



ROBOSUIT™ INSTALLATION INSTRUCTIONS FOR THE FANUC 410iHS/HW SERIES ROBOT

If you are installing a four (4) piece Robosuit™, follow all steps. Otherwise, proceed accordingly. Position the robot arm to facilitate installation using a step ladder. Make sure you have properly identified all suit pieces before proceeding.

A. Pedestal Suit Piece

1. Open the skirt zipper.
2. Hang the skirt on the four (4) comers of the pedestal making sure the zipper is properly located over the controller door.
3. Close the zipper.

B. Upper Arm Suit Piece

1. Open all zippers.
2. Place the fourth (4th.) axis servo motor pocket over the end of the arm and push the balance of the suit piece around the joint and close the zipper.
3. Position the third (3rd) axis opening around the joint and close the zipper to keep it in place. Make sure the rubber hard stop and "dog" are outside the suit.
4. Close all zippers and snap them close.

Note: The linkage suit piece will overlap the upper arm piece at the third (3rd) and fourth (4th) axis cuffs.

C. Lower Arm Suit Piece

1. Open all zippers.
2. Place the opening inside the folds around the lower linkage and close the rear zipper.
3. Place the second (2nd) axis servo motor pocket over the motor and secure the pocket around the motor with the belt.
4. Position the third (3rd) axis opening around the joint and close the zippers to keep it in place. Make sure the rubber hard stop and "dog" are outside the suit.

D. Linkage Suit Piece

1. Open all zippers.
2. Place the third (3rd.) axis servo motor pocket over the motor and cover the lower and upper linkages. Secure the pocket around the motor with the buckle belt inside. The "dog" and hard stop must be inside the suit.
3. Align and secure the bottom of the linkage piece to the arm piece at the Velcro strips.
4. Position the upper link rod folds in front of and behind the third (3rd.) and fourth (4th.) axis joints respectively. Note: The folds should not cover the rotational joints. They should be on the connecting link rod.



5. Secure the fourth (4th) axis motor pocket with the belt inside and snap all zippers. The third (3rd.) and fourth (4th.) axis cuffs will overlap the arm suit pieces.
6. Attach the supplied pipe clamp around the cuff at the end of the arm (optional).

Slowly (25% speed) move the robot through the limit of the work envelope while checking the fit. The Robosuit has been designed and tested for unrestricted work envelope operation when properly installed.

Should you have any questions, please call ROBOWORLD.