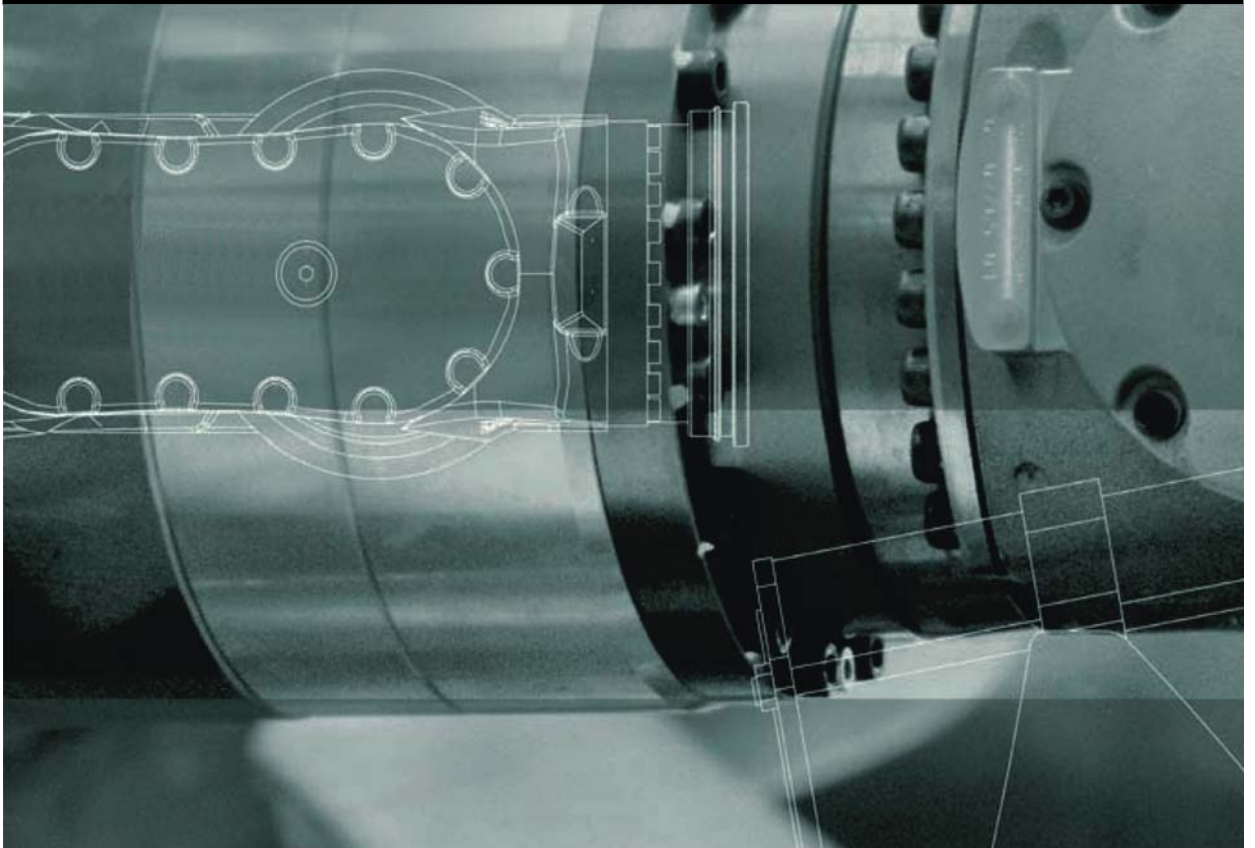


## **KR 1000 1300 titan PA, KR 1000 L950 titan PA**

**With F Variants  
Specification**



Issued: 25.07.2011

Version: Spez KR 1000 titan PA V3 en



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KUKA Roboter GmbH  
Zugspitzstraße 140  
D-86165 Augsburg  
Germany

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

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

Subject to technical alterations without an effect on the function.

Translation of the original documentation

KIM-PS5-DOC

Publication:	Pub Spez KR 1000 titan PA en
Bookstructure:	Spez KR 1000 titan PA V3.1
Label:	Spez KR 1000 titan PA V3 en

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# 1 Introduction

## 1.1 Industrial robot documentation

The industrial robot documentation consists of the following parts:


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


Each of these sets of instructions is a separate document.


## 1.2 Representation of warnings and notes


### Safety


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

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

 **WARNING** These warnings mean that death or severe physical injury **may** occur, if no precautions are taken.


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

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

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

### Hints

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

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



## 2 Purpose

### 2.1 Target group

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

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



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

### 2.2 Intended use

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

#### Misuse

Any use or application deviating from the intended use is deemed to be impermissible misuse; examples of such misuse include:

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

#### NOTICE

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



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



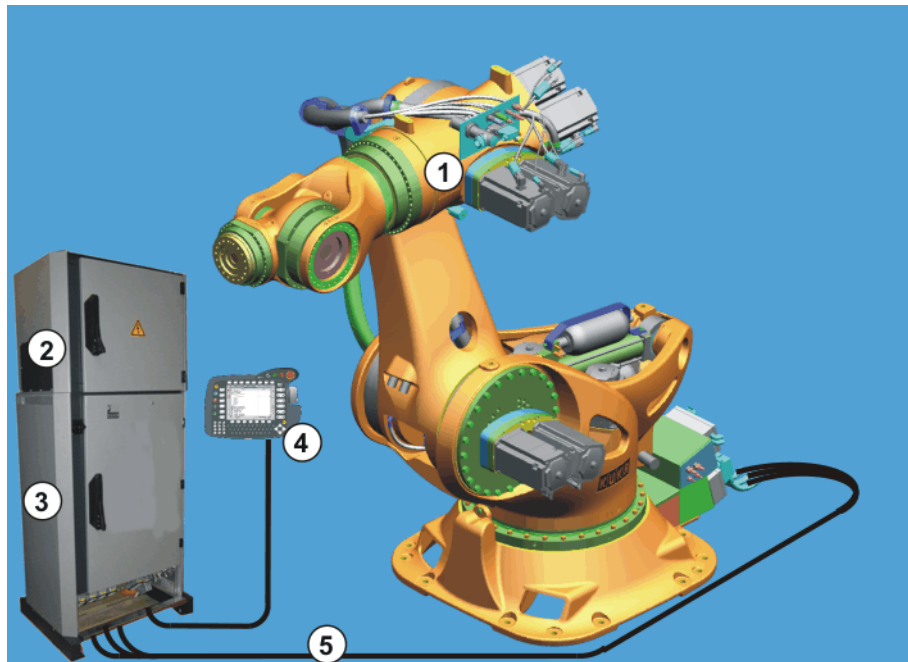


## 3 Product description

### 3.1 Overview of the industrial robot

The industrial robot consists of the following components:

- Manipulator
- Robot controller
- Teach pendant
- Connecting cables
- Software
- Options, accessories



**Fig. 3-1: Example of an industrial robot**

- |                       |                       |
|-----------------------|-----------------------|
| 1 Manipulator         | 4 Teach pendant (KCP) |
| 2 Top-mounted cabinet | 5 Connecting cables   |
| 3 Robot controller    |                       |

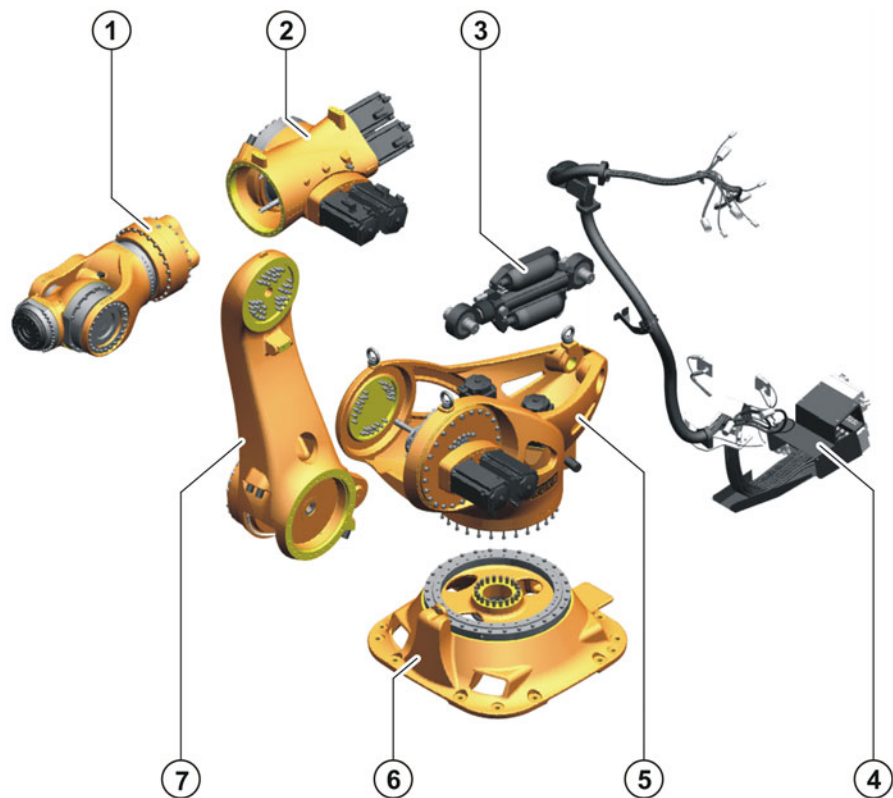
### 3.2 Description of the robot

#### Overview

The robots are designed as 6-axis jointed-arm kinematic systems. The structural components of the robot are made of iron castings. The design and structure of the robot variants KR 1000 titan and KR 1000 titan PA are identical. The robot may only be operated in palletizing mode with the specified rated payloads.

The robot consists of the following principal components:

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



**Fig. 3-2: Principal components of the KR 1000 titan**

- |   |                          |   |                 |
|---|--------------------------|---|-----------------|
| 1 | In-line wrist            | 5 | Rotating column |
| 2 | Arm                      | 6 | Base frame      |
| 3 | Counterbalancing system  | 7 | Link arm        |
| 4 | Electrical installations |   |                 |

### In-line wrist

The robot is fitted with a 3-axis in-line wrist. The in-line wrist comprises axes 4, 5 and 6. It is driven by 3 motors installed at the rear end of the arm via connecting shafts. For attaching end effectors (tools), the in-line wrist has a mounting flange. The gear units of the in-line wrist are supplied with oil from 3 separate oil chambers. The robot can be equipped with an in-line wrist for a rated payload of 1000 kg or 750 kg, depending on the variant. The 1000 kg in-line wrist is used in palletizing mode with a rated payload of 1300 kg. The 750 kg in-line wrist is 400 mm longer and can be operated with a rated payload of 950 kg.

If the robot is used in palletizing mode, axis 4 is deactivated and axis 5 is always kept parallel to the robot mounting plane, depending on the specific program.

Additional measures have been taken to enable in-line wrists of the F variants to meet higher specifications in terms of resistance to temperature, dust and corrosion. F variant in-line wrists meet the requirements of IP 67.

### Arm

The arm is the link between the in-line wrist and the link arm. It houses the motors of the wrist axes A4, A5 and A6 and the motors of main axis A3. The arm is driven by the 2 motors of axis 3, which drive the gear unit between the arm and the link arm via an input stage. The maximum permissible swivel angle is mechanically limited by a stop for each direction, plus and minus. The associated buffers are attached to the arm.

The arms of the F variants are pressurized to prevent penetration of moisture and dust. The required compressed air is supplied via a hose in the cable har-

ness. The pressure regulator for this is installed in the push-in module for the electrical installations.

<b>Link arm</b>	The link arm is the assembly located between the arm and the rotating column. It is mounted in the rotating column with a gear unit on each side and is driven by 2 motors. The two motors engage with an input stage before driving both gear units via a shaft.
<b>Rotating column</b>	The rotating column houses the motors of axes 1 and 2. The rotational motion of axis 1 is performed by the rotating column. It is screwed to the base frame via the gear unit of axis 1. The motors for driving axis 1 are mounted inside the rotating column. The bearings of the counterbalancing system are situated at the rear.
<b>Base frame</b>	The base frame is the base of the robot. It is screwed to the mounting base. The interfaces for the electrical installations and the energy supply systems (accessory) are housed in the base frame. For transportation by fork lift truck, fork slots are provided on the base frame.
<b>Counterbalancing system</b>	<p>The counterbalancing system is installed between the rotating column and the link arm and serves to minimize the moments generated about axis 2 when the robot is in motion and at rest. A closed, hydropneumatic system is used. The system consists of 2 diaphragm accumulators and a cylinder with associated hoses, pressure gauge and safety valve.</p> <p>When the link arm is vertical, the counterbalancing system has no effect. With increasing deflection in the plus or minus direction, the hydraulic oil is pressed into the two diaphragm accumulators, thereby generating the necessary counterforce to compensate the moment of the axis. The diaphragm accumulators are filled with nitrogen.</p> <p>Different variants of the counterbalancing system are used for F variant robots. These variants are characterized by their improved resistance to dust, temperature and humidity.</p>



## 4 Technical data

### 4.1 Basic data, KR 1000 1300 titan PA

#### Basic data

Type	KR 1000 1300 titan PA
Number of axes	4
Volume of working envelope	69.5 m <sup>3</sup>
Pose repeatability (ISO 9283)	±0.10 mm
Working envelope reference point	Intersection of the center of the mounting flange face with axis 6
Weight	approx. 4,690 kg
Principal dynamic loads	See "Loads acting on the mounting base"
Protection classification of the robot	IP 65 ready for operation, with connecting cables plugged in (according to EN 60529)
Protection classification of the in-line wrist	IP 65
Protection classification of the F in-line wrist	IP 67
Sound level	< 75 dB (A) outside the working envelope
Mounting position	Floor
Surface finish, paintwork	Base (stationary): black (RAL 9005); moving parts: KUKA orange 2567

#### Transport dimensions

	Without buffer A2	With buffer A2
Length	2,123 mm	2,106 mm
Width	1,420 mm	1,420 mm
Height	2,371 mm	2,543 mm
	These dimensions refer to the robot only, without wooden transport blocks.	

#### Transport dimensions with transport frame

Length	4,000 mm
Width	1,750 mm
Height	2,191 mm
Height with lifting tackle	3,500 mm

#### Foundry robot

Overpressure in the arm	0.01 MPa (0.1 bar)
Compressed air	Free of oil and water

<b>Compressed air supply line</b>	Air line in the cable set
<b>Air consumption</b>	0.1 m <sup>3</sup> /h
<b>Air line connection</b>	Quick Star push-in fitting for hose PUN-6x1, blue
<b>Pressure regulator connection</b>	R 1/8", internal thread
<b>Input pressure</b>	0.1 - 1.2 MPa (1 - 12 bar)
<b>Pressure regulator</b>	0.005 - 0.07 MPa (0.05 - 0.7 bar)
<b>Manometer range</b>	0.0 - 0.1 MPa (0.0 - 1.0 bar)
<b>Filter gauge</b>	25 - 30 µm
<b>Thermal loading</b>	10 s/min at 353 K (180 °C)
<b>Resistance</b>	Increased resistance to dust, lubricants, coolants and water vapor.
<b>Special paint finish on wrist</b>	Heat-resistant and heat-reflecting silver paint finish on the in-line wrist.
<b>Special paint finish on the robot</b>	Special paint finish on the entire robot, and an additional protective clear coat.
<b>Other ambient conditions</b>	KUKA Roboter GmbH must be consulted if the robot is to be used under other ambient conditions.

#### Ambient temperature

<b>Operation</b>	+10 °C to +55 °C (283 K to 328 K)
<b>Operation with Safe RDC</b>	+10 °C to +50 °C (283 K to 323 K)
<b>Storage and transportation</b>	-40 °C to +60 °C (233 K to 333 K)
<b>Start-up</b>	+10 °C to +15 °C (283 K to 288 K) At these temperatures the robot may have to be warmed up before normal operation. Other temperature limits available on request.
<b>Humidity rating</b>	Humidity class EN 60204/4.4.4 F

#### Connecting cables

<b>Cable designation</b>	<b>Connector designation</b>	<b>Interface with robot</b>
Motor cable 1	X20.1 - X30.1	Rectangular connector, size 24
Motor cable 2	X20.2 - X30.2	Rectangular connector, size 24
Motor cable 3	X20.3 - X30.3	Rectangular connector, size 24
Control cable 1, A1/A2	XA21 - X31.2	Circular connector M23
Control cable 2, A1/A2	X21.1 - X41	Circular connector M23
Safe control cable	X21 - X31	Circular connector M23
Ground conductor		Ring cable lug, 8 mm

<b>Cable lengths</b>	
<b>Standard</b>	15 m, 25 m, 35 m, 50 m
<b>with RoboTeam</b>	15 m, 25 m, 35 m
<b>with SafeRobot</b>	15 m, 25 m, 35 m

For detailed specifications of the connecting cables, see (>>> 6.3 "Connecting cables and interfaces" Page 60)

For connecting cables longer than 35 m an additional ground conductor is provided and must be installed.

## 4.2 Basic data, KR 1000 L950 titan PA

### Basic data

<b>Type</b>	KR 1000 L950 titan PA
<b>Number of axes</b>	4
<b>Volume of working envelope</b>	102.5 m <sup>3</sup>
<b>Pose repeatability (ISO 9283)</b>	±0.10 mm
<b>Working envelope reference point</b>	Intersection of the center of the mounting flange face with axis 6
<b>Weight</b>	approx. 4,740 kg
<b>Principal dynamic loads</b>	See "Loads acting on the mounting base"
<b>Protection classification of the robot</b>	IP 65 ready for operation, with connecting cables plugged in (according to EN 60529)
<b>Protection classification of the in-line wrist</b>	IP 65
<b>Protection classification of the F in-line wrist</b>	IP 67
<b>Sound level</b>	< 75 dB (A) outside the working envelope
<b>Mounting position</b>	Floor
<b>Surface finish, paintwork</b>	Base (stationary): black (RAL 9005); moving parts: KUKA orange 2567

### Transport dimensions

	Without buffer A2	With buffer A2
<b>Length</b>	2,506 mm	2,506 mm
<b>Width</b>	1,420 mm	1,420 mm
<b>Height</b>	2,371 mm	2,543 mm
	These dimensions refer to the robot only, without wooden transport blocks.	

**Transport dimensions with transport frame**

<b>Length</b>	4,000 mm
<b>Width</b>	1,750 mm
<b>Height</b>	2,191 mm
<b>Height with lifting tackle</b>	3,500 mm

**Foundry robot**

<b>Overpressure in the arm</b>	0.01 MPa (0.1 bar)
<b>Compressed air</b>	Free of oil and water
<b>Compressed air supply line</b>	Air line in the cable set
<b>Air consumption</b>	0.1 m <sup>3</sup> /h
<b>Air line connection</b>	Quick Star push-in fitting for hose PUN-6x1, blue
<b>Pressure regulator connection</b>	R 1/8", internal thread
<b>Input pressure</b>	0.1 - 1.2 MPa (1 - 12 bar)
<b>Pressure regulator</b>	0.005 - 0.07 MPa (0.05 - 0.7 bar)
<b>Manometer range</b>	0.0 - 0.1 MPa (0.0 - 1.0 bar)
<b>Filter gauge</b>	25 - 30 µm
<b>Thermal loading</b>	10 s/min at 353 K (180 °C)
<b>Resistance</b>	Increased resistance to dust, lubricants, coolants and water vapor.
<b>Special paint finish on wrist</b>	Heat-resistant and heat-reflecting silver paint finish on the in-line wrist.
<b>Special paint finish on the robot</b>	Special paint finish on the entire robot, and an additional protective clear coat.
<b>Other ambient conditions</b>	KUKA Roboter GmbH must be consulted if the robot is to be used under other ambient conditions.

**Ambient temperature**

<b>Operation</b>	+10 °C to +55 °C (283 K to 328 K)
<b>Operation with Safe RDC</b>	+10 °C to +50 °C (283 K to 323 K)
<b>Storage and transportation</b>	-40 °C to +60 °C (233 K to 333 K)
<b>Start-up</b>	+10 °C to +15 °C (283 K to 288 K) At these temperatures the robot may have to be warmed up before normal operation. Other temperature limits available on request.
<b>Humidity rating</b>	Humidity class EN 60204/4.4.4 F



**Connecting  
cables**

Cable designation	Connector designation	Interface with robot
Motor cable 1	X20.1 - X30.1	Rectangular connector, size 24
Motor cable 2	X20.2 - X30.2	Rectangular connector, size 24
Motor cable 3	X20.3 - X30.3	Rectangular connector, size 24
Control cable 1, A1/A2	XA21 - X31.2	Circular connector M23
Control cable 2, A1/A2	X21.1 - X41	Circular connector M23
Safe control cable	X21 - X31	Circular connector M23
Ground conductor		Ring cable lug, 8 mm

Cable lengths	
<b>Standard</b>	15 m, 25 m, 35 m, 50 m
<b>with RoboTeam</b>	15 m, 25 m, 35 m
<b>with SafeRobot</b>	15 m, 25 m, 35 m

For detailed specifications of the connecting cables, see

For connecting cables longer than 35 m an additional ground conductor is provided and must be installed.

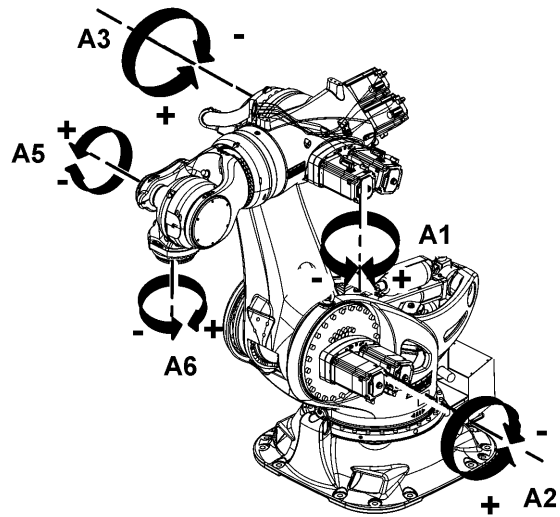
**4.3 Axis data**

The following data are valid for the robots KR 1000 1300 titan PA and KR 1000 L950 titan PA.

**Axis data**

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-150°	58°/s
2	+17.5° to -130°	50°/s
3	+145° to -110°; in palletizing mode +62° to +145°	50°/s
5	+/-118° program-dependent, parallel to the robot mounting plane	60°/s
6	+/-350°	72°/s

The direction of motion and the arrangement of the individual axes may be noted from the diagram ([>>> Fig. 4-1](#)). Axis 5 is in palletizing mode.



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

The diagrams ( >>> Fig. 4-2 ) and ( >>> Fig. 4-3 ) show the shape and size of the working envelopes.

# Working envelope

Maße / Dimensions: mm

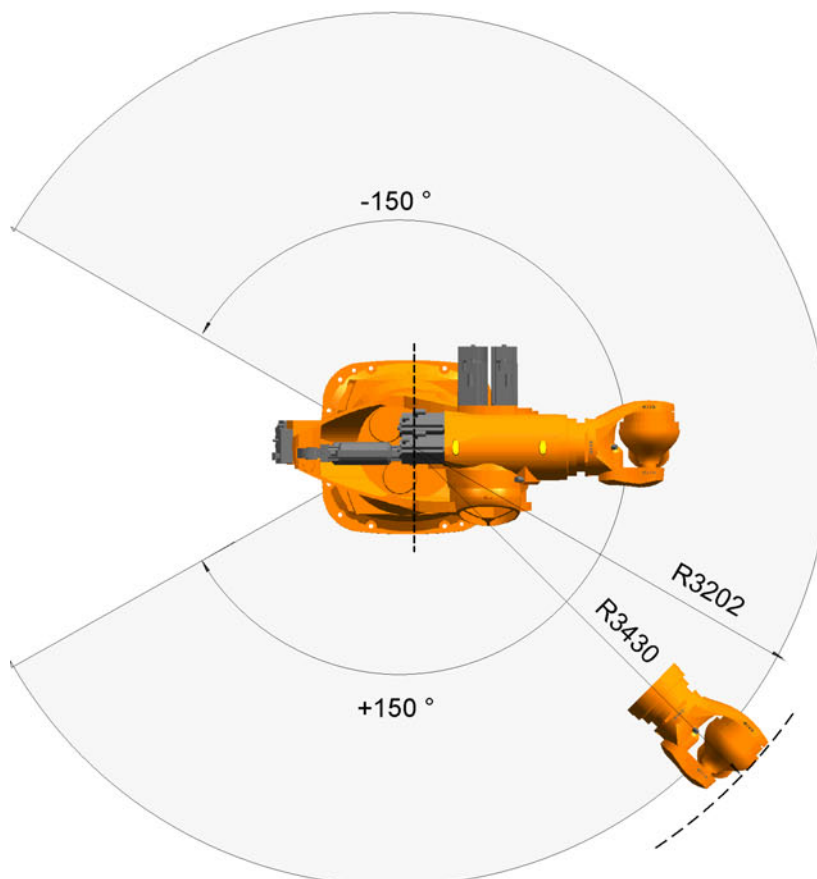
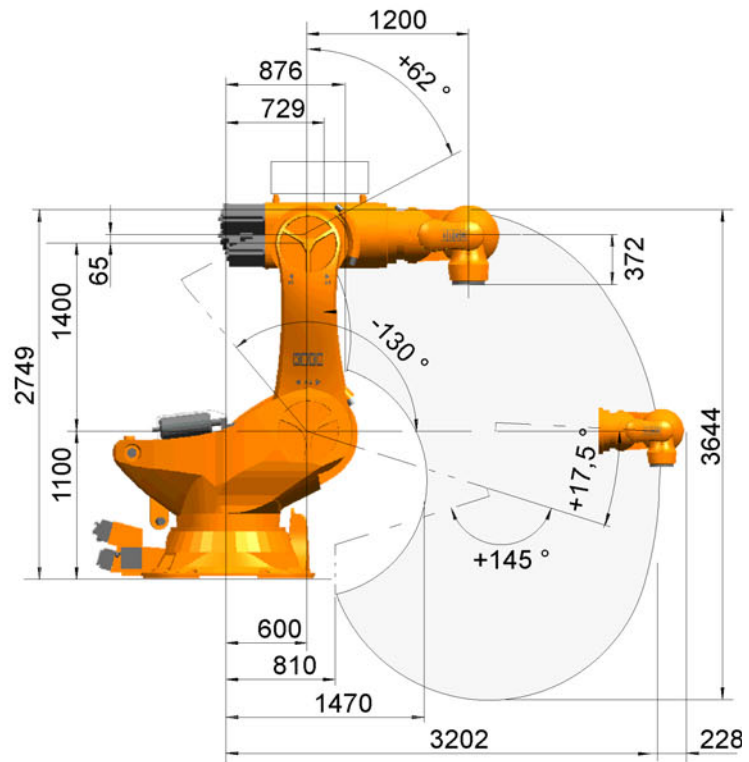
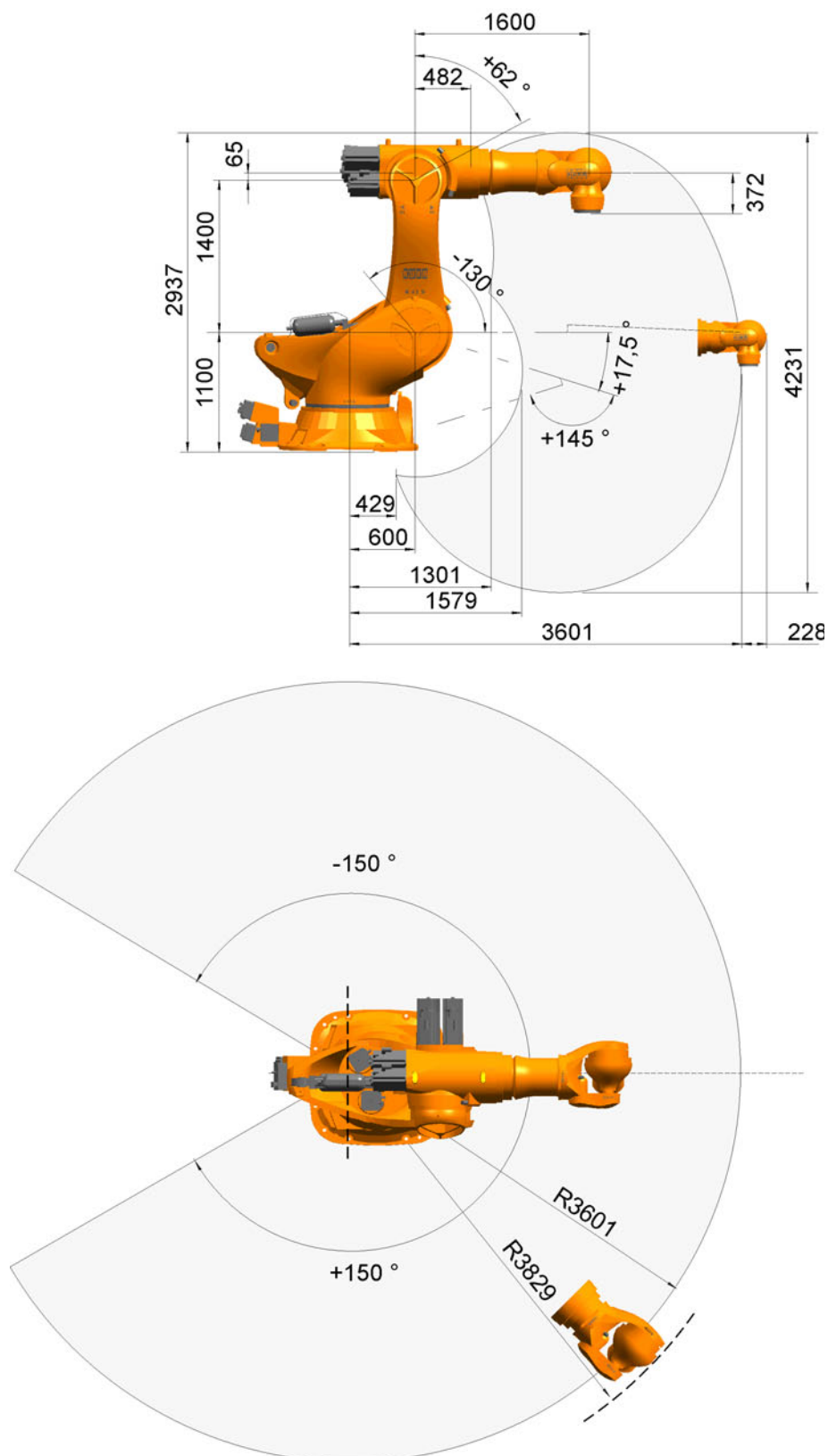


Fig. 4-2: Working envelope, KR 1000 1300 titan PA

Maße / Dimensions: mm



**Fig. 4-3: Working envelope, KR 1000 L950 titan PA**

The reference point for the working envelope is the intersection of the mounting flange face with axis 6.

#### 4.4 Payloads, KR 1000 1300 titan PA

##### Payloads

Robot	KR 1000 1300 titan PA
In-line wrist	IW 1000
Rated payload	1,300 kg
Distance of the load center of gravity $L_z$	400 mm
Distance of the load center of gravity $L_{xy}$	150 mm
Permissible moment of inertia	500 kgm <sup>2</sup>
Max. total load = Payload + Supplementary load	1,350 kg
Supplementary load on arm	100 kg
Supplementary load on link arm	0 kg
Supplementary load on rotating column	0 kg
Supplementary load on base frame	0 kg

##### Load center of gravity P

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

##### Payload diagram

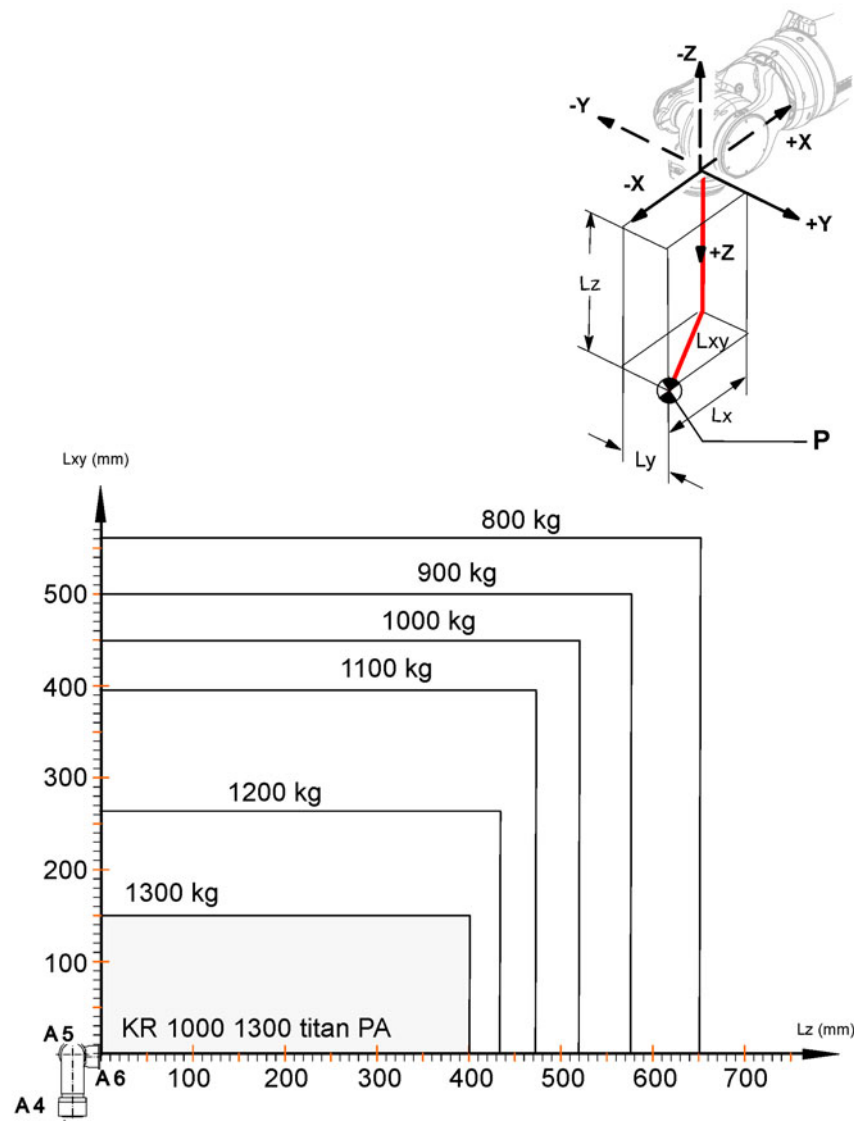


Fig. 4-4: Payload diagram for KR 1000 1300 titan PA



This loading curve corresponds to the maximum load capacity. Both values (payload and principal moment of inertia) must be checked in all cases. Exceeding this capacity will reduce the service life of the robot and overload the motors and the gears; in any such case KUKA Roboter GmbH must be consulted beforehand.

The values determined here are necessary for planning the robot application. For commissioning the robot, additional input data are required in accordance with operating and programming instructions of the KUKA System Software.

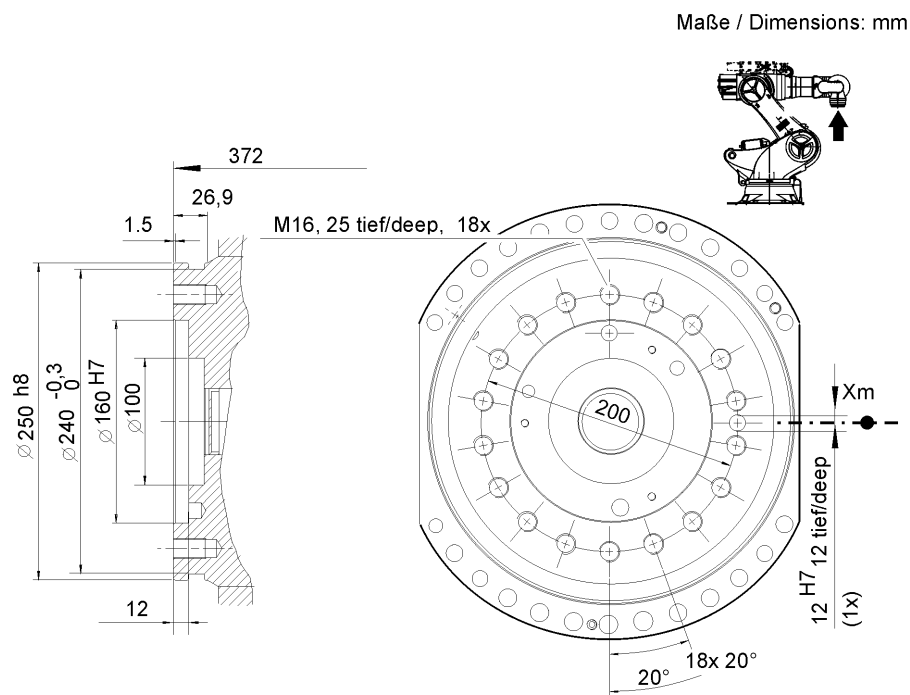
The mass inertia must be verified using KUKA.Load. It is imperative for the load data to be entered in the robot controller!

### Mounting flange

Mounting flange	similar to DIN/ISO 9409-1-A200*
Screw grade	10.9
Screw size	M16
Grip length	1.5 x nominal diameter
Depth of engagement	min. 24 mm, max. 25 mm
Locating element	12 <sup>H7</sup>

\*The inner locating diameter is  $\varnothing 160$  <sup>H7</sup>. This deviates from the standard.

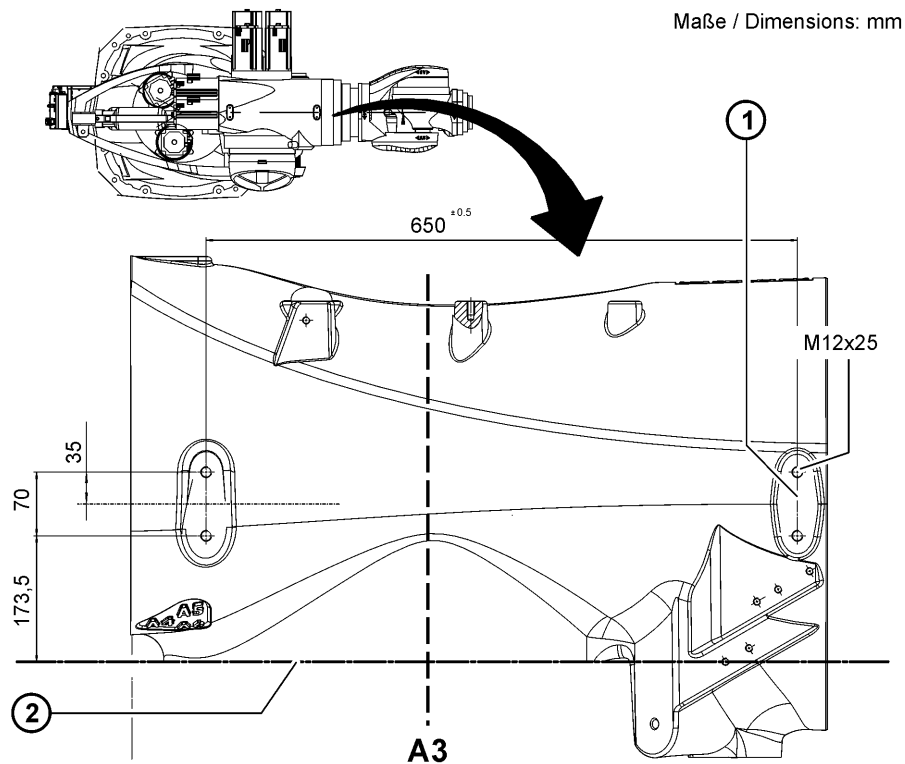
The mounting flange is depicted (>>> "Mounting flange" Page 22) with axes 4 and 6 in the zero position. The symbol  $X_m$  indicates the position of the locating element (bushing) in the zero position.



**Fig. 4-5: Mounting flange**

### Supplementary load

The robot can carry supplementary loads on the arm. When mounting the supplementary loads, be careful to observe the maximum permissible total load. If an energy supply system A3 - A6 is used, the maximum supplementary load is reduced by the mass of the energy supply system. The dimensions and positions of the installation options can be seen in the diagram (>>> Fig. 4-6 ). All other threads and holes on the robot are not suitable for attaching additional loads.



**Fig. 4-6: Supplementary load on arm**

- 1 Mounting surface on arm
- 2 Interference contour, axis 3

#### 4.5 Payloads, KR 1000 L950 titan PA

##### Payloads

Robot	KR 1000 L950 titan PA
In-line wrist	IW 750
Rated payload	950 kg
Distance of the load center of gravity $L_z$	400 mm
Distance of the load center of gravity $L_{xy}$	150 mm
Permissible moment of inertia	500 kgm <sup>2</sup>
Max. total load = Payload + Supplementary load	1,000 kg
Supplementary load on arm	100 kg
Supplementary load on link arm	0 kg
Supplementary load on rotating column	0 kg
Supplementary load on base frame	0 kg

##### Load center of gravity P

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

## Payload diagram

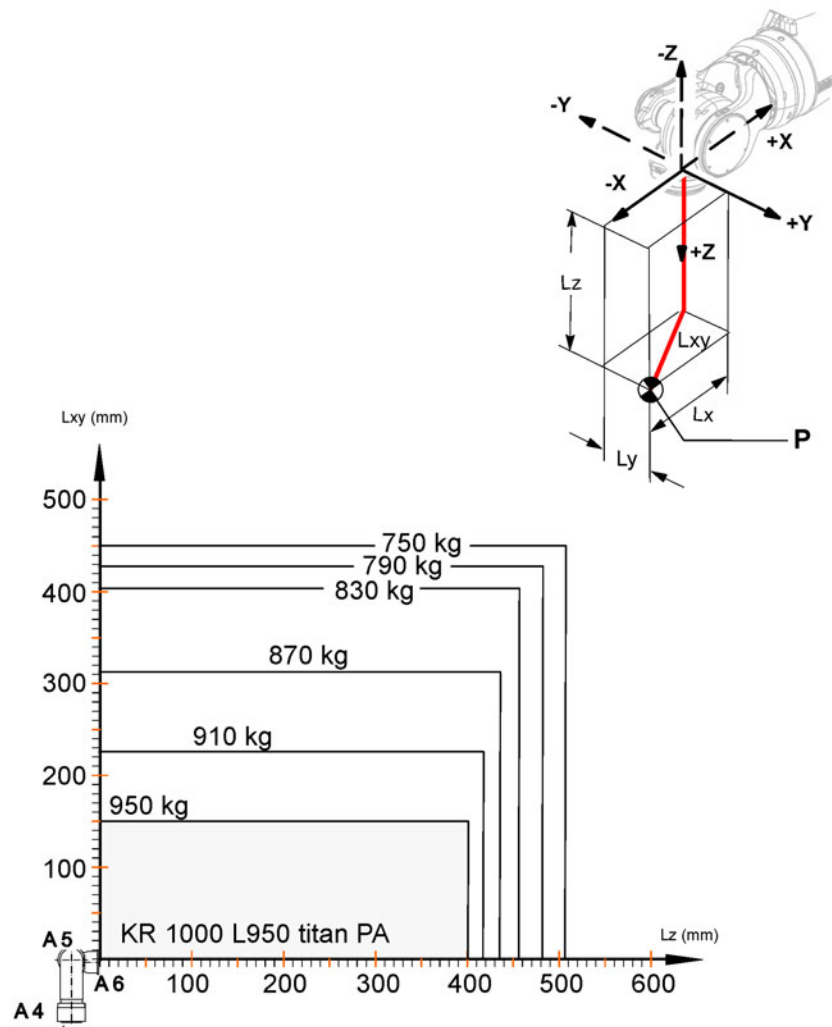


Fig. 4-7: Payload diagram for KR 1000 L950 titan PA



This loading curve corresponds to the maximum load capacity. Both values (payload and principal moment of inertia) must be checked in all cases. Exceeding this capacity will reduce the service life of the robot and overload the motors and the gears; in any such case KUKA Roboter GmbH must be consulted beforehand.

The values determined here are necessary for planning the robot application. For commissioning the robot, additional input data are required in accordance with operating and programming instructions of the KUKA System Software.

The mass inertia must be verified using KUKA.Load. It is imperative for the load data to be entered in the robot controller!

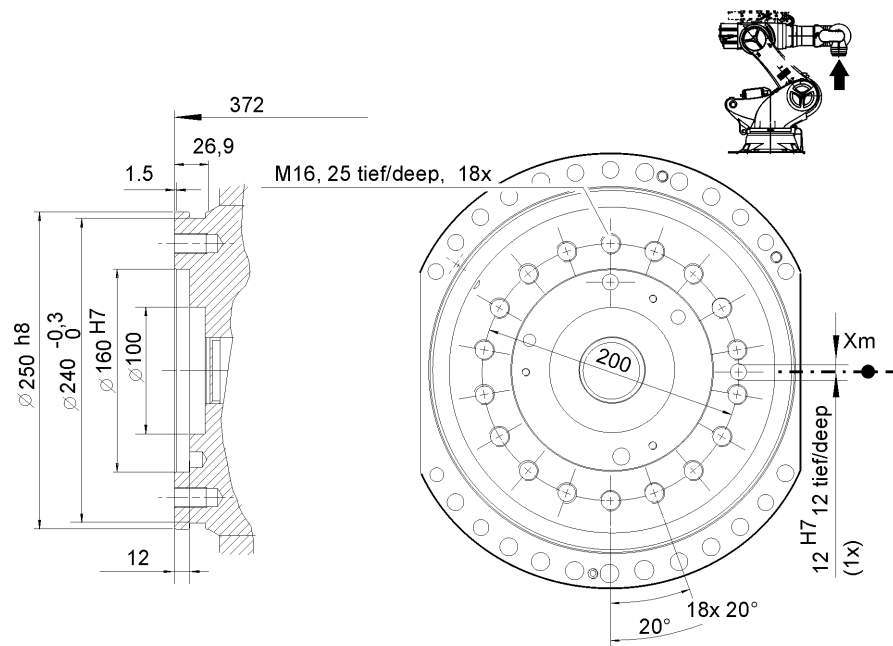
## Mounting flange

Mounting flange	similar to DIN/ISO 9409-1-A200*
Screw grade	10.9
Screw size	M16
Grip length	1.5 x nominal diameter
Depth of engagement	min. 24 mm, max. 25 mm
Locating element	12 <sup>H7</sup>

\*The inner locating diameter is  $\varnothing 160^{H7}$ . This deviates from the standard.



Maße / Dimensions: mm



## Supplementary load

Issued: 25.07.2011 Version: Spec KR 1000 titan PA V3 en

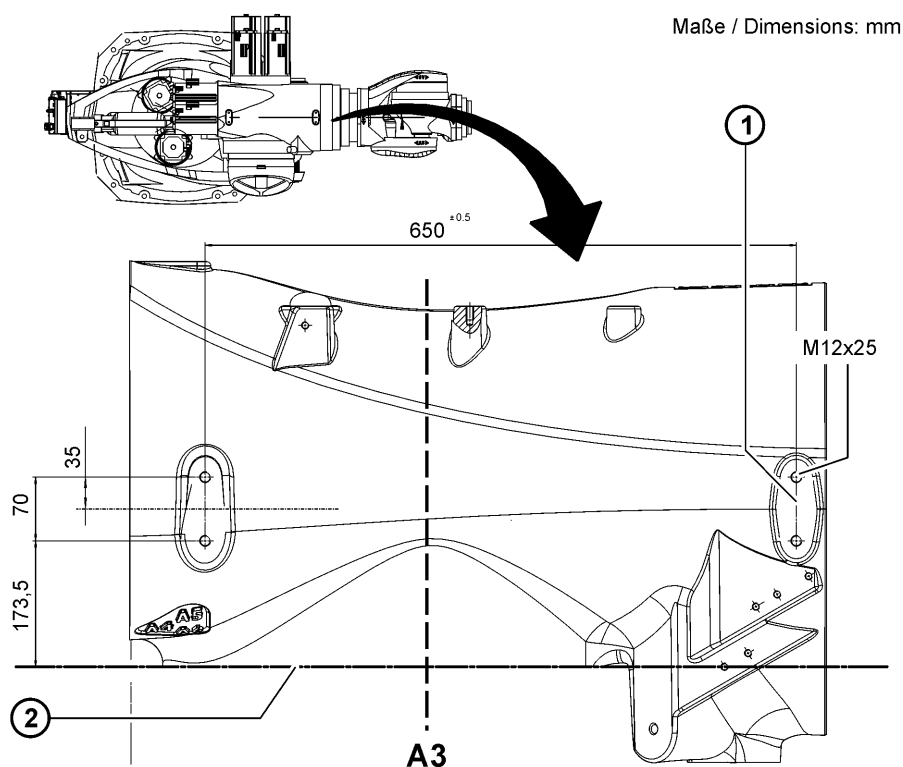


Fig. 4-9: Supplementary load on arm

- 1 Mounting surface on arm
- 2 Interference contour, axis 3

#### 4.6 Foundation data

##### Loads acting on the mounting base

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

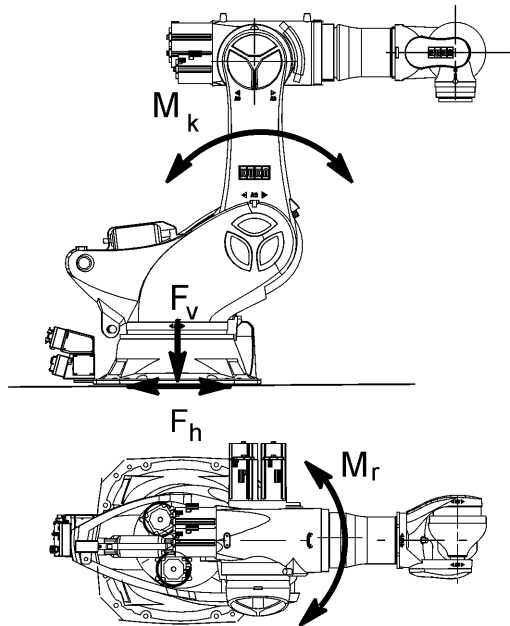


Fig. 4-10: Loads acting on the mounting base

Type of load	Force/torque/mass
$F_v$ = vertical force	$F_{vmax} = 70,000 \text{ N}$
$F_h$ = horizontal force	$F_{hmax} = 35,500 \text{ N}$
$M_k$ = tilting moment	$M_{kmax} = 133,700 \text{ Nm}$
$M_r$ = torque	$M_{rmax} = 99,700 \text{ Nm}$
Total mass for load acting on the mounting base	6,000 kg
Robot	KR 1000 1300 titan PA, 4,690 kg KR 1000 L950 titan, 4,740 kg
Total load acting on the mounting base	1,350 kg for KR 1000 1300 titan PA 1000 kg for KR 1000 L950 titan PA



The supplementary loads are not taken into consideration in the calculation of the foundation load. These supplementary loads must be taken into consideration for  $F_v$ .

#### Grade of concrete for foundations

When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. The concrete must have no cracks and fulfill the following norms for quality:

- B25 according to DIN 1045:1988
- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2001

## 4.7 Plates and labels

### Plates and labels

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

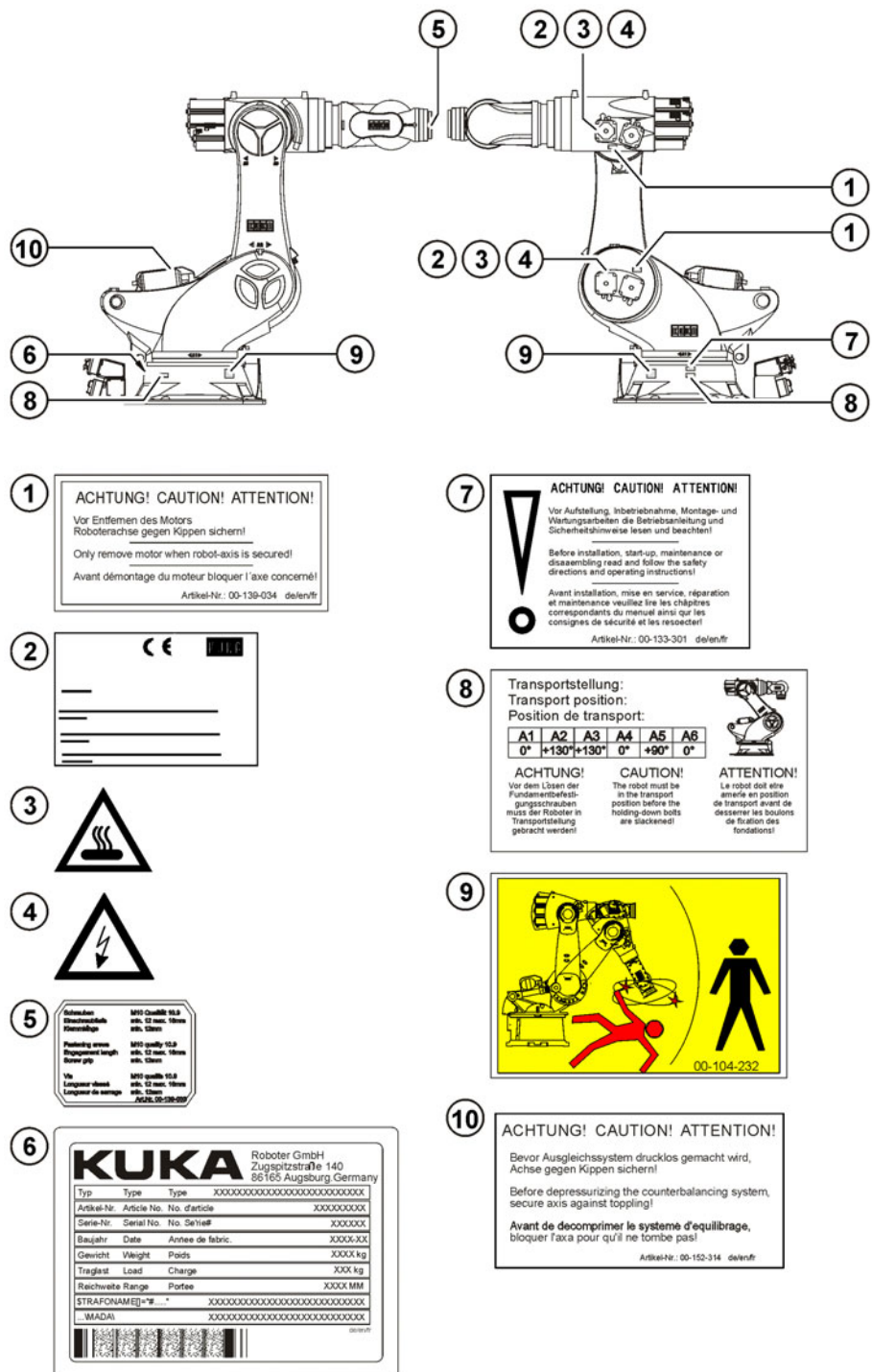


Fig. 4-11: Plates and labels

## 4.8 Stopping distances and times

### 4.8.1 General information

Information concerning the data:

- The stopping distance is the angle traveled by the robot from the moment the stop signal is triggered until the robot comes to a complete standstill.
- The stopping time is the time that elapses from the moment the stop signal is triggered until the robot comes to a complete standstill.

- The data are given for the main axes A1, A2 and A3. The main axes are the axes with the greatest deflection.
- Superposed axis motions can result in longer stopping distances.
- Stopping distances and stopping times in accordance with DIN EN ISO 10218-1, Annex B.
- Stop categories:
  - Stop category 0 » STOP 0
  - Stop category 1 » STOP 1  
according to IEC 60204-1
- The values specified for Stop 0 are guide values determined by means of tests and simulation. They are average values which conform to the requirements of DIN EN ISO 10218-1. The actual stopping distances and stopping times may differ due to internal and external influences on the braking torque. It is therefore advisable to determine the exact stopping distances and stopping times where necessary under the real conditions of the actual robot application.
- Measuring technique  
The stopping distances were measured using the robot-internal measuring technique.
- The wear on the brakes varies depending on the operating mode, robot application and the number of STOP 0 triggered. It is therefore advisable to check the stopping distance at least once a year.

#### 4.8.2 Terms used

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

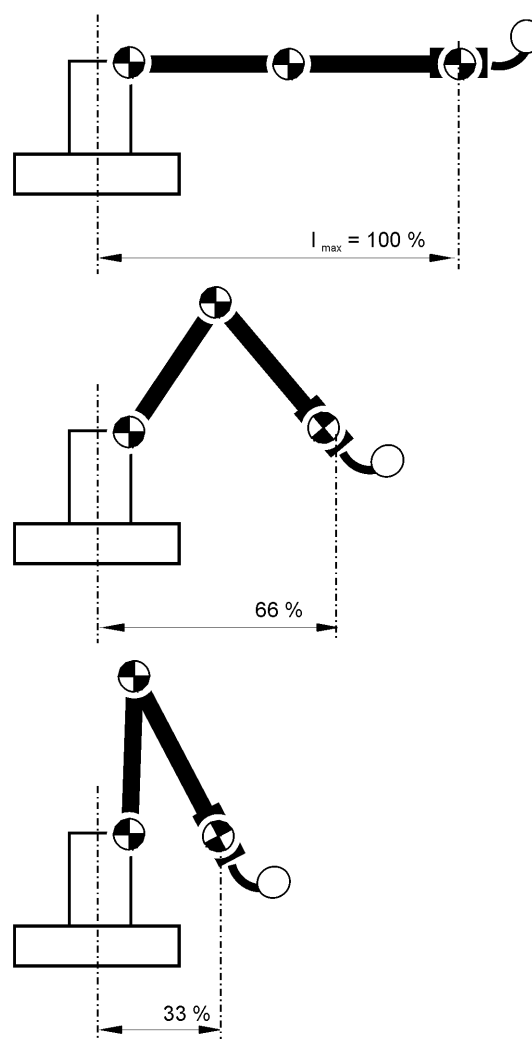


Fig. 4-12: Extension

### 4.8.3 Stopping distances and times, KR 1000 1300 titan PA

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

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

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

	Stopping distance (°)	Stopping time (s)
Axis 1	38.17	1.096
Axis 2	16.70	0.535
Axis 3	14.01	0.359

#### 4.8.3.2 Stopping distances and stopping times for STOP 1, axis 1

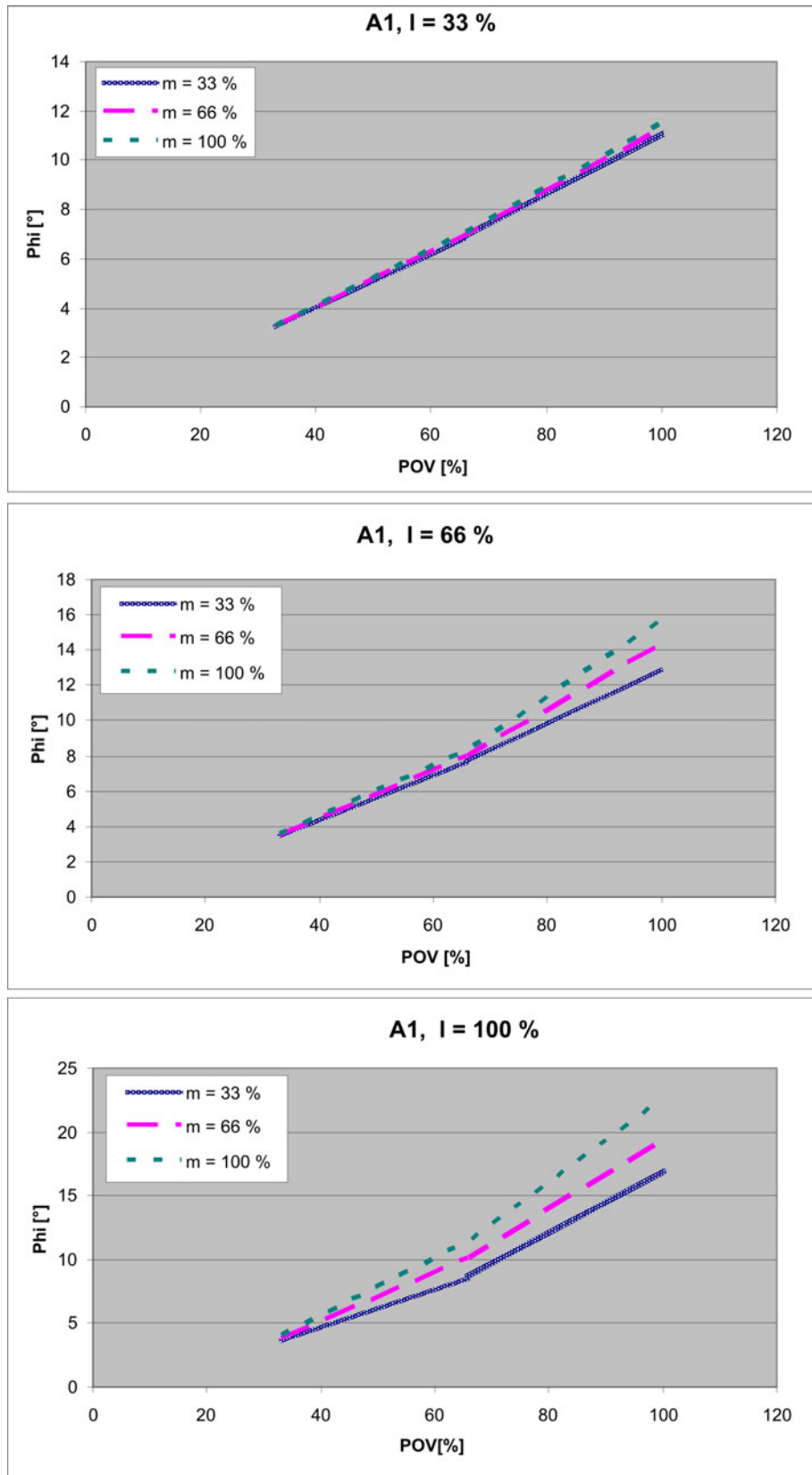


Fig. 4-13: Stopping distances for STOP 1, axis 1

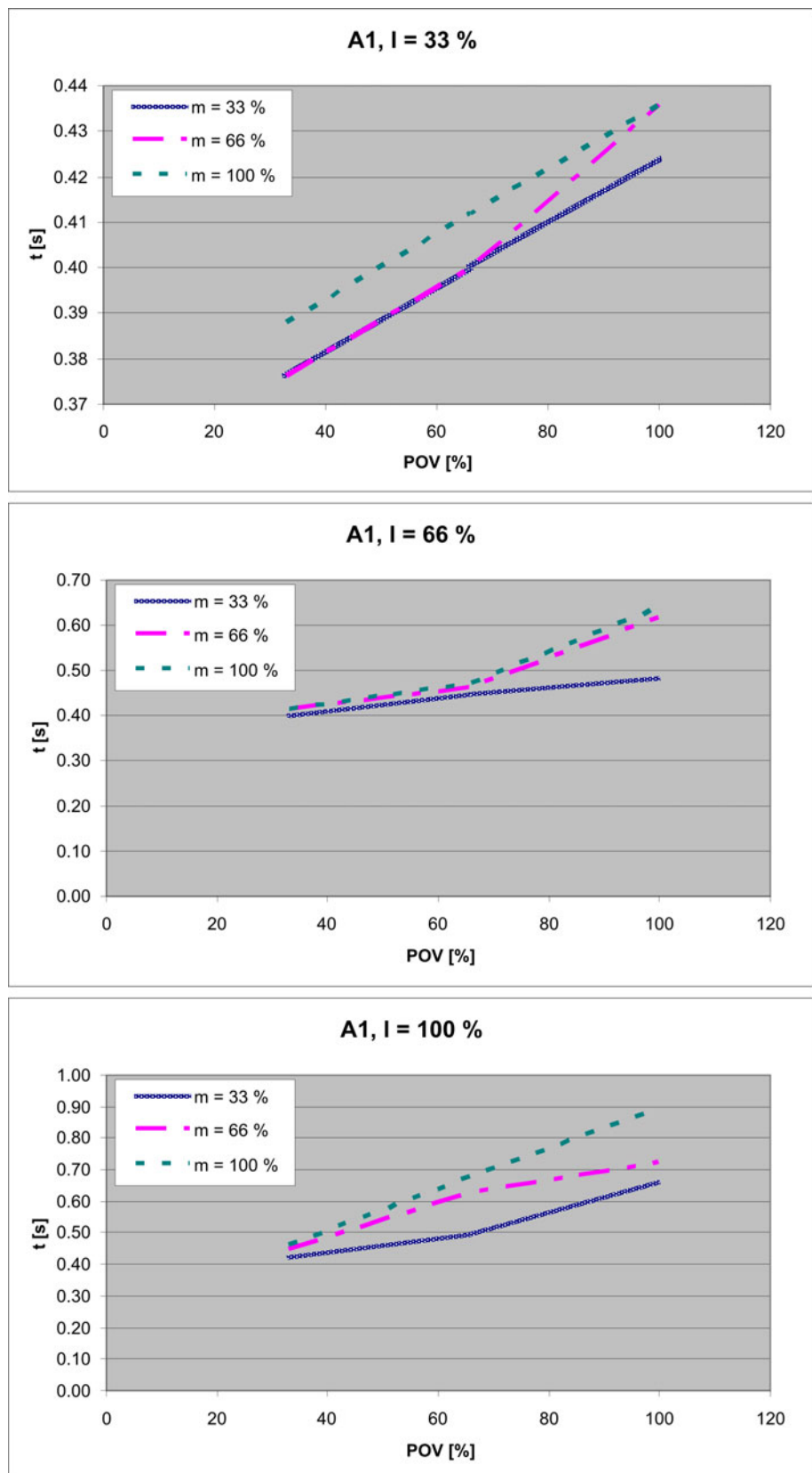


Fig. 4-14: Stopping times for STOP 1, axis 1



#### 4.8.3.3 Stopping distances and stopping times for STOP 1, axis 2

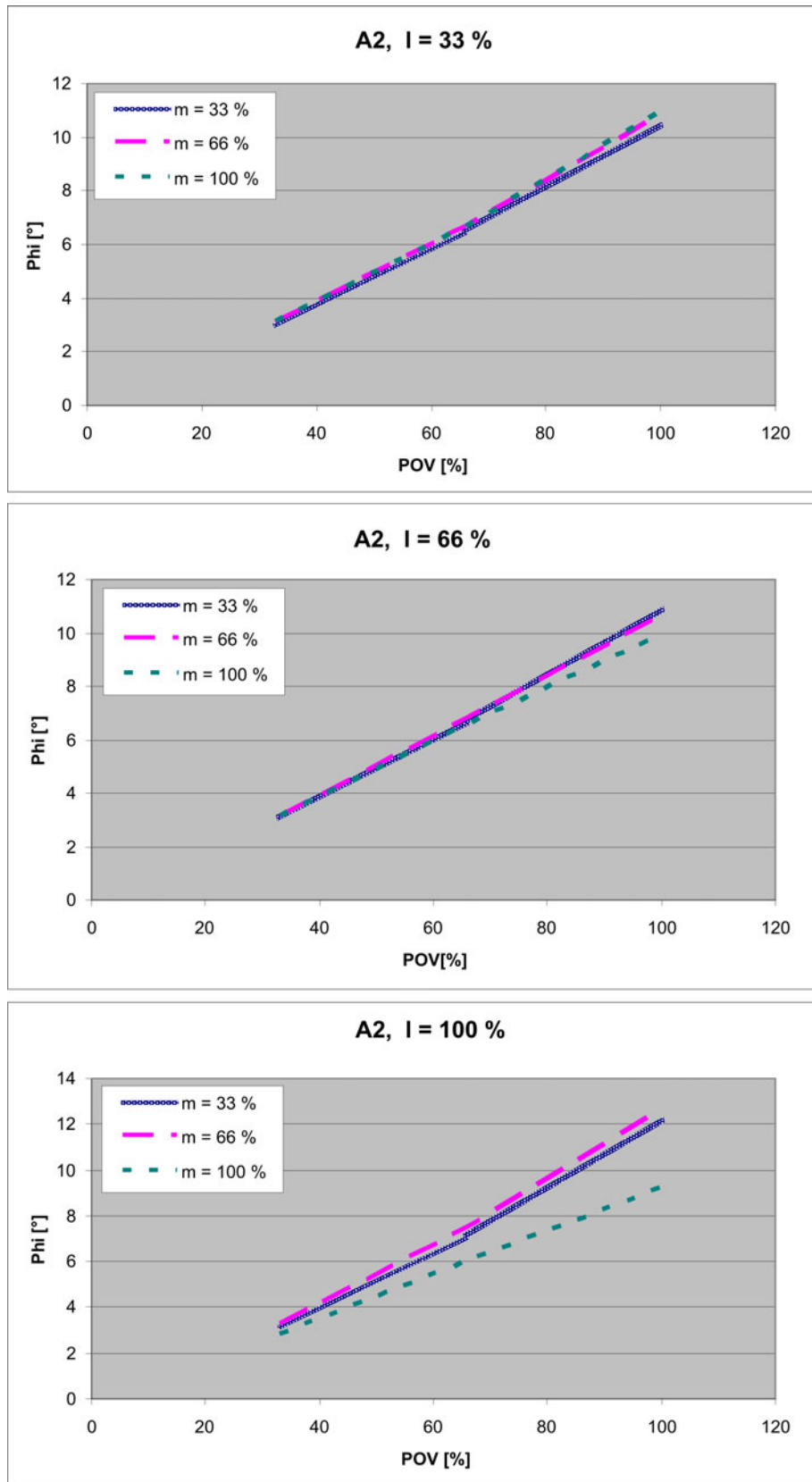


Fig. 4-15: Stopping distances for STOP 1, axis 2

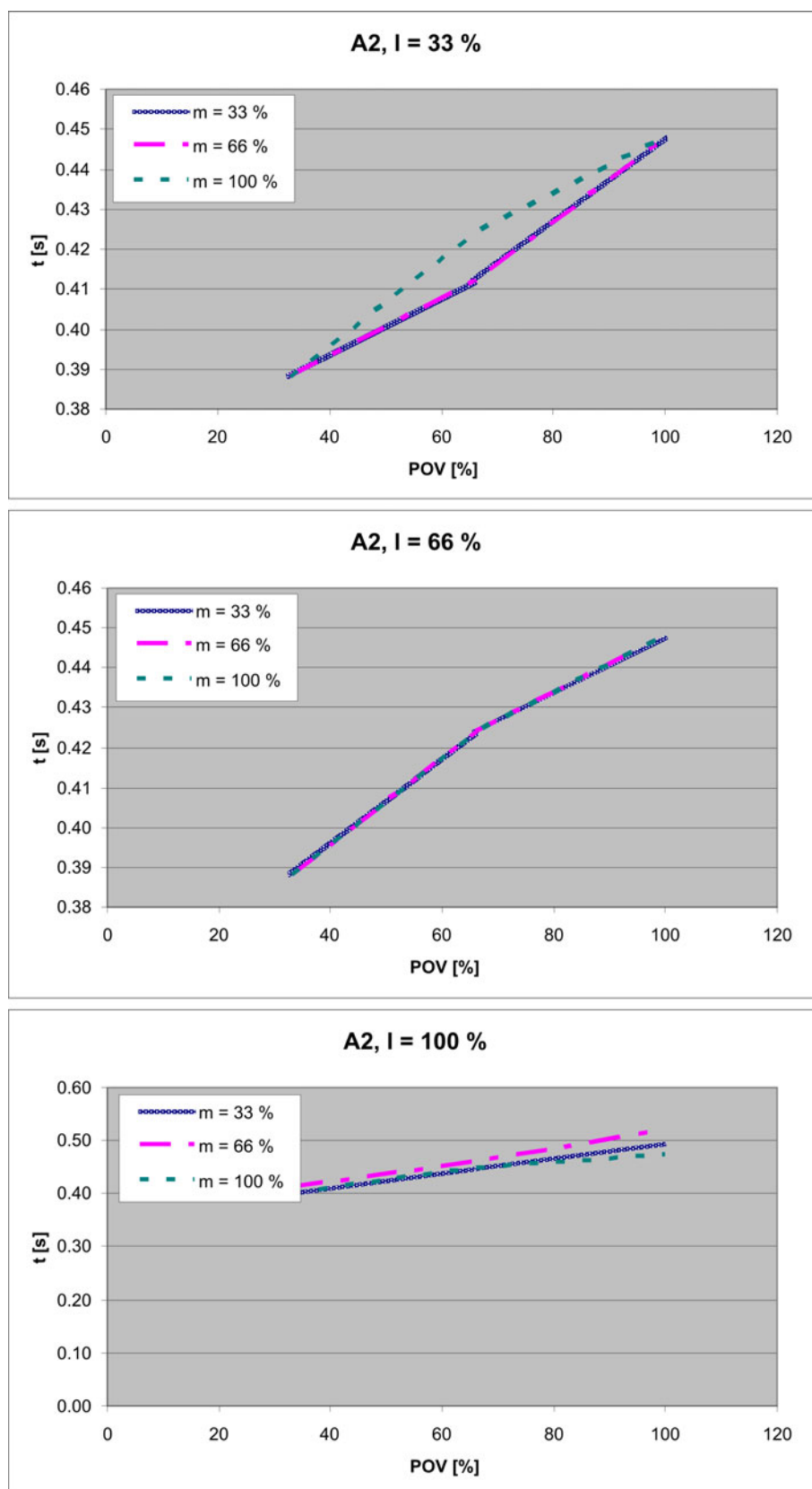


Fig. 4-16: Stopping times for STOP 1, axis 2

#### 4.8.3.4 Stopping distances and stopping times for STOP 1, axis 3

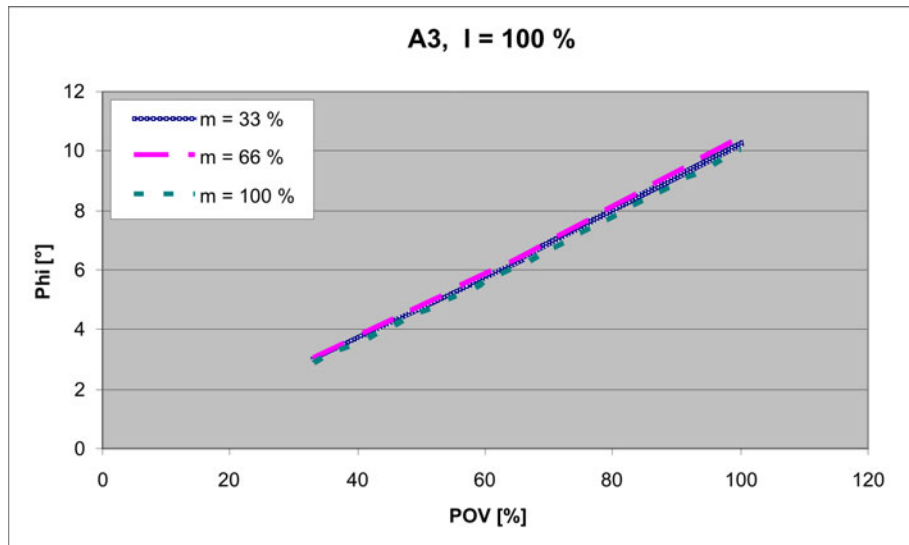


Fig. 4-17: Stopping distances for STOP 1, axis 3

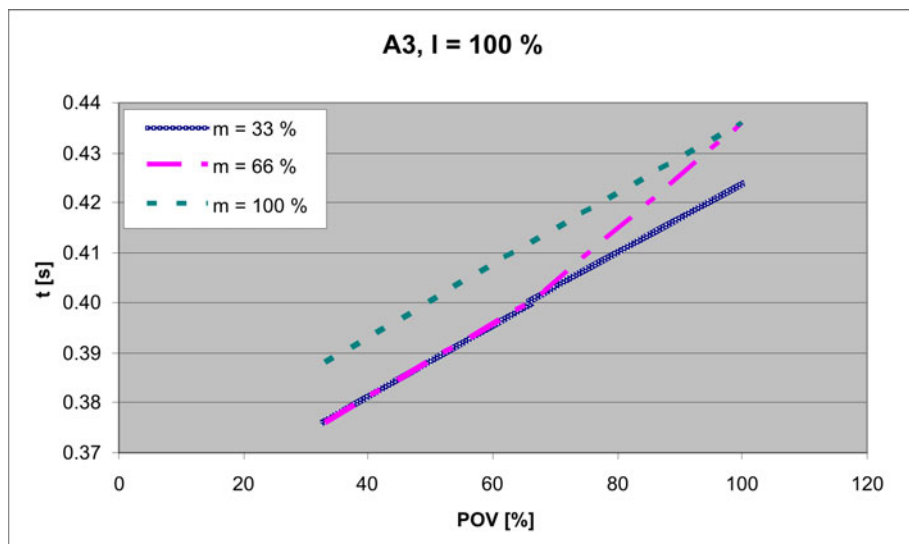


Fig. 4-18: Stopping times for STOP 1, axis 3

#### 4.8.4 Stopping distances and times, KR 1000 L950 titan PA

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

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

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

	Stopping distance (°)	Stopping time (s)
Axis 1	39.58	1.119
Axis 2	17.67	0.556
Axis 3	14.71	0.386

## 4.8.4.2 Stopping distances and stopping times for STOP 1, axis 1

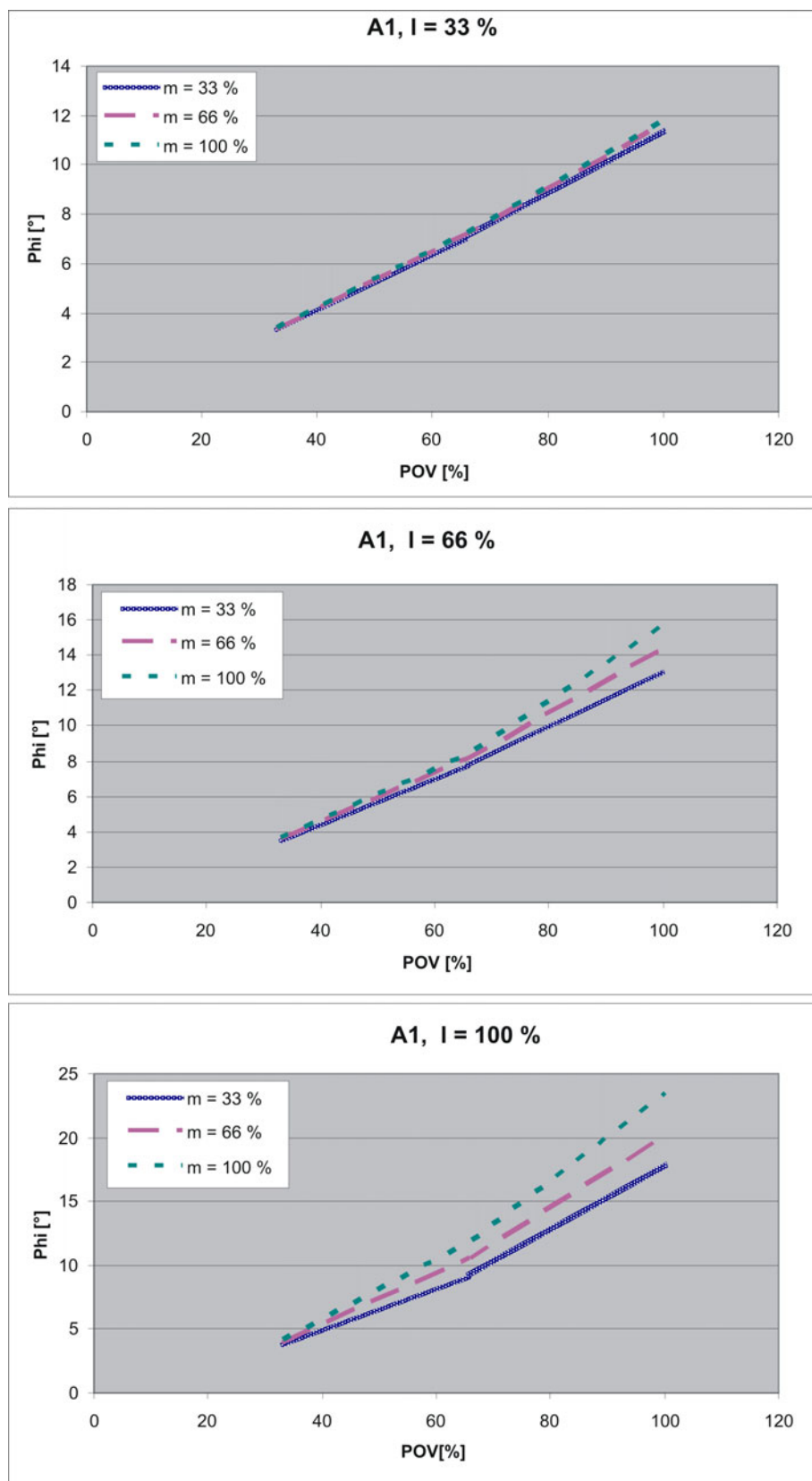


Fig. 4-19: Stopping distances for STOP 1, axis 1

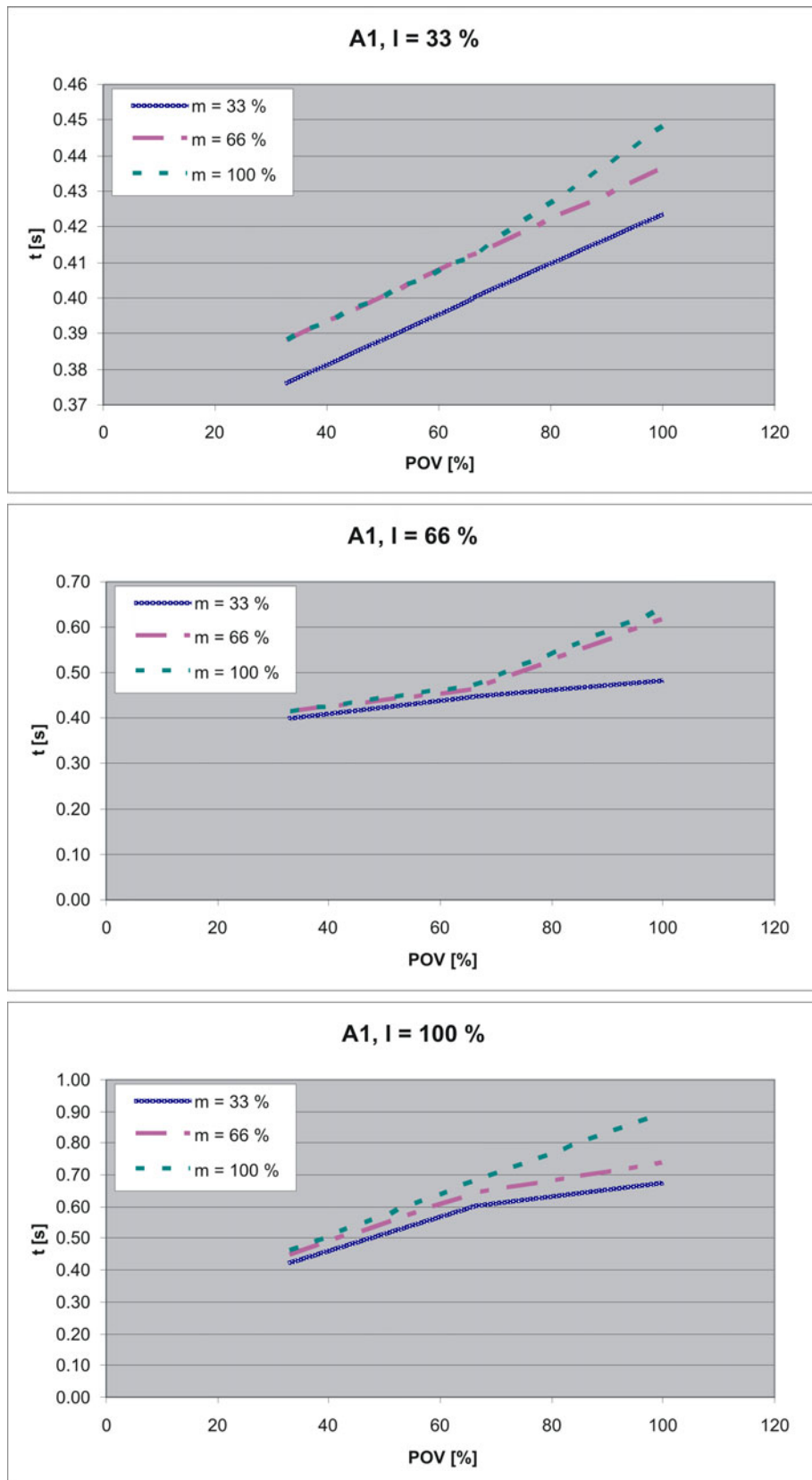


Fig. 4-20: Stopping times for STOP 1, axis 1

## 4.8.4.3 Stopping distances and stopping times for STOP 1, axis 2

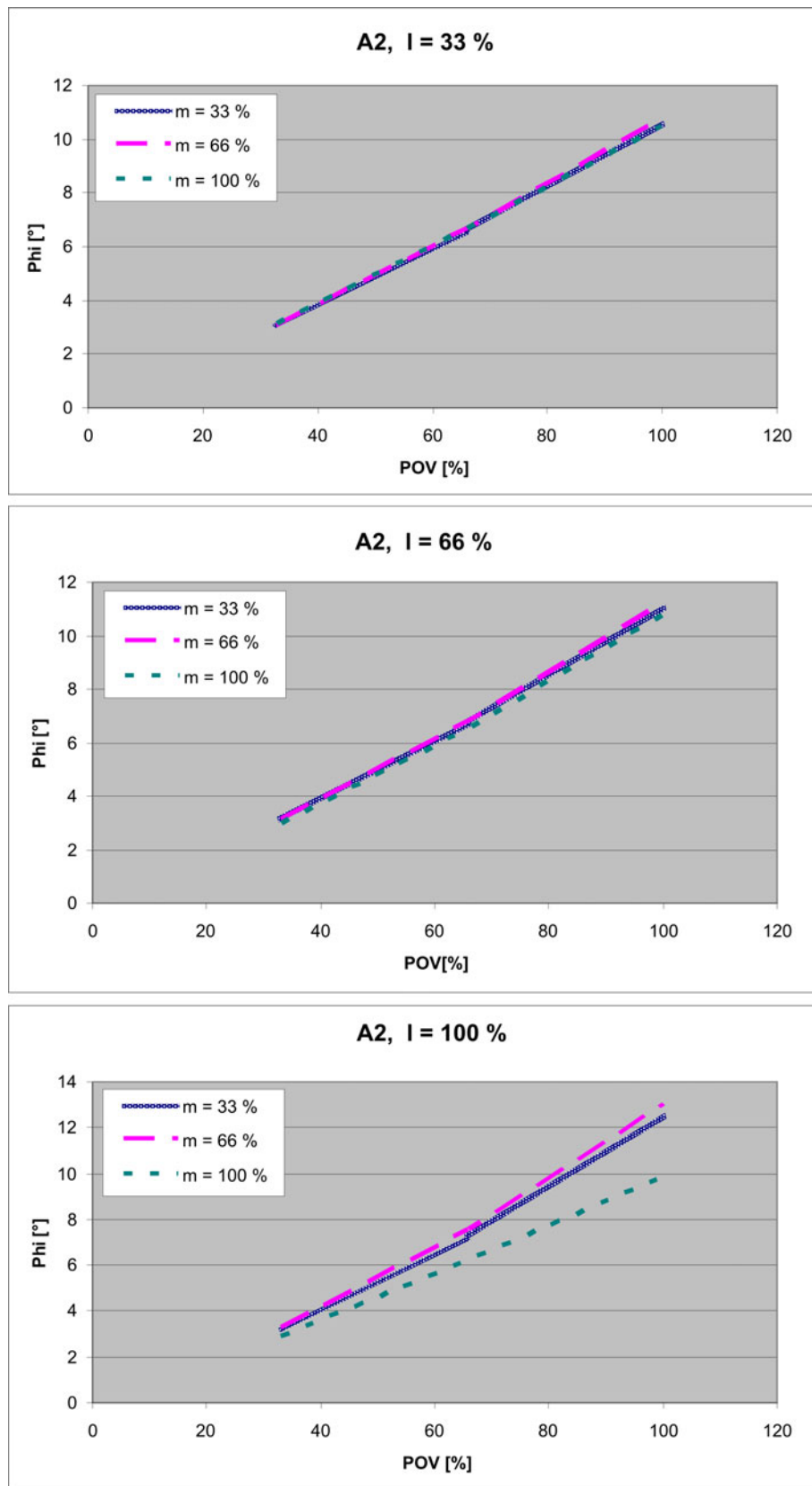


Fig. 4-21: Stopping distances for STOP 1, axis 2

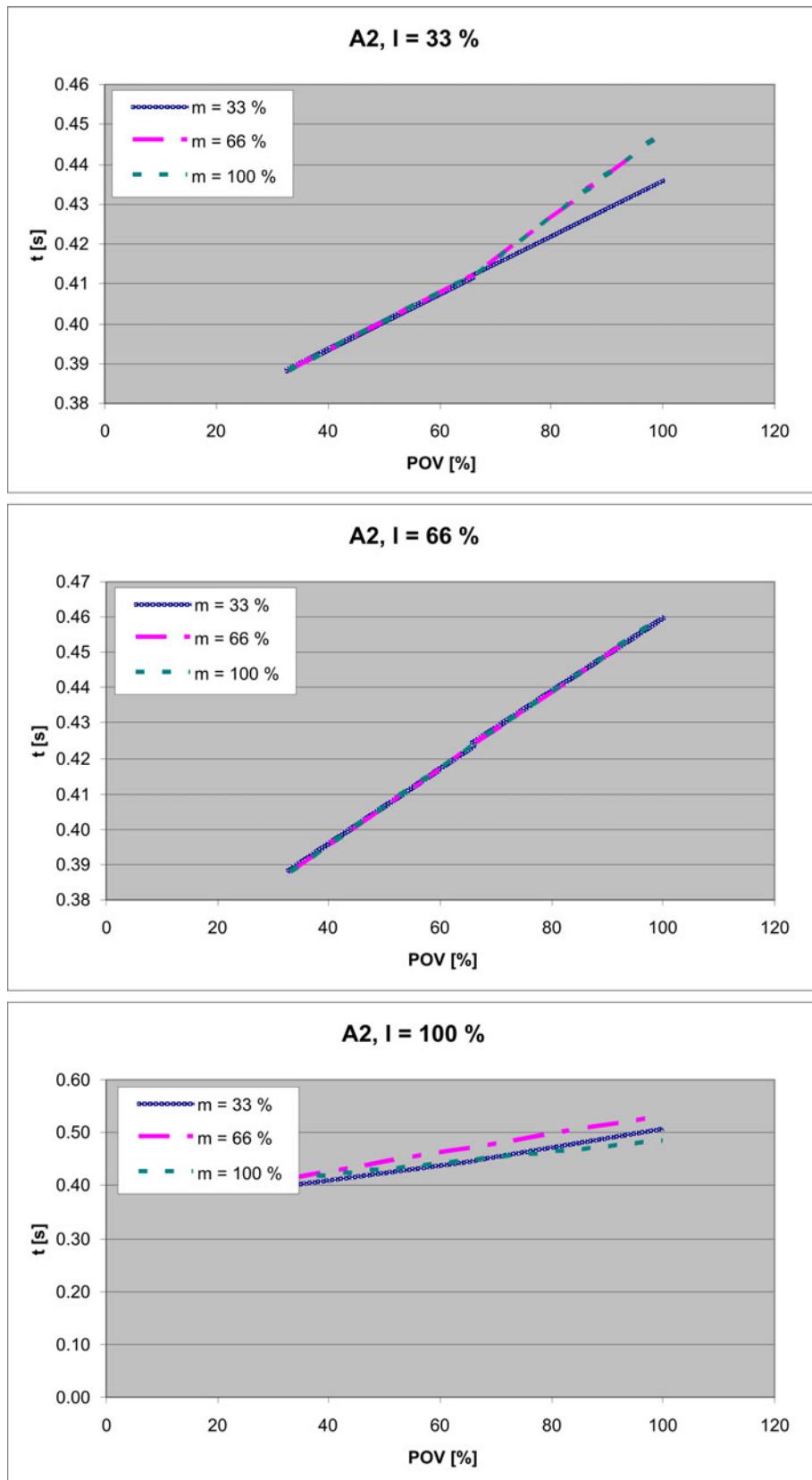


Fig. 4-22: Stopping times for STOP 1, axis 2

#### 4.8.4.4 Stopping distances and stopping times for STOP 1, axis 3

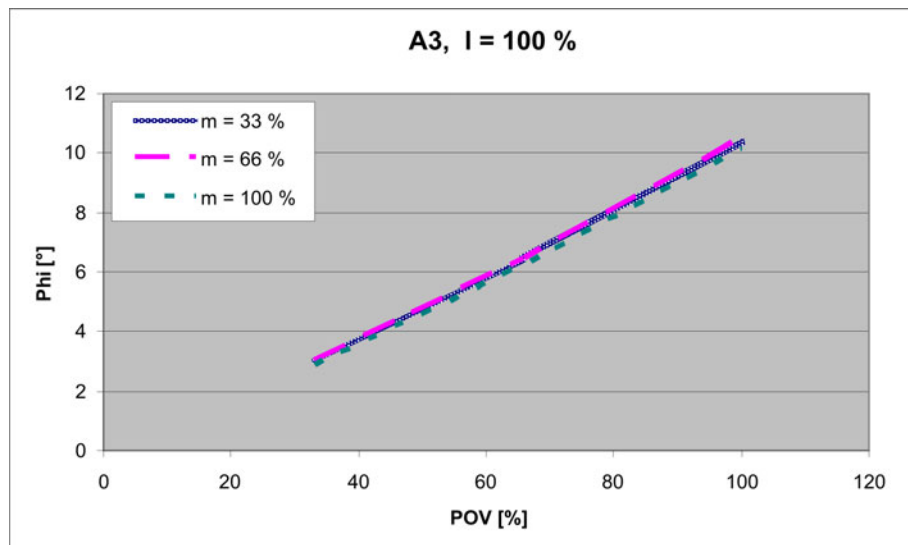


Fig. 4-23: Stopping distances for STOP 1, axis 3

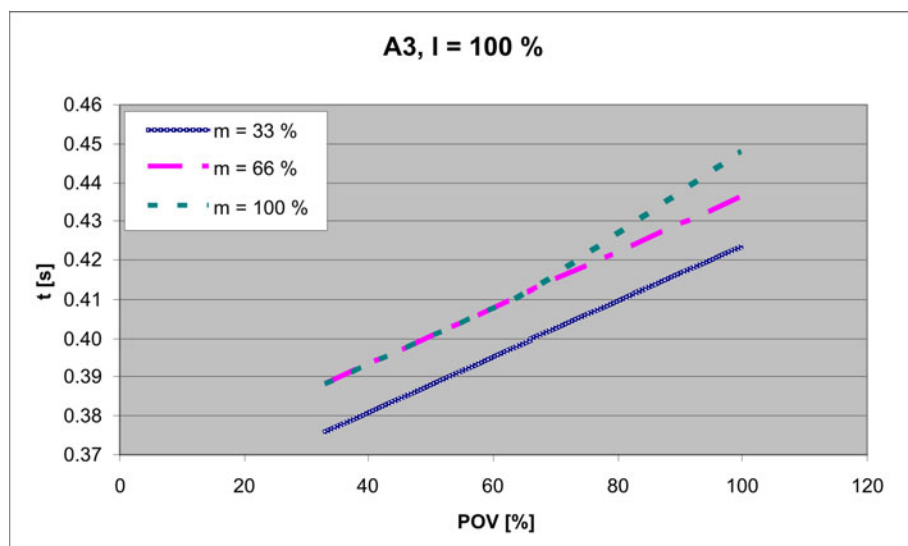


Fig. 4-24: Stopping times for STOP 1, axis 3



## 5 Safety

### 5.1 General



■ This “Safety” chapter refers to a mechanical component of an industrial robot.

■ If the mechanical component is used together with a KUKA robot controller, the “Safety” chapter of the operating instructions or assembly instructions of the robot controller must be used!

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

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

#### 5.1.1 Liability

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

Components of the industrial robot:

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

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

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

#### Safety information

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

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

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

### 5.1.2 Intended use of the industrial robot

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



Further information is contained in the “Purpose” chapter of the operating instructions or assembly instructions of the industrial robot.

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

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

#### Misuse

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

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

### 5.1.3 EC declaration of conformity and declaration of incorporation

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

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

#### Declaration of conformity

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

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

#### Declaration of incorporation

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

The declaration of incorporation declares that the start-up of the partly completed machinery remains impermissible until the partly completed machinery has been incorporated into machinery, or has been assembled with other parts

to form machinery, and this machinery complies with the terms of the EC Machinery Directive, and the EC declaration of conformity is present in accordance with Annex II A.

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

#### 5.1.4 Terms used

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


## 5.2 Personnel

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

- User
- Personnel



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

- User** The user must observe the labor laws and regulations. This includes e.g.:
- The user must comply with his monitoring obligations.
  - The user must carry out instructions at defined intervals.
- Personnel** Personnel must be instructed, before any work is commenced, in the type of work involved and what exactly it entails as well as any hazards which may exist. Instruction must be carried out regularly. Instruction is also required after particular incidents or technical modifications.
- Personnel includes:
- System integrator
  - Operators, subdivided into:
    - Start-up, maintenance and service personnel
    - Operating personnel
    - Cleaning personnel
- 

Installation, exchange, adjustment, operation, maintenance and repair must be performed only as specified in the operating or assembly instructions for the relevant component of the industrial robot and only by personnel specially trained for this purpose.
- System integrator** The industrial robot is safely integrated into a complete system by the system integrator.
- The system integrator is responsible for the following tasks:
- Installing the industrial robot
  - Connecting the industrial robot
  - Performing risk assessment
  - Implementing the required safety functions and safeguards
  - Issuing the declaration of conformity
  - Attaching the CE mark
  - Creating the operating instructions for the complete system
- Operator** The operator must meet the following preconditions:
- The operator must be trained for the work to be carried out.
  - Work on the industrial robot must only be carried out by qualified personnel. These are people who, due to their specialist training, knowledge and experience, and their familiarization with the relevant standards, are able to assess the work to be carried out and detect any potential hazards.
- Example** The tasks can be distributed as shown in the following table.

Tasks	Operator	Programmer	System integrator
Switch robot controller on/off	x	x	x
Start program	x	x	x
Select program	x	x	x
Select operating mode	x	x	x
Calibration (tool, base)		x	x
Master the manipulator		x	x

Tasks	Operator	Programmer	System integrator
Configuration		x	x
Programming		x	x
Start-up			x
Maintenance			x
Repair			x
Decommissioning			x
Transportation			x



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

### 5.3 Workspace, safety zone and danger zone

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

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

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

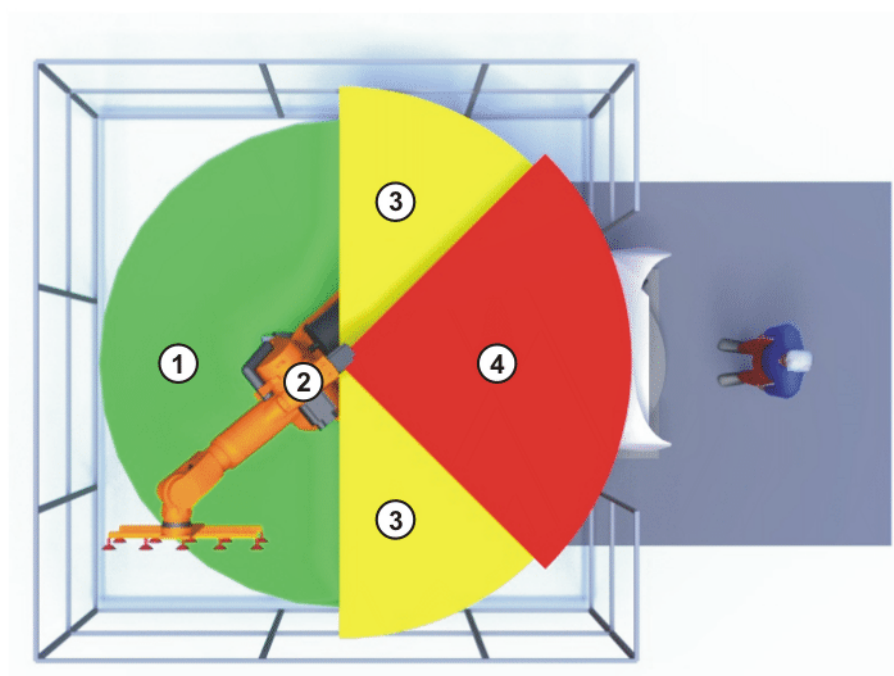


Fig. 5-1: Example of axis range A1

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

## 5.4 Overview of protective equipment

The protective equipment of the mechanical component may include:

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

Not all equipment is relevant for every mechanical component.

### 5.4.1 Mechanical end stops

The axis ranges of main axes A1 to A3 and wrist axis A5 of the manipulator are limited by means of mechanical end stops with buffers.

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

#### **NOTICE**

If the manipulator or an external axis hits an obstruction or a buffer on the mechanical end stop or axis range limitation, this can result in material damage to the industrial robot. KUKA Roboter GmbH must be consulted before the industrial robot is put back into operation. (>>> 8 "KUKA Service" Page 69)  
The affected buffer must be replaced with a new one before operation of the industrial robot is resumed. If a manipulator (or external axis) collides with a buffer at more than 250 mm/s, the manipulator (or external axis) must be exchanged or recommissioning must be carried out by KUKA Roboter GmbH.

### 5.4.2 Mechanical axis range limitation (optional)

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

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

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



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

### 5.4.3 Axis range monitoring (optional)

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



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

#### 5.4.4 Release device, KR 1000 titan product family

The release device can be used to move the manipulator manually after an accident or malfunction. The release device can be used for the drive motors of A1 and A2. It is only for use in exceptional circumstances and emergencies (e.g. for freeing people).

##### 5.4.4.1 Moving A1 with the release device

**Required parts** Required parts of the release device:

- Reversible ratchet
- 12 mm hexagon insert
- 12 mm hexagonal socket

**Procedure**

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

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

2. Unplug the motor connectors from the left-hand motor of A1.
3. Unscrew the four M12 Allen screws from the left-hand motor.
4. Lift out the left-hand motor (weight: approx. 32 kg) and set it down.
5. Unscrew the motor shaft cover of the right-hand motor.
6. Fit the ratchet with the 12 mm hexagonal socket onto the motor shaft.
7. Turn A1 using the ratchet. The axis turns in the same direction as the ratchet is turned.

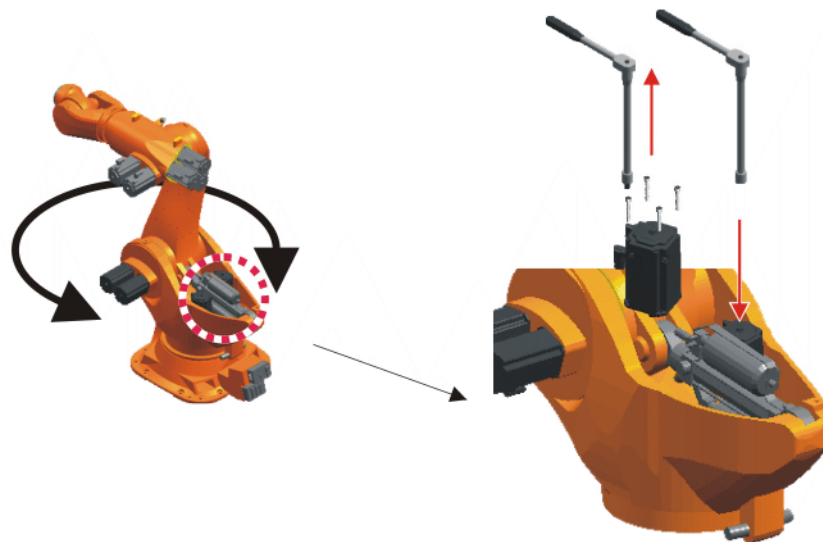


Fig. 5-2: Moving A1

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



#### 5.4.4.2 Moving A2 with the release device

##### Required parts

Required parts of the release device:

- Torque bracket
- 12 mm hexagon insert
- Drive shaft
- Reversible ratchet
- 24 mm hexagonal socket

##### Procedure

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



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

2. Unscrew the motor shaft cover from the left-hand motor of A2.
3. Insert the torque bracket on the left-hand motor.
4. Position the hexagon insert on the motor shaft of the left-hand motor and secure it with the two M6 Allen screws to prevent it from turning.
5. Unscrew the four M12 Allen screws from the right-hand motor.
6. Pull out the motor (weight: approx. 44 kg) and set it down.
7. Fit the drive shaft onto the gear input shaft of the right-hand motor.
8. Fit the ratchet with the 24 mm hexagonal socket onto the drive shaft.
9. Turn A2 using the ratchet. The axis turns in the same direction as the ratchet is turned.

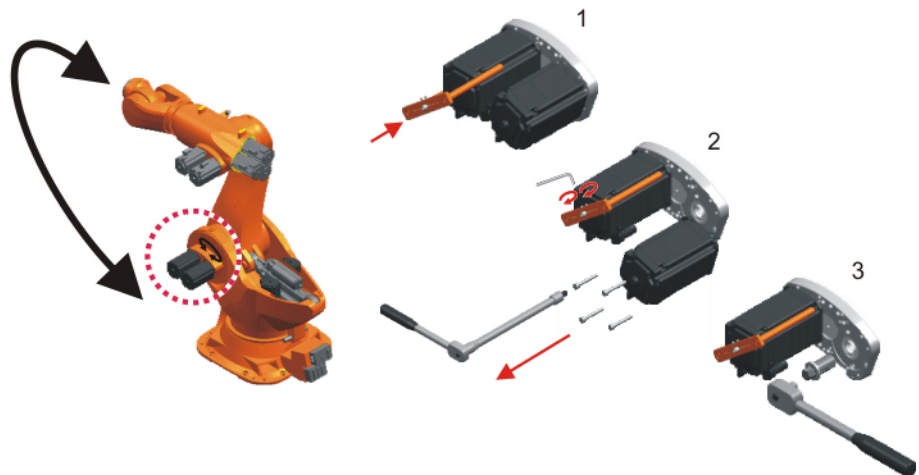


Fig. 5-3: Moving A2



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

#### 5.4.5 Labeling on the industrial robot

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

Labeling on the industrial robot consists of:



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



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

## 5.5 Safety measures

### 5.5.1 General safety measures

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

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



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



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



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

### KCP

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

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



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

<b>External keyboard, external mouse</b>	<p>An external keyboard and/or external mouse may only be used if the following conditions are met:</p> <ul style="list-style-type: none"> <li>■ Start-up or maintenance work is being carried out.</li> <li>■ The drives are switched off.</li> <li>■ There are no persons in the danger zone.</li> </ul> <p>The KCP must not be used as long as an external keyboard and/or external mouse are connected.</p> <p>The external keyboard and/or external mouse must be removed as soon as the start-up or maintenance work is completed or the KCP is connected.</p>
<b>Faults</b>	<p>The following tasks must be carried out in the case of faults in the industrial robot:</p> <ul style="list-style-type: none"> <li>■ Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.</li> <li>■ Indicate the fault by means of a label with a corresponding warning (tag-out).</li> <li>■ Keep a record of the faults.</li> <li>■ Eliminate the fault and carry out a function test.</li> </ul>
<b>Modifications</b>	<p>After modifications to the industrial robot, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.</p> <p>New or modified programs must always be tested first in Manual Reduced Velocity mode (T1).</p> <p>After modifications to the industrial robot, existing programs must always be tested first in Manual Reduced Velocity mode (T1). This applies to all components of the industrial robot and includes modifications to the software and configuration settings.</p>

### 5.5.2 Transportation

<b>Manipulator</b>	<p>The prescribed transport position of the manipulator must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the manipulator.</p>
<b>Robot controller</b>	<p>The robot controller must be transported and installed in an upright position. Avoid vibrations and impacts during transportation in order to prevent damage to the robot controller.</p> <p>Transportation must be carried out in accordance with the operating instructions or assembly instructions of the robot controller.</p>
<b>External axis (optional)</b>	<p>The prescribed transport position of the external axis (e.g. KUKA linear unit, turn-tilt table, etc.) must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the external axis.</p>

### 5.5.3 Start-up and recommissioning

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

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



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



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



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



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

#### Function test

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

It must be ensured that:

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

#### Machine data

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



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

#### 5.5.4 Manual mode

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

- Jog mode
- Teaching
- Programming
- Program verification

The following must be taken into consideration in manual mode:

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

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

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

- If it can be avoided, there must be no other persons inside the safeguarded area.  
If it is necessary for there to be several persons inside the safeguarded area, the following must be observed:
  - Each person must have an enabling device.
  - All persons must have an unimpeded view of the industrial robot.
  - Eye-contact between all persons must be possible at all times.
- The operator must be so positioned that he can see into the danger area and get out of harm's way.

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

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

### 5.5.5 Automatic mode

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

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

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

### 5.5.6 Maintenance and repair

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

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

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

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



### **WARNING**

Before work is commenced on live parts of the robot system, the main switch must be turned off and secured against being switched on again by unauthorized personnel. The incoming power cable must be deenergized. The robot controller and mains supply lead must then be checked to ensure that it is deenergized.

If the KR C4 or VKR C4 robot controller is used:

It is not sufficient, before commencing work on live parts, to execute an EMERGENCY STOP or a safety stop, or to switch off the drives, as this does not disconnect the robot system from the mains power supply in the case of the drives of the new generation. Parts remain energized. Death or severe physical injuries may result.

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

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

## **Robot controller**

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

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

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

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

## **Counterbalancing system**

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

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

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

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

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

- The manipulator assemblies supported by the counterbalancing systems must be secured.
- Work on the counterbalancing systems must only be carried out by qualified personnel.

#### **Hazardous substances**

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

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



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

#### **5.5.7 Decommissioning, storage and disposal**

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

#### **5.6 Applied norms and regulations**

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

Name	Definition	Edition
<b>EN ISO 13849-2</b>	Safety of machinery: Safety-related parts of control systems - Part 2: Validation	2008
<b>EN ISO 12100-1</b>	Safety of machinery: Basic concepts, general principles for design - Part 1: Basic terminology, methodology	2003
<b>EN ISO 12100-2</b>	Safety of machinery: Basic concepts, general principles for design - Part 2: Technical principles	2003
<b>EN ISO 10218-1</b>	Industrial robots: Safety	2008
<b>EN 614-1</b>	Safety of machinery: Ergonomic design principles - Part 1: Terms and general principles	2006
<b>EN 61000-6-2</b>	Electromagnetic compatibility (EMC): Part 6-2: Generic standards; Immunity for industrial environments	2005
<b>EN 61000-6-4</b>	Electromagnetic compatibility (EMC): Part 6-4: Generic standards; Emission standard for industrial environments	2007
<b>EN 60204-1</b>	Safety of machinery: Electrical equipment of machines - Part 1: General requirements	2006





## 6 Planning

### 6.1 Mounting base with centering

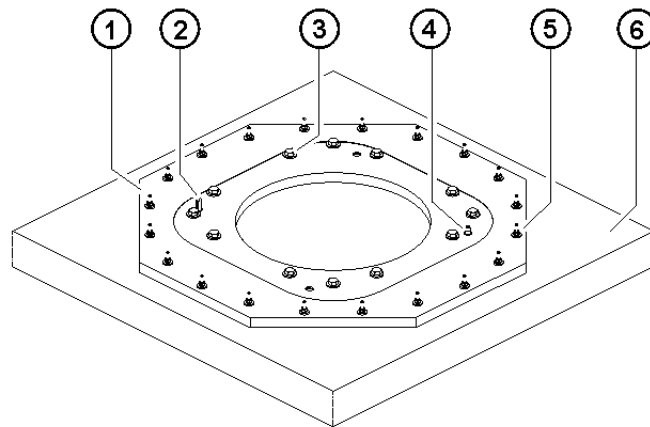
**Description** The mounting base with centering is used when the robot is fastened to the floor.

The mounting base with centering consists of:

- Bedplate
- Chemical anchors (resin-bonded anchors)
- Fasteners

This mounting variant requires a level and smooth surface on a concrete foundation with adequate load bearing capacity. The concrete foundation must be able to accommodate the forces occurring during operation. There must be no layers of insulation or screed between the bedplate and the concrete foundation.

The minimum dimensions must be observed.



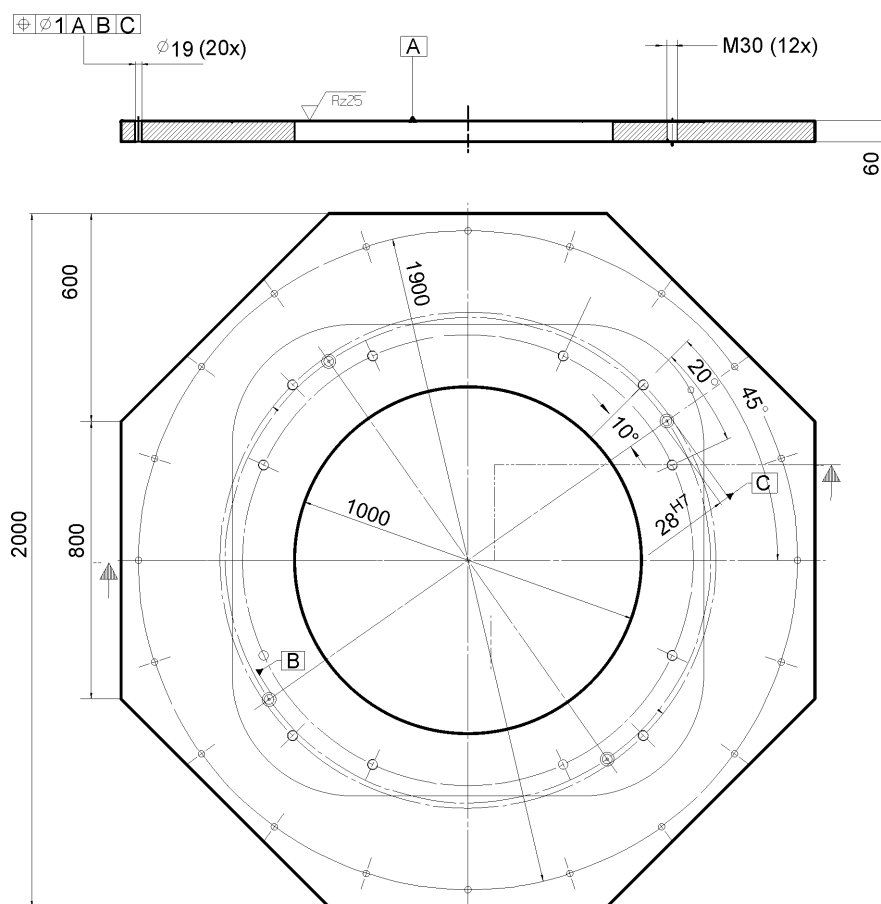
**Fig. 6-1: Fastening to mounting base**

- |                |   |
|----------------|---|
| 1 Bedplate     | 4 Pin                                   |
| 2 Sword pin    | 5 Chemical anchor (resin-bonded anchor) |
| 3 Hexagon bolt | 6 Concrete foundation                   |

**Grade of concrete for foundations** When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. The concrete must have no cracks and fulfill the following norms for quality:

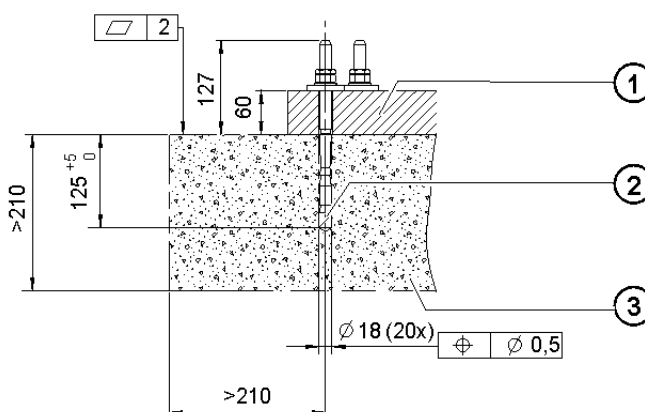
- B25 according to DIN 1045:1988
- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2001

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



**Fig. 6-2: Mounting base with centering, dimensioned drawing**

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



**Fig. 6-3: Cross-section of foundations**

- 1 Bedplate
- 2 Chemical anchor (resin-bonded anchor)
- 3 Concrete foundation

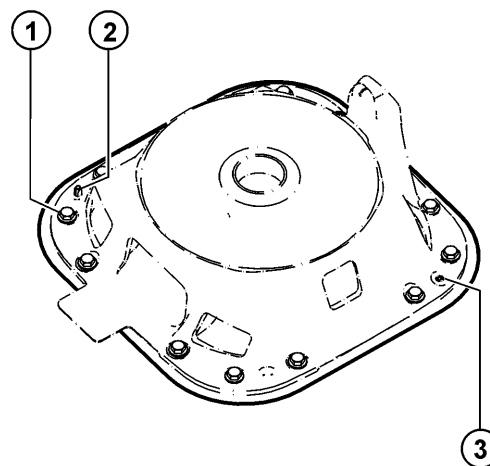
## 6.2 Machine frame mounting

### Description

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

The machine frame mounting assembly consists of:

- Pin with fasteners (>>> Fig. 6-4 )
- Sword pin with fasteners
- Hexagon bolts with conical spring washers

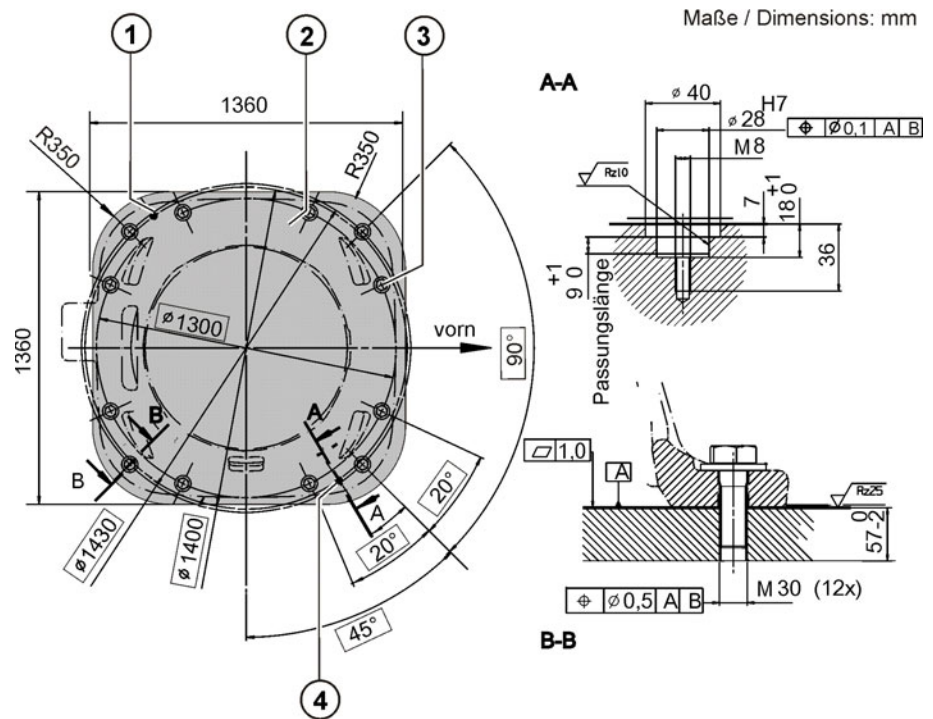


**Fig. 6-4: Machine frame mounting**

- |                      |       |
|----------------------|-------|
| 1 Hexagon bolts, 12x | 3 Pin |
| 2 Sword pin          |       |

### Dimensioned drawing

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



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

- |   |                            |   |                    |
|---|----------------------------|---|--------------------|
| 1 | Sword pin                  | 3 | Hexagon bolts, 12x |
| 2 | Mounting surface, machined | 4 | Pin                |

### 6.3 Connecting cables and interfaces

### Description

The connecting cables comprise all the cables for transferring energy and signals between the robot and the robot controller. Depending on the specification of the robot, the following connecting cables are used:

- Standard connecting cables
- Connecting cables for RoboTeam robots
- Connecting cables for SafeRobot

Depending on the specification of the robot, various connecting cables are used. Cable lengths of 7 m, 15 m, 25 m, 35 m and 50 m are available. The maximum length of the connecting cables must not exceed 50 m. Thus if the robot is operated on a linear unit which has its own energy supply chain these cables must also be taken into account.

If the length of the connecting cables is greater than 35 m, a separate ground conductor must be connected between the robot and the control cabinet. An additional ground conductor is always required to provide a low-resistance connection between the robot and the control cabinet in accordance with DIN EN 60204. The ground conductors are connected via ring cable lugs. The threaded bolt for connecting the ground conductor is located on the base frame of the robot.

Wiring diagrams, connector pin allocations and connector designations can be found in the section “Electrical installations” .

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

- The bending radius for fixed routing – 150 mm for motor cables and 60 mm for control cables – must not be exceeded.
- Protect cables against exposure to mechanical stress.
- Route the cables without mechanical stress – no tensile forces on the connectors
- Cables are only to be installed indoors.
- Observe permissible temperature range (fixed installation) of 263 K (-10 °C) to 343 K (+70 °C).
- Route the motor cables and the control cables separately in metal ducts; if necessary, additional measures must be taken to ensure electromagnetic compatibility (EMC).

#### **Interface for energy supply system**

The robot can be equipped with an energy supply system between axis 1 and axis 3 and a second energy supply system between axis 3 and axis 6. The A1 interface required for this is located on the rear, the A3 interface is located on the side of the arm and the interface for axis 6 is located on the robot tool. The interfaces are equipped with connections for cables and hoses depending on the application. Detailed information on the connector pin allocation, threaded unions, etc. is given in separate documentation.



## 7 Transportation

### 7.1 Transporting the robot

Before transporting the robot, always move the robot into its transport position (>>> Fig. 7-1 ). It must be ensured that the robot is stable while it is being transported. The robot must remain in its transport position until it has been fastened in position. Before the robot is lifted, it must be ensured that it is free from obstructions. Remove all transport safeguards, such as nails and screws, in advance. First remove any rust or glue on contact surfaces.

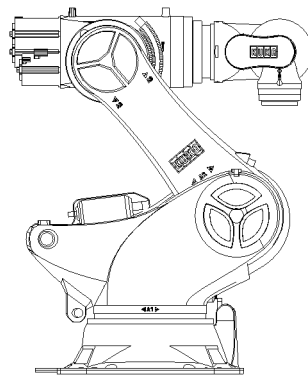
#### Transport position

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

Axis	A 1	A 2	A 3	A 4	A 5	A 6
Angle <sup>1)</sup>	0°	-130°	+130°	0°	+90°	0°
Angle <sup>2)</sup>	0°	-140°	+140°	0°	+90°	0°

<sup>1)</sup> Robot with buffer installed on axis 2

<sup>2)</sup> Robot without buffer on 2



**Fig. 7-1: Transport position**

#### Transport dimensions

The transport dimensions (>>> Fig. 7-2 ) and (>>> Fig. 7-3 ) for the robot can be noted from the following diagrams. The position of the center of gravity and the weight vary according to the specific configuration and the position of axis 2. The specified dimensions refer to the robot without equipment.

The dimensions with the index <sup>1)</sup> apply for normal transportation. The dimensions with the index <sup>2)</sup> are obtained if the buffer on the minus side of axis 2 is removed.

Maße / Dimensions: mm

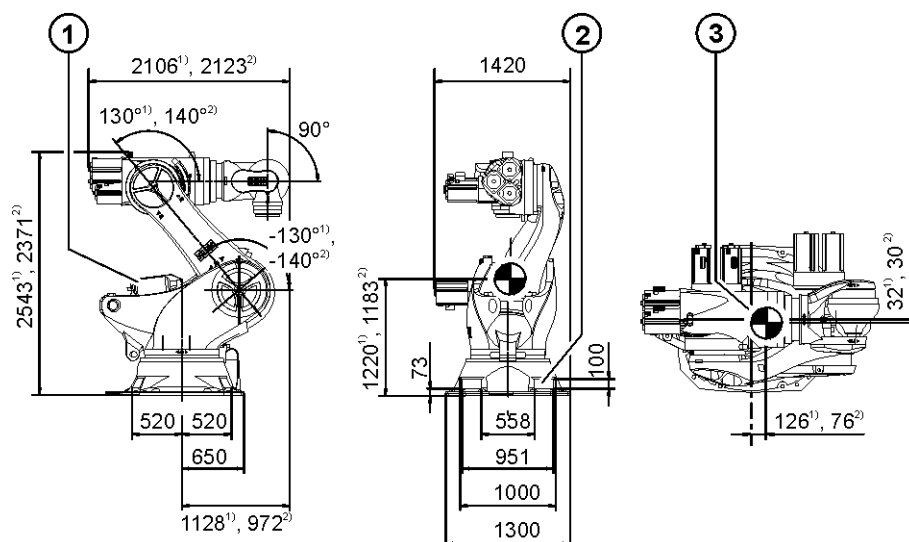


Fig. 7-2: Transport dimensions with in-line wrist IW 1000

- 1 Robot
- 2 Fork slots
- 3 Center of gravity

Maße / Dimensions: mm

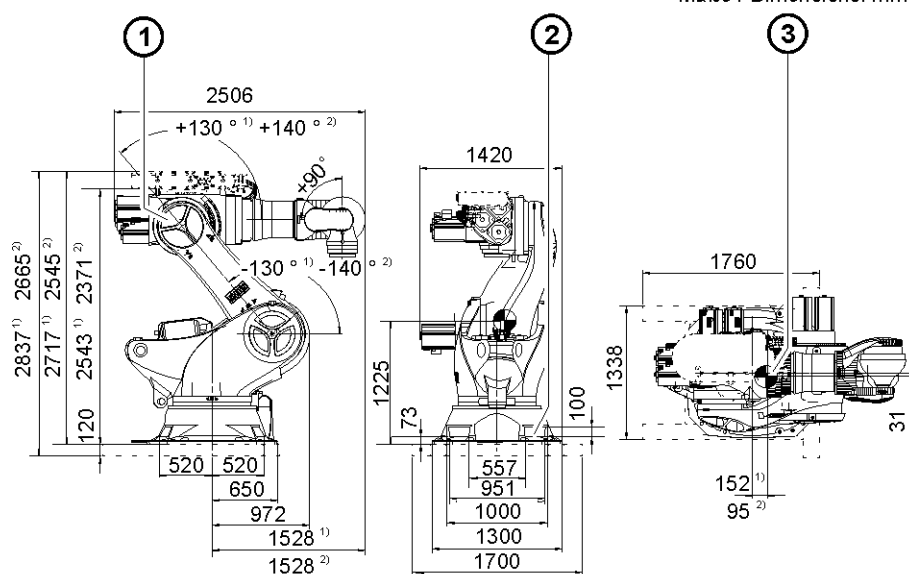


Fig. 7-3: Transport dimensions with in-line wrist IW 750

- 1 Robot
- 2 Fork slots
- 3 Center of gravity

## Transportation

The robot can be transported by fork lift truck or using lifting tackle.



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

#### Transportation by fork lift truck

For transport by fork lift truck (>>> Fig. 7-4 ), cast fork slots are provided in the base frame. The fork lift truck must have a minimum payload capacity of 6 t.

**NOTICE** Avoid excessive loading of the fork slots through undue inward or outward movement of hydraulically adjustable forks of the fork lift truck.

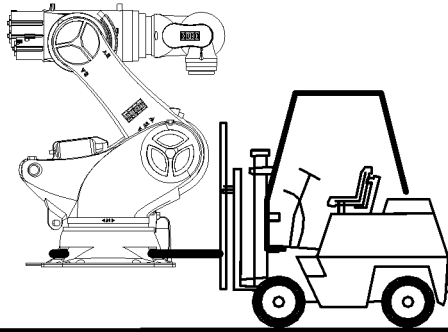


Fig. 7-4: Transport by fork lift truck

#### Transportation using lifting tackle

The robot can also be transported using lifting tackle (>>> Fig. 7-5 ) (1). The robot must be in the transport position. The lifting tackle is attached to 3 eye-bolts (2) that are permanently screwed into the rotating column (3). All ropes must be long enough and must be routed in such a way that the robot is not damaged. Installed tools and pieces of equipment can cause undesirable shifts in the center of gravity.

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

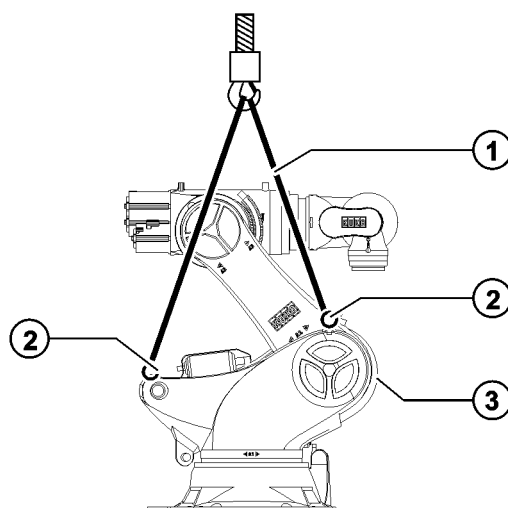


Fig. 7-5: Lifting tackle

- |                  |                   |
|------------------|-------------------|
| 1 Lifting tackle | 3 Rotating column |
| 2 Eyebolt        |                   |

#### Transportation with transport frame

If the permitted height for transportation is exceeded in the transport position, the robot can be moved into a different position. To do this, the robot must be secured to the transport frame with all holding-down bolts. Once this has been done, axes 2 and 3 can be moved so as to reduce the overall height (>>> Fig. 7-6 ) and (>>> Fig. 7-7 ). The robot can be transported on the transport frame by crane or fork lift truck (minimum payload capacity 8,000 kg). Both robot variants, with transport frame and without equipment, have an overall weight of approx. 5,600 kg.

Before the robot can be transported on the transport frame, the robot axes must be in the following positions:

Axis	A 1	A 2	A 3	A 4	A 5	A 6
Angle	0°	-16°	+145°	0° +25°*	0° +120°*	-90°
* Angle for in-line wrist IW 750						

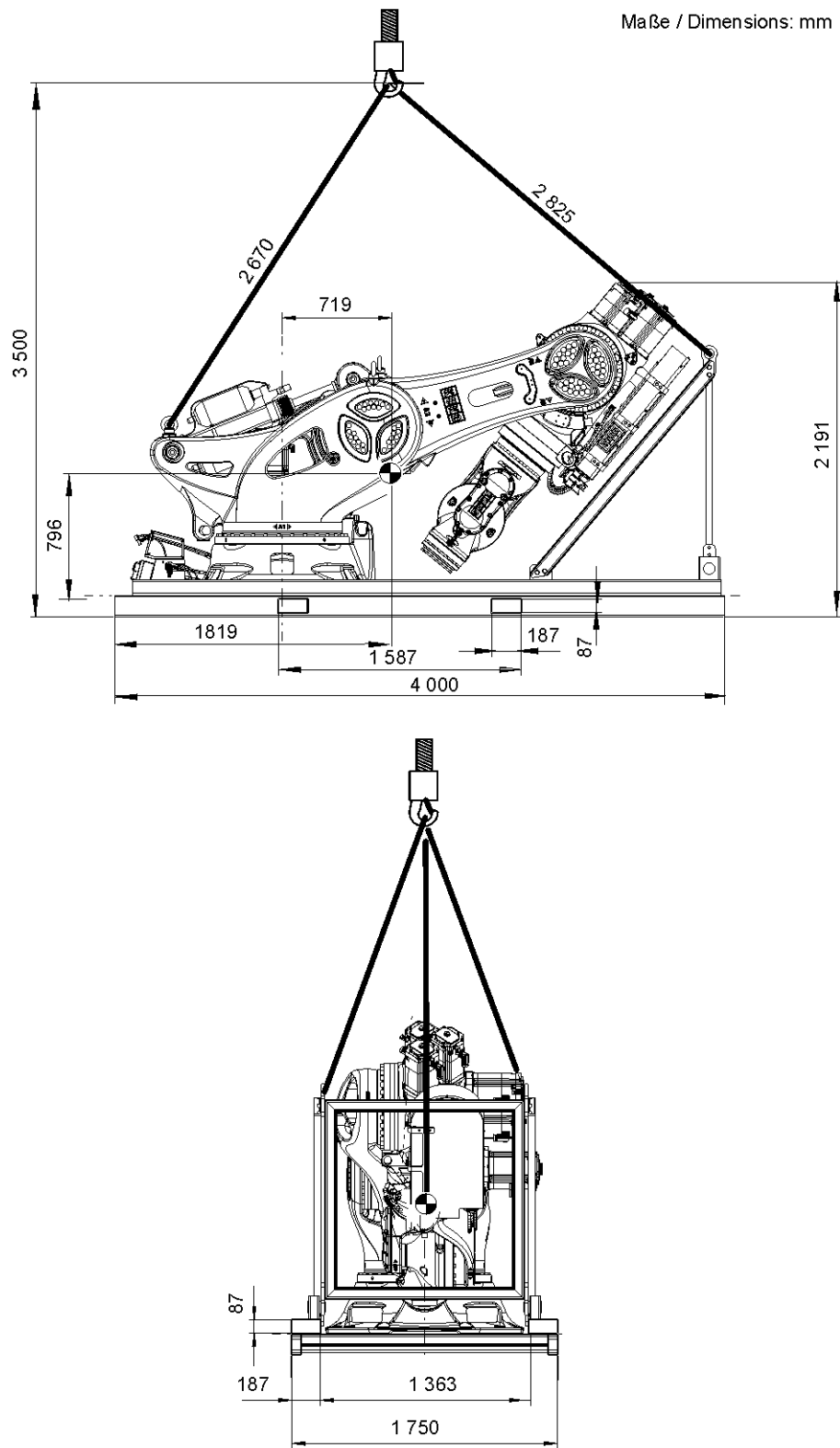


Fig. 7-6: Transport frame for in-line wrist IW 1000

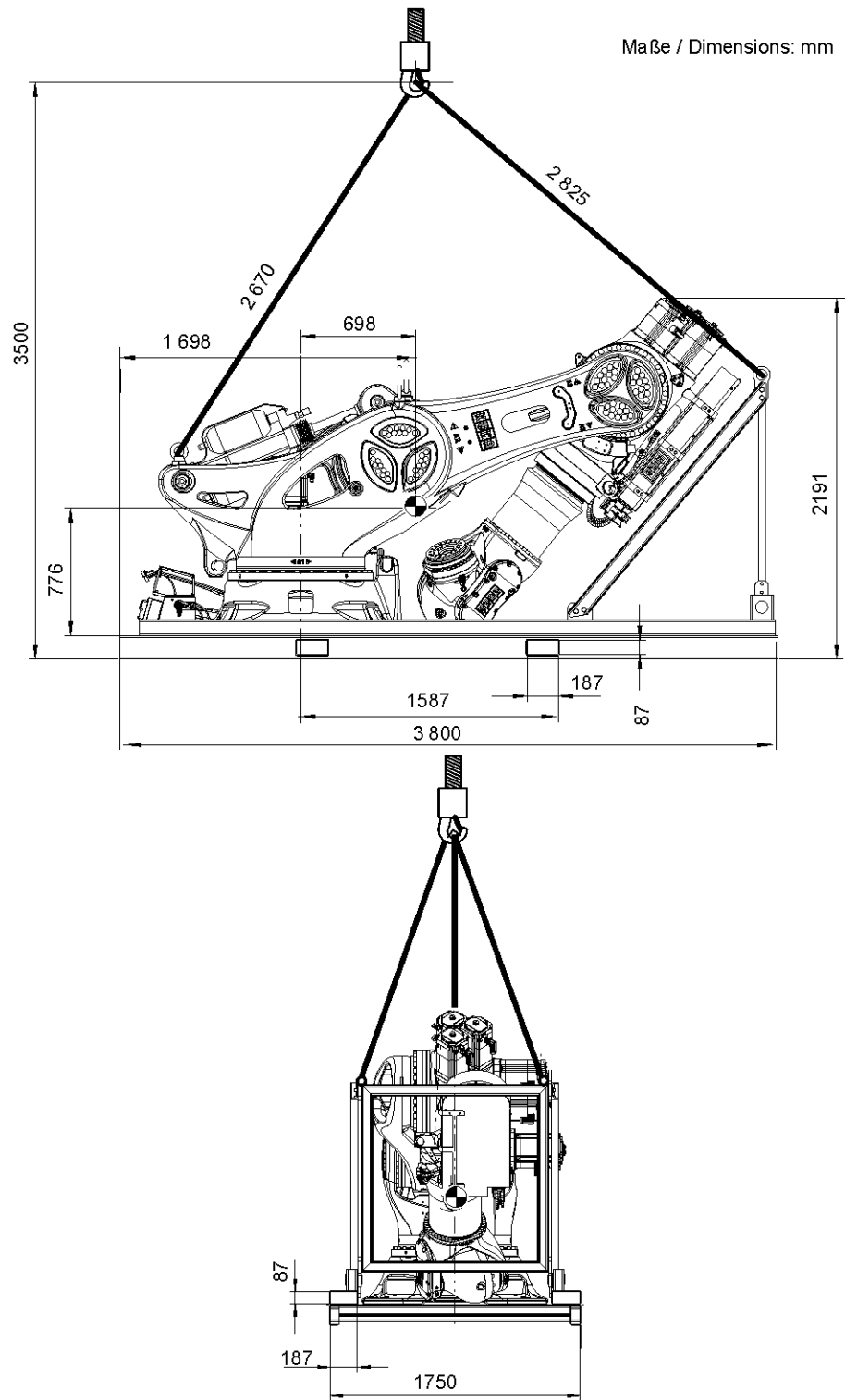


Fig. 7-7: Transport frame for in-line wrist IW 750

## 8 KUKA Service

### 8.1 Requesting support

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

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

- Model and serial number of the robot
- Model and serial number of the controller
- Model and serial number of the linear unit (if applicable)
- Version of the KUKA System Software
- Optional software or modifications
- Archive of the software
- Application used
- Any external axes used
- Description of the problem, duration and frequency of the fault

### 8.2 KUKA Customer Support

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

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

**Australia** Marand Precision Engineering Pty. Ltd. (Agency)  
153 Keys Road  
Moorabbin  
Victoria 31 89  
Australia  
Tel. +61 3 8552-0600  
Fax +61 3 8552-0605  
robotics@marand.com.au

**Belgium** KUKA Automatisering + Robots N.V.  
Centrum Zuid 1031  
3530 Houthalen  
Belgium  
Tel. +32 11 516160  
Fax +32 11 526794  
info@kuka.be  
www.kuka.be

<b>Brazil</b>	<p>KUKA Roboter do Brasil Ltda.  Avenida Franz Liszt, 80  Parque Novo Mundo  Jd. Guançã  CEP 02151 900 São Paulo  SP Brazil  Tel. +55 11 69844900  Fax +55 11 62017883  <a href="mailto:info@kuka-roboter.com.br">info@kuka-roboter.com.br</a></p>
<b>Chile</b>	<p>Robotec S.A. (Agency)  Santiago de Chile  Chile  Tel. +56 2 331-5951  Fax +56 2 331-5952  <a href="mailto:robotec@robotec.cl">robotec@robotec.cl</a>  <a href="http://www.robotec.cl">www.robotec.cl</a></p>
<b>China</b>	<p>KUKA Automation Equipment (Shanghai) Co., Ltd.  Songjiang Industrial Zone  No. 388 Minshen Road  201612 Shanghai  China  Tel. +86 21 6787-1808  Fax +86 21 6787-1805  <a href="mailto:info@kuka-sha.com.cn">info@kuka-sha.com.cn</a>  <a href="http://www.kuka.cn">www.kuka.cn</a></p>
<b>Germany</b>	<p>KUKA Roboter GmbH  Zugspitzstr. 140  86165 Augsburg  Germany  Tel. +49 821 797-4000  Fax +49 821 797-1616  <a href="mailto:info@kuka-roboter.de">info@kuka-roboter.de</a>  <a href="http://www.kuka-roboter.de">www.kuka-roboter.de</a></p>
<b>France</b>	<p>KUKA Automatisme + Robotique SAS  Techvallée  6, Avenue du Parc  91140 Villebon S/Yvette  France  Tel. +33 1 6931660-0  Fax +33 1 6931660-1  <a href="mailto:commercial@kuka.fr">commercial@kuka.fr</a>  <a href="http://www.kuka.fr">www.kuka.fr</a></p>

<b>India</b>	KUKA Robotics, Private Limited 621 Galleria Towers DLF Phase IV 122 002 Gurgaon Haryana India Tel. +91 124 4148574 info@kuka.in www.kuka.in
<b>Italy</b>	KUKA Roboter Italia S.p.A. Via Pavia 9/a - int.6 10098 Rivoli (TO) Italy Tel. +39 011 959-5013 Fax +39 011 959-5141 kuka@kuka.it www.kuka.it
<b>Japan</b>	KUKA Robotics Japan K.K. Daiba Garden City Building 1F 2-3-5 Daiba, Minato-ku Tokyo 135-0091 Japan Tel. +81 3 6380-7311 Fax +81 3 6380-7312 info@kuka.co.jp
<b>Korea</b>	KUKA Robotics Korea Co. Ltd. RIT Center 306, Gyeonggi Technopark 1271-11 Sa 3-dong, Sangnok-gu Ansan City, Gyeonggi Do 426-901 Korea Tel. +82 31 501-1451 Fax +82 31 501-1461 info@kukakorea.com
<b>Malaysia</b>	KUKA Robot Automation Sdn Bhd South East Asia Regional Office No. 24, Jalan TPP 1/10 Taman Industri Puchong 47100 Puchong Selangor Malaysia Tel. +60 3 8061-0613 or -0614 Fax +60 3 8061-7386 info@kuka.com.my

<b>Mexico</b>	<p>KUKA de Mexico S. de R.L. de C.V.  Rio San Joaquin #339, Local 5  Colonia Pensil Sur  C.P. 11490 Mexico D.F.  Mexico  Tel. +52 55 5203-8407  Fax +52 55 5203-8148  <a href="mailto:info@kuka.com.mx">info@kuka.com.mx</a></p>
<b>Norway</b>	<p>KUKA Sveiseanlegg + Roboter  Bryggeveien 9  2821 Gjøvik  Norway  Tel. +47 61 133422  Fax +47 61 186200  <a href="mailto:geir.ulsrud@kuka.no">geir.ulsrud@kuka.no</a></p>
<b>Austria</b>	<p>KUKA Roboter Austria GmbH  Vertriebsbüro Österreich  Regensburger Strasse 9/1  4020 Linz  Austria  Tel. +43 732 784752  Fax +43 732 793880  <a href="mailto:office@kuka-roboter.at">office@kuka-roboter.at</a>  <a href="http://www.kuka-roboter.at">www.kuka-roboter.at</a></p>
<b>Poland</b>	<p>KUKA Roboter Austria GmbH  Spółka z ograniczoną odpowiedzialnością  Oddział w Polsce  Ul. Porcelanowa 10  40-246 Katowice  Poland  Tel. +48 327 30 32 13 or -14  Fax +48 327 30 32 26  <a href="mailto:ServicePL@kuka-roboter.de">ServicePL@kuka-roboter.de</a></p>
<b>Portugal</b>	<p>KUKA Sistemas de Automatización S.A.  Rua do Alto da Guerra n° 50  Armazém 04  2910 011 Setúbal  Portugal  Tel. +351 265 729780  Fax +351 265 729782  <a href="mailto:kuka@mail.telepac.pt">kuka@mail.telepac.pt</a></p>



<b>Russia</b>	OOO KUKA Robotics Rus Webnaja ul. 8A 107143 Moskau Russia Tel. +7 495 781-31-20 Fax +7 495 781-31-19 kuka-robotics.ru
<b>Sweden</b>	KUKA Svetsanläggningar + Robotar AB A. Odhners gata 15 421 30 Västra Frölunda Sweden Tel. +46 31 7266-200 Fax +46 31 7266-201 info@kuka.se
<b>Switzerland</b>	KUKA Roboter Schweiz AG Riedstr. 7 8953 Dietikon Switzerland Tel. +41 44 74490-90 Fax +41 44 74490-91 info@kuka-roboter.ch www.kuka-roboter.ch
<b>Spain</b>	KUKA Robots IBÉRICA, S.A. Pol. Industrial Torrent de la Pastera Carrer del Bages s/n 08800 Vilanova i la Geltrú (Barcelona) Spain Tel. +34 93 8142-353 Fax +34 93 8142-950 Comercial@kuka-e.com www.kuka-e.com
<b>South Africa</b>	Jendamark Automation LTD (Agency) 76a York Road North End 6000 Port Elizabeth South Africa Tel. +27 41 391 4700 Fax +27 41 373 3869 www.jendamark.co.za

<b>Taiwan</b>	<p>KUKA Robot Automation Taiwan Co., Ltd.  No. 249 Pujong Road  Jungli City, Taoyuan County 320  Taiwan, R. O. C.  Tel. +886 3 4331988  Fax +886 3 4331948  <a href="mailto:info@kuka.com.tw">info@kuka.com.tw</a>  <a href="http://www.kuka.com.tw">www.kuka.com.tw</a></p>
<b>Thailand</b>	<p>KUKA Robot Automation (M)SdnBhd  Thailand Office  c/o Maccall System Co. Ltd.  49/9-10 Soi Kingkaew 30 Kingkaew Road  Tt. Rachatheva, A. Bangpli  Samutprakarn  10540 Thailand  Tel. +66 2 7502737  Fax +66 2 6612355  <a href="mailto:atika@ji-net.com">atika@ji-net.com</a>  <a href="http://www.kuka-roboter.de">www.kuka-roboter.de</a></p>
<b>Czech Republic</b>	<p>KUKA Roboter Austria GmbH  Organisation Tschechien und Slowakei  Sezemická 2757/2  193 00 Praha  Horní Počernice  Czech Republic  Tel. +420 22 62 12 27 2  Fax +420 22 62 12 27 0  <a href="mailto:support@kuka.cz">support@kuka.cz</a></p>
<b>Hungary</b>	<p>KUKA Robotics Hungaria Kft.  Fő út 140  2335 Taksony  Hungary  Tel. +36 24 501609  Fax +36 24 477031  <a href="mailto:info@kuka-robotics.hu">info@kuka-robotics.hu</a></p>
<b>USA</b>	<p>KUKA Robotics Corp.  22500 Key Drive  Clinton Township  48036  Michigan  USA  Tel. +1 866 8735852  Fax +1 586 5692087  <a href="mailto:info@kukarobotics.com">info@kukarobotics.com</a>  <a href="http://www.kukarobotics.com">www.kukarobotics.com</a></p>

**UK**

KUKA Automation + Robotics  
Hereward Rise  
Halesowen  
B62 8AN  
UK  
Tel. +44 121 585-0800  
Fax +44 121 585-0900  
[sales@kuka.co.uk](mailto:sales@kuka.co.uk)



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