

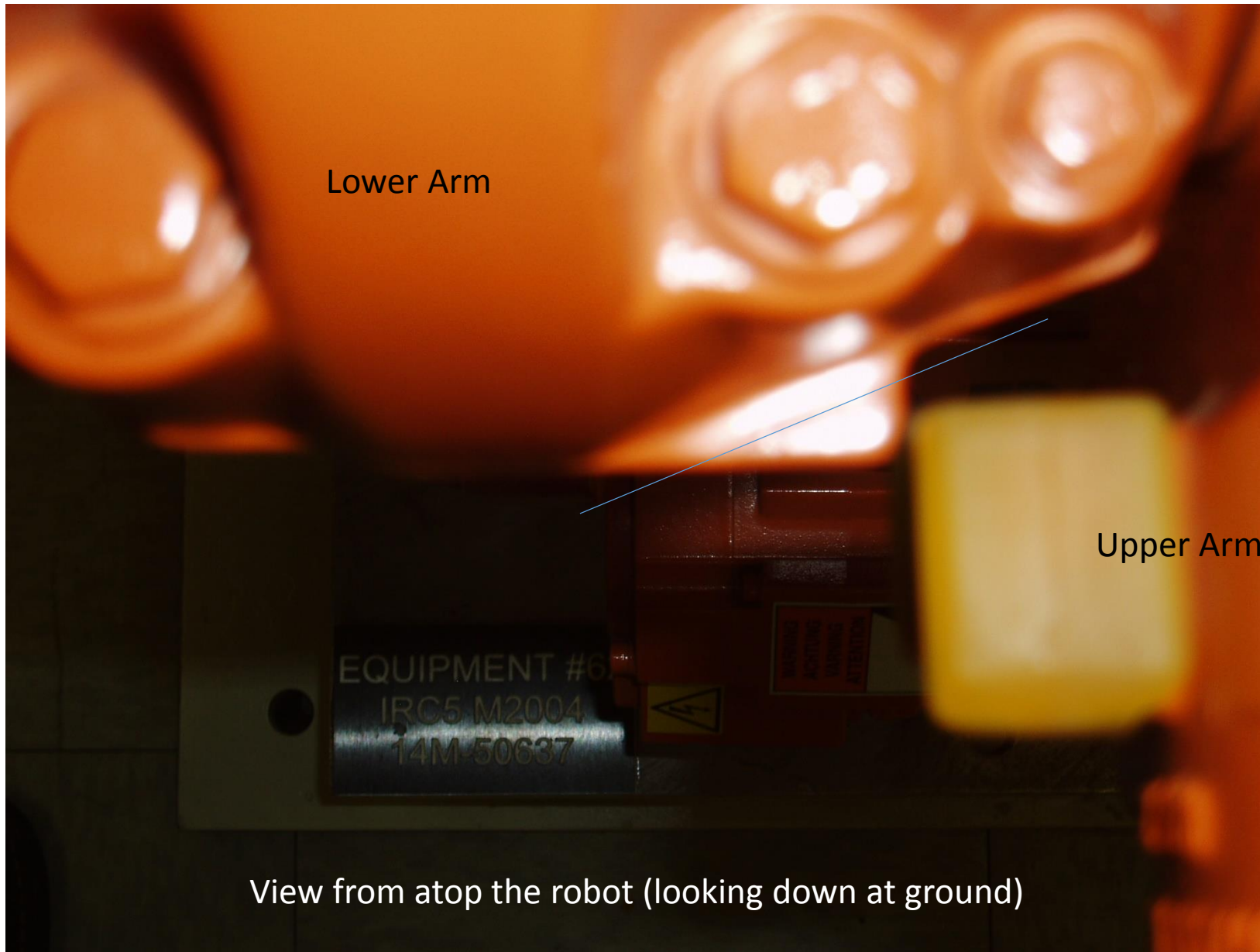


ABB IRB 140, Right side of robot

OPTIONS to address J3 Synchronization Markers

Synch indexer (on lower arm casting)

Reference pad (on upper arm casting)



Lower Arm

Upper Arm

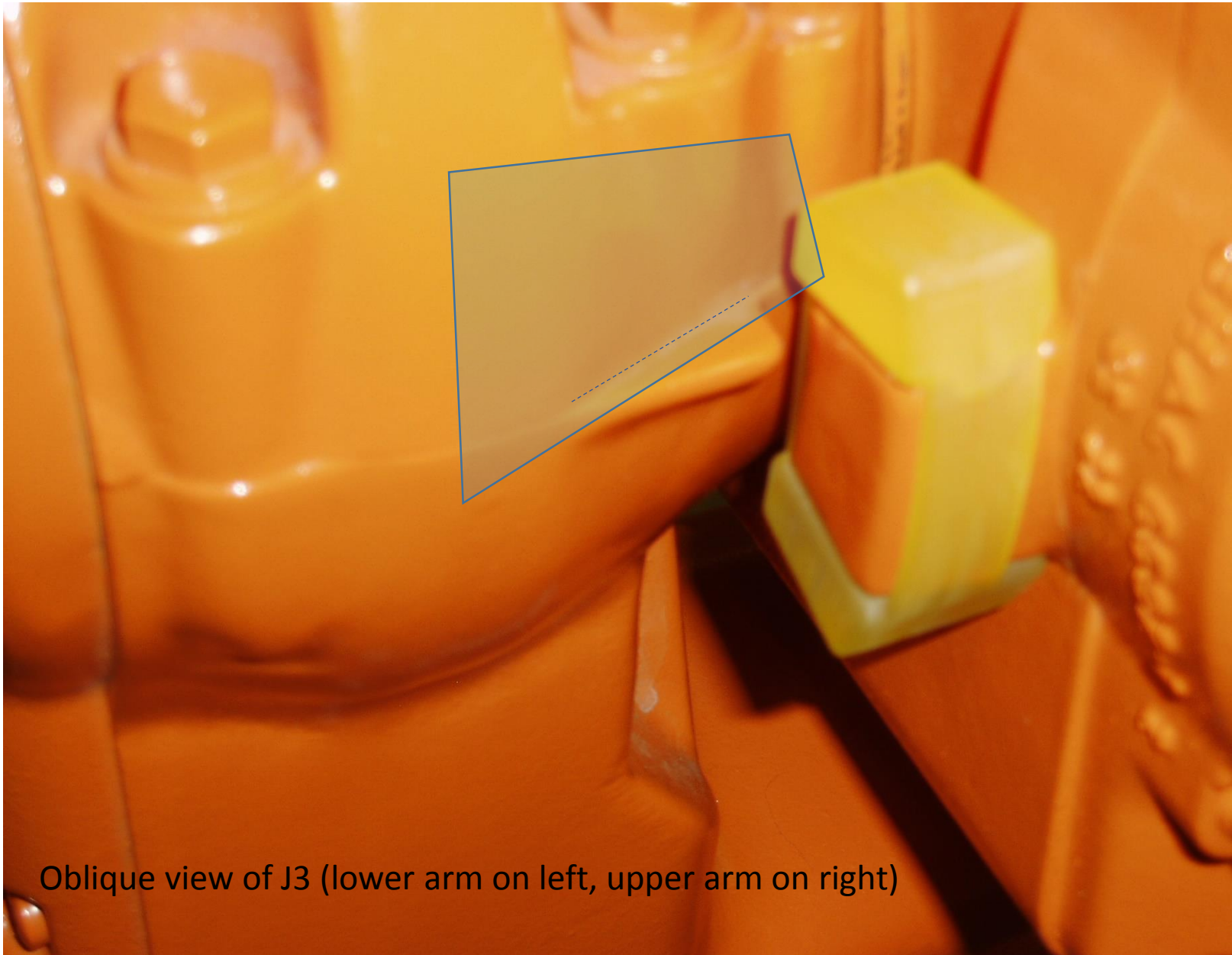
EQUIPMENT #6
IRC5 M2004
14M-50637

View from atop the robot (looking down at ground)

OPTION-1: Grind Indexer

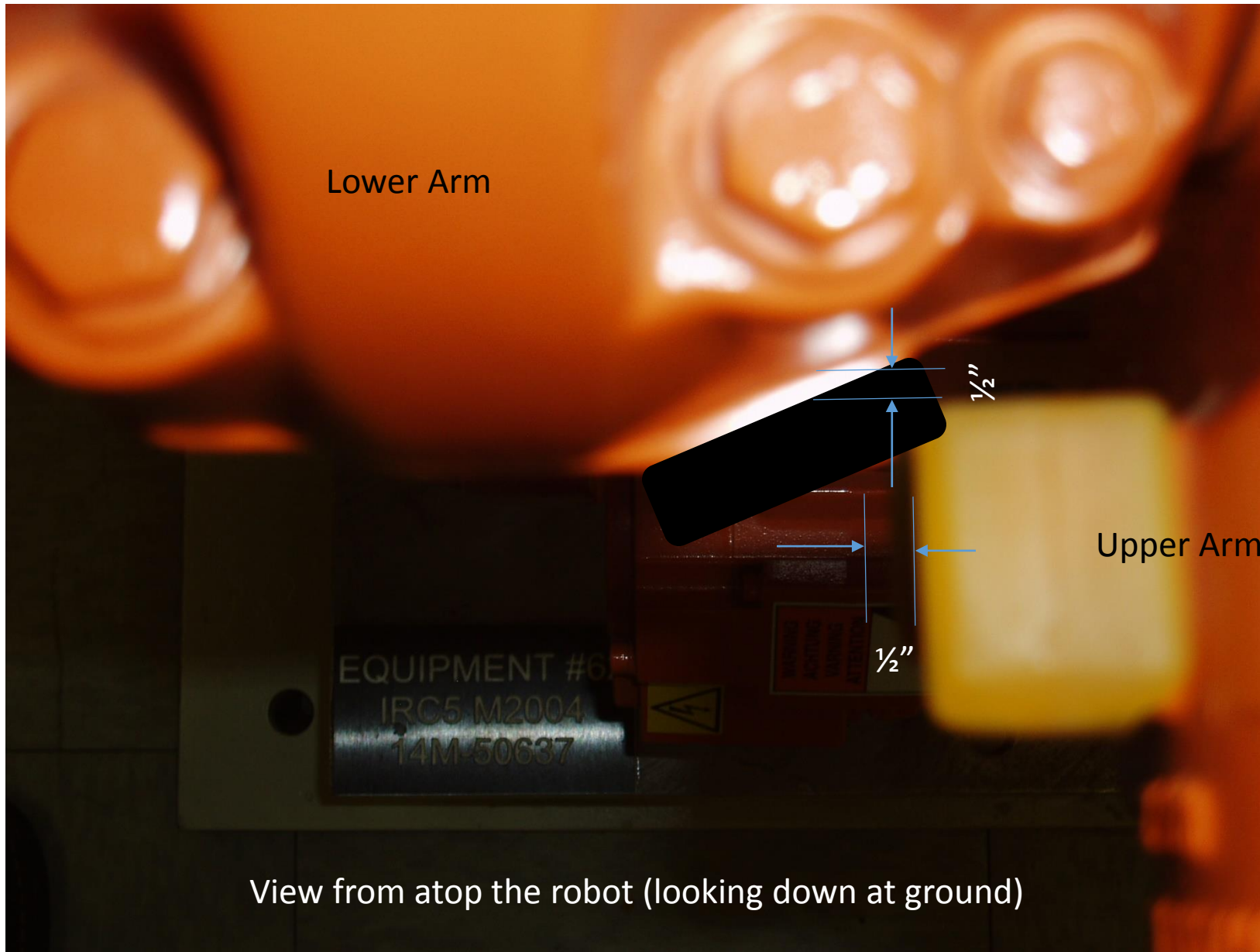
Approximate “grind”
clearance line.

Intent is to create a gap
for suit-material to pass
through/around markers
without destroying the
“cuff” at J3.



Oblique view of J3 (lower arm on left, upper arm on right)

Approximate “grind”
angle is parallel to the
indexer cast line at the
lower arm interface.

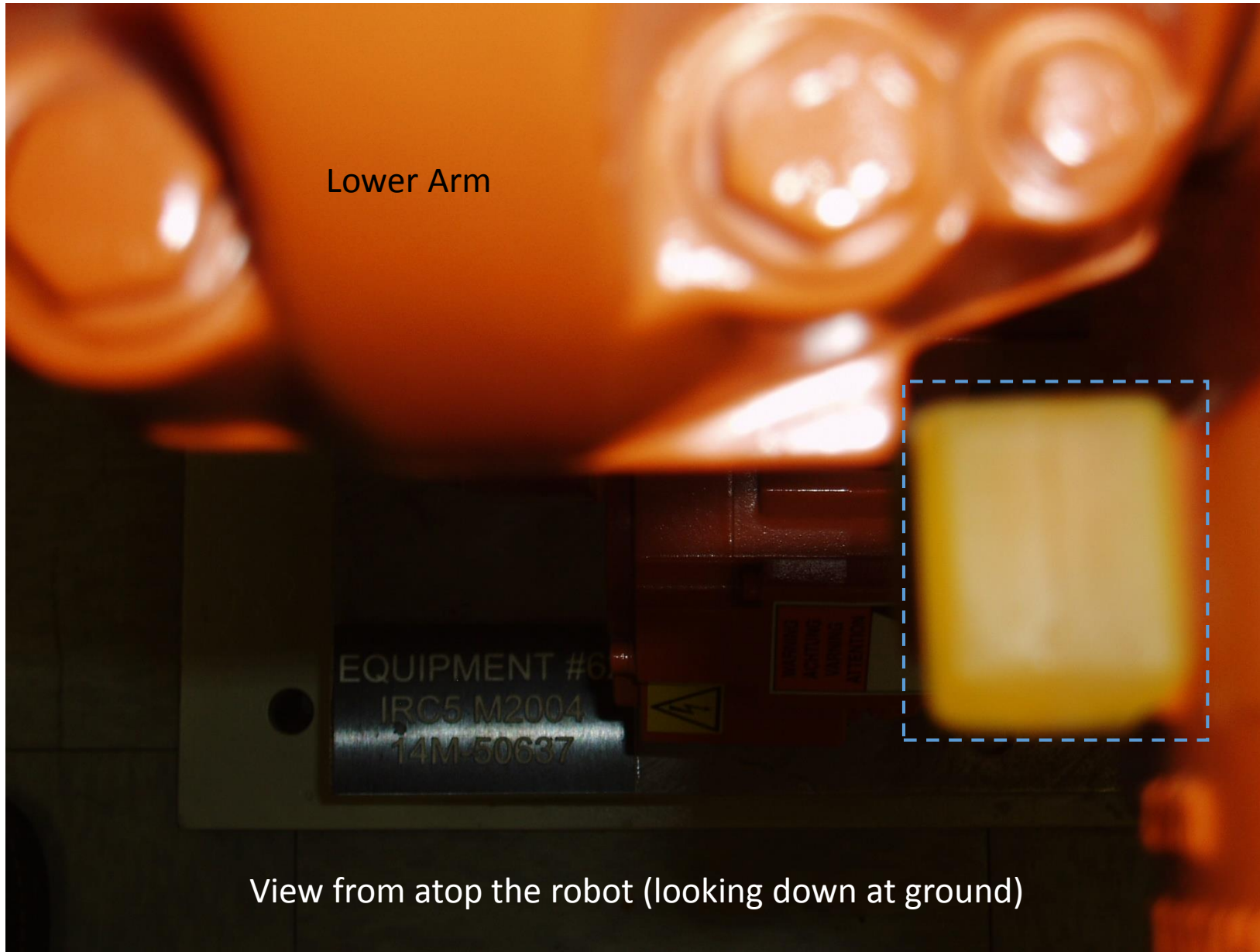


OPTION-1: Grind Indexer

Approximate “grind”
clearance line.

Intent is to create a gap
for suit-material to pass
through/around without
destroying the suit “cuff”
at J3.

A 1/2” gap is sufficient.



OPTION-2: Remove Pad

Remove urethane bumper (stop).

Grind down (or fully remove) pad.