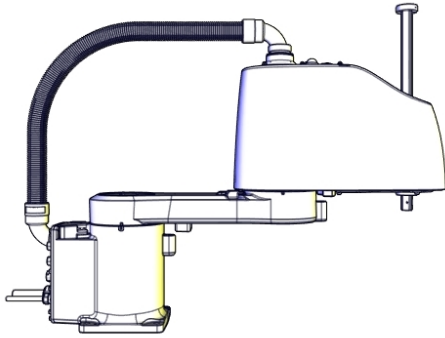

Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the axis-2 drive unit

Use these procedures to remove the axis-2 drive unit.

Preparations before removing the axis-2 drive unit

	Action	Note
1	Jog all axes to zero position.	 xx1500002227
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Removing the main cable package from the upper arm

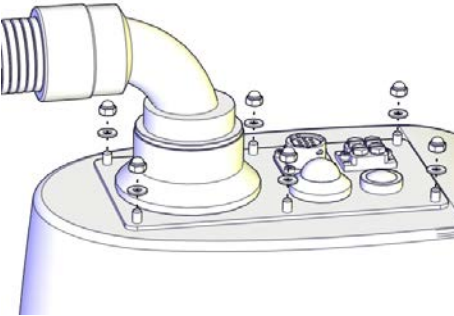

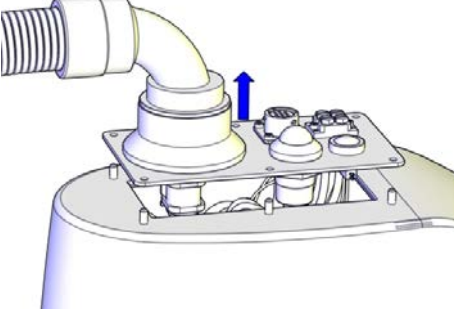

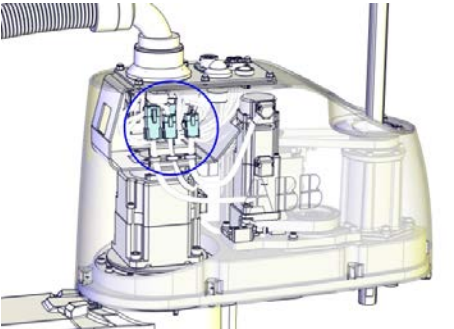
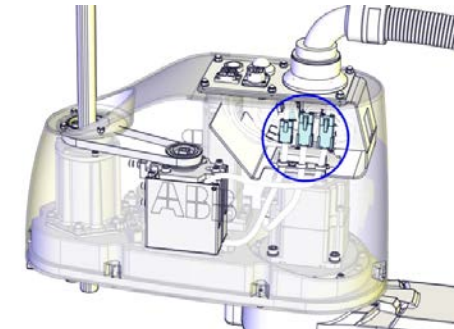
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

Continues on next page

4 Repair

4.6.2 Replacing the axis-2 drive unit

Continued

	Action	Note
2	Remove the dome nuts and washers.	 xx1500002182
3	Carefully open the user interface plate and pull out the cable package.  CAUTION The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.	 xx1500002183
4	Disconnect the connectors: <ul data-bbox="501 1108 774 1301" style="list-style-type: none">• R2.MP2• R2.MP3• R2.MP4• R2.ME2• R2.ME3• R2.ME4  Tip Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.	 xx1500002184  xx1500002185





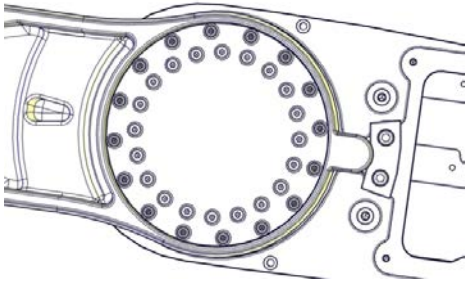
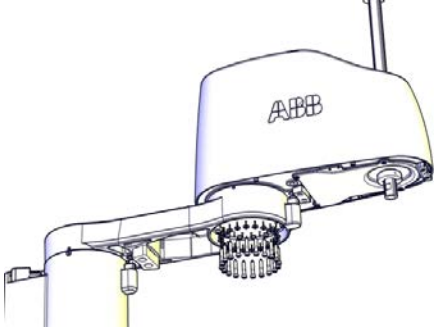
Removing the upper arm




Note

Two persons working together are required to perform this procedure.

Continues on next page

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING The upper arm weights 13.2 kg. It may drop by the force of gravity when it is released from the lower arm. Make sure the weight of the upper arm body is properly supported.	
3	 Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Remove the screws that fasten the upper arm to the lower arm.	
4	Remove the screws and washers.  WARNING Keep the twelve screws in the outer circle fitted. They hold the axis-2 motor flange on the lower arm.  xx1500002257	 xx1500002256
5	Remove the upper arm and lay it aside on a workbench.	

Removing the upper cover


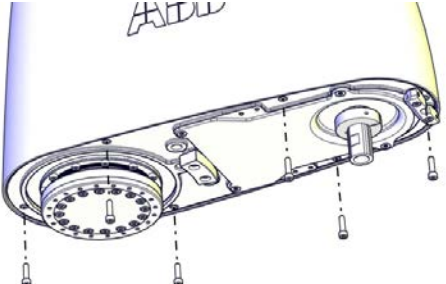

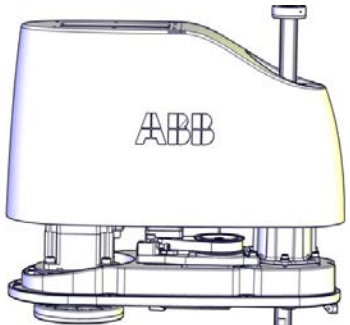
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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4 Repair

4.6.2 Replacing the axis-2 drive unit


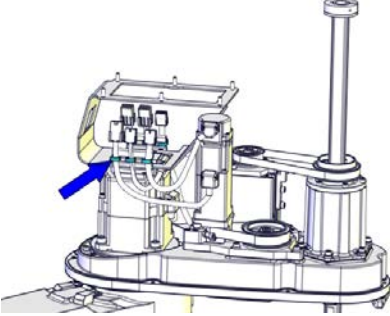
Continued

	Action	Note
2	 WARNING Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.	
3	Remove the screws.	 xx1500002220
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 xx1500002221


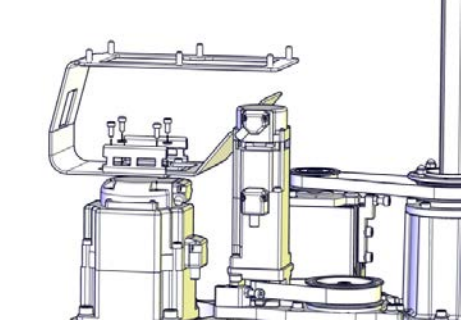
Removing the drive unit cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	



Continues on next page

	Action	Note
2	<p>Cut the cable ties. Be careful not to damage the cabling.</p> <p> Tip</p> <p>Take photos of the cable position before removing them, to have as a reference when refitting.</p>	 <p>xx1500002226</p>

Removing the cable harness plate

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	Remove the screws and washers.	 <p>xx1500002228</p>
3	Remove the cable harness plate.	

Removing the axis-2 drive unit


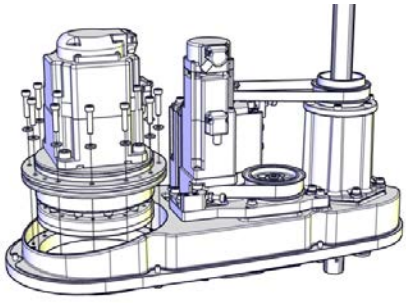

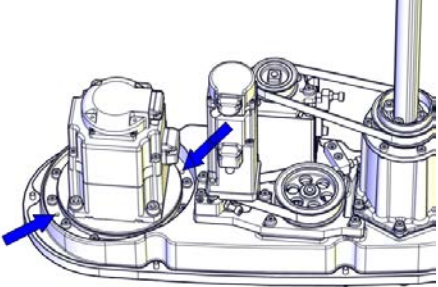
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>There is a risk of tipping during the removal. Make sure the gravity center is well supported.</p>	

Continues on next page

4 Repair

4.6.2 Replacing the axis-2 drive unit



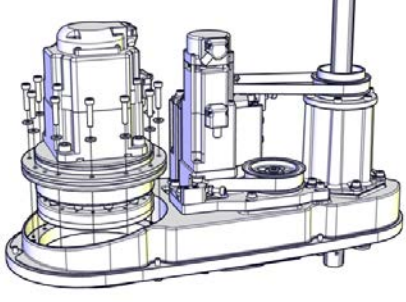
Continued

	Action	Note
3	<p>Remove drive unit screws and washers.</p> <p> WARNING</p> <p>Pay attention to the screw positions and keep the others fitted. The other screws hold the gearbox together. Removing them can damage the gearbox severely.</p>	 <p>xx1500002496</p>
4	<p> Tip</p> <p>If the drive unit is hard to be removed, insert two M2 screws to the press out holes and press out the drive unit.</p>	 <p>xx1500002498</p>

Refitting the axis-2 drive unit

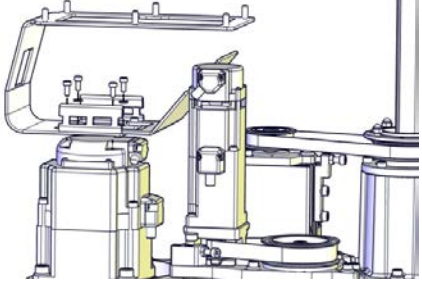
Use these procedures to refit the axis-2 drive unit.

Refitting the axis-2 drive unit

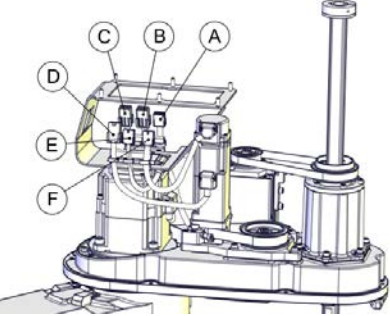
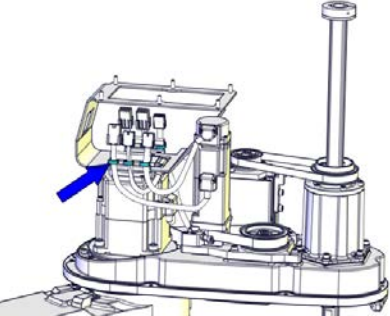
	Action	Note
1	<p>Make sure that:</p> <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	<p>Refit the axis-2 drive unit into the upper arm.</p> <p> CAUTION</p> <p>Do not mix axis-1 and axis-2 drive units. Always check the mark or label on the drive units before refitting.</p> <p> Note</p> <p>Make sure to refit the drive unit correctly oriented, that is, the motor connectors should point to the end where the ball screw spline unit is to be fitted.</p>	<p>Axis-2 drive unit: 3HAC056153-001</p>  <p>xx1500002496</p>
3	<p>Refit the screws and washers.</p>	<p>Screw: M4x25 (12 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1 (12 pcs)</p>

Continues on next page

Refitting the cable harness plate

	Action	Note
1	Refit the cable harness plate.	 <p data-bbox="970 696 1082 719">xx150002228</p> <p data-bbox="970 734 1198 763">Screw: M3x8 (4 pcs)</p> <p data-bbox="970 770 1262 799">Tightening torque: 1.5 Nm</p> <p data-bbox="970 806 1187 835">Washer: M3 (4 pcs)</p>
2	Secure with screws and washers.	

Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p data-bbox="970 1290 1082 1312">xx150003063</p> <table border="1" data-bbox="975 1330 1441 1603"> <tr> <td data-bbox="975 1330 1023 1375">A</td> <td data-bbox="1023 1330 1441 1375">R2.ME3</td> </tr> <tr> <td data-bbox="975 1375 1023 1420">B</td> <td data-bbox="1023 1375 1441 1420">R2.MP2</td> </tr> <tr> <td data-bbox="975 1420 1023 1464">C</td> <td data-bbox="1023 1420 1441 1464">R2.MP3</td> </tr> <tr> <td data-bbox="975 1464 1023 1509">D</td> <td data-bbox="1023 1464 1441 1509">R2.MP4</td> </tr> <tr> <td data-bbox="975 1509 1023 1554">E</td> <td data-bbox="1023 1509 1441 1554">R2.ME2</td> </tr> <tr> <td data-bbox="975 1554 1023 1599">F</td> <td data-bbox="1023 1554 1441 1599">R2. ME4</td> </tr> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p data-bbox="970 1962 1082 1984">xx150002226</p>												

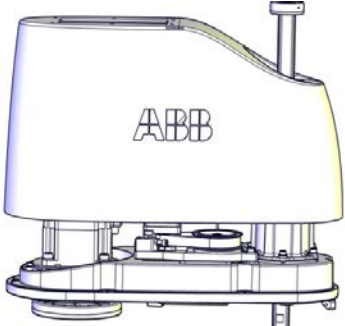

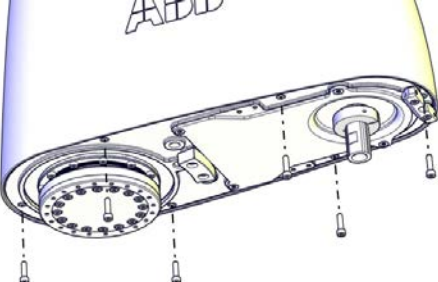
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4 Repair


4.6.2 Replacing the axis-2 drive unit


Continued

Refitting the upper cover

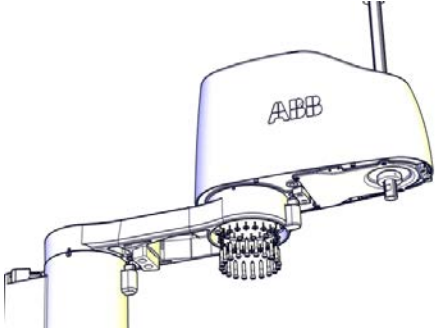
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	Upper cover unit: 3HAC057615-001  <small>xx1500002221</small>
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <small>xx1500002220</small> Screw: M4x16 (6 pcs) Tightening torque: 2 Nm

Refitting the upper arm

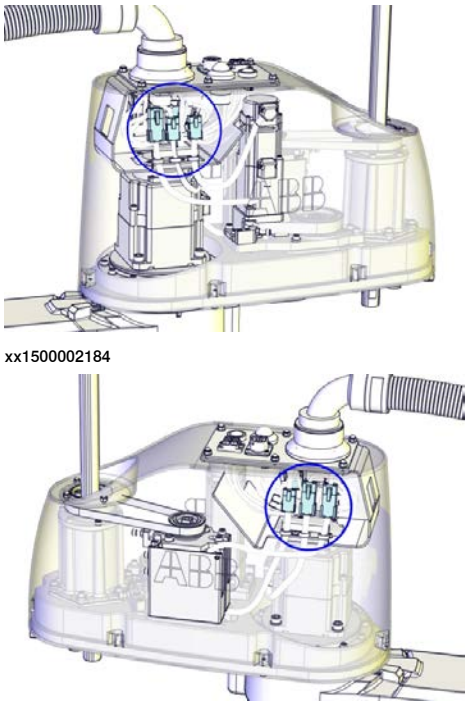
	Note
Two persons working together are required to perform this procedure.	

	Action	Note
1	 Note Two persons working together are required to perform this step. Person 1: Hold the upper arm. Person 2: Refit the screws that fasten the upper arm to the lower arm.	

Continues on next page

	Action	Note
2	Make sure the lower arm is secured. Lower the upper arm down onto the right place of the lower arm.	
3	Refit the upper arm screws and washers.	 <p data-bbox="970 741 1082 763">xx1500002256</p> <p data-bbox="970 779 1276 875">Screw: M4x20 (16 pcs) Tightening torque: 4.5 Nm Washer: 4.3x9x1.3 (16 pcs)</p>

Refitting the main cable to the upper arm

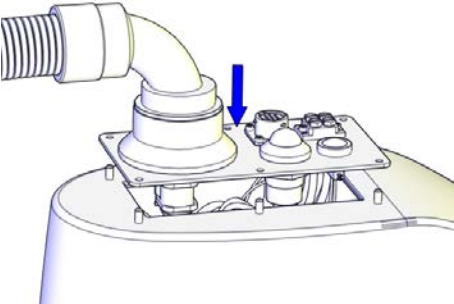
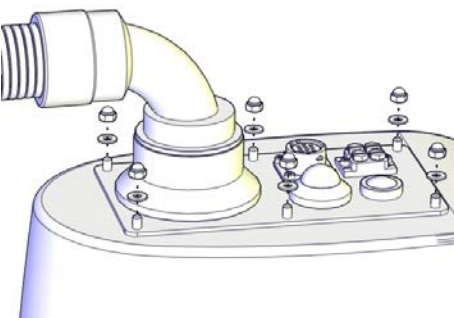
	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p data-bbox="970 1413 1082 1435">xx1500002184</p> <p data-bbox="970 1783 1082 1805">xx1500002185</p>

Continues on next page


4 Repair

4.6.2 Replacing the axis-2 drive unit

Continued

	Action	Note
3	Push the main cable package into place.	 <p>xx1500002207</p>
4	Refit the user interface plate.	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>

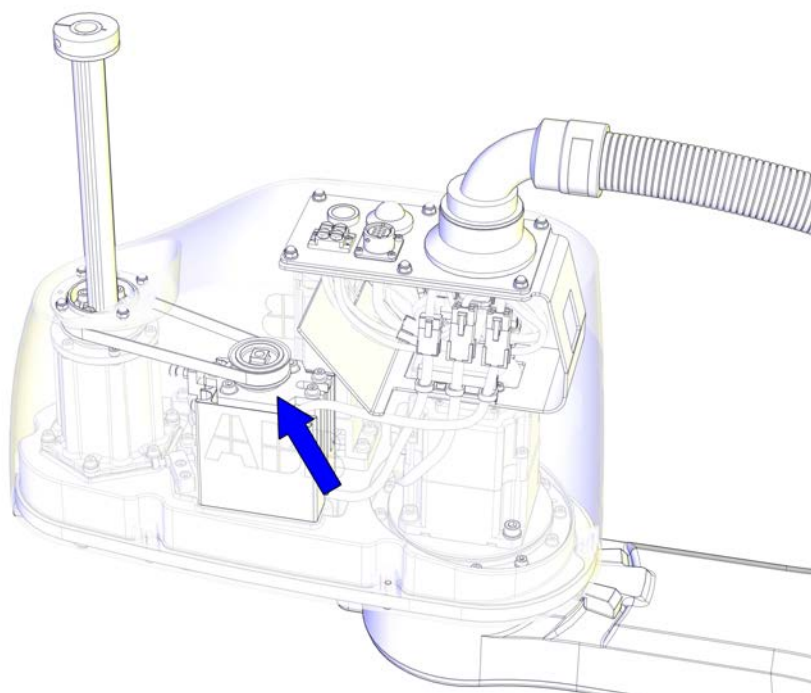
Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.6.3 Replacing the axis-3 drive unit

Location of the axis-3 drive unit

The axis-3 drive unit is located as shown in the figure.



xx1500002219

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-3 drive unit	3HAC056111-001	Includes axis-3 gearbox, motor and motor adapter.
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.
Plain washer	3HAC056937-001	Replace if damaged.
Axis-3 drive unit housing	3HAC055184-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .

Continues on next page

4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued

Equipment	Article number	Note
Sonic tensiometer	-	Used for measuring the timing belt tension.
Dynamometer	-	Used for measuring the timing belt tension.

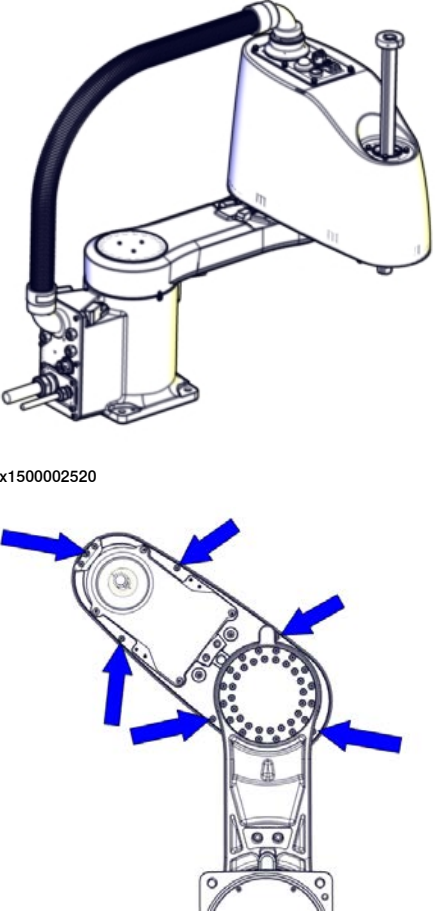
Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the axis-3 drive unit

Use these procedures to remove the axis-3 drive unit.


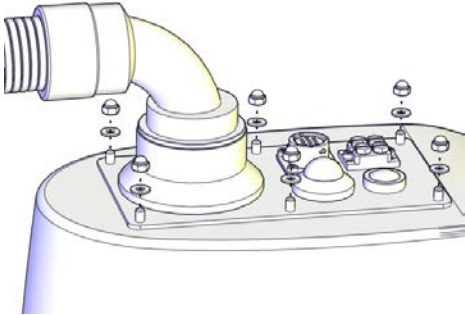

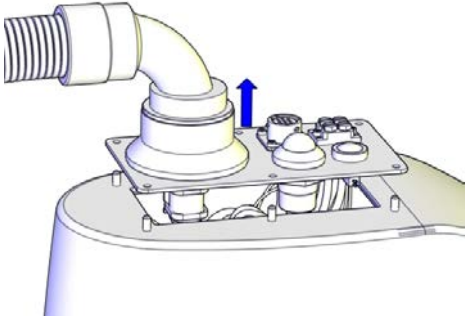
Preparations before removing the axis-3 drive unit

Action	Note
1 Jog axis 2 to access the cover screws.	 <p>The diagram consists of two parts. The top part, labeled 'xx1500002520', shows a perspective view of the axis-3 drive unit with a black timing belt. The bottom part, labeled 'xx1500002782', is a top-down view of the drive unit's housing with six blue arrows pointing to the locations of the cover screws.</p>

Continues on next page

	Action	Note
2	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	

Removing the main cable package from the upper arm


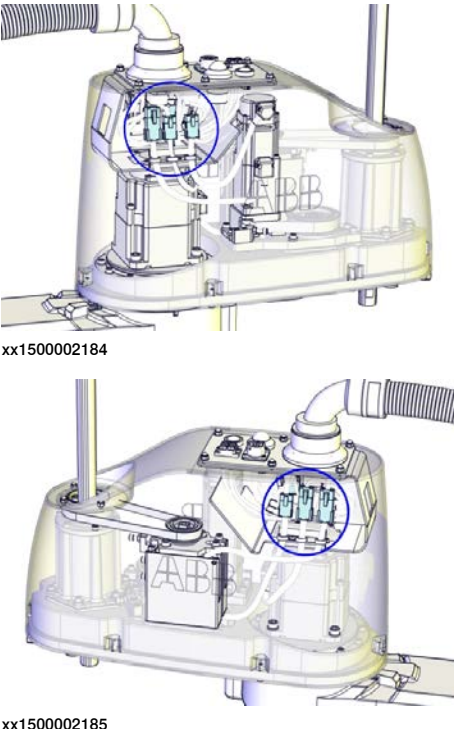
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the dome nuts and washers.</p>	 <p>xx1500002182</p>
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 <p>xx1500002183</p>

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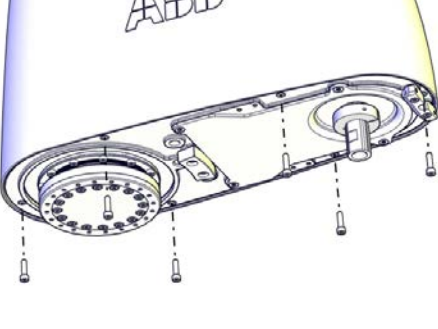
4 Repair

4.6.3 Replacing the axis-3 drive unit


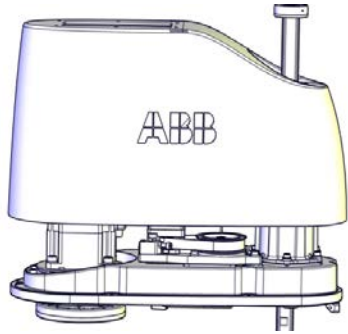
Continued

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002184</p> <p>xx1500002185</p>



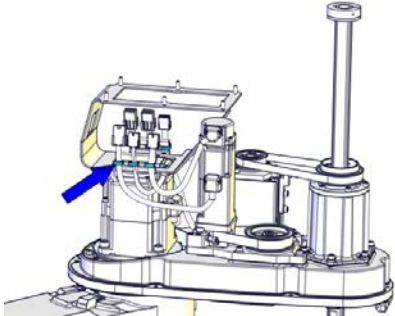
Removing the upper cover

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	 <p>xx1500002220</p>


Continues on next page

	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 xx1500002221

Removing the drive unit cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Cut the cable ties. Be careful not to damage the cabling.  Tip Take photos of the cable position before removing them, to have as a reference when refitting.	 xx1500002226

Removing the axis-3 timing belt


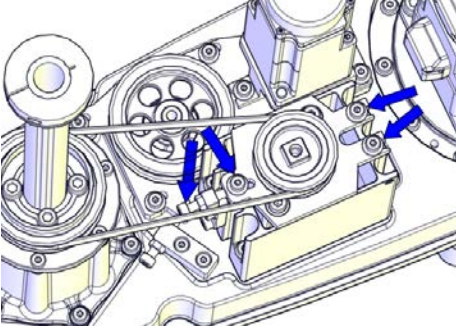
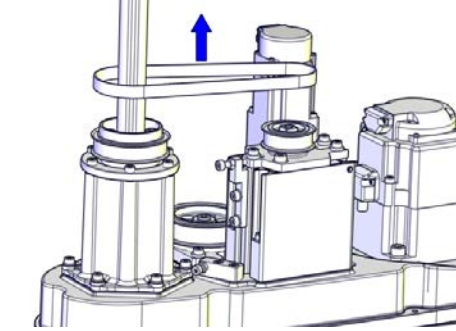
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued

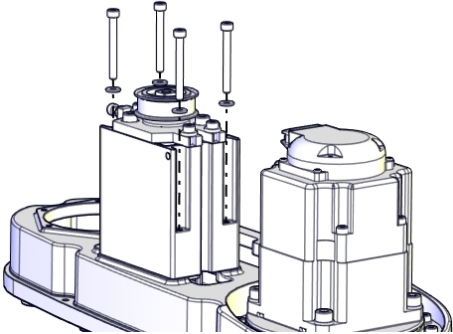
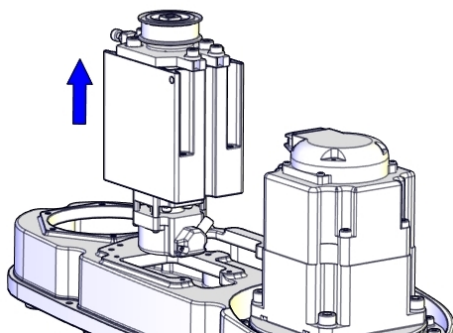
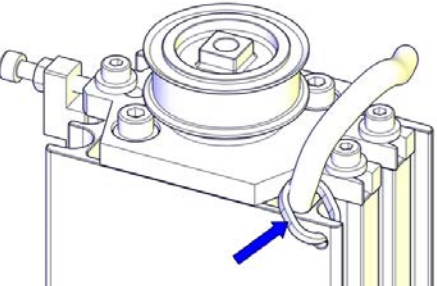
	Action	Note
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-3 drive unit upwards to slacken the timing belt.	 <p>xx1500002229</p>
4	Remove the timing belt.	 <p>xx1500002230</p>

Removing the axis-3 housing and axis-3 drive unit

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	

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4.6.3 Replacing the axis-3 drive unit
Continued


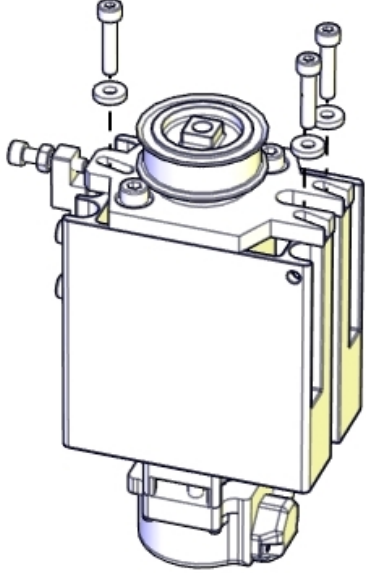
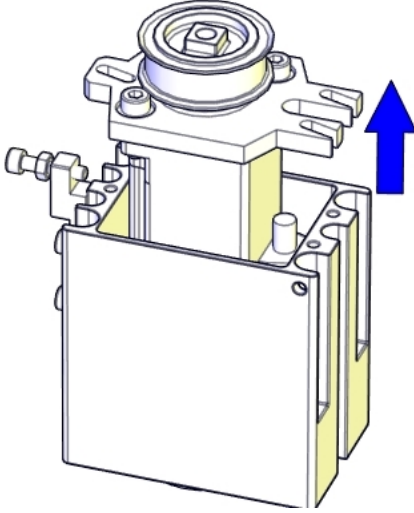
	Action	Note
3	Remove the screws and washers.	 <p>xx1500002810</p>
4	Lift out the axis-3 housing and drive unit.	 <p>xx1500002238</p>
5	Cut the cable tie. Be careful not to damage the cabling.	 <p>xx1500002815</p>

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4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued


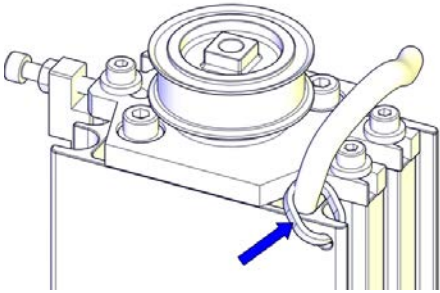
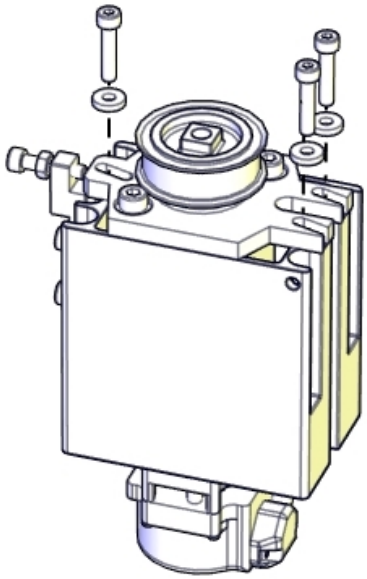

	Action	Note
6	<p>Remove the screws.</p> <p> WARNING</p> <p>Do not remove the other screws. They hold the gearbox together. Removing them can damage the gearbox severely.</p>	 <p>xx1500002797</p>
7	<p>Lift out the axis-3 drive unit carefully.</p>	 <p>xx1500002239</p>

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Refitting the axis-3 drive unit

Use these procedures to refit the axis-3 drive unit.

Refitting the axis-3 housing and axis-3 drive unit

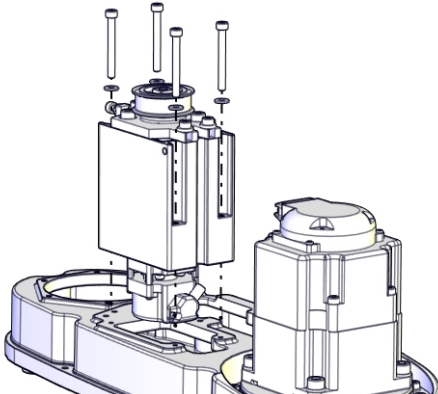
	Action	Note
1	<p>Refit the drive unit with one cabling coming out from the upside and the other coming out from the downside.</p> <p> Note</p> <p>Make sure to refit the drive unit correctly oriented with the lugs of the drive unit bracket as a reference.</p>	<p>Axis-3 drive unit: 3HAC056111-001 Axis-3 drive unit housing: 3HAC055184-001</p>
2	<p>Secure the upper cabling with a cable tie. Do not tighten the tie too tight.</p>	 <p>xx1500002815</p>
3	<p>Refit drive unit screws and washers just enough to still be able to move the drive unit.</p>	 <p>xx1500002797</p> <p>Screw: M4x20 (3 pcs) Tightening torque: 4.5 Nm Washer (3HAC056937-001, 3 pcs)</p> <p> Note</p> <p>Only use specified washers, never replace them with other washers.</p>

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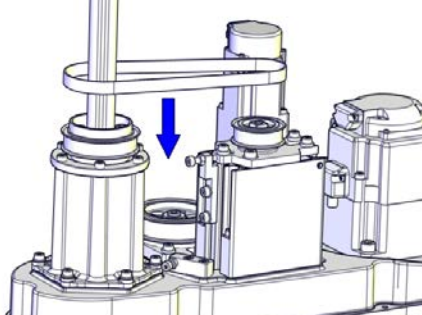
4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued

	Action	Note
4	Refit the housing with drive unit.	 <p data-bbox="941 716 1053 739">xx1500002798</p> <p data-bbox="941 750 1228 851">Screw: M4x40 (4 pcs) Tightening torque: 3.5 Nm Washer: M4 (4 pcs)</p>

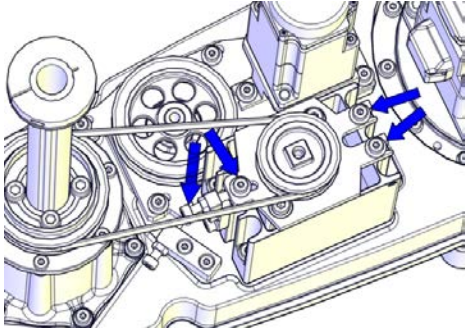
Refitting the axis-3 timing belt

	Action	Note
1	Make sure that: <ul data-bbox="494 996 925 1120" style="list-style-type: none">• all assembly surfaces are clean and undamaged.• the drive unit is clean and undamaged.	
2	Refit axis-3 timing belt. Ensure that the belt runs correctly in the grooves.	<p data-bbox="941 1142 1340 1164">Axis-3 timing belt: 3HAC055209-001</p>  <p data-bbox="941 1500 1053 1523">xx1500002789</p>

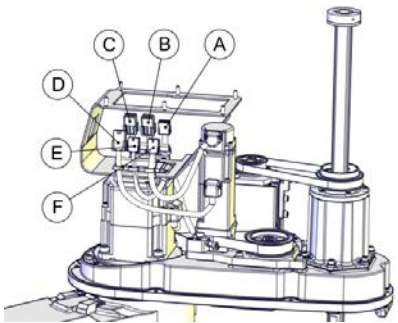
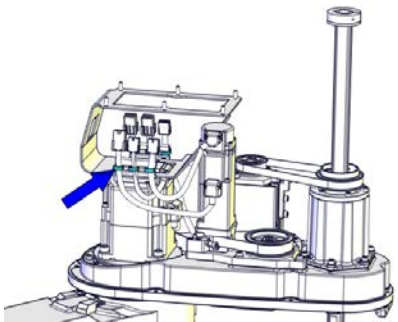
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4.6.3 Replacing the axis-3 drive unit

Continued

	Action	Note
3	Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.	 <p data-bbox="970 645 1082 667">xx150002229</p> <p data-bbox="970 680 1406 712">Belt tension: $F = 34 \text{ N}$ (Recommended)</p> <p data-bbox="970 716 1182 748">Belt tension range:</p> <p data-bbox="970 752 1437 831">21.8 N to 24.9 N (for used timing belt, which has been installed and used for more than 24 hours)</p> <p data-bbox="970 835 1358 866">31.1 to 34.2 N (for new timing belt)</p>

Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p data-bbox="970 1323 1082 1346">xx150003063</p> <table border="1" data-bbox="970 1361 1437 1637"> <tbody> <tr> <td data-bbox="970 1368 1023 1400">A</td> <td data-bbox="1023 1368 1437 1400">R2.ME3</td> </tr> <tr> <td data-bbox="970 1413 1023 1444">B</td> <td data-bbox="1023 1413 1437 1444">R2.MP2</td> </tr> <tr> <td data-bbox="970 1458 1023 1489">C</td> <td data-bbox="1023 1458 1437 1489">R2.MP3</td> </tr> <tr> <td data-bbox="970 1503 1023 1534">D</td> <td data-bbox="1023 1503 1437 1534">R2.MP4</td> </tr> <tr> <td data-bbox="970 1547 1023 1579">E</td> <td data-bbox="1023 1547 1437 1579">R2.ME2</td> </tr> <tr> <td data-bbox="970 1592 1023 1624">F</td> <td data-bbox="1023 1592 1437 1624">R2. ME4</td> </tr> </tbody> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p data-bbox="970 1998 1082 2020">xx150002226</p>												

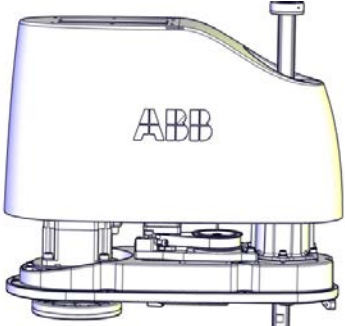

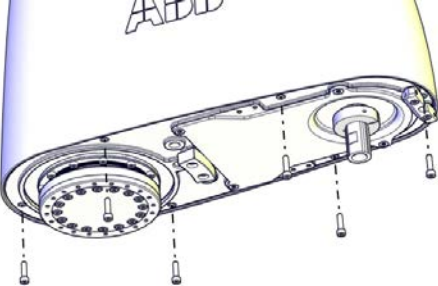
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4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued

Refitting the upper cover

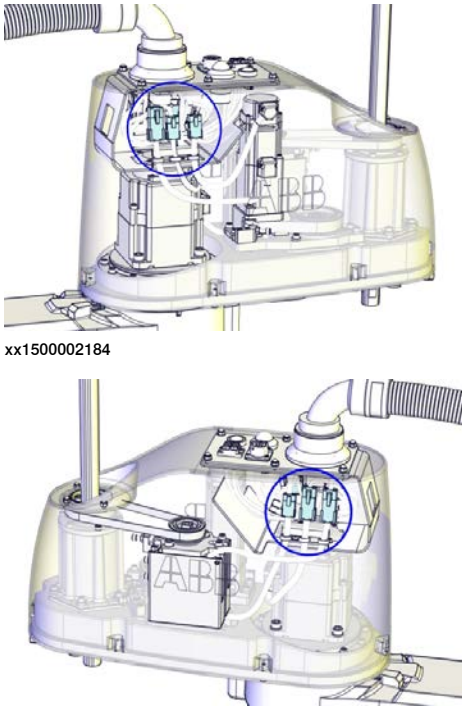
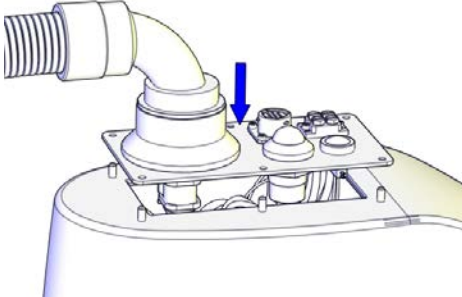
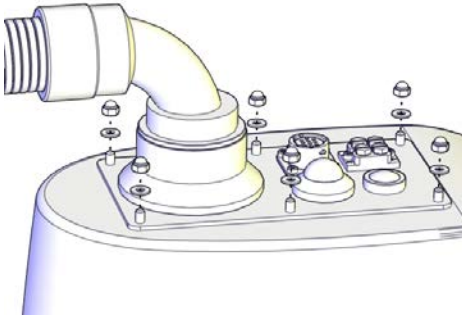
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	Upper cover unit: 3HAC057615-001  <small>xx1500002221</small>
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <small>xx1500002220</small> Screw: M4x16 (6 pcs) Tightening torque: 2 Nm

Refitting the main cable to the upper arm

	Action	Note
1	Secure the main cable package with cable ties if needed.	

Continues on next page

4.6.3 Replacing the axis-3 drive unit
Continued

	Action	Note
2	<p>Reconnect the connectors.</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p>xx1500002184</p> <p>xx1500002185</p>
3	<p>Push the main cable package into place.</p>	 <p>xx1500002207</p>
4	<p>Refit the user interface plate.</p>	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>


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4 Repair

4.6.3 Replacing the axis-3 drive unit

Continued

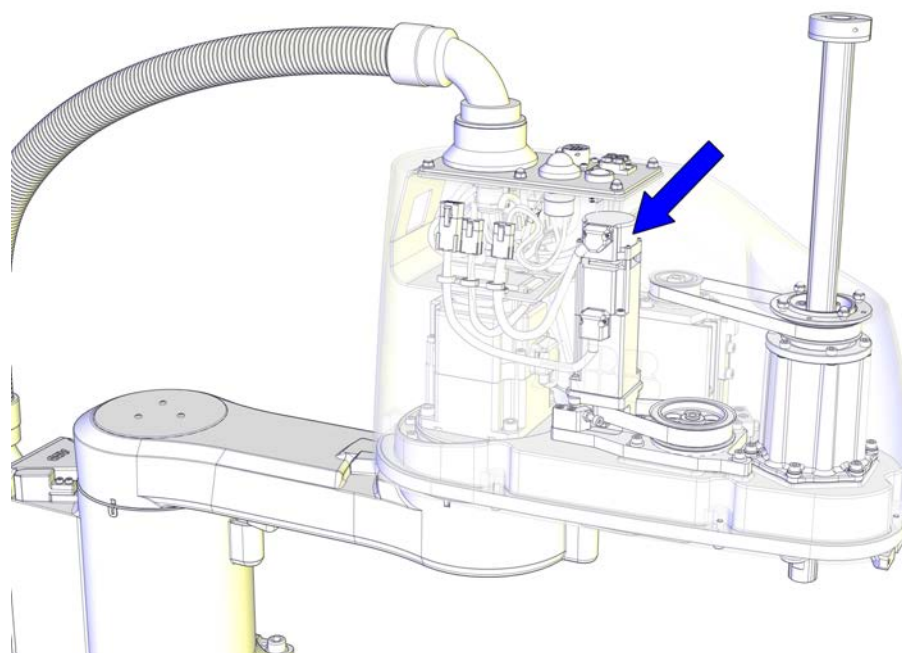
Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 DANGER Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i> .	

4.6.4 Replacing the axis-4 drive unit

Location of the axis-4 drive unit

The axis-4 drive unit is located as shown in the figure.



xx1500002215

Required spare parts



Note

The spare part numbers that are listed in the table can be out of date. See the latest spare parts of the IRB 910SC via myABB Business Portal, www.abb.com/myABB.

Spare part	Article number	Note
Axis-4 drive unit	3HAC056112-001	Includes axis-4 gearbox, motor and motor adapter.
Upper cover unit	3HAC057615-001	Includes upper cover and cover flange.
Plain washer	3HAC056937-001	Replace if damaged.

Required tools and equipment

Equipment	Article number	Note
Standard toolkit	-	The content is defined in the section Standard toolkit on page 386 .
Sonic tensiometer	-	Used for measuring the timing belt tension.

Continues on next page

4 Repair

4.6.4 Replacing the axis-4 drive unit

Continued

Equipment	Article number	Note
Dynamometer	-	Used for measuring the timing belt tension.

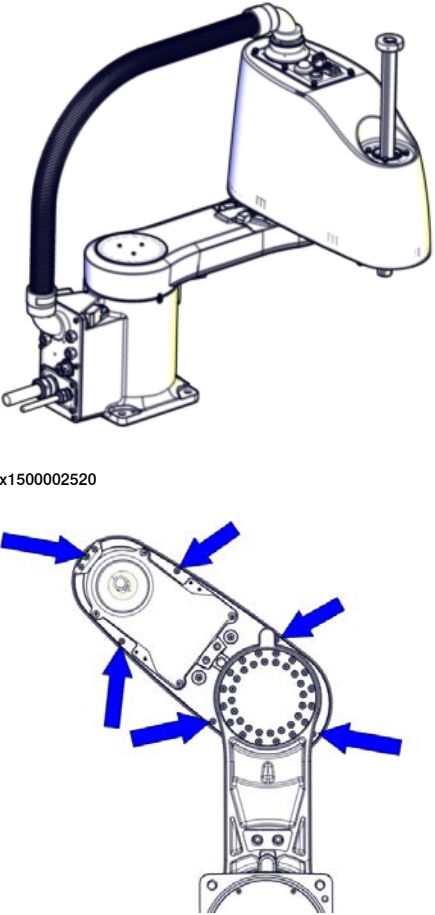
Required consumables

Consumable	Article number	Note
Cable ties	-	


Removing the axis-4 drive unit

Use these procedures to remove the axis-4 drive unit.


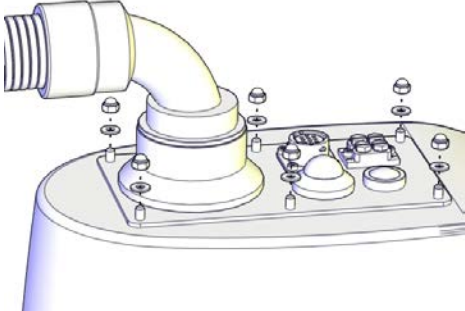

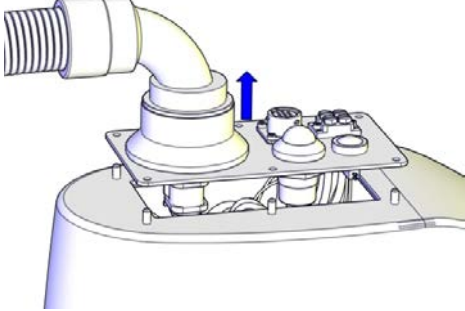
Preparations before removing the axis-4 drive unit

	Action	Note
1	Jog axis 2 to access the cover screws.	 <p>xx1500002520</p> <p>xx1500002782</p>

Continues on next page

	Action	Note
2	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	

Removing the main cable package from the upper arm


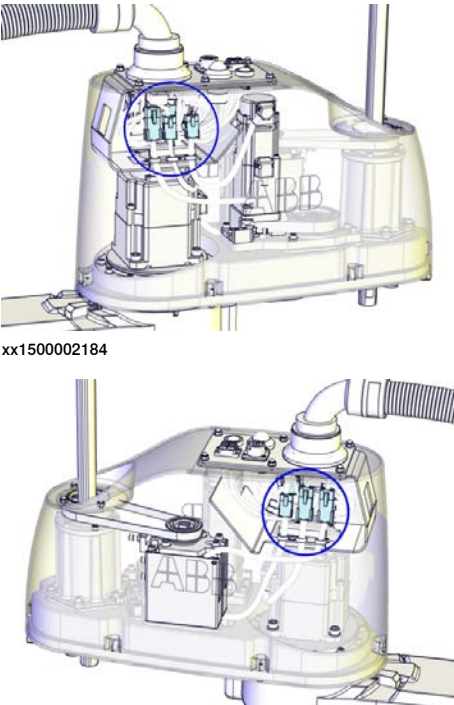
	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p>Remove the dome nuts and washers.</p>	 <p>xx1500002182</p>
3	<p>Carefully open the user interface plate and pull out the cable package.</p> <p> CAUTION</p> <p>The plate cannot be removed completely until the connectors are disconnected, as shown in the following step.</p>	 <p>xx1500002183</p>

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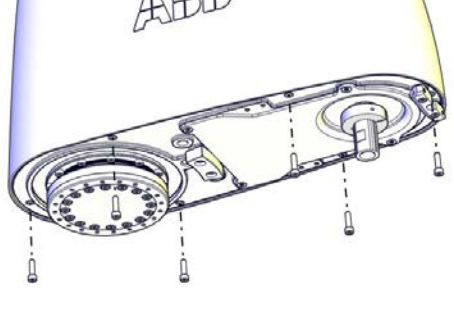
4 Repair

4.6.4 Replacing the axis-4 drive unit


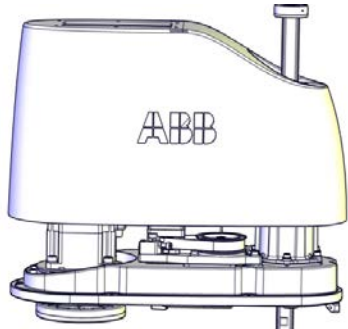
Continued

	Action	Note
4	<p>Disconnect the connectors:</p> <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 <p> Tip</p> <p>Take photos of the connectors and cable position before disconnecting them, to have as a reference when reconnecting.</p>	 <p>xx1500002184</p> <p>xx1500002185</p>



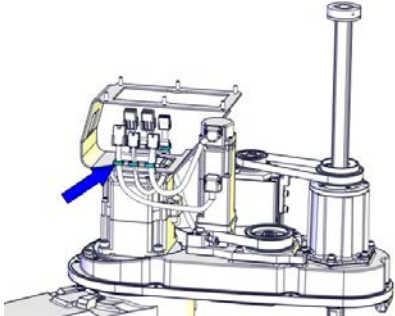
Removing the upper cover

	Action	Note
1	<p> DANGER</p> <p>Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.</p>	
2	<p> WARNING</p> <p>Risk of tipping. Make sure the robot is well secured and that the upper arm is supported during the removal work.</p>	
3	<p>Remove the screws.</p>	 <p>xx1500002220</p>


Continues on next page

	Action	Note
4	 WARNING The cover may be damaged due to improper shift. Keep the cover in position while removing the screws.	
5	Lift out the upper cover carefully.	 xx1500002221

Removing the drive unit cables

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	Cut the cable ties. Be careful not to damage the cabling.  Tip Take photos of the cable position before removing them, to have as a reference when refitting.	 xx1500002226

Removing the lower cover

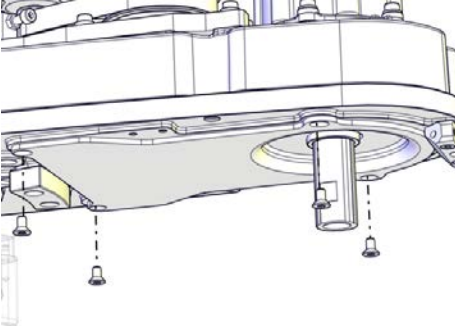

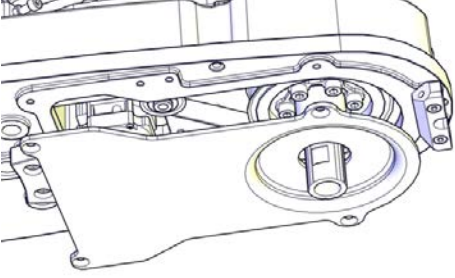
	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	

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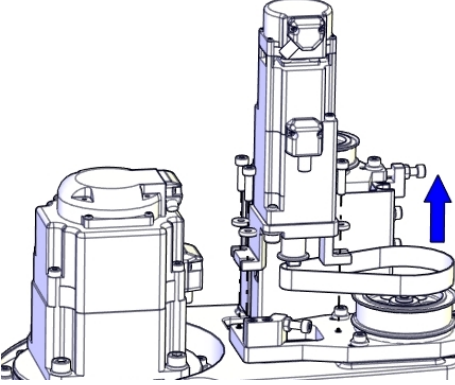
4 Repair

4.6.4 Replacing the axis-4 drive unit

Continued

	Action	Note
2	Remove the screws.	 <p>xx1500002785</p>
3	Remove the cover.  Tip If only working with lower axis-4 timing belt, no need to remove the stop block of ball screw spline unit before removing the lower cover.	 <p>xx1500002225</p>

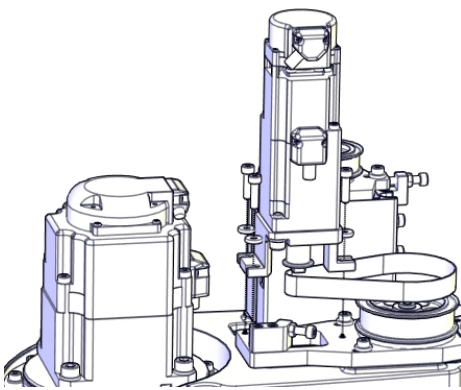
Removing the axis-4 drive unit and upper timing belt

	Action	Note
1	 DANGER Make sure that all supplies for electrical power, hydraulic pressure, and air pressure are turned off.	
2	 WARNING Risk of tipping. Make sure the gravity center is well supported.	
3	Loosen the screws and move the axis-4 drive unit upwards to slacken the upper axis-4 timing belt.	 <p>xx1500002233</p>

Continues on next page

4.6.4 Replacing the axis-4 drive unit

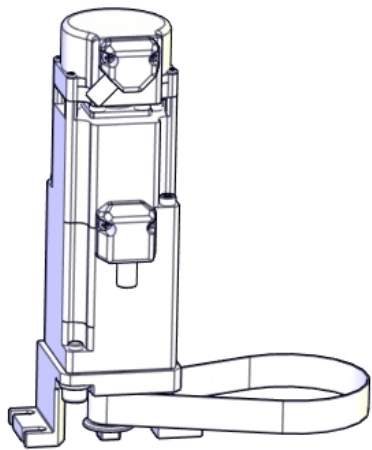
Continued

	Action	Note
4	Remove the drive unit and timing belt.	 <p>xx1500002234</p>

Refitting the axis-4 drive unit

Use these procedures to refit the axis-4 drive unit.

Refitting the axis-4 drive unit and upper timing belt


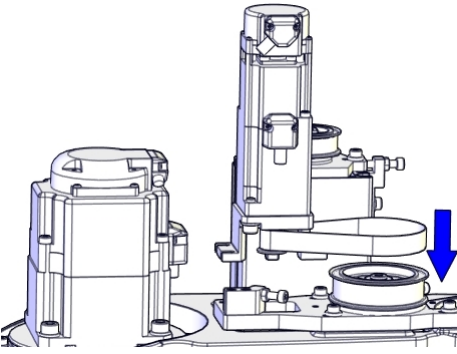
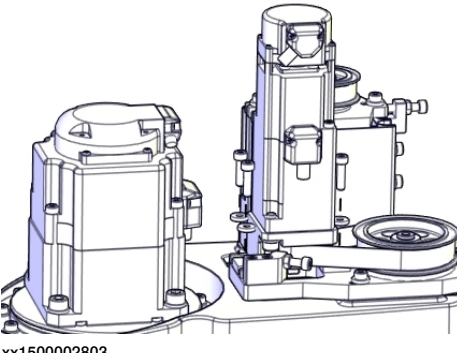

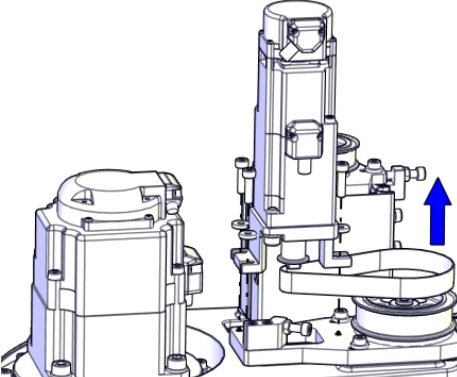
	Action	Note
1	Make sure that: <ul style="list-style-type: none"> • all assembly surfaces are clean and undamaged. • the drive unit is clean and undamaged. 	
2	Place the timing belt.	Axis-4 drive unit: 3HAC056112-001 Upper axis-4 timing belt: 3HAC055206-001  <p>xx1500002801</p>

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4 Repair

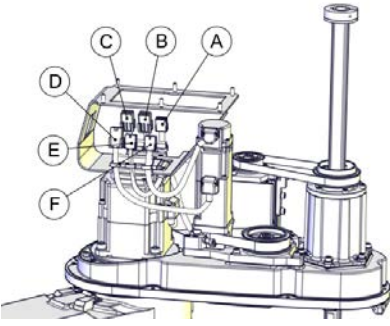
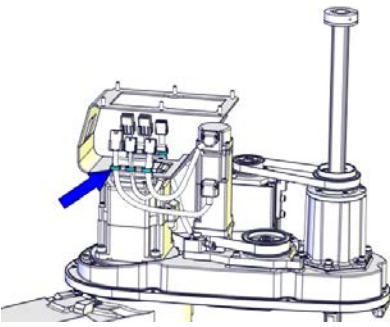
4.6.4 Replacing the axis-4 drive unit

Continued


	Action	Note
3	<p>Refit the drive unit and timing belt.</p> <p> Note</p> <p>Make sure to refit the drive unit with motor connectors pointing against axis-3 drive unit.</p>	 <p>xx1500002802</p>
4	<p>Refit screws and washers just enough to still be able to move the drive unit upwards.</p>	 <p>xx1500002803</p> <p>Screw: M4x16 (3 pcs) Washer (3HAC056937-001, 3 pcs)</p> <p> Note</p> <p>Only use specified washers, never replace them with other washers.</p>
5	<p>Fasten the screws little by little while using a dynamometer to measure the belt tension until a proper belt tension is achieved.</p>	 <p>xx1500002233</p> <p>Belt tension: $F = 37 \text{ N}$ (Recommended) Belt tension range: 24.1 N to 27.6 N (for used timing belt, which has been installed and used for more than 24 hours) 34.5 N to 37.9 N (for new timing belt)</p>

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Securing the drive unit cables

	Action	Note												
1	Put the drive unit cables in place.	 <p>xx150003063</p> <table border="1" data-bbox="973 728 1433 1008"> <tr> <td>A</td> <td>R2.ME3</td> </tr> <tr> <td>B</td> <td>R2.MP2</td> </tr> <tr> <td>C</td> <td>R2.MP3</td> </tr> <tr> <td>D</td> <td>R2.MP4</td> </tr> <tr> <td>E</td> <td>R2.ME2</td> </tr> <tr> <td>F</td> <td>R2. ME4</td> </tr> </table>	A	R2.ME3	B	R2.MP2	C	R2.MP3	D	R2.MP4	E	R2.ME2	F	R2. ME4
A	R2.ME3													
B	R2.MP2													
C	R2.MP3													
D	R2.MP4													
E	R2.ME2													
F	R2. ME4													
2	Secure the cables with cable ties. Do not tighten the ties too tight.	 <p>xx150002226</p>												

Refitting the upper cover


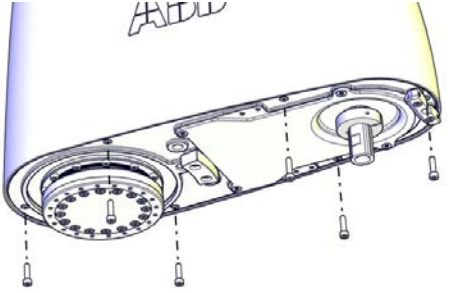
	Action	Note
1	Carefully put down the upper cover, avoiding any collision to the ball screw spline unit and drive units.	<p>Upper cover unit: 3HAC057615-001</p>  <p>xx150002221</p>

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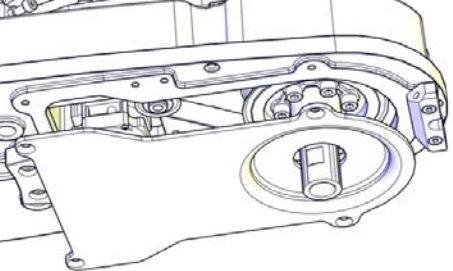
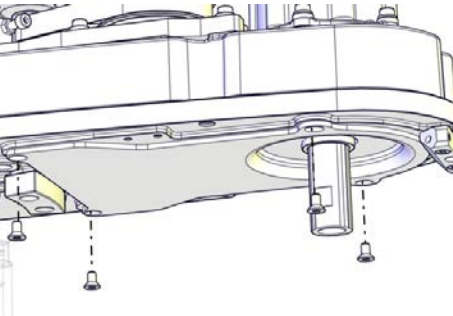
4 Repair

4.6.4 Replacing the axis-4 drive unit

Continued

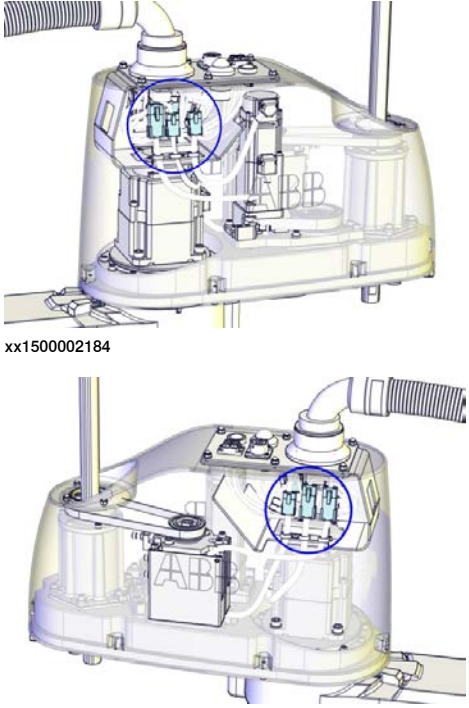
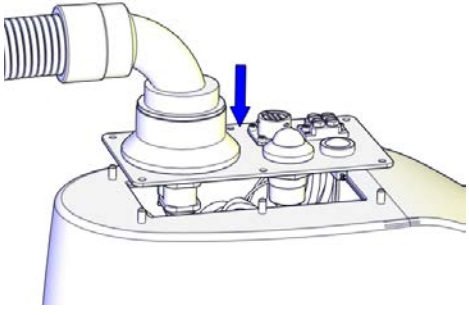
	Action	Note
2	 Tip Some of the screws are accessed from below. Make sure that the robot is properly fastened and hang out the upper arm from the workbench to access them.	
3	Refit the cover.	 <p data-bbox="948 882 1050 904">xx1500002220</p> <p data-bbox="948 920 1182 943">Screw: M4x16 (6 pcs)</p> <p data-bbox="948 954 1214 976">Tightening torque: 2 Nm</p>

Refitting the lower cover

	Action	Note
1	Refit the cover.	<p data-bbox="948 1115 1286 1137">Lower cover: 3HAC060106-001</p>  <p data-bbox="948 1473 1050 1496">xx1500002225</p>
2	Secure with screws.	 <p data-bbox="948 1861 1050 1883">xx1500002785</p> <p data-bbox="948 1899 1166 1921">Screw: M4x8 (4 pcs)</p> <p data-bbox="948 1933 1214 1955">Tightening torque: 2 Nm</p>

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Refitting the main cable to the upper arm

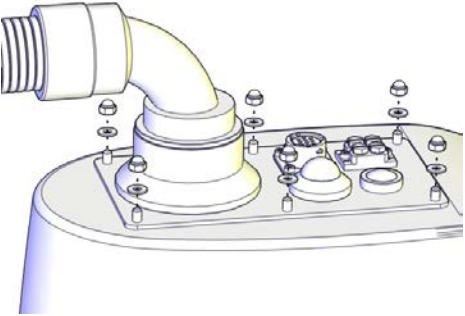
	Action	Note
1	Secure the main cable package with cable ties if needed.	
2	Reconnect the connectors. <ul style="list-style-type: none"> • R2.MP2 • R2.MP3 • R2.MP4 • R2.ME2 • R2.ME3 • R2.ME4 	 <p>xx1500002184</p> <p>xx1500002185</p>
3	Push the main cable package into place.	 <p>xx1500002207</p>

Continues on next page


4 Repair

4.6.4 Replacing the axis-4 drive unit

Continued

	Action	Note
4	Refit the user interface plate.	 <p>xx1500002182</p> <p>Dome nut: M4 (6 pcs) Tightening torque: 2 Nm Washer, 6 pcs</p>

Concluding procedure

	Action	Note
1	Recalibrate the robot.	Calibration is detailed in section Calibration on page 345 .
2	 <p>DANGER</p> <p>Make sure all safety requirements are met when performing the first test run. These are further detailed in the section "First test run may cause injury or damage" in <i>Safety manual for robot - Manipulator and IRC5 or OmniCore controller</i>.</p>	

5 Calibration

5.1 Introduction to calibration

5.1.1 Introduction and calibration terminology

Calibration information

This chapter includes general information about the recommended calibration methods and also the detailed procedures for updating the revolution counters, checking the calibration position etc.

Calibration terminology

Term	Definition
Calibration method	A collective term for several methods that might be available for calibrating the ABB robot. Each method contains calibration routines.
Synchronization position	Known position of the complete robot where the angle of each axis can be checked against visual synchronization marks.
Calibration position	Known position of the complete robot that is used for calibration of the robot.
Standard calibration	A generic term for all calibration methods that aim to move the robot to calibration position.
Fine calibration	A calibration routine that generates a new zero position of the robot.
Reference calibration	<p>A calibration routine that in the first step generates a reference to current zero position of the robot. The same calibration routine can later on be used to recalibrate the robot back to the same position as when the reference was stored.</p> <p>This routine is more flexible compared to fine calibration and is used when tools and process equipment are installed.</p> <p>Requires that a reference is created before being used for recalibrating the robot.</p> <p>Requires that the robot is dressed with the same tools and process equipment during calibration as during creation of the reference values.</p>
Update revolution counter	A calibration routine to make a rough calibration of each manipulator axis.
Synchronization mark	Visual marks on the robot axes. When marks are aligned, the robot is in synchronization position.

5 Calibration


5.1.2 Calibration methods

5.1.2 Calibration methods

Overview

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

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, <code>calib.cfg</code>, supplied with the robot at delivery. The file identifies the correct resolver/motor position corresponding to the robot home position.</p>	Manual calibration
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, <code>absacc.cfg</code>, supplied with the robot at delivery. The file replaces the <code>calib.cfg</code> 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>  <p>xx0400001197</p>	CalibWare

Continues on next page

Brief description of calibration methods

Manual calibration method

With the manual calibration method, the robot's axes are positioned in specific calibration positions using calibration tools. Under this condition, the position of the axis to be calibrated is pre-determined. The axes must be calibrated one at a time.

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.

References

Article numbers for the calibration tools are listed in the section [Special tools on page 387](#).

5 Calibration

5.1.3 When to calibrate

5.1.3 When to calibrate

When to calibrate

The system must be calibrated if any of the following situations occur.

The resolver values are changed

If resolver values are changed, the robot must be re-calibrated using the calibration methods supplied by ABB. Calibrate the robot carefully with standard calibration, according to information in this manual.

If the robot has *absolute accuracy* calibration, it is also recommended, but not always necessary to calibrate for new absolute accuracy.

The resolver values will change when parts affecting the calibration position are replaced on the robot, for example motors or parts of the transmission.

The revolution counter memory is lost

If the revolution counter memory is lost, the counters must be updated. See [Updating revolution counters on page 351](#). This will occur when:

- The battery is discharged
- A resolver error occurs
- The signal between a resolver and measurement board is interrupted
- A robot axis is moved with the control system disconnected

The revolution counters must also be updated after the robot and controller are connected at the first installation.

The robot is rebuilt

If the robot is rebuilt, for example, after a crash or when the reach ability of a robot is changed, it needs to be re-calibrated for new resolver values.

If the robot has *absolute accuracy* calibration, it needs to be calibrated for new absolute accuracy.

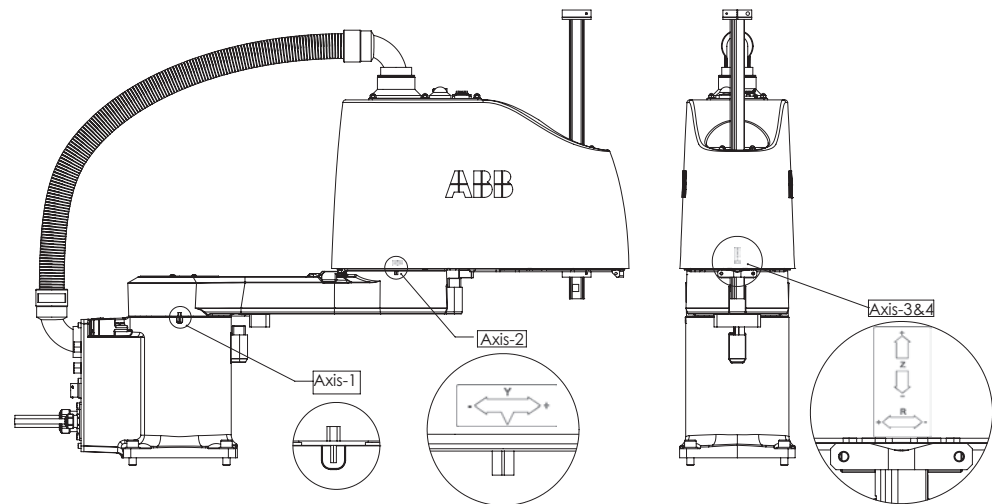
5.2 Synchronization marks and axis movement directions

5.2.1 Synchronization marks and synchronization position for axes

Introduction

This section shows the position of the synchronization marks and the synchronization position for each axis.

Synchronization marks, IRB 910SC



xx1500002634

5 Calibration

5.2.2 Calibration movement directions for all axes

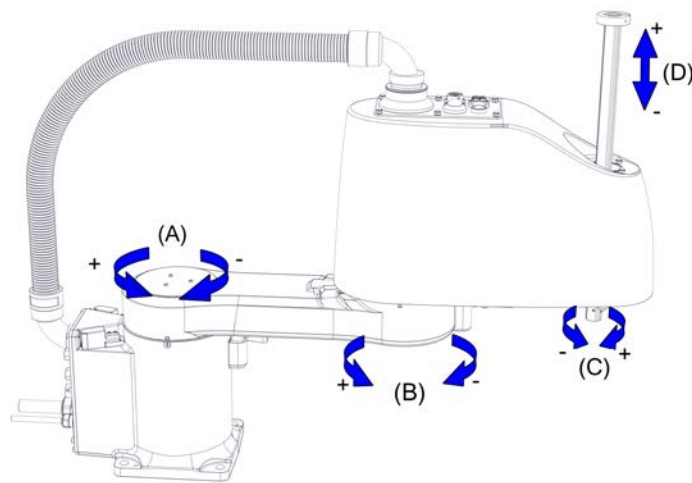
5.2.2 Calibration movement directions for all axes

Overview

When calibrating, the axis must consistently be run towards the calibration position in the same direction in order to avoid position errors caused by backlash in gears and so on. Positive directions are shown in the graphic below.

Calibration service routines will handle the calibration movements automatically and these might be different from the positive directions shown below.

Manual movement directions



xx1500002631

Position	Description	Position	Description
A	Axis 1	B	Axis 2
C	Axis 4	D	Axis 3

5.3 Updating revolution counters

Introduction

This section describes how to do a rough calibration of each manipulator axis by updating the revolution counter for each axis, using the FlexPendant.

Coupled axes

When updating the revolution counters for a coupled axis, also the axis it is coupled to needs to be at its synchronization position for the update to be correct; i.e. axis 4 needs to be in synchronization position when updating axis 5 and 6.

With reversed coupled joints, the relationship is the opposite, i.e. axis 4 needs to be in synchronization position to update axis 3.

Coupled axes	IRB 140	IRB 1410	IRB 1520	IRB 1600	IRB 1600ID	IRB 1660ID	IRB 910 SC	IRB 2400	IRB 2600	IRB 2600ID	IRB 4400	IRB 4450S	IRB 4600
Axis 4, 5, 6	x			x				x	x		x	x	x
Axis 5, 6		x	x		x	x				x			
Axis 4, 3							x						

Step 1 - Manually running the manipulator to the synchronization position

Use this procedure to manually run the manipulator to the synchronization position.

	Action	Note
1	Select axis-by-axis motion mode.	
2	Jog the manipulator to align the synchronization marks.	See Synchronization marks and synchronization position for axes on page 349 .
3	When all axes are positioned, update the revolution counter.	Step 2 - Updating the revolution counter with the FlexPendant on page 352 .

Continues on next page

5 Calibration

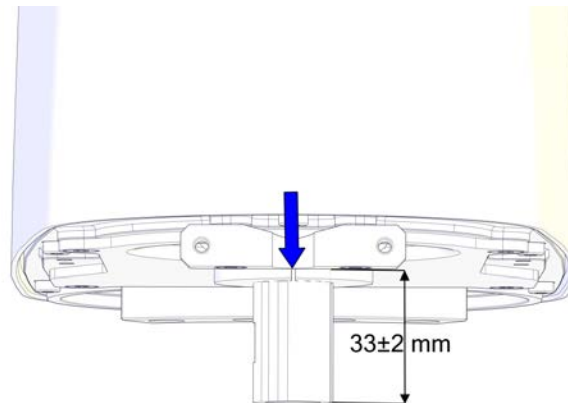
5.3 Updating revolution counters

Continued

Correct calibration position of axes 3 and 4

When jogging the manipulator to synchronization position, it is extremely important to make sure that axes 3 and 4 are positioned correctly. Axis 4 can be calibrated at the wrong turn, resulting in an incorrect axis 3 calibration position and manipulator calibration.

Make sure the notch on the stop block points to the center of fixing calibration block, and the distance between lower surfaces of shaft and fixing calibration block is 33 mm.



xx1500002907

At delivery the manipulator is in the correct position. Do NOT shift axis 3 or rotate axis 4 at power up before the revolution counters are updated.

If axis 4 is rotated one or more turns from its calibration position before updating the revolution counter, the correct calibration position will be lost due to non-integer gear ratio. This will further affect the calibration position of axis 3.

Step 2 - Updating the revolution counter with the FlexPendant

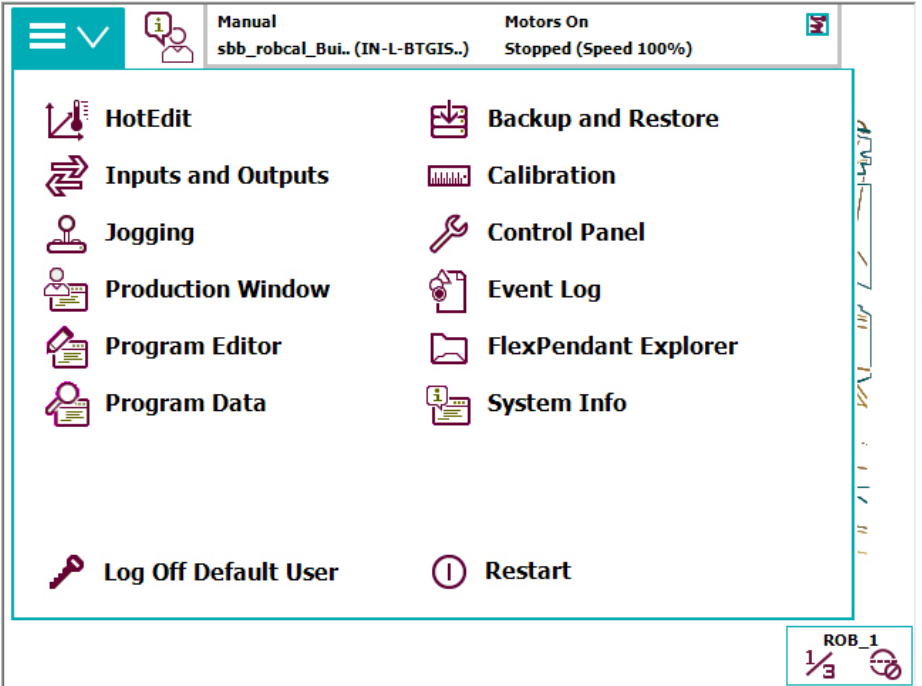
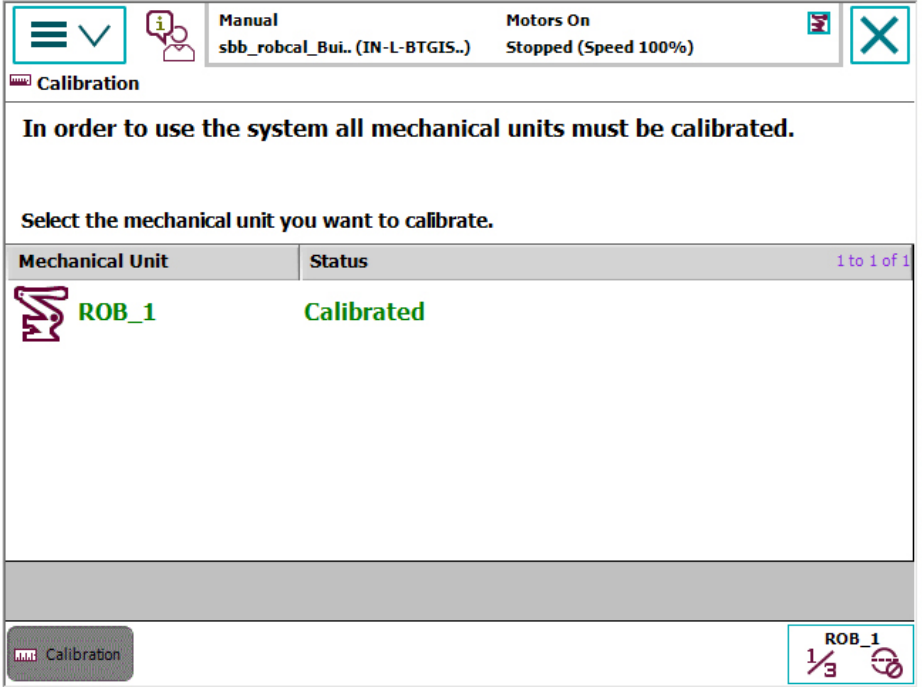


Note

Revolution counters of axes 3 and 4 must be updated together.

Continues on next page

Use this procedure to update the revolution counter with the FlexPendant (IRC5).

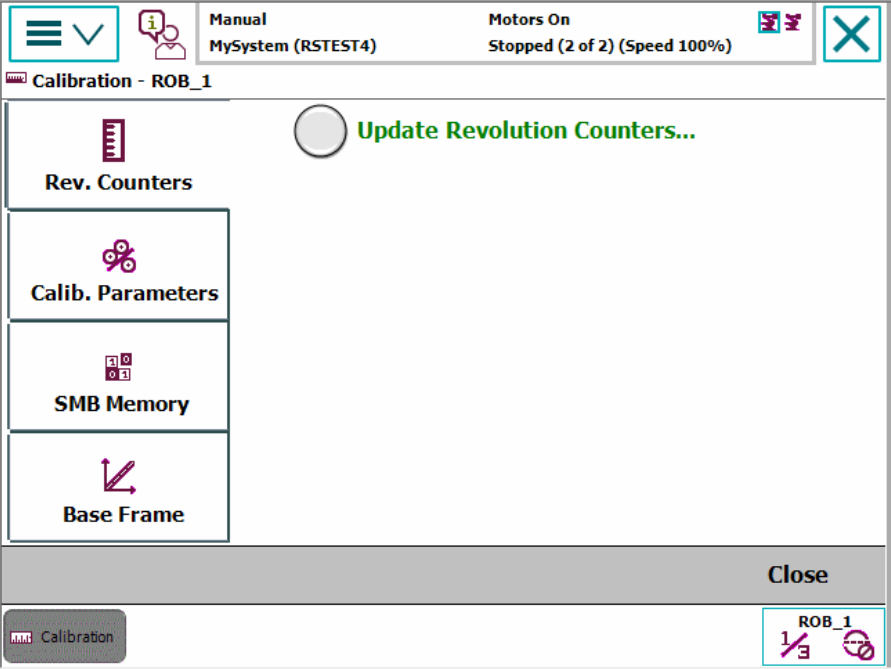

Action					
1	<p>On the ABB menu, tap Calibration.</p>  <p>xx1500000942</p>				
2	<p>All mechanical units connected to the system are shown with their calibration status. Tap the mechanical unit in question.</p>  <table border="1"> <thead> <tr> <th>Mechanical Unit</th> <th>Status</th> </tr> </thead> <tbody> <tr> <td>ROB_1</td> <td>Calibrated</td> </tr> </tbody> </table> <p>xx1500000943</p>	Mechanical Unit	Status	ROB_1	Calibrated
Mechanical Unit	Status				
ROB_1	Calibrated				

Continues on next page

5 Calibration

5.3 Updating revolution counters

Continued

	Action
3	<p>A screen is displayed, tap Rev. Counters.</p>  <p>en040000771</p>
4	<p>Tap Update Revolution Counters....</p> <p>A dialog box is displayed, warning that updating the revolution counters may change programmed robot positions:</p> <ul style="list-style-type: none">• Tap Yes to update the revolution counters.• Tap No to cancel updating the revolution counters. <p>Tapping Yes displays the axis selection window.</p>
5	<p>Select the axis to have its revolution counter updated by:</p> <ul style="list-style-type: none">• Ticking in the box to the left• Tapping Select all to update all axes. <p>Then tap Update.</p>
6	<p>A dialog box is displayed, warning that the updating operation cannot be undone:</p> <ul style="list-style-type: none">• Tap Update to proceed with updating the revolution counters.• Tap Cancel to cancel updating the revolution counters. <p>Tapping Update updates the selected revolution counters and removes the tick from the list of axes.</p>
7	<p> CAUTION</p> <p>If a revolution counter is incorrectly updated, it will cause incorrect manipulator positioning, which in turn may cause damage or injury!</p> <p>Check the synchronization position very carefully after each update. See Checking the synchronization position on page 373.</p>

5.4 Calibrating the robot

5.4.1 Calibration position

Calibration position

The position of the axis to be calibrated is illustrated in each calibration section respectively.

The table below specifies the exact axis positions in degrees.

Axis	IRB 910SC-3/0.45	IRB 910SC-3/0.55	IRB 910SC-3/0.65
1	-6.9199168°	-6.9199168°	-6.9199168°
2	-7.12701982°	-7.12701982°	-7.12701982°
3	0 mm	0 mm	0 mm
4	0°	0°	0°

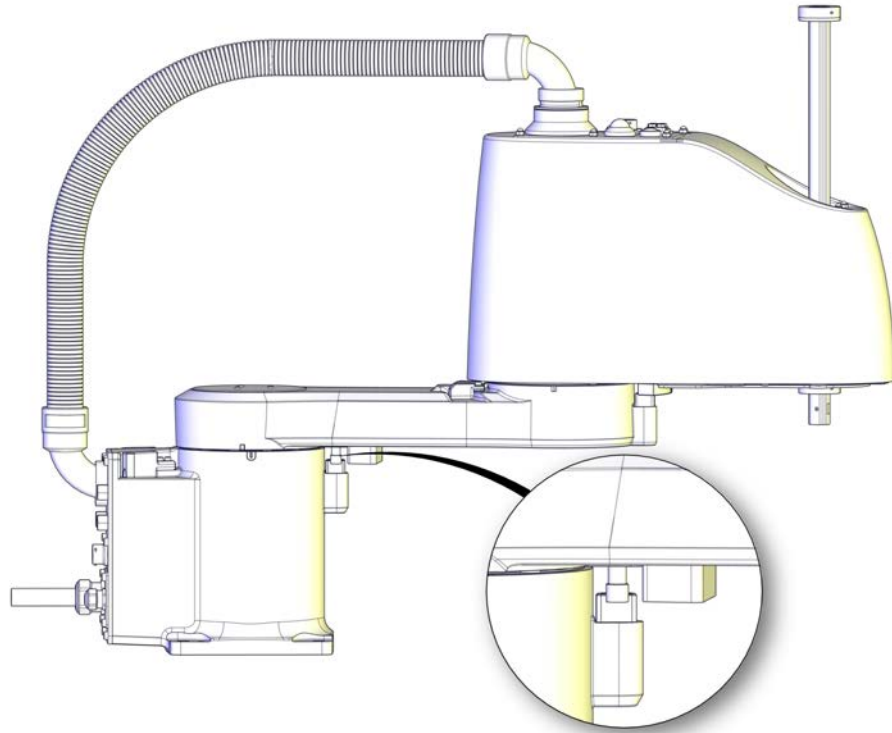
5 Calibration

5.4.2 Calibrating axis 1

5.4.2 Calibrating axis 1

Calibration position of axis 1

The figure shows axis 1 in calibration position, with calibration tools fitted.



xx1500002512

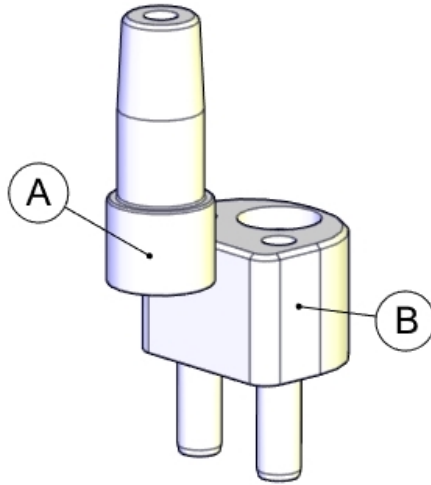
Required equipment

Calibration of axis 1 is done by moving the lower arm so that the moving calibration pin and calibration block touches each other gently.

The calibration block is already fitted to the robot.

Continues on next page

See figures below for reference, and follow the step-by-step procedure that follows.



xx1500002516

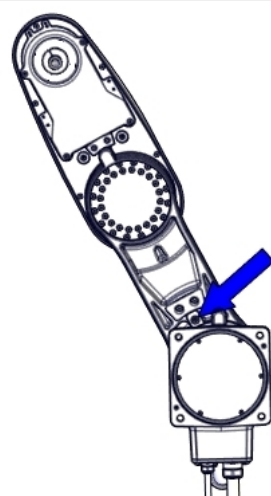
A	Moving calibration pin
B	Calibration block

Required consumables

Equipment	Art. no.	Note
Cleaning agent	-	Isopropanol

Calibrating axis 1

Moving the robot to calibration position


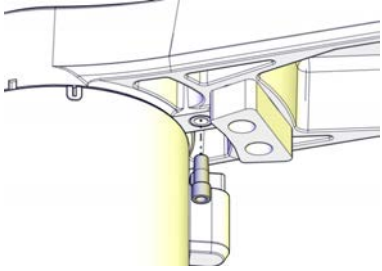

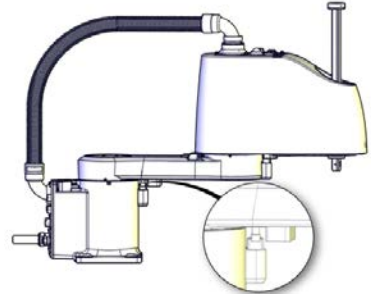

	Action	Note
1	Jog axis 1 to a suitable position where the calibration pin can be fitted in to the press fit bushing.	 <p>xx1500002808</p>

Continues on next page

5 Calibration


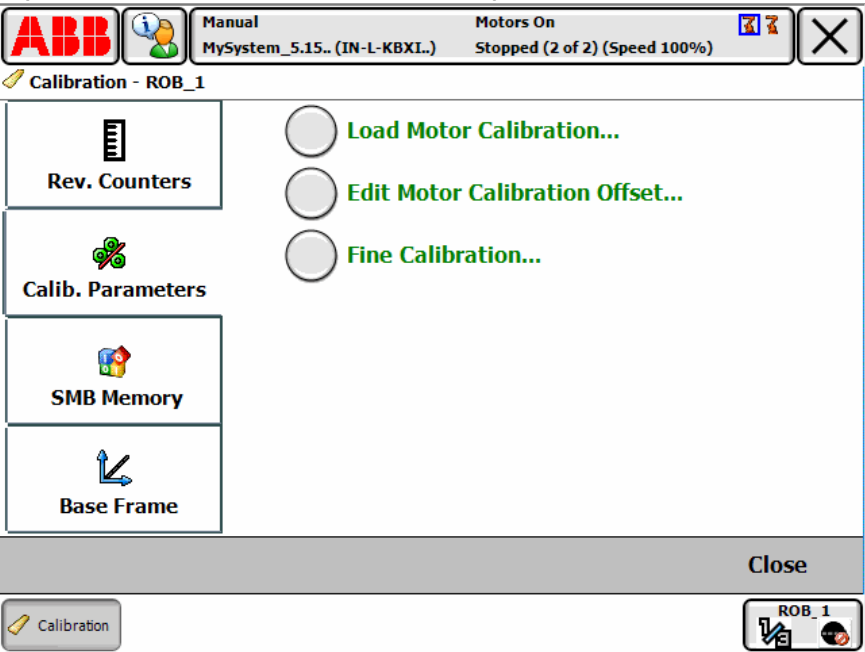
5.4.2 Calibrating axis 1

Continued

	Action	Note
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	Fit the calibration pin to the press fit bushing.	 xx1500002509
4	Turn on the electric power to the robot.	
5	 DANGER When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways! Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.	
6	Release the brakes and manually rotate axis 1 until the calibration pin touches the calibration block gently. There should be no pressing force between them.	See Manually releasing the brakes on page 61 .  xx1500002508
7	 CAUTION Pay attention to robot pose in order to avoid arm collision.	
8	Release the brake release button to activate the brakes.	

Continues on next page

Performing the fine calibration procedure

	Action	Note
1	 WARNING Do not fine calibrate the robot without special equipment used for axis calibration! It would cause an unsatisfied accuracy in the robot movement.	
2	Choose fine calibration from Calib menu. On the ABB menu, tap Calibration . All mechanical units connected to the system are shown along with their calibration status.	
3	Tap to select the mechanical unit and then tap Calib. Parameters . 	
4	Tap Fine Calibration.... A dialog box is displayed, urging you to use external equipment to perform the actual calibration. Make sure all necessary calibration equipment is fitted for the axis to be calibrated. A dialog box is displayed, warning that updating the revolution counters may change programmed robot positions: <ul style="list-style-type: none"> • Tap Yes to proceed. • Tap No to cancel. 	
5	Select the check-box for the current axis/axes to be calibrated.	

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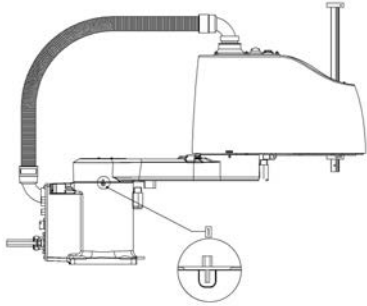
5 Calibration

5.4.2 Calibrating axis 1

Continued

	Action	Note
6	<p>Tap Calibrate.</p> <p>A dialog box is displayed, warning that calibration of the selected axes will be changed, which cannot be undone:</p> <ul style="list-style-type: none"> • Tap Calibrate to proceed. • Tap Cancel to cancel. <p>Tapping Calibrate results in briefly displaying a dialog box, announcing that the calibration process has started.</p> <p>The axis is calibrated and the system returns to the list of available mechanical units.</p>	

Checking and finalizing the calibration

	Action	Note
1	 <p>DANGER</p> <p>Always remember to remove the calibration tools from the robot before jogging axes to zero position during calibration.</p>	
2	<p>Release the brakes and manually rotate the axis to apart the calibration pins from each other. This is done to avoid damage on the pins if incorrect operation should occur during next step of jogging.</p>	
3	<p>Jog axis 1 to zero degree using the FlexPendant.</p>	
4	<p>Check that the synchronization marks on axis 1 are aligned with each other.</p> <p>Are they aligned within the tolerances?</p> <ul style="list-style-type: none"> • If yes, the calibration is verified OK. • If no, redo the fine calibration procedure. 	 <p>xx1500002514</p>

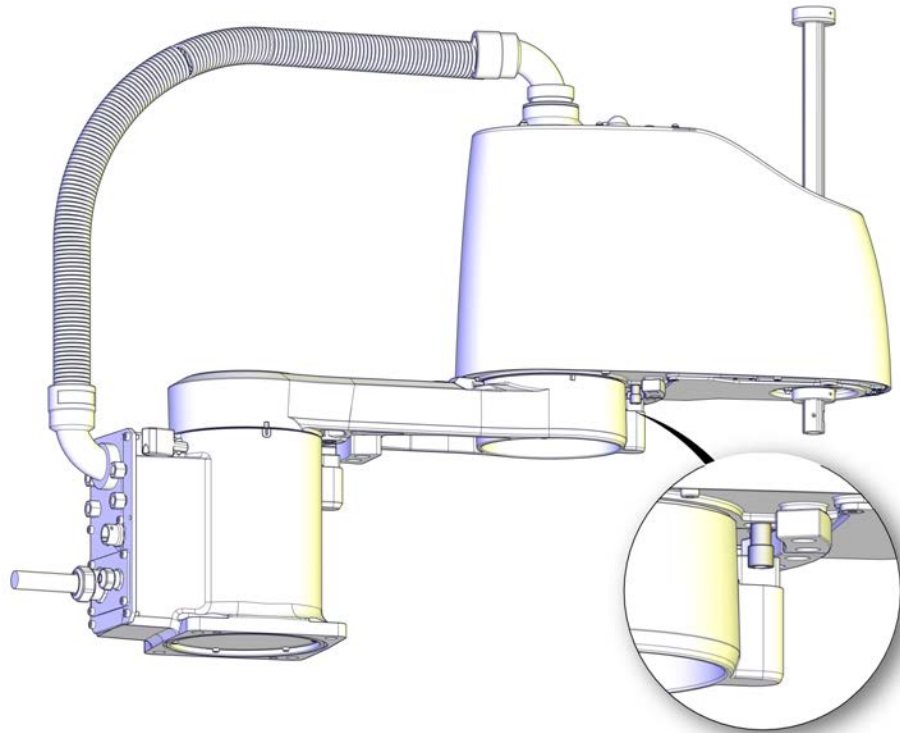
After calibration

	Action	Note
1	<p>Write down the new system parameters on a new label and stick on top of the calibration label on the robot.</p>	

5.4.3 Calibrating axis 2

Calibration position of axis 2

The figure shows axis 2 in calibration position.



xx1500002513

Required equipment

Calibration of axis 2 is done by moving the lower arm so that the moving calibration pin and calibration block touches each other gently.

The calibration block is already fitted to the robot.

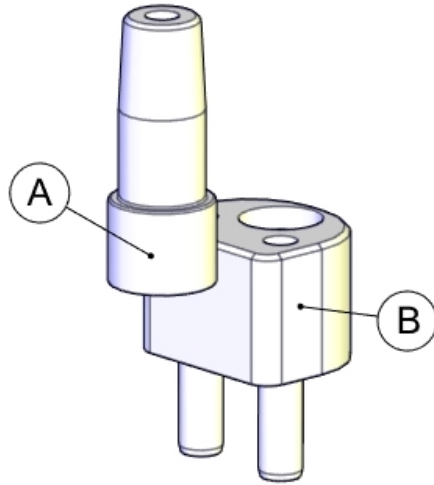
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5 Calibration

5.4.3 Calibrating axis 2

Continued

See figures below for reference, and follow the step-by-step procedure that follows.



xx1500002516

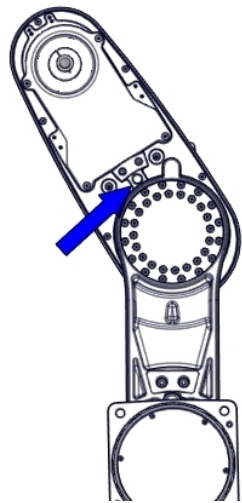
A	Moving calibration pin
B	Calibration block

Required consumables


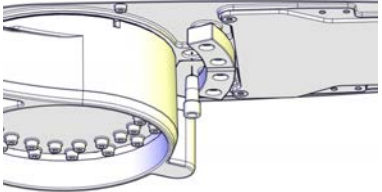

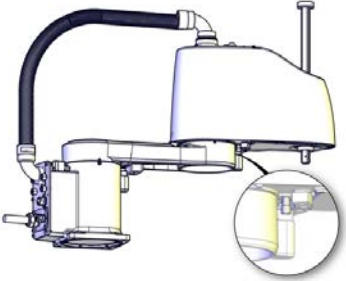

Equipment	Art. no.	Note
Cleaning agent	-	Isopropanol

Calibrating axis 2

Moving the robot to calibration position

	Action	Note
1	Jog axis 2 to a suitable position where the calibration pin can be fitted to the press fit bushing.	 <p>xx1500002809</p>

Continues on next page

	Action	Note
2	 DANGER Turn off all: <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	Fit the calibration pin to the press fit bushing.	 xx1500002511
4	Turn on the electric power to the robot.	
5	 DANGER When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways! Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.	
6	Release the brakes and manually rotate axis 2 until the calibration pin touches the calibration block gently. There should be no pressing force between them.	See Manually releasing the brakes on page 61 .  xx1500002510
7	 CAUTION Pay attention to robot pose in order to avoid arm collision.	
8	Release the brake release button to activate the brakes.	


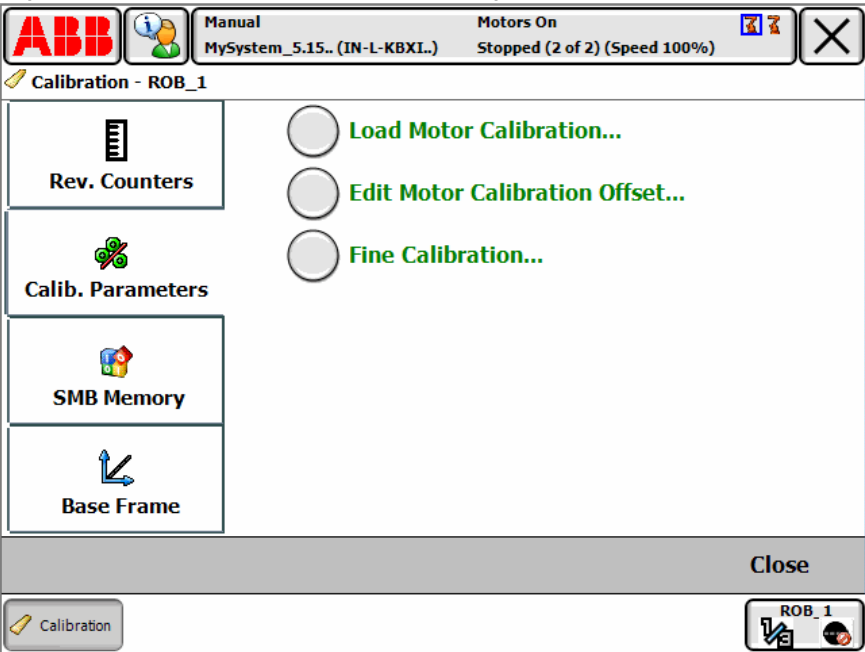
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5 Calibration

5.4.3 Calibrating axis 2

Continued


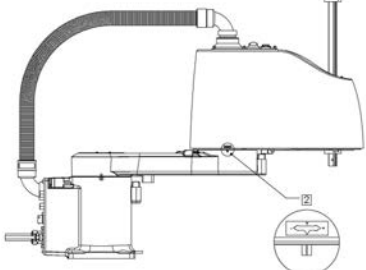
Performing the fine calibration procedure

	Action	Note
1	 WARNING Do not fine calibrate the robot without special equipment used for axis calibration! It would cause an unsatisfied accuracy in the robot movement.	
2	Choose fine calibration from Calib menu. On the ABB menu, tap Calibration . All mechanical units connected to the system are shown along with their calibration status.	
3	Tap to select the mechanical unit and then tap Calib. Parameters . 	
4	Tap Fine Calibration.... A dialog box is displayed, urging you to use external equipment to perform the actual calibration. Make sure all necessary calibration equipment is fitted for the axis to be calibrated. A dialog box is displayed, warning that updating the revolution counters may change programmed robot positions: <ul style="list-style-type: none"> • Tap Yes to proceed. • Tap No to cancel. 	
5	Select the check-box for the current axis/axes to be calibrated.	

Continues on next page

	Action	Note
6	<p>Tap Calibrate.</p> <p>A dialog box is displayed, warning that calibration of the selected axes will be changed, which cannot be undone:</p> <ul style="list-style-type: none"> • Tap Calibrate to proceed. • Tap Cancel to cancel. <p>Tapping Calibrate results in briefly displaying a dialog box, announcing that the calibration process has started.</p> <p>The axis is calibrated and the system returns to the list of available mechanical units.</p>	

Checking and finalizing the calibration

	Action	Note
1	 <p>DANGER</p> <p>Always remember to remove the calibration tools from the robot before jogging axes to zero position during calibration.</p>	
2	<p>Release the brakes and manually rotate the axis to apart the calibration pins from each other. This is done to avoid damage on the pins if incorrect operation should occur during next step of jogging.</p>	
3	<p>Jog axis 2 to zero degree using the FlexPendant.</p>	
4	<p>Check that the synchronization marks on axis 2 are aligned with each other.</p> <p>Are they aligned within the tolerances?</p> <ul style="list-style-type: none"> • If yes, the calibration is verified OK. • If no, redo the fine calibration procedure. 	 <p>xx1500002515</p>

After calibration

	Action	Note
1	<p>Write down the new system parameters on a new label and stick on top of the calibration label on the robot.</p>	

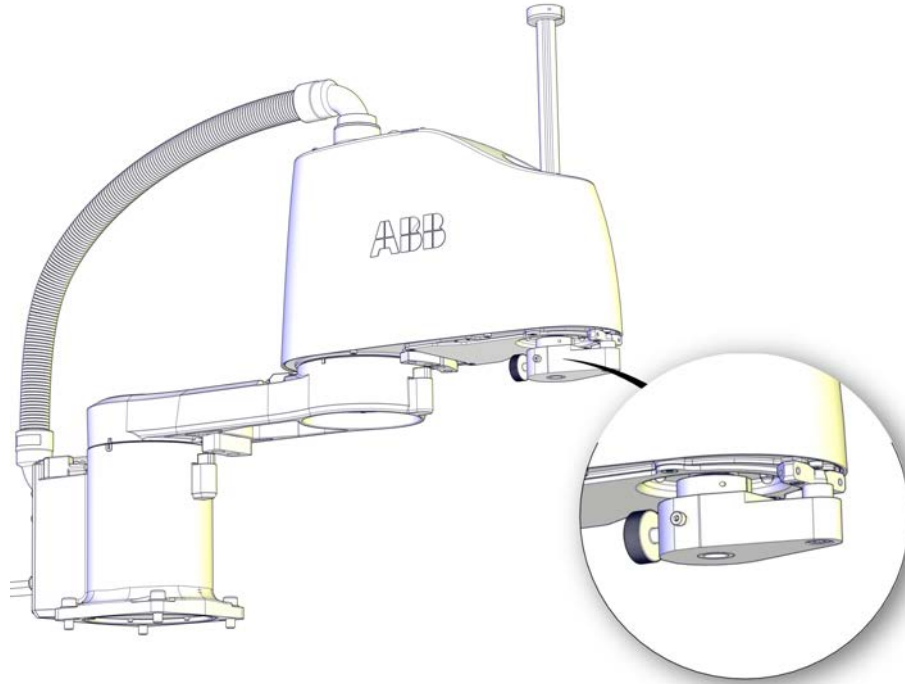
5 Calibration

5.4.4 Calibrating axis 3 and axis 4

5.4.4 Calibrating axis 3 and axis 4

Calibration position of axis 3 and axis 4

The figure shows axis 3 and axis 4 in calibration position. The axes 3 and 4 are calibrated together.



xx1500002499

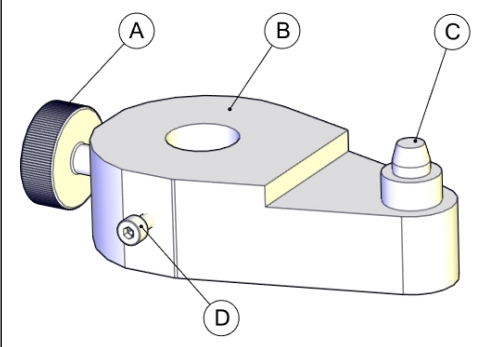
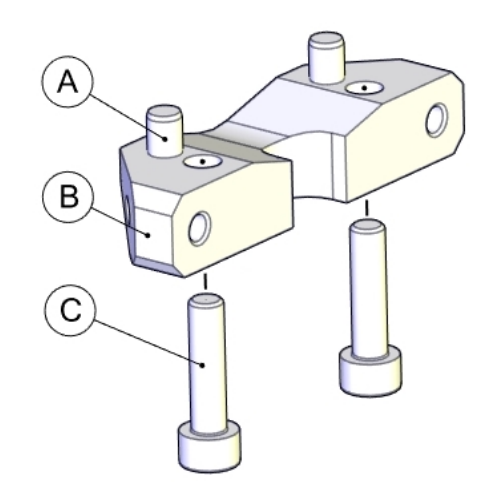
Required equipment

Axes 3 and 4 are calibrated together. The calibration is done by moving the ball screw spline unit so that the calibration pin on the moving calibration block and the fixing calibration block touch each other gently.

The fixing calibration block is already fitted to the robot.

Continues on next page

See figures below for reference, and follow the step-by-step procedure that follows the figures.

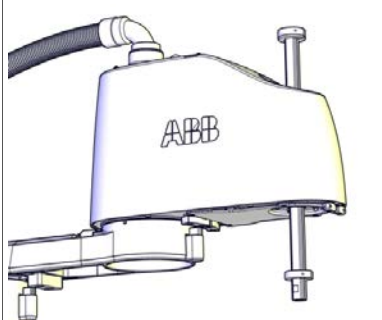
Moving calibration block (including calibration pin, knob and adjusting screw)	Fixing calibration block (including parallel pins and attachment screws)
 <p>xx1500002500</p> <ul style="list-style-type: none"> A Knob B Moving calibration block C Calibration pin D Screw 	 <p>xx1500002501</p> <ul style="list-style-type: none"> A Parallel pin B Fixing block C Screw

Required consumables

Equipment	Art. no.	Note
Cleaning agent	-	Isopropanol

Calibrating axis 3 and axis 4

Moving the robot to calibration position


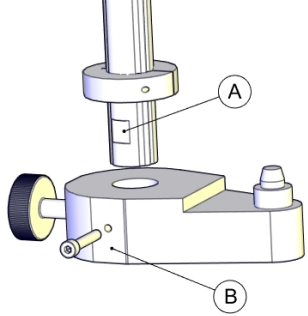
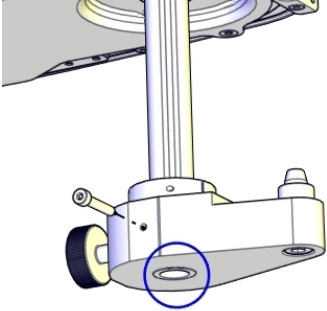
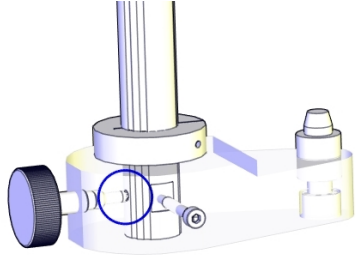
	Action	Note
1	Jog axis 3 and axis 4 to find a suitable position where axis-3/4 calibration tools can be fitted.	 <p>xx1500002502</p>

Continues on next page



5 Calibration

5.4.4 Calibrating axis 3 and axis 4


Continued

	Action	Note
2	<p> DANGER</p> <p>Turn off all:</p> <ul style="list-style-type: none"> • electric power supply • hydraulic pressure supply • air pressure supply <p>to the robot, before entering the robot working area.</p>	
3	<p>Fit the moving calibration block with its flat part aligned with the shaft flat mark.</p>	 <p>xx1500002503</p> <p>A Shaft flat mark B Block flat part</p>
4	<p>When the lower surfaces of the shaft and block are at the same level, tighten the screw slowly to a degree just enough to ensure the block not drop.</p>	 <p>xx1500002504</p>
5	<p>Turn the knob gently until its sphere head is properly inserted into the conical hole.</p>	 <p>xx1500002505</p>
6	<p>Tighten the screw to lock the block on the shaft.</p>	
7	<p>Turn on the electric power to the robot.</p>	

Continues on next page

	Action	Note
8	 <p>DANGER</p> <p>When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways!</p> <p>Make sure the payload is disassembled or tooling is properly supported; otherwise, fast downward movements of axis 3 may cause severe hits.</p>	
9	<p>Release the brakes and manually move the ball screw spline up and down until:</p> <ul style="list-style-type: none"> the calibration pin on the moving calibration block locates in the groove of the fixing calibration block and; the contact surfaces of the calibration pin and fixing calibration block touches each other gently; there should be no pressing force between the surfaces. <p>When doing this, pay attention to robot pose in order to avoid arm collision.</p> <p>When the axes are in position, release the brake release button to activate the brakes again.</p>	<p>How to release the brakes is detailed in Manually releasing the brakes on page 61.</p>  <p>xx1500002506</p>

Performing the fine calibration procedure

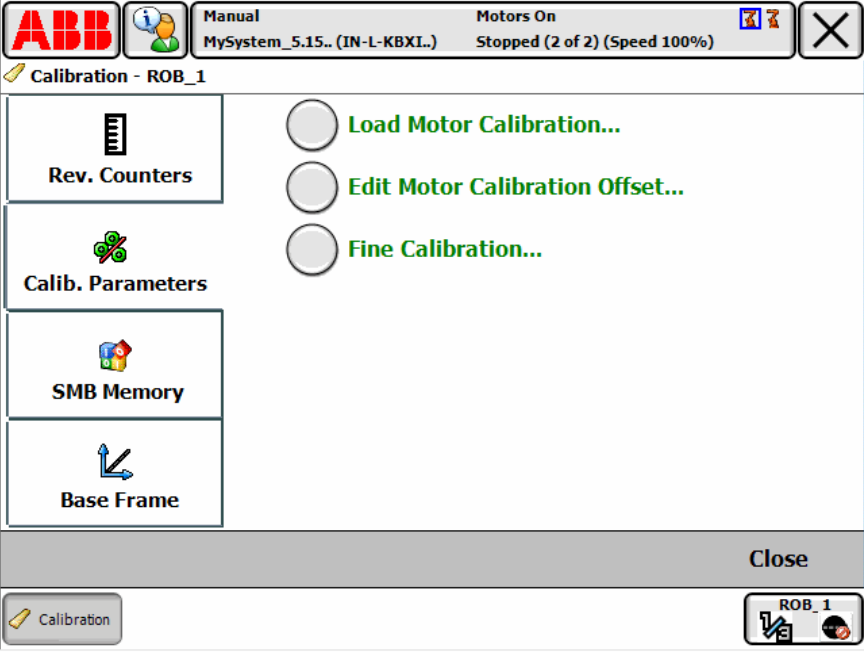
	Action	Note
1	 <p>WARNING</p> <p>Do not fine calibrate the robot without special equipment used for axis calibration! It would cause an unsatisfied accuracy in the robot movement.</p>	
2	<p>Choose fine calibration from Calib menu.</p> <p>On the ABB menu, tap Calibration.</p> <p>All mechanical units connected to the system are shown along with their calibration status.</p>	

Continues on next page

5 Calibration


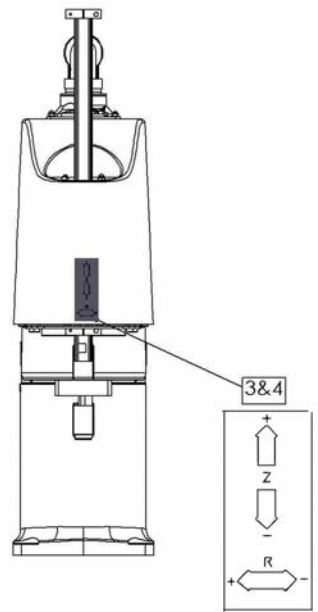
5.4.4 Calibrating axis 3 and axis 4

Continued

	Action	Note
3	<p>Tap to select the mechanical unit and then tap Calib. Parameters.</p>  <p>en0400001127</p>	
4	<p>Tap Fine Calibration....</p> <p>A dialog box is displayed, urging you to use external equipment to perform the actual calibration. Make sure all necessary calibration equipment is fitted for the axis to be calibrated.</p> <p>A dialog box is displayed, warning that updating the revolution counters may change programmed robot positions:</p> <ul style="list-style-type: none"> • Tap Yes to proceed. • Tap No to cancel. 	
5	<p>Select the check-box for the current axis/axes to be calibrated.</p>	
6	<p>Tap Calibrate.</p> <p>A dialog box is displayed, warning that calibration of the selected axes will be changed, which cannot be undone:</p> <ul style="list-style-type: none"> • Tap Calibrate to proceed. • Tap Cancel to cancel. <p>Tapping Calibrate results in briefly displaying a dialog box, announcing that the calibration process has started.</p> <p>The axis is calibrated and the system returns to the list of available mechanical units.</p>	

Continues on next page

Checking and finalizing the calibration

	Action	Note
1	 DANGER Always remember to remove the calibration tools from the robot before jogging axes to zero position during calibration.	
2	Release the brakes and manually rotate the axis to apart the calibration pins from each other. This is done to avoid damage on the pins if incorrect operation should occur during next step of jogging.	
3	Jog axes 3 and 4 to zero degree using the Flex-Pendant.	
4	Check that the synchronization marks on axes 3 and 4 are aligned with each other. Are they aligned within the tolerances? <ul style="list-style-type: none"> • If yes, the calibration is verified OK. • If no, redo the fine calibration procedure. 	 <p>xx1500002507</p>

After calibration

	Action	Note
1	Write down the new system parameters on a new label and stick on top of the calibration label on the robot.	

5 Calibration

5.5 Verifying the calibration

5.5 Verifying the calibration

Introduction

Always verify the results after calibrating *any* robot axis to verify that all calibration positions are correct.

Verifying the calibration

Use this procedure to verify the calibration result.

	Action	Note
1	Run the calibration home position program twice. Do not change the position of the robot axes after running the program!	See Checking the synchronization position on page 373 .
2	Adjust the <i>synchronization marks</i> when the calibration is done, if necessary.	This is detailed in section Synchronization marks and synchronization position for axes on page 349 .
3	Write down the values on a new label and stick it on top of the calibration label. The label is located on the base.	
4	Remove any calibration equipment from the robot.	

5.6 Checking the synchronization position

Introduction

Check the synchronization position of the robot before beginning any programming of the robot system. This may be done:

- Using a `MoveAbsJ` instruction with argument zero on all axes.
- Using the **Jogging** window on the FlexPendant.

Using a `MoveAbsJ` instruction

Use this procedure to create a program that runs all the robot axes to their synchronization position.

	Action	Note
1	On ABB menu tap Program editor .	
2	Create a new program.	
3	Use MoveAbsJ in the Motion&Proc menu.	
4	Create the following program: <pre>MoveAbsJ [[0,0,0,0,0,0], [9E9,9E9,9E9,9E9,9E9,9E9]] \NoEOffs, v1000, fine, tool0</pre>	
5	Run the program in manual mode.	
6	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See Synchronization marks and synchronization position for axes on page 349 and Updating revolution counters on page 351 .

Using the jogging window

Use this procedure to jog the robot to the synchronization position of all axes.

	Action	Note
1	On the ABB menu, tap Jogging .	
2	Tap Motion mode to select group of axes to jog.	
3	Tap to select the axis to jog, axis 1, 2, or 3.	
4	Manually run the robots axes to a position where the axis position value read on the FlexPendant, is equal to zero.	
5	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See Synchronization marks and synchronization position for axes on page 349 and Updating revolution counters on page 351 .

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6 Decommissioning

6.1 Introduction

Introduction

This section contains information to consider when taking a product, robot or controller, out of operation.

It deals with how to handle potentially dangerous components and potentially hazardous materials.

General

All used grease/oils and dead batteries **must** be disposed of in accordance with the current legislation of the country in which the robot and the control unit are installed.

If the robot or the control unit is partially or completely disposed of, the various parts **must** be grouped together according to their nature (which is all iron together and all plastic together), and disposed of accordingly. These parts **must** also be disposed of in accordance with the current legislation of the country in which the robot and control unit are installed.

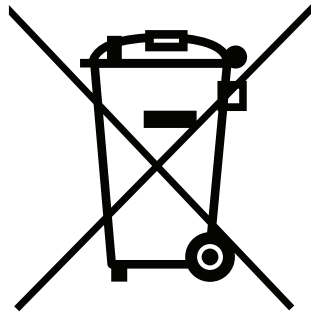
6 Decommissioning

6.2 Environmental information

6.2 Environmental information

Symbol

The following symbol indicates that the product must not be disposed of as common garbage. Handle each product according to local regulations for the respective content (see table below).



xx180000058

Hazardous material

The table specifies some of the materials in the product and their respective use throughout the product.

Dispose components properly according to local regulations to prevent health or environmental hazards.

Material	Example application
Aluminium	Base, upper arm, lower arm, axis-3 housing, etc
Batteries, Lithium	Battery pack
Neodymium	Drive units
Oil, grease	Drive units, ball screw spline unit
Plastic/rubber	Upper arm cover, mechanical stop rubbers
Steel	Drive units, ball screw spline unit, etc

Oil and grease

Where possible, arrange for oil and grease to be recycled. Dispose of via an authorized person/contractor in accordance with local regulations. Do not dispose of oil and grease near lakes, ponds, ditches, down drains, or onto soil. Incineration must be carried out under controlled conditions in accordance with local regulations.

Also note that:

- Spills can form a film on water surfaces causing damage to organisms. Oxygen transfer could also be impaired.
- Spillage can penetrate the soil causing ground water contamination.

7 Reference information

7.1 Introduction

General

This chapter includes general information, complementing the more specific information in the different procedures in the manual.

7 Reference information

7.2 Applicable standards

7.2 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

Deviation for delay circuit

Some variants of IRB 910SC has an inherent delay circuit to enhance the lifetime of speed reducers. This only applies to variants IRB 910SC-3/0.45, IRB 910SC-3/0.55, and IRB 910SC-3/0.65.

This circuit allows an extended time period for soft stop by enabling a delay of about 0.5 s before motor brakes are engaged, e.g. when the three-position enabling device is released or compressed, or the emergency stop is pressed. During this period, the robot axes 1 and 2 will continue their movement until they are stopped by the motor or eventually by brakes. Make sure the robot safeguarded area is free from obstacles, even during manual operations. Note that this delay does not apply to axes 3 and 4.

For more details regarding stopping time and distance metric, see *Product specification - Robot stopping distances according to ISO 10218-1*.

Continues on next page

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
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 ^f	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.

7 Reference information

7.3 Unit conversion

7.3 Unit conversion

Converter table

Use the following table to convert units used in this manual.

Quantity	Units		
Length	1 m	3.28 ft.	39.37 in
Weight	1 kg	2.21 lb.	
Weight	1 g	0.035 ounces	
Pressure	1 bar	100 kPa	14.5 psi
Force	1 N	0.225 lbf	
Moment	1 Nm	0.738 lbf-ft	
Volume	1 L	0.264 US gal	

7.4 Specification of screws

Screws, nuts and washers not handled as spare parts

The screws, nuts and washers listed have no special treatment and can be bought locally if lost or damaged.

Screw/Nut/Washer	Dimension, class and treatment
Hex socket head cap screw	M5x16 12.9 Steel Black Oxide
Hex socket head cap screw	M5x25 12.9 Steel Black Oxide
Hex socket head cap screw	M6x30 12.9 Steel Black Oxide
Hex socket head cap screw	M3x8 12.9 Steel Black Oxide
Hex socket head cap screw	M3x20 12.9 Steel Black Oxide
Hex socket head cap screw	M4x16 12.9 Steel Black Oxide
Hex socket head cap screw	M4x25 12.9 Steel Black Oxide
Hex socket head cap screw	M4x20 12.9 Steel Black Oxide
Hex socket head cap screw	M5x12 12.9 Steel Black Oxide
Hex socket head cap screw	M3x12 12.9 Steel Black Oxide
Hex socket head cap screw	M4x12 12.9 Steel Black Oxide
Hex socket head cap screw	M2.5x6 12.9 Steel Black Oxide
Hex socket head cap screw	M4x30 12.9 Steel Black Oxide
Hex socket head cap screw	M4x10 12.9 Steel Black Oxide
Hex socket head cap screw	M6x16 8.8 Steel Zinc electroplated and chromated, bluish
Torx pan head screw	M3x4 8.8 Steel Zinc electroplated and chromated, bluish
Torx pan head screw	M3x6 8.8 Steel Zinc electroplated and chromated, bluish
Hex socket counters. flat head screw	M4x8 8.8 Steel Zinc electroplated and chromated, bluish
Hex socket pan head thread rolling screw	M3x6 8.8 Stainless steel Zinc electroplated and chromated, bluish
Hexagon domed cap nut	M4 DIN1587 Stainless steel A2
Hexagon nut	M4 8 Steel Zinc electroplated and chromated, bluish
Plain washer	4.3x9x0.8 200HV Steel Zinc electroplated and chromated, bluish
Plain washer	6.4x12x1.6 200HV Steel Zinc electroplated and chromated, bluish
Plain washer	6.4x17x3 200HV Steel Zinc electroplated and chromated, bluish
Conical spring washer	3.2x7x0.6 420-510HV Spring steel acc.to DIN267 Teil26 Zinc plated mechanically and chromated, bluish
Conical spring washer	4.3x9x1 420-510HV Spring steel acc.to DIN267 Teil26 Zinc plated mechanically and chromated, bluish
Conical spring washer	5.3x11x1.2 420-510HV Spring steel acc.to DIN267 Teil26 Zinc plated mechanically and chromated, bluish

7 Reference information

7.5 Screw joints

7.5 Screw joints

General

This section describes how to tighten the various types of screw joints on ABB robots.

The instructions and torque values are valid for screw joints comprised of metallic materials and do *not* apply to soft or brittle materials.

UNBRAKO screws

UNBRAKO is a special type of screw recommended by ABB for certain screw joints. It features special surface treatment (Gleitmo as described below) and is extremely resistant to fatigue.

Whenever used, this is specified in the instructions, and in such cases, *no other type of replacement screw* is allowed. Using other types of screws will void any warranty and may potentially cause serious damage or injury.

Gleitmo treated screws

Gleitmo is a special surface treatment to reduce the friction when tightening the screw joint. Screws treated with Gleitmo may be reused 3-4 times before the coating disappears. After this the screw must be discarded and replaced with a new one.

When handling screws treated with Gleitmo, protective gloves of **nitrile rubber** type should be used.

Screws lubricated in other ways

Screws lubricated with Molycote 1000 should *only* be used when specified in the repair, maintenance or installation procedure descriptions.

In such cases, proceed as follows:

- 1 Apply lubricant to the screw thread.
- 2 Apply lubricant between the plain washer and screw head.
- 3 Screw dimensions of M8 or larger must be tightened with a torque wrench. Screw dimensions of M6 or smaller may be tightened without a torque wrench *if* this is done by trained and qualified personnel.

Lubricant	Article number
Molycote 1000 (molybdenum disulphide grease)	3HAC042472-001

Tightening torque

Before tightening any screw, note the following:

- Determine whether a **standard** tightening torque or **special** torque is to be applied. The **standard torques** are specified in the following tables. Any **special torques** are specified in the repair, maintenance or installation procedure descriptions. **Any special torque specified overrides the standard torque!**
- Use the *correct tightening torque* for each type of screw joint.
- Only use *correctly calibrated* torque keys.

Continues on next page

- Always *tighten the joint by hand*, and never use pneumatic tools.
- Use the *correct tightening technique*, that is *do not jerk*. Tighten the screw in a slow, flowing motion.
- Maximum allowed total deviation from the specified value is **10%**!

Oil-lubricated screws with slotted or cross-recess head screws

The following table specifies the recommended standard tightening torque for *oil-lubricated screws with slotted or cross-recess head screws*.

**Note**

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Oil-lubricated screws with allen head screws

The following table specifies the recommended standard tightening torque for *oil-lubricated screws with allen head screws*.

**Note**

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Dimension	Tightening torque (Nm) Class 8.8, oil-lubricated	Tightening torque (Nm) Class 10.9, oil-lubricated	Tightening torque (Nm) Class 12.9, oil-lubricated
M5	6	-	-
M6	10	-	-
M8	24	34	40
M10	47	67	80
M12	82	115	140
M16	200	290	340
M20	400	560	670
M24	680	960	1150

Lubricated screws (Molycote, Gleitmo or equivalent) with allen head screws

The following table specifies the recommended standard tightening torque for *screws lubricated with Molycote 1000, Gleitmo 603 or equivalent with allen head screws*.

**Note**

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Dimension	Tightening torque (Nm) Class 10.9, lubricated ⁱ	Tightening torque (Nm) Class 12.9, lubricated ⁱ
M8	28	35

Continues on next page

7 Reference information

7.5 Screw joints

Continued

Dimension	Tightening torque (Nm) Class 10.9, lubricated ⁱ	Tightening torque (Nm) Class 12.9, lubricated ⁱ
M10	55	70
M12	96	120
M16	235	280
M20	460	550
M24	790	950

ⁱ Lubricated with Molycote 1000, Gleitmo 603 or equivalent

Water and air connectors

The following table specifies the recommended standard tightening torque for *water and air connectors* when *one or both* connectors are made of *brass*.



Note

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Dimension	Tightening torque Nm - Nominal	Tightening torque Nm - Min.	Tightening torque Nm - Max.
1/8	12	8	15
1/4	15	10	20
3/8	20	15	25
1/2	40	30	50
3/4	70	55	90

7.6 Weight specifications


Definition

In installation, repair, and maintenance procedures, weights of the components handled are sometimes specified. All components exceeding 22 kg (50 lbs) are highlighted in this way.

To avoid injury, ABB recommends the use of a lifting accessory when handling components with a weight exceeding 22 kg. A wide range of lifting accessories and devices are available for each manipulator model.

Example

Following is an example of a weight specification in a procedure:

	Action	Note
	 CAUTION The arm weighs 25 kg. All lifting accessories used must be sized accordingly.	

7 Reference information

7.7 Standard toolkit

7.7 Standard toolkit

General

All service (repairs, maintenance, and installation) procedures contains lists of tools required to perform the specified activity.

All special tools required are listed directly in the procedures while all the tools that are considered standard are gathered in the standard toolkit and defined in the following table.

This way, the tools required are the sum of the standard toolkit and any tools listed in the instruction.

Contents, standard toolkit

Qty	Tool	Rem.
1	Socket head cap 2-17 mm	
1	Torque wrench 0.3-45 Nm	
1	Torque wrench 45 Nm	For securing robot to foundation.
1	Ratchet head for torque wrench 1/2	
1	Hex socket head cap no. 2.5 socket 1/2" bit L=110 mm	
1	Small screwdriver	
1	T-handle with ball head	
1	Small cutting plier	
1	Plastic mallet	

7.8 Special tools

General

All service instructions contain lists of tools required to perform the specified activity. The required tools are a sum of standard tools, defined in the section [Standard toolkit on page 386](#), and of special tools, listed directly in the instructions and also gathered in this section.

Special tools



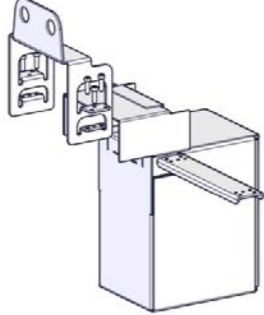
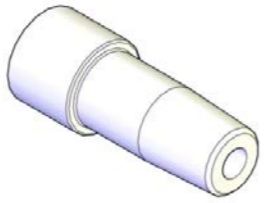
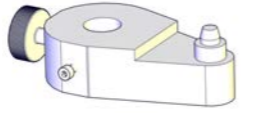
Note

If the replacing procedure is not listed in the table below, only standard tools are needed for the procedure.

Continues on next page

7 Reference information

7.8 Special tools

Tools and equipment with spare part number: (These tools can be ordered from ABB)			Cable harness spare parts	Base spare parts	Lower arm spare parts	Upper arm spare parts	Ball screw spline unit	Axis-1 motor	Axis-2 motor	Axis-3 motor	Axis-4 motor	Axis-3 timing belt	Axis-4 timing belts
Lifting accessories													
-	Lifting accessory, robot Includes lifting accessories and screws.	 xx1500002471											
-	Lifting chain, capacity > 50 kg. Hook												
Calibration toolkit													
3HAC057036-001	Moving calibration pin	 xx1500002518	1	1	1	1		1	1				
3HAC057137-001	Moving calibration block, axis3 and axis 4 Includes calibration pin, knob and adjusting screw.	 xx1500002682					1			1	1	1	1
Other tools													
-	24 VDC power supply						1						
-	Sonic tensiometer				1	1			1	1	1	1	
-	Dynamometer				1	1				1	1	1	1

Continues on next page

7.9 Lifting accessories and lifting instructions

General

Many repair and maintenance activities require different pieces of lifting accessories, which are specified in each procedure.

The use of each piece of lifting accessories is *not* detailed in the activity procedure, but in the instruction delivered with each piece of lifting accessories.

The instructions delivered with the lifting accessories should be stored for later reference.

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8 Spare parts

8.1 Spare part lists and illustrations

Location

Spare parts and exploded views are not included in the manual but delivered as a separate document for registered users on myABB Business Portal, www.abb.com/myABB.



Tip

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

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9 Circuit diagrams

9.1 Circuit diagrams

Overview

The circuit diagrams are not included in this manual, but are available for registered users on myABB Business Portal, www.abb.com/myABB.

See the article numbers in the tables below.

Controllers

Product	Article numbers for circuit diagrams
<i>Circuit diagram - IRC5</i>	<i>3HAC024480-011</i>
<i>Circuit diagram - IRC5 Compact</i>	<i>3HAC049406-003</i>
<i>Circuit diagram - IRC5 Panel Mounted Controller</i>	<i>3HAC026871-020</i>
<i>Circuit diagram - Euromap 67, design 14</i>	<i>3HAC024120-005</i>
<i>Circuit diagram - Spot welding cabinet</i>	<i>3HAC057185-001</i>

Robots

Product	Article numbers for circuit diagrams
<i>Circuit diagram - IRB 120</i>	<i>3HAC031408-003</i>
<i>Circuit diagram - IRB 140 type C</i>	<i>3HAC6816-3</i>
<i>Circuit diagram - IRB 260</i>	<i>3HAC025611-001</i>
<i>Circuit diagram - IRB 360</i>	<i>3HAC028647-009</i>
<i>Circuit diagram - IRB 460</i>	<i>3HAC036446-005</i>
<i>Circuit diagram - IRB 660</i>	<i>3HAC025691-001</i>
<i>Circuit diagram - IRB 760</i>	<i>3HAC025691-001</i>
<i>Circuit diagram - IRB 1200</i>	<i>3HAC046307-003</i>
<i>Circuit diagram - IRB 1410</i>	<i>3HAC2800-3</i>
<i>Circuit diagram - IRB 1600/1660</i>	<i>3HAC021351-003</i>
<i>Circuit diagram - IRB 1520</i>	<i>3HAC039498-007</i>
<i>Circuit diagram - IRB 2400</i>	<i>3HAC6670-3</i>
<i>Circuit diagram - IRB 2600</i>	<i>3HAC029570-007</i>
<i>Circuit diagram - IRB 4400/4450S</i>	<i>3HAC9821-1</i>
<i>Circuit diagram - IRB 4600</i>	<i>3HAC029038-003</i>
<i>Circuit diagram - IRB 6620</i>	<i>3HAC025090-001</i>
<i>Circuit diagram - IRB 6620 / IRB 6620LX</i>	<i>3HAC025090-001</i>
<i>Circuit diagram - IRB 6640</i>	<i>3HAC025744-001</i>
<i>Circuit diagram - IRB 6650S</i>	<i>3HAC13347-1</i> <i>3HAC025744-001</i>

Continues on next page

9 Circuit diagrams

9.1 Circuit diagrams

Continued

Product	Article numbers for circuit diagrams
<i>Circuit diagram - IRB 6660</i>	<i>3HAC025744-001 3HAC029940-001</i>
<i>Circuit diagram - IRB 6700 / IRB 6790</i>	<i>3HAC043446-005</i>
<i>Circuit diagram - IRB 7600</i>	<i>3HAC13347-1 3HAC025744-001</i>
<i>Circuit diagram - IRB 14000</i>	<i>3HAC050778-003</i>
<i>Circuit diagram - IRB 910SC</i>	<i>3HAC056159-002</i>

Index

A

Absolute Accuracy, calibration, 347
 allergenic material, 28
 aluminum
 disposal, 376
 ambient humidity
 operation, 43
 storage, 42
 ambient temperature
 operation, 43
 storage, 42
 assembly instructions, 39
 assessment of hazards and risks, 28
 axis-4 drive unit
 replacing, 333
 axis-3 drive unit
 replacing, 319
 axis-3 timing belt
 replacing, 246
 axis-2 drive unit
 replacing, 308
 axis-2 mechanical stop
 replacing, 271
 axis-1 drive unit
 replacing, 299
 axis-1 mechanical stop
 replacing, 296

B

ball screw spline unit
 lubrication, 111
 replacing, 229
 base
 replacing, 285
 batteries
 disposal, 376
 battery pack
 replacing, 100
 brake release harness
 replacing, 191
 brakes
 testing function, 36

C

cabinet lock, 29
 cabling, robot, 71
 cabling between robot and controller, 71
 calibrating
 roughly, 351
 calibration
 Absolute Accuracy type, 346
 rough, 351
 standard type, 346
 verification, 372
 when to calibrate, 348
 calibration, Absolute Accuracy, 347
 calibration manuals, 347
 calibration marks, 349
 calibration position
 jogging to, 373
 scales, 349
 calibration scales, 349
 CalibWare, 346
 carbon dioxide extinguisher, 29

cleaning, 114
 climbing on robot, 32
 Cold environments, 75
 connecting the robot and controller, cabling, 71

D

dimensions
 robot, 66
 direction of axes, 350

E

EIB mounting plate
 replacing, 164
 EIB unit
 replacing, 146
 environmental information, 376
 equipment, robot, 66
 ESD
 damage elimination, 52
 sensitive equipment, 52
 extra equipment, 66

F

fire extinguishing, 29
 fitting, equipment, 66
 FlexPendant
 jogging to calibration position, 373
 MoveAbsJ instruction, 373
 updating revolution counters, 352
 floor cables
 replacing, 183
 foundation
 requirements, 42

G

grease, 32
 disposal, 376

H

hanging
 installed hanging, 28
 hazard levels, 19
 hazardous material, 376
 height
 installed at a height, 28
 hot surfaces, 32
 HRA, 28
 humidity
 operation, 43
 storage, 42

I

installation
 equipment, 66
 instructions for assembly, 39
 integrator responsibility, 28
 intervals for maintenance, 80

L

labels
 robot, 21
 lifting accessory, 385
 limitation of liability, 17
 Lithium
 disposal, 376
 loads on foundation, 41
 lock and tag, 29

- lower arm
 - replacing, 276
- lubricants, 32
- lubrication
 - ball screw spline unit, 111

M

- main cable package
 - replacing, 122
- maintenance intervals, 80
- maintenance schedule, 80
- mounting, equipment, 66
- MoveAbsJ instruction, 373

N

- national regulations, 28
- negative directions, axes, 350
- neodymium
 - disposal, 376

O

- oil, 32
 - disposal, 376
- operating conditions, 43
- original spare parts, 17

P

- PCB board
 - replacing, 156
- pedestal
 - installed on pedestal, 28
- personnel
 - requirements, 18
- plastic
 - disposal, 376
- positive directions, axes, 350
- PPE, 18
- product standards, 378
- protection classes, 43
- protection type, 43
- protective equipment, 18
- protective wear, 18

R

- regional regulations, 28
- release brakes, 35
- replacements, report, 117
- replacing
 - axis-4 drive unit, 333
 - axis-3 drive unit, 319
 - axis-3 timing belt, 246
 - axis-2 drive unit, 308
 - axis-2 mechanical stop, 271
 - axis-1 drive unit, 299
 - axis-1 mechanical stop, 296
 - ball screw spline unit, 229
 - base, 285
 - battery pack, 100
 - brake release harness, 191
 - EIB mounting plate, 164
 - EIB unit, 146
 - floor cables, 183
 - lower arm, 276
 - main cable package, 122
 - PCB board, 156
 - timing belts, 256
 - upper arm, 196

- report replacements, 117
- requirements on foundation, 42
- responsibility and validity, 17
- revolution counters
 - storing on FlexPendant, 352
 - updating, 351
- risk of burns, 32
- risk of tipping, 50
- robot
 - dimensions, 66
 - equipment, fitting, 66
 - labels, 21
 - protection class, 43
 - protection types, 43
 - symbols, 21
- rubber
 - disposal, 376

S

- safety
 - brake testing, 36
 - ESD, 52
 - fire extinguishing, 29
 - release robot axes, 35
 - signals, 19
 - signals in manual, 19
 - symbols, 19
 - symbols on robot, 21
- safety devices, 29
- safety hazard
 - hydraulic system, 30
 - pneumatic system, 30
- safety signals
 - in manual, 19
- safety standards, 378
- scales on robot, 349
- schedule of maintenance, 80
- screw joints, 382
- securing, robot, 63
- signals
 - safety, 19
- speed
 - adjusting, 75
- stability, 50
- standards, 378
 - ANSI, 379
 - CAN, 379
 - EN IEC, 378
 - EN ISO, 378
- start of robot in cold environments, 75
- steel
 - disposal, 376
 - storage conditions, 42
- symbols
 - safety, 19
- synchronization position, 351
- sync marks, 349
- system integrator requirements, 28

T

- temperatures
 - operation, 43
 - storage, 42
- testing
 - brakes, 36
- timing belts
 - replacing, 256

torques on foundation, 41

troubleshooting

 safety, 37

U

updating revolution counters, 351

upper arm

 replacing, 196

users

 requirements, 18

V

validity and responsibility, 17

velocity

 adjusting, 75

verifying calibration, 372

W

weight, 41

 robot, 58, 64

Z

zero position

 checking, 373