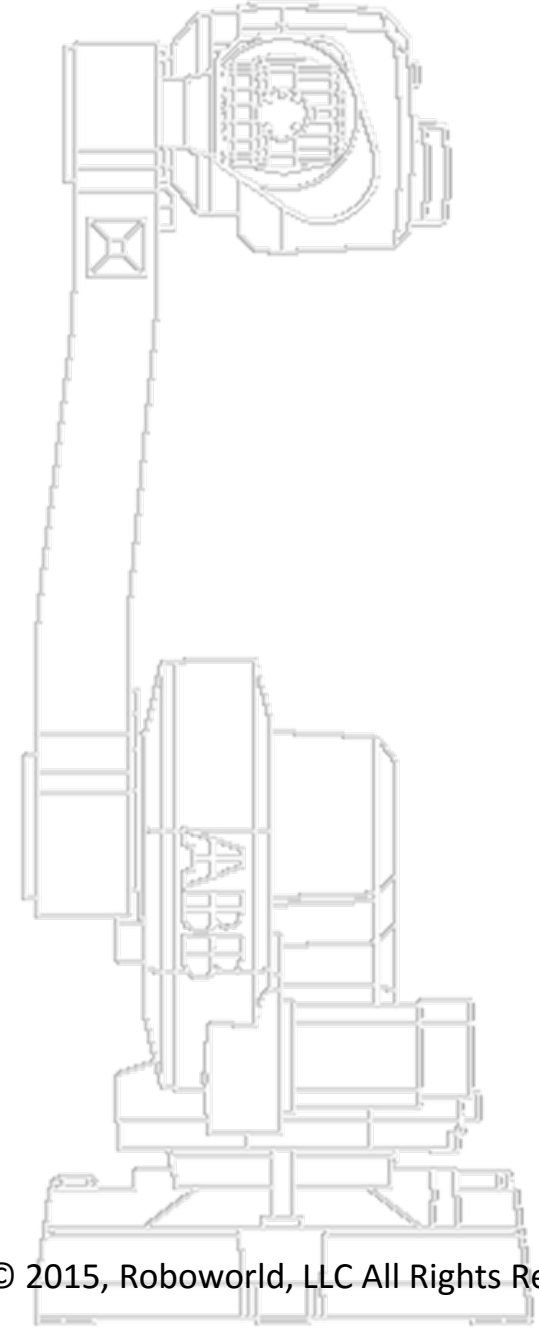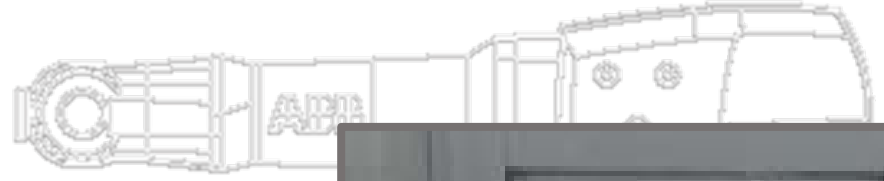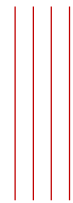# ABB IRB1600 Robosuit® Installation
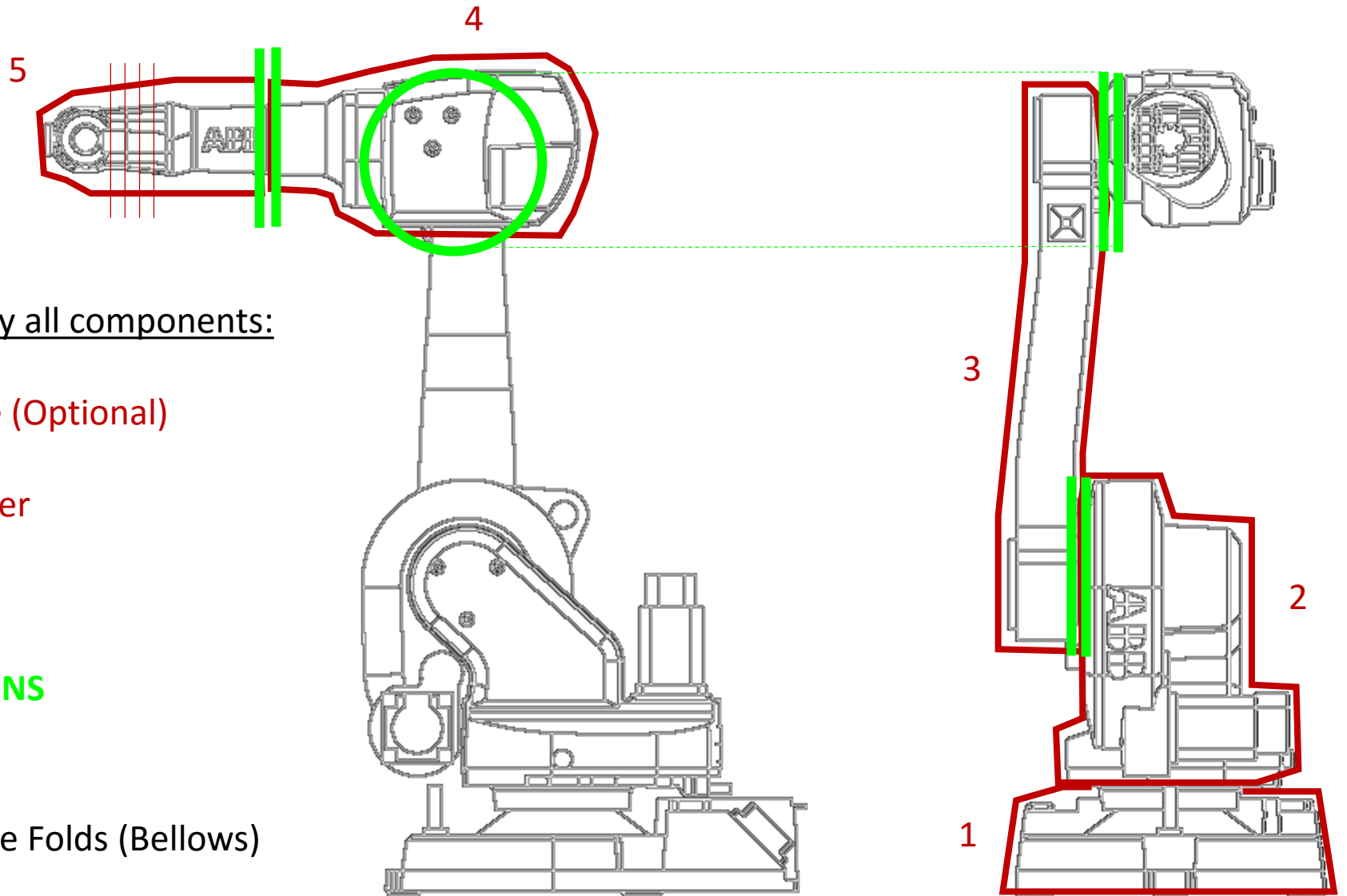## All Variants

ABB IRB1600 Robosuit® Installation
All Variants

Unpack and identify all components:

1) Stationary Base (Optional)
2) J2 Cover
3) Lower Arm Cover
4) Shoulder Cover
5) Wrist Cover

PVC RING LOCATIONS

Accordion-Style Folds (Bellows)

PRIOR TO INSTALLING THE ROBOSUIT®, CLEAN THE ROBOT SURFACE IF THE ROBOT HAS BEEN IN OPERATION WITHOUT ANY EFFECTIVE PROTECTION. DISCONNECT ANYTHING THAT WILL INTERFERE WITH INSTALLATION. NORMALLY, END-OF-ARM TOOLING DOESN'T INTERFERE IF THE ROBOT'S FLANGE IS FACE-OUT. IF POSSIBLE, PLACE THE ROBOT IN ITS SYNC ALIGNED (HOME) POSITION.

OPEN ALL ZIPPERS AND VELCRO SEAMS.

INSTALL THE STATIONARY BASE COVER FIRST. IT IS CONTOURED TO THE STATIONARY BASE SHAPE.

INSTALL THE J2 COVER NEXT. THIS COMPONENT OVERLAPS THE STATIONARY BASE (TO SHED FLUIDS OVER THE STATIONARY BASE COVER). A RING IS PROVIDED AT J2.

INSTALL THE LOWER ARM PIECE NEXT. THE RING AT J2 BUTTS FLUSH AGAINST THE RING ON THE J2 COVER, AND IS HELD IN PLACE WITH THE RING RETAINER POCKET. ZIPPER THE LOWER ARM CLOSED.

J2 RING RETAINER

Lower Arm

J2 Cover
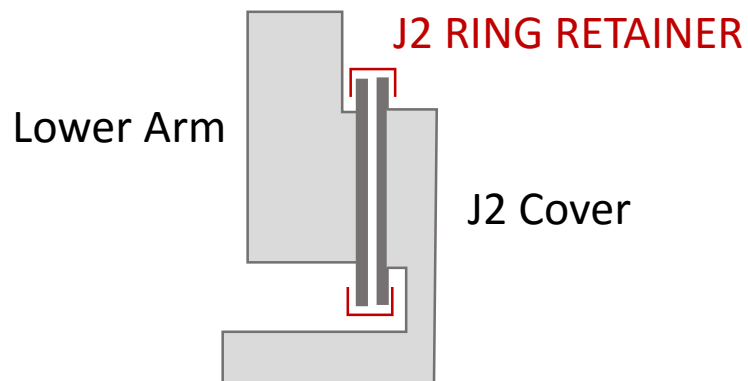
INSTALL THE SHOULDER PIECE NEXT. AGAIN, MATE THE J3 RING ON THE SHOULDER TO THE J3 RING ON THE LOWER ARM AND SECURE IN PLACE WITH THE RING RETAINER POCKET.

NEXT, INSTALL THE WRIST PIECE WITH THE SEAM FACING DOWNWARD.   MATE THE J4 RING ON THE SHOULDER WITH THE J4 RING ON THE WRIST. POSITIONING THE TOOL FLANGE PERPENDICULAR TO THE ARM WILL FACILITATE INSTALLATION.   (OPTIONAL: CLAMP THE UPPER ARM PIECE IN FRONT OF (DISTAL TO) THE 4TR AXIS OVERLAP. MAKE CERTAIN THE CLAMP DOESN'T INTERFERE WITH ARM ROTATION).

ATTACH ALL TOOLING AND RECONNECT ALL ELECTRIC/PNEUMATIC LINES THAT WERE DISCONNECTED PRIOR TO INSTALLATION. VELCRO PANELS HAVE BEEN INCORPORATED TO ACCESS THE ROBOT PERIPHERAL MOUNTING PADS. CAREFULLY MAKE "CROSS HAIR" CUTS (AS NEEDED) TO ATTACH BOLTS, BRACKETS, ETC THROUGH THE SUIT.

REMOVE ALL TOOLS, LADDERS, (ETC), AND ENSURE THERE ARE NO OBJECTS IN THE CELL THAT THE SUIT COULD SNAG ON BEFORE PLACING THE ROBOT INTO MOTION.

SLOWLY JOG THE ROBOT ONE AXIS AT A TIME BEGINNING WITH THE WRIST (AXIS 6) AND ENDING AT THE BASE (AXIS I) WHILE CHECKING FOR ANY INTERFERENCE PROBLEMS.