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ABB IRB1200 Robosuit® Installation Revised March 2017

For Assistance, Please Contact our Offices at
216.798.5839 or 513.633.2585
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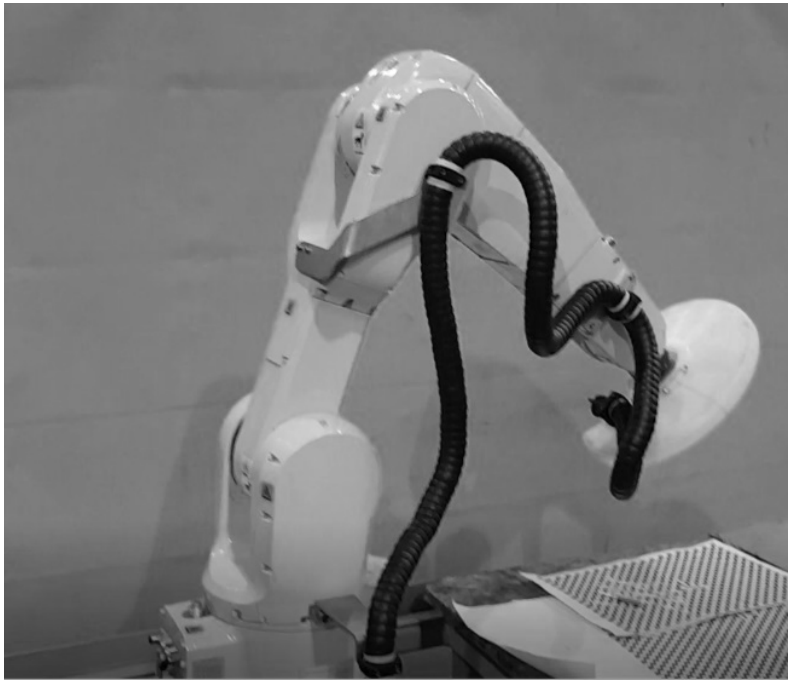


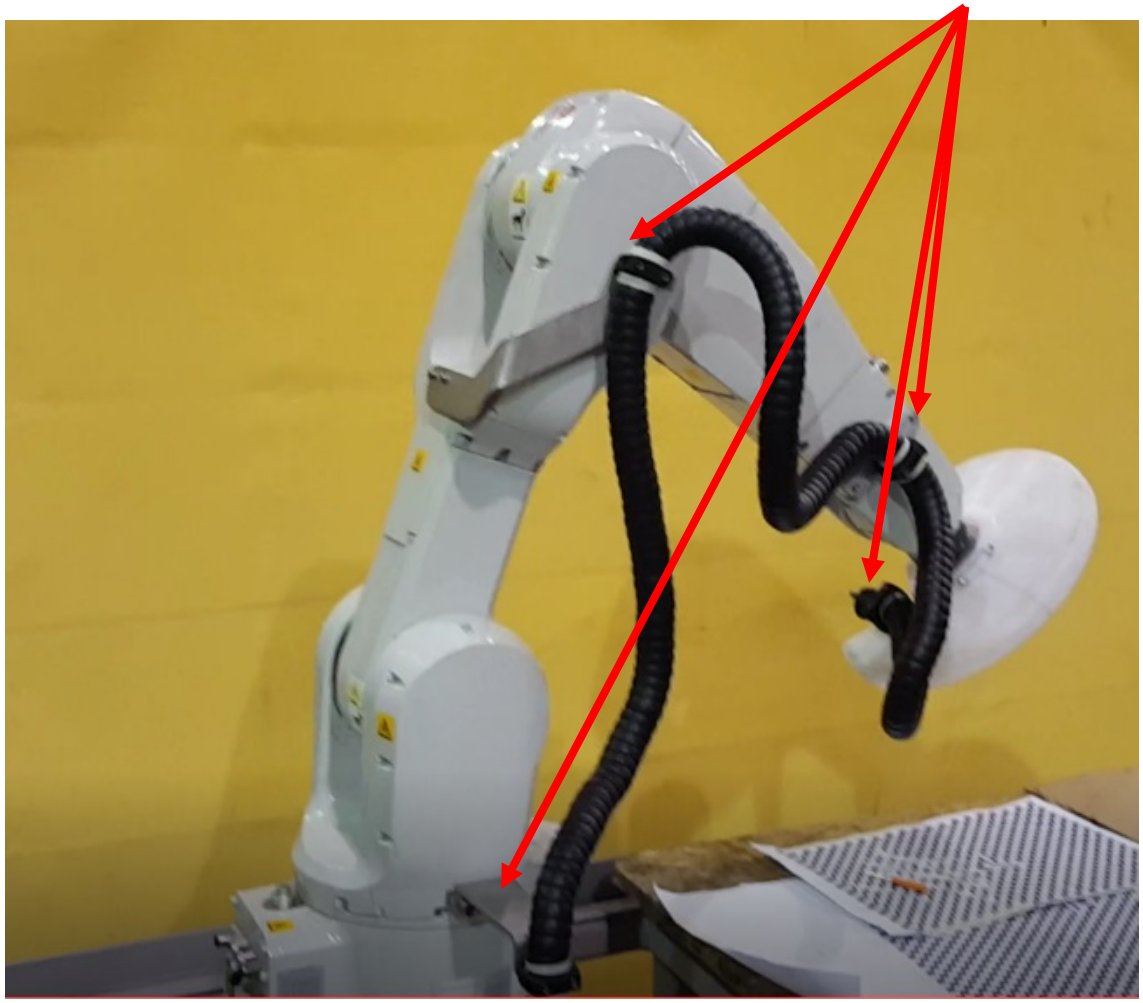
These installation instructions pertain to both floor mount, as well as inverted mount robots.

Please note, for floor mount robots, the use of adhesive Velcro at J1 may not be necessary.

Your material (and color) may be different than what is shown in this presentation.

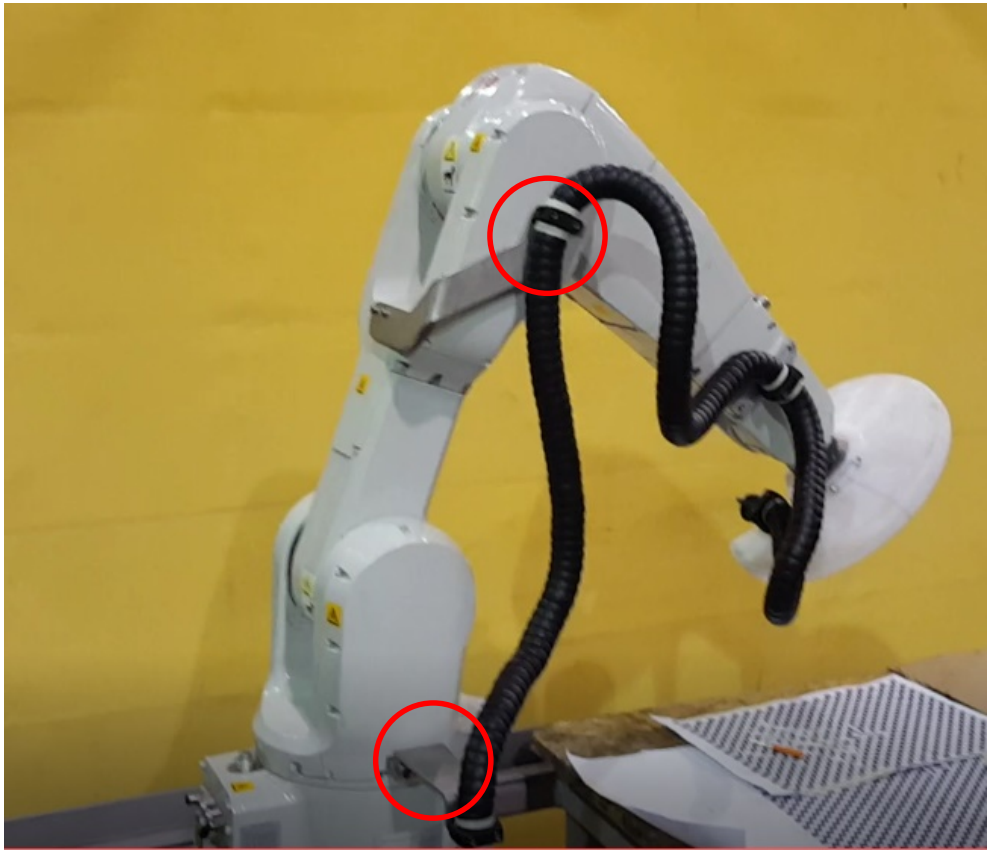
Begin by removing all external cables, conduit, dress-packs etc. The Robosuit is designed to fit the casting of the robot only.

Accessories will be re-attached (through the suit) once the Robosuit® is installed.



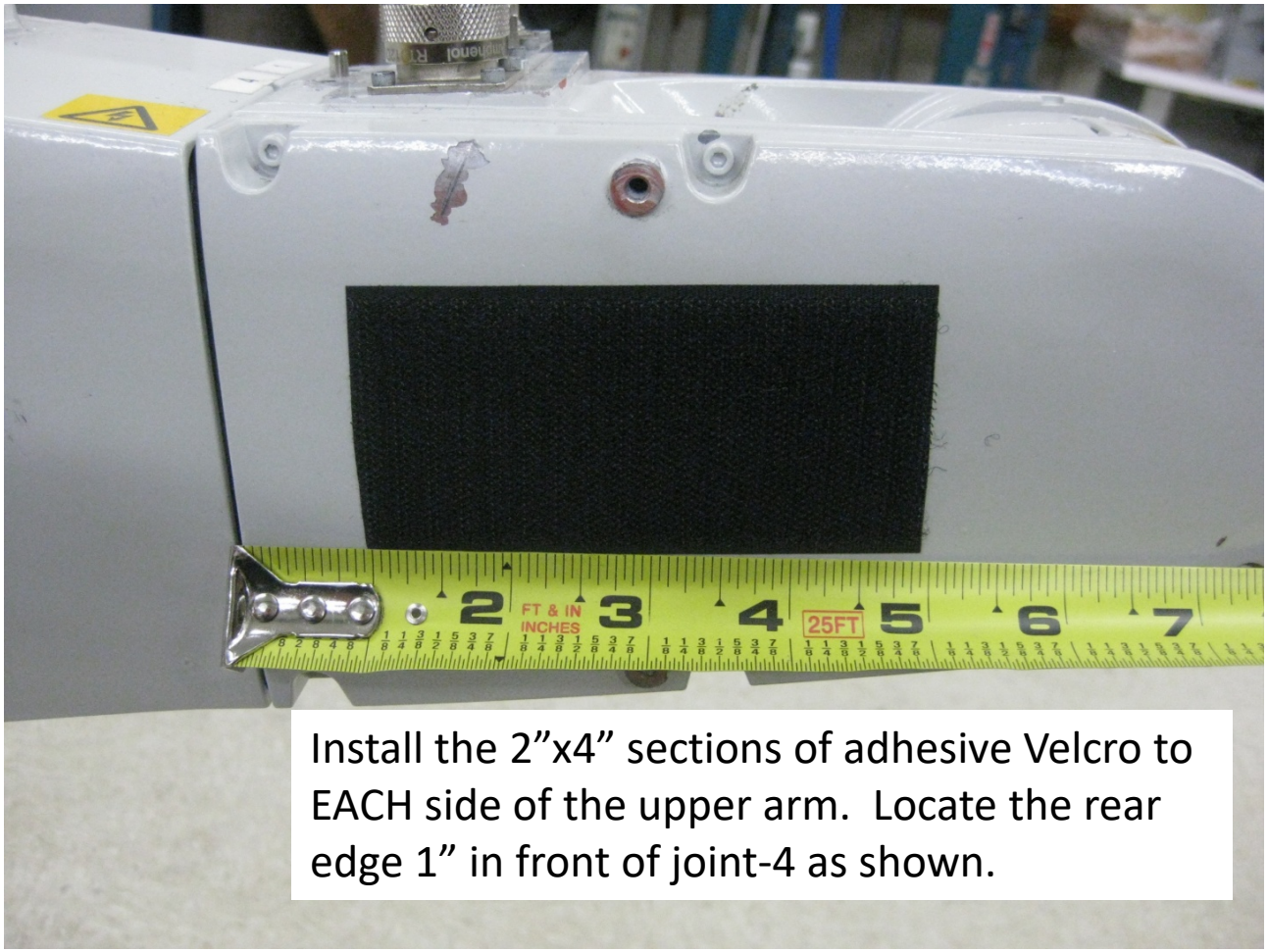
Depending on your specific dress-pack, spacers may be required to create sufficient stand-off between the bracketry and the Robosuit®.

These are <u>not</u> supplied by Roboworld.



Begin by installing Velcro pads on both sides of the robot's upper-arm.

Wipe the casting of the robot with isopropyl alcohol (or commercial degreaser) to remove any oils, dust and dirt prior to applying the Velcro pads.

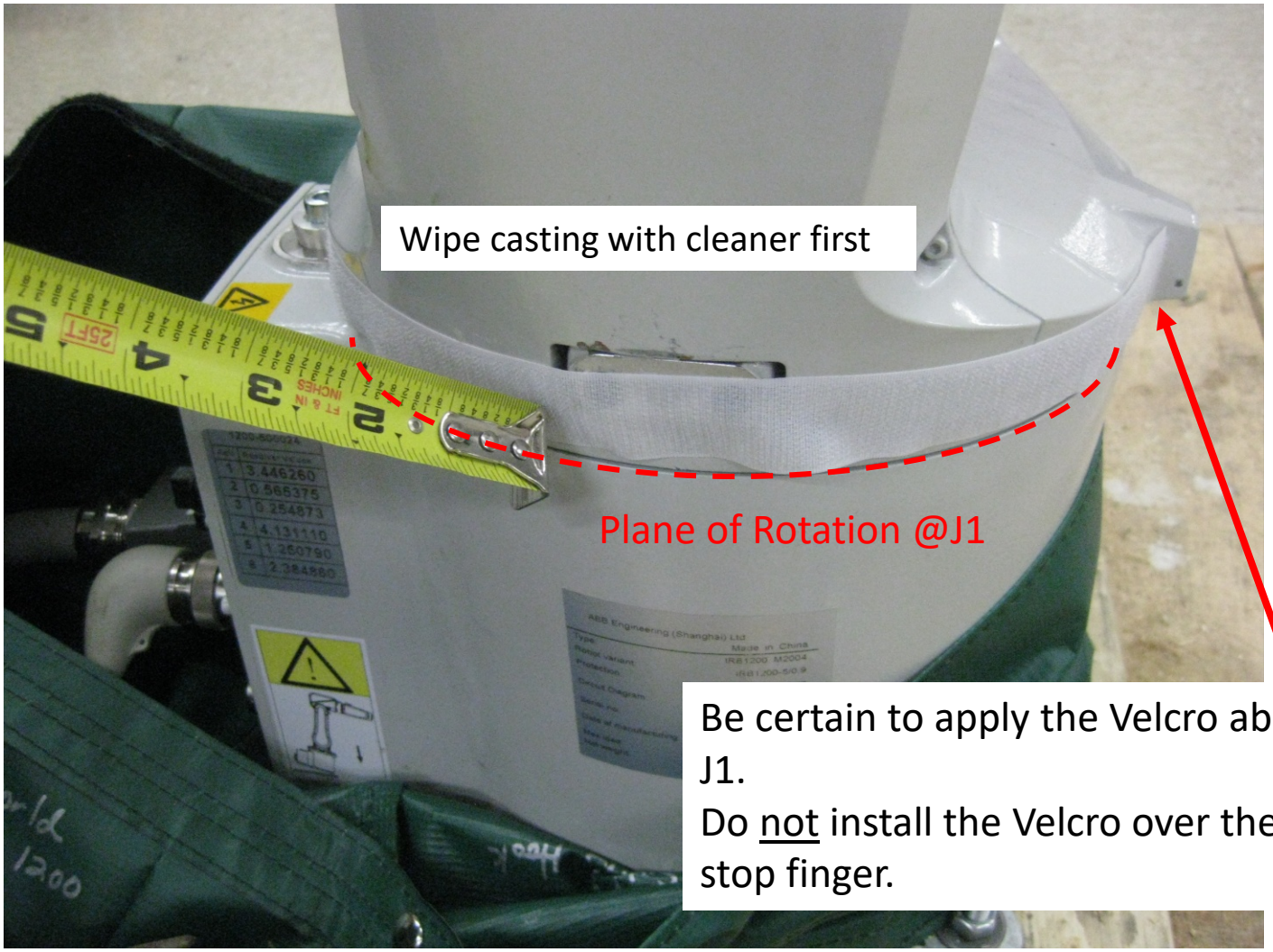


Install the 2"x4" sections of adhesive Velcro to EACH side of the upper arm. Locate the rear edge 1" in front of joint-4 as shown.

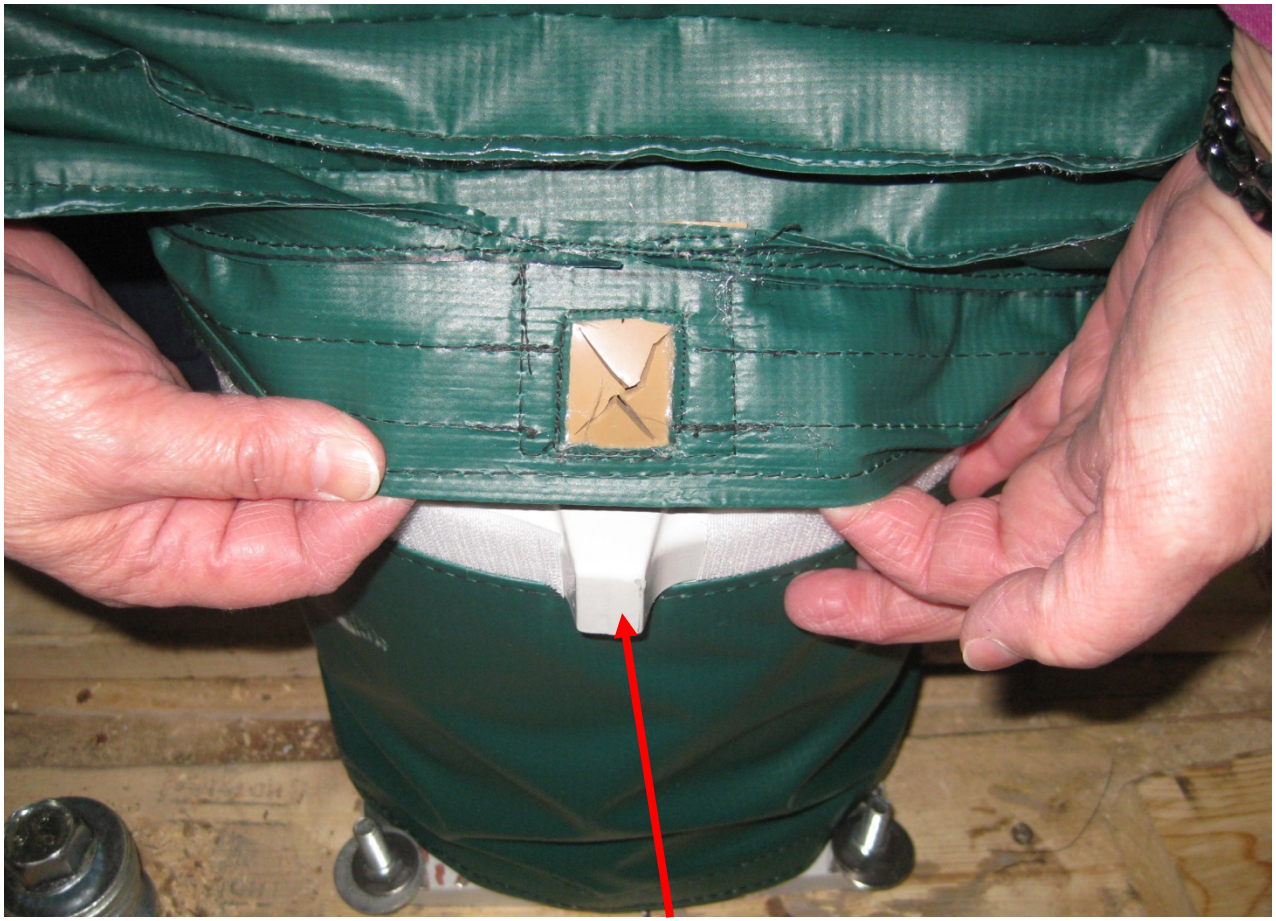
Identify the Lower Arm Section

Slide the larger end of the lower arm over J6; over the upper arm; and locate on the lower arm of the robot.

Note that the internal circumference of the lower arm features a band of Velcro. This will mate to a band of adhesive Velcro you may install at the location shown below.



The lower arm has a gum-rubber window. Using a razor knife, carefully cut an “X” in the gum rubber. This will allow for the J1 finger to extend through the cover. Once in place, push on the cover to adhere the Velcro sides.



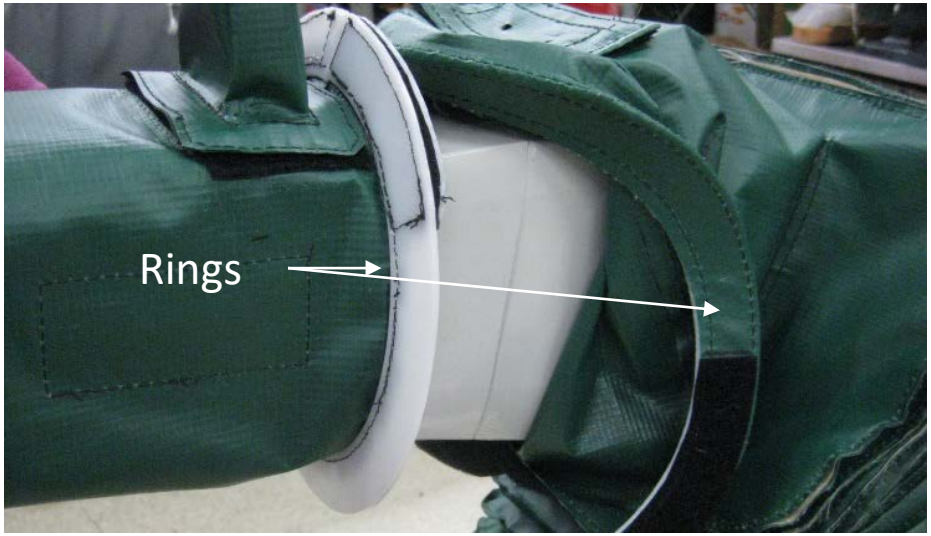
Align the finger and window to properly orient the lower-arm cover.

Open the flat Velcro access panel near joint-4.

Here you will find an anchor for the top portion of the lower-arm.

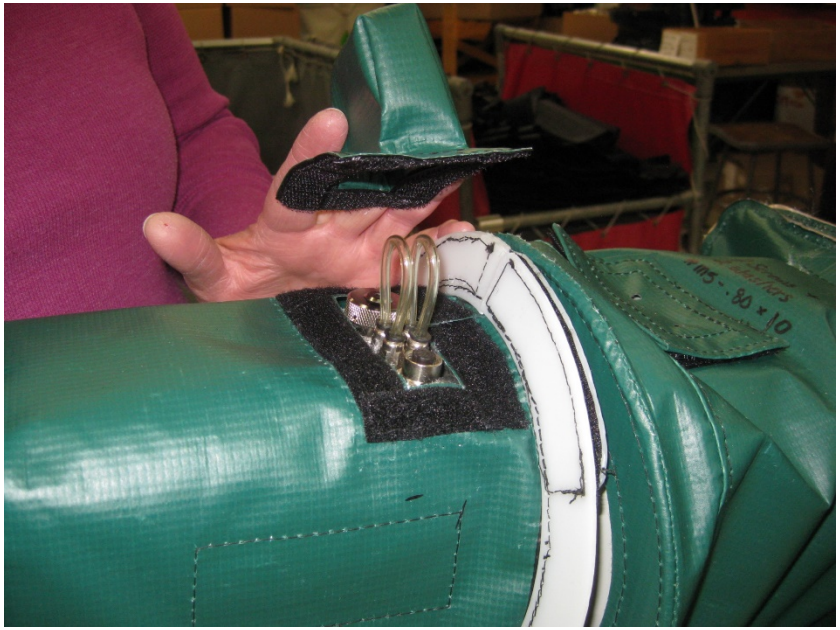
Secure the Velcro panel in place using the screws and washers provided/

There are two connection options for joint-4. One is a material-overlapping “cuff,” and the other is an interlocking Delrin ring.

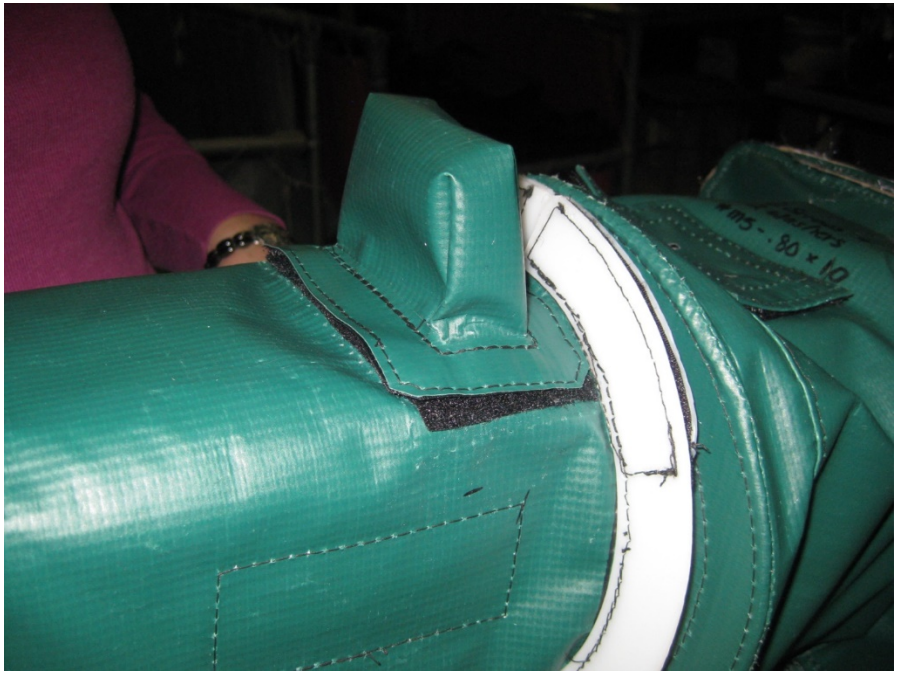


Install the upper arm by sliding it over J6 and positioning it at J4.

Notice the cut-out in the upper arm aligns with the air assembly connections.



Remove cap to align, then replace when in position.

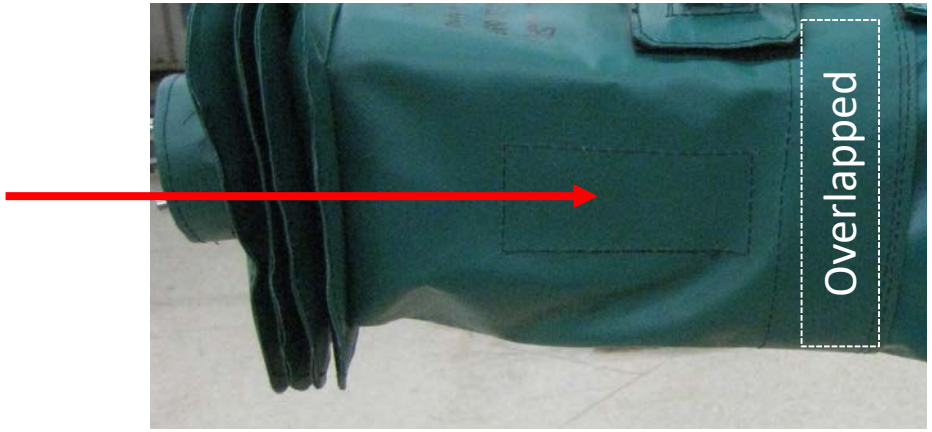


Once the upper arm is in position:

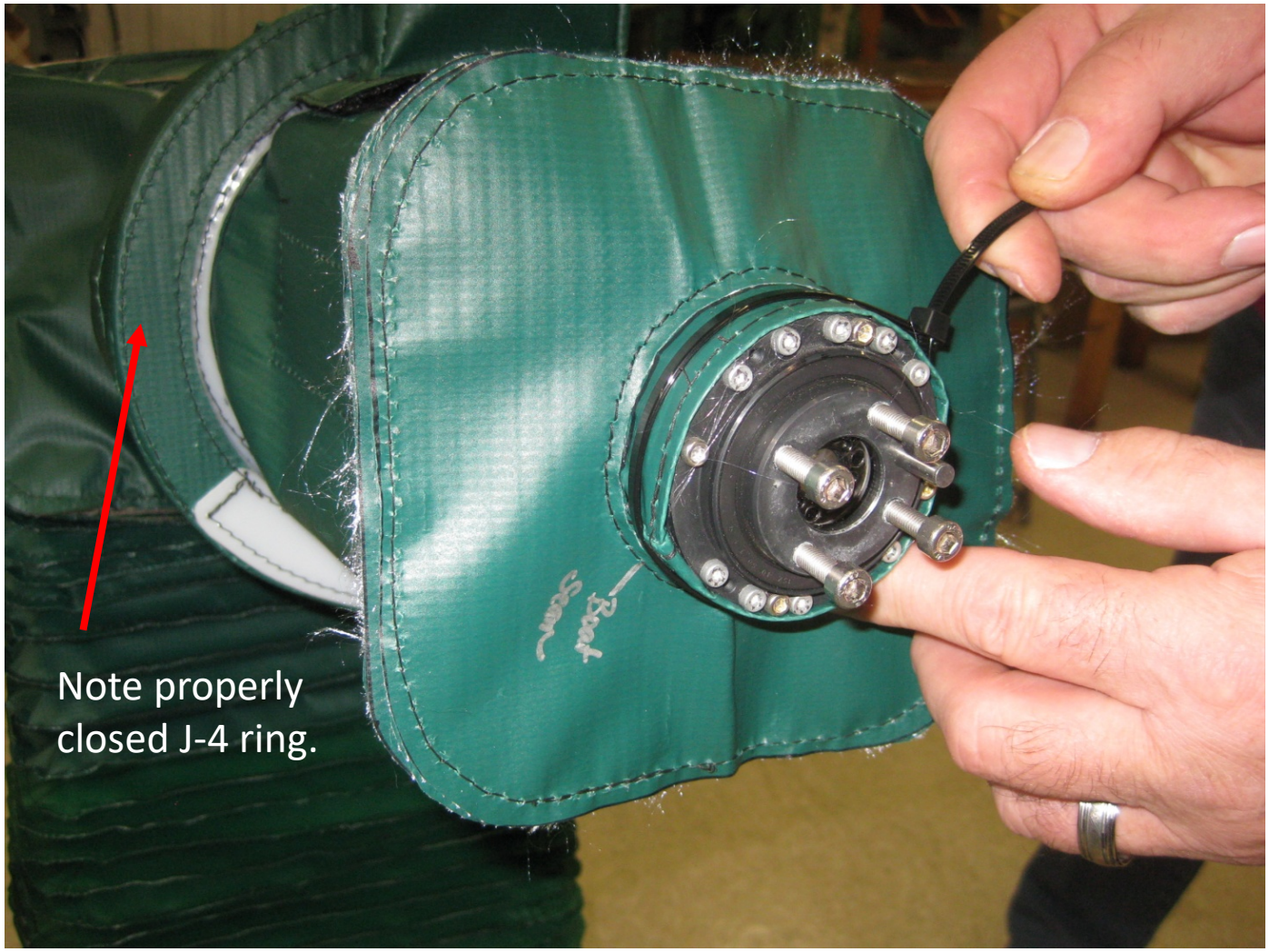
(Suit equipped with ring): Pull the lower-arm ring retainer over the upper-arm ring, and secure the Velcro tab, or

(Suit equipped with cuff): Overlap the lower-arm.

In <u>both</u> cases: Secure the Velcro panel on the inside of the upper-arm to the adhesive panels installed earlier.



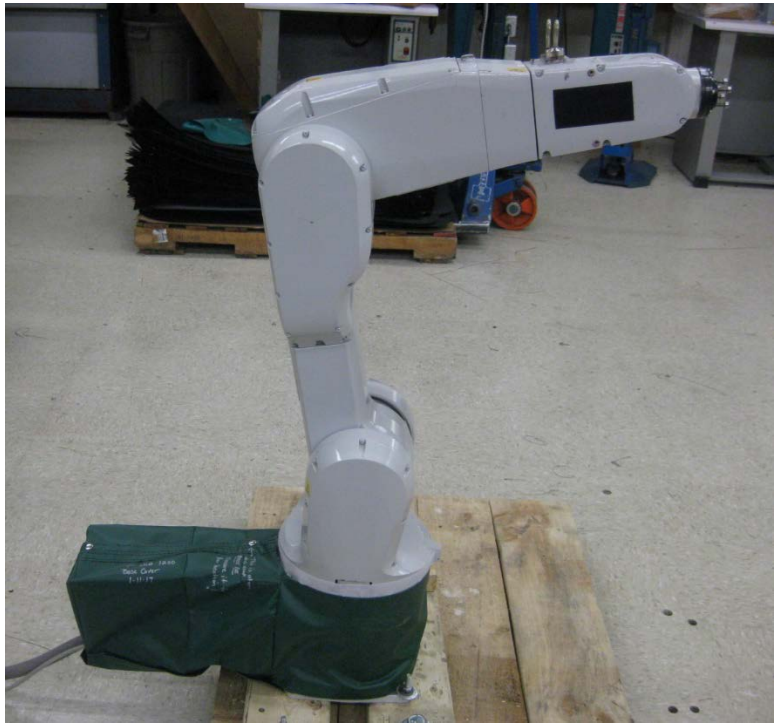
Install zip tie (or clamp) around the cuff at tool flange. Be certain to clamp on the non-rotating casting of the upper-arm and NOT the rotating tool flange as the cover will twist if clamped to the rotating tool-flange.



Install the base cover.

(Robot is floor mounted): Notice the top of the base cover is split with Velcro and snaps.

You have the option of using the “flat panel” bottom if desired.



If the robot is mounted inverted: The flat panel must be installed as it will be used to hold the base cover in proper position while the robot operates inverted.

Identify the cable exit port at the rear.

(Optional when using flat panel) Once in position, fold the bottom panel around the sides to secure Velcro seams.

You have completed the installation of the ABB IRB1200 Robosuit®.

Slowly jog the robot and check for any interference or binding. Should you see/find any, it may be necessary to adjust clamps or Velcro to settle into place.

Reinstall cables/conduit/dress packs at this time. If you specified protective cable wrap, install it at this time.