ROBOTICS

Product specification

IRB 8700

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Product specification

IRB 8700

OmniCore

Document ID: 3HAC087213-001
Revision: C

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Original instructions.

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Overview of this product specification

About this product specification

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

- The structure and dimensions prints
- The fulfillment of standards, safety and operating requirements
- The load diagrams, mounting or extra equipment, the motion and the robot reach
- The specification of variants and options available

Usage

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

Users

It is intended for:

- Product managers and product personnel
- Sales and marketing personnel
- Order and customer service personnel
- Robot programmers
- Project leaders
- Design engineers

References

Reference	Document ID
Product specification - OmniCore V line	*3HAC074671-001*
Product specification - Robot user documentation, OmniCore with RobotWare 7	*3HAC065042-001*
Product manual - IRB 8700	*3HAC052853-001*
Product manual - DressPack IRB 8700	*3HAC055802-001*

Revisions

Revision	Description
A	First edition.
B	Published in release 24C. The following updates are done in this revision: • Added 22 m process cables.
C	Published in release 24D. The following updates are done in this revision: • Updated the section *Technical data on page 17*. • Corrected fork lift option. • Removed options for DressPack that are not available.

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1 Description

1.1 Structure

1.1.1 Introduction

General

The IRB 8700 serie is ABB Robotics 8:th generation of heavy payload robot, high performance industrial robots. With focus on high production capacity, compact design, simple service and low maintenance cost. The IRB 8700 is a general purpose robot targeting market segment as for example Automotive (BIW), Foundry, Mining and Metal fabrication.

Software product range

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

Process options

There are a large number of process options for Material Handling/SpotWelding integrated in the robot.

Operating system

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

The IRB 8700 manipulator can be connected to the following robot controllers:

- OmniCore V400XT

Safety

Safety standards valid for complete robot, manipulator and controller.

Additional functionality

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

Protection type Foundry Plus 2

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

Typical applications are spraying insertion and part extraction of die-casting machines, handling in sand casting and gravity casting, etc. (Please refer to Foundry

Continues on next page

1.1.1 Introduction
Continued

Prime robots for washing applications or other similar applications). Special care must be taken in regard to operational and maintenance requirements for applications in foundry are as well as in other applications areas. Please contact ABB Robotics Sales organization if in doubt regarding specific application feasibility for the Foundry Plus 2 protected robot.

The robot is painted with two-component epoxy on top of a primer for corrosion protection. To further improve the corrosion protection additional rust preventive are applied to exposed and crucial areas, e.g. has the tool flange a special preventive coating. Although, continuous splashing of water or other similar rust formation fluids may cause rust attach on the robots unpainted areas, joints, or other unprotected surfaces. Under these circumstances it is recommended to add rust inhibitor to the fluid or take other measures to prevent potential rust formation on the mentioned.

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

Selected Foundry Plus 2 features:

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

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

Available robot variants

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

See *Specification of variants and options on page 71* for robot versions and other options not selectable together with Foundry Plus 2.

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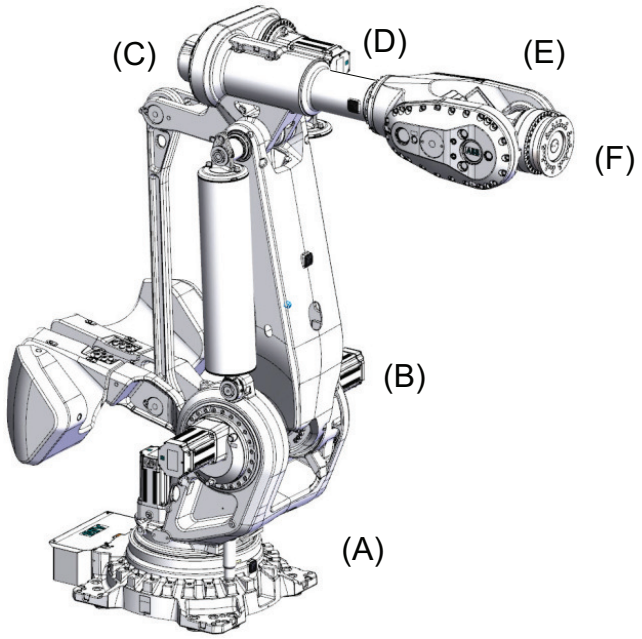
Robot axes



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

1.1.2 Different robot variants

General

The IRB 8700 is available in two variants.

Robot variants

The following standard robot versions are available.

Robot	Handling capacity (kg)	Handling capacity for LeanID (kg)	Reach (m)
IRB 8700	550 kg	475 kg	4.20 m
IRB 8700	800 kg	630 kg	3.50 m

Note

If option 780-4, LeanID is selected, the payload will decrease as stated above, for detailed information see *Load diagrams on page 32*

1.1.3 Technical data

IRB 8700 mounting

Handling capacity (kg)/Reach (m)

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

Manipulator weight

Robot type	Weight
IRB 8700-550/4.20	4,575 kg [i]
IRB 8700-800/3.50	4,525 kg [i]

[i] Weight without DressPack

Other technical data

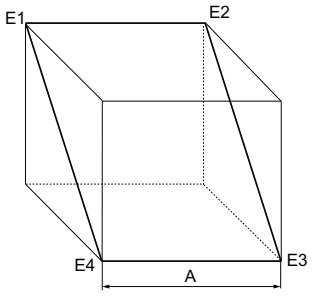
Data	Description	Note
Airborne noise level	The sound pressure level outside the working space.	< 71 dB (A) Leq (acc. to machinery directive 2006/42/EG)

Power consumption at max load

NOT YET UPDATED

Type of movement	-550/4.20	-800/3.50
ISO Cube Max. velocity	3.03 kW	3.93 kW

Robot in calibration position	-550/4.20	-800/3.50
Brakes engaged	0.29 kW	0.29 kW
Brakes disengaged	0.90 kW	0.98 kW



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Pos	Description
A	1,000 mm

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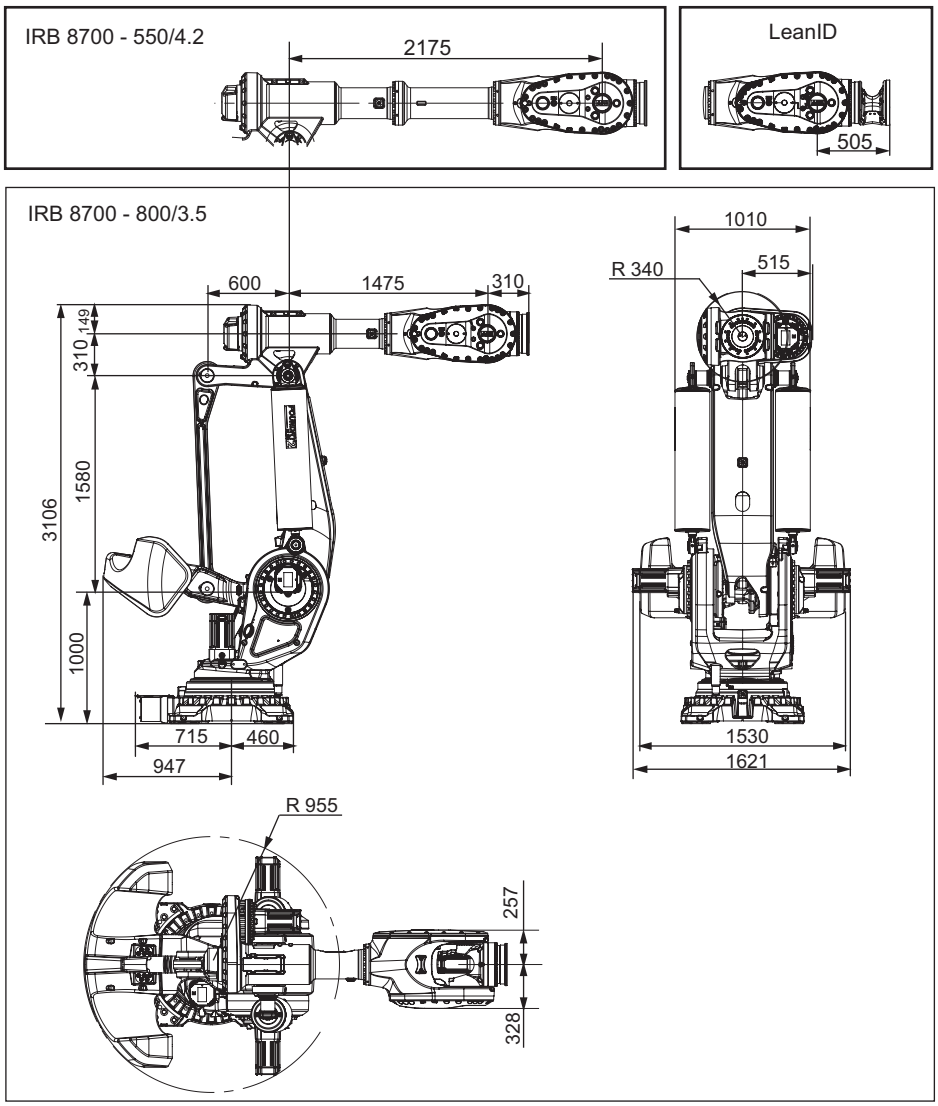
1.1.3 Technical data
Continued

Main dimensions



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1.2 Standards

1.2.1 Applicable standards

General

The product is compliant 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 deviation from ISO 10218-1:2011, these are listed in the declaration of incorporation. The declaration of incorporation is part of the delivery.

Robot standards

Standard	Description
ISO 9283	Manipulating industrial robots – Performance criteria and related test methods
ISO 9787	Robots and robotic devices – Coordinate systems and motion nomenclatures
ISO 9946	Manipulating industrial robots – Presentation of characteristics

Other standards used in design

Standard	Description
IEC 60204-1	Safety of machinery - Electrical equipment of machines - Part 1: General requirements, normative reference from ISO 10218-1
IEC 61000-6-2	Electromagnetic compatibility (EMC) – Part 6-2: Generic standards – Immunity standard for industrial environments
IEC 61000-6-4	Electromagnetic compatibility (EMC) – Part 6-4: Generic standards – Emission standard for industrial environments
ISO 13849-1:2006	Safety of machinery - Safety related parts of control systems - Part 1: General principles for design, normative reference from ISO 10218-1
UL 1740 (option) CSA Z434 (option)	Standards For Safety - Robots and Robotic Equipment Industrial robots and robot Systems - General safety requirements Valid for USA and Canada.

1.3 Installation

1.3.1 Introduction to installation

General

Both versions of IRB 8700 should be mounted on to the floor or tilted to ±15º (around the Y-axis or Y-axis). Depending on the robot version, an end effector with max. weight of 550 to 800 kg including payload, can be mounted on the tool flange (axis 6). See *Load diagrams on page 32*.

Extra loads

Extra load (valve packages, DressPack) of 50 kg, which is included in the load diagrams, can be mounted on the upper arm. An extra load of 500 kg can also be mounted on the frame of axis 1.

See *Fitting equipment on page 43*.

Working range limitation

The working range of axes 1 can be limited by mechanical stops as option. See *Limited working range on page 76*.

Explosive environments

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

1.3.2 Technical data

Weight, robot

The table shows the weight of the robot.

The weight does not include the weight of the DressPack.

Robot model	Weight
IRB 8700	4,750 kg

Note

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

The weight does not include the weight of the DressPack.

Mounting positions

The table shows valid mounting options for the manipulator.

Mounting option	Installation angle	Note
Floor mounted	0°	

Note

The actual mounting angle must always be configured in the system parameters, otherwise the performance and lifetime is affected. See the product manual for details.

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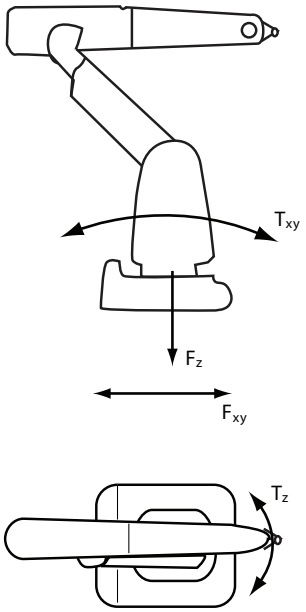
1.3.2 Technical data
Continued

Loads on foundation, robot

The illustration shows the directions of the robots stress forces.

The directions are valid for all floor mounted, suspended and inverted robots.



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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!

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	±13.5 kN	±50.3 kN
Force z	52.2 ±13.7 kN	52.2 ±41.9 kN
Torque xy	±77.7 kNm	±146.9 kNm
Torque z	±9.2 kNm	±31.8 kNm

Continues on next page

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	0.3 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.
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 the application manual of the controller software, section *Motion Process Mode*.

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 possibly 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 (-13°F)
Maximum ambient temperature	+55°C (+131°F)
Maximum ambient temperature (less than 24 hrs)	+70°C (+158°F)
Maximum ambient humidity	Maximum 95% at constant temperature.

Operating conditions, robot

The table shows the allowed operating conditions for the robot:

Parameter	Value
Minimum ambient temperature	+5°C i (41°F)
Maximum ambient temperature	+50°C (122°F)

Continues on next page

1.3.2 Technical data
Continued

Parameter	Value
Maximum ambient humidity	Maximum 95% at constant temperature.

i At low environmental temperature (below 10° C) a warm-up phase is recommended to be run with the robot. Otherwise there is a risk that the robot stops or runs 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[i]
Manipulator, protection type Foundry Plus	IP67

i According to IEC 60529.

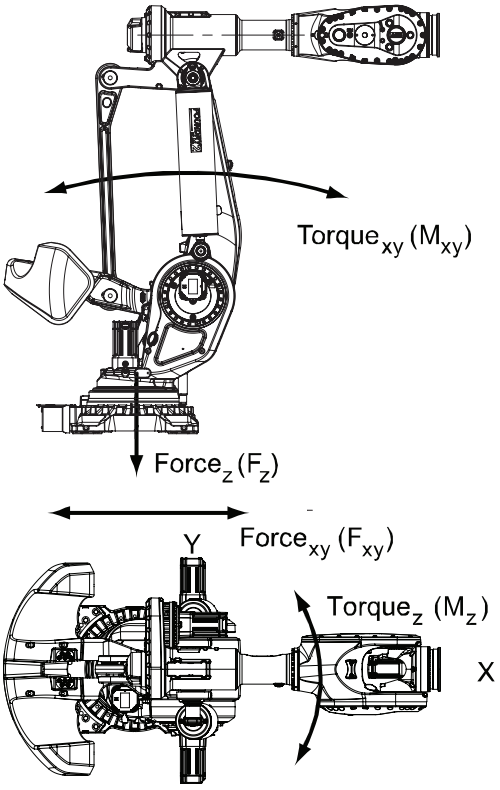
1.3.3 Assembling the manipulator

Maximum load

Maximum load in relation to the base coordinate system.

Floor mounted

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	±13.5 kN	±50.3 kN
Force z	52.2 ±13.7 kN	52.2 ±41.9 kN
Torque xy	±77.7 kNm	±146.9 kNm
Torque z	±9.2 kNm	±31.8 kNm



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Note regarding M_{xy} and F_{xy}

The bending torque (M_{xy}) can occur in any direction in the XY-plane of the base coordinate system.

The same applies to the transverse force (F_{xy}).

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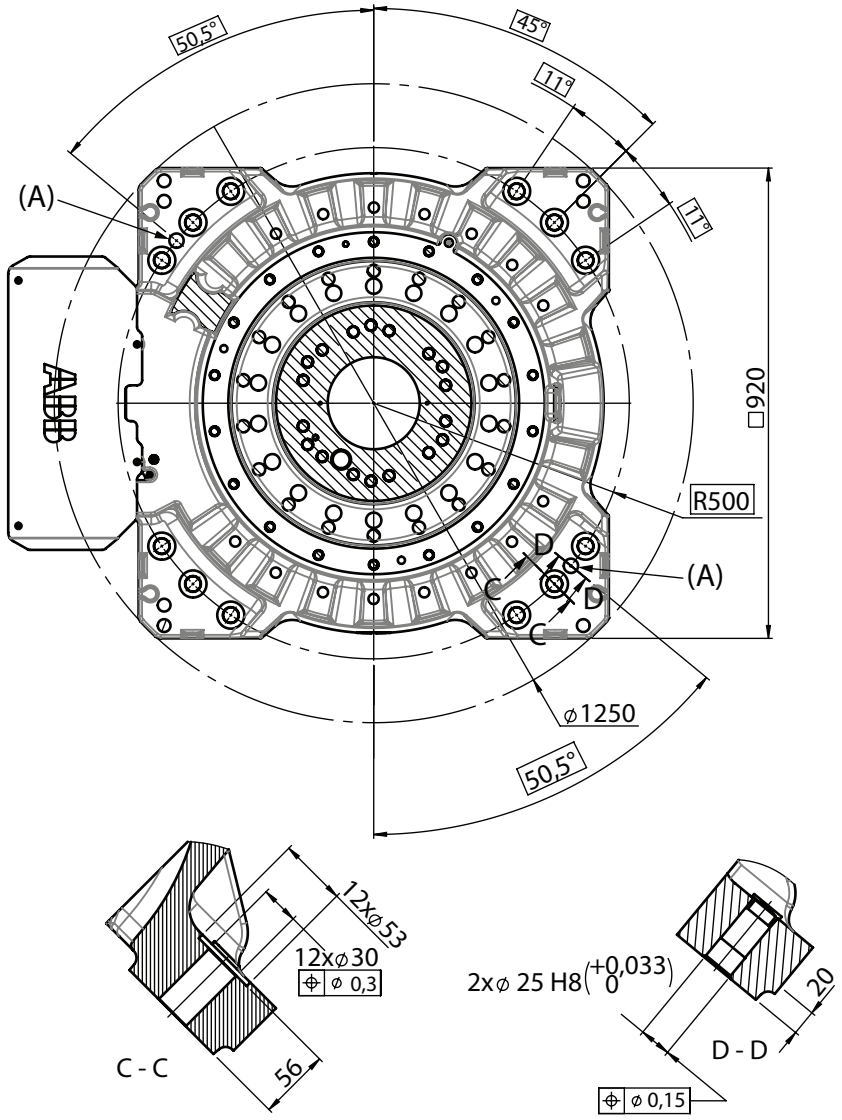
1.3.3 Assembling the manipulator

Continued

Fastening holes robot base - for all variants



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Pos	Description
A	Holes for guide pins (x2) Rear hole straight slot

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Attachment screws

The table below specifies the type of securing screws and washers to be used for securing the robot to the base plate/foundation.

Suitable screws, lightly lubricated:	M24 x 100
Quantity:	12 pcs
Quality:	8.8
Screw tightening yield point utilization factor (v) (according to VDI2230):	90% (v=0.9)
Suitable washer:	4 mm flat washer
Tightening torque:	550 Nm (screws lubricated with Molykote 1000) 600-725 Nm, typical 650 Nm (screws none or lightly lubricated)

Note

Only two guide pins shall be used. The corresponding holes in the base plate shall be circular according to figure *Base plate drawing on page 24*.

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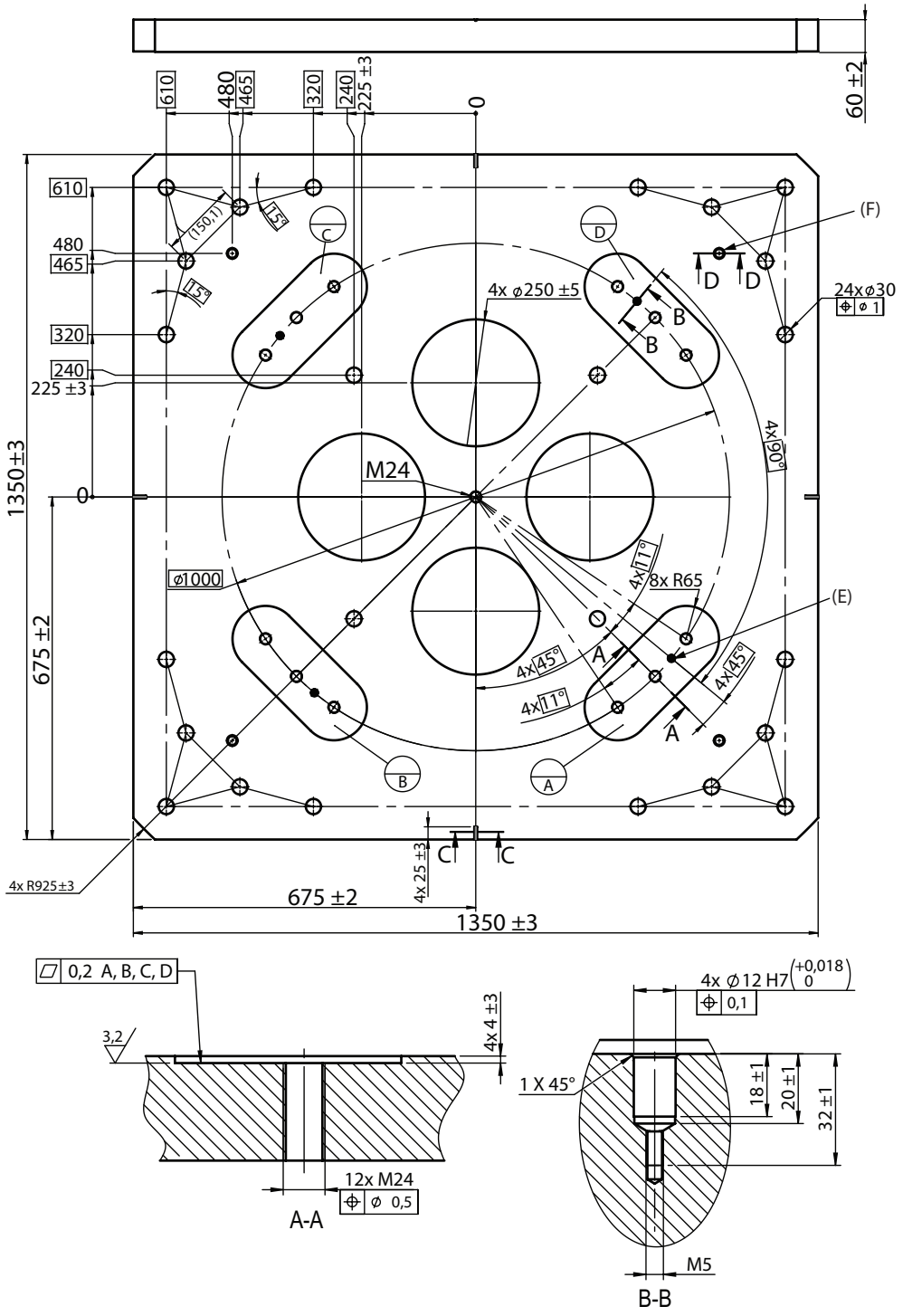
1.3.3 Assembling the manipulator
Continued

Base plate drawing

The following figure shows the option base plate (dimensions in mm). The weight of the base plate is 750 kg.



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Pos	Description
A, B, C, D	Common tolerance zone (accuracy all over the base plate from one contact surface to the other)

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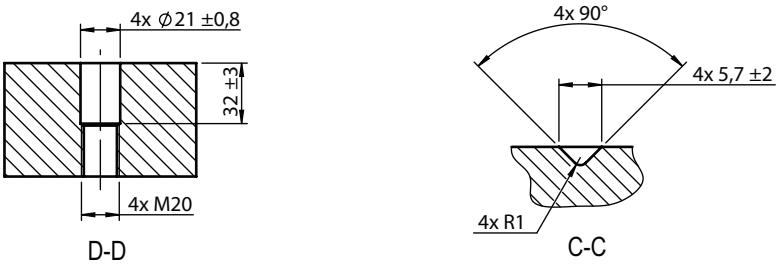
Pos	Description
E	Hole for guide pins, see *Guide pins on page 25*
F	Holes for levelling the base plate



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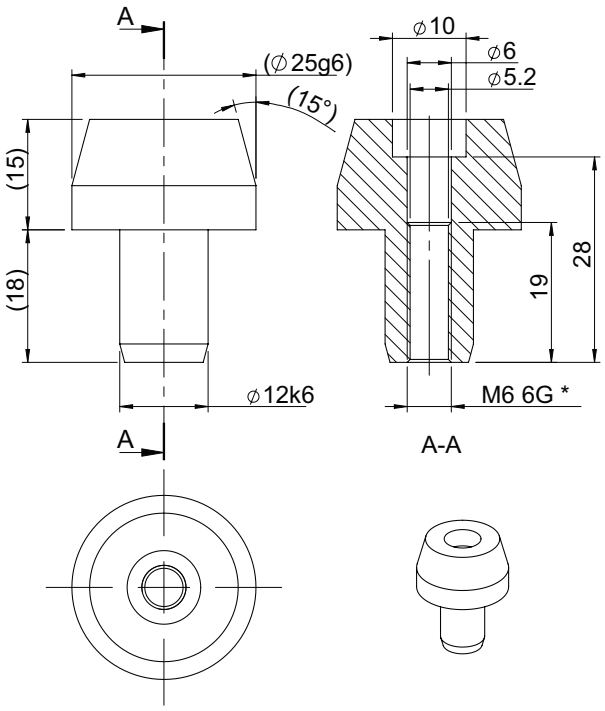
Guide pins



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Pos	Description
A	Cylindrical guide pin (x2), for position see *Fastening holes robot base - for all variants on page 22*

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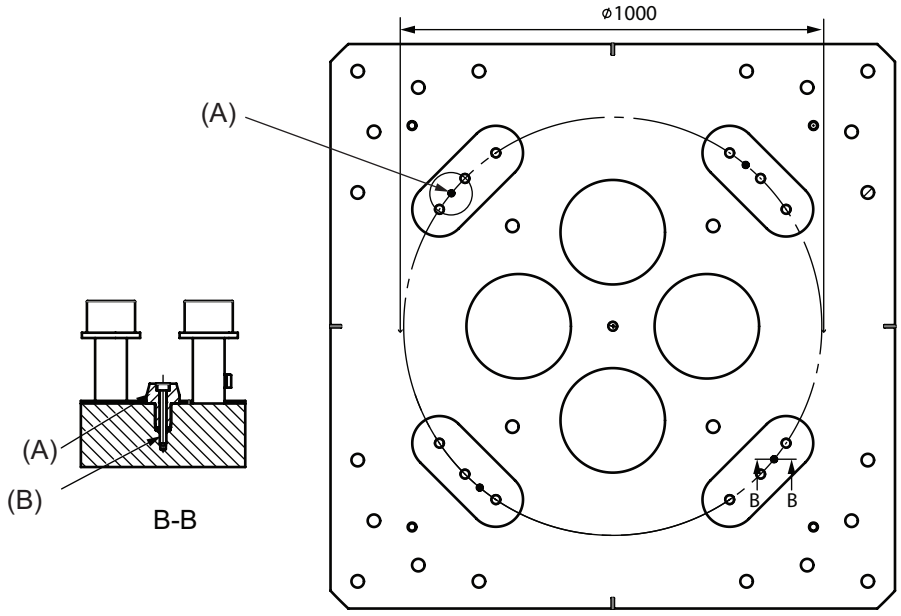
1.3.3 Assembling the manipulator
Continued

Assembly of guide pins



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Pos	Description
A	Cylindrical guide pin (x2)
B	M5 x 40. Tightening torque 6 Nm. (x2)

Note

All screws and pins are delivered in a plastic bag together with the base plate.

1.4 Calibration and references

1.4.1 Calibration methods

Overview

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

More information is available in the product manual.

Types of calibration

Type of calibration	Description	Calibration method
Standard calibration	The calibrated robot is positioned at calibration position. Standard calibration data is found on the SMB (serial measurement board) or EIB in the robot.	Axis Calibration
Absolute accuracy calibration (optional)	Based on standard calibration, and besides positioning the robot at synchronization position, the Absolute accuracy calibration also compensates for: • Mechanical tolerances in the robot structure • Deflection due to load Absolute accuracy calibration focuses on positioning accuracy in the Cartesian coordinate system for the robot. Absolute accuracy calibration data is found on the serial measurement board (SMB) or other robot memory. A robot calibrated with Absolute accuracy has the option information printed on its name plate (OmniCore). To regain 100% Absolute accuracy performance, the robot must be recalibrated for absolute accuracy after repair or maintenance that affects the mechanical structure.	CalibWare
Optimization	Optimization of TCP reorientation performance. The purpose is to improve reorientation accuracy for continuous processes like welding and gluing. Wrist optimization will update standard calibration data for axes 4 and 5. **Note** For advanced users, it is also possible to use the do the wrist optimization using the RAPID instruction `WristOpt`, see *Technical reference manual - RAPID Instructions, Functions and Data types*. This instruction is only available for OmniCore robots.	Wrist Optimization

Continues on next page

1.4.1 Calibration methods
Continued

Brief description of calibration methods

Axis Calibration method

Axis Calibration is a standard calibration method for calibration of IRB 8700. It is the recommended method in order to achieve proper performance.

The following routines are available for the Axis Calibration method:

- Fine calibration
- Update revolution counters
- Reference calibration

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

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

Wrist Optimization method

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

The actual instructions of how to perform the wrist optimization procedure is given on the FlexPendant.

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*.

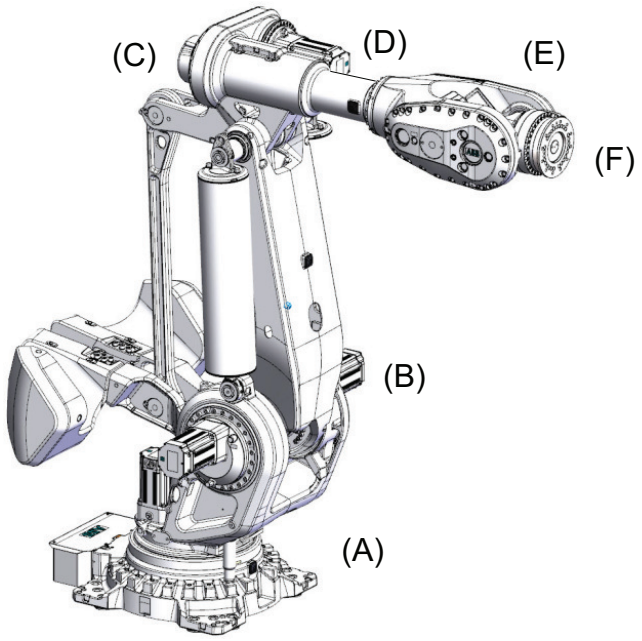
If a service operation is done to a robot with the option Absolute Accuracy, a new absolute accuracy calibration is required in order to establish full performance. For most cases after replacements that do not include taking apart the robot structure, standard calibration is sufficient.

The Absolute Accuracy option varies according to the robot mounting position. This is printed on the robot name plate for each robot. The robot must be in the correct mounting position when it is recalibrated for absolute accuracy.

1.4.2 Fine calibration

General

Fine calibration is made using the Axis calibration, see *Product manual - IRB 8700*.



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Axes

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

Calibration

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

1.4.3 Absolute Accuracy calibration

Purpose

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

Here are some examples of when this accuracy is important:

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

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

Note

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

Note

Singularities might appear in slightly different positions on a real robot compared to RobotStudio, where *Absolute Accuracy* is off compared to the real controller.

What is included

Every *Absolute Accuracy* robot is delivered with:

- compensation parameters saved in the robot memory
- a birth certificate representing the *Absolute Accuracy* measurement protocol for the calibration and verification sequence.

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

Absolute Accuracy supports floor mounted, wall mounted, and ceiling mounted installations. The compensation parameters that are saved in the robot memory differ depending on which Absolute Accuracy option is selected.

When is *Absolute Accuracy* being used

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

Continues on next page

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

Absolute Accuracy active

Absolute Accuracy will be active in the following cases:

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

Absolute Accuracy not active

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

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

Note

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

RAPID instructions

There are no RAPID instructions included in this option.

Production data

Typical production data regarding calibration are:

Robot	Positioning accuracy (mm)		
	Average	Max	% Within 1.5 mm
IRB 8700-550/4.20	0.7	1.5	100
IRB 8700-800/3.50	0.6	1.3	100

1.5 Load diagrams

1.5.1 Introduction

WARNING

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

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

- motors
- gearboxes
- mechanical structure

WARNING

In RobotWare, the service routine LoadIdentify can be used to determine correct load parameters. The routine automatically defines the tool and the load.

See *Operating manual - OmniCore*, for detailed information.

WARNING

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

General

The load diagrams include a nominal payload inertia, J_0 of 100 kgm^2, and an extra load of 50 kg at the upper arm housing.

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

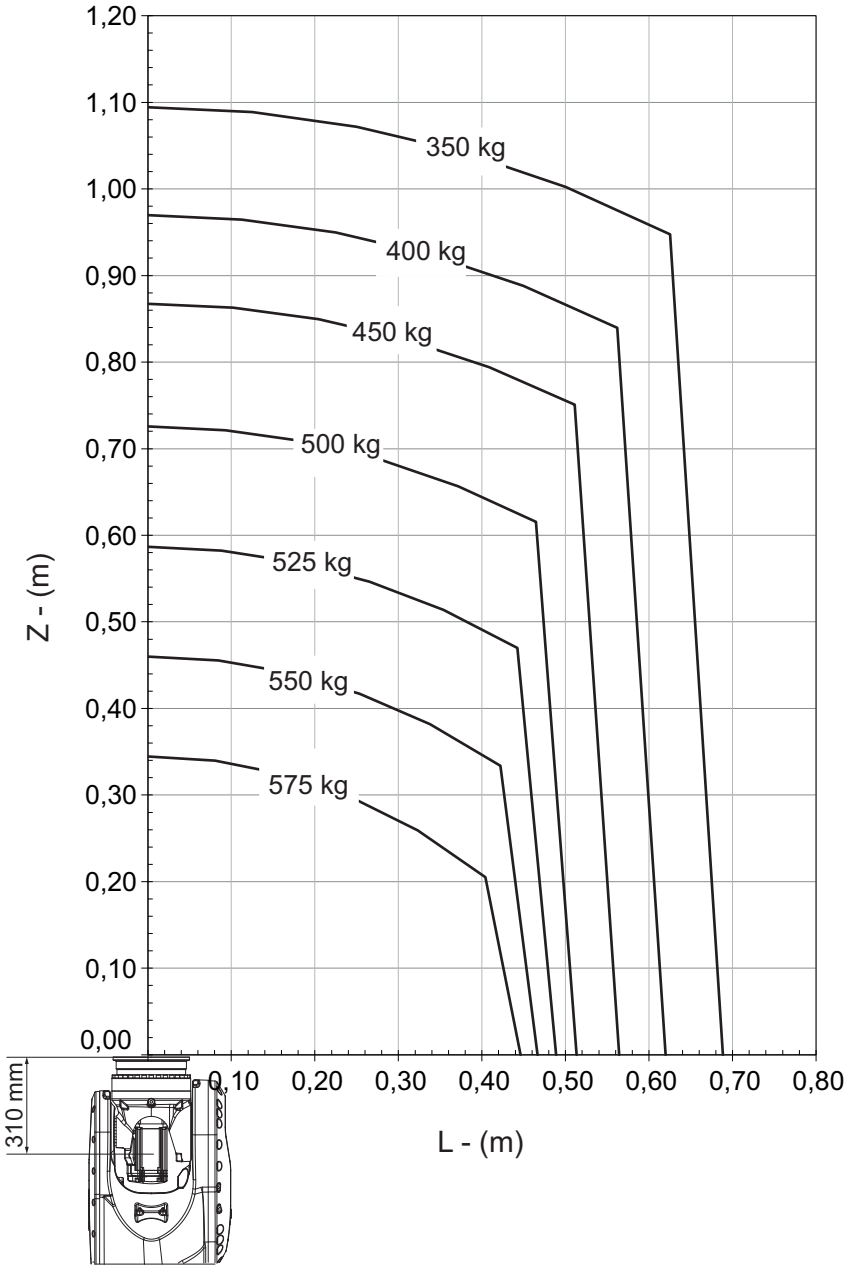
Control of load case with RobotLoad

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

The result from RobotLoad is only valid within the maximum loads and tilt angles. There is no warning if the maximum permitted arm load is exceeded. For over-load cases and special applications, contact ABB for further analysis.

1.5.2 Load diagrams

IRB 8700-550/4.20



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1.5.2 Load diagrams
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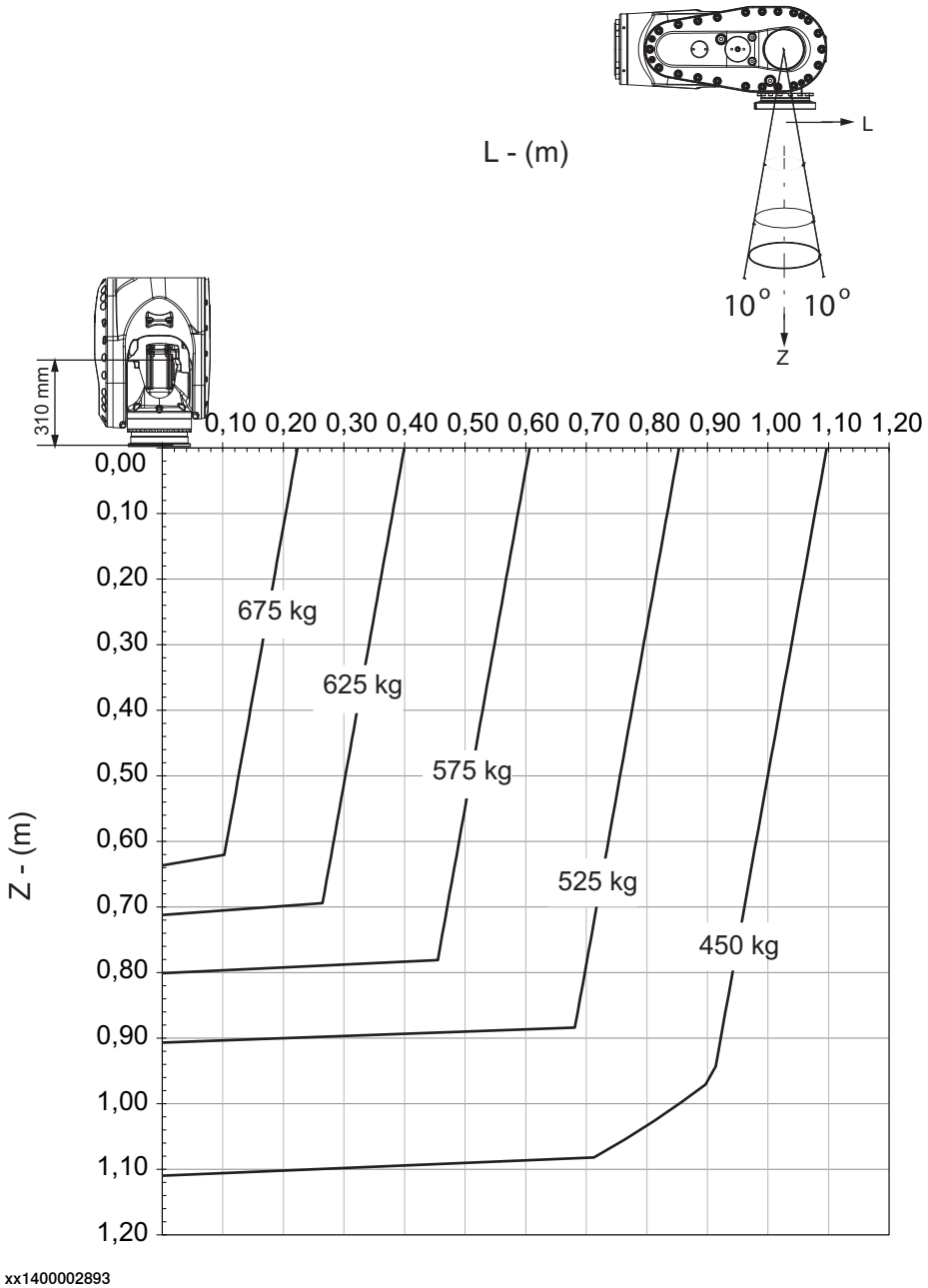
IRB 8700-550/4.20 "Vertical Wrist" (±10°)



xx1400002893

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

	Description
Max load	700 kg
Z_{max}	0.602 m
L_{max}	0.196 m

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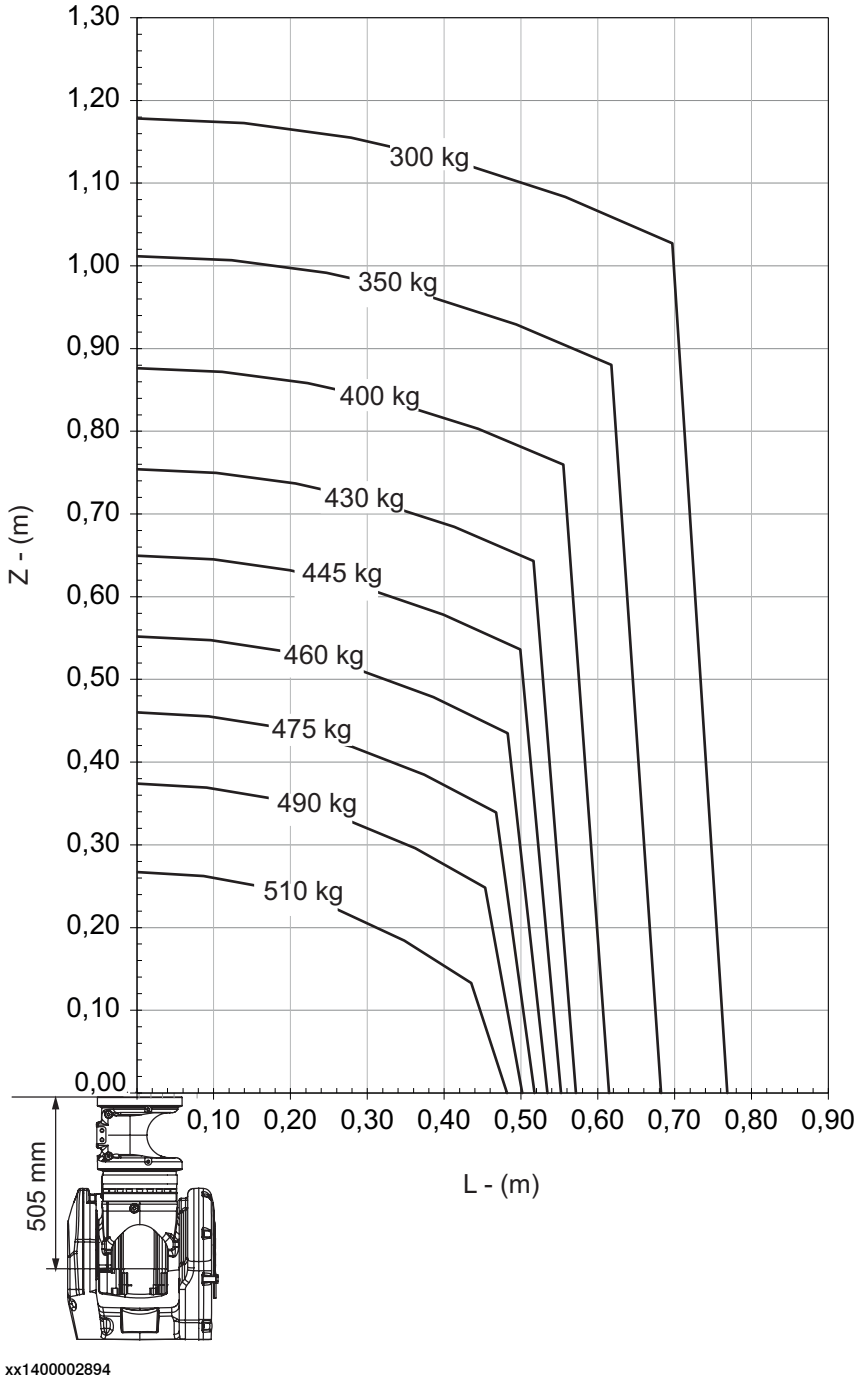
IRB 8700-550/4.20 "LeanID", option 780-4



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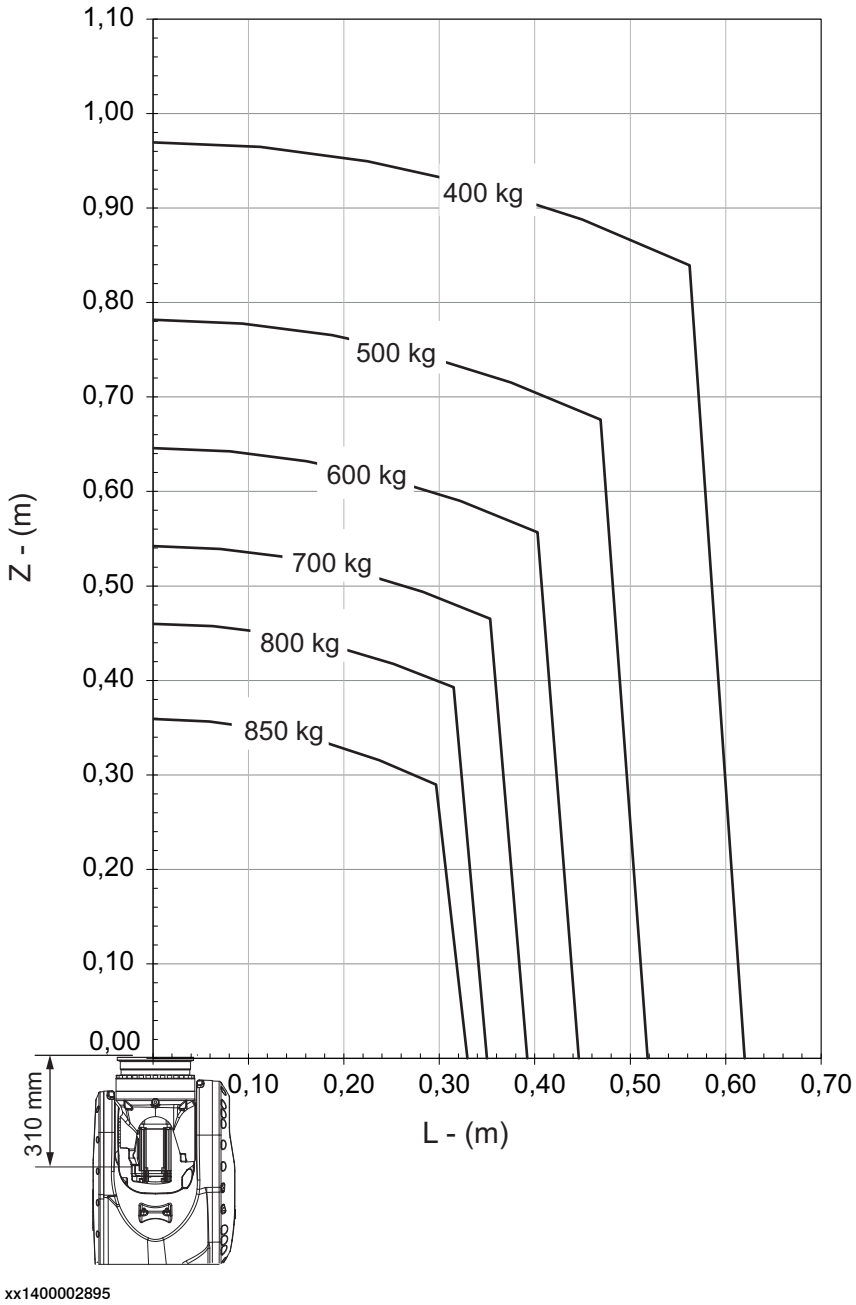
1.5.2 Load diagrams
Continued

IRB 8700-800/3.50



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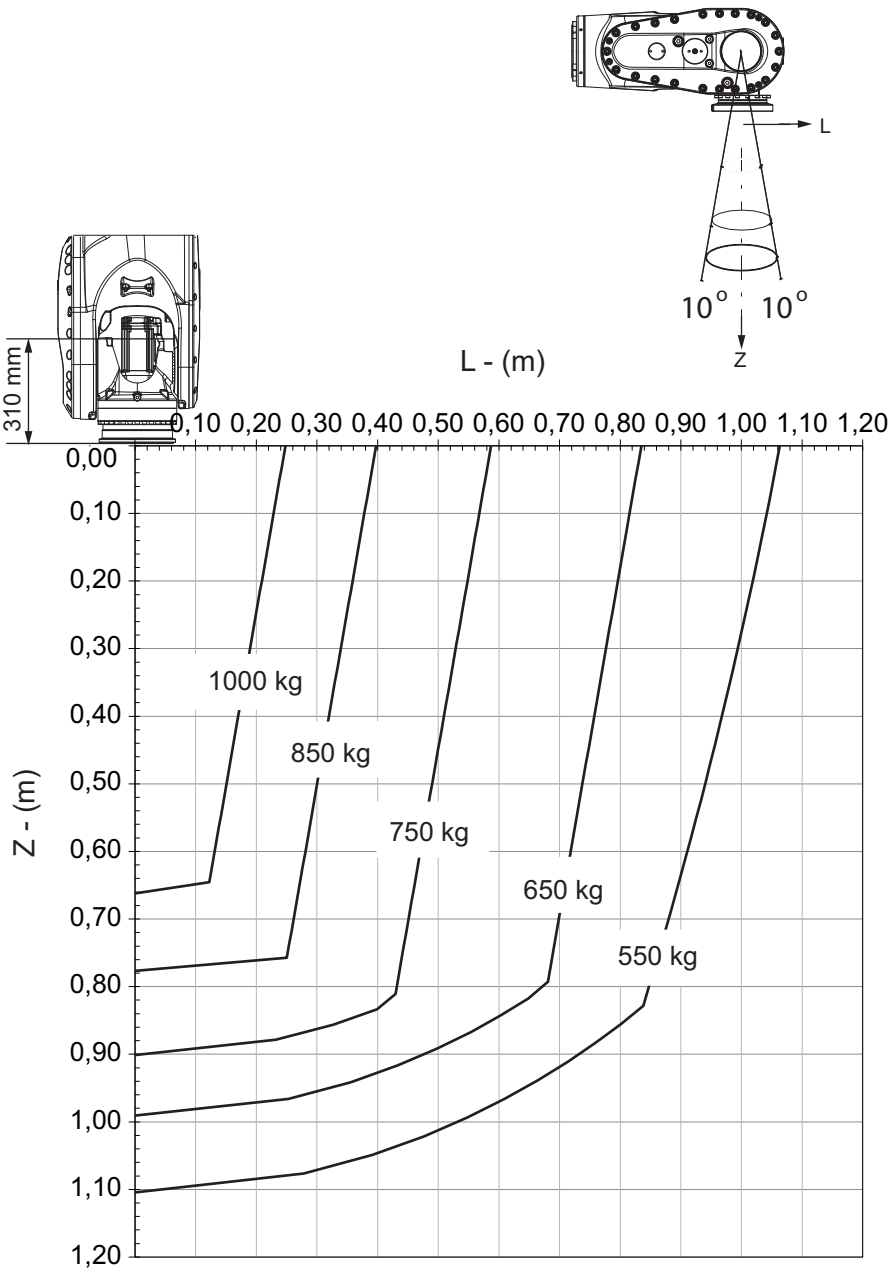
IRB 8700-800/3.50 "Vertical Wrist" (±10°)



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

	Description
Max load	1,000 kg
Z_{max}	0.662 m
L_{max}	0.297 m

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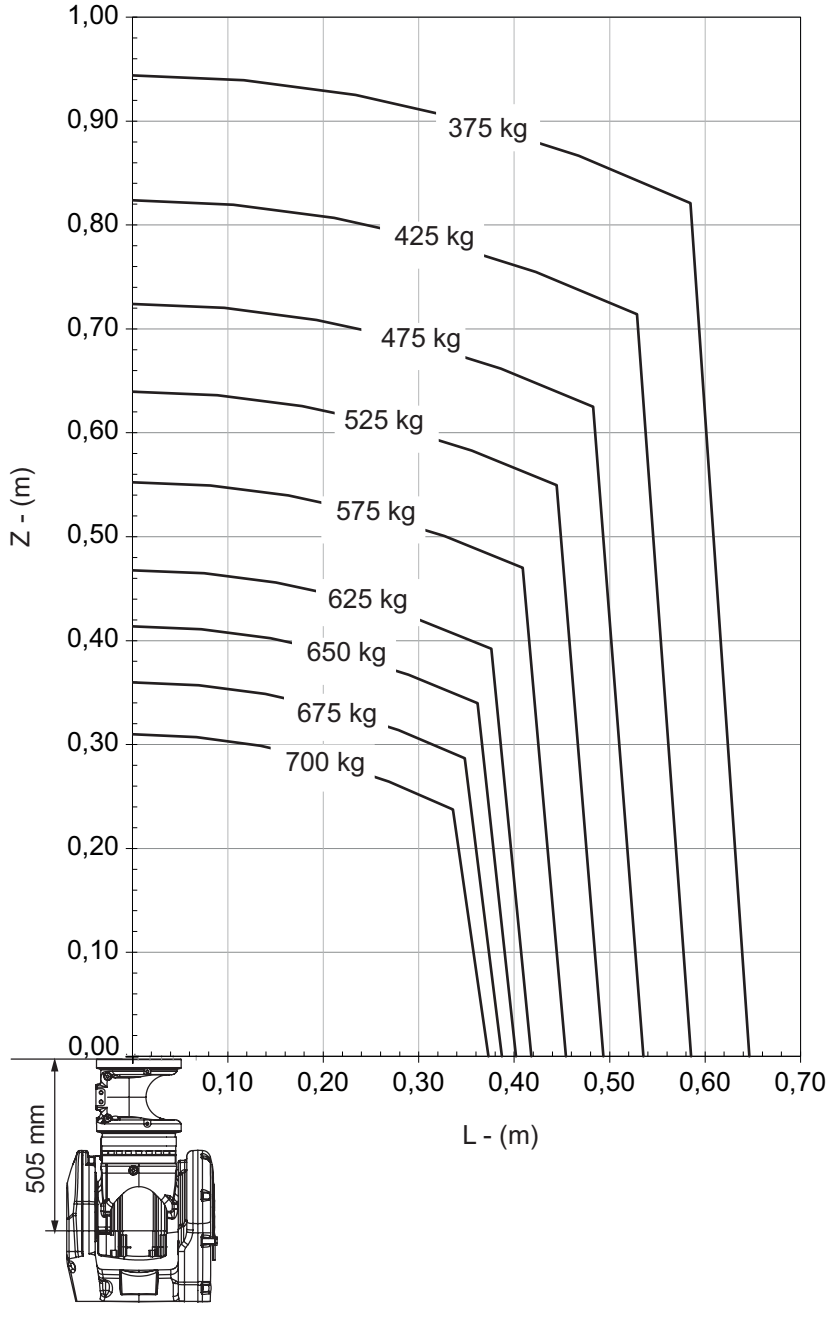
1.5.2 Load diagrams
Continued

IRB 8700-800/3.50 "LeanID", option 780-4



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

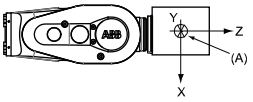
Note

Total load given as: mass in kg, center of gravity (Z and L) in meters and moment of inertia (J_{ox}, J_{oy}, J_{oz}) in kgm^2. L= sqr (X^2 + Y^2), see the following figure.

Full movement of axis 5 (±130°)

Axis	Robot type	Maximum moment of inertia
5	IRB 8700-550/4.20 IRB 8700-800/3.50	Ja_5 = Load x (($Z + 0{,}310^{i})^2 + L^2$) + max (J_{0x}, J_{0y}) ≤ 1100 kgm^2
6	IRB 8700-550/4.20 IRB 8700-800/3.50	Ja_6 = Load x L^2 + J_{0Z} ≤ 725 kgm^2

i For option 780-4, LeanID = 0,505 m



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Pos	Description
A	Center of gravity

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

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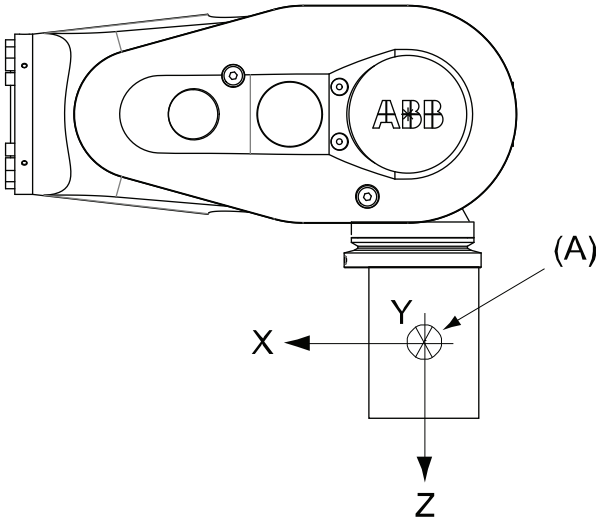
1.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement
Continued

Limited axis 5, center line down

Axis	Robot type	Maximum moment of inertia
5	IRB 8700-550/4.20 IRB 8700-800/3.50	Ja_5 = Load x $((Z + 0{,}310^{i})^2 + L^2) + \max(J_{0x}, J_{0y}) \leq 1100$ kgm^2
6	IRB 8700-550/4.20 IRB 8700-800/3.50	Ja_6 = Load x $L^2 + J_{0Z} \leq 725$ kgm^2

i For option 780-4, LeanID = 0,505 m



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Pos	Description
A	Center of gravity

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

1.5.4 Wrist torque

Note

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

Torque

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

Robot type	Max wrist torque axis 4 and 5	Max wrist torque axis 6	Max torque valid at load
IRB 8700-550/4.20	5279 Nm	2517 Nm	475 kg
IRB 8700-800/3.50	6043 Nm	2747 Nm	800 kg

1.5.5 Maximum TCP acceleration

General

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

Maximum Cartesian design acceleration for nominal loads

Robot type	E-stop Max acceleration at nominal load COG [m/s^2]	Controlled Motion Max acceleration at nominal load COG [m/s^2]
IRB 8700-800/3.50	32	17
IRB 8700-550/4.20	35	18
IRB 8700-630/3.50 LeanID	34	20
IRB 8700-475/4.20 leanID	37	18

Note

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

1.6 Fitting equipment

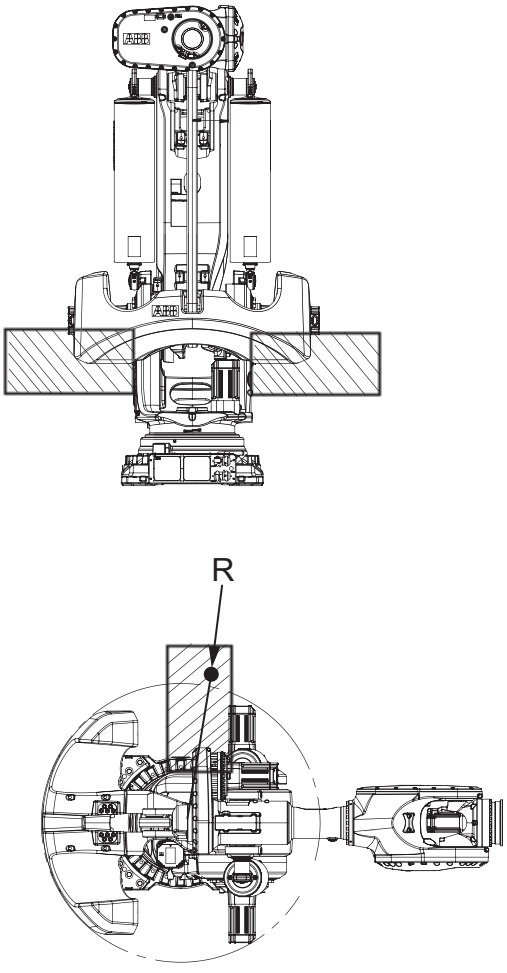
General

Extra loads can be fitted on the upper arm housing, the lower arm, and on the frame. Definitions of distances and masses are shown in the following figures. The robot is supplied with holes for fitting extra equipment (see figure in *Holes for fitting extra equipment on page 45*). Maximum allowed arm load depends on center of gravity of arm load and robot payload.

Frame (hip load)

Extra load can be fitted on the frame.

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



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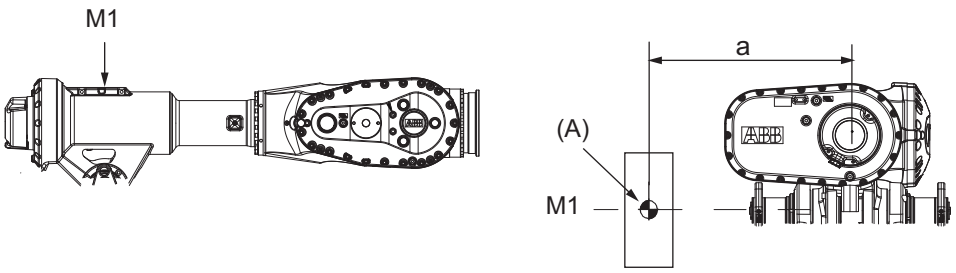
1.6 Fitting equipment
Continued

Upper arm

Allowed extra load on the upper arm housing, in addition to the maximum handling weight, is M1 ≤ 50 kg with a distance (a) ≤ 500 mm from the center of gravity in the axis-3 extension.



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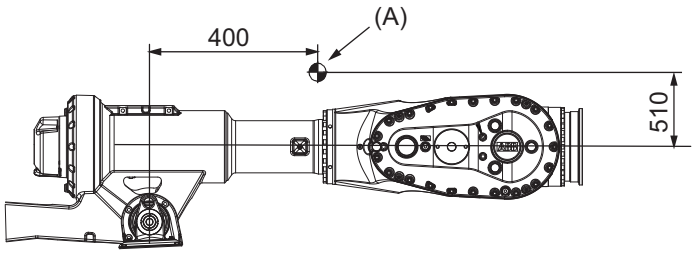
A	Mass center



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A	Center of gravity 50 kg

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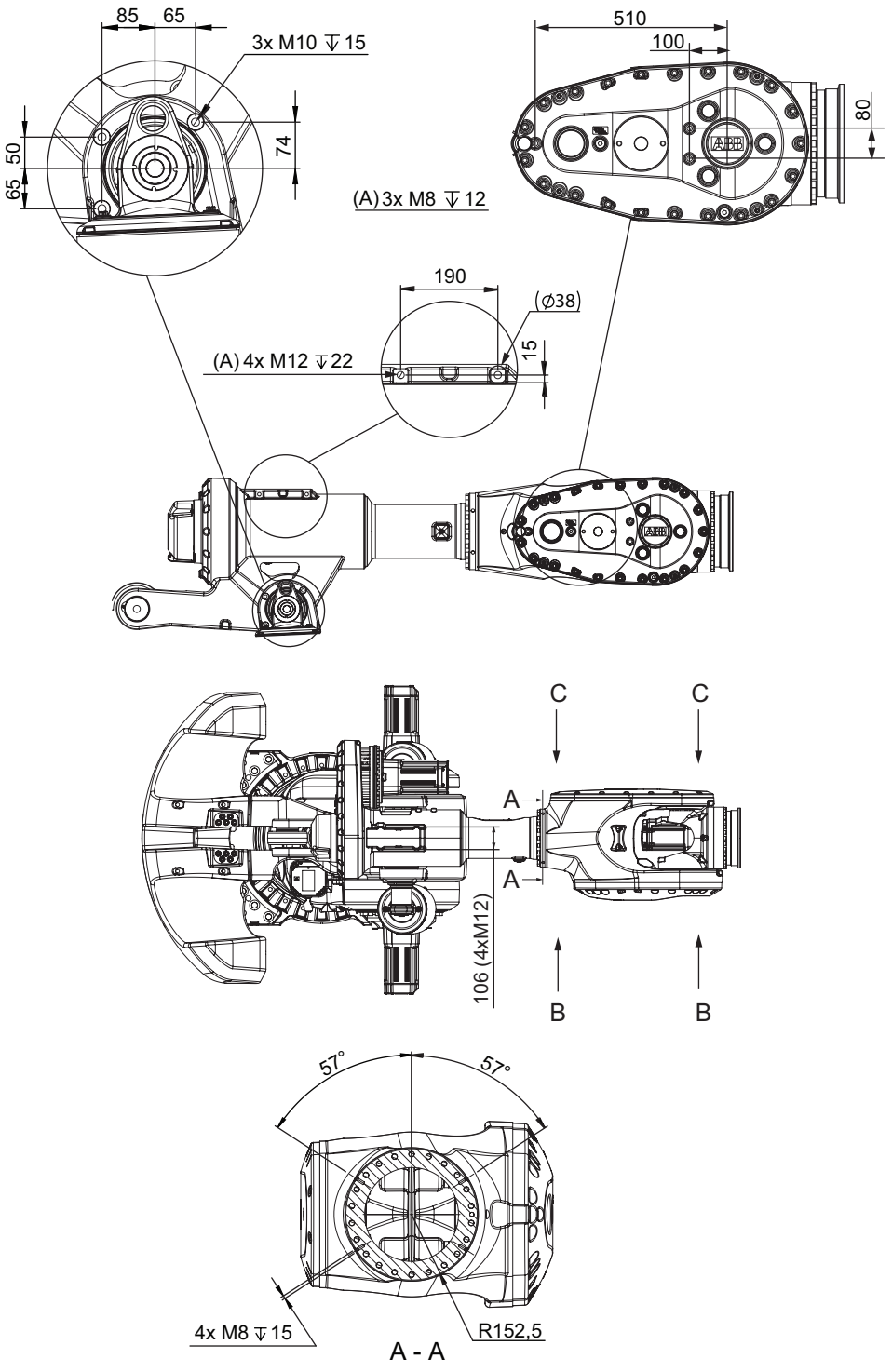
Holes for fitting extra equipment

Upper arm



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A	Holes located on both sides.

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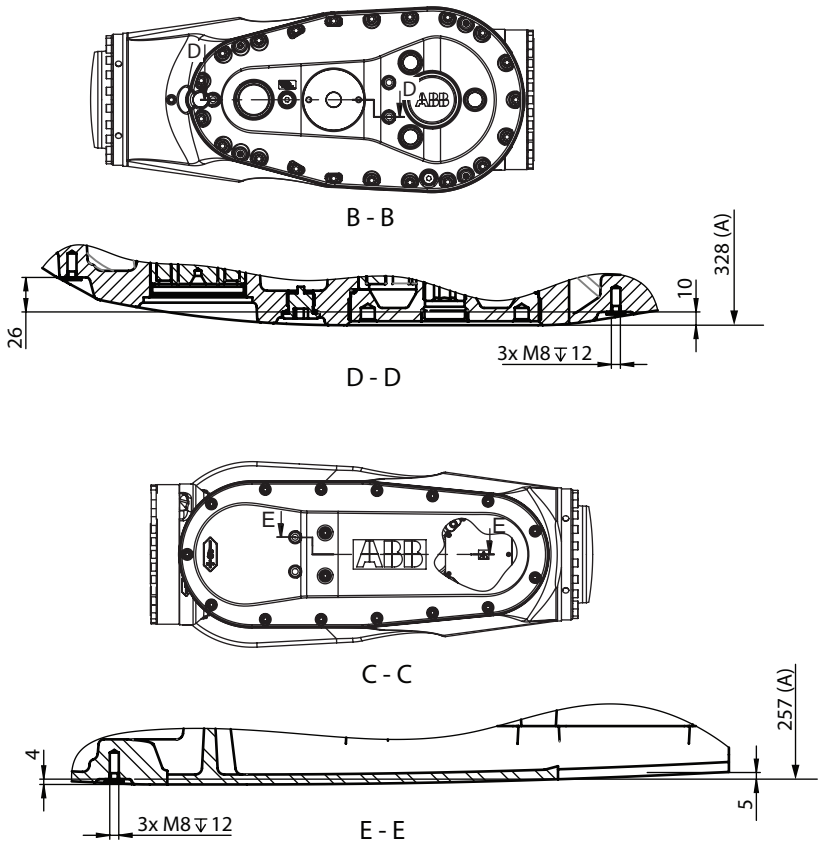
1.6 Fitting equipment
Continued



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A	Measure from center axis 6

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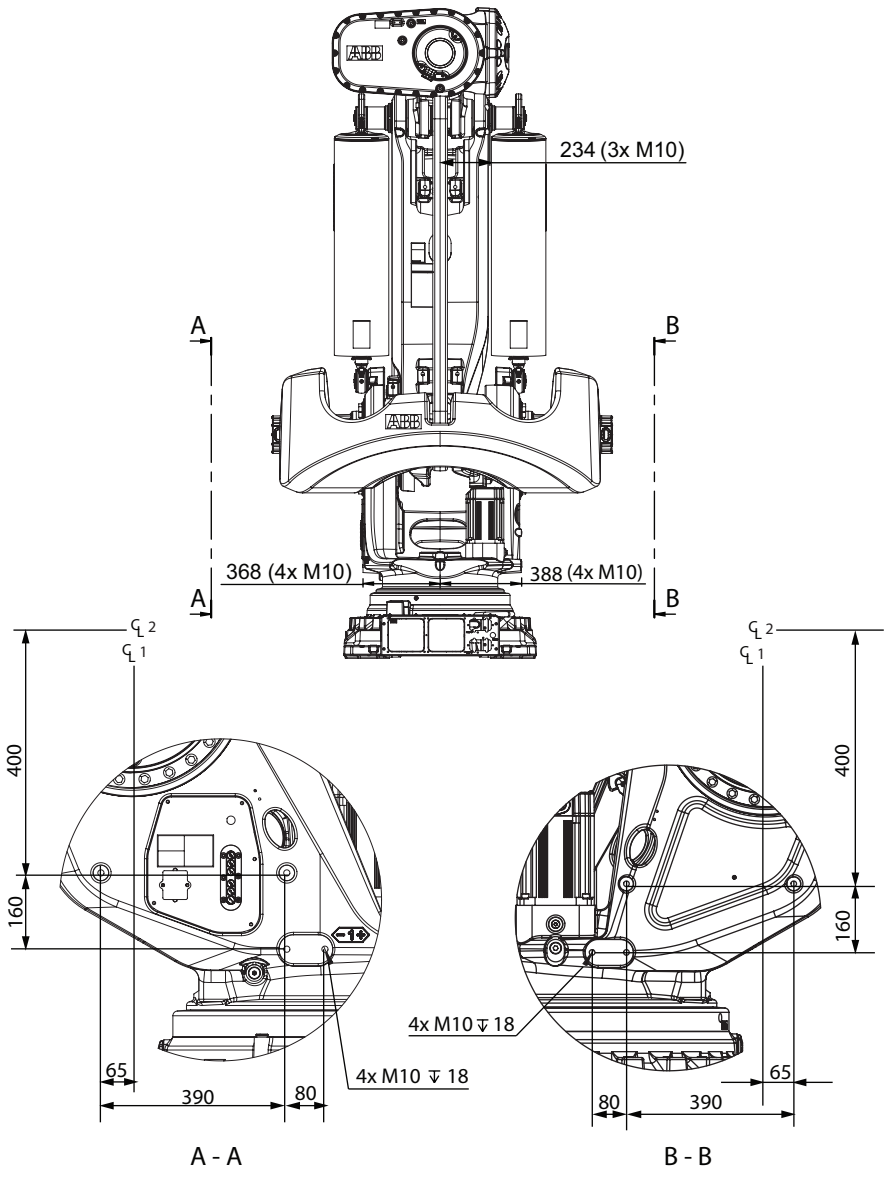
Frame



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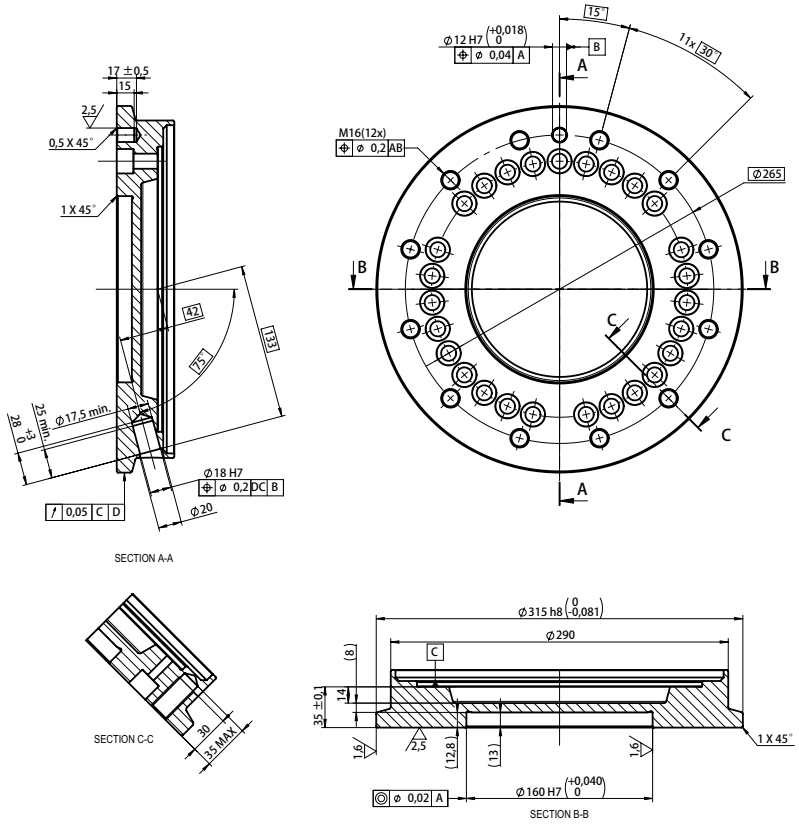
1.6 Fitting equipment
Continued

Tool flange, standard and LeanID



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Fastener quality

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

1.7 Maintenance and troubleshooting

General

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

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

Maintenance

The maintenance intervals depend on the use of the robot. The required maintenance activities also depend on the selected options. For detailed information on maintenance procedures, see the maintenance section in *Product manual - IRB 8700*.

1.8 Robot motion

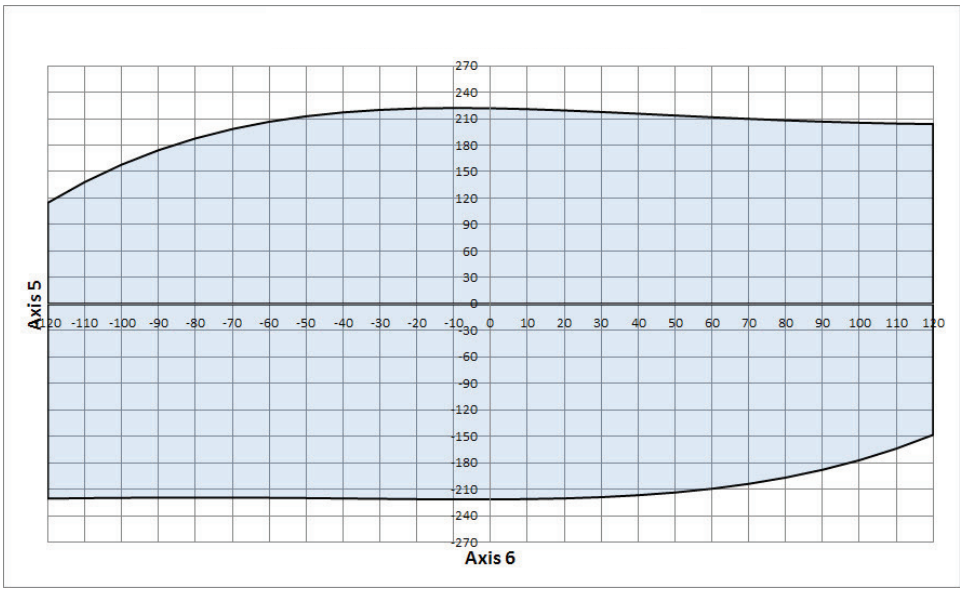
1.8.1 Robot motion

Type of motion

Axis	Type of motion	Range of movement	Note
Axis 1	Rotation motion	±170°	
		±220°	Option
Axis 2	Arm motion	-65°/+90°	
Axis 3	Arm motion	-30°/+132°	
Axis 4	Wrist motion	±300°	
Axis 5	Bend motion	±130°	
Axis 6	Turn motion	±360°	
		±93.7 revolutions	Maximum value. The default working range for axis 6 can be extended by changing parameter values in the software. Option 610-1 *Independent axis* can be used for resetting the revolution counter after the axis has been rotated (no need for "rewinding" the axis).

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

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



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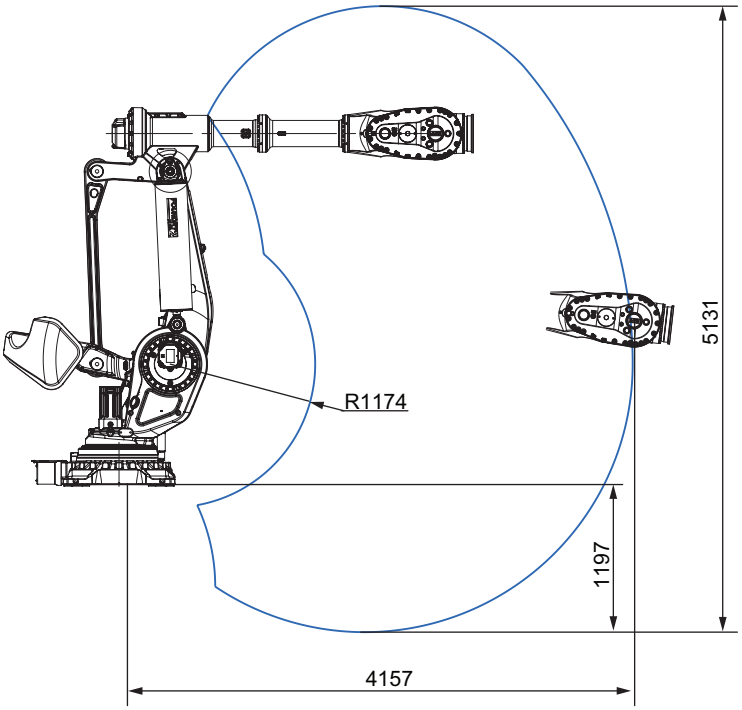
Working range

Robot type	Handling capacity (kg)	Reach (m)
IRB 8700	550	4.20



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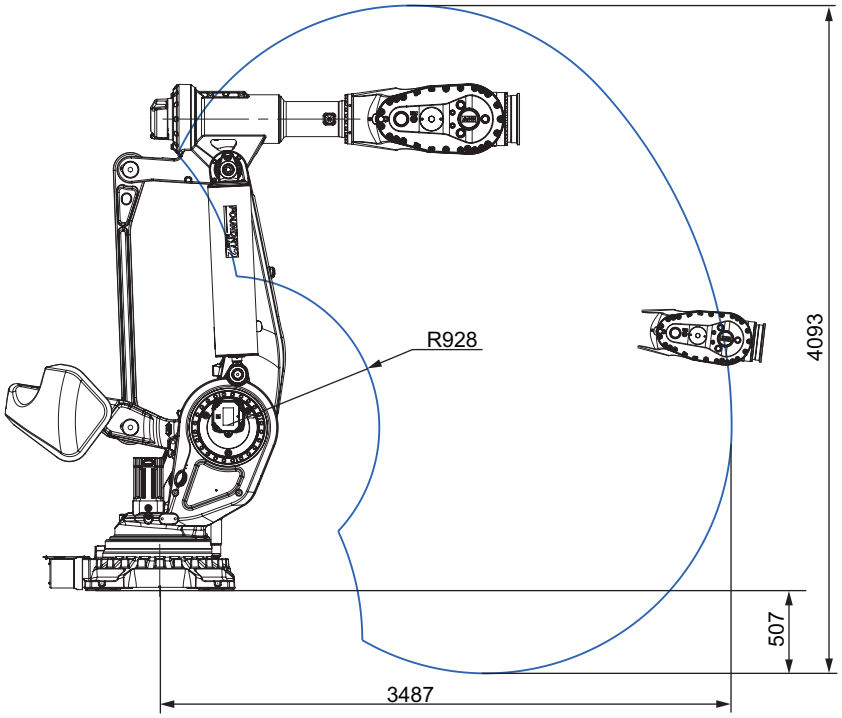
1.8.1 Robot motion

Continued

Robot type	Handling capacity (kg)	Reach (m)
IRB 8700	800	3.50



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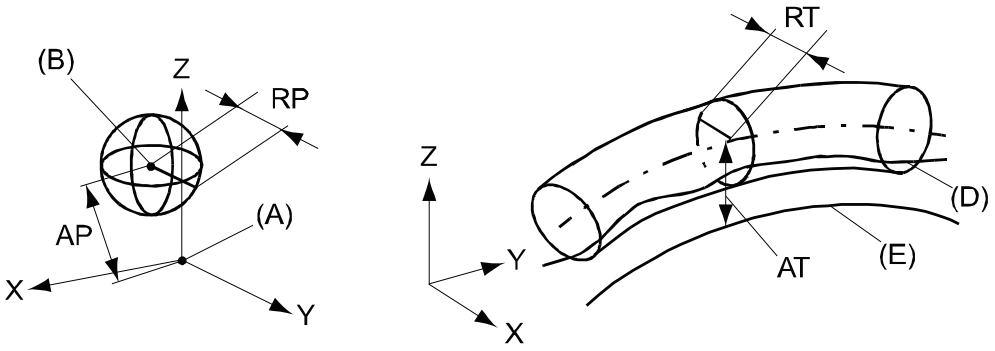
1.8.2 Performance according to ISO 9283

General

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

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



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

IRB 8700	-550/4.20	-800/3.50
Pose accuracy, AP (mm) [i]	0.07	0.09
Pose repeatability, RP (mm)	0.08	0.05
Pose stabilization time, PSt (s) within 0.4 mm of the position	0.48	0.25
Path accuracy, AT (mm)	1.36	1.29
Path repeatability, RT (mm)	0.14	0.07

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

1.8.3 Velocity

Maximum axis speed

Robot type	Axis 1	Axis 2	Axis 3	Axis 4	Axis 5	Axis 6
IRB 8700-550/4.20	75 °/s	60 °/s	60 °/s	85 °/s	85 °/s	115 °/s
IRB 8700-800/3.50	75 °/s	60 °/s	60 °/s	85 °/s	85 °/s	115 °/s

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

1.8.4 Robot stopping distances and times

Introduction

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

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2 DressPack

2.1 Introduction

2.1.1 Included options

DressPack

Includes options for upper arm, lower arm and floor pos C, D and E, see the following figure. These are described separately below but are designed as a complete package for various applications.

The DressPack for the floor contains customer signals.

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

Necessary supports and brackets are also included.

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

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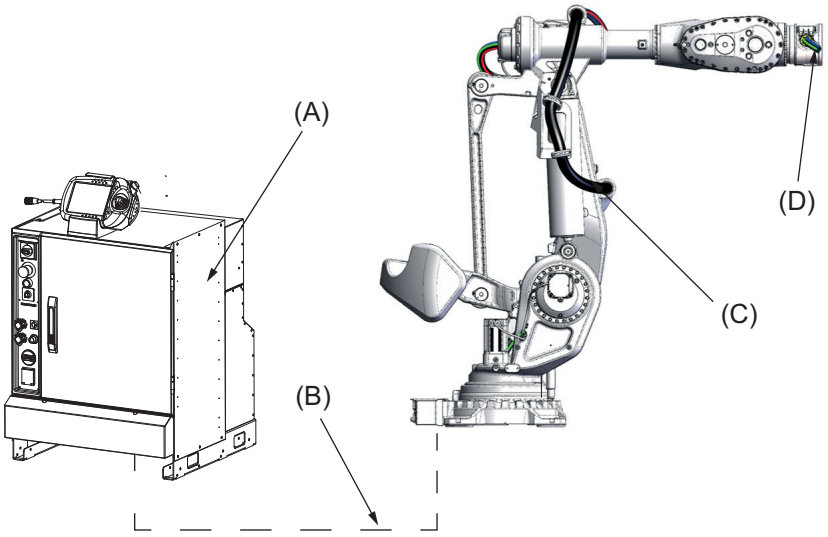
2.1.1 Included options
Continued

Spot welding

The package supplies the transformer gun/gripper with necessary media, such as compressed air, electrical power and software.



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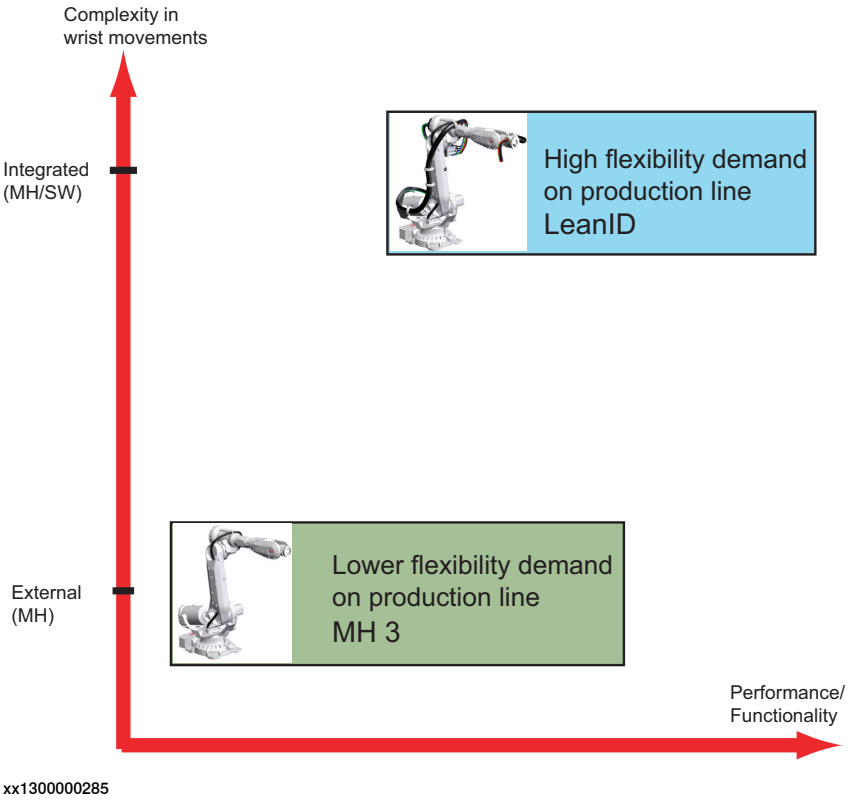
Pos	Description
A	Robot controller, (including 7th axis drive for servo gun)
B	DressPack, floor
C	DressPack, lower arm
D	DressPack, upper arm

2.1.2 Product range

DressPack solutions for different users needs

The different robot types can be equipped with the well integrated cable and hose packages in the DressPack option. The DressPack is designed in close conjunction with the development of the manipulator and is therefore well synchronized with the robot.

As there is a big span between different users need of flexibility, depending of the complexity of the operation/wrist movements, there are two major levels of dress pack solutions available, see Figure below.



Integrated

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

External

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

2.1.3 Limitations of robot movements

General

When using DressPack options on the upper arm the robot movements will be limited.

- Might restrict working range, see *Robot motion on page 50*.

Note

For more detail information please contact Serop Product support/SEROP/ABB.

E-mail address: serop.product_support@se.abb.com

Restrictions for LeanID

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

Axis	Working range
Axis 5	120° to -120°
Axis 6	220° to -220°

2.1.4 Impact on DressPack lifetime

General

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

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

For more detailed information and recommended set-up adjustments, see *Product manual - IRB 8700*.

2.2 DressPack

2.2.1 Introduction

Available DressPack configurations for Material Handling

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

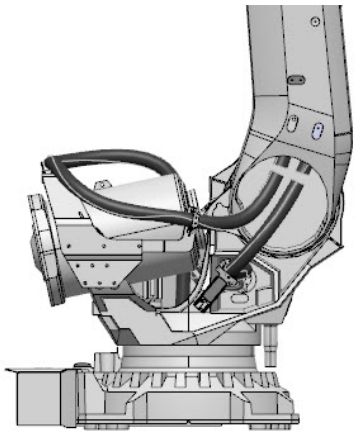
	Lower arm	Upper arm
Material Handling	Option 3325-5x, Base to axis 3 Internal routing in lower arm	Option 3326-1x, Axis 3 to axis 6 External routing
		Option 3326-3x, Axis 3 to axis 6 (LID) Internal routing

Available DressPack configurations for Spot Welding

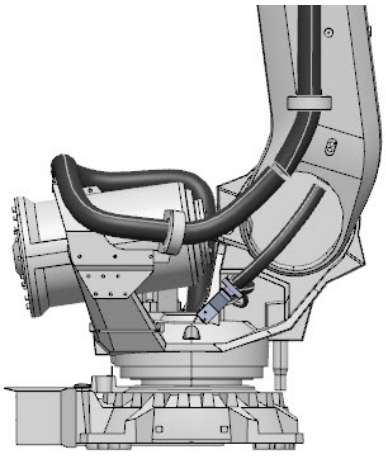
The table below shows the different DressPack configurations available for Spot Welding.

	Lower arm	Upper arm
Spot Welding	Option 3325-5x/6x Base to axis 3	Option 3326-5x/6x Int. Axis 3 to 6 (LeanID) Internal routing

Lower arm



Internal routing in lower arm
Option 3325-1x, Base to axis 3



External routing
Option 3325-1x, Base to axis 3

2.2.2 Built-in features for upper arm DressPack

External

Material handling (option 3326-1x, Axis 3 to axis 6)

- Internal routing through the rear part of the upper arm.
- Protection hose can easily be replaced if damaged.
- One version for all IRB 8700 variants.
- Adjustment for optimal hose/cable lengths.
- Easy exchange of DressPack

Internal

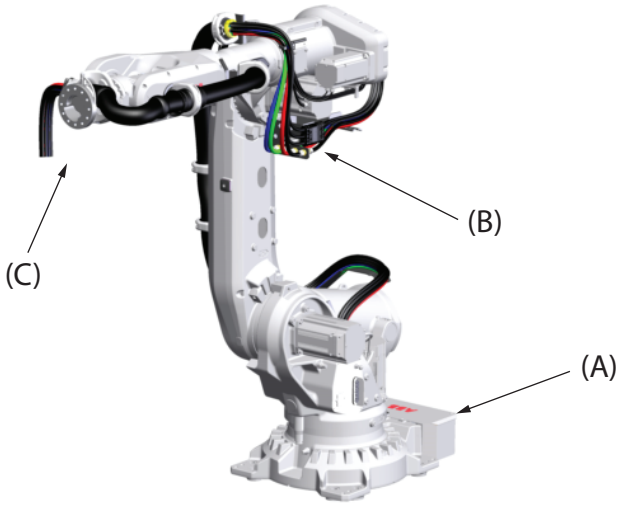
Material handling (option 3326-3x, Axis 3 to axis 6 (LID)), or spot welding (option 3326-5x/6x, Axis 3 to axis 6 (LID))

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

2.2.3 Interface descriptions for DressPack

General

Below is an overview showing the different DressPack options connection points, and their locations. For detailed information see the circuit diagram, and product manual for the manipulator.



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Pos	Location	Description	Options
A	Base	FB7, CP/CS/CBUS/Ethernet	3325-1x
B	Axis 3	CP/CS/CBUS/Ethernet	3325-1x
C	Axis 6	CP/CS/CBUS/Ethernet, WELD	3326-1x, 3326-3x

Base

Material handling (option 3325-11/12), see figure below:

- Included are: A, one D (Proc 1).

Material handling (option 3325-13/14/15), see figure below:

- Included are: A, E, F and one D.

Spot welding (option 3325-5x/6x), see figure below:

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

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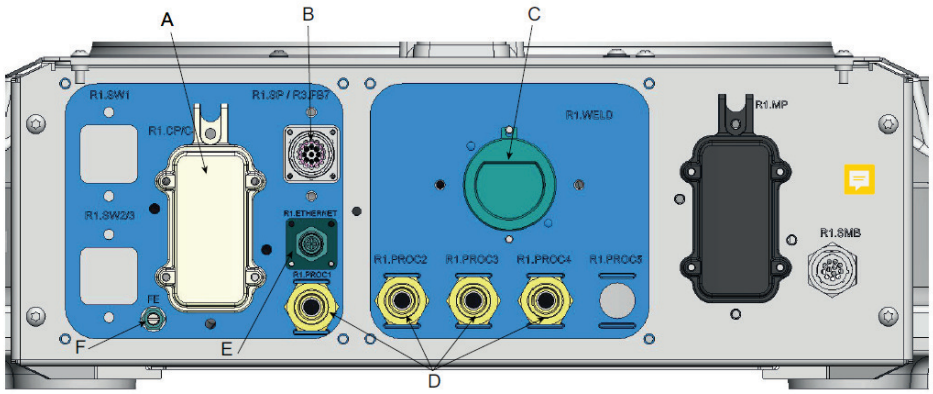

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For corresponding parts of the tool, see *Connector kits on page 70*.

Pos	Description
A	R1.CP/CS
B	R1.SP (spot welding servo gun) or FB7 (resolver connection)
C	R1.WELD 3x35mm^2 (spot welding)
D	R1.PROC 1 (material handling/spot welding 1/2", M22x1.5, 24 degree seal) R1.PROC 2 - 4 (spot welding 1/2", M22x1.5, 24 degree seal)
E	R1.ETHERNET (M12 connector, when EtherNet communication is selected)
F	FE (functional earth, when EtherNet communication is selected)

Axis 3

Material handling (option 3325-11), see figure below:

- Included are: A and one C (Proc 1).

Material handling (option 3325-12), see figure below:

- Included are: A, G and one C (Proc 1).

Material handling (option 3325-13/14/15), see figure below:

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

Spot welding (option 3325-5x/6x), see figure below:

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

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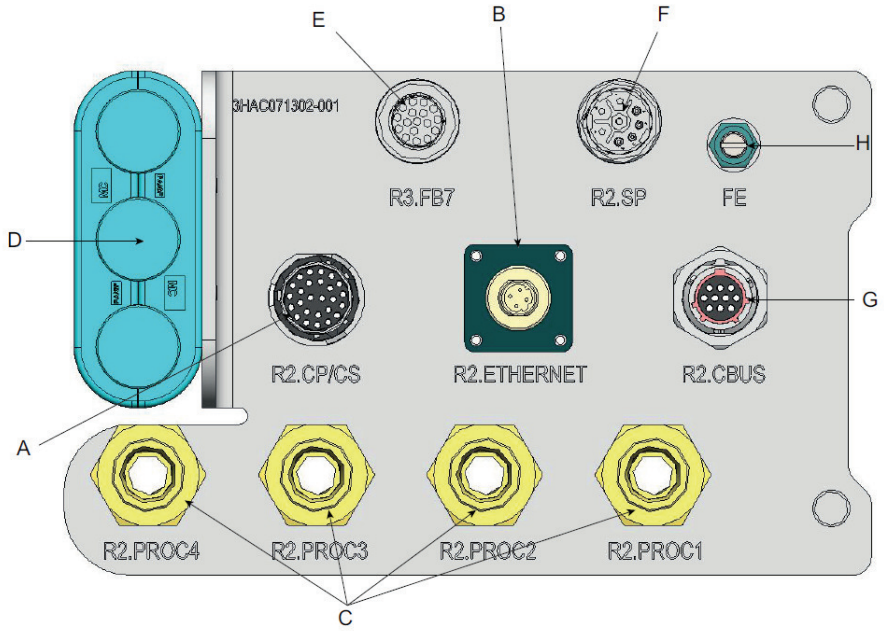
2.2.3 Interface descriptions for DressPack

Continued



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For corresponding parts of the tool, see *Connector kits on page 70*.

Pos	Description
A	R2.CP/CS
B	R2.ETHERNET (M12 connector, when EtherNet communication is selected)
C	R2.PROC 1 (material handling 1/2", M22x1.5, 24 degree seal) R2.PROC 2-4 (spot welding 1/2", M22x1.5, 24 degree seal)
D	R2.WELD 3x35mm^2 (spot welding)
E	R2.FB7
F	R2.SP (spot welding servo gun)
G	R2.CBUS (UTOW connector when DeviceNet communication is selected)
H	FE (functional earth, when EtherNet communication is selected)

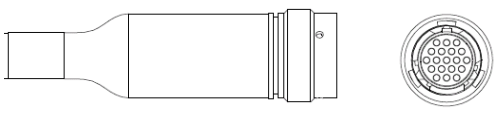
Axis 6

External

Material handling (option 3326-1x), see figure below:

- Hose and cable free length, min. 1,000 mm
- Air hose ends with free end.

The cable ends with a connector, the main parts are described in the list below (for corresponding parts of the tool, see *Connector kits on page 70*):



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Continues on next page

Material handling connector

Material handling (option 3326-1x), see figure below:

- Cable free length, min. 1,000 mm
- Signals are connected with an M12 connector.

The connectors are the same as for option 3326-3x/5x. The difference is the free length of the cables.

Name	Harting article
PIN connector, R3.ETHERNET	21 03 881 1405
PIN	61 03 000 0094

xx1100000956

Material handling connector (LeanID)

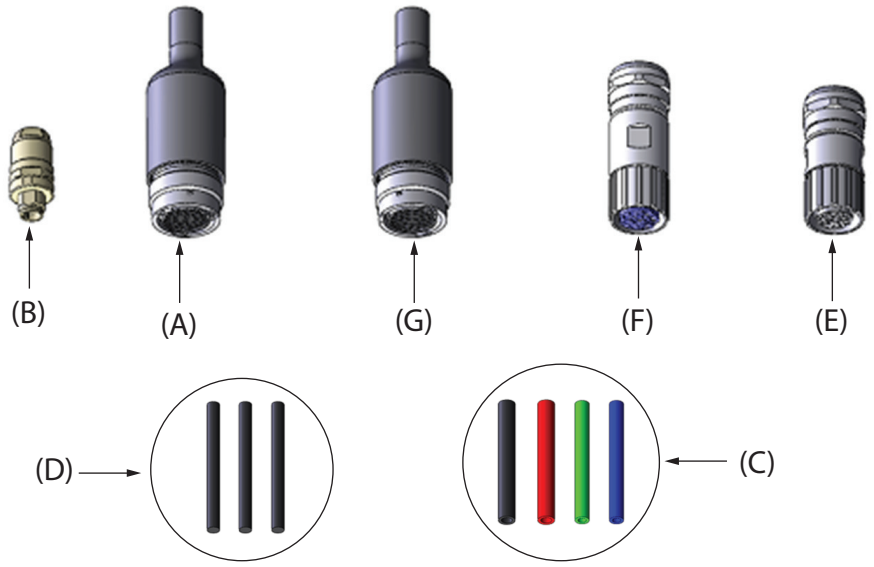
Material handling option 3326-3x/54/55 (LeanID), see figure below:

- Hose and cable free length, min. 1,160 mm
- Hoses with free end.

Continues on next page

2.2.3 Interface descriptions for DressPack
Continued

The cable ends with connectors, for corresponding parts of the tool, see *Connector kits on page 70* and within the UTOW product offer.



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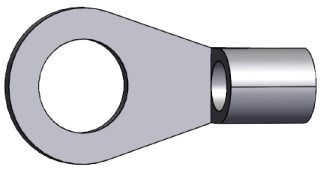
Pos	Description
A	R3.CP/CS (UTOW connector 26p) Customer signals and power
B	R3.ETHERNET (M12 connector) EtherNet signals (when EtherNet communication is selected)
C	R3.PROC 1-2 (1/2", free end) R3.PROC 2-4 (3/8", free end) Media hoses
D	R3.WELD 3x25mm^2 (free end) Spot Welding power
E	R3.FB7 (M23 connector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

- FE (M8 cable lug), when Ethernet option 3326-13/33/34/35/54/55 is selected



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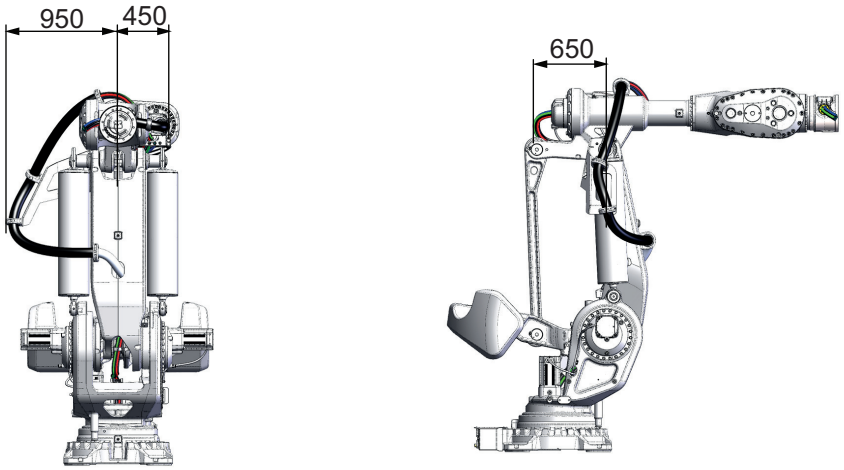
2.2.4 Dimensions

Dimensions for robot with DressPack



xx1500000772

Base to axis 3 + Axis 3 to axis 6

2.3 Connector kits

General

The connector kits are described in section *Connector kits manipulator on page 79*.

3 Specification of variants and options

3.1 Introduction to variants and options

General

The different variants and options for the IRB 8700 are described in the following sections. The same option numbers are used here as in the specification form.

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

3.2 Manipulator

Manipulator variant

Option	Robot variant	Handling capacity (kg)	Reach (m)
3300-105	8700-800/3.5	800	3.50
3300-106	8700-630/3.5 LID	630	3.50
3300-107	8700-550/4.2	550	4.20
3300-108	8700-475/4.2 LID	475	4.20

Manipulator color

Option	Color	RAL code[i]
209-1	ABB orange standard	RAL 7032
209-2	ABB white standard	RAL 9003
209-202	ABB Graphite White std Standard color	RAL 7035
209	RAL code should be specified (ABB non-standard colors)	

[i] The colors can differ depending on supplier and the material on which the paint is applied.

Note

The delivery time for painted spare parts is longer for non-standard colors.

Manipulator protection

Option	Description
3352-10	Foundry Plus2 67, IP67

Requirements

The option *Foundry Plus2 67* [3352-10] requires option *Upper arm cover* [3316-1].

Note

It is strongly recommended, if Foundry Plus robots in another color than ABB orange is required, that only colors in a yellow nuance are selected, if not the robot can look discolored after a while in the foundry environment. The protection is still preserved in any color.

Note

Base 67 includes IP67, according to standard IEC 60529.

Continues on next page

Foundry cable guard

Option	Description
3315-1	Foundry cable guard

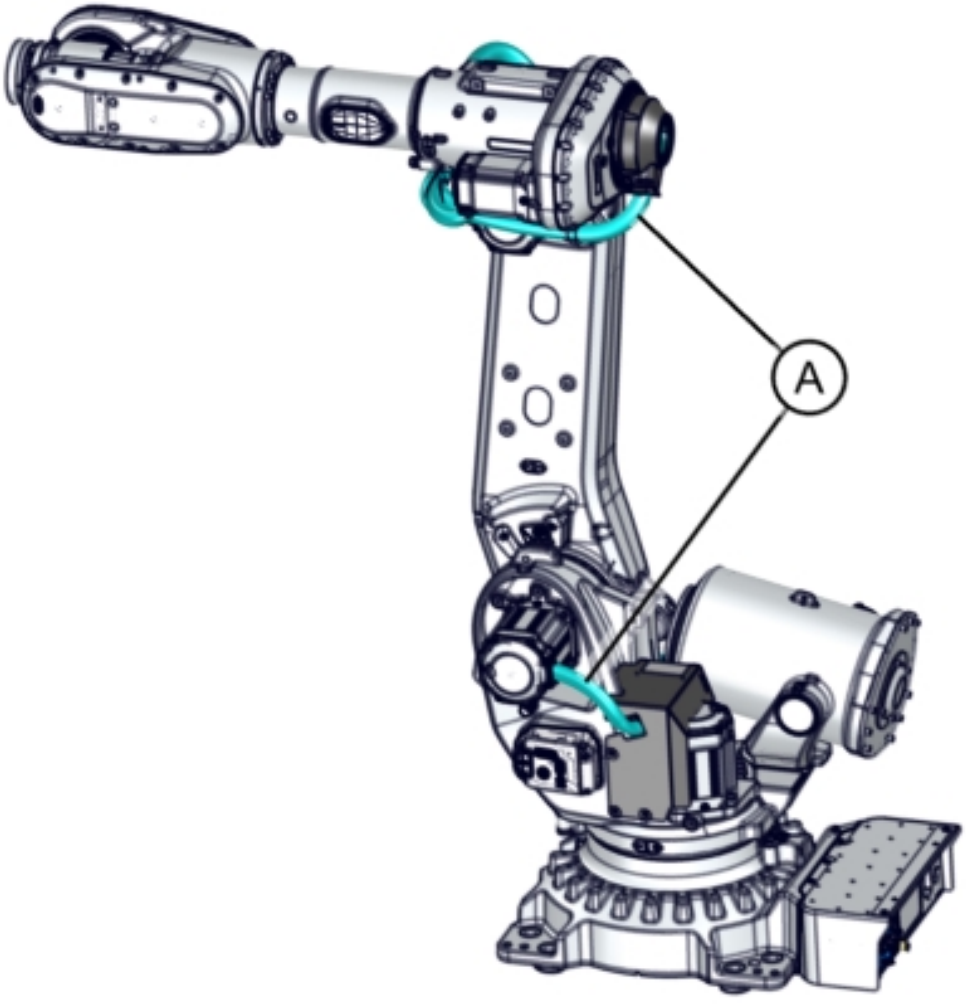
The manipulator can be equipped with additional cable guards for extra tough environmental conditions, for example, metals spits or frequent weld spatter. These additional covers will prolong cable lifetime and simplify service/maintenance as the robot is kept more clean under the covers.

The option *Foundry Cable Guard* is recommended for *Foundry Plus2*.

Requirements

The option *Foundry Cable Guard* requires option *Upper arm cover* [3316-1].

Foundry cable guards for manipulator cable harness



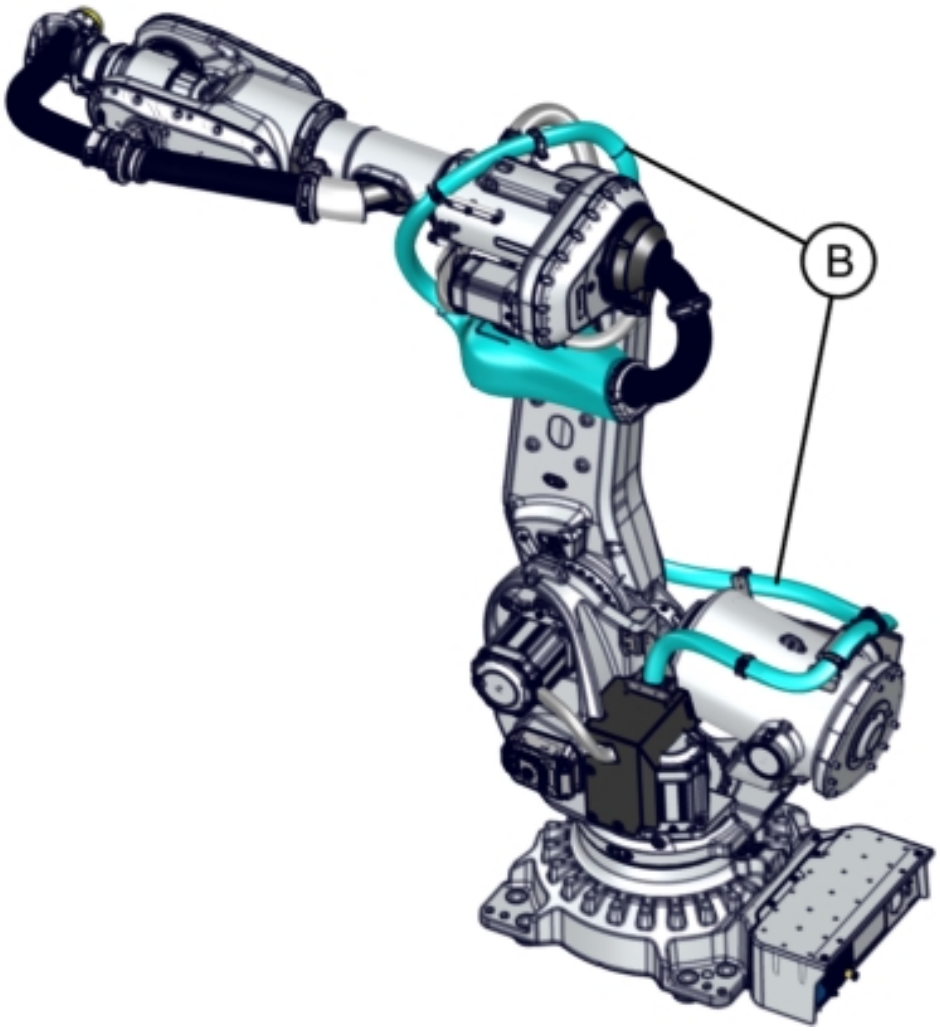
xx2300001724

Schematic illustration

A	Foundry cable guard for manipulator cable harness

Continues on next page

Foundry cable guard for DressPack



xx2300001725

Schematic illustration

B	Foundry cable guard for DressPack

Upper arm cover

Option	Description
3316-1	Upper arm cover

The manipulator can be equipped with additional upper arm covers for environmental conditions, where you want to further seal off the upper arm in wet

Continues on next page

or dirty conditions. These additional covers will prolong the lifetime of the cables, and simplify service/maintenance as the robot is kept more clean under the covers.

xx2100002592

Requirements

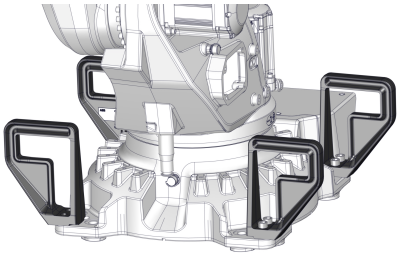
This option is mandatory to order with the option *Foundry Plus2 [3352-10]*.

This option is mandatory to order with the option *Foundry Cable Guard [3315-1]*.

This option is mandatory to order with the option *DressPack axis 3-6* [3326-x].

Forklift device

The manipulator can be delivered with forklift devices, allowing a forklift to be used when moving the manipulator.

Option	Description	
3318-1	Forklift device on base Forklift pockets placed on the base gives a low lifting point.	 xx2300001244

Resolver connection 7th axis

Option	Description
3322-1	On base
3322-2	In servo DressPack This option is required for the option 3325-x DressPack base-axis 3 including servo.

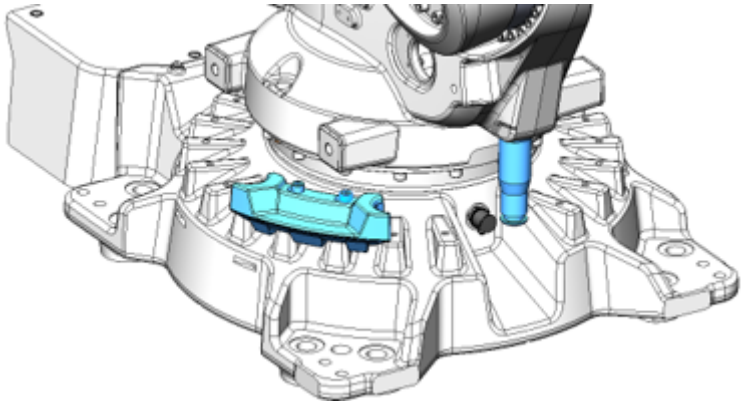
Option 3222-2 In servo DressPack adds a connection point for the 7th axis servo feedback on the frame of the robot to be used in servo DressPack.

Continues on next page

Limited working range

Option	Description
3323-1	Axis 1 adjustable 15°

The manipulator can be equipped with adjustable mechanical stops. This is to mechanically limit the working range on axis 1. The mechanical stops are delivered alongside the robot (not installed). The stops can be placed in steps according to the option.



xx2100002595

Extended working range

Option	Description	
3324-1	Axis 1 to ±220°	The option extends the working range on axis 1 from ±170° to ±220°.

CAUTION

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

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

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

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

Requirements

This option requires the option *SafeMove* [3043-x].

3.3 Floor cables

Manipulator cable length

Option	Lengths
3200-2	7 m
3200-3	15 m
3200-4	22 m
3200-5	30 m

3.4 Application manipulator

DressPack base-axis 3

Option	Description	Additional information
3325-13	MH EtherNet	Includes parallel signals. Supports ProfiNet, EtherNetIP
3325-14	MH CC Link	Includes parallel signals
3325-15	MH EtherCat	Includes parallel signals
3325-63	SW EtherNet-Servo	Includes parallel signals. Supports ProfiNet, EtherNetIP
3325-64	SW CC Link-Servo	Includes parallel signals
3325-65	SW EtherCat-Servo	Includes parallel signals

DressPack axis 3-6

Option	Description	Additional information
3326-13	MH3 EtherNet	Includes parallel signals. Supports ProfiNet, EtherNetIP
3326-14	MH3 CC Link	Includes parallel signals
3326-15	MH3 EtherCat	Includes parallel signals
3326-33	MH LID EtherNet	Includes parallel signals. Supports ProfiNet, EtherNetIP
3326-34	MH LID CC Link	Includes parallel signals
3326-35	MH LID EtherCat	Includes parallel signals
3326-63	SW LID EtherNet-Servo	Includes parallel signals. Supports ProfiNet, EtherNetIP
3326-64	SW LID CC Link-Servo	Includes parallel signals
3326-65	SW LID EtherCat-Servo	Includes parallel signals

3.5 Connector kits manipulator

General

Below is an example of how a connector kit and its parts can look like.

xx1300000223

Continues on next page

3.5.1 Base - Connector kits

Available options

		DressPack options		
Option	Name	3325-1x	3325-5x	3325-6x
3330-2	CP/CS, Proc 1 base	X	X	
3331-1	Weld Proc 2-4 base		X	X
3332-1	FB7 on base			

Note

Servo power connection kits are not available.

Option CP/CS, Proc 1 on base - 3330-2

R1. CP/CS and Proc 1 on base

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

- 1 Hose fittings (swivel nut adapter, (½", M22x1.5 Brass, 24 degree seal))
- Connector with:

1 pcs Hood Foundry (Harting)	HAN EMC / M 40
1 pcs Hinged frame (Harting)	Shell size 16
2 pcs Multicontact, female (Harting)	Type HD (25 pin)
1 pcs Multicontact, female (Harting)	Type DD (12 pin)
1 pcs Multicontact, female (Harting)	Type EE (8 pin)
10 pcs Female crimp contacts	For 1.5 mm^2
10 pcs Female crimp contacts	For 0.5 mm^2
10 pcs Female crimp contacts	For 1.0 mm^2
10 pcs Female crimp contacts	For 2.5 mm^2
12 pcs Female crimp contacts	For 0.14 - 0.37 mm^2
45 sockets	For 0.2 - 0.56 mm^2
Assembly Accessories to complete connector	
Assembly instruction	

Option Weld Proc 2-4 base - 3331-1

This option offers a kit with connectors. This must be assembled by the customer. The kit contains the following components.

WELD

Amount	Description	Size, material, etc.	Brand
1	Welding connector socket	TSB150/L-UR	Stäubli
3	Socket	For 35 mm^2	

Continues on next page

Amount	Description	Size, material, etc.	Brand
1	Form shroud welding conn.	202K174-3/42-0, for cable diameter 15.7-35 mm	Raychem

Media

Amount	Description	Size, material, etc.	Brand
4	Hose coupling	1/2", M22 x 1.5 Brass	

Option FB7 on base - 3332-1

R3. FB 7 on base

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

- Connector with:

1 pcs Multiple connector (pin)	UTOW
1 pcs Adapter	8 pin
8 pcs Pin	For 0.13 - 0.25 mm^2
Assembly Accessories to complete connector	
Assembly instruction	

3.5.2 Axis 3 - Connector kits

Available options

		DressPack options	Description
Option	Name	3325-1x	
3333-2	CP/CS bus, Proc 1 axis 3	X	UTOW
3334-3	CP/CS Proc1, Servo & FB		

Option CP/CS/CBus, Proc 1 axis 3 - 3333-2

CP/CS/CBus, Proc 1 axis 3 on tool side for option 3326-1x and 3326-3x.

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

This must be assembled by the customer.

The kit contains:

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

CP/CS	
1 pcs UTOW Pin connector 26p, bayonet	UTOW61626PH, Shell size 16
26 pcs Pin	RM18W3K, 0.5-0.82 mm^2
CBUS	
1 pcs UTOW Pin connector 10p, bayonet	UTOW61210PH, Shell size 12
10 pcs Pin	RM18W3K, 0.5-0.82 mm^2
Ethernet	
1 pcs Pin connector M12	Harting 21 03 881 1405
4 pcs Pin	Harting 09670005576, 0.13-0.33 mm^2

Option CP/CS Proc1, Servo & FB - 3334-3

SP (Servo Power)	
1 pc Straight connector M23 8p	
4 pcs Crimp pin 1 mm	AWG 24-17
4 pcs Crimp pin 2 mm	AWG 18-14
SS (Servo Signal)	
1 pcs Straight connector M23 17p	
17 pcs Pin	AWG 28-20
Assembly Accessories to complete connector	
Assembly instruction	

3.5.3 Axis 6 - Connector kits

Available options

		DressPack options	DressPack options	Description
Option	Name	3326-1x	3326-3x	
3334-2	CP/CS bus axis 6	X	X	UTOW
3334-3	CP/CS Proc1, Servo & FB			
3335-1	Weld Proc 2-4 axis 6			

Option CP/CS/CBus, Proc 1 axis 6 - 3334-2

CP/CS/CBus/SP/SS, Proc 1 axis 6 on tool side for option 3326-1x and 3326-3x.

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

This must be assembled by the customer.

The kit contains:

- 1 Hose fitting (swivel nut adapter (1/2", M22x1.5 Brass, 24 degree seal))
- Connector with:

CP/CS	
1 pcs UTOW Pin connector 26p, bulkhead	UTOW71626PH05, Shell size 16
26 pcs Pin	RM18W3K, 0.5-0.82 mm^2
CBUS	
1 pcs UTOW Pin connector 10p, bulkhead	UTOW71210PH05, Shell size 12
10 pcs Pin	RM18W3K, 0.5-0.82 mm^2
Ethernet	
1 pcs Socket connector M12	Harting 21 03 881 2425
4 pcs Socket	Harting 09670005476, 0.13-0.33 mm^2

Option CP/CS Proc1, Servo & FB - 3334-3

SP (Servo Power)	
1 pcs Bulkhead contact M23	
4 pcs Crimp pin 1 mm	AWG 24-17
4 pcs Crimp pin 2 mm	AWG 18-14
SS (Servo Signal)	
1 pcs Bulkhead contact M23	
17 pcs Pin	AWG 28-20
Assembly Accessories to complete connector	
Assembly instruction	

Continues on next page

3.5.3 Axis 6 - Connector kits
Continued

Option Weld Proc 2-4 axis 6 - 3335-1

Weld and Proc 2-4 axis 6 on manipulator side for option 3335-1

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

The kit contains:

- 4 Hose fittings (Swivel Nut adapter, (2 x ½", M22x1.5) and (2x 3/8", M16x1.5))
- 1 Multi contact connector (Female) type including:
-

1 pc Welding connector	3x25 mm^2
1 pc Cable gland	Diameter 24-28 mm
1 pc End housing	0.21-0.93 mm^2
1 pcs Reducing coupling	PG36/PG29
Assembly Accessories to complete connector	
Assembly instruction	

3.6 Application floor cables

Parallel cable - Length

Option	Description	Note
3201-2	7 m	
3201-3	15 m	
3201-4	22 m	
3201-5	30 m	

Ethernet cable - Length

Note

Occupies 1 Ethernet port.

Option	Description	Note
3202-2	7 m	Includes Parallel cable
3202-3	15 m	Includes Parallel cable
3202-4	22 m	Includes Parallel cable
3202-5	30 m	Includes Parallel cable

CC-Link cable - Length

Option	Description	Note
3205-2	7 m	Includes Parallel cable
3205-3	15 m	Includes Parallel cable
3205-4	22 m	Includes Parallel cable
3205-5	30 m	Includes Parallel cable

Servo cable 1 axis - Length

Option	Description	Note
3206-2	7 m	
3206-3	15 m	
3206-4	22 m	
3206-5	30 m	

EtherCat cable - Length

Note

Occupies 1 Ethernet port.

Option	Description	Note
3210-2	7 m	Includes Parallel cable

Continues on next page

3.6 Application floor cables
Continued

Option	Description	Note
3210-3	15 m	Includes Parallel cable
3210-4	22 m	Includes Parallel cable
3210-5	30 m	Includes Parallel cable

MCB Servo cable 1 axis

Option	Description	Note
3212-2	7 m	

Requirements

This option requires options DressPack base-axis 3 and Motor Connection Kit [3069-x].

3.7 Warranty

Warranty

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

Note

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

Option	Type	Description
438-1	Standard warranty	Standard warranty is 12 months from *Customer Delivery Date* or latest 18 months after *Factory Shipment Date*, whichever occurs first. Warranty terms and conditions apply.
438-2	Standard warranty + 12 months	Standard warranty extended with 12 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-4	Standard warranty + 18 months	Standard warranty extended with 18 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-5	Standard warranty + 24 months	Standard warranty extended with 24 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-6	Standard warranty + 6 months	Standard warranty extended with 6 months from end date of the standard warranty. Warranty terms and conditions apply.
438-7	Standard warranty + 30 months	Standard warranty extended with 30 months from end date of the standard warranty. Warranty terms and conditions apply.
438-8	Stock warranty	Maximum 6 months postponed start of standard warranty, starting from factory shipment date. Note that no claims will be accepted for warranties that occurred before the end of stock warranty. Standard warranty commences automatically after 6 months from *Factory Shipment Date* or from activation date of standard warranty in WebConfig. **Note** Special conditions are applicable, see *Robotics Warranty Directives*.

Continues on next page

Warranty for DressPack

Note

Option 3326-11/13 upper arm DressPack MH3 is not covered by the warranty.

4 Accessories

4.1 Introduction to accessories

General

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

Basic software and software options for robot and PC

For more information, see *Product specification - OmniCore V line*.

Robot peripherals

- Track Motion
- Motor Units

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