

ROBOTICS

Product specification

OmniCore V line



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Product specification
OmniCore V250XT Type B
OmniCore V400XT

OmniCore

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Original instructions.

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Overview of this specification

About this product specification

This product specification describes the properties of the OmniCore V line robot controller in terms of:

- Technical data and dimension
- The fulfilment of standards, safety and operating equipment
- RobotWare OS
- Controller system
- Variants and options

Usage

Product specifications are used to find data and performance about the product, for example to decide which product to buy. How to handle the product is described in the product manual.

The specification is intended for:

- Product managers and product personnel
- Sales and marketing personnel
- Order and customer service personnel
- Integrators and customers

References



Tip

All documents can be found via myABB Business Portal, www.abb.com/myABB.

Document name	Document ID
<i>Product manual - OmniCore V250XT Type B</i>	3HAC087112-001
<i>Circuit diagram - OmniCore V250XT</i>	3HAC074000-008
<i>Product manual - OmniCore V400XT</i>	3HAC081697-001
<i>Circuit diagram - OmniCore V400XT</i>	3HAC082020-008
<i>User manual - FlexPendant</i>	3HAC093167-001
<i>Product manual - FlexPendant Retractable Cable</i>	3HAC048816-001

Revisions

Revision	Description
A	First edition.

Continues on next page

Revision	Description
B	<p>Published in release 22A with RobotWare 7.6.</p> <ul style="list-style-type: none"> • Minor changes. • Updated the description for Scalable safety I/O [3037-x]. • Updated the description for Safety Interface [3054-1]. • Updated the option name for Hot swappable FlexPendant [3018-1]. • Updated information about humidity. • The option Externally Guided Motion [3124-1] is available for IRB 910INV. • CC-Link IE Field Basic Device [3066-2].
C	<p>Published in release 22B with RobotWare 7.7.</p> <ul style="list-style-type: none"> • Added information of power consumption. • Added 24V customer power supply. • Added introduction of cooling. • Added introduction of <i>Safety digital base device</i>. • Added SoftMove [3108-1]. • Added Machining Standard [3418-1] and Machining Premium [3418-2]. • Updated introduction of Safety internal conn. [3054-1]
D	<p>Published in release 22C with RobotWare 7.8.</p> <ul style="list-style-type: none"> • Added Conv.Tracking unit int. [3041-1]. • Added Conv.Tracking unit ext. [3042-1]. • Technical data for manipulators IRB 460, IRB 660 and IRB6650S added in section "Load current" and "Residual current".
E	<p>Published in release 22D with RobotWare 7.8.1.</p> <ul style="list-style-type: none"> • Minor changes. • Introduced V250XT Type A, description added in section Type change of the OmniCore controller on page 235. • Added the options CAP and DAP [3125-1].
F	<p>Published in release 23A with RobotWare 7.10.</p> <ul style="list-style-type: none"> • Added image for mains label in technical data section. • Technical data for manipulator IRB 2600 added in section "Load current" and "Residual current". • Updated the list of System signals on page 38. • Added PROFIsafe Controller [3023-1]. • Added CAP Premium [3125-2].
G	<p>Published in release 23B with RobotWare 7.10.</p> <ul style="list-style-type: none"> • <i>Force Control Interface</i> [3038-1] phase out. • Added <i>Production Framework</i> [1243-1] • Added <i>Spot welding</i> [3417-x] • Added <i>Additional drive units</i> [3062-1] • Added new option <i>Production Framework</i> [3404-1]. • Descriptions of <i>Mains voltage</i> [3007-x] updated • Information about options for Integrated Vision cameras and lenses removed. For detailed descriptions of the options and related hardware, see <i>Product specification - Integrated Vision</i>.
H	<p>Published in release 23C with RobotWare 7.12.</p> <ul style="list-style-type: none"> • Added information about power factor. • Added new option <i>CC-Link IE Field Master</i> [3066-1].

Revision	Description
J	<p>Published in release 23D with RobotWare 7.13.</p> <ul style="list-style-type: none"> Introduced V250XT Type B and V400XT. Description added in section Type change of the OmniCore controller on page 235 and OmniCore V line on page 13. ABB Connected Services is the new name for the functionality previously known as ABB Ability. During a period of time, both names will appear in and on our products. New options for Connected Services added: Mobile network 4G EU [3013-5] and Mobile network 4G US [3013-6] New options added: <i>Motor connection box, 3-axis, BRB</i> [3069-1x] and <i>Motor connection box, 6-axis, BRB</i> [3069-2x]. Added options for dispensing and arcwelding.
K	<p>Published in release 24A with RobotWare 7.14.</p> <ul style="list-style-type: none"> Option Tool Control [3109-1] added. Option [3050-2] 2xCable gland added. Options [3012-X] for lock variants added. Options [3070-1] No brake release and [3070-2] Analog brake release added. Options Base Dig. 16In/16Out (1-2) [3032-1] and Base Dig. 16In/16Out (1-2) [3032-1] updated with information about a second row of I/O units (for V400XT). Updated protection class of FlexPendant. Updated information about power factor. Updated the section Ethernet & signal interfaces on page 109. Updated the section Ethernet switch on page 90. Section Supported manipulators on page 15 updated with information about IRB 390 and IRB 2400. Updated the section Line fusing on page 17. Updated the section Ethernet & signal interfaces on page 109.
L	<p>Published in release 24B with RobotWare 7.15.</p> <ul style="list-style-type: none"> New options added: <ul style="list-style-type: none"> [3053-1] Status LEDs at front. [3011-1] Wheels. [3004-2] Max 52deg. [3079-1] Additional robot power. [3071-2] Wake-on-LAN#V-line. [3013-7] Mobile network 4G CN. [3015-3] 24V 20Amps. [3016-21/22/23] FP retractable. [3021-1] PROFlenergy. [3075-2] EtherCAT Device. [3076-2] Safety Over EtherCAT Device. [3068-3] Track motion and [3068-4] MU/GU. [3069-15] Connection box 30m and [3069-25] 2xConnection box 30m. [3102] MultiMove. [3154-2] IoT Data client. [3213/3214] IMM Interface. [3411-1] BullsEye and [3411-2] Torch Service Center. [3420/3421/3422/3423] Weldguide. [3415-1] Force Control Standard. [3039] Force Control Package. Minor corrections.

Continues on next page

Revision	Description
M	<p>Published in release 24C with RobotWare 7.16.</p> <ul style="list-style-type: none">• New options added:<ul style="list-style-type: none">- [3006-1] UL/CSA• Updated the list of supported FTP servers.• Information about total cable length added in Motor connection kit on page 137.
N	<p>Published in release 24D with RobotWare 7.17.</p> <ul style="list-style-type: none">• Added new option <i>No connected services</i> [3013-99].• Added new option <i>Arc welding Premium+</i> [3416-3].• Added new option <i>Automatic Path Planning</i> [4400].• Information about options Ethernet 2xM12 X-coded [3060-1] and Ethernet 5xM12 X-coded [3061-1] updated.• Updated the section Motion Coordination on page 162.• Maximum cable length updated in FlexPendant on page 53.• Minor corrections.
P	<p>Published in release 25A with RobotWare 7.18.</p> <ul style="list-style-type: none">• New option: <i>Cylinder with key</i> [3012-6].• Phased out IRB 6700, IRB 7600.• Cybersecurity information added.

1 OmniCore V line

General

ABB OmniCore is the industry most versatile and powerful industrial robot controller range, offering increased flexibility and incorporates the latest digital technologies. OmniCore V Line (Extra Tough) is medium sized controllers within the OmniCore controller family, optimized for medium and large robots in industrial environments, for applications such as machine tending, material handling, arc welding, spot welding, etc.

OmniCore power saving solutions

The OmniCore V line controllers use bi-directional active rectifiers, which reduces waste. Additional benefits are that no extra space is needed, no capacity limitation, and there is no safety risk with energy storage.

The bi-directional rectifier (power supply unit) is always active and does not require any configuration from the user. The savings are highly dependent on the usage of the robot. Aggressive running with high speed and acceleration will generate more savings compared to a slow and easy path/usage of the robot.

The power factor is ~1.00 (~0% reactive power). See also the product specification for the respective manipulator.

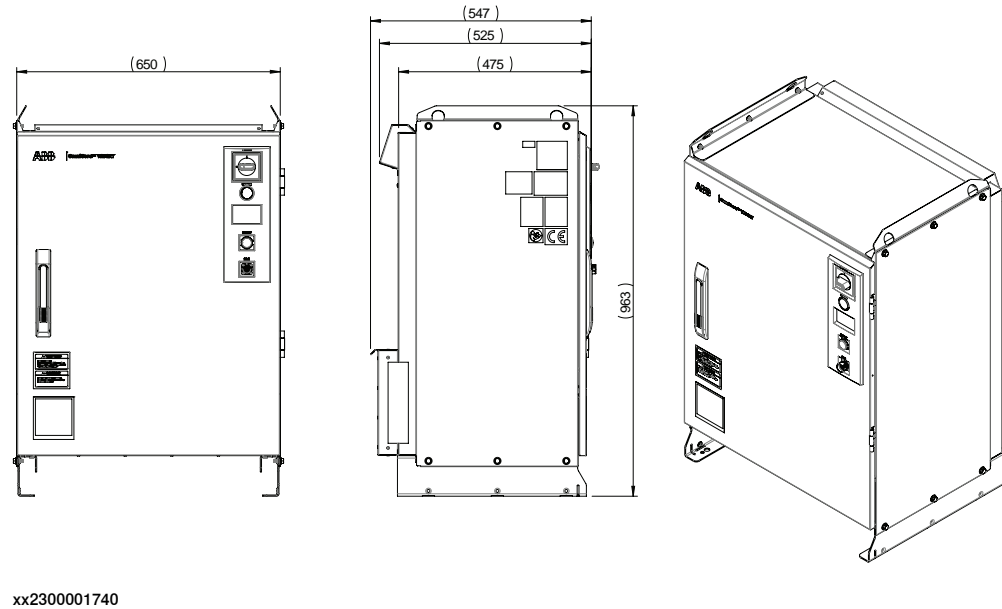
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1 OmniCore V line

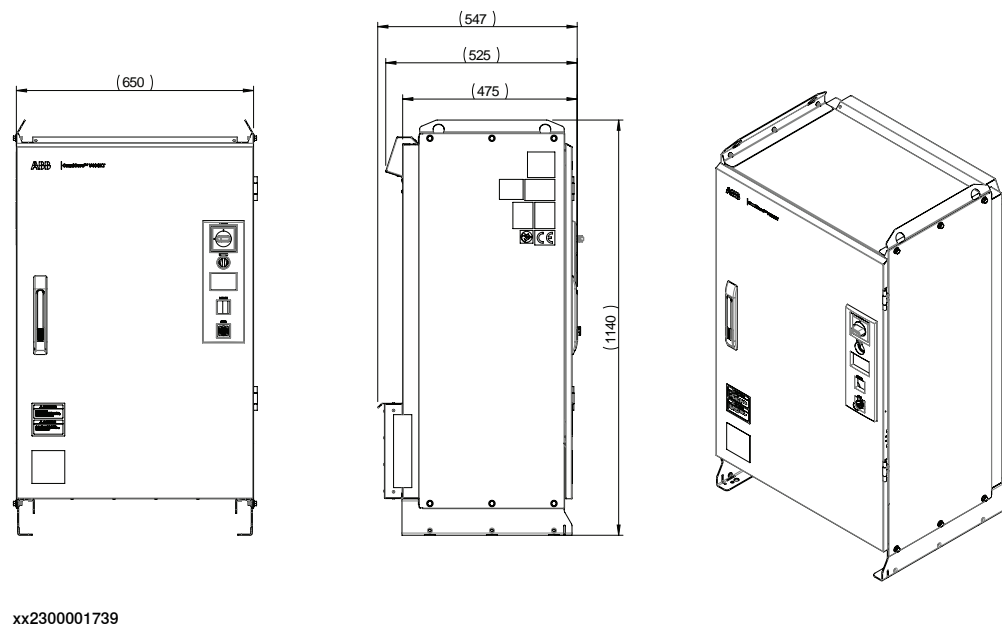
1.1 Cabinet design

1.1 Cabinet design

OmniCore V250XT Type B



OmniCore V400XT



1.2 Technical data

Supported manipulators

Manipulator	V250XT Type B	V400XT
IRB 390	✓	✓
IRB 460	✓	✓
IRB 660	✓	✓
IRB 760		✓
IRB 1300	✓	✓
IRB 1520	✓	✓
IRB 1600	✓	✓
IRB 2400	✓	✓
IRB 2600	✓	✓
IRB 4400	✓	✓
IRB 4600	✓	✓
IRB 5710, IRB 5720	✓	✓
IRB 6650S	✓	✓
IRB 6660	✓	✓
IRB 6790	✓	✓
IRB 6710, IRB 6720, IRB 6730, IRB 6740	✓	✓
IRB 7710, IRB 7720		✓
IRB 8700		✓

Dimensions and weight

Parameter	V250XT Type B	V400XT
Width	650 mm	650 mm
Depth	475 mm	475 mm
Height	960 mm	1,140 mm
Weight	85 kg	118 kg



Note

The weight does not include any mounting kits fitted on the controller.

Transportation and storage conditions

Parameter	Value
Minimum ambient temperature	-40 °C (-40 °F)
Maximum ambient temperature	+55 °C (+131 °F)
Maximum ambient temperature (less than 24 hrs)	+70 °C (+158 °F)

Continues on next page

1 OmniCore V line

1.2 Technical data

Continued

Parameter	Value
Shock and Vibration	In accordance with ETSI EN 300 019-2-2 / Environmental class 2.3 (No severity reduction for horizontal axes)

After storage, the operating conditions inside the controller must be met for at least 6 hours before switching on the controller (see [Operating conditions on page 16](#)).

The robot controller shall be stored according to its IP classification (IP54), that is, indoors, in an environment that is dry and dust-free. In addition, wind, temperature fluctuations, and condensation shall be avoided.

Operating conditions

Parameter	Value
Minimum ambient temperature	+5 °C (+41 °F)
Maximum ambient temperature	+45 °C (+113 °F)
Maximum ambient altitude	2,000 m
Shock and Vibration	In accordance with ETSI EN 300 019-2-3 / Environmental class 3.5 (3M5) (Random vibration)



Note

The humidity conditions shall apply with the environmental conditions EN 60721-3-3, climatic class 3K3. For temperatures 0-30 °C, the relative humidity must not exceed 85%. For temperatures exceeding 30 °C, the absolute humidity must not exceed 25g/m³.

If the environmental conditions in EN 60721-3-3, climatic class 3K3, are not possible to meet at the installation site, desiccant bags can be placed inside the controller to achieve corresponding conditions. The desiccant bags must be replaced regularly to maintain approved operating conditions.

Protection classes

	Protection class (IEC 60529)
Controller cabinet, inner compartment for electronics	IP54
Controller cabinet, compartment including cooling channel	IP23
FlexPendant	IP65

The cabinet must be closed and sealed when no internal access is required.

If the cabinet is not properly closed and sealed (door and cable grommets), it does not comply with the protection class (IP54) and may affect the following:

- The electromagnetic compatibility (EMC) is affected
- Units inside the cabinet are exposed to dust or moisture. Especially important in cases with high heat and humidity, or much pollution.

Continues on next page

**Note**

To comply with IP54, all openings to the controller cabinet must be sealed. This includes unconnected connectors which must be fitted with covers.

Airborne noise level

Data	Description	Note
Airborne noise level	The sound pressure level one meter away from each surface of the controller.	Controller in Motors On Mode: < 65 dB(A) Leq Controller in Standby Mode: < 60 dB(A) Leq

Power supply

Mains	Value
Voltage for OmniCore V line	380 VAC-480 VAC, 3-phase
Voltage tolerance	+10%, -15%
Frequency	50/60 Hz
Frequency tolerance	±3%
Short circuit current rating	According to rating label.

**Note**

For installations according to UL requirements, short circuit current rating is 5 kA.

Line fusing

There is no integrated fuse inside the OmniCore V line controller. Add an external fuse (time-delay) or circuit breaker (class K) according to full load current, as marked on the controller nameplate. The following table shows the recommended rating for an external fuse or circuit breaker.

As baseline there is no integrated fuse or circuit breaker. The option 3008-3 Mains connector/Fuse includes integrated circuit breaker.

To find the rated voltage and the full load current of the controller, see the name plate on the upper side of the cabinet.

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1 OmniCore V line

1.2 Technical data

Continued



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The rated current means maximum current in ISO Cube rapid when the robot is running at rated voltage 380 VAC. It depends on application (manipulator size, options). See the following table.

Manipulator	Voltage (V)	Current (A)
IRB 390	380 VAC-480 VAC, 3-phase	3x16 A
IRB 460	380 VAC-480 VAC, 3-phase	3x25 A
IRB 660	380 VAC-480 VAC, 3-phase	3x25 A
IRB 760	380 VAC-480 VAC, 3-phase	3x25 A
IRB 1300	380 VAC-480 VAC, 3-phase	3x16 A
IRB 1520	380 VAC-480 VAC, 3-phase	3x16 A
IRB 1600	380 VAC-480 VAC, 3-phase	3x16 A
IRB 2400	380 VAC-480 VAC, 3-phase	3x16 A
IRB 2600	380 VAC-480 VAC, 3-phase	3x16 A
IRB 4400	380 VAC-480 VAC, 3-phase	3x25 A
IRB 4600	380 VAC-480 VAC, 3-phase	3x25 A
IRB 5710, IRB 5720	380 VAC-480 VAC, 3-phase	3x25 A
IRB 6650S	380 VAC-480 VAC, 3-phase	3x25 A
IRB 6660	380 VAC-480 VAC, 3-phase	3x25 A
IRB 6790	380 VAC-480 VAC, 3-phase	3x25 A
IRB 6710, IRB 6720, IRB 6730, IRB 6740	380 VAC-480 VAC, 3-phase	3x25 A
IRB 7710, IRB 7720	380 VAC-480 VAC, 3-phase	3x25 A
IRB 8700	380 VAC-480 VAC, 3-phase	3x25 A

Continues on next page

**Note**

For information about what controller supports each manipulator, see [Supported manipulators on page 15](#).

Residual current

An external earth fault protection (residual current device, RCD) is required. For detailed information on how to select an external earth fault protection, see the respective product manual.

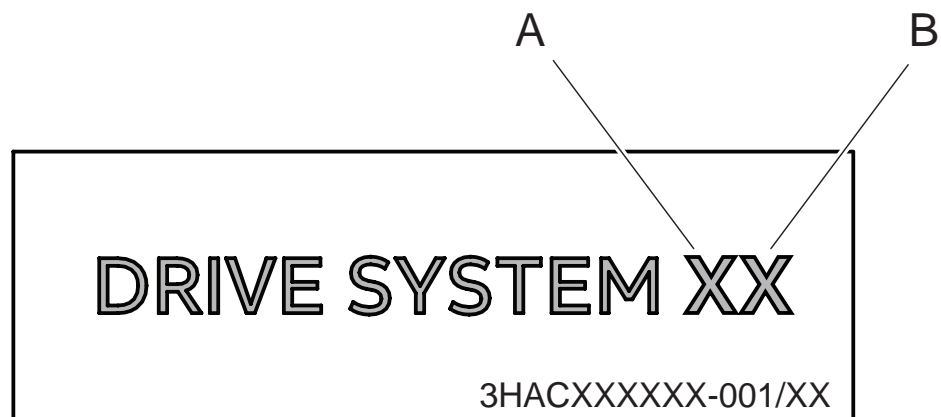
**Note**

The integrator is responsible to address local electrical requirements.

Drive system

The drive system provides motion power and absorbs excess braking energy when the robot is running.

The drive system label, which is placed on the left side of the controller, contains information about the drive system type for this specific controller:



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The drive system type (letter and number) indicates the combination of drive unit (A) and power unit (B) that may be used for this controller:

Type reference	Drive unit	Power unit
E*	Drive unit HV DSQC3062	-
B*	Drive unit LV DSQC3084	-
*4	-	Power unit LVHP DSQC3069A
*5	-	Power unit LVLP DSQC 3071
*8	-	Power unit HVHP DSQC3070
*9	-	Power unit HVLP DSQC3072

Continues on next page

1 OmniCore V line

1.2 Technical data

Continued

The controller drive system shall only be used with the manipulator variant that is specified in the following table:

Product		Power									
Manipulator	Controller	2.5kVA- 310V	2.5kVA- 370V	3.0kVA- 370V	7.0kVA- 370V	3.0kVA- 370V	480VA- 24V	1.2kVA- 48V	1.5kVA- 48V	13kVA- 650V	7.5kVA- 650V
IRB 1600 or smaller	V250XT				B4	B5					
	V400XT										
IRB 390 IRB 2400 IRB 2600	V250XT				E4	E5					
	V400XT										
IRB 4600 or larger	V250XT									E8	E9
	V400XT										

2 Safety

2.1 Applicable standards

General

The product is compliant with ISO 10218-1:2011, *Robots for industrial environments - Safety requirements - Part 1 Robots*, and applicable parts in the normative references, as referred to from ISO 10218-1:2011. In case of deviation from ISO 10218-1:2011, these are listed in the declaration of incorporation. The declaration of incorporation is part of the delivery.

Robot standards

Standard	Description
ISO 9283	Manipulating industrial robots – Performance criteria and related test methods
ISO 9787	Robots and robotic devices – Coordinate systems and motion nomenclatures
ISO 9946	Manipulating industrial robots – Presentation of characteristics

Other standards used in design

Standard	Description
IEC 60204-1	Safety of machinery - Electrical equipment of machines - Part 1: General requirements, normative reference from ISO 10218-1
IEC 61000-6-2	Electromagnetic compatibility (EMC) – Part 6-2: Generic standards – Immunity standard for industrial environments
IEC 61000-6-4	Electromagnetic compatibility (EMC) – Part 6-4: Generic standards – Emission standard for industrial environments
ISO 13849-1:2006	Safety of machinery - Safety related parts of control systems - Part 1: General principles for design, normative reference from ISO 10218-1

2 Safety

2.2 Safety functions

2.2 Safety functions

Safety

The safety design of the controller is state of the art. It has a dedicated safety system based on a two-channel circuit which is monitored continuously. If any component fails, the electrical power supplied to the motors is cut off and the brakes engage.

Safety functions	Description
Stop category 0	Stop function that immediately removes the power to the motors and applies the brakes.
Stop category 1	Stop function that stops the robot using the motors instead of the brakes which leads to a controlled stop where the robot is stopping on the programmed path. This stop is more effective especially on large robots. A stop category 0 will be applied with a 1 second delay after a stop category 1 is triggered.
Protective Stop	The integrator of the cell can connect sensors/equipment which triggers the safety controller to issue a stop the robot using stop category 0 or stop category 1. The sensor could be placed on the cell door, stopping the robot when the door is opened.
Emergency Stop	If something happens either with the robot system or in a machine near the robot system and the operator presses the emergency stop, then all machines/systems in sight shall be stopped. Emergency Stop status output is available in the basic delivery of OmniCore controller family including all variants. The emergency stop button is integrated in the FlexPendant.
Manual Operation Supervision	In manual reduced speed the robot can be moved using the FlexPendant and the enabling device. The enabling switch must be pressed to maintain safety.
Start / Restart Function	The start / restart function ensures that all safety conditions are met before enabling movement after a stop.
Service Mode	During service of the robot, it must be possible to move the robot without the safety monitoring, for example move the robot without being disturbed by forbidden zones/ranges stopping the robot. When the Service Mode is activated, all safety monitoring is deactivated (muted). The safety is maintained by not allowing service mode to be active in automatic mode. For safety, the enabling device needs to be pressed for moving the robot. The enabling device is integrated in the FlexPendant.
Axis Speed Supervision	The axis speed supervision function can monitor if the axis speed is too high or too low. If an axis in the supervised system moves over a configured limit then the robot is stopped. If an axis moves too slowly then a signal is set, for example, to indicate that there is a risk for overheating if the axis controls a band going through an oven.
Tool Speed Supervision	The tool speed supervision function can monitor if the tool speed is too high or too low. If a point on the supervised tool system moves over a configured limit then the robot is stopped. If the tool moves too slowly then a signal is set, for example, to indicate that there is a risk for overheating if a laser is mounted on the tool.
Axis Position Supervision	If the robot moves outside the given axis range then the robot is stopped.

Continues on next page

Safety functions	Description
Tool Position Supervision	If the tool on the robot is moved outside a given zone or inside a protected zone then the robot is stopped.
Tool Orientation Supervision	If the tool points in an unsafe direction then a signal is set, for example, if a laser cutter is mounted on the tool.
Stand Still Supervision	If the robot is moving when the function is active then the robot stops or the opposite, when the robot is standing still a signal is set.
Power and force limiting	The power and force limiting function relaxes the diagnostic function <i>Control Error Supervision</i> for making it possible for the robot to be in contact with the work piece. All safety functions are still active but the safety is decreased when the diagnostic tolerance is increased. The Operational Safety Area is only possible to activate in a limited area (zone or range).
Safe disable of drive unit	Safely disables a robot or additional axis by setting it in a state with all brakes applied and servo control switched off.
Parameterization	The parameterization consists the following functions. <ul style="list-style-type: none"> • Configuration of a Safety System • Safety Configuration Integrity Check • Configuration of Zones • Signal Configuration
Hot Swappable FlexPendant	It is possible to remove the FlexPendant while the robot is in automatic mode. This makes it possible to use only one FlexPendant for several robots, where the FlexPendant is only connected occasionally and used for recovering from stops. In manual mode, there is no use of the functionality since it is not possible to do anything with the system without the FlexPendant. The functionality is in therefore deactivated in manual mode.
Monitored stop category 1	The stop category 1 stops the robot using the motors. The safety controller monitors that the stop is performed, that the retardation is above the limit. If the retardation is less than the limit a stop category 0 is triggered. When the robot has stopped, the power to the motors is removed and the brakes are applied.
Fire safety	The control system complies with the requirement of UL (Underwriters Laboratories) for fire safety.

Operating cycles for safety parts

The expected cycles for safety parts are listed below.

Safety part	Cycles
Enabling device	750 000
Emergency stop (FlexPendant)	750 000

2 Safety

2.3 Safety data

2.3 Safety data

Prevailing standards and directives

For the use of industrial robots, regulations must be fulfilled as described in the following standards and directives:

- EN ISO 10218-1:2011
- Machinery Directive 2006/42/EC

Related information

For more detailed information, see the product manual for the robot controller.

3 Installation and maintenance

3.1 Installation

General

The controller is delivered with a standard configuration for the corresponding manipulator, and can be operated immediately after installation. Its configuration is displayed in plain language and can easily be changed using the RobotStudio or the FlexPendant.

3 Installation and maintenance

3.2 Maintenance

3.2 Maintenance

General

The controller requires only a minimum of maintenance during operation. It has been designed to make it as easy to service as possible.

The controller is enclosed, which means that the electronic circuitry is protected when operating in a workshop environment. The only maintenance parts are cooling fans and optional air filters.

See the product manual for the controller for maintenance activities and intervals.

Functions

The robot has several functions to provide efficient diagnostics and error reports.

Function	Detail
Online supervision	CPU temperature
	AC and DC voltage levels
	Power Supply functions
	UPS capacitor status
	All internal communication channels (cables)
	CMOS battery
	Safety chains (two channel supervision)
	Safety chains (function test)
	Safety switches
	Motor temperatures
	Drive system: communication cable, voltage levels, temperatures, motor current and cable, reference quality
	Measurement system: communication cable, resolver function including cables
	Fieldbus cable (communication and power)
	Fieldbus units (connection, status)
	Program execution and resource handling
Power on	Built-in self-test
Fault tracing support	Computer status LEDs
Error message	Displayed in selected language The message includes the reason for the fault and suggests recovery action
Faults and major events are logged and time-stamped.	This makes it possible to detect error chains and provides the background for any downtime. The log can be saved to file or viewed from PC tools like RobotStudio, Robot Web Services or any OPC client application
Manual test	Commands and service programs in RAPID to test units and functions
Properties	Detailed properties of hardware and software in the controller are available for viewing from FlexPendant or RobotStudio

4 Controller system

4.1 Cybersecurity

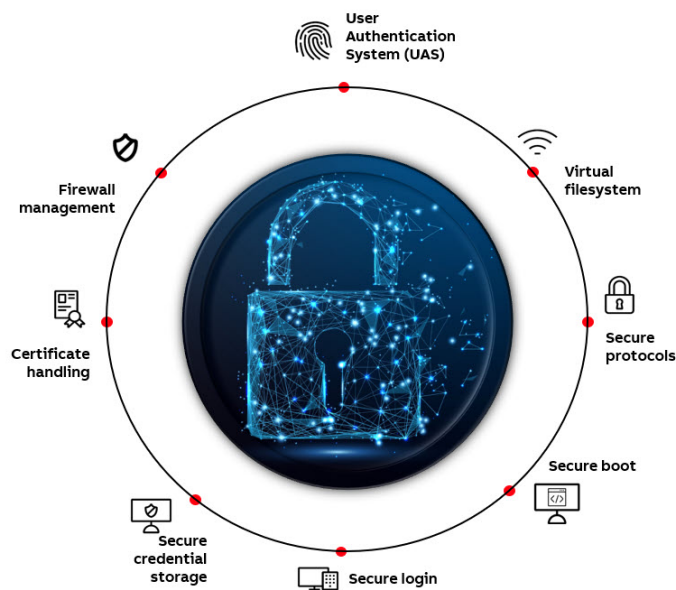
Overview

Cybersecurity approach

OmniCore is developed according to the ABB cybersecurity standards, which include the following processes and features:

- ABB has well-established and governed product and software development processes that serve as the foundation for ABB's Security Development Lifecycle (SDL).
- ABB's Device Security Assurance Center (DSAC) enhances product security and quality through rigorous testing. DSAC ensures the integration of cybersecurity throughout ABB's product lifecycle.

Cybersecurity features



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The OmniCore cybersecurity comprises several combined security features for the protection against threats such as viruses, malware, and other exploits. Some included features are:

- **Certificate handling**
Certificates are used to provide secure communication over the network.
- **Firewall management**
The objective of the firewall management is to protect the OmniCore controller from threats originating in the office network. By defining firewall settings, you can monitor the selection of enabled Network Services.
- **User authentication system**

Continues on next page

4 Controller system

4.1 Cybersecurity

Continued

The User Authentication System (UAS) provides authentication and authorization functionality to the OmniCore controllers.

- **Virtual filesystem**

Access to all top-level folders in the virtual filesystem is managed through grants.

- **Secure protocols**

Secure protocols ensure the security and integrity of data in transit over a network connection. They are primarily designed to prevent any unauthorized user, application, service or device from accessing network data.

- **Secure boot**

A secure boot chain has been implemented in order to ensure that only trusted ABB software is used, thus minimizing the security risks. When the PC starts it validates the digital signatures of the software before executing it.

- **Secure login**

Username and matching password used to enter a specific authorized domain. The username and password are in an encrypted format to ensure secure access.

- **Secure credential storage**

The secure storage functionality is used to store sensitive data (i.e. private keys, credentials etc.), thereby providing confidentiality and integrity for the user.

- **RobotWare Installation Utilities**

RobotWare Installation Utilities provides settings for user and security admin passwords.

4.2 Communication

Ethernet

The controller has several Ethernet channels which can be used at 100 Mbit/s or 1 Gbit/s. The communication speed is set automatically or can be set to a fixed speed.

The communication includes TCP/IP with network configuration possibilities like:

- DNS, DHCP etc.
- Network file system access using SFTP server
- Control and/or monitoring of controllers by Windows applications built with PC SDK
- Boot/upgrading of controller software via the network or a portable PC
- Communication with RobotStudio
- Connected Services

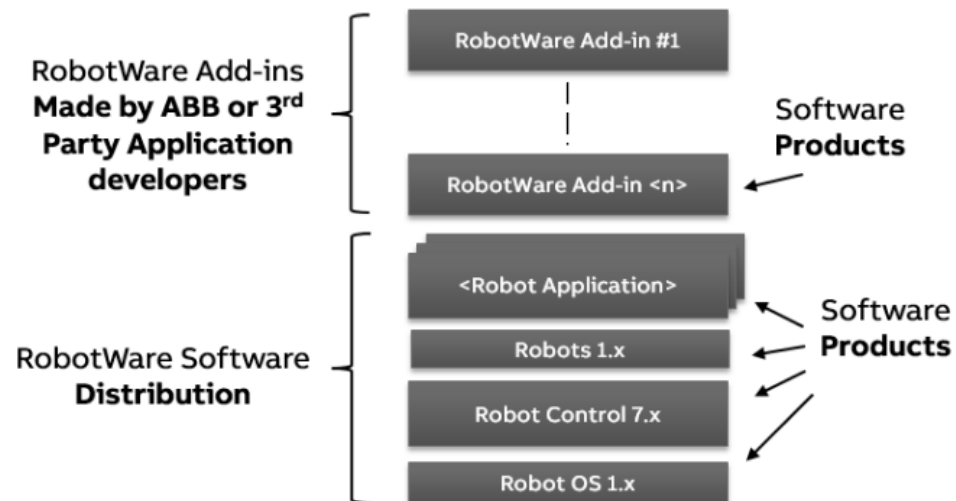
4 Controller system

4.3 RobotWare

4.3 RobotWare

RobotWare 7

RobotWare 7 is the control software platform that runs on the OmniCore controllers. The distribution consists of several software products.



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Standard features of RobotWare

The RobotWare software distribution contains the standard features for robot control, and selected additional software products. The unique motion control in RobotWare together with the built-in high-level programming language RAPID offers a reliable and flexible performance.

See also [Robot motion on page 34](#), [I/O system on page 38](#), [Programming on page 44](#), and [RAPID language and programming environment on page 48](#).

Motion technology

QuickMove 2nd generation	A unique self-optimizing motion control feature that keeps cycle times to a minimum by ensuring maximum acceleration at every moment. ABB robots cycle times are up to 25% shorter than competitors. See QuickMove™ on page 34 .
TrueMove 2nd generation	TrueMove ensures that the motion path followed by the robot is the same as the programmed path regardless of the robot speed. See TrueMove™ on page 34 .
Additional axes	Up to 36 axes can be run from the control system. The robot main axes can be coordinated with external mechanical structures such as work-piece positioners and track-motion devices or gantries. This requires that the controller has additional drive units.
Electronically linked motors	Create robot control master/slave motor configurations to replace mechanical driving shafts in gantries or positioners.
Motion Process modes	Optimize robot behavior based on specific needs, i.e. optimize the performance of the robot for a specific application.
Motion Error Handler	Maintain RAPID execution when motion errors such as collision and singularities occur.

Continues on next page

Programming technology

Error handling	Exceptional robot behavior is ensured through customized error handlers which can be set up to take a certain action depending on error type.
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Communications technology

Robot web services	Programming interface based on HTML5 to communicate with robot from any device, regardless of operating system.
Socket messaging	Allows for the exchange TCP/IP messages over a network for machine-to-machine communication.

Service technology

Remote Service enabled	A robot in need of maintenance will, through wireless technology, alert ABB so we can offer quick support. see Connected Services on page 89 .
Service Information System	Predicts robot service needs. It includes operating time, calendar time and advanced algorithms for calculation of gearbox services.

General technology

User-authorization system (UAS)	The data, functionality, and commands of a controller are protected by the UAS, which defines the access rights for the individual users of the robot controller.
Power failure support	If the power supply is cut off during operation, the robot restarts at the exact same position and system status as before the power failure.
Modify Installation	Managing RobotWare installation and adding new options has never been as hassle free and easy.
Improved jogging response	Manual robot movement, also known as jogging, is more responsive.
Snapshots	Snapshots are used to create a backup of the current system state. The backup also includes all installed software products, user data, and system internal data. This is a useful tool before making changes to or updating the RobotWare system, which makes it easy to restore old systems and enables fast switching between different systems in a flexible production environment.

RobotWare options and application support

RobotWare comes with various application specific support.

Motion performance

Advanced Robot Motion	Functionality for optimizing the robot's motion control and for minimizing path deviation. See Advanced robot motion [3100-1] on page 144 .
Absolute Accuracy	Makes your robot even more precise. Perfect for off-line programming and fast replacements of robots. See Absolute Accuracy [3101] on page 151 .

Motion coordination

MultiMove™	A MultiMove controller that handles several manipulators uses an additional controller per manipulator, that is, a MultiMove installation consists of one main controller and up to two additional controllers. The ABB MultiMove configuration is considered to be one robot.
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Continues on next page

4 Controller system

4.3 RobotWare

Continued

Conveyor tracking	Coordinates the robot motion with a conveyor line. See Conveyor on page 194 .
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Motion functions

World Zones	Defines actions when a robot enters a defined area of the working space. The zones can be used to stop the robot from entering a zone, either permanently or only when another robot is working in the zone. See World Zones [3106-1] on page 155 .
Independent Axis	Makes an additional axis (linear or rotating) run independently of the other axes in the robot system. See Independent Axis [3111-1] on page 166 .
Path Recovery	Stores all system data, when an interrupt occurs (fault message or other) and restores them after necessary actions have been taken. Useful for service interrupts. See Path Recovery [3113-1] on page 169 .
SoftMove	In applications where materials or tools cannot be precisely positioned, the robot can be set to Soft Servo mode, allowing the robot to act like a mechanical spring when encountering resistance from the environment. See SoftMove [3108-1] on page 160 .
Collision Detection	Protects equipment and robot from severe damage. It stops the robot if the motion torque values are exceeded. See Collision detection [3107-1] on page 157 .
Collision Avoidance	Collision Avoidance is a software option that enables the possibility to stop the robot before colliding with fixed objects. See Collision avoidance [3150-1] on page 158 .

Communications

SFTP/FTP and NFS Client	SFTP/FTP/NFS Client makes it possible to read information on a remote hard disk directly from the controller. See Communication on page 172 .
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Engineering tools

Multi-tasking dialog	Run up to 14 RAPID programs simultaneously. Use them for supervision of external equipment, operator or advanced calculations.
Continuous Application Platform	Used for designing continuous path process applications, such as arc welding applications. By using CAP, the development work is much faster and results in robust high performance applications.
Discrete Application Platform	Used for designing discrete point process applications, such as spot-welding applications. By using DAP, the development work is much faster and results in robust high performance applications.
Externally Guided Motion (EGM)	Enables external sensors and controllers to control the robot motion with very fast robot response.

Vision

Integrated Vision interface	Makes the most advanced vision tools an integral part of ABB robots. Enables a variety of applications with minimum experience and programming time. See Vision interface [3127-1] on page 193 .
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Application options

ArcWare	Optimizes the robot for arc welding. The positioning of the robot and the process control and monitoring are handled in one and the same instruction as well as process equipment supervision, error recovery, etc
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SpotWare	This option provides dedicated spot weld instructions for fast and accurate positioning combined with gun manipulation, process start and supervision of the weld equipment.
DispenseWare	This option provides support for different types of dispensing processes such as gluing and sealing.
Prepared for PickMaster	PickMaster application are configurable integration of robots, vision systems and conveyors.
RobotWare Force Control	Allows the robot to be contact force controlled. Typically this is useful in assembly and machining.
RobotWare Machining	This is a set of instructions, which facilitate the use of robots for machining applications.

SafeMove

SafeMove ensures a high safety level in the robot by using supervision functions that can stop the robot. Note that the functional safety options is one component in the safety system of a complete robot cell, normally complemented by other equipment (for example light barriers) for detecting the whereabouts of the operator.

Function	Description
Tool supervision functions	Protects the operator and enhances machine and equipment safety by supervising the position (<i>Tool Position Supervision</i>), speed (<i>Tool Speed Supervision</i>) and orientation (<i>Tool Orientation Supervision</i>) of the tool. For some robots, the tool force can also be supervised (<i>Tool Force Supervision</i>). This function also includes supervision of the axis torque.
Axis supervision functions	Protects the surroundings by supervising the axis position (<i>Axis Position Supervision</i>) and the axis speed (<i>Axis Speed Supervision</i>).
Stand Still Supervision	Supervises the stand-still of robot axes without having to switch the robot to Motors Off. It enables operators to perform tasks in the immediate vicinity of the robot.
Contact application tolerance	Allows the robot to be in contact with the work-piece in limited areas. This can for example be used in applications where the robot is used for grinding or during tool change.
Power and force limiting	Functions for collaborative applications, for example power and force limiting, and support to calculate speed and force.
Cyclic brake check	Supervises that the brakes are checked with a cyclic interval.
Stop functions	Triggers stop of the robot using safe fieldbus inputs from the safety PLC.
Safe Disable of Drive Unit	Safely disables a robot or additional axis by setting it in a state with all brakes applied and servo control switched off.

Some examples of applications:

- Manual loading stations
- Manual workpiece inspection during operation
- Optimization of cell size
- Protection of sensitive equipment
- Ensuring safe orientation of emitting processes

4 Controller system

4.4 Robot motion

4.4 Robot motion

QuickMove™

The QuickMove™ concept means that a self-optimizing motion control is used. The robot automatically optimizes the motion parameters to achieve the best possible performance throughout the cycle - based on load properties, location in working area, velocity, and direction of movement.

- No parameters have to be adjusted to achieve correct path, orientation, and velocity
- Maximum acceleration is always obtained (acceleration can be reduced, for example when handling fragile parts)
- The number of adjustments that have to be made to achieve the shortest possible cycle time is minimized

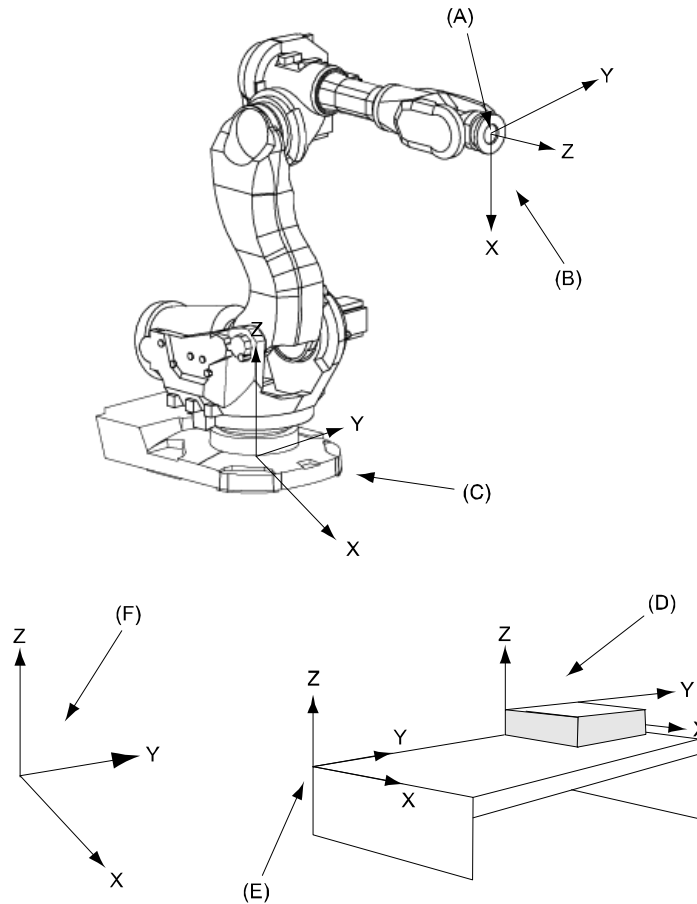
TrueMove™

The TrueMove™ concept means that the programmed path is followed - regardless of the speed or operating mode - even after a safeguarded stop, a process stop, a program stop, or a power failure.

The very accurate path and speed are based on advanced dynamic modelling.

Continues on next page

Coordinate systems



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Pos	Description
A	Tool Center Point (TCP)
B	Tool coordinates
C	Base coordinates
D	Object coordinates
E	User coordinates
F	World coordinates

System	Description
Coordinate systems	RobotWare includes a very powerful concept of multiple co-ordinate systems that facilitates jogging, program adjustment, copying between robots, off-line programming, sensor based applications, additional axes co-ordination etc. Full support for TCP (Tool Center Point) attached to the robot or fixed in the cell ("Stationary TCP").
World coordinate system	The world coordinate system defines a reference to the floor, which is the starting point for the other coordinate systems. Using this coordinate system, it is possible to relate the robot position to a fixed point in the workshop. The world coordinate system is also very useful when two robots work together or when using a robot carrier.

Continues on next page

4 Controller system

4.4 Robot motion

Continued

System	Description
Base coordinate system	The base coordinate system is attached to the base mounting surface of the robot.
Tool coordinate system	The tool coordinate system specifies the tool's center point and orientation.
User coordinate system	The user coordinate system specifies the position of a fixture or workpiece manipulator.
Object coordinate system	<p>The object coordinate system specifies how a workpiece is positioned in a fixture or workpiece manipulator.</p> <p>The coordinate systems can be programmed by specifying numeric values or jogging the robot through a number of positions (the tool does not have to be removed).</p> <p>Each position is specified in object coordinates with respect to the tool's position and orientation. This means that even if a tool is changed because it is damaged, the old program can still be used, unchanged, by making a new definition of the tool.</p> <p>If a fixture or workpiece is moved, only the user or object coordinate system has to be redefined.</p>
Stationary TCP	When the robot is holding a work object and working on a stationary tool, it is possible to define a TCP for that tool. When that tool is active, the programmed path and speed are related to the work object.
Program displacement	If the location of a workpiece varies from time to time, the robot can find its position by means of a digital sensor. The robot program can then be modified in order to adjust the motion to the location of the part.

MultiMove

The purpose of MultiMove is to let one robot controller handle several mechanical units. This allows advanced coordination.

A MultiMove system is a system where one main controller controls up to three manipulators, where the additional 1 or 2 manipulators have their own additional controllers. MultiMove exists in two different modes - Independent and Coordinated. The option *MultiMove Coordinated* makes a robot system a MultiMove system with coordinated manipulators functionality.

The option *MultiMove Independent* makes a robot system a MultiMove system with independent manipulators functionality.

For more details, see *Application manual - MultiMove*.



Note

MultiMove is an option allowing up to three manipulators to be controlled from a single controller. In the context of ISO 10218-1, the ABB MultiMove configuration is considered to be one robot.

A risk assessment, as outlined in ISO 10218-2, shall always be performed on the robot cell.

Continues on next page

Additional features

System	Description
Program execution	<p>The robot can move in any of the following ways:</p> <ul style="list-style-type: none"> • Joint motion (all axes move individually and reach the programmed position at the same time). • Linear motion (the TCP moves in a linear path). • Circle motion (the TCP moves in a circular path).
Soft servo	<p>Soft servo - allowing external forces to cause deviation from programmed position - can be used as an alternative to mechanical compliance in grippers, where imperfection in processed objects can occur.</p> <p>Any motors (also additional) can be switched to soft servo mode, which means that it will adopt a spring-like behavior.</p>
Jogging	<p>The robot can be manually operated in any one of the following ways:</p> <ul style="list-style-type: none"> • Axis-by-axis, that is one axis at a time. • Linearly, that is the TCP moves in a linear path (relative to one of the coordinate systems mentioned above). • Reoriented around the TCP. <p>It is possible to select the step size for incremental jogging. Incremental jogging can be used to position the robot with high precision, since the robot moves a short distance each time the joystick is moved.</p> <p>During manual operation, the current position of the robot and the additional axes can be displayed on the FlexPendant.</p>
Singularity handling	<p>The robot can pass through singular points in a controlled way, that is points where two axes coincide.</p>
Motion supervision	<p>The behavior of the motion system is continuously monitored in regards to position and speed level to detect abnormal conditions and quickly stop the robot if something is not OK. A further monitoring function, Collision Detection, is optional, see option Collision detection [3107-1] on page 157.</p>
Big inertia	<p>One side effect of the dynamic model concept is that the system can handle very big load inertias by automatically adapting the performance to a suitable level. For big, flexible objects it is possible to optimize the servo tuning to minimize load oscillation.</p>
Load identification	<p>The robot can automatically identify the load properties and thus ensures a correct dynamic model of the total arm system. This leads to optimum performance and life time, without need for cumbersome manual calculations or measurements. Load identification is available for most robots, and positioners (IRP). For more information, see <i>Operating manual - OmniCore</i>.</p> <p>It is also possible to tune the parameters in the mounting stiffness to compensate for a non rigid mounting frame.</p>

4 Controller system

4.5 I/O system

4.5 I/O system

Industrial networks and fieldbus

There are options available for different industrial networks.

Option	Description	Number of I/O devices
DeviceNet™	PCIe card certified by ABB included	20
PROFINET IO	Software based	50
EtherNet/IP	Software based	20 (4,049 signals/device)
CC-Link IE Field Basic	Software based	Maximum 16 devices per master.
EtherCAT	Software based	N/A. Only EtherCAT Device is supported.

Multiple industrial networks can be installed and configured in parallel. Two software based masters can be used. Maximum total number of I/O devices is 50.

For all bus types commercially available third party I/O devices can be used.

For more information, see [Industrial networks & fieldbuses on page 97](#).

Number of logical signals

The maximum number of logical signals is 12000 in total for all installed fieldbuses (inputs or outputs, group I/O, analog and digital).

System signals

Signals can be assigned to special system functions such as program start, so as to be able to control the robot from an additional panel or PLC. Several signals can be given the same functionality.



Note

For more information on system signals, see *Technical reference manual - System parameters*.

Digital inputs

- Backup
- Collision Avoidance
- Disable backup
- Enable Energy Saving
- Interrupt
- Limit Speed
- Load
- Load and Start
- Motors Off
- Motors On
- Motors On and Start

Continues on next page

- PP to Main
- ProfiSafeOpAck
- Quick Stop
- Reset Execution Error Signal
- Set Speed Override
- SimMode
- Start
- Start at Main
- Stop
- Stop at End of Cycle
- Stop at End of Instruction
- System Restart
- Trust Revolution Counter
- Verify Local Presence
- Verify Move Robot in Auto
- Write Access

Digital outputs

- Absolute Accuracy Active
- Auto On
- Backup Error
- Backup in Progress
- Collision Avoidance
- Control On State
- Cycle On
- Emergency Stop
- Energy Saving Blocked
- Execution Error
- Limit Speed
- Mechanical Unit Active
- Mechanical Unit Not Moving
- Motion Supervision On
- Motion Supervision Triggered
- Motors Off
- Motors Off State
- Motors On
- Motors On State
- Path Return Region Error
- Power Fail Error
- PP Moved
- Production Execution Error

Continues on next page

4 Controller system

4.5 I/O system

Continued

- Revolution Counter Lost
- Robot In Trusted Position
- Run Chain OK
- SimMode
- Simulated I/O
- SMB Battery Charge Low
- Speed Override
- Stop from client
- System Input Busy
- TaskExecuting
- TCP Speed
- TCP Speed Reference
- Write Access

Analog outputs

- TCP Speed
- TCP Speed Reference

General I/O

The inputs and outputs can be configured to suit your installation.

- Each signal and unit can be given a name, for example *Gripper*, or *Feeder*
- I/O mapping (that is a physical connection for each signal)
- Polarity (active high or low)
- Cross connections
- Up to 32 digital signals can be grouped together and used as a single signal when, for example, entering a bar code
- Sophisticated error handling
- Selectable trust level (that is what action to take when a unit is "lost")
- Program controlled enabling/disabling of I/O units
- Scaling of analog signals
- Filtering
- Pulsing
- TCP-proportional analog signal
- Programmable delays
- Virtual I/O (for forming cross connections or logical conditions without need for the physical hardware)
- Accurate coordination with motion

Manual functions

Manual functions are available to:

- List all the signal values
- Create your own list of your most important signals

Continues on next page

- Manually change the status of an output signal

Scalable I/O

Introduction

Scalable I/O is a modular, compact, and scalable I/O system that consists of a base unit, which is the minimum configuration, and add-on units. Up to four add-on units can be controlled by a base unit with maintained performance (it may be reduced depending on controller variant), and any combination of add-on units are supported.

When using the standard Plug & Produce interface no additional RobotWare options or hardware options are required to connect to the robot controller.

The add-on devices have an optical interface and must be attached to the base device. The additional Ethernet port on the base device can be used to daisy chain any Ethernet based equipment on the same network, for example additional base devices.

The following I/O devices are available:

- Base module with industrial network connectivity, 16 digital inputs, and 16 digital outputs.
- Add-on module with 16 digital inputs and 16 digital outputs.
- Add-on module with 4 analog inputs and 4 analog outputs.
- Add-on module with 8 digital inputs and 8 relay outputs.



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See [Scalable I/O on page 119](#).

Features

- Easy to install.
- Easy to configure in RobotWare with support of the new Plug & Produce interface.
- Compact and scalable.

Continues on next page

4 Controller system

4.5 I/O system

Continued

- Can be mounted inside the controller and/or distributed outside.
- Supports standard DIN-rail mounting.
- Galvanically isolated add-on devices.
- Dual port switch for Daisy chaining.

Digital I/O electrical data

Supply voltage	21-28 V DC
Output current, nominal	500 mA per output, short circuit protected
Input voltage levels	0-5 V digital low 15-30 V digital high
Input current	<0.5 mA

Analog I/O electrical data

Input voltage	0 - +10 V
Output voltage	0 - +10 V
Resolution	12 bit

Relay I/O electrical data

Max voltage	230 V AC per contact
Max current	2 A per contact

Safety digital base device

The safety I/O unit *DSQC1042 Safety Digital Base* is a device that can be used to control and monitor machine safety equipment in a system. The device can be used together with the add-on devices. It uses dual channels, meaning that no undetected single fault can lead to loss of safety functions.

For more information, see *Application manual - Scalable I/O*.

4.6 Memory

DRAM memory

The DRAM memory is used for runtime storage of the system software, volatile data and power fail protected data.

The size and the free space of the DRAM memory can be seen in the window *System Info* on the FlexPendant.

Mass memory

The mass memory is used for permanent storage of firmware, products, system internal data and user data.

The total size and the free space of the mass memory can be seen in the window *System Info* on the FlexPendant.

RAPID memory

The RAPID memory consists of an internal representation of the RAPID programs and data. The memory also contains runtime stacks and data that are needed for the RAPID interpreter.

The RAPID memory is power fail protected and therefore the programs and data do not need to be reloaded after system powered off/on.

The total available memory for user programs can vary depending on the number of installed RobotWare options. The total size of the RAPID memory is statically allocated and will not vary during runtime.

The total size and the free space of the RAPID memory can be seen in the window *System Info* the FlexPendant.

The storage allocated for the programs depends on the type of data and instructions that are used and not on the size of the program files on disk, see [Example of RAPID memory consumption on page 43](#).



Note

RAPID tasks in a Multitasking and MultiMove system share the same memory.

Example of RAPID memory consumption

For details on RAPID memory consumption, see *Technical reference manual - RAPID kernel*.

Introduction	Robtarget marked (*)	Robtarget named
MoveL or MoveJ	312 bytes	552 bytes

4 Controller system

4.7.1 Overview of programming

4.7 Programming

4.7.1 Overview of programming

General

Programming the robot can be done by RAPID programming language and both from the FlexPendant or RobotStudio. Instructions and arguments are picked from lists of appropriate alternatives.

Wizard is a programming application available on the FlexPendant for the small and collaborative robots, see [Wizard programming on page 51](#).

Programming environment

The programming environment can be easily customized:

- Shop floor language can be used to name programs, signals, counters, etc
- New instructions with suitable names can be created
- The most common instructions can be collected in easy-to-use pick lists
- Positions, registers, tool data, or other data, can be created

Programs, parts of programs, and any modifications can be tested immediately without having to translate (compile) the program.

Movements

A sequence of movements is programmed as a number of partial movements between the positions to which you want the robot to move.

End position

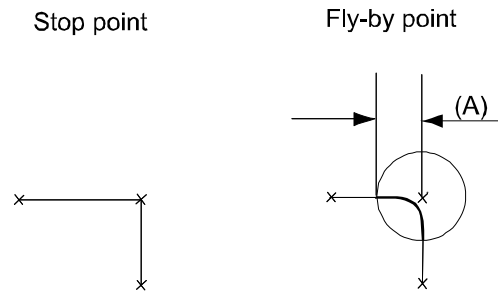
The end position of a movement is selected either by manually jogging the robot to the desired position, by referring to a previously defined position or by defining numeric values.

Position types

A position can be defined either as:

- a stop point, that is the robot reaches the programmed position.
- or a fly-by point, that is the robot passes close to the programmed position. The size of the deviation is defined independently for the TCP, the tool orientation and the additional axes.

Continues on next page



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A	User definable distance (in mm).
---	----------------------------------

Velocity

The velocity may be specified in the following units:

- mm/s
- seconds (time it takes to reach the next programmed position)
- degrees/s (for reorientation of the tool or for rotation of an additional axis)

Program management

When saving a program to disk, the program is a folder containing the program file, and the files that contain the modules. All these files are loaded when loading a program. If needed, other modules can be loaded when executing.

The modules are stored as normal PC text files, which means they can be edited using a standard PC.

Editing programs

Programs can be edited using standard editing commands, that is, cut-and-paste, copy, delete, etc. Individual arguments in an instruction can also be edited using these commands.

A robot position can easily be changed either by:

- jogging the robot to a new position and then pressing *Modify Position* (this registers the new position)
- entering or modifying numeric values

To prevent unauthorized personnel from making program changes, user authorization system can be used.

Testing programs

Several helpful functions can be used when testing programs. For example, it is possible to:

- start from any instruction
- execute an incomplete program
- run a single cycle
- execute forwards/backwards step-by-step
- simulate wait conditions
- temporarily reduce the speed

Continues on next page

4 Controller system

4.7.1 Overview of programming

Continued

- change a position

For more information, see *Operating manual - OmniCore* and *Operating manual - RobotStudio*.

4.7.2 Automatic operation

General

A dedicated production window with commands and information required by the operator is displayed during automatic operation.

The operation procedure can be customized to suit the robot installation by means of user-defined displays and dialogs.

The robot can be ordered to go to a service position when a specific signal is set. After service, the robot is ordered to return to the programmed path and continue program execution.

Special routines

You can also create special routines that will be automatically executed when the power is switched on, at program start and on other occasions. This allows you to customize each installation and to make sure that the robot is started up in a controlled way.

Automatic restore of parameters and I/O at power on

The robot is equipped with absolute measurement, making it possible to operate the robot directly when the power is switched on. For your convenience, the robot saves the used path, program data and configuration parameters so that the program can be easily restarted from where you left off. Digital outputs are also set automatically to the value prior to a power failure if this behavior has been selected.

4 Controller system

4.7.3 RAPID language and programming environment

4.7.3 RAPID language and programming environment

General

RAPID is the primary programming language used for ABB Robotics, designed to facilitate the control and automation of industrial robots. It is a high-level language that is both powerful and user-friendly, making it accessible for both novice and experienced programmers. Its syntax and structure are designed to be intuitive, reducing the learning curve for new users.

RAPID is suitable for a wide range of applications, from simple pick-and-place tasks to complex assembly operations. The language is designed to be reliable and robust, ensuring consistent performance in industrial environments.

Key features of RAPID

RAPID uses a structured text format similar to other programming languages like Python or C, which includes loops, conditionals, and variable handling. It excels in handling complex motion commands, allowing precise control over robot movements.

RAPID supports various data types and operations, enabling efficient data handling and processing. Users can create custom functions and procedures, enhancing the flexibility and adaptability of the programming environment.

It allows seamless communication with external devices and systems, making it ideal for integrated automation solutions.

Overall, RAPID is a versatile and powerful tool that enhances the capabilities of ABB robots, making automation more efficient and accessible.

Summary of the RAPID concept

- Hierarchical and modular program structure to support structured programming and reuse
- Routines can be *Functions* or *Procedures*
- Local or global data and routines
- Data typing, including structured and array data types
- User defined names on variables, routines, and I/O
- Extensive program flow control
- Arithmetic and logical expressions
- Interrupt handling
- Error handling (for exception handling in general, see [Error handling on page 50](#))
- User defined instructions (appear as an inherent part of the system)
- Backward handler (user definition of how a procedure should behave when stepping backwards)
- Many powerful built-in functions, for example mathematics and robot specific
- Unlimited language (no maximum number of variables etc., only memory limited). Built-in RAPID support in user interfaces, for example user defined pick lists, facilitate working with RAPID.

Continues on next page

- Support for Unicode symbols in strings and comments

Ease of use

Creating and editing RAPID programs is done using the integrated code editors in RobotStudio or on the FlexPendant. Additionally, there is an app for the FlexPendant called Wizard, where RAPID programming is further simplified to block programming.

RAPID programs can range from simple movement procedures to complex structures including sending and receiving data from sensors, cameras, I/O devices, other machines, and more. This to enable a highly flexible automation, utilizing the robot's capability.

References

The RAPID programming language is described in detail in the following documents.

What do you want to know	Where to read about it
<ul style="list-style-type: none">• More detailed information about the functionality• What instructions are there for a specific category, for example, move instructions• Descriptions of specific functionality, for example, interrupts or error handling	<i>Technical reference manual - RAPID Overview</i>
<ul style="list-style-type: none">• Information about a specific instruction, function, or data type	<i>Technical reference manual - RAPID Instructions, Functions and Data types</i>
<ul style="list-style-type: none">• Details about how the robot controller handles different parts of RAPID	<i>Technical reference manual - RAPID kernel</i>

4 Controller system

4.7.4 Error handling

4.7.4 Error handling

General

Many advanced features are available to make fast error recovery possible. The error recovery features easily adapt to a specific installation in order to minimize downtime.

Examples

- Error Handlers (automatic recovery often possible without stopping production)
- Restart on path
- Power failure restart
- Service routines
- Error messages: plain text with remedy suggestions, user defined messages
- Diagnostic tests
- Event logging

4.7.5 Wizard programming

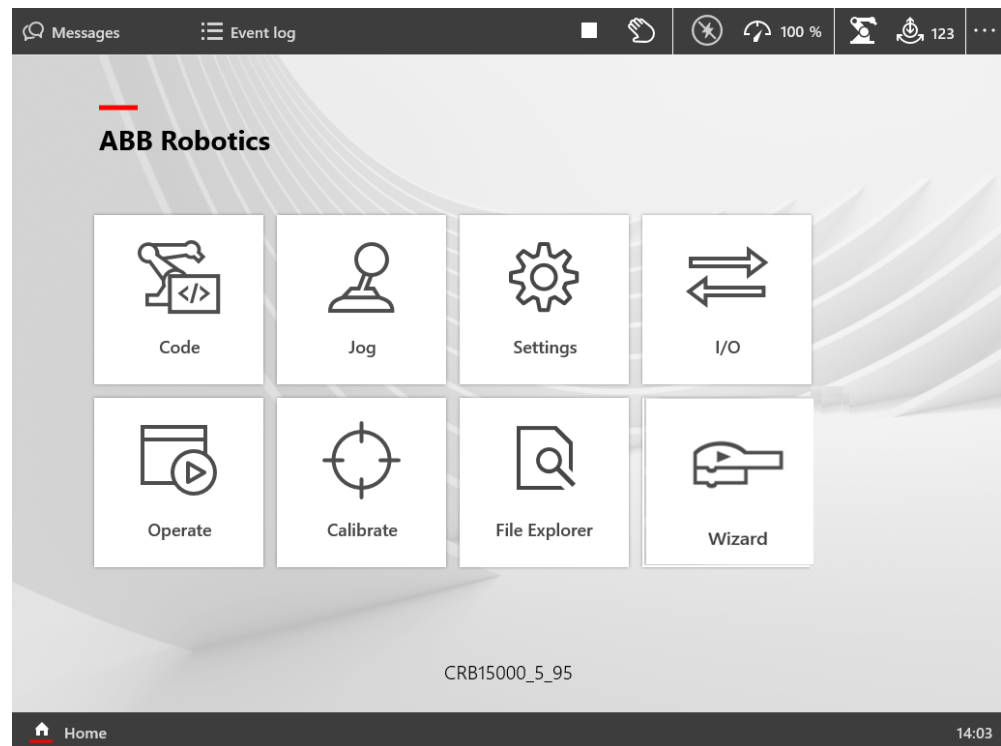
General

The Wizard is an easy programming application on the FlexPendant for GoFa, SWIFTI, and YuMi robots. Wizard provides an easy and interactive programming means, enabling users to program by simply combining visible instruction blocks and setting pre-defined parameters.

It is easy to use by dragging blocky instructions and organizing it, RAPID instructions are generated and downloaded to the controller automatically without need to edit RAPID codes.

The Wizard programming contains the following functions:

- Moving the fingers
- Controlling the fingers and suction cups
- Performing picking and placing
- Working with I/O signals



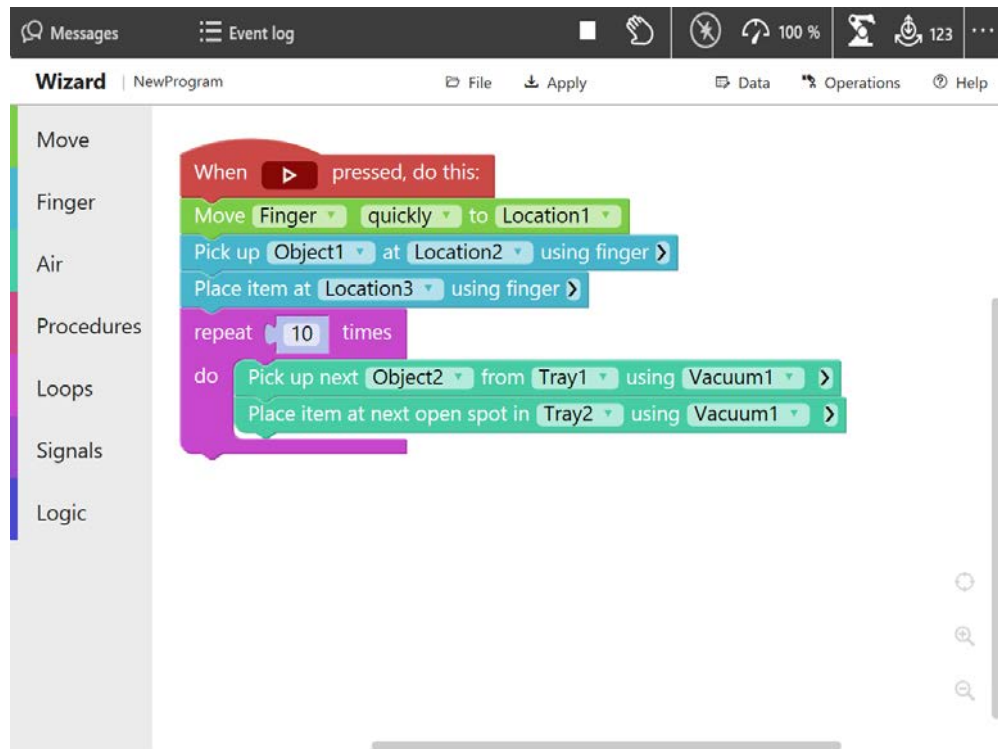
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4 Controller system

4.7.5 Wizard programming

Continued



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The Wizard programming requires the following options for IRB 14050:

- *Collision Detection* [3107-1]
- *Multitasking* [3114-1]

5 Operator interface

5.1 FlexPendant

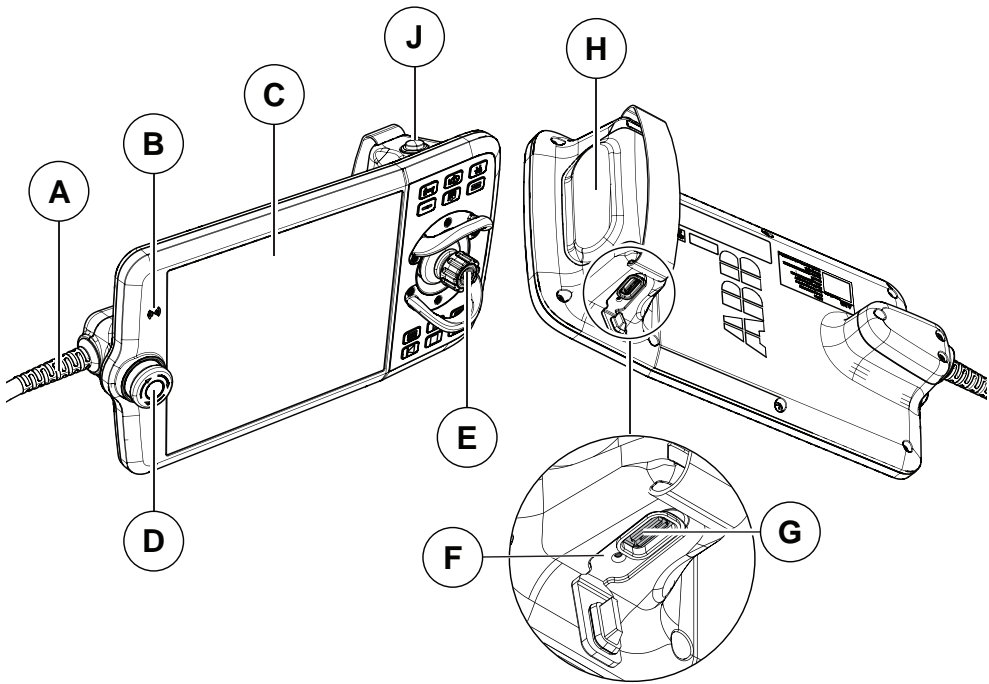
General

The FlexPendant is a handheld operator unit that is used to perform many of the tasks involved when operating a robot system, such as running programs, jogging the manipulator, programming and modifying robot programs, and so on.

The FlexPendant is designed for continuous operation in harsh industrial environment. The touch screen is easy to clean and resistant to water, oil, and accidental welding splashes. The FlexPendant hardware is IP54 rated.

The capabilities of the FlexPendant is dependent on which FlexPendant software options are available.

Main parts of the FlexPendant



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A	Connector
B	RFID reader (functionality not yet implemented)
C	Touchscreen
D	Emergency stop device
E	Joystick
F	Reset button
G	USB port
H	Three-position enabling device

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5 Operator interface

5.1 FlexPendant

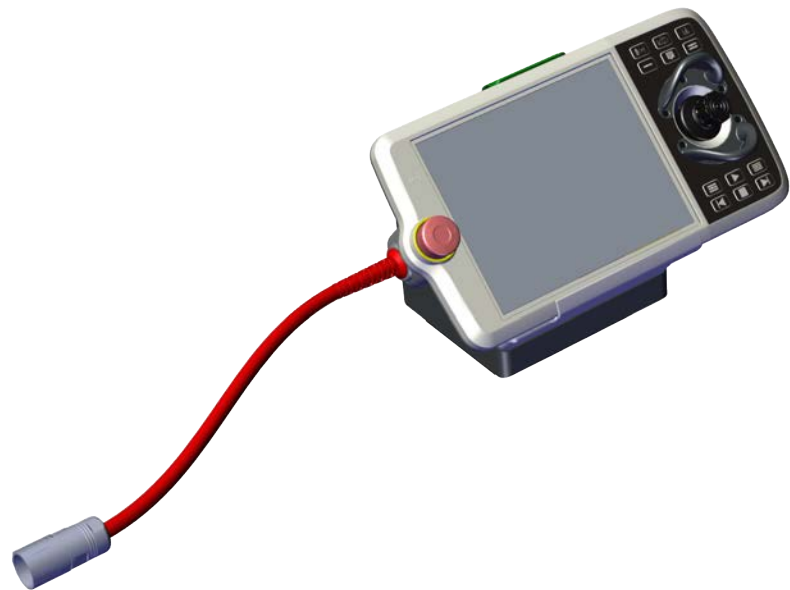
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J	Thumb button. Manual hold to run full speed button ⁱ
ⁱ Functionality not available in all markets.	
Features	Description
Touchscreen display	<p>An 8" color display which displays text as well as graphical information. User input is entered by pressing menu commands, push buttons etc. with the finger or with the supplied stylus on the display.</p> <div> Note</div> <p>If protective gloves are used, these must be compatible with touchscreens when using the FlexPendant.</p>
Manual hold to run full speed button	One of the program execution keys must be pressed continuously when running the program in manual mode with full speed.
Joystick	The 3D joystick is used to jog (move) the robot manually, for example when programming the robot. Large deflections of the joystick will move the robot quickly, smaller deflections will move it more slowly.
Emergency stop button	The robot stops immediately when the button is pressed in.
Left handed users	The display will adapt to left handed users by automatically rotating the display and invert the joystick directions.
IP 54 classification	Protected to dust and splashing of water.

FlexPendant holder

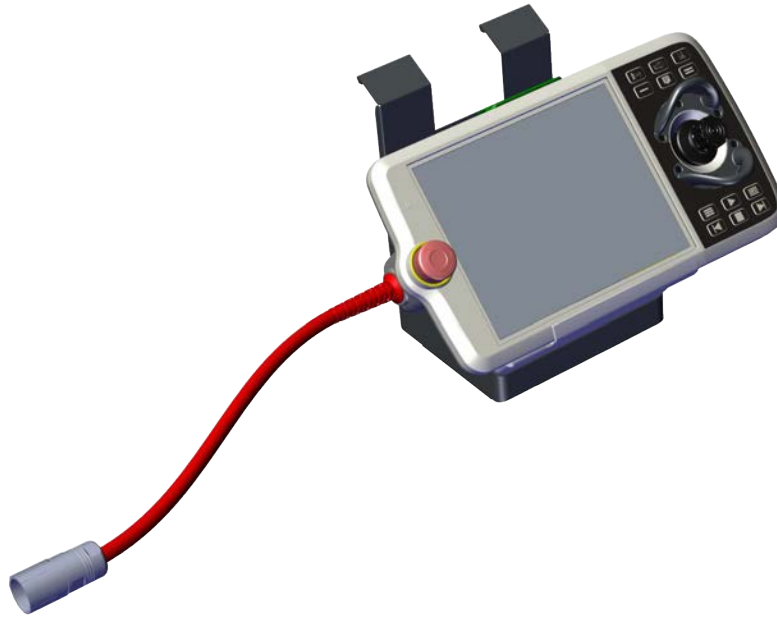
The FlexPendant should always be placed in the holder when it is not used and it is not allowed to use by unauthorized person.

The FlexPendant holder can be split in 2 parts which enables to mount the holder horizontally or vertically. It is possible to hang the FlexPendant holder with the bracket.



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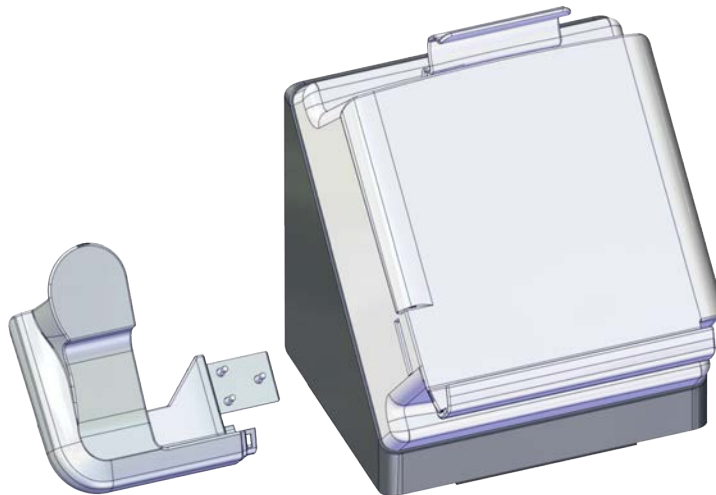
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E-stop cover

The E-stop cover can be mounted by users after risk analysis of the finished production cell. See OmniCore product manual - *Mounting the bracket for the emergency stop on the FlexPendant holder* for more details.



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Continues on next page

5 Operator interface

5.1 FlexPendant

Continued




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FlexPendant options

FlexPendant hardware options are separated from the software options/apps.

Hardware options

Hardware options	Description
3016-x FlexPendant	The FlexPendant hardware device. Available with 3, 10, or 30 meters cable length. Requires option FlexPendant base apps [3120-x]. The options 3016-21/22/23 offer a cable reel with a retractable cable.
3017-x FlexPend ext cable	Extension cables. Available with 15, 22, or 30 meters cable length.  Note The maximum FlexPendant cable length is 52 m.
3018-1 Hot swappable FlexP.	The possibility to remove and attach the FlexPendant during operation. Used to share FlexPendant between several robots. Requires option FlexPendant base apps [3120-x].

See [Human machine interface on page 94](#).

Software options

Software options	
3120-1 Limited App Package	Software to be able to jog, calibrate, operate, and work with basic settings.
3120-2 Essential App Package	Additional features making it easy and efficient working with the robot system. Includes 3120-1 Limited App Package.

Continues on next page

Software options	
3151-1 Program Package	The tools needed for creating new programs and configurations on the FlexPendant.

See [FlexPendant base apps on page 176](#) and [FlexPendant independent apps on page 181](#).

For more information about what functionality is available in the different options, see [FlexPendant applications on page 59](#).

Connecting the FlexPendant

The controller must be in manual mode when connecting the FlexPendant.



CAUTION

Always inspect the connector for dirt or damage before connecting it to the controller. Clean or replace any damaged parts.



CAUTION

Make sure that the emergency stop button is not pressed in when connecting the FlexPendant.

FlexPendant Retractable Cable

The FlexPendant Retractable Cable, FPRC, is an automatic cable winding system for teach pendants. Spring driven, the system is a fast and easy way to maintain a clear and safe work area. Thanks to its spring-loaded retraction system, the FPRC automatically rewinds the teach pendant cable inside the reel.

The cable is available in the following lengths: 4, 10, 20 meters.

The bracket holding the retractable cable unit should be installed in a location that is suitable for your robot cell. ABB does not recommend installing it on the robot controller cabinet.

The size and quality of the attachment screws depend on the installation place.

Continues on next page

5 Operator interface

5.1 FlexPendant

Continued



Note

The retractable cable unit must be installed vertically with the cable outlet at the top and the connection cable to the controller pointing down, see figure.



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5.1.1 FlexPendant applications

The FlexPendant applications

The FlexPendant contains applications for controlling the robot. There are different application packages depending on the options selected for the robot. The *Limited App Package* is always included, unless another app package is selected.

There are more applications available than those listed below. These can be specific for the selected products and options, for example, application software, or applications for controlling grippers and tools.

Code

The **Code** application is used to create new programs, modify existing programs, and so on.

Feature	<i>Limited App Package</i> [3120-1]	<i>Essential App Package</i> [3120-2]	<i>Program Package</i> [3151-1]
Create new programs, edit existing programs			✓
View and edit RAPID modules and RAPID routines			✓
Debug Options PP to main, cursor to program pointer, goto position, call routine, cancel routine, check program, view system data, next move instruction			✓
Teach position (ModPos)			✓
Check for syntactic and semantic error			✓

If the option *Program Package* is not selected then programs must be created and edited using RobotStudio.

Program Data

The **Program Data** application is used to view and edit RAPID data.

Feature	<i>Limited App Package</i> [3120-1]	<i>Essential App Package</i> [3120-2]	<i>Program Package</i> [3151-1]
View and edit RAPID data (program data)			✓
Manage payload data	✓	✓	
Manage tool data	✓	✓	
Manage work object data	✓	✓	

Jog

The **Jog** application is used to jog the ABB industrial robot using an intuitive touch based user interface or using a joystick.

Feature	<i>Limited App Package</i> [3120-1]	<i>Essential App Package</i> [3120-2]	<i>Program Package</i> [3151-1]
Joystick jog	✓	✓	

Continues on next page

5 Operator interface

5.1.1 FlexPendant applications

Continued

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
Touch jog		✓	
Align tool		✓	
Lead-through	✓ ⁱ	✓ ⁱ	
Jog supervision	✓	✓	
GoTo (jog to target)		✓	
3D visualization	✓	✓	

ⁱ Only applicable for compatible manipulators, currently IRB 14050 and CRB 15000.

Settings

The **Settings** application is used to configure the general settings of OmniCore controller and FlexPendant. Controller configuration includes Network, ABB Connected Services, Time and Language, Backup, Restore, System diagnostics and so on. FlexPendant configuration includes background settings and programmable keys.

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
System About, hardware devices, software resources	✓	✓	
Network Status, WAN settings, DNS Client	✓	✓	
ABB Connected Services Status, Connected Services status, configure 3G/WiFi/wired Status, Connected Services status, configure 4G/3G/Wi-Fi/wired	✓	✓	
Configure Connected Services	✓	✓	
Backup and Recovery Backup, restore, system diagnostics, restart, reset user data, RobotWare Installation Utilities	✓	✓	
Date & time	✓	✓	
Region & language	✓	✓	
Programmable keys	✓	✓	

I/O

The **I/O** application is used to manage the I/O signals. Signals are configured with system parameters.

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
Show industrial networks	✓	✓	
View all I/O signals	✓	✓	

Continues on next page

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
Display I/O signals with respect to category	✓	✓	
Filter signals	✓	✓	
Sort signals	✓	✓	
Set signals	✓	✓	
Bit values	✓	✓	
Navigate to device specific signals	✓	✓	
Identify device	✓	✓	
Scan EDS	✓	✓	
Activate and deactivate devices	✓	✓	
Start	✓	✓	
Scan	✓	✓	
Firmware upgrade	✓	✓	

Operate

The **Operate** application is used to view the program code while the program is running. Controller data can be configured for viewing the data in the form of dashboards. Updates during production are shown here.

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
View dashboards		✓	
Configure dashboards		✓	
Load and execute RAPID programs	✓	✓	
View loaded RAPID programs	✓	✓	
Teach position (ModPos) of robot targets in loaded RAPID programs	✓	✓	
Reset program pointer to Main	✓	✓	
Show program pointer position	✓	✓	
Show motion pointer position	✓	✓	
Execute service routines	✓	✓	

Calibrate

The **Calibrate** application is used for calibration and definition of frames for ABB robots.

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
Mechanical unit calibration	✓	✓	
Update revolution counters	✓	✓	
Edit motor offset values	✓	✓	
Load motor offset values	✓	✓	

Continues on next page

5 Operator interface

5.1.1 FlexPendant applications

Continued

Feature	Limited App Package [3120-1]	Essential App Package [3120-2]	Program Package [3151-1]
Fine calibration	✓	✓	
Robot memory	✓	✓	
Base frame calibration	✓	✓	
Execute calibration specific service routines	✓	✓	

File Explorer

The File Explorer is a file manager, similar to Windows Explorer, with which you can view, rename, delete, or move files and folders on the controller or on a connected external USB memory.

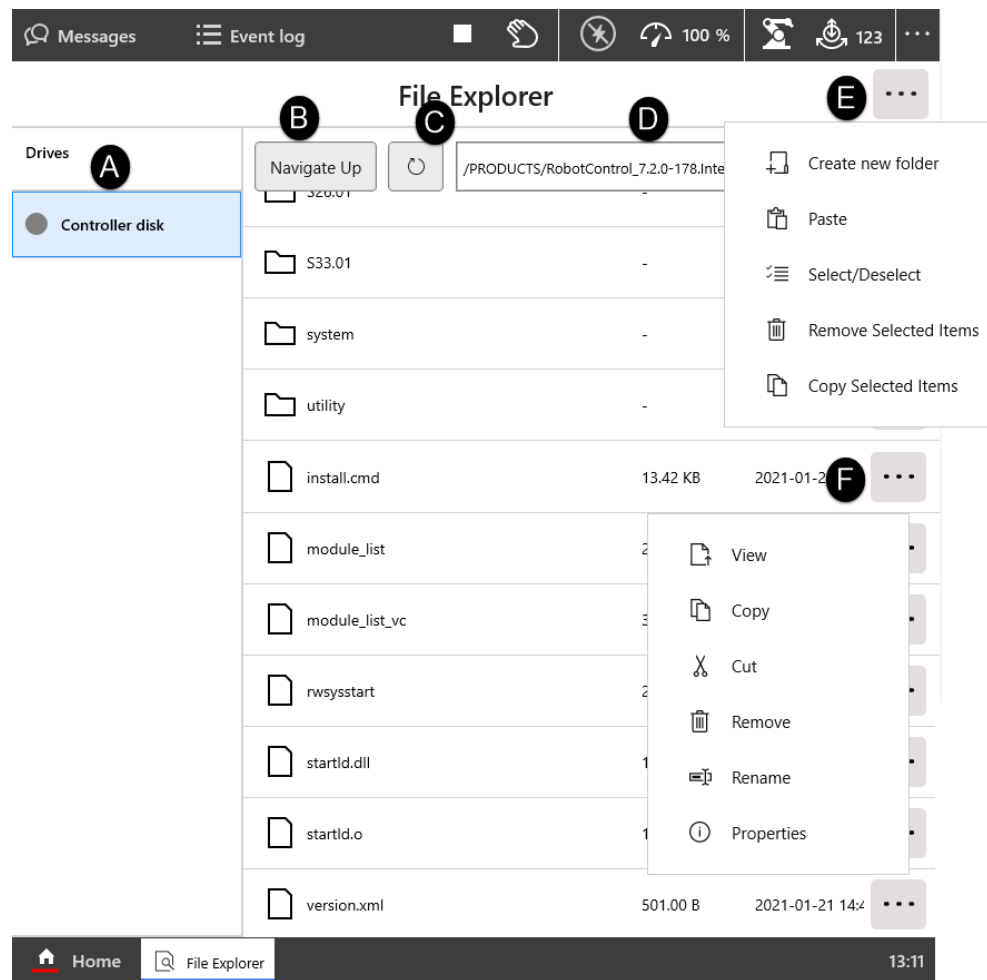


Note

The file explorer supports operations on the following file formats: TXT, CFG, PNG, XML, ZIP, JPG, MOD, PGF, LOG, and MODX.

To manage files and folders, from the Home screen, open **File Explorer**. The file explorer window is displayed. The following image and table provides information regarding the functions available in the file explorer window.

Continues on next page



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Label	Description
A	Displays the available drives. If a USB memory is connected to the FlexPendant that is also displayed here.
B	Navigates to the folder up by one level.
C	Refreshes the files and folders.
D	Displays the path of the selected folder.
E	Displays the options available for a selected folder. <ul style="list-style-type: none"> • Create new folder: Creates a new folder in the selected folder. • Paste: Pastes the copied files or folders in the selected folder. • Select/Deselect: Selects or clear the selection for a set of files and folders. • Remove Selected Items: Removes the selected items. • Copy Selected Items: Copies the selected items.
F	Displays the options available for a selected item. <ul style="list-style-type: none"> • View: Allows you to view the selected text or picture files. • Copy: Copies the selected item. • Cut: Cuts the selected item. • Remove: Deletes the selected item. • Rename: Changes the name of the selected item. • Properties: Displays the properties of the selected item.

Continues on next page

5 Operator interface

5.1.1 FlexPendant applications

Continued



Note

The following grants are required for full access to controller disk:

- **Read access to controller disks**
- **Write access to controller disks**

Without the **Read and Write access to controller disks** grant you may get access to some folders in controller disk like `/TEMP` but not all of them.

While moving the file and folders following are the possible scenarios:

- Moving files and folders within the controller disk.
- Moving files and folders from controller to USB memory and vice versa.



Note

It is not possible to move or copy files and folders within a USB memory.

SafeMove

The application **SafeMove** is used to configure some parts of SafeMove. See *Application manual - Functional safety and SafeMove*. For full SafeMove configuration, see *Visual SafeMove* in RobotStudio.

Web apps

Web apps running on the FlexPendant use the EdgeHTML web engine by default. It is possible to change to Chromium web engine from **Settings > FlexPendant > Web App Mode**.

5.2 RobotStudio

Overview

RobotStudio is a PC application for working efficiently with controller data. RobotStudio can be seen as a companion to the FlexPendant, where the two complement each other and each is optimized for its specific tasks. By exploiting the benefits of this powerful combination, an efficient way of working can be achieved.

The FlexPendant is primarily intended for jogging, teach-in, operation, and touch-up, whereas RobotStudio is ideal for dealing with configuration data, program management, online documentation, and remote access.

RobotStudio acts directly on the active data in the controller. Connection to the controller can be made locally through the service PC connection and, if the controller is equipped with the RobotWare option *RobotStudio Connect [3119-1]*, over a network connection.

The mastership handling system ensures that RobotStudio can only take control of a robot if this is acknowledged from the FlexPendant in manual mode.

The main entry to the functionality of RobotStudio is a robot view explorer. From this you select which robot to work with, in case you have several robots installed, and what parts of the system you want to work with.

RobotStudio basic delivery contains:

- The **Modify Installation** function for creating, installing, and maintaining systems
- A *Configuration Editor* for editing the system parameters of the running system
- A *Program Editor* for online programming
- An *Event Recorder* for recording and monitoring robot events
- Tools for backing up and restoring systems
- An administration tool for user authorization (UAS)
- Other tools for viewing and handling controller and system properties

Access to the full scope of RobotStudio as a powerful off-line programming and simulating tool is ordered separately.

See *Operating manual - RobotStudio* for detailed information.

Configuration Editor

Use the Configuration Editor to make easy and controlled changes of system parameters on a running system.

From the configuration editor you view and edit the system parameters of a specific topic in a controller. The Configuration Editor has direct communication with the controller. This means that changes apply as soon as you complete the command.

For some parameters, however, a restart is required in order for the change to take effect, in which case you will be notified of this.

Continues on next page

5 Operator interface

5.2 RobotStudio

Continued

Program Editor

With the Program Editor you view and edit programs loaded into the controller's program memory. The Program Editor has built in functionality for making it easier to write the RAPID code when programming a robot.

Event Recorder

With the Event Recorder you can view and save events from controllers in your robot view. You can start one Event Recorder for each controller.

Miscellaneous

RobotStudio has a number of other useful tools, for example:

- Backing up and restoring systems
- Administration tool for User Authorization
- Other tools for viewing and handling controller and system properties, for example monitoring of I/O signals

6 ABB Connected Services

General

ABB Connected is a suite of solutions that provide advanced analytics and proactive, actionable data to optimize and fine-tune performance, to ensure reliability from single robots to entire fleets of robots deployed across several factories.



Note

ABB Connected Services is the new name for the functionality previously known as ABB Ability. During a period of time, both names will appear in and on our products.

All new ABB robots come with a secure and encrypted connection via Ethernet, WiFi, or 3G/4G, between robots controller and ABB Connected Services cloud to ensure optimal customer data and network security.



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7 Specification of controller & RobotWare options

General

The available options for the controller and for the RobotWare are described in this section.

For details about manipulator options, see the product specification for the respective manipulator.

Continues on next page

7 Specification of controller & RobotWare options

7.1.1.1 OmniCore V250XT [3000-310]

7.1 Controller

7.1.1 Controller variant

7.1.1.1 OmniCore V250XT [3000-310]

General

OmniCore V250XT Type B is a versatile controller in OmniCore V line with protection class IP54.

The main objective for this controller is to meet the need for a compact solution for general industry paint, polishing, material handling, machine tending applications, and other applications with requirements for high IP protection class for small robots or relatively power intensive low voltage robots.

Specific characteristics

- Support for manipulators up to IRB 67x0
- Up to three additional drive units
- 15 liter optional space inside

See more details in [OmniCore V line on page 13](#).

Standalone controller

It is possible to order the controller without a manipulator, also known as a standalone controller.

Requirements

A standalone controller must be configured for a specific manipulator to assure the correct configuration of power module, drive module etc.

Limitations

The available options depend on what robot and controller variant is selected. It will not be possible to order externally mounted equipment apart for the motor connection box and associated cables.

7.1.1.2 OmniCore V400XT [3000-410]

General

OmniCore V400XT is a versatile controller in OmniCore V line with protection class IP54.

The main objective for this controller is to meet the need for a compact solution for general industry paint, polishing, material handling, machine tending applications, and other applications with requirements for high IP protection class for robot sizes up to IRB 8700 or relatively power-intensive low voltage robots.

Specific characteristics

- Support for manipulators up to IRB 8700
- Up to six additional drive units
- 50 liter optional space inside

See more details in [OmniCore V line on page 13](#).

Standalone controller

It is possible to order the controller without a manipulator, also known as a standalone controller.

Requirements

A standalone controller must be configured for a specific manipulator to assure the correct configuration of power module, drive module etc.

Limitations

The available options depend on what robot and controller variant is selected. It will not be possible to order externally mounted equipment apart for the motor connection box and associated cables.

7 Specification of controller & RobotWare options

7.1.2.1 Status LEDs at front [3053-1]

7.1.2 Status LEDs at front

7.1.2.1 Status LEDs at front [3053-1]

General

With the option *Status LEDs at front* the robot controller will be delivered with an HMI panel indicating the status of the controller. With this option you can easily detect the overall status without opening the door or checking the FlexPendant.



xx2400000615

- The Auto LED indicates if the robot controller is in automatic mode.
- The Attention LED indicates if a fault is detected.
- The Ready LED indicates if the system is in **Motors ON** or **Motors OFF** state.
- The Emergency LED indicates if the robot is in E-STOP status.

7.1.3 Wheels

7.1.3.1 Wheels [3011-1]

General

With the option *Wheels* the robot controller will be delivered with a set of wheels.



xx2400000618



Note

The inner dimensions between the cabinet feet is slightly smaller with the wheel option.

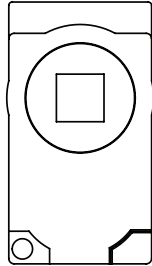
7 Specification of controller & RobotWare options

7.1.4 Door lock

7.1.4 Door lock

Square 6 mm [3012-1]

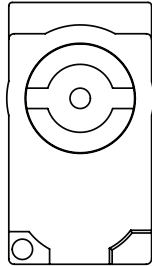
The option *Square 6 mm* [3012-1] is the default lock variant for OmniCore.



xx2400000118

Double bit 3 [3012-2]

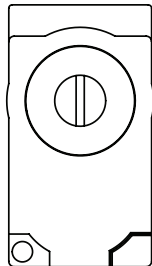
The following lock insert is used for the option *Double bit 3* [3012-2]:



xx2400000119

Slot 1, 2 x 3 [3012-3]

The following lock insert is used for the option *Slot 1, 2 x 3* [3012-3]:

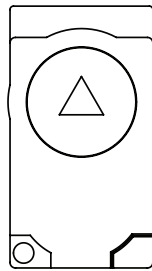


xx2400000120

Triangular 6,5 CNOMO [3012-4]

The following lock insert is used for the option *Triangular 6,5 CNOMO* [3012-4]:

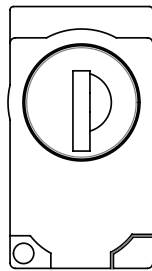
Continues on next page



xx2400000121

Cylinder with key [3012-6]

The following lock insert is used for the option *Cylinder with key* [3012-6]:



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7 Specification of controller & RobotWare options

7.2.1.1 Max 45deg [3004-1]

7.2 Environment

7.2.1 Operating temperature

7.2.1.1 Max 45deg [3004-1]

General

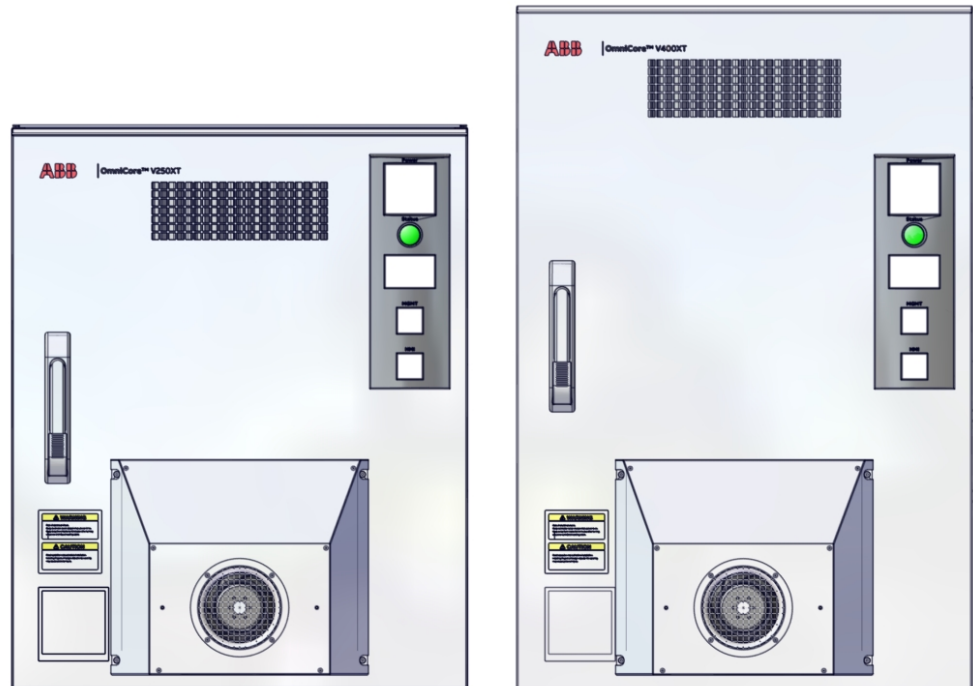
The option *Max 45deg* [3004-1] allows room temperature up to 45°C.

7.2.1.2 Max 52deg [3004-2]

General

The option *Max 52deg* [3004-2] allows room temperature up to 52 °C.

This option includes a door with extra fans and cooling flanges.



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7 Specification of controller & RobotWare options

7.2.2 Cooling air filter

7.2.2 Cooling air filter

General

The air filter module prevents particles from entering air ducts thereby protecting fans and preventing build-up of debris on the drive and power supply heat exchangers, which could reduce the cooling efficiency.

A coarse or fine filter may be fitted depending on the level of ambient dust.

The air filter module is a serviceable item and should at such come in few variants that are easily replaced by a service technician. The design of the air filter makes it easy to maintain.

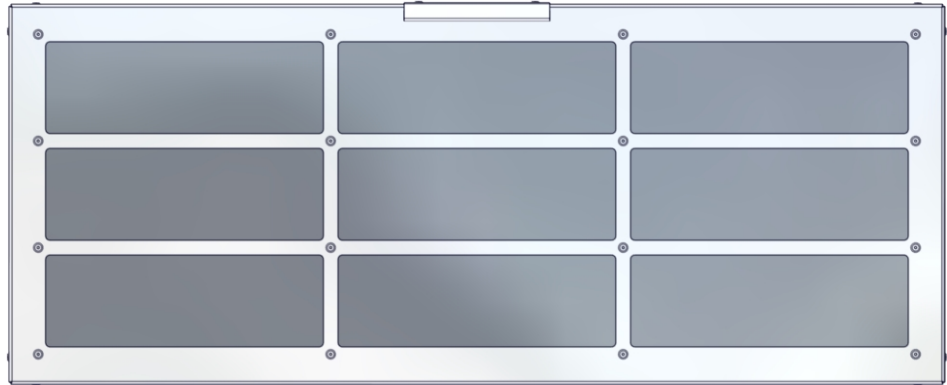
The air filter module is available in the two variants: *Moist particle filter* and *Moist dust filter*.

Continues on next page

7.2.2.1 Moist particle filter [3005-1]

General

Moist particles are prevented from entering the air ducts and fans by metal mesh filter. Select when cooling air contains moist particles > 0.5 mm.



xx2500000063



Note

For controllers with option *3004-2 Max 52deg*, an air filter for the heat exchanger is also included.

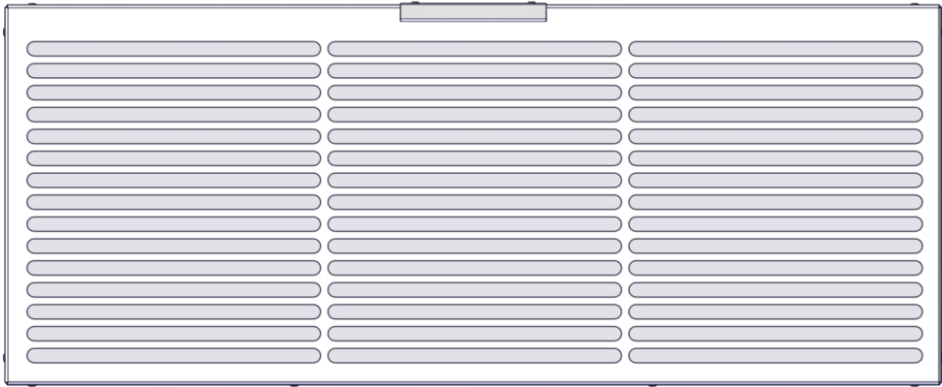
7 Specification of controller & RobotWare options

7.2.2.2 Moist dust filter [3005-2]

7.2.2.2 Moist dust filter [3005-2]

General

Moist particles are prevented from entering the air ducts and fans by polymeric filter. Select when cooling air contains moist dust.



xx2500000064



Note

For controllers with option *3004-2 Max 52deg*, an air filter for the heat exchanger is also included.

7.3 Regional & installation options

7.3.1 Standards

7.3.1.1 UL/CSA [3006-1]

General

The robot and the control system are certified by Underwriters Laboratories to comply with the Safety Standard ANSI/UL 1740 *Industrial Robots and Robotic Equipment* and CAN/CSA Z 434. Law for UL/CSA certification is required in some US states and Canada.

UL (UL listed) means certification of the complete robot product. The option is visualized by a "UL" label attached to the cabinet.

Limitations

This option cannot be used together with the option *MultiMove*.

This option cannot be used together with the option *Wake-on-LAN*.

This option cannot be used together with the options for spot welding DressPack.

7 Specification of controller & RobotWare options

7.3.2.1 380-480 V 3~ ($\pm 10\%$) [3007-3]

7.3.2 Mains voltage

7.3.2.1 380-480 V 3~ ($\pm 10\%$) [3007-3]

General

OmniCore V line controller can be connected to a rated voltage between 380 V and 480 V.

7.3.3 Maximum robot power supply

7.3.3.1 Additional robot power [3079-1]

General

The option *Additional robot power* gives you a power unit (DSQC3070 or DSQC3069A) that allows the usage of more than one additional drive units.

Requirements

The option *Additional robot power* [3079-1] is required when two or more additional drive units are used, option *Additional drive units* [3062-1]. For more information, see [Additional axis on page 134](#).

The option *Additional robot power* [3079-1] is required for IRB 8700.

7 Specification of controller & RobotWare options

7.3.4.1 Cable gland [3008-1]

7.3.4 Mains connection type [3008]

7.3.4.1 Cable gland [3008-1]

General

The customer power cable is routed via the cable gland through a pipe up to the mains switch. Protective grounding PE (green/yellow cable) is connected directly to structure.



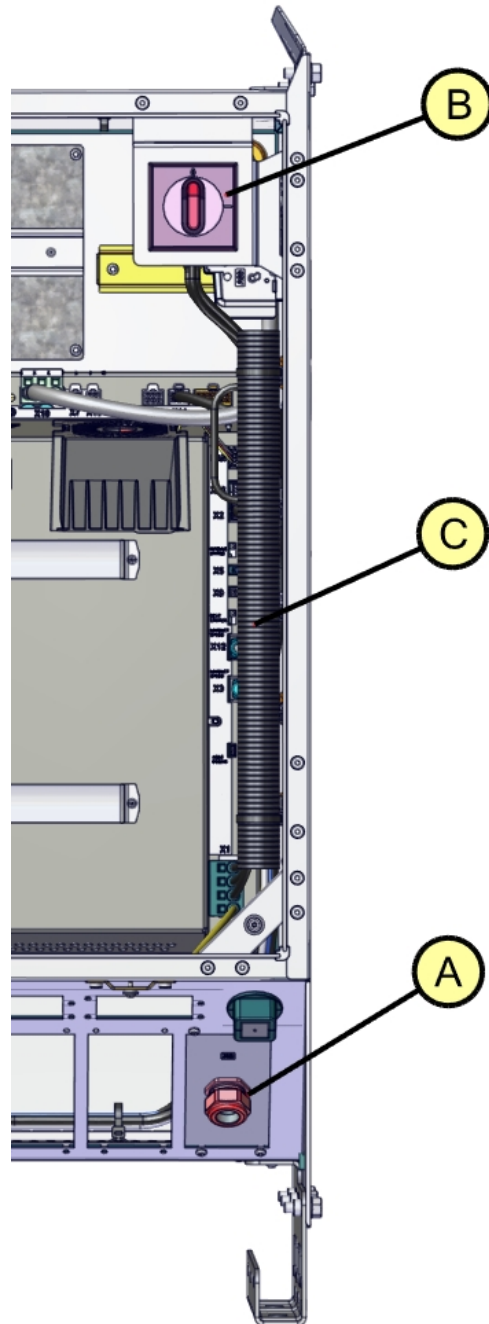
Note

Basic option - no connector means low cost.



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Continues on next page



xx2100002286

A	Cable gland
B	Incoming mains switch
C	Cable pipe

7 Specification of controller & RobotWare options

7.3.4.2 Connector [3008-2]

7.3.4.2 Connector [3008-2]

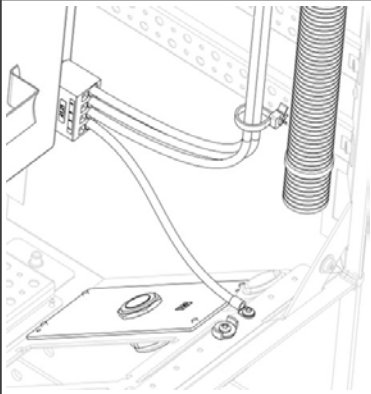
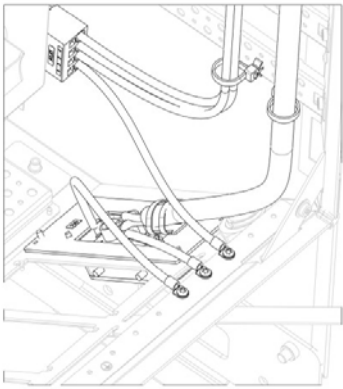
General

Select when a quick power connection in cabinet end is desired, this option saves installation time and time for replacing cabinet.

The customer cable connector (Harting) is included. Compared to 3008-1 the internal cable is already routed to the mains switch inside the cabinet.



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Cable gland [3008-1]	Connector [3008-2]
 <p>xx2100002511</p>	 <p>xx2100002512</p>

7.3.4.3 Connector/fuse [3008-3]

General

Select when a quick power connection in cabinet end is desired, this option saves installation time and time for replacing cabinet.

The customer cable connector (Harting) is included. Compared to 3008-1 the internal cable is already routed to the mains switch inside the cabinet.



Note

Includes integrated circuit breaker rated for selected Robot mains current.



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7 Specification of controller & RobotWare options

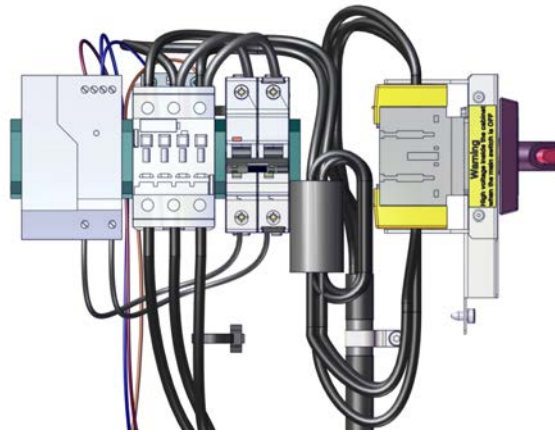
7.3.5.1 Wake-on-LAN3# V-line [3071-2]

7.3.5 Hibernate mode

7.3.5.1 Wake-on-LAN3# V-line [3071-2]

General

With the option *Wake-on-LAN3# V-line*, the controller is equipped with the hardware needed in order to use the *SLEEP WOL* energy saving mode in PROFlenergy. The Wake-on-LAN kit includes the DSQC1104 power supply unit, a miniature circuit breaker, a contactor and harness.



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SLEEP WOL energy saving mode

With the *SLEEP WOL* energy saving mode, the robot controller is set to sleep and waits to receive a wake up request. All energy enabled devices that are managed by the internal PROFINET controller will be paused during this sleep. Recommended pause time is ≥ 60 minutes. See *Application manual - PROFINET Controller/Device* for more information.

Requirements

The option *Wake-on-LAN3# V-line* [3071-2] requires option *PROFlenergy* [3021-1]. For more information, see [PROFINET on page 97](#).

Limitations

The option *Wake-on-LAN3# V-line* [3071-2] cannot be combined with the options *MultiMove Additional robot* [3102-3] or *Connector/fuse* [3008-3].

7.4 Connectivity & logical power

7.4.1 Connected Services

General

ABB Ability™ Connected Services provide communication capabilities between robots controller and ABB.

The connectivity can be directed securely through an embedded, wired, Connected Services.

Wired LAN [3013-1]

The option *Wired LAN* for Connected Services uses a wired connection for transferring data.

WiFi [3013-2]

The option *WiFi* for Connected Services uses a WiFi connection for transferring data.

Mobile network 4G EU [3013-5]

The option *Mobile network 4G EU* for Connected Services uses a 4G mobile network connection for transferring data.

The 4G EU gateway is supported in all European countries, including UK.

ABB sim card is included in the gateway. No customer sim card is required.

Mobile network 4G US [3013-6]

The option *Mobile network 4G EU* for Connected Services uses a 4G mobile network connection for transferring data.

The 4G US gateway is supported in USA and Canada.

ABB sim card is included in the gateway. No customer sim card is required.

Mobile network 4G CN [3013-7]

The option *Mobile network 4G CN* for Connected Services uses a 4G mobile network connection for transferring data.

The 4G CN gateway is supported in China.

ABB sim card is included in the gateway. No customer sim card is required.

No connected services [3013-99]

The option *No connected services* is selected when no connection to Connected Services is requested.

7 Specification of controller & RobotWare options

7.4.2.1 5 port Ethernet switch [3014-1]

7.4.2 Ethernet switch

7.4.2.1 5 port Ethernet switch [3014-1]

General

The option *5 port Ethernet switch* can be used to connect for example *Conveyor Tracking* modules, *Integrated Vision* cameras, *Scalable I/O* units or other devices from the ABB EcoSystem, such as Grippers.

The Ethernet switch cannot be used for fieldbus options like PROFINET, and does not have a PROFINET certification.

7.4.3 Additional logic 24V power

7.4.3.1 24V 4Amps [3015-2]

General

4A selected due to application/process.



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7 Specification of controller & RobotWare options

7.4.3.2 24V 20Amps [3015-3]

7.4.3.2 24V 20Amps [3015-3]

General

Additional 24V 20Amps power supply for customer use.



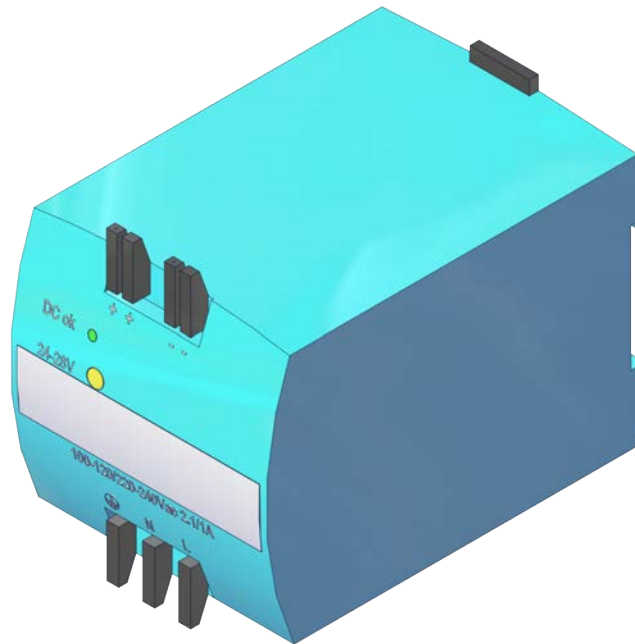
xx2400000732

7.4.4 DeviceNet logic 24V power

7.4.4.1 24V 4Amps [3049-1]

General

24V power supply for customer use. One 4Amp unit certified for ODVA (DeviceNet). It is only needed for supply of external DeviceNet devices.



xx2000000350

Limitations

The option *DeviceNet logic 24V 4Amps* is not possible to order with:

- Option *Additional logic 24V Power* [3015-x]

7 Specification of controller & RobotWare options

7.5.1 FlexPendant

7.5 Human machine interface

7.5.1 FlexPendant

FlexPendant [3016]

Color graphic teach pendant with touch screen of resolution 1024 x 768 px.

For more information, see [FlexPendant on page 53](#).

Option	Description
3016-2	FlexPendant 10m
3016-3	FlexPendant 30m
3016-21	FP retractable 4m
3016-22	FP retractable 10m
3016-23	FP retractable 20m



Note

If ordering the *FlexPendant Retractable Cable*, options 3016-2x, then the cable is not connected to the FlexPendant on delivery.

Requirements

The option *FlexPendant* requires option *FlexPendant base apps* [3120-x]

For more information, see [FlexPendant base apps on page 176](#).

7.5.2 FlexPendant extension

FlexPend ext cable [3017]

Option	Description
3017-1	FlexPend ext cable 15m
3017-2	FlexPend ext cable 22m
3017-3	FlexPend ext cable 30m

Limitations

The total cable length when order *FlexPendant* [3016-x] together with *FlexPendant extension* [3017-x] is less than or equal to 52m.

7 Specification of controller & RobotWare options

7.5.3 Hot swappable FlexPendant [3018-1]

7.5.3 Hot swappable FlexPendant [3018-1]

General

With the option *Hot swappable FlexPendant [3018-1]* it is possible to detach and attach the FlexPendant from an OmniCore controller in automatic mode, without interrupting the ongoing process.

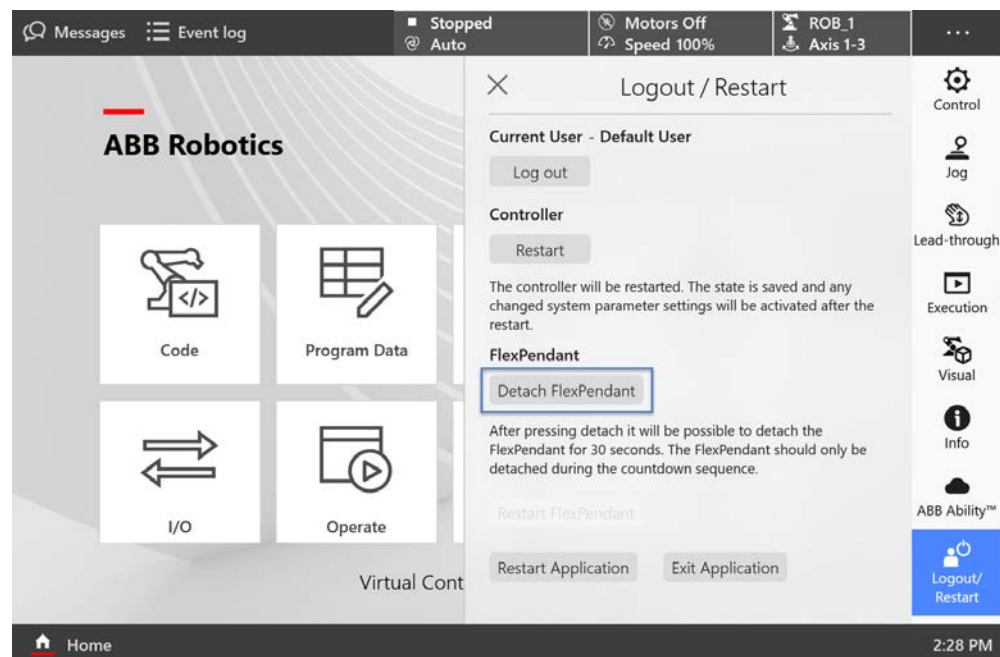
This option is required if the option *FlexPendant [3016-x]* is not selected.

This allows for the following, but not limited to, use cases:

- Avoid damage due to accidental wear (tripping, falling to the ground), when the FlexPendant is not used.
- Avoid damage to the FlexPendant in harsh environment.
- Avoid unintentional user interaction in automatic mode.
- Reusing one FlexPendant on several robots.



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xx1800003667

Requirements

The option *Hot swappable FlexP.* requires option *FlexPendant base apps [3120-x]*

For more information, see [FlexPendant base apps on page 176](#).

7.6 Industrial networks & fieldbuses

7.6.1 PROFINET

7.6.1.1 PROFINET Controller [3020-1]

General

PROFINET is an open standard for Industrial Ethernet. PROFINET satisfies requirements for automation technology. PROFINET solutions can be implemented for factory and process automation, for safety applications, and for the entire range of drive technology right up to clock-synchronized motion control.

PROFINET has a modular design and different PROFINET communication profiles are all combinations of modular elements from the groups transmission technology, communication protocol, and application profiles.

With this option the robot controller can only act as a PROFINET controller on the PROFINET network.

7 Specification of controller & RobotWare options

7.6.1.2 PROFINET Device [3020-2]

7.6.1.2 PROFINET Device [3020-2]

General

With this option *PROFINET Device* the robot controller can only act as a PROFINET device with 256 byte inputs and 256 byte outputs on the PROFINET network.

7.6.1.3 PROFlenergy [3021-1]

General

PROFlenergy is a profile of the PROFINET communications protocol that allows the power consumption of automation equipment in manufacturing (such as robot assembly cells, laser cutters and sub-systems such as paint lines) to be managed over a PROFINET network. It offers an open and standardized means of controlling energy usage during planned and unplanned breaks in production.

Requirements

Requires option PROFINET [3020-x].

The SLEEP WOL energy saving mode requires option Wake-on-LAN3# V-line [3071-2].

Limitations

The option *PROFlenergy* [3021-1] cannot be combined with the option *MultiMove Additional robot* [3102-3].

7 Specification of controller & RobotWare options

7.6.1.4.1 PROFIsafe Controller [3023-1]

7.6.1.4 PROFINET Safety Network

7.6.1.4.1 PROFIsafe Controller [3023-1]

General

The robot controller acts as a PROFIsafe controller and host safe I/O devices (F-Devices) directly. The devices are connected to the Public network or I/O network on the main computer.

A RobotWare license with the options *PROFINET SW* [3020-x] and *PROFIsafe Controller* are required to run PROFIsafe on the controller.

Network segment	V250XT Type B	V400XT	Description
Public Network	WAN 1	WAN 1	Wide Area Network that can host a public industrial network.
	WAN 2	WAN 2	
I/O Network	LAN	LAN	Secondary public/factory network. Isolated from WAN.

Requirements

The option *PROFIsafe Controller* requires option *PROFINET Controller* [3020-1].

7.6.1.4.2 PROFIsafe Device [3023-2]

General

All I/O communication for the SafeMove functionality is done via a safety PLC using PROFIsafe (safe PROFINET). The safety PLC will act as a PROFIsafe controller (F-Host) and the robot controller will act as a PROFIsafe device (F-Device). The PROFIsafe I/O is connected to one of the the Ethernet ports WAN 1, WAN 2, or LAN on the main computer.

A RobotWare license with the options *PROFINET SW* [3020-x] and *PROFIsafe Device* are required to to run PROFIsafe on the controller.

Requirements

The option *PROFIsafe Device* requires option *PROFINET Device* [3020-2].

7.6.2 EtherNet/IP

7.6.2.1 EtherNet/IP Scanner [3024-1]

General

EtherNet/IP is a communications link to connect industrial devices. The EtherNet/IP (EtherNet Industrial Protocol) is managed by ODVA (Open DeviceNet Vendors Association). It is a well established industrial EtherNet communication system with good real-time capabilities. EtherNet/IP extends commercial off-the-shelf Ethernet to the CIP (Common Industrial Protocol); the same upper-layer protocol and object model found in DeviceNet and ControlNet.

CIP allows EtherNet/IP and DeviceNet system integrators and users to apply the same objects and profiles for plug-and-play interoperability among devices from multiple vendors and in multiple sub-nets. Combined, DeviceNet, ControlNet, and EtherNet/IP promote transparency from sensors to the enterprise software.

With this option the robot controller can only act as an EtherNet/IP scanner on the EtherNet/IP network.

7.6.2.2 EtherNet/IP Adapter [3024-2]

General

With the option *EtherNet/IP Adapter* the robot controller can only act as a EtherNet/IP Adapter with 509 byte inputs and 505 byte outputs on the EtherNet/IP network.

7 Specification of controller & RobotWare options

7.6.3.1.1 DeviceNet single ch. [3029-1]

7.6.3 DeviceNet

7.6.3.1 DeviceNet m/s IO

7.6.3.1.1 DeviceNet single ch. [3029-1]

General

The DeviceNet is a communications link to connect industrial devices. It is a simple networking solution that reduces both cost and time to wire and install industrial automation devices, and the direct connectivity provides improved communication between devices. DeviceNet is an open network standard.

- Peer-to-peer data exchange where a DeviceNet product can produce and consume messages
- Master/slave operation defined as a proper subset of peer-to-peer
- A DeviceNet product can function as a master or server, or both

Requirements

The option *DeviceNet single ch.* occupies 1 PCIe slot.

7.6.4 CC-Link

7.6.4.1 CC-Link IE FB Master [3066-1]

General

CC-Link IE FB (Industrial Ethernet Field Basic) is a communications link for industrial devices. CC-Link IE communication using general-purpose Ethernet technology which can be easily applied to small-scale equipment not requiring high-speed control and is easy to use and develop. Realizing cyclic communication on the CC-Link IE field network by software. The communication can be done simultaneously with standard Ethernet TCP/IP communication (HTTP, FTP, etc.) CC-Link standard is monitored by CLPA (CC-Link Partner Association).

Features

With this option the robot controller can act as an CC-Link IE Field Basic Master on the Industrial Ethernet network.

7 Specification of controller & RobotWare options

7.6.4.2 CC-Link IE Field Basic Device [3066-2]

7.6.4.2 CC-Link IE Field Basic Device [3066-2]

General

CC-Link IE FB (Industrial Ethernet Field Basic) is a communications link for industrial devices. CC-Link IE communication using general-purpose Ethernet technology which can be easily applied to small-scale equipment not requiring high-speed control and is easy to use and develop. Realizing cyclic communication on the CC-Link IE field network by software. The communication can be done simultaneously with standard Ethernet TCP/IP communication (HTTP, FTP, etc.) CC-Link standard is monitored by CLPA (CC-Link Partner Association).

Features

With this option the robot controller can act as an CC-Link IE Field Basic Device on the Industrial Ethernet network.

7.6.5 EtherCAT

7.6.5.1 EtherCAT Device [3075-2]

General

EtherCAT is a protocol suitable for both hard and soft real-time computing requirements in automation technology. For more information, see *Application manual - EtherCAT*.

7 Specification of controller & RobotWare options

7.6.5.2 Safety Over EtherCAT Device [3076-2]

7.6.5.2 Safety Over EtherCAT Device [3076-2]

General

Safety over EtherCAT (FSoE) is a protocol for the communication of safety-critical control data. For more information, see *Application manual - EtherCAT*.

Requirements

Requires option EtherCAT Device [3075-2].

7.7 Ethernet & signal interfaces

7.7.1 Safety internal conn. [3054-1]

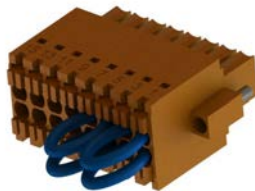
General

The signals are connected directly to the safety board in the main computer in the controller.

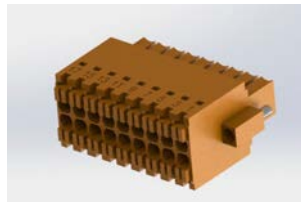
Delivery includes internal spring terminal connectors and cable jumpers.



xx2300000501



xx2200000923



xx2200000924

For a full description of all available signals, see the product manual and the circuit diagram.



CAUTION

Safety functions must be verified before use. Safety functions must be tested regularly.

Connector X14

	Description
Connection	Customer Safety Interface: Automatic Stop/General Stop and external Emergency Stop

The connector X14 allows for connecting *protective stop* and *emergency stop* devices.

Continues on next page

7 Specification of controller & RobotWare options

7.7.1 Safety internal conn. [3054-1]
Continued

Connector X15

	Description
Connection	Customer Optional Interface

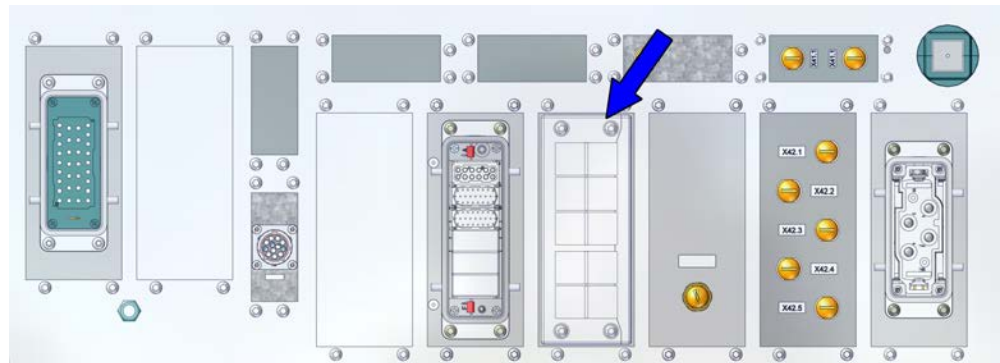
7.7.2 Cable grommet [3050-1]

General

The option *Cable grommet* provides for connections of Ethernet-based communication links to external ABB selected devices such as cameras, conveyor tracker, etc.

The technical solutions in this module vary with the number of Ethernet ports that should be available for communication, IP class, and requirements on the Ethernet connector itself (RJ45 or M12).

The option *Cable grommet* provides extended capability for connectivity.

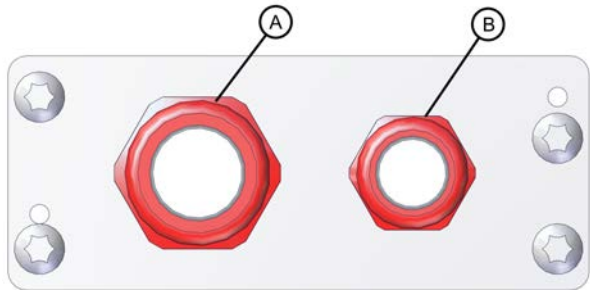


xx2100000844

7.7.3 2xCable gland [3050-2]

General

The option *2xCable gland* is used for connection of external process equipment.



xx2400000150

The glands allow for cables of the following dimensions:

Cable gland	Cable diameter (mm)
A	4.5 mm - 6.0 mm
B	11.0 mm - 14.5 mm

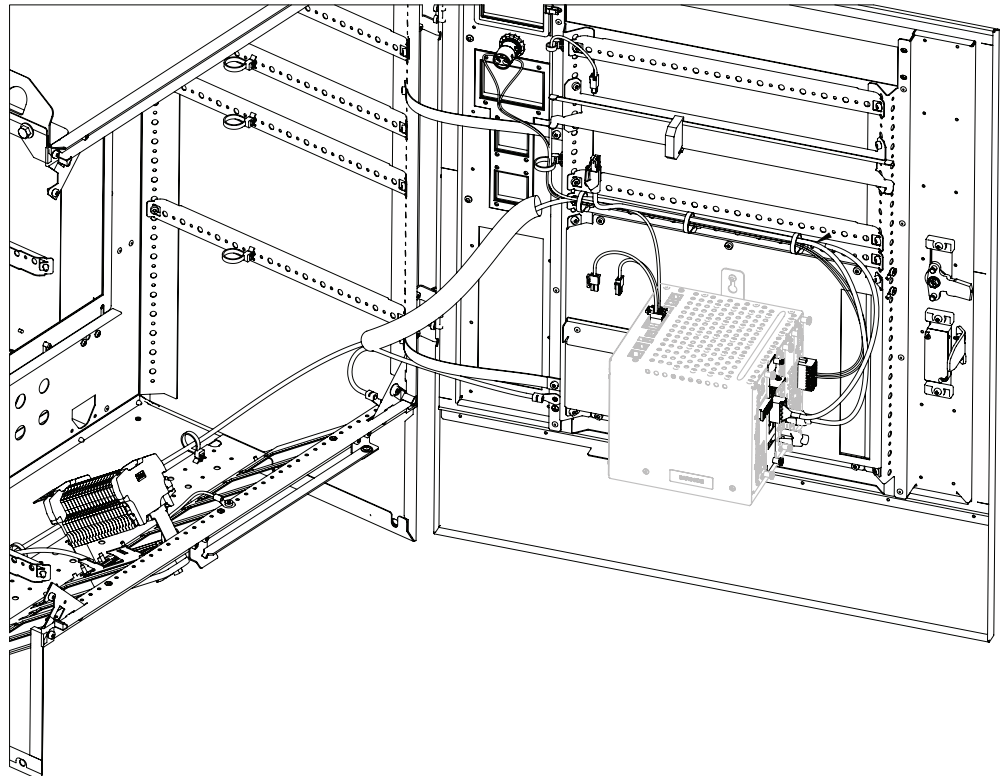
The interface is located in the fixed installation panel.

7.7.4 Parallel manip I/O interface

7.7.4.1 Parallel interface 1 [3055-1]

General

Parallel interface allows to connect internal signals within the controller to outside process equipment using a multipurpose connector. It is the interface for robot floor cable and DressPack.



xx2400000278

Limitation

Cannot be combined with DressPack options for IRB 57X0, 6710, 6720, 6730, 6740.

7 Specification of controller & RobotWare options

7.7.4.2 Parallel interface 2 [3055-2]

7.7.4.2 Parallel interface 2 [3055-2]

General

Parallel interface allows to connect internal signals within the controller to outside process equipment using a multipurpose connector. It is the interface for robot floor cable and DressPack.

Limitation

Cannot be combined with DressPack options for IRB 460, 660, 760, 2600, 4600, 6650S, 6660, 8700.

Requirement

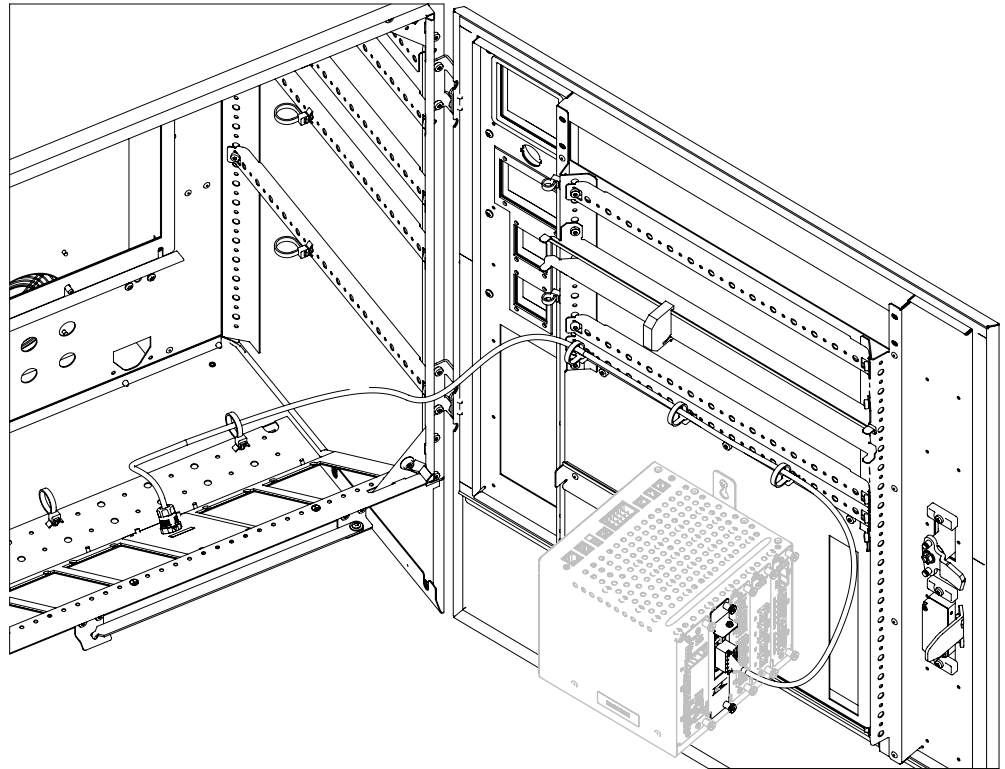
Required by DressPack options for IRB 57X0, 6710, 6720, 6730, 6740.

7.7.5 DeviceNet interface

7.7.5.1 DeviceNet interface [3056-1]

General

DeviceNet interface adds a connector on the front of the control cabinet to be used for DeviceNet fieldbus. Internally connected to DeviceNet single channel board.



xx2400000279

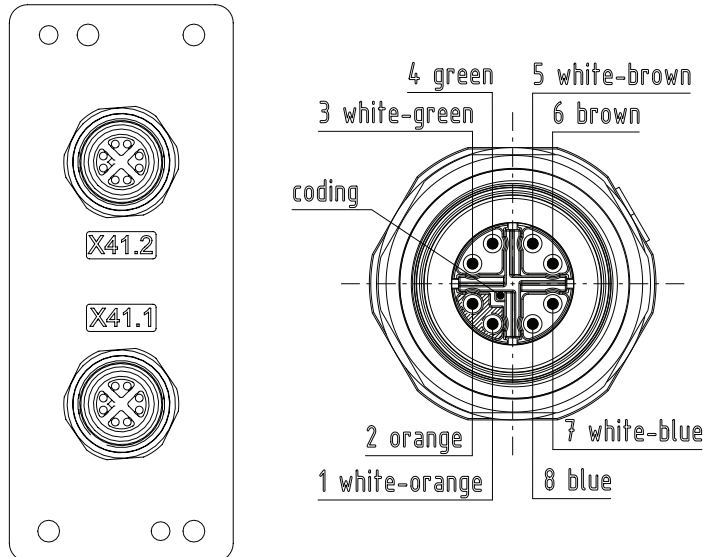
7 Specification of controller & RobotWare options

7.7.6 Ethernet 2xM12 X-coded [3060-1]

7.7.6 Ethernet 2xM12 X-coded [3060-1]

General

The option *Ethernet 2xM12 X-coded* adds 2 connectors of M12 standard on the front of the controller cabinet to be used for Industrial Ethernet fieldbuses.

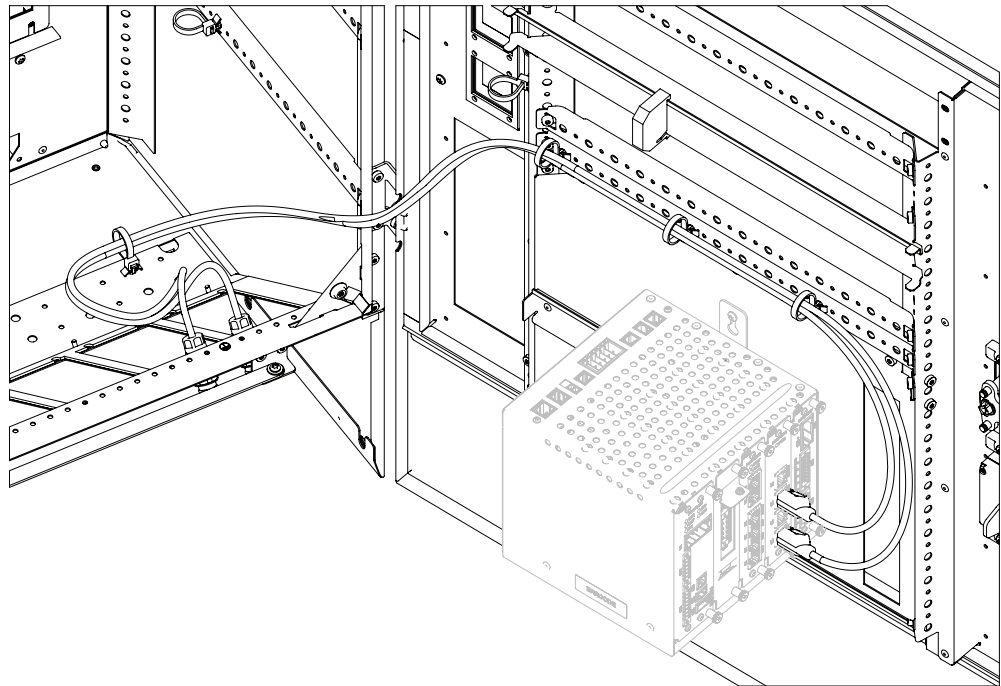


xx2400001768

The M12 connectors are X-coded and have a female interface. They utilize a screw-locking mechanism and support push-pull functionality.

They are internally connected to two EtherNet/IP ports, serving as the interface for the robot floor cable and dresspack.

Continues on next page



xx2400000280

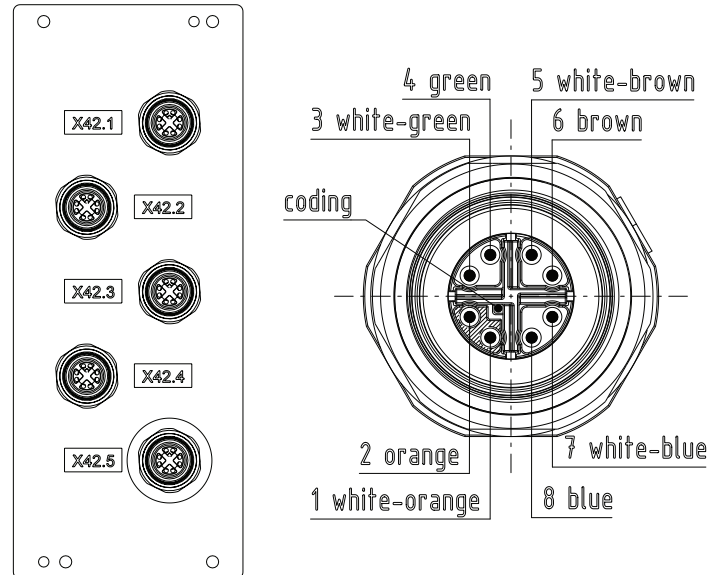
7 Specification of controller & RobotWare options

7.7.7 Ethernet 5xM12 X-coded [3061-1]

7.7.7 Ethernet 5xM12 X-coded [3061-1]

General

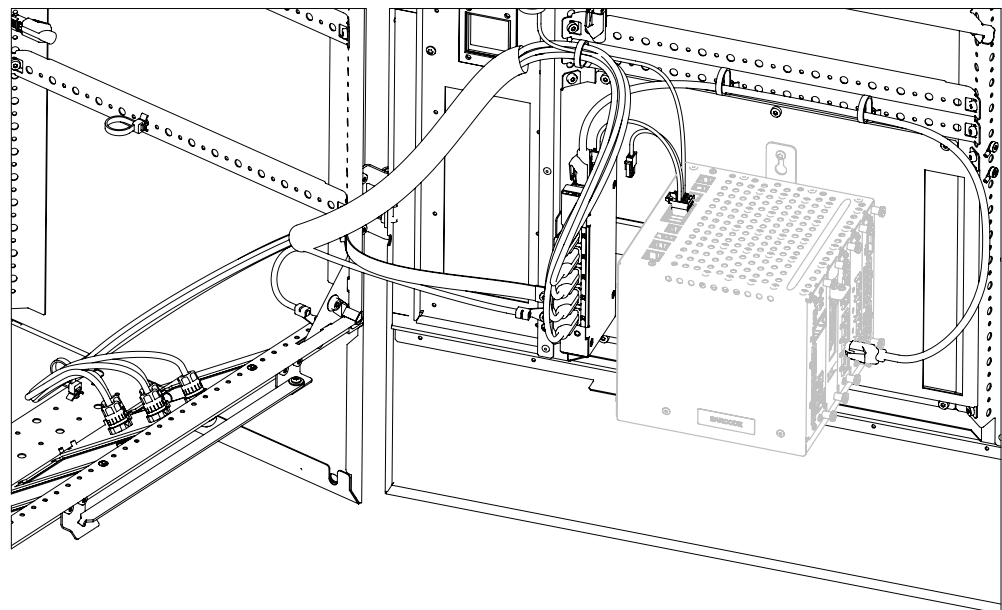
The option *Ethernet 5xM12 X-coded* adds 5 connectors of M12 standard on the front of the controller cabinet to be used for Industrial Ethernet fieldbuses.



xx2400001769

The M12 connectors are X-coded and have a female interface. They utilize a screw-locking mechanism and support push-pull functionality.

They are internally connected to two EtherNet/IP ports, serving as the interface for the robot floor cable and dresspack.



xx2400000281

7.8 Scalable I/O

7.8.1 Scalable I/O Internal

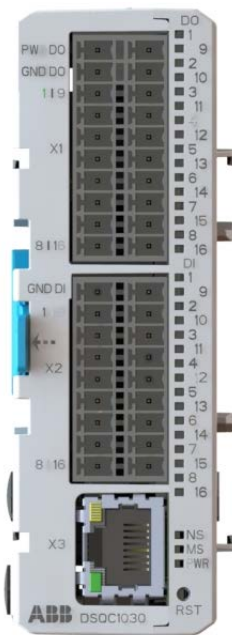
7.8.1.1 Base Dig. 16In/16Out (1-2) [3032-1]

General

DSQC1030 Base unit

24 V Digital with 16 Inputs, 16 Outputs

For more information see [Scalable I/O on page 41](#).



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Limitations

Up to two add-on units can be controlled by the base unit, and any combination of add-on units are supported.

For V400XT, a second row of I/O units can be added. This option is not applicable for V250XT.

7 Specification of controller & RobotWare options

7.8.1.2 Add-on Dig. 16In/16Out [3033-1]

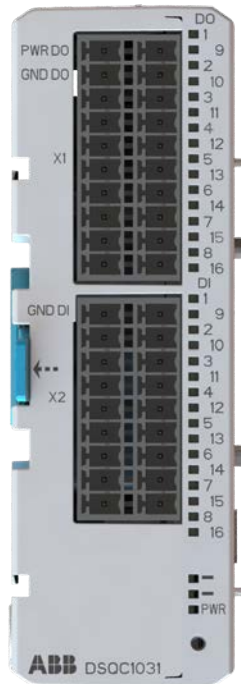
7.8.1.2 Add-on Dig. 16In/16Out [3033-1]

General

DSQC1031

24 V Digital with 16 Inputs, 16 Outputs

For more information, see [Scalable I/O on page 41](#).



xx2200000419

Requirements

The option *Add-on Dig. 16In/16Out* requires option *Base Dig. 16In/16Out* [3032-1].

7.8.1.3 Add-on Analog 4In/4Out [3034-1]

General

DSQC1032

4 Analog Inputs 4 Analog Outputs

For more information, see [Scalable I/O on page 41](#).



xx1800003685

Requirements

The option *Add-on Analog 4In/4Out* requires option *Base Dig. 16In/16Out* [3032-1].

7 Specification of controller & RobotWare options

7.8.1.4 Add-on Relay 8In/8Out [3035-1]

7.8.1.4 Add-on Relay 8In/8Out [3035-1]

General

DSQC1033

8 Digital inputs 8 Relay outputs

For more information, see [Scalable I/O on page 41](#).



xx2200000420

Requirements

The option *Add-on Relay 8In/8Out* requires option *Base Dig. 16In/16Out* [3032-1].

7.8.2 Scalable I/O External

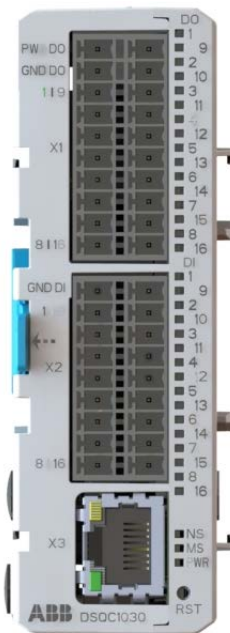
7.8.2.1 Base Dig. 16In/16Out [3032-2]

General

DSQC1030 Base unit

24 V Digital with 16 Inputs, 16 Outputs

For more information, see [Scalable I/O on page 41](#).



xx1800003682

Requirements

- Occupies 1 Ethernet port

7 Specification of controller & RobotWare options

7.8.2.2 Add-on Dig. 16In/16Out [3033-2]

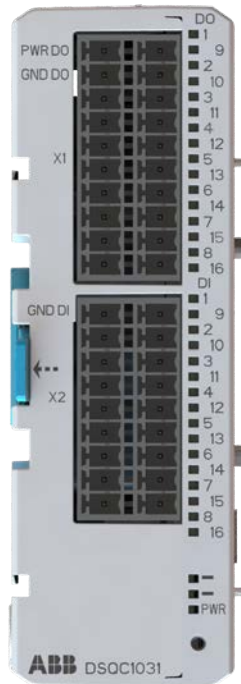
7.8.2.2 Add-on Dig. 16In/16Out [3033-2]

General

DSQC1031

24 V Digital with 16 Inputs, 16 Outputs

For more information, see [Scalable I/O on page 41](#).



xx2200000419

Requirements

The option *Add-on Dig. 16In/16Out* requires option *Base Dig. 16In/16Out* [3032-2].

7.8.2.3 Add-on Analog 4In/4Out [3034-2]

General

DSQC1032

4 Analog Inputs 4 Analog Outputs

For more information, see [Scalable I/O on page 41](#).



xx1800003685

Requirements

The option *Add-on Analog 4In/4Out* requires option *Base Dig. 16In/16Out* [3032-2].

7 Specification of controller & RobotWare options

7.8.2.4 Add-on Relay 8In/8Out [3035-2]

7.8.2.4 Add-on Relay 8In/8Out [3035-2]

General

DSQC1033

8 Digital inputs 8 Relay outputs

For more information, see [Scalable I/O on page 41](#).



xx2200000420

Requirements

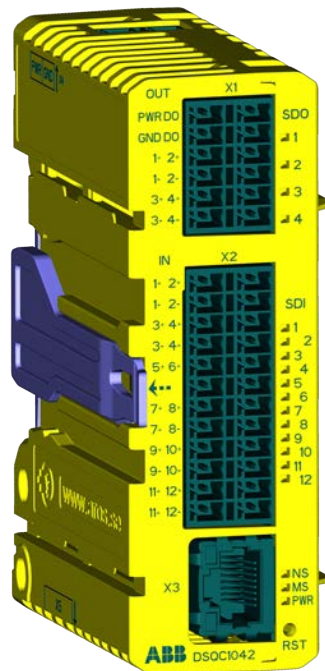
The option *Add-on Relay 8In/8Out* requires option *Base Dig. 16In/16Out* [3032-2].

7.8.3 Scalable safety I/O Internal

7.8.3.1 Safe base Dig. 6In/2Out (1-2) [3037-1]

General

The DSQC1042 safety digital base device has 12 inputs and 4 outputs working in dual channel pairs. Due to the dual channel configuration, the device has 6 safe digital inputs and 2 safe digital outputs. The safety digital base device can be combined with up to four additional add-on devices.



xx2100001681

Connector	Description
X1	Digital outputs, process power
X2 ⁱ	Digital inputs
X3	EtherNet
X4	Logic power
X5	EtherNet

ⁱ The numbers (printings) on the module only show the I/O numbers (digital input/output). It is not the pin position number for connector X1 or X2 (only I/O number).

For more information see *Application manual - Scalable I/O*.

Limitations

The option *Safe base Dig. 6In/2Out* is not possible to order with option *Base Dig. 16In/16Out* [3032-1].

For V400XT, a second row of I/O units can be added. This option is not applicable for V250XT.

7 Specification of controller & RobotWare options

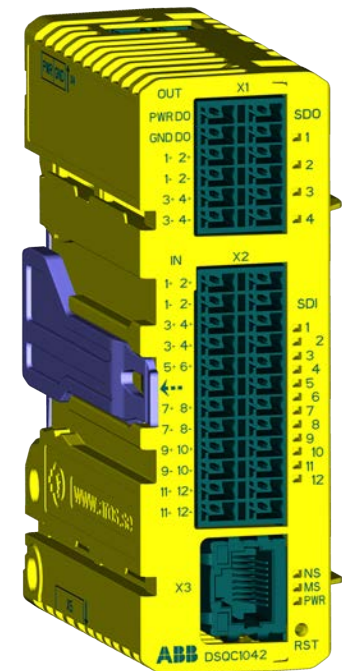
7.8.4.1 Safe base Dig. 6In/2Out [3037-2]

7.8.4 Scalable safety I/O External

7.8.4.1 Safe base Dig. 6In/2Out [3037-2]

General

The DSQC1042 safety digital base device has 12 inputs and 4 outputs working in dual channel pairs. Due to the dual channel configuration, the device has 6 safe digital inputs and 2 safe digital outputs. The safety digital base device can be combined with up to four additional add-on devices.



xx2100001681

Connector	Description
X1	Digital outputs, process power
X2 ⁱ	Digital inputs
X3	EtherNet
X4	Logic power
X5	EtherNet

ⁱ The numbers (printings) on the module only show the I/O numbers (digital input/output). It is not the pin position number for connector X1 or X2 (only I/O number).

For more information see *Application manual - Scalable I/O*.

7.9 Functional Safety

General

The OmniCore controller is prepared with the hardware to run keyless mode switch and SafeMove.

Continues on next page

7 Specification of controller & RobotWare options

7.9.1.1 SafeMove Basic [3043-1]

7.9.1 Robot safety supervision

7.9.1.1 SafeMove Basic [3043-1]

General

The option *SafeMove Basic* gives you access to the configurator **Visual SafeMove** in RobotStudio. With **Visual SafeMove** you can:

- configure and visualize supervision functions in a 3D environment
- configure stop functions, such as automatic stop
- configure *Cyclic Brake Check*
- configure safe signals (safe EtherNet communication and I/O)
- configure signal logics
- configure system status outputs

For more information, see *Application manual - Functional safety and SafeMove*.

Included functions	
Supported number of axes	9
Safe ranges	8
Safe zones	1
Axis position supervision	Yes
Contact application support	Yes

7.9.1.2 SafeMove Pro [3043-2]

General

The option *SafeMove Pro* gives you access to the configurator **Visual SafeMove** in RobotStudio. With **Visual SafeMove** you can:

- configure and visualize supervision functions in a 3D environment
- configure stop functions, such as automatic stop
- configure *Cyclic Brake Check*
- configure safe signals (safe EtherNet communication and I/O)
- configure signal logics
- configure system status outputs

For more information, see *Application manual - Functional safety and SafeMove*.

Included functions	
Supported number of axes	9
Safe ranges	8
Safe zones	16
Tool changer support	Yes (16 tools)
Axis position supervision	Yes
Axis speed supervision	Yes
Tool orientation supervision	Yes
Tool position supervision	Yes
Tool speed supervision	Yes
Stand still supervision	Yes
Contact application support	Yes

7 Specification of controller & RobotWare options

7.9.2.1 3 modes Keyless [3044-1]

7.9.2 Operation mode selector

7.9.2.1 3 modes Keyless [3044-1]

General

Operator mode selection from the FlexPendant without key switch.

The operational modes to switch between is:

- Auto mode
- Manual mode (reduced speed)
- Manual mode (full speed)

7.9.2.2 2 modes Keyless [3044-2]

General

Operator mode selection from the FlexPendant without key switch.

The operational modes to switch between is:

- Auto mode
- Manual mode (reduced speed)

7 Specification of controller & RobotWare options

7.10.1 Additional drive units

7.10 Additional axis

7.10.1 Additional drive units

Additional drive units [3062-1]

The additional drive unit option is used when the robot controller needs to control additional axes besides the robot axes. These axes are synchronized and, if desired, coordinated with the movement of the robot, which results in high speed and high accuracy.

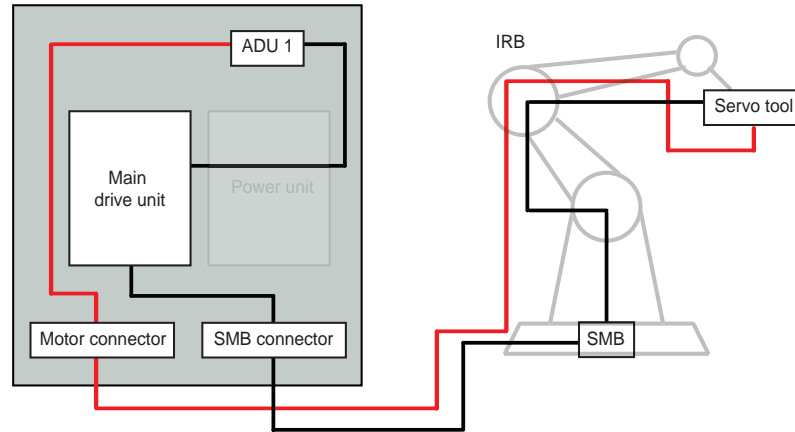
Drive unit type	Rated current (Amp rms)	Max current (Amp rms)	Input voltage (VDC)
DSQC3065	30	55	370/650 ⁱ

ⁱ Depending on the type of power unit.

7.10.2 1st ADU connection to manipulator

Robot held servo tool [3068-1]

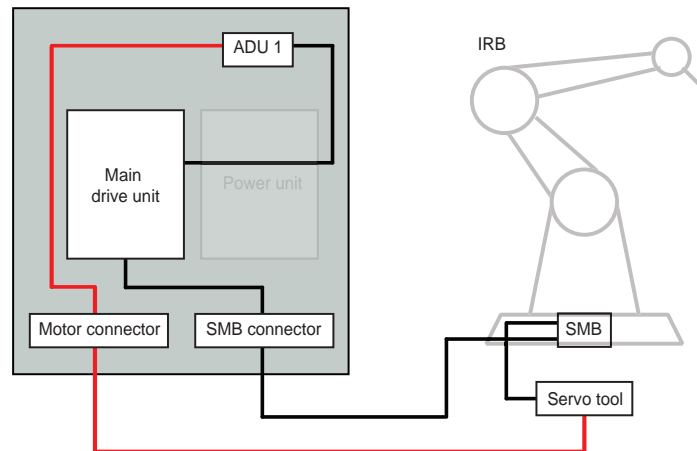
The option *Robot held servo tool [3068-1]* is used for setups with robot held servo tools:



xx2300000931

Stationary servo tool [3068-2]

The option *Stationary servo tool [3068-2]* is used for setups with stationary servo tools:



xx2300000932

If this option is selected, an additional SMB cable is included.



Note

Requires option *On base [3322-1]* (Resolver connection 7th axis).

Track motion [3068-3]

This option is required when including a track motion in the robot.

Limitation

This option cannot be combined with option [3206-X].

Continues on next page

7 Specification of controller & RobotWare options

7.10.2 1st ADU connection to manipulator

Continued

This option is not available for IRB 1300/2400/4400/460/6790.

MU/GU [3068-4]

This option is required when including an ABB motor unit or ABB gear unit in the robot.

Limitation

This option cannot be combined with option [3206-X].

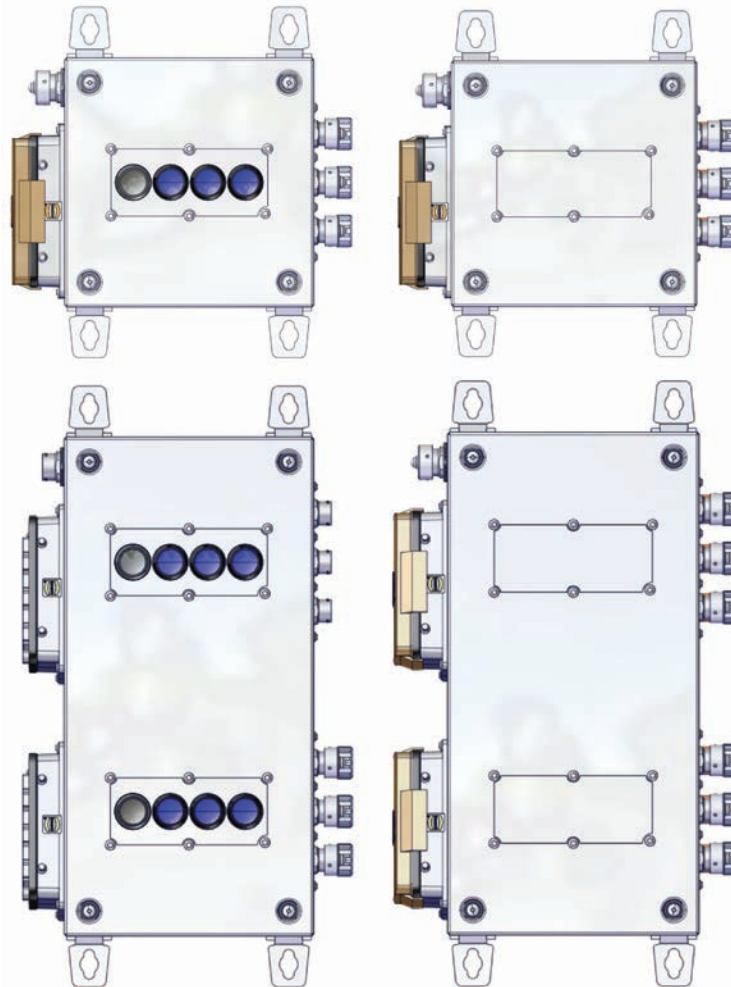
This option is not available for IRB 1300/2400/4400/460/6790.

7.10.3 Motor connection kit

General

The motor connection kit consists of the motor connection box and floor cables. Depending on the selected option, the motor connection box allows the connection of one to six motor units and/or gear units to the robot controller.

The motor connection box can be located 7, 15, or 22 meters from the cabinet. Motor units and gear units can be connected to the motor connection box through flexible cables with lengths of 7, 15, or 22 meters. The motor connection box can be equipped with brake release buttons, one for each motor unit.



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Installation requirements

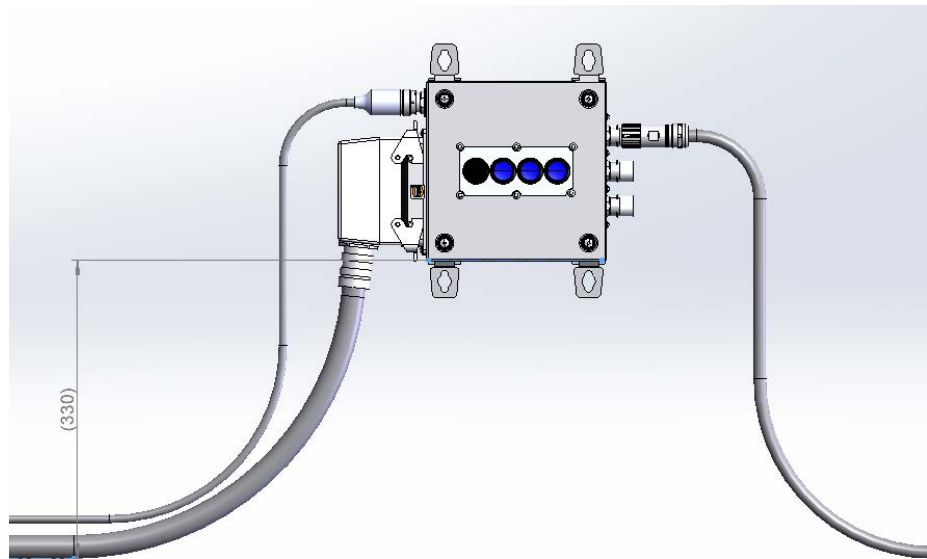
- If third party motors are to be used, a quenching circuit must be installed.
- The following minimum space is required beside the motor connection box due to stiffness of floor cables:

Continues on next page

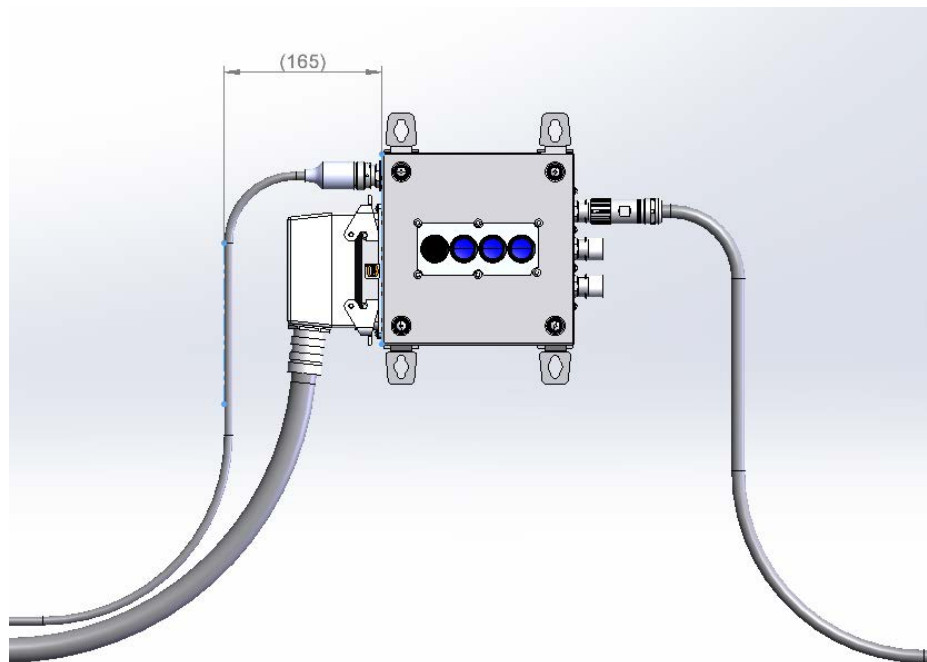
7 Specification of controller & RobotWare options

7.10.3 Motor connection kit

Continued

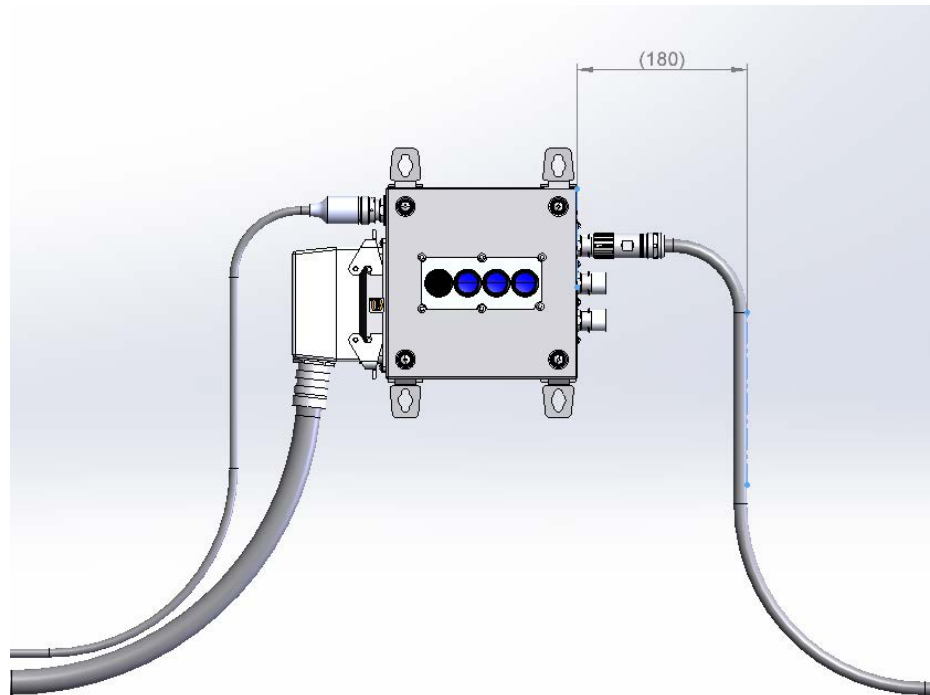


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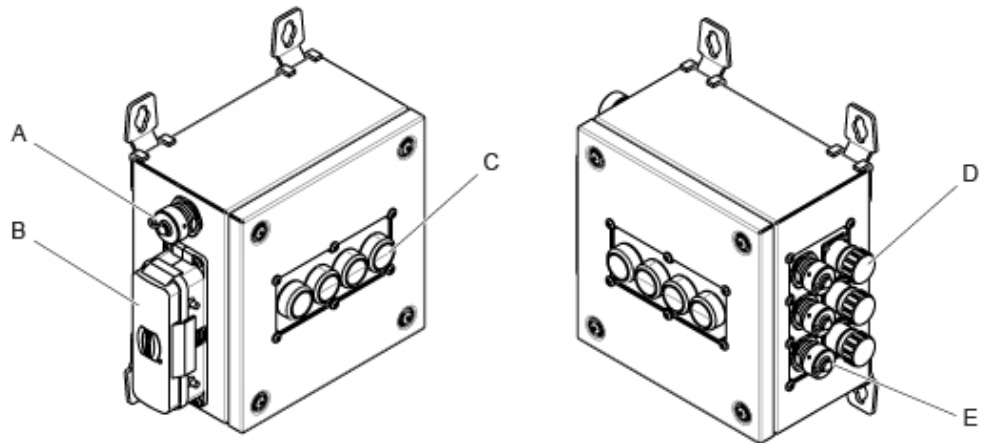
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xx2300001743

Motor connection box, 3-axis [3069-1x]

Overview



xx2300001719

A	Cable harness resolver, bus
B	Cable harness power, axis 1-3
C	Brake release buttons (optional)
D	Cable harness motor power, axis 1-3
E	Resolver signal, axis 1-3

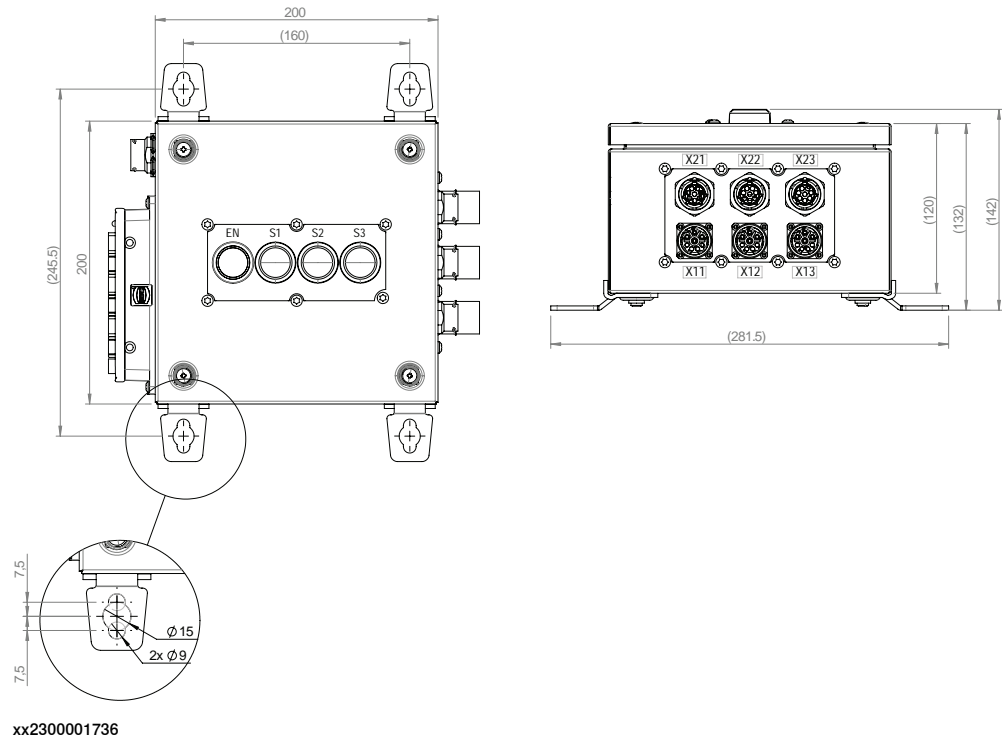
Dimensions

The graphic below shows the dimensions of the motor connection box.

Continues on next page

7 Specification of controller & RobotWare options

7.10.3 Motor connection kit
Continued



Option description

The option *Connection box [3069-1x]* includes the following:

- 1 Motor connection box, 3-axis
- 1 External axis power harness
- 1 SMB cable

Cable length

Length of cables is determined by the selected option, see below:

Option	Cable length
Connection box [3069-12]	7 m
Connection box [3069-13]	15 m
Connection box [3069-14]	22 m
Connection box [3069-15]	30 m



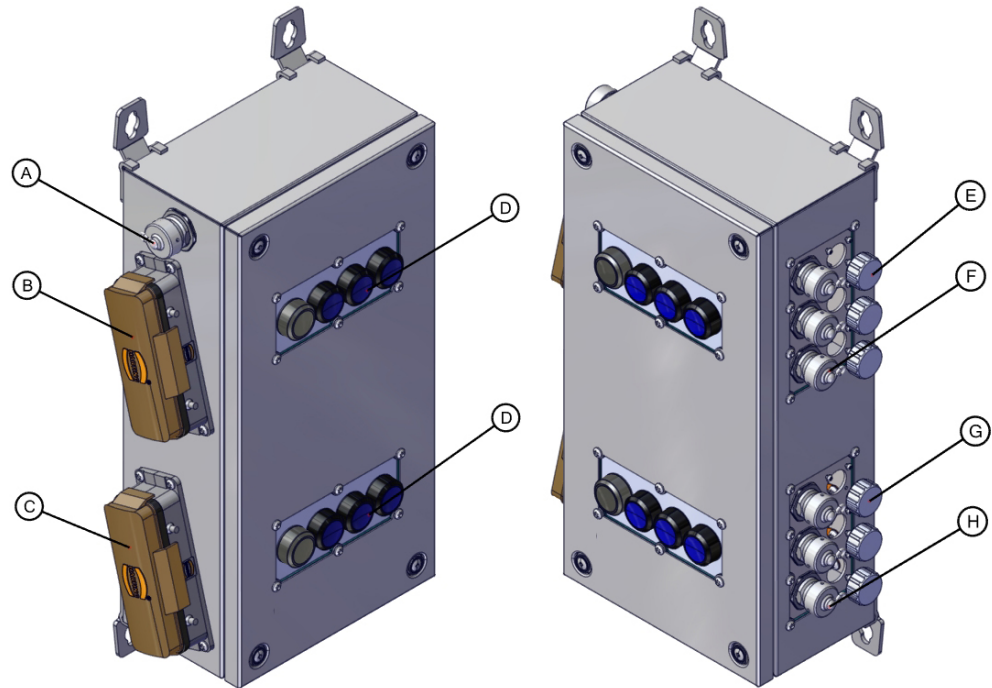
Note

The maximum cable length that can be ordered is 30 m. However, the power cable may be extended up to a total length of 50 m.

Continues on next page

Motor connection box, 6-axis [3069-2x]

Overview



xx2300001718

A	Cable harness resolver, bus
B	Cable harness power, axis 1-3
C	Cable harness power, axis 4-6
D	Brake release buttons (optional)
E	Cable harness motor power, axis 1-3
F	Resolver signal, axis 1-3
G	Cable harness motor power, axis 4-6
H	Resolver signal, axis 4-6

Dimensions

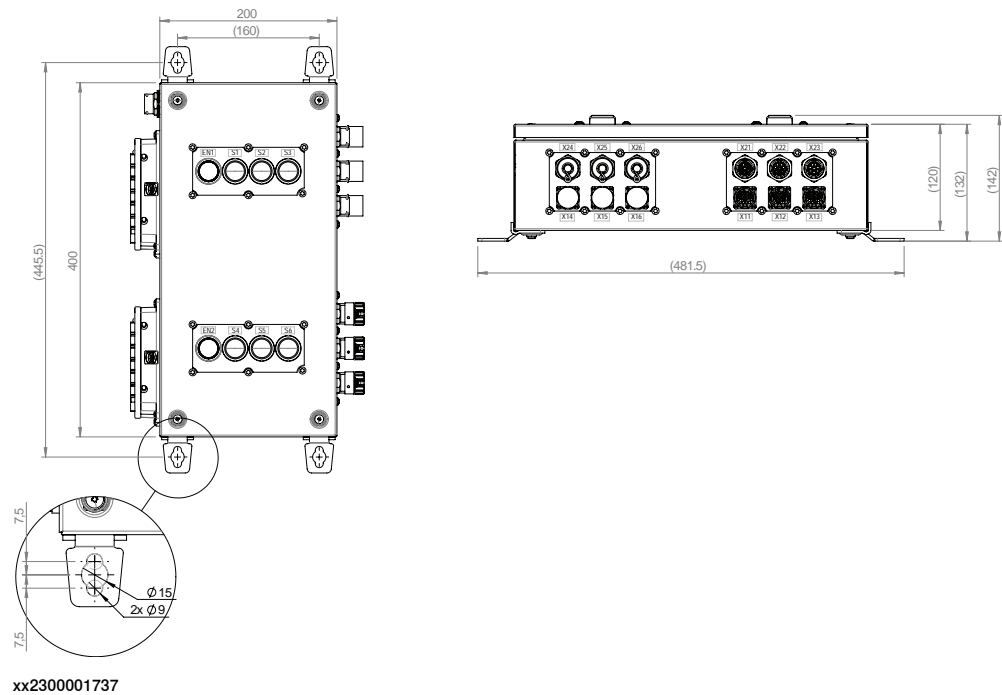
The graphic below shows the dimensions of the motor connection box.

Continues on next page

7 Specification of controller & RobotWare options

7.10.3 Motor connection kit

Continued



Option description

The option *Connection box [3069-2x]* includes the following:

- 1 Motor connection box, 3-axis
- 2 External axis power harnesses
- 1 SMB cable

Cable length

Length of cables is determined by the selected option, see below:

Option	Cable length
Connection box [3069-22]	7 m
Connection box [3069-23]	15 m
Connection box [3069-24]	22 m
Connection box [3069-25]	30 m



Note

The maximum cable length that can be ordered is 30 m. However, the power cable may be extended up to a total length of 50 m.

No brake release [3070-1]

The option *No brake release* is selected for motor connection boxes without brake release buttons.

Analog brake release [3070-2]

The option *Analog brake release* is selected for motor connection boxes with brake release buttons.

Continues on next page

Motor Connector Plug [3072-1]

The option *Motor Connector Plug* is applicable when PTC supervision is activated in system configuration and when any of the motor outputs on the Motor Connection Box are not used.

The PTC supervision signal must be a closed circuit (when the supervision is activated).



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7 Specification of controller & RobotWare options

7.11.1.1 Advanced robot motion [3100-1]

7.11 Motion Performance

7.11.1 Advanced robot motion

7.11.1.1 Advanced robot motion [3100-1]

About Advanced robot motion

The option *Advanced robot motion* gives you access to:

- *Advanced Shape Tuning*, see [Advanced Shape Tuning on page 145](#).
- *Wrist Move*, see [WristMove on page 149](#).
- Changing *Motion Process Mode* from RAPID, see [Motion Process Mode on page 147](#).

Continues on next page

7.11.1.1.1 Advanced Shape Tuning

General



Note

This functionality is included in the option *Advanced robot motion*, see [Advanced robot motion \[3100-1\] on page 144](#).

Advanced Shape Tuning offers the possibility to compensate for frictional effects that might appear at low speed cutting robot motion (10-100 mm/s). This is especially useful when cutting advanced shapes, for example, small circles, or other similar applications when path accuracy is crucial. Friction tuning can be used to improve path accuracy of the robot in cutting applications.

The option gives the user access to tuning parameters and the possibility to change the tuning parameters for each axis during program execution with RAPID commands in the robot program. The option also includes RAPID instructions for automatic fine tuning of friction level for each specific shape. The software automatically repeats the movement until the best friction level for each axis has been found. After the tuning has been completed each robot axis has a unique set of tuning values for each shape. The tuning is performed by the user and for each specific shape.

Features

- Very accurate path performance for advanced motion at low speed, e.g. shape cutting
- Automatic tuning of the friction level using RAPID
- Access to tuning parameters
- Tuning axis by axis
- Change tuning from RAPID program

Application

Friction effects typically arise when cutting small, advanced shapes like for example circles. The major source of friction effects comes changing direction of axis movement. The effects appear in the form of up to 0.5 mm path deviations.

Typical applications are cutting of small shapes, such as holes, slots, rectangles. Other applications may be high precision gluing or dispense of small geometries.

Performance

Using *Advanced Shape Tuning*, typically a 0.5 mm path deviation can be reduced to about 0.1 mm. This however, requires careful tuning of the friction level (see *Operating manual - OmniCore* for tuning procedure, and the instruction `TuneServo` described in *Technical reference manual - RAPID Instructions, Functions and Data types*). Note that even with careful tuning, there is no guarantee that "perfect" paths will always be generated.

Continues on next page

7 Specification of controller & RobotWare options

7.11.1.1.1 Advanced Shape Tuning

Continued

Requirements

There are no hardware or software requirements for this option.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
FricIdInit	Instruction to start the friction level identification
FricIdEvaluate	Function that will return the friction level that produced the best results
FricIdSetFricLevels	Instruction to set friction levels

Change of tuning from RAPID is done with standard parameters.

Instruction	Description
TuneServo	<i>Technical reference manual - RAPID Instructions, Functions and Data types</i>

Limitations

- The movement sequence for which friction tuning is done must begin and end with a fine point.
- The tuning process requires about 15 iterations of the movement per axis.
- The movement sequence between `FricIdInit` and `FricIdEvaluate` cannot be longer than 4 seconds.

7.11.1.1.2 Motion Process Mode

Purpose



Note

This functionality is included in the option *Advanced robot motion*, see [Advanced robot motion \[3100-1\] on page 144](#).

The purpose of Motion Process Mode is to simplify application specific tuning, i.e. to optimize the performance of the robot for a specific application.

For most applications the default mode is the best choice.



Tip

If the default mode does not give sufficient accuracy, first test to use *Accuracy mode*, and if that is not sufficient, use *Low speed accuracy*.

Available motion process modes

A motion process mode consists of a specific set of tuning parameters for a robot. Each tuning parameter set, that is each mode, optimizes the robot tuning for a specific class of applications.

There following modes are predefined:

- *Optimal cycle time mode* – this mode gives the shortest possible cycle time and is normally the default mode.
- *Accuracy mode* – this mode improves path accuracy. The cycle time will be slightly increased compared to *Optimal cycle time mode*.
- *Low speed accuracy mode* – this mode improves path accuracy. The cycle time will be slightly increased compared to *Accuracy mode*.
- *Low speed stiff mode* - this mode is recommended for contact applications where maximum servo stiffness is important. Could also be used in some low speed applications, where a minimum of path vibrations is desired. The cycle time will be increased compared to *Low speed accuracy mode*.
- *Press tending mode* – Changes the *Kv Factor*, *Kp Factor* and *Ti Factor* in order to mitigate tool vibrations. This mode is primarily intended for use in press tending applications where flexible grippers with a large extension in the y-direction are used.
- *Collaborative mode* – This mode is recommended for collaborative applications where robot should run smoothly. The cycle time will be increased compared to optimal cycle time mode. This will only have any effect on GoFa CRB 15000.

There are also four modes available for application specific user tuning:

- *MPM User mode 1 – 4*

Continues on next page

7 Specification of controller & RobotWare options

7.11.1.1.2 Motion Process Mode

Continued

Selection of mode

The default mode is automatically selected and can be changed by changing the system parameter *Use Motion Process Mode* for type *Robot*.

Changing the *Motion Process Mode* from RAPID is only possible if the option *Advanced Robot Motion* is installed. The mode can only be changed when the robot is standing still, otherwise a fine point is enforced.

The following example shows a typical use of the RAPID instruction

`MotionProcessModeSet.`

```
MotionProcessModeSet OPTIMAL_CYCLE_TIME_MODE;
! Do cycle-time critical movement
MoveL *, vmax, ...;
...

MotionProcessModeSet ACCURACY_MODE;
! Do cutting with high accuracy
MoveL *, v50, ...;
...
```

Limitations

- The *Motion Process Mode* concept is currently available for all six- and seven-axes robots except paint robots with TrueMove1.
- The *Mounting Stiffness Factor* parameters are only available for the following robots:
IRB 120, IRB 140, IRB 1200, IRB 1520, IRB 1600, IRB 2600, IRB 4600, IRB 6620 (not LX), IRB 6640, IRB 6700.
- For IRB 1410, only the *Accset* and the geometric accuracy parameters are available.
- The following robot models do not support the use of *World Acc Factor* (i.e. only *World Acc Factor* = -1 is allowed):
IRB 340, IRB 360, IRB 540, IRB 1400, IRB 1410

7.11.1.1.3 WristMove

General



Note

This functionality is included in the option *Advanced robot motion*, see [Advanced robot motion \[3100-1\] on page 144](#).

WristMove is an interpolation method that only uses two axes to perform the movement. It is favorable to use in applications where one needs to improve the accuracy for small shapes, for example in cutting applications. For shapes like small holes, the friction effects from the main axes (axes 1-3) of the robot may cause path deviations. *WristMove* is a method to limit the axes movement to only use two wrist axes, and thereby minimizing the friction effects on the path. In addition, a movement with *WristMove* interpolation is faster than corresponding movement without *WristMove* as less robot weight needs to be moved. The user can define which axis pair to be used for the specific movement.

Features

- Interpolation method to only use a pair of two axes. Allowable combinations, Axis5/Axis6, Axis4/Axis5 or Axis4/Axis6
- Support for any shape consisting of circular arc and straight lines, e.g. holes, slots, rectangles, etc.
- Lead in - Lead out -> any shape
- Activate interpolation mode prior to shape generation
- Used together with RAPID instruction `CirPathMode` and movement instructions for circular arcs, that is, `MoveC`, `TrigC`, `CapC`, etc
- Straight line segments can be achieved using `MoveC` with collinear targets.

Application

WristMove is an option that can be used in cutting applications, like laser cutting, water jet cutting, routing, etc, to improve the accuracy for small shapes. The solution is a flexible, easy-to-use software feature that can be applied in any application where the robot needs to perform small shape movements.

The option can help to reduce path deviations up to or above 50% in favorable circumstances.

Continues on next page

7 Specification of controller & RobotWare options

7.11.1.1.3 WristMove

Continued

Performance

WristMove is especially useful in cutting small holes, or other similar movements, with radius up to 25 mm. For these kinds of movements one can expect an accuracy of about ± 0.1 mm when using *WristMove* at normal cutting speeds. This accuracy is the radial deviation between the actual movement and the programmed circle. This however, requires careful usage of the *WristMove* option (see *Operating manual - OmniCore* for details, and the instruction `CirPathMode` described in *Technical reference manual - RAPID Instructions, Functions and Data types*). Note that even with careful usage, there is no guarantee that "perfect" paths will always be generated.

WristMove can potentially improve cycle time as a movement with *WristMove* is faster than a corresponding movement without *WristMove* interpolation. The reason is that less robot weight needs to be moved in order to achieve the movement.

Requirements

There are no additional hardware or software requirements for this option.

RAPID instructions

There are no RAPID instructions included in this option.

Change of interpolation mode is done by setting parameters in RAPID instruction `CirPathMode`.

Limitations

- *WristMove* cannot be used if the work object is moving
- *WristMove* cannot be used if the robot is mounted on a track that is moving
- Can only use movement instructions for circular arcs, that is, `MoveC`, `TrigC`, `CapC` etc
- When cutting holes, or other shapes, the edges will be conical depending on the robot movement and the distance between tool and workobject
- The tool's height above the surface and the distance to the cutting point will vary during the cut due to the movement of only two axes
- *WristMove* cannot be used on robots with non-spherical wrist, for example, GoFa or YuMi

7.11.2 Absolute Accuracy [3101]

Purpose

Absolute Accuracy is a calibration concept that improves TCP accuracy. The difference between an ideal robot and a real robot can be several millimeters, resulting from mechanical tolerances and deflection in the robot structure. *Absolute Accuracy* compensates for these differences.

Here are some examples of when this accuracy is important:

- Exchangeability of robots
- Offline programming with no or minimum touch-up
- Online programming with accurate movement and reorientation of tool
- Accurate cell alignment for MultiMove coordinated motion
- Programming with accurate offset movement in relation to eg. vision system or offset programming
- Re-use of programs between applications

The option *Absolute Accuracy* is integrated in the controller algorithms and does not need external equipment or calculation.



Note

The performance data is applicable to the corresponding RobotWare version of the individual robot.



Note

Singularities might appear in slightly different positions on a real robot compared to RobotStudio, where *Absolute Accuracy* is off compared to the real controller.

What is included

Every *Absolute Accuracy* robot is delivered with:

- compensation parameters saved in the robot memory
- a birth certificate representing the *Absolute Accuracy* measurement protocol for the calibration and verification sequence.

A robot with *Absolute Accuracy* calibration has a label with this information on the manipulator.

Absolute Accuracy supports floor mounted, wall mounted, and ceiling mounted installations. The compensation parameters that are saved in the robot memory differ depending on which Absolute Accuracy option is selected.

When is *Absolute Accuracy* being used

Absolute Accuracy works on a robot target in Cartesian coordinates, not on the individual joints. Therefore, joint based movements (e.g. MoveAbsJ) will not be affected.

If the robot is inverted, the Absolute Accuracy calibration must be performed when the robot is inverted.

Continues on next page

7 Specification of controller & RobotWare options

7.11.2 Absolute Accuracy [3101]

Continued

Absolute Accuracy active

Absolute Accuracy will be active in the following cases:

- Any motion function based on robtargets (e.g. `MoveL`) and ModPos on robtargets
- Reorientation jogging
- Linear jogging
- Tool definition (4, 5, 6 point tool definition, room fixed TCP, stationary tool)
- Work object definition

Absolute Accuracy not active

The following are examples of when Absolute Accuracy is not active:

- Any motion function based on a jointtarget (`MoveAbsJ`)
- Independent joint
- Joint based jogging
- Additional axes
- Track motion



Note

In a robot system with, for example, an additional axis or track motion, the Absolute Accuracy is active for the manipulator but not for the additional axis or track motion.

RAPID instructions

There are no RAPID instructions included in this option.

Absolute Accuracy and MultiMove

If the main robot in a MultiMove system has the Absolute Accuracy option, it opens up Absolute Accuracy capability for all the robots in the system. However, each robot needs to be calibrated individually.



Note

Note that this is the only RobotWare option that is relevant for an additional robot.



Note

It is possible to mix robots with and without the option Absolute Accuracy arbitrarily in a MultiMove system.

Available options

The following options are available for *Absolute Accuracy*:

- *AbsAcc Floor mounted* [3101-1]
- *AbsAcc Ceiling mounted* [3101-2]
- *AbsAcc Wall mounted* [3101-3]

Continues on next page

- *AbsAcc All mounting pos* [3101-4]

The mounting options for the manipulator can limit the available options for *Absolute Accuracy*. See the product specification for the respective manipulator.

Performance data

The performance data is described in the product specification for the respective manipulator.

Limitations

Absolute Accuracy [3101-x] is not available for delta robots.

[3101-3] and [3101-4] are not possible to select for IRB 1300.

Absolute Accuracy cannot be selected for robots with the option *Inverted*.

7 Specification of controller & RobotWare options

7.12.1.1 Motion supervision bundle [3105-1]

7.12 Motion Supervision

7.12.1 Motion supervision bundle

7.12.1.1 Motion supervision bundle [3105-1]

About Motion supervision bundle

The option *Motion supervision bundle* gives you access to the included options:

- *World Zones*, see [World Zones \[3106-1\] on page 155](#)
- *Collision detection*, see [Collision detection \[3107-1\] on page 157](#)
- *Collision avoidance*, see [Collision avoidance \[3150-1\] on page 158](#)

7.12.2 World Zones

7.12.2.1 World Zones [3106-1]

General

The option *World Zones* is used to define in which area in space the TCP is operating, or the current joint configuration.

Features

- Set input/output signal, when TCP or joint within or outside zone
- Stop robot when reaching a zone border
- Cubical, Cylindrical, Spherical and Joint zones
- Set I/O when the robot is in home position and configuration
- Automatic activation at start-up or activated/deactivated from RAPID program
- Active in automatic and manual mode

Application

Application	Description
Home position	When the robot is started from a PLC, the PLC will check that the robot is inside the volume of the home configuration. In this way other equipment may move safely in the cell.
Protection of equipment	A zone may enclose other cell equipment, and thus prevent the robot from moving into that area.
Robots working in the same area	Handshaking between robots ensures that only one robot at a time is working within a zone. This functionality also ensures efficiency in these operations, since robots can be put waiting for another robot to finish its work within the zone and immediately enter the zone, when the first is finished.

Performance

For safety reasons, this software function shall not be used for protection of personnel. Use hardware protection equipment.

Requirements

There are no software or hardware requirements for this option.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
WZBoxDef	Define a cubical world zone
WZCylDef	Define a cylindrical world zone
WZLimSup	Activate world zone limit supervision
WZSphDef	Define a sphere-shaped world zone
WZDOSet	Activate world zone digital output
WZDisable	Deactivate world zone supervision

Continues on next page

7 Specification of controller & RobotWare options

7.12.2.1 World Zones [3106-1]

Continued

Instruction	Description
WZEnable	Activate world zone supervision
WZFree	Erase world zone supervision
WZHomeJointDef	Define a global zone in joint coordinates
WZLimJointDef	Define a global zone in joint coordinates, for limitation of work area

7.12.3 Collision detection

7.12.3.1 Collision detection [3107-1]

General

Collision detection is a software option, which reduces collision impact forces on the robot. In this way, the robot and external equipment can be protected from severe damage.

Features

- Protection of robot and equipment
- Protection from collisions from any direction
- Robot movement stops and the robot moves back, along the programmed path
- Can reduce the collision force to 30%

Application

Abnormal torque levels on any robot axis (for additional axes, only positioners listed below are covered) are detected and will cause the robot to stop quickly and thereafter back off to relieve forces between the robot and environment.

Performance

The sensitivity (with default tuning) is comparable to the mechanical alternative (mechanical clutch) and it is in most cases much better. In addition, *Collision detection* has the advantages of no added stick-out and weight, no need for connection to the e-stop circuit, no wear, the automatic backing off after collision and, finally, the adjustable tuning.

Tuning is normally not required, but the sensitivity can be changed from RAPID or manually. *Collision detection* can also be switched off completely for part of a program. This may be necessary when strong process forces are acting on the robot.

RAPID instructions

RAPID instruction included in this option:

Instruction	Description
MotionSup	Changing the sensitivity of the collision detection or activating/deactivating the function.

7 Specification of controller & RobotWare options

7.12.4.1 Collision avoidance [3150-1]

7.12.4 Collision avoidance

7.12.4.1 Collision avoidance [3150-1]

General

Collision avoidance is a software option that enables the possibility to stop the robot before colliding with fixed objects, such as fences, the floor or equipment in the cell. A collision model for the objects need to be built and downloaded to the controller using RobotStudio.

Features

The *Collision avoidance* feature monitors the geometries of the robot and its work envelope and stops the robot before a possible collision. The static geometry surrounding the robot can also be included in the configuration. This is useful where object positions are dynamically created during runtime by cameras or sensors. The predicted collision can be visualized in the RobotStudio Online Monitor.

Collision avoidance is active during jogging and program execution. The Collision Prediction supports convex geometries such as points, line segments, and convex polygons. Non-convex objects must be split into smaller parts that can be approximated.

Application

This feature can be activated in RobotStudio where it is also possible to define the objects that should be supervised.

For more information, see *Application manual - Controller software OmniCore* and *Operating manual - RobotStudio*.

Performance

The *Collision avoidance* is optimized for and runs on the controller in the motion planner to be able to stop the robot before colliding with monitored objects.

Limitations



CAUTION

Collision Avoidance shall not be used for safety of personnel.

- Paint robots are not supported.
- *Collision Avoidance* cannot be used in manual mode together with responsive jogging. The system parameter *Jog Mode* must be changed to *Standard*.
- Only stationary/non-moving objects can be configured with a trigger signal. A trigger signal must correspond to a group signal. Furthermore, each collision object must have its own trigger signal.
- There is no support for applications that do corrections to the path, such as conveyor tracking, WeldGuide, Force Control, SoftMove, SoftAct etc.

Continues on next page

- The *Collision Avoidance* functionality between 2 robots (or more) can only be achieved when using a MultiMove system.

RAPID instructions

There are no RAPID instructions related to this option but it is possible to enable and disable the function using the digital output signal *Collision_Avoidance*. By setting *Collision_Avoidance* to 0 the function is disabled. It is recommended to enable it (set *Collision_Avoidance* to 1) as soon as the work is done that required Collision Avoidance to be disabled.

7.13 Motion Functions

7.13.1 SoftMove

7.13.1.1 SoftMove [3108-1]

General

SoftMove is a cartesian soft servo option that allows the robot to be compliant or floating in order to adjust to external forces or variations in work objects. *SoftMove* can lower the stiffness of the robot in one or several pre-defined cartesian direction(s) (in relation to either the tool or the work object) while keeping the original behavior in the other directions. The behavior of the softness is controlled by two parameters *Stiffness* and *Damping*. With *SoftMove*, the robot is compliant in the specified direction(s) only which facilitates high accuracy and reliability. The option reduces robot programming time and enables effective interaction between robot and machine, which reduces cycle time.

Features

SoftMove is used to set up softness in one of the following directions:

- one of the Cartesian directions (x, y or z)
- one of the Cartesian planes (xy, xz or yz)
- all directions (xyz)
- the plane xy and rotational around the z axis

Applications

Machine tending of different machines, for example die casting machines, injection moulding machines, machine tools, etc. Extraction of parts from machine

- Insertion of parts into the machine – robot holds or pushes
- Extraction of parts from machine
- Placing/picking a work object in a tool
- Placing a molded or cast part in a fixture
- Tool exchanging on peripheral machines
- Absorbing of shocks and vibrations

Assembly functions

- Framing - a robot holds and presses a part towards the rest of the car body while another process attaches the part to the body
- Simple assembly functions not requiring searching or fitting

Welding

- Hold-and-Weld
- Hotplate welding

Press tending

- Follow movement of press

Continues on next page

Polishing/Grinding

- Simple polishing and grinding applications with low process forces not requiring process feedback

RAPID instructions

See *Application manual - SoftMove*.

7 Specification of controller & RobotWare options

7.14.1.1 MultiMove [3102]

7.14 Motion Coordination

7.14.1 MultiMove

7.14.1.1 MultiMove [3102]

General

The purpose of MultiMove is to let one robot controller handle several mechanical units. This allows advanced coordination.

A MultiMove system is configured with one main controller and manipulator, and one or two additional controllers with their respective manipulators.

- [3102-1] Main robot Coordinated
- [3102-2] Main robot Independent
- [3102-3] Additional robot

The MultiMove option includes the following options:

- Multitasking
- Multiple Axis Positioner (for the option MultiMove Coordinated)

The option [3102-3] *Additional robot* includes a 4 meter cable for connecting the additional controller with the main controller.

See *Application manual - MultiMove*.

The safety signals are connected to the main controller.

Features

A MultiMove configuration can consist of:

- Up to three cabinets, each powering one manipulator and up to totally six additional axes, allowing for a maximum of 24 axes in total.¹ This limit includes the main drives for the three 6-axis manipulators (3 x 6 axes) plus six additional drives for additional axis motors.
- Up to seven motion tasks

¹ The number of additional axes depends on the controller encapsulation.

Configuration examples

The following example has 24 axes.

- 1x IRB 4600, OmniCore V400XT, 6x additional drive units
- 1x IRB 4600, OmniCore V250XT, 0x additional drive units
- 1x IRB 4600, OmniCore V250XT, 0x additional drive units

The following example has 24 axes.

- 1x IRB 2600, OmniCore V250XT, 3x additional drive units
- 1x IRB 2600, OmniCore V250XT, 3x additional drive units
- 1x IRB 2600, OmniCore V250XT, 0x additional drive units

The following example has 22 axes.

- 1x IRB 2600, OmniCore V250XT, 3x additional drive units
- 1x IRB 1600, OmniCore C90XT, 1x additional drive units

Continues on next page

- 1x IRB 1600, OmniCore C90XT, 0x additional drive units

Application

Some examples of applications:

- Several manipulators can work synchronized on the same work object.
- One manipulator can move a work object while other manipulators work on it.
- Several manipulators can cooperate to lift heavy objects.

Limitations

This option cannot be combined with option [3039-X].

This option cannot be combined with option [3006-1].

MultiMove and ISO 10218-1:2011

MultiMove is an option allowing up to three manipulators to be controlled from a single controller. In the context of ISO 10218-1, the ABB MultiMove configuration is considered to be one robot.

A risk assessment, as outlined in ISO 10218-2, shall always be performed on the robot cell.

7 Specification of controller & RobotWare options

7.15.1 Tool Control [3109-1]

7.15 Motor Control

7.15.1 Tool Control [3109-1]

General

Tool Control can be used to control a servo tool, for example in a spot weld application or servo driven grippers. *Tool Control* makes it possible to close the tool to a specific plate thickness and force, and maintain the force during the process until the tool is requested to be opened.

Target users are advanced system integrators who want to develop customer specific application software, such as spot welding packages.

Features

- Position control (gap)
- Force control
- Dynamic and kinematic model (tool configured as additional axis)
- Quick Start code package

Performance

The tool is configured as an additional axis, which ensures optimal performance, regarding path following and speed. (Dynamic and kinematic model)

The option *Tool Change* can be added to the system in order to allow a switch between two or more servo tools which will then utilize the same drive unit and measurement board.

Requirements

A specific servo tool parameter file must be installed in the controller for each servo tool. The parameter file is optimized for each system, regarding system behavior and motion/process performance.

For information on drive module & measurement board see *Application manual - Additional axes*.

Limitations

- *Tool Control* can only be applied to one robot in a MultiMove configuration.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
STClose	Close a servo tool with a predefined force and thickness
STOpen	Open a servo tool
STCalib	Calibrate a servo tool
STTune	Tune motion parameters for a servo tool
STTuneReset	Reset tuned motion parameters
STIsClosed	Test if a servo tool is closed

Continues on next page

Instruction	Description
STIsOpen	Test if a servo tool is open
STCalcTorque	Calculate the motor torque for a servo tool
STCalcForce	Calculate the programmable force for a servo tool

7 Specification of controller & RobotWare options

7.15.2.1 Independent Axis [3111-1]

7.15.2 Independent Axis

7.15.2.1 Independent Axis [3111-1]

General

The option *Independent Axis* is used to make an additional axis (linear or rotating) run independently of the other axes in the robot.

The option also includes the function *Axis Reset*, which can reset the axis position counter from RAPID. *Axis Reset* is useful for repeated maneuvers, where mechanical reset of the axis (mechanically turning back the axis) would mean loss of cycle time in the process.



Note

In the current version, additional axis is not supported.

Features

- Movement of an axis, independent of the robot motion
- Independent movements, programmed with absolute or relative positions
- Continuous rotational/linear movement of an axis
- Speed regulation of the independent axis
- Reset of Axis position counter (axes 4, 6 and additional (rotating) axes)

Application

Application	Description
Axis Reset	<p>When polishing, a large work area is sometimes needed on the robot axis 6 in order to be able to carry out final polishing without stopping. Assume that the axis has rotated 3 turns, for example. It can now be reset using this function, without having to physically rotate it back again, this will reduce cycle times.</p> <p>Pick and place - In a pick and place operation using, the rotation angle of axis 4 can increase and move towards the limit. Instead of moving axis 4 back to zero angle it can be reset saving cycle time in the application.</p>

Performance

The movements will be made with the same performance as additional axes without *Independent Axis*.

Requirements

There are no software or hardware requirements for this option.

Limitations

If an axis has a gear ratio which is not an integer number, fine calibration is required after resetting the revolution counter on the serial measurement board, if a precise axis position is needed in the application.

Continues on next page

Internal and customer cabling and equipment may limit the ability to use independent axis functionality on axis 4 and 6.

The option is not possible to use together:

- 4 axis robots, for example IRB 910INV
- *Robot safety supervision* options [3043-x]
- Tool change

For information about what capability a specific robot's axis 4/6 has, contact ABB.

RAPID instructions and functions

RAPID instructions included in this option:

Instructions	Description
IndCMove	Running an axis continuously
IndDMove	Running an axis independently a specified distance
IndRMove	Running an axis Independently to a position within one revolution, without taking into consideration the number of turns the axis had rotated earlier
IndAMove	Running an axis Independently to an absolute position
IndReset	Change an axis to dependent mode and/or reset the working area

RAPID functions included in this option:

Instructions	Description
IndInpos	Checking whether or not an independent axis has reached the programmed position
IndSpeed	Checking whether or not an independent axis has reached the programmed speed

7 Specification of controller & RobotWare options

7.16.1.1 Program feature bundle [3112-1]

7.16 RAPID Program Features

7.16.1 Program feature bundle

7.16.1.1 Program feature bundle [3112-1]

About Program feature bundle

The option *Program feature bundle* gives you access to the included options:

- *Path Recovery*, see [Path Recovery \[3113-1\] on page 169](#)
- *Multitasking*, see [Multitasking \[3114-1\] on page 170](#)

7.16.2 Path Recovery

7.16.2.1 Path Recovery [3113-1]

General

The option *Path Recovery* is used to store all system data, when an interrupt occurs (fault message or other) and restore them after necessary actions have been taken.

Features

- Store path data (all current system information)
- Restore path data (all system information, as was before interrupt/fault)

Application

Application	Description
Service of process equipment	When an error message occurs, the position/path data can be stored and the robot moves automatically to a service area. After service, the robot moves back to the exact same position, including all system data and continues welding.

Performance

There is no performance data available for this option.

Requirements

There are no software or hardware requirements for this option.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
StorePath	Stores the path when an interrupt occurs
RestorePath	Restores the path after an interrupt
PathRecStart	Start the path recorder
PathRecStop	Stop the path recorder
PathRecMoveBwd	Move path recorder backwards
PathRecMoveFwd	Move path recorder forward

7 Specification of controller & RobotWare options

7.16.3.1 Multitasking [3114-1]

7.16.3 Multitasking

7.16.3.1 Multitasking [3114-1]

General

The option *Multitasking* gives the possibility of executing up to 20 programs (tasks) in parallel, including the main program. *Multitasking* can be used to control peripheral equipment or other processes concurrently with robot motion.

Features

- Automatic start at power on
- START/STOP commands for task execution
- Tasks are programmed using standard RAPID instructions
- Priorities can be set between tasks
- Communications between tasks using signal persistent data or Rapid Message Queue

Application

Application	Description
Supervision	A task can be used to continuously monitor certain signals even when the main program has stopped, thus taking over the job traditionally allocated to a PLC.
Operator dialogue	An operator dialogue might be required at the same time as the robot is performing, for example welding. By putting this operator dialogue into a parallel task, the operator can specify input data for the next work cycle without having to stop the robot.
Control of external equipment	The robot can control a piece of external equipment in parallel with the normal program execution.

Performance

It is possible to configure if the task shall react on START/STOP requests or if it shall start automatically. In the later case it will not stop at emergency stops, which can be useful for some applications.



Note

The response time of *Multitasking* does not match that of a PLC. *Multitasking* is primary intended for less demanding tasks.

The longer time is for cases when heavy calculation of movement is performed.

Requirements

There are no software or hardware requirements for this option.

Continues on next page

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
WaitSyncTask	Synchronize several program tasks at a special point in each program.
IRMQMessage	Orders RMQ interrupts for a data type
RMQFindSlot	Find a slot identity from the slot name
RMQGetMessage	Get an RMQ message
RMQGetMsgData	Get the data part from an RMQ message
RMQGetMsgHeader	Get header information from an RMQ message
RMQSendMessage	Send an RMQ data message
RMQSendWait	Send an RMQ data message and wait for a response
RMQGetSlotName	Get the name of an RMQ client

7 Specification of controller & RobotWare options

7.17.1.1 FTP & SFTP Client [3116-1]

7.17 Communication

7.17.1 File Transfer Protocol

7.17.1.1 FTP & SFTP Client [3116-1]

General

The option *FTP & SFTP Client* makes it possible to read information from a remote computer, directly from the controller.

Once the application protocol is configured, the remote computer can be accessed in the same way as the controller's internal hard disk.

Performance

There is no performance data available for this option.

Requirements

The external computer must have an FTP or an SFTP server.

The FTP client has been validated against the following FTP servers:

- FileZilla
- MS IIS
- Linux Ubuntu

The SFTP client has been validated against the following SFTP servers:

- Rebex
- Complete
- Cerberus

RAPID instructions

There are no RAPID instructions included in this option.

7.17.2 Network File System

7.17.2.1 NFS Client [3117-1]

General

The option *NFS client* (Network File System) makes it possible to read information from a remote computer, directly from the controller.

Once the application protocol is configured, the remote computer can be accessed in the same way as the controller's internal hard disk.

Performance

There is no specific performance data available for this option.

Requirements

The external computer must have an NFS server.

RAPID instructions

There are no RAPID instructions included in this option.

7 Specification of controller & RobotWare options

7.17.3.1 IoT Data Gateway [3154-1]

7.17.3 IoT Connectivity

7.17.3.1 IoT Data Gateway [3154-1]

General

The option *IoT Data Gateway* [3154-1] is needed to enable IoT Gateway to communicate with RobotWare.

IoT Gateway is an application that share information from the robot controller with other parts of the process/production unit. The information can be configured according to the OPC UA standard format or MQTT with a customer defined format.

The IoT Gateway application software is deployed/installed on a customer Windows PC or Server, connected to the same network as the robot controller(s) and can access data from multiple robot controllers at the same time (each robot controller require to have the option *IoT Data Gateway*).

The application software package is available for download at the ABB Developer Center (robotstudio.com), <https://developercenter.robotstudio.com>

In the download package, an Application manual (3HAC078375-001) and video tutorial are available illustrating the configuration and usage of the IoT Gateway.

7.18 User Interaction Application

7.18.1 RobotStudio Connect

7.18.1.1 RobotStudio Connect [3119-1]

General

RobotStudio is the programming, configuration and commissioning tool for OmniCore controllers. RobotStudio acts directly on the active data in the controller and enables activities like RAPID programming, update/booting of the systems software and system configuration. Connecting RobotStudio directly to the local management port is enabled by default, but connecting RobotStudio over a public network requires option *RobotStudio Connect* [3119-1].

Features

This option allows RobotStudio to connect to the robot using the public network interface (WAN)

Application

This feature is applicable for the RobotStudio PC product.

Performance

There is no performance data available for this feature

Requirements

There are no additional software or hardware requirements for this feature

7 Specification of controller & RobotWare options

7.18.2.1 Limited app package [3120-1]

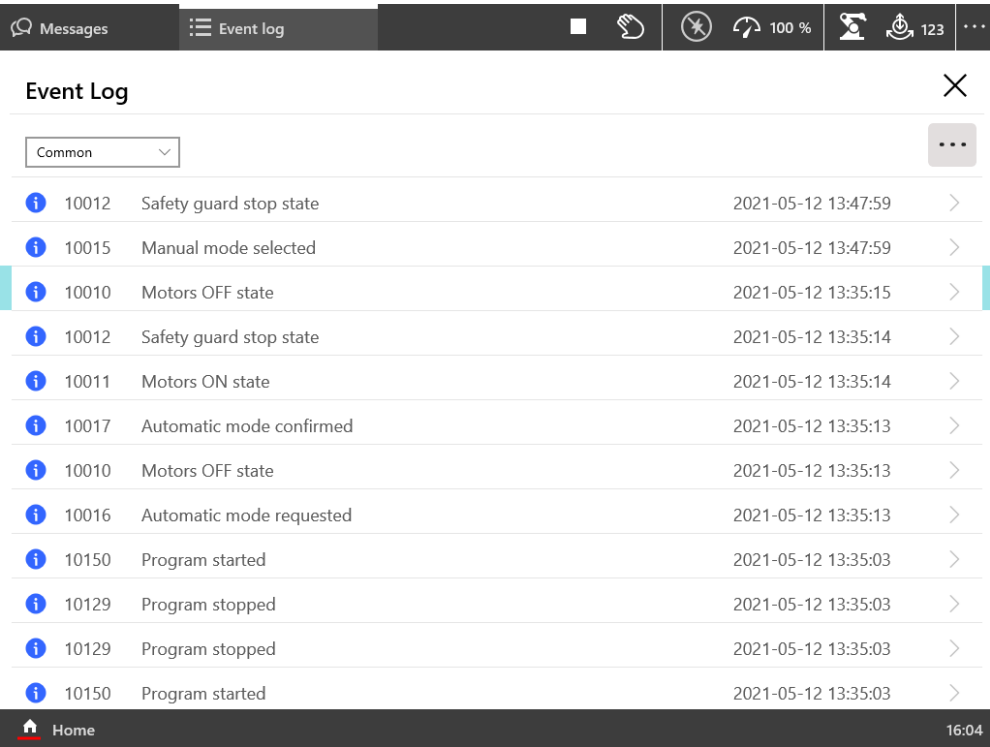
7.18.2 FlexPendant base apps

7.18.2.1 Limited app package [3120-1]

General

The option *Limited app package* contains base functionality to operate the robot system. This base version of software for the FlexPendant allows for the most crucial functionality, like jogging the robot, calibration of the robot, basic operation (start, stop, loading programs), read and write I/O signals, event log and operator messages.

For more information about what functionality is available in this option, see [FlexPendant applications on page 59](#).



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Continues on next page

7 Specification of controller & RobotWare options

7.18.2.1 Limited app package [3120-1]

Continued

Messages


Event log


100 %


123


Settings


Find a setting


 **System**
About, rename this robot, hardware devices, software resources


 **Network**
Network status, configuration


 **ABB Ability™**
Connectivity & services


 **Backup & Recovery**
Reset, restart, installer, backup & restore

 **Time & Language**
Set language, date & time

 **Personalization**
Programmable keys

 **Update**
Update FlexPendant and Controller software

 **Advanced**
Path and Jog supervisions

 **Safety Controller**
Safety Controller Settings and Control

Log out Default User

Restart Controller

Home

Settings

16:13

xx1800003655

Messages

Event log

100 %

123

Signals

32 Items Filter: All Signals

Search by name

Name	Value	Label	Type	Device	
ACOK	0		DI	DrvSys	...
Auto	0		DO	IoPanel	...
AutoReqExt	0		DI	IoPanel	...
AutoReqTPU	0		DI	IoPanel	...
AXCDCOK	0		DI	DrvSys	...
BrakeEn	0		DO	DrvSys	...
BrakeFb	0		DI	DrvSys	...
BrakeOk	0		DI	DrvSys	...
BrakeSupply	0		DI	DrvSys	...

Home

I/O

16:14

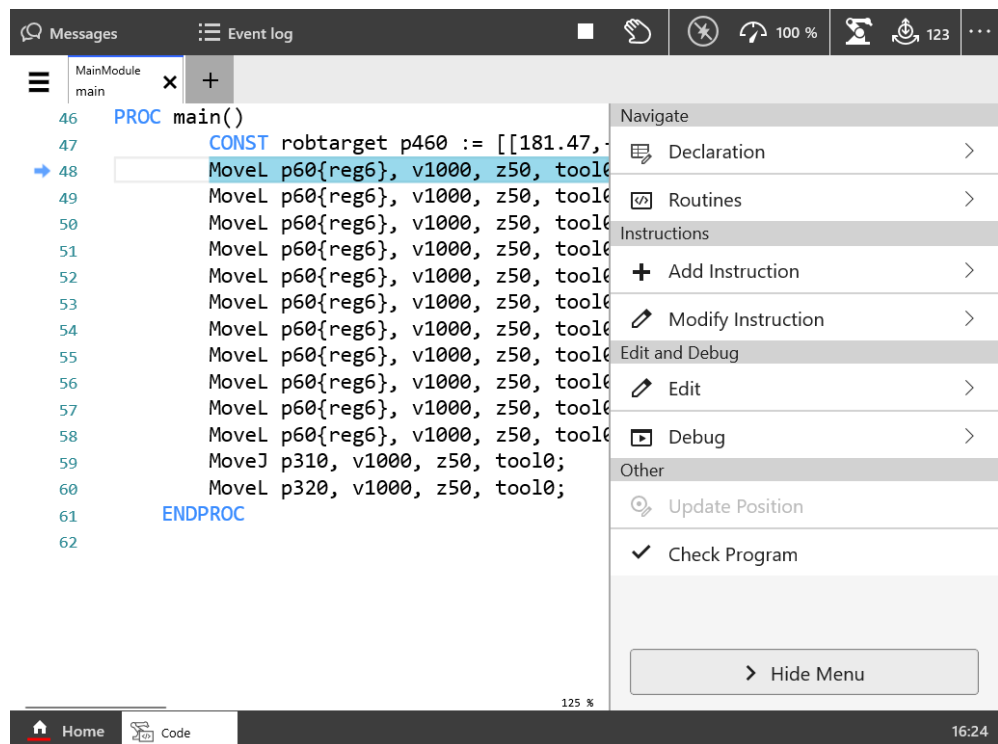
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7 Specification of controller & RobotWare options

7.18.2.1 Limited app package [3120-1]

Continued



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7.18.2.2 Essential app package [3120-2]

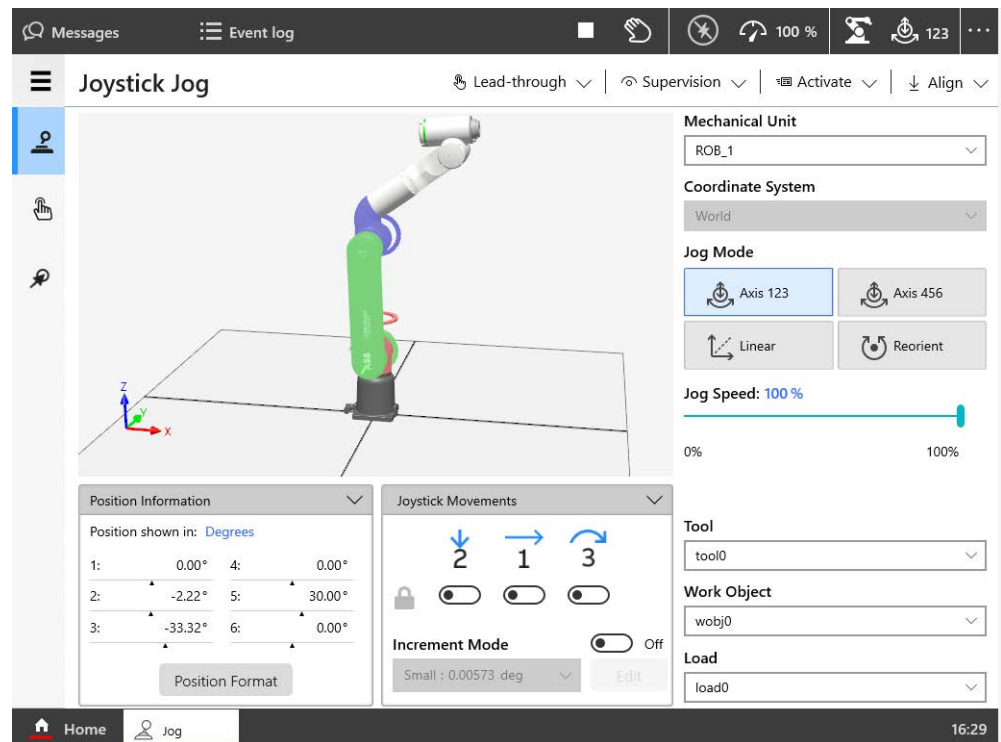
General

The option *Essential app package* includes features that will make it easy and efficient to work with the robot system.

Jog functionality is improved with 3D illustrations, and dashboards makes it easy to view the system status at a glance.

The option *Essential app package* includes option *Limited app package* [3120-1].

For more information about what functionality is available in this option, see [FlexPendant applications on page 59](#).



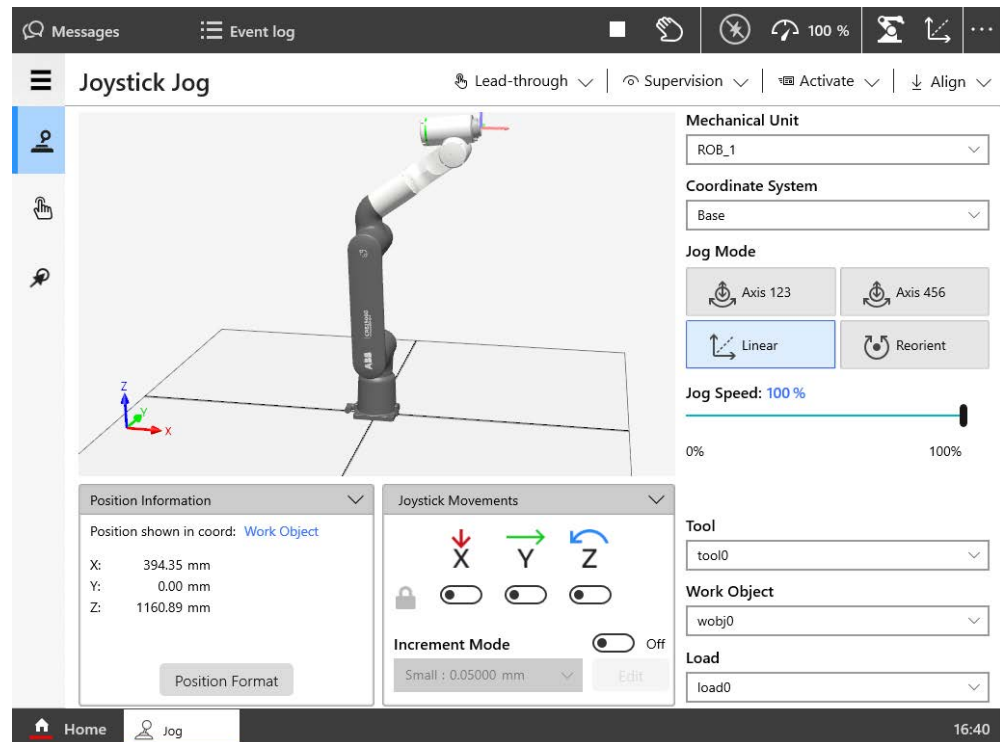
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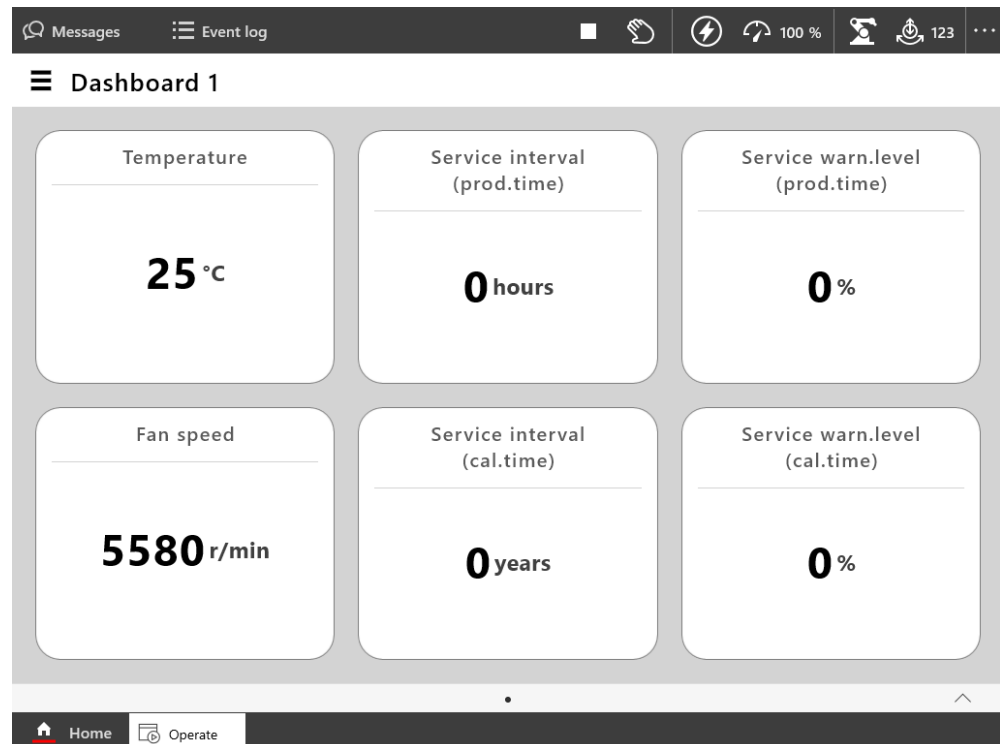
7 Specification of controller & RobotWare options

7.18.2.2 Essential app package [3120-2]

Continued



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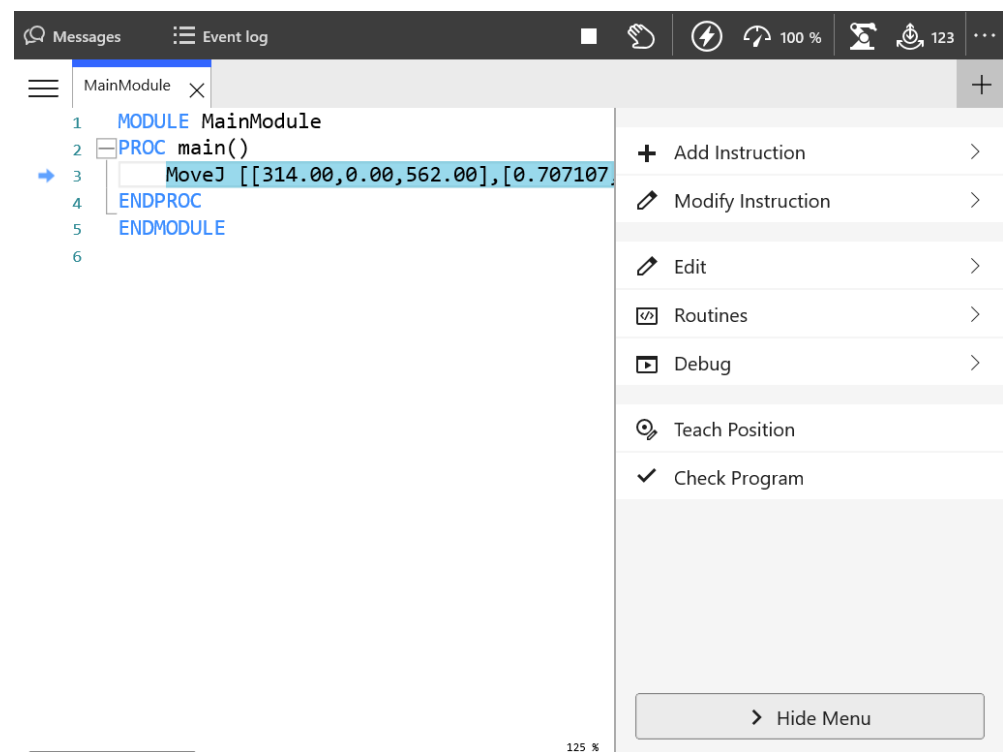
7.18.3 FlexPendant independent apps

7.18.3.1 Program package [3151-1]

General

The option *Program package* is required in order to create new and edit existing RAPID programs on the FlexPendant. If the program package is not selected with the FlexPendant, RobotStudio must instead be used on a separate PC to create and edit RAPID programs.

For more information about what functionality is available in this option, see [FlexPendant applications on page 59](#).



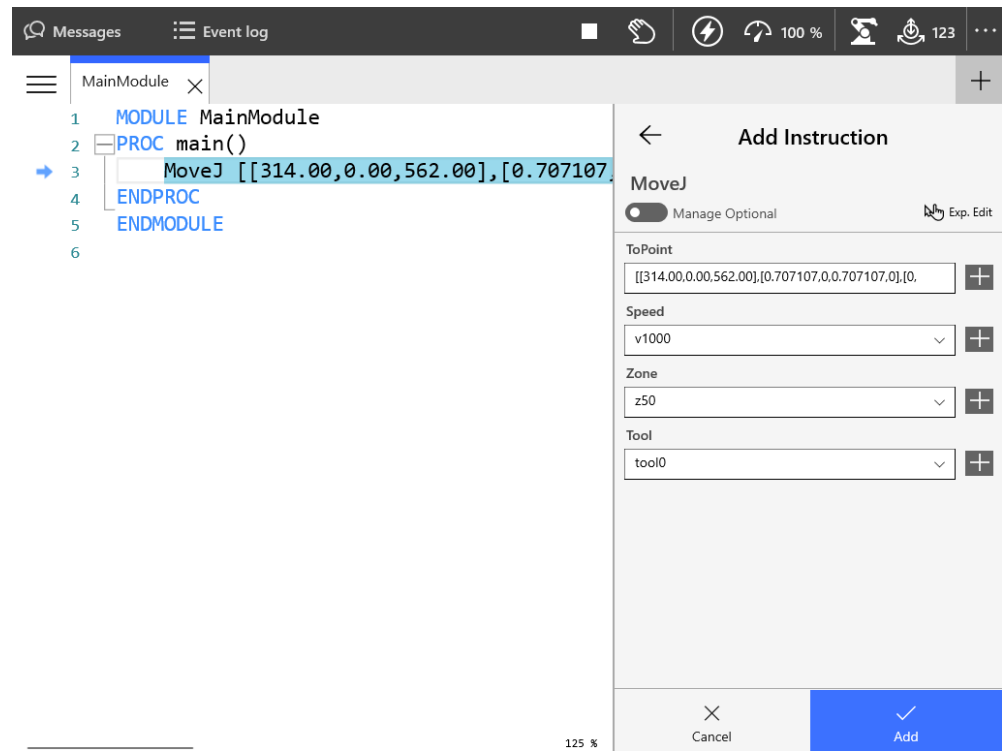
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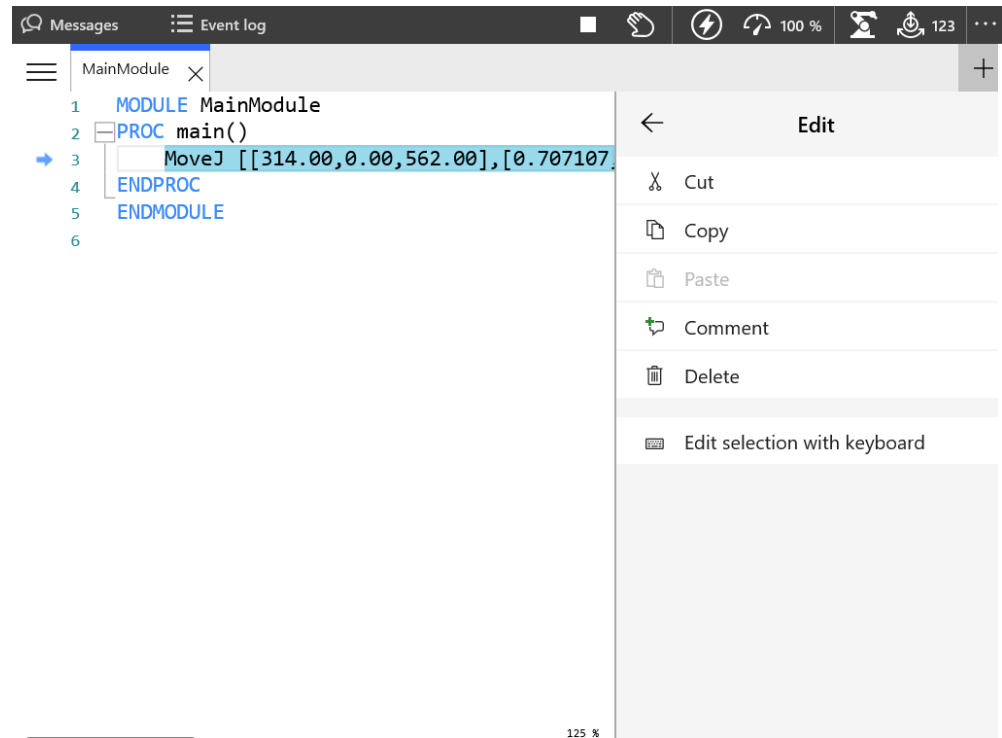
7 Specification of controller & RobotWare options

7.18.3.1 Program package [3151-1]

Continued



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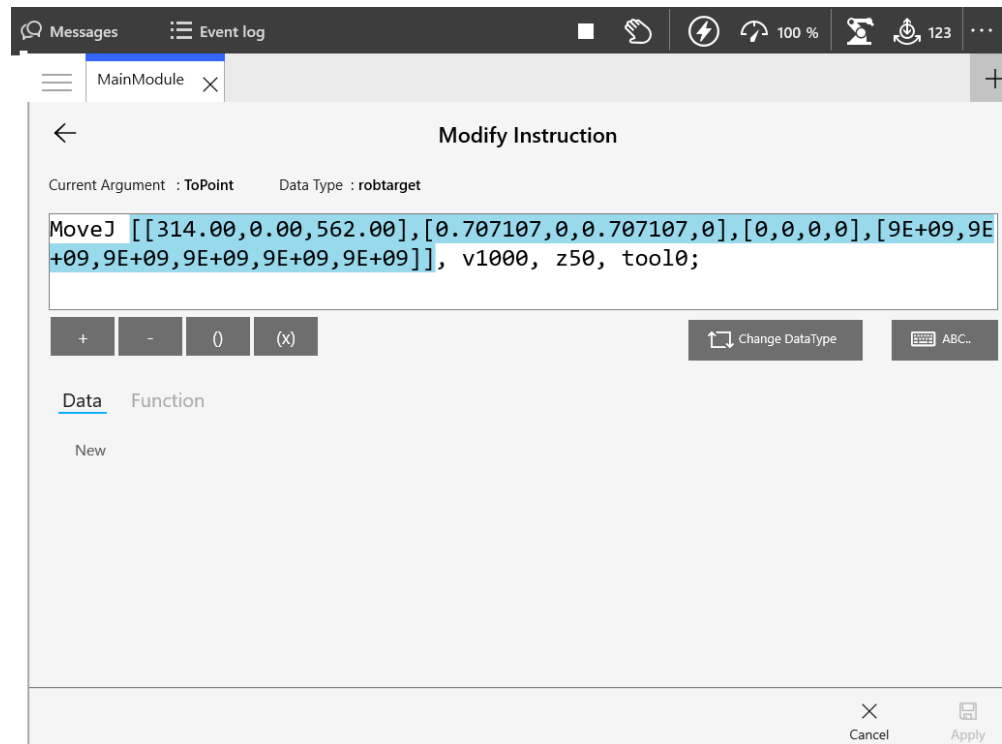
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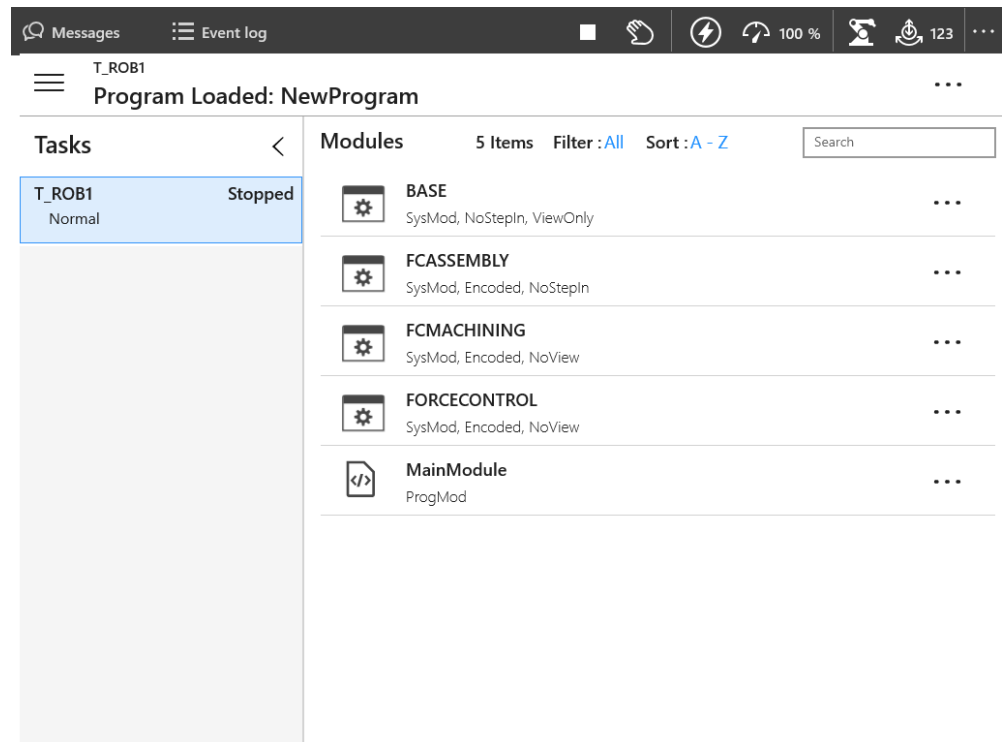
7 Specification of controller & RobotWare options

7.18.3.1 Program package [3151-1]

Continued



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Requirements

The option *Program package* requires option *FlexPendant base apps* [3120-x].

Continues on next page

7 Specification of controller & RobotWare options

7.18.3.1 Program package [3151-1]

Continued

Limitations

The FlexPendant options are not tied to the FlexPendant hardware, but instead to OmniCore controller. This means a FlexPendant runs the apps licensed to the controller its connected to.

The same shared FlexPendant can accordingly have different apps on different robots.

7.19 Engineering Tools

7.19.1 RobotWare Add-in

7.19.1.1 RobotWare Add-In prepared [3121-1]

General

The option *RobotWare Add-In prepared* makes it possible to run licensed Add-Ins from 3rd party developers on the robot controller.

Features

Add-Ins allow to create installable additional software packages that extend the capabilities offered by RobotWare, making ABB's robot controllers even smarter and even more user-friendly. Creating RobotWare Add-Ins is also the recommended way for 3rd party developers to add new features into RobotWare.

An Add-In can include a number of RAPID modules, system modules, or program modules which hold the basic code for the Add-In. The Add-In also includes some files for loading and configuration at start up. The Add-In may also include .xml files with event log messages in different languages.

An Add-In can also consist of more advanced coding, such as C# code, for FlexPendant applications. For more advanced coding, use RobotStudio SDK applications.



Note

The RobotWare option *RobotWare Add-In prepared* is only needed for licensed Add-Ins. It is not needed for open Add-Ins or Add-Ins delivered together with RobotWare, for example track motion and positioners.

For more information, see *Application manual - RobotWare add-ins*.

Application

Add-Ins can be used for any application, equipment, or functionality that extends the capabilities offered by RobotWare.

Performance

There is no performance data available for this option.

Requirements

Unlicensed, open, Add-Ins

What you need from ABB to package and run your own open Add-In is:

- RobotWare Add-In Packaging tool

Licensed Add-Ins

What you need from ABB to package and run your own licensed Add-In is:

- RobotWare Add-In Packaging tool

Continues on next page

7 Specification of controller & RobotWare options

7.19.1.1 RobotWare Add-In prepared [3121-1]

Continued

- a license certificate for the RobotWare Add-In Packaging tool for your Add-In name
- RobotWare option *RobotWare Add-In prepared*

To license the Add-In, you will also need:

- License Generator
- a publisher certificate
- a licensing certificate for the License Generator

RAPID instructions

There are no RAPID instructions included in this option.

7.19.2 Path Corrections

7.19.2.1 Path Corrections [3123-1]

General

The option *Path Correction* changes the robot path according to the user input. The robot can thus follow/track a contour, such as an edge or a seam.

The performance is limited by RAPID, which provides the corrections. When the correction is written with `CorrWrite`, it is taken into account immediately. The path corrections are entered from the RAPID program. *Path Correction* have to be made in the path coordinate system.

Path correction can be used with CAP, RobotWare Arc, linear move instructions, `Trigg` instructions, and `Search` instructions.

Features

- Adjust a robot path at a user set offset
- Read current path offset
- Change path on the fly

Application

Application	Description
Path offset	Mainly used in arc welding, to adjust a welding path.

Performance

Minimum offset: 0.1 mm.

Requirements

There are no additional software or hardware requirements for this option.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
<code>CorrCon</code>	Activating path correction
<code>CorrDisCon</code>	Deactivating path correction
<code>CorrRead</code>	Read current path correction
<code>CorrWrite</code>	Changing path correction
<code>CorrClear</code>	Removes all correction generators

7.19.3 Automatic Path Planning

Introduction to *Automatic Path Planning*

The *Automatic Path Planning* is a self-contained path planning server built for Windows and Linux. The software addresses both offline and online applications that can benefit from kinematics, collision-checking, and automatic path planning services.



CAUTION

Automatic Path Planning will produce collision-free paths under the assumption that the virtual model is an accurate representation of the robot cell, and that the kinematic model of the robot has no errors. It is up to the user verify the accuracy of the model and provide *Automatic Path Planning* with safety margins that are large enough to compensate for errors in the kinematics and the virtual model. SafeMove can be used to set up safe zones for areas where people can be present, or obstacles that are not represented in the virtual model.

After adding a robot, attachments to the robot (for example, a robot tool from a CAD model), obstacles from CAD models or point clouds, the server will, on request, return a collision-free path from a starting target (RobTarget or JointTarget in RAPID) to a goal target. The server will try to find the shortest path from the start to the end. The returned path is a sequence of targets that are to be sent to the robot controller. The path does not have a speed parameter, as the server is a geometrical path planner and has no notion of motion time. Since the path is optimized in the joint space it is singularity-free. Furthermore, the zones of the targets are optimized to be as large as possible so that the motion is smooth, efficient, and fast.

The time needed by the server to generate a path depends on the complexity of the problem, the number of obstacles, and the available CPU performance, and can range from a few tens of milliseconds to some seconds. The server uses multi-threading to speed-up computations, and the user can configure the number of threads that can be used by the server.

Supported robots

The following robots are supported by the path planning server:

- Six DOF elbow IRB robots (Elbow), for example, IRB 5710, CRB 1100
- Six DOF parallel rod robots (ParallelRod), for example, IRB 8700
- GoFa robots (ElbowWristOffset), CRB 15000
- Single arm YuMi (RedundantRobots), IRB 14050
-

The name within parentheses is the corresponding enum name in the proto file. The difference between the Elbow type and the ElbowWristOffset type is that the former has a spherical wrist, while the latter has a z offset in the wrist.

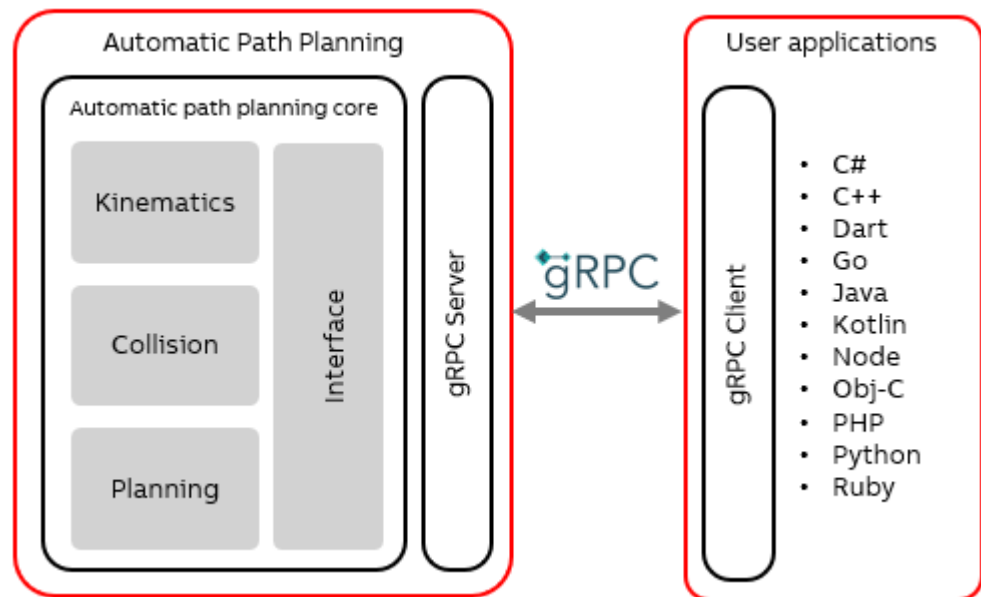
Paint robots are not supported.

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Communication

The *Automatic Path Planning* is using gRPC, an open-source high performance Remote Procedure Call (RPC) framework from Google™ that can run in any environment. The client can be implemented in any language supported by the gRPC including C++, C#, Python, and Java. The server has no relation to RobotWare.

The following figure shows an overview of the server architecture. Tests show communication overhead with gRPC to be around 1ms for most services. The latency will depend on the message size. Large message loads (for example, sending a large point cloud) will result in higher latencies. Messages in gRPC are encoded in binary, using Google Protobuf.



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Ordering details

The *Automatic Path Planning* is ordered separately from the robot.

Available options

The available options are:

- 4400-1 IRB 6-axis robot
- 4400-2 IRB 14050
- 4400-3 CRB 1100
- 4400-4 CRB 1300
- 4400-5 CRB 15000

Related information

See *Application manual - Automatic Path Planning*, 3HAC092826-001.

7.19.4 Externally Guided Motion

7.19.4.1 Externally Guided Motion [3124-1]

General

The option *Externally Guided Motion* (EGM) offers three different features:

- EGM Position Stream is available for input via UDP sockets only. It provides the possibility to periodically send planned and actual mechanical unit (e.g. robot, positioner, track motion ...) position data from the robot controller to an external device. The message contents is specified by the Google Protobuf definition file `egm.proto`. The cyclic communication channel (UDP) can be executed in the high-priority network environment of the robot controller which ensures a stable data exchange up to 250 Hz.
- EGM Position Guidance is designed for advanced users and provides a low level interface to the robot controller, by by-passing the path planning that can be used when high responsiveness to robot movements are needed. EGM can be used to read positions from and write positions to the motion system at a high rate, every 4 ms with a control lag of 10–20 ms depending on the robot type. The references can either be specified using joint values or cartesian values. The cartesian data can be relative to any work object for robots.
- EGM Path Correction gives the user the possibility to correct a programmed robot path. The device or sensor that is used to measure the actual path has to be mounted on the tool flange of the robot and it must be possible to calibrate the sensor frame.

The corrections are performed in the path coordinate system, which gets its x-axis from the tangent of the path, the y-axis is the cross product of the path tangent, and the z-direction of the active tool frame and the z-axis is the cross product of x-axis and y-axis.

EGM Path correction has to start and end in a fine point. The sensor measurements can be provided at multiples of about 48 ms.

Features

The RobotWare option *Externally Guided Motion* gives you access to:

- Instructions to start and stop EGM Position Stream.
- Instructions to set up, activate, and reset EGM Position Guidance.
- Instructions to set up, activate, and reset EGM Path Correction.
- Instructions to initiate EGM Position Guidance movements, synchronized with RAPID execution or not, and to stop them.
- Instructions to perform EGM Path Correction movements.
- A function to retrieve the current EGM state.
- System parameters to configure EGM and set default values.
- Support of *Absolute Accuracy*.

Continues on next page

Application

The purpose of EGM Position Stream is to provide external equipment with the current and planned positions of mechanical units that are controlled by the robot controller.

Some example of applications are:

- Laser Welding, where the Laser head is controlling the Laser beam dynamically.
- Any robot mounted equipment that controls the "robot"-TCP with an external controller.

The purpose of EGM Position Guidance is to use external devices to generate position data for one or several robots. The robots will be moved to that given position.

Some examples of applications are:

- Place an object (e.g. car door or window) at a location (e.g. car body) that was given by an external sensor.
- Bin picking. Pick objects from a bin using an external sensor to identify the object and its position.

The purpose of EGM Path Correction is to use external robot mounted devices to generate path correction data for one or several robots. The robots will be moved along the corrected path, which is the programmed path with added measured corrections.

Some examples of applications are:

- Seam tracking.
- Tracking of objects moving near a known path.

Performance

EGM Position Stream can be used to read positions from and write positions to the motion system at a high rate, every 4 ms.

EGM Position Guidance can be used to read positions from and write positions to the motion system at a high rate, every 4 ms with a control lag of 10–20 ms depending on the robot type.

EGM Path Correction can handle sensor measurements at a rate of about 48 ms.

Requirements

External devices communicating with the controller via Analog Signals, Group signals or an Ethernet link (UDP). For the Ethernet link, the application protocol (UdpUc – UDP UniCast) is used.

Limitations

EGM does not support coordinated MultiMove.

Limitations for EGM Position Stream

- EGM Position Stream is available with UdpUc communication only.
- Tool data and load data cannot be changed dynamically during an active position stream.

Continues on next page

7 Specification of controller & RobotWare options

7.19.4.1 Externally Guided Motion [3124-1]

Continued

- It is not possible to stream positions of coordinated MultiMove systems.
- **Absolute Accuracy** is not supported if streaming is started using `EGMStreamStart`, but it is supported if it started using `EGMActXXX\StreamStart`.
- **EGM Position Stream** is not compatible with **EGM Path Correction**.
- It is not allowed to activate or deactivate mechanical units if **EGM Position Stream** is active.

Limitations for EGM Position Guidance

- Has to start and to end in a fine point.
- The first movement that is performed after a controller restart cannot be an EGM movement.
- Pose mode supports 6-axis robots, 4-axis palletizer robots, YuMi robots, and SCARA robots.
- It is not possible to perform linear movements using EGM Position Guidance, since EGM Position Guidance does not contain interpolator functionality. The actual path of the robot will depend on the robot configuration, the start position, and the generated position data.
- EGM Position Guidance does not support MultiMove coordinated.
- There is a limitation of one mechanical unit per motion task.
- It is not possible to use EGM Position Guidance to guide a mechanical unit in a moving work object.
- If the robot ends up near a singularity, i.e. when two robot axes are nearly parallel, the robot movement will be stopped with an error message. In that situation the only way is to jog the robot out of the singularity.
- When EGM is active, Motion Supervision can behave differently than during normal movements. The recommended action after a collision is to disable EGM and start the EGM sequence from the beginning.

Limitations for EGM Path Correction

- Supports only 6-axis robots.
- Has to start and to end in a fine point.
- The external device has to be robot mounted.
- Corrections can only be applied in the path coordinate system.
- Only position correction in y and z can be performed. It is not possible to perform orientation corrections, nor corrections in x (which is the path direction/tangent).
- When EGM is active, Motion Supervision can behave differently than during normal movements. The recommended action after a collision is to disable EGM and start the EGM sequence from the beginning.

RAPID instructions

For information about the included RAPID instructions, functions, and data types see *Application manual - Controller software OmniCore*.

7.20 Vision and sensor

7.20.1 Vision

7.20.1.1 Vision interface [3127-1]

General

ABB's Integrated Vision system provides a robust and easy-to-use vision system for general purpose Vision Guided Robotics (VGR) applications.

The system includes a complete software and hardware solution that is fully integrated with the robot controller and the RobotStudio programming environment. The vision capability is based on the Cognex In-Sight® smart camera family, with embedded image processing and an Ethernet communication interface.

RobotStudio is equipped with a vision programming environment that exposes the full palette of Cognex EasyBuilder® functionality with robust tools for 2D part location, part inspection, and identification. The RAPID programming language is extended with dedicated instructions and error tracing for camera operation and vision guidance.

For more information about the option *Integrated Vision*, see *Product specification - Integrated Vision*.

7 Specification of controller & RobotWare options

7.20.2.1.1 Conveyor Tracking [3103-1]

7.20.2 Conveyor

7.20.2.1 Conveyor Tracking

7.20.2.1.1 Conveyor Tracking [3103-1]

General

The option *Conveyor Tracking* (also known as line tracking) contains functionality which makes the robot follow a work object on a moving conveyor. While tracking the conveyor, the programmed TCP path and speed, relative to the work object, will be maintained even when the conveyor speed is changing slowly.

Features

- Linear and circular conveyors
- Up to 4 conveyors simultaneously. Switch between tracking the one or the other
- Up to 254 objects can be organized in an object queue that can be manipulated by RAPID instructions
- Possibility to define a start window on the conveyor where an object must be enter before tracking of the object can start
- A maximum tracking distance may be specified
- If the robot is mounted on a parallel track motion, the system can be configured such that the track will follow the conveyor and maintain the relative position to the conveyor
- Tracking of a conveyor can be activated *on the fly*, that is it is not necessary to stop in a fine point

Application

Any application where conveyors are used for example painting, arc welding, picking and other applications.

Performance

In automatic mode, at 150 mm/s constant conveyor speed, the tool center point (TCP) of the robot will stay within +/- 2 mm of the path as seen with no conveyor motion. This is valid as long as the robot is within its dynamic limits with the added conveyor motion. This figure depends on the calibration of the robot and conveyor and is applicable for linear conveyor tracking only.

RAPID instructions

RAPID instructions included in this option:

Instruction	Description
WaitWObj	Connects to a work object in the start window
DropWObj	Disconnects from the current object

7.20.2.2 Conv.Tracking unit int. [3041-1]

General

Encoder interface unit for conveyor tracking (DSQC2000). The network based conveyor interface provides connections for 4 encoders and 8 cameras. Network communication is used to share conveyor speed and position data with one or more robot controllers. It can be located inside a robot controller. Each of the encoder inputs supports one 2 phase encoder. Each of the camera connections consists of one digital sync input, one 24V digital trigger output and a camera power output. The camera connection may also be used for other kind of sync input sources, for example, photocells.

The option *Conv.Tracking unit int.* requires:

- *Conveyor Tracking* [3103-1] (the RobotWare option) which makes the robot follow a work object on a moving conveyor.

General	
Power supply input	24 VDC (-15/+20%), typically 200 mA (current not including power outputs)
Operating temperature	+5°C - +65°C
Ethernet LAN	2 switched LAN ports, 100Mbit
Ethernet WAN	1 WAN port, 100Mbit

Encoders	
	4 pcs (X11-X14)
Power output	24 VDC, max 120 mA With connection discovery and overload protection/diagnostic (floating pins will stay at discovery voltage of 10V at off state)
Frequency	0-20 kHz
Input current	5.2 mA at 24 VDC
Voltage levels	15 VDC < '1' < 30 VDC, -3 VDC < '0' < 5 VDC
Supported Encoder types	PNP, NPN, and Push-Pull

The following encoder is verified: Lenord & Bauer GEL 262.

Cameras	
	8 pcs (X21-X28)
Camera power output	Supplied from X20 camera power inlet. Normally 24VDC With overload protection

Sync input signal	
Power output	24 VDC, 120 mA With overload protection
Frequency	0-20 kHz
Input Current	5.2 mA at 24 VDC
Voltage levels	15 VDC < '1' < 30 VDC, -3 VDC < '0' < 5 VDC
Supported input types	PNP and Push-Pull

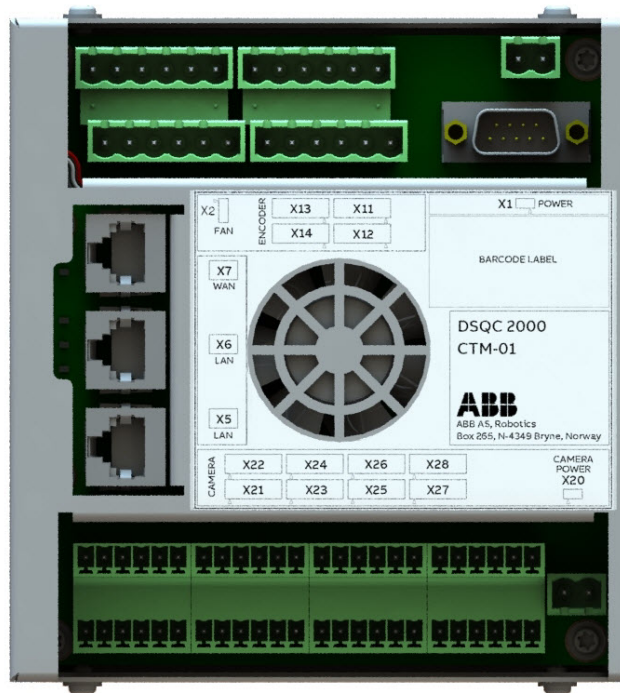
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7 Specification of controller & RobotWare options

7.20.2.2 Conv.Tracking unit int. [3041-1]

Continued

Trigger output	
Digital output	24 VDC , max 120 mA With connection discovery and overload protection/diagnostic. (Floating pins will stay at discovery voltage of 10V at off state)
Minimum load	0.1 mA



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Requirements

The option Conv.Tracking unit int. requires:

- Option *Conveyor Tracking* [3103-1] or *PickMaster Ready* [3152-x]
- Occupies 1 Ethernet port

7.20.2.3 Conv.Tracking unit ext. [3042-1]

General

Encoder interface unit for conveyor tracking (DSQC2000). It is provided as a separate unit from the controller and needs to be installed in a separate, customized cabinet.

The network based conveyor interface provides connections for 4 encoders and 8 cameras. Network communication is used to share conveyor speed and position data with one or more robot controllers. Each of the encoder inputs supports one 2 phase encoder. Each of the camera connections consists of one digital sync input, one 24V digital trigger output and a camera power output. The camera connection may also be used for other kind of sync input sources, for example, photocells.

The option *Conv.Tracking unit Ext.* requires:

- *Conveyor Tracking* [3103-1] (the RobotWare option) which makes the robot follow a work object on a moving conveyor.

General	
Power supply input	24 VDC (-15/+20%), typically 200 mA (current not including power outputs)
Operating temperature	+5°C - +65°C
Ethernet LAN	2 switched LAN ports, 100Mbit
Ethernet WAN	1 WAN port, 100Mbit
Encoders	
	4 pcs (X11-X14)
Power output	24 VDC, max 120 mA With connection discovery and overload protection/diagnostic (floating pins will stay at discovery voltage of 10V at off state)
Frequency	0-20 kHz
Input current	5.2 mA at 24 VDC
Voltage levels	15 VDC < '1' < 30 VDC, -3 VDC < '0' < 5 VDC
Supported Encoder types	PNP, NPN, and Push-Pull

The following encoder is verified: Lenord & Bauer GEL 262.

Cameras	
	8 pcs (X21-X28)
Camera power output	Supplied from X20 camera power inlet. Normally 24VDC With overload protection
Sync input signal	
Power output	24 VDC, 120 mA With overload protection
Frequency	0-20 kHz
Input Current	5.2 mA at 24 VDC
Voltage levels	15 VDC < '1' < 30 VDC, -3 VDC < '0' < 5 VDC

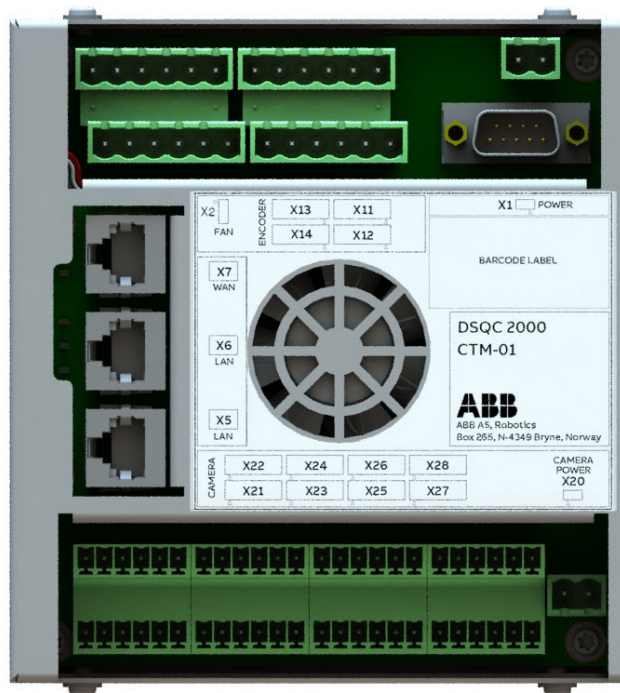
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7 Specification of controller & RobotWare options

7.20.2.3 Conv.Tracking unit ext. [3042-1]

Continued

Sync input signal	
Supported input types	PNP and Push-Pull
Trigger output	
Digital output	24 VDC, max 120 mA With connection discovery and overload protection/diagnostic. (Floating pins will stay at discovery voltage of 10V at off state)
Minimum load	0.1 mA



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Requirements

The option *Conv.Tracking unit ext.* requires:

- Option *Conveyor Tracking* [3103-1] or *PickMaster Ready* [3152-x]
- Occupies 1-2 Ethernet port(s)

Limitations

The possible order combinations of option *Conv.Tracking unit int.* and option *Conv.Tracking unit ext.* is up to two units.

7.21 Process Interface

IMM Interface [3213]

IMM (Injection Mould Machines) interface offers double channel signal communication between injection moulding machines and the robot controller. The option follows the standards from Euromap (European Committee of Machinery Manufacturers for the Plastics and Rubber Industries) and SPI (Society of Plastics Industry).

Option	Description
3213-2	Euromap67 and SPI AN146

The option includes a Euromap connector on the connector plate.

To configure the IMM input and output signals in RobotWare, I/O configuration files are available in the RobotWare installation in the folder *Utility*. In robot test mode, when the machine is disconnected, the controller jumper plug can be used.

Requirements

This option requires the option [3032-1] or [3035-1].

For additional devices such as gripper, conveyor, additional scalable I/O modules may be needed.

IMM Interface Cable [3214]

Option	Description
3214-1	IMM Cable 10m
3214-2	IMM Cable 15m

These options require option [3213-2].

7 Specification of controller & RobotWare options

7.22.1.1.1 PickMaster Cell Ready [3152-1]

7.22 Packaging

7.22.1 PickMaster Twin

7.22.1.1 PickMaster Ready

7.22.1.1.1 PickMaster Cell Ready [3152-1]

General

The option *PickMaster Cell Ready*

- Checked by PickMaster Runtime when connecting to a robot, during commissioning when configuring position source and when starting a recipe
- The license is needed to enable PickMaster Runtime with vision for one robot
- Digital I/O is needed for PickMaster functions
- The option is used with Conveyor Tracking options: *Conv. Tracking unit ent.* [3041-1], *Conv. Tracking unit ext.* [3042-1]

Includes RobotWare options

- *Conveyor Tracking* [3103-1]
- *PickMaster Vision Ready* [3153-1]

7.22.1.1.2 PickMaster Robot Ready [3152-2]

General

The option *PickMaster Robot Ready*

- Checked by PickMaster Runtime when connecting to one robot without vision and when starting a recipe
- The license is needed for a robot to be included in PickMaster Runtime
- Digital I/O is needed for PickMaster functions
- The option is used with Conveyor Tracking options: *Conv. Tracking unit ent.* [3041-1], *Conv. Tracking unit ext.* [3042-1]

Includes RobotWare option

- *Conveyor Tracking* [3103-1]

7 Specification of controller & RobotWare options

7.22.1.2.1 PickMaster Vision Ready [3153-1]

7.22.1.2 PickMaster Vision

7.22.1.2.1 PickMaster Vision Ready [3153-1]

General

The option *PickMaster Vision Ready*

- Checked by PickMaster Runtime during commissioning when configuring position source and when starting a recipe
- The License is needed to receive positions generated by a sensor, either the standard vision or External Sensor
- Valid for multiple sensor driven position sources
- The option is included in *PickMaster Cell Ready* [3152-1]

Requirements

The option *PickMaster Vision Ready* requires option *PickMaster Robot Ready* [3152-2]

7.23 Application Spot welding

7.23.1 Spot welding [3417-x]

7.23.1.1 Spot option and features

The Spot options

Spot is a general and flexible software platform for creation of customized and easy to use function packages for different types of spot welding systems and process equipment.

There are three different main **Spot** options supporting spot welding.

- The *Spot Welding Standard* option provides support for sequential welding with **one servo gun**, robot held or stationary. Can also be used for servo guns without mechanical equalizing systems.
- The *Spot Welding Premium* option provides support for sequential welding with **one servo gun**. It is also possible to install multiprocess support for **up to four servo guns** at the same time. Can also be used for servo guns without mechanical equalizing systems using different software features included.
- The *Spot Welding Premium+* option has the same functionality as **Spot Welding Premium**, but also with the possibility to search with the movable gun arm to compensate for varying geometry and access to process related data via a log file or RAPID interface.

All Spot options provide dedicated spot welding instructions for fast and accurate positioning combined with gun manipulation, process start and supervision of the different gun equipment.

Communication with the external welding equipment is done with standard I/O interface.

The Spot options are general and can be extensively customized. They have a default "template" functionality after installation, that can easily be customized to fit the surrounding equipment's by changing I/O signals, configuration data from RobotStudio.

Distribution

The Spot Welding software is distributed as a separate RobotWare add-in product, SpotWare for OmniCore. This allows for independent release cycles not dependent on the RobotWare releases.

Any version of the product can be downloaded from the RobotStudio Add-Ins Gallery.

Spot Welding requires a licence for one of the following options:

- [3417-1] Spot Welding Standard
- [3417-2] Spot Welding Premium
- [3417-3] Spot Welding Premium+

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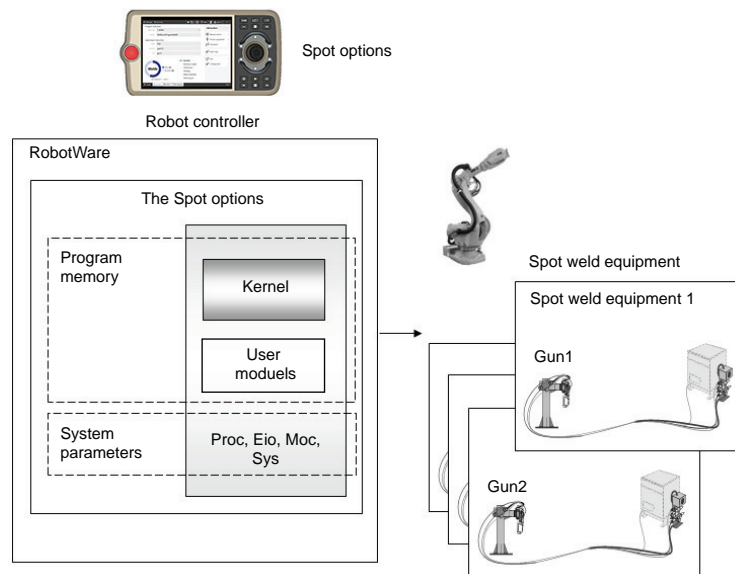
7 Specification of controller & RobotWare options

7.23.1.1 Spot option and features

Continued

Overview of the Spot options

The Spot software can be customized to handle different types of process equipment, the picture below shows schematic examples of different spot welding system variants.



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Features

The Spot software packages contain the following features:

- Fast and accurate positioning using the unique *QuickMove* and *TrueMove* concept.
- Gun pre-closing, gun closing will be synchronized with robot reaching the weld position to save cycle time.
- Software equalizing functions.
- Support for mechanical gun equalizing systems.
- Support functions for tip wear management.
- Constant or changeable gun force during welding for servo guns.
- Gravity compensation of gun force during welding.
- Calibration functions for servo guns.
- Detection of missing or improper plates for servo guns.
- Reverse execution with gun control.
- Manual actions for welding and gun control.
- Support for fast tool changing between up to 8 different servo guns. Note that this requires the option *3110-1 Servo Tool Change* (Included in *3417-2 Spot Welding Premium* and *3417-3 Spot Welding Premium Plus*).
- Support for simultaneous welding with up to four guns at the same time. Note that this requires the option *3417-2 Spot Welding Premium* or *3417-3 Spot Welding Premium Plus*.

Continues on next page

- Several simulation possibilities for test purposes.
- Weld error recovery with automatic re-weld.
- Wide customizing possibilities, process data types, spotdata, gundata, such as weld counters and tip wear data, for each used gun.
- Built in error handling and possibility for customizable user-defined supervision and error recovery.
- A dedicated Spot operator interface on the FlexPendant.
- Possibility to run some Spot functionality without a robot selected, i.e. a stand-alone controller system.
- Possibility for weld process data access. Note that option *3417-3 Spot Welding Premium Plus* is required.
- Possibility to search with the movable gun arm to compensate for varying geometry. Note that option *3417-3 Spot Welding Premium Plus* is required.

Servo Equalizing Features

The software equalizing features are embedded in all Spot options. Software equalizing allows you to solve spot welding gun equalizing without mechanical equalizing hardware on the weld gun, and thus provides an opportunity to reduce investment cost and improve productivity. Removed hardware on the gun also reduces weight, and in addition, no gravitational influence means easier optimizing when programming the robot path. Furthermore, using the software equalizing features instead of mechanical equalizing, less spare parts are required, and lower maintenance costs are achieved. Valid for:

- Robot mounted C- and X-type guns.
- Pedestal C- and X-type guns.
- Tool changing between guns with different equalizing data.
- Weld position touch up - Simplifies adjustment of the programmed weld positions.
- Release of the fixed gun arm - Automatic gun arm release from the welded sheets when the robot is moving among weld points.
- Gun arm deflection compensation - The robot program compensates for the gun arm deflection automatically.
- Tip wear measurement and compensation - The robot program automatically compensates the weld gun TCP (Tool Center Point) for tip wear without using external sensors.
- The equalizing type (mechanical or software) is determined by data set in the configuration for each used gun equipment.
- Possibility to search with the movable gun arm to compensate for varying geometry.

Spot application

The SpotWare application software can be used for any spot welding process using standard I/O interface with external equipment. The robot's movement and the spot welding process are controlled from the instructions SpotL/SpotJ and SpotML/SpotMJ.

7 Specification of controller & RobotWare options

7.23.1.1 Spot option and features

Continued

The spot welding process is specified by:

- Spot and equipment specific data types.
- Spot and equipment specific process configuration.
- I/O configuration.
- RAPID routines and global data for customizing purposes.
- User modules.

Spot instructions

Both the robot movement and the control of the spot weld equipment are embedded in the basic spot weld instructions `SpotL` and `SpotJ`. These are used for sequential welding and are available in all spot welding options. If welding with several guns simultaneously then `SpotML` or `SpotMJ` has to be used.

Instruction	Used to
<code>SpotL</code>	Control the motion, gun closure/opening and the welding process. Move the TCP along a linear path and perform a spot welding at the end position.
<code>SpotJ</code>	Control the motion, gun closure/opening and the welding process. Move the TCP along a non-linear path and perform a spot welding at the end position.
<code>SpotML</code>	Control the motion, gun closure/opening and 1 - 4 welding processes. Move the TCP along a linear path and perform spot welding with 1 - 4 gun equipments at the end position. Only available in option <i>3417-2 Spot Welding Premium</i> or <i>3417-3 Spot Welding Premium Plus</i> .
<code>SpotMJ</code>	Control the motion, gun closure/opening and 1 - 4 welding processes. Move the TCP along a non-linear path and perform spot welding with 1 - 4 gun equipments at the end position. Only available in option <i>3417-2 Spot Welding Premium</i> or <i>3417-3 Spot Welding Premium Plus</i> .
<code>IndGunMove</code>	Set the servo gun in independent mode and thereafter move the gun to a specific independent position.
<code>IndGunMoveReset</code>	Reset the independent mode for servo gun.
<code>SetForce</code>	Close the gun a predefined time then open the gun.
<code>OpenHighLift</code>	Open the pneumatic gun to the highlift position (large gap).
<code>CloseHighLift</code>	Close the pneumatic gun to the work stroke position (small gap).
<code>CalibL</code>	Calibrate the servo gun during linear movement to the programmed position.
<code>CalibJ</code>	Calibrate the servo gun during non-linear movement to the programmed position.
<code>Calibrate</code>	Calibrate the servo gun in current position without movement.
<code>STTune</code>	Tune motion parameters for the servo gun.
<code>STTuneReset</code>	Reset tuned motion parameters for the servo gun.
<code>MeasureWearL</code>	Measure the tip wear and recalculates the TCP.
<code>ReCalcTCP</code>	Measure the tip wear and recalculates the TCP.

Limitations

- Servo equalizing functions can only be applied during sequent welding (not with several guns simultaneously, e.g. SpotML).

7 Specification of controller & RobotWare options

7.23.2 Servo Tool Change [3110-1]

7.23.2 Servo Tool Change [3110-1]

General

Servo Tool Change enables an on-line change of tools (external axes), for a certain drive- and measurement system. The control is switched between the axes by switching the motor cables from one servomotor to another. The switch is performed on-line during production.

Main advantages:

- Flexibility in the production process. One robot handles several tools.
- Minimized equipment. A single drive-measurement system shared by many tools.

Features

- On-line change of tools
- Up to 8 different tools

Application

Application	Description
Servo gun changing	Robot held servo guns, designed for different reach and weld forces, equipped with different brands and sizes of servo motors, may be held and operated by a robot, switching from one servo gun to another.
Servo Tool Change	Can be used as an independent option, or as an addition to the RobotWare Spot Servo options.

Performance

When switching tools, the following steps are performed (switching from Axis 1 to Axis 2):

- Axis 1 is deactivated using the RAPID instruction `DeactUnit`
- Axis 1 is disconnected from the motor cables
- Axis 2 is connected to the motor cables
- Axis 2 is activated using RAPID instruction `ActUnit`
- After activation, axis 2 is ready to run

The motor position at the moment of deactivation of one axis is saved and restored next time the axis is activated.



Note

The motor position must not change more than half a motor revolution, when the axis is disconnected. In RobotWare Spot Servo, there is a calibration routine, which handles larger position changes.

Requirements

Servo Tool Change requires a mechanical wrist interface, a tool changer.

Continues on next page

A MOC service parameter, *Disconnect deactive* (type *Measurement channel*), must be defined as *YES* for each tool (external axis) used with this function.

Limitations

- *Servo Tool Change* can only be applied to one robot in a MultiMove configuration
- *Servo Tool Change* can be used up to 8 different tools but is limited by 14 axes in total for the drive module. For example, if the robot is on a track motion or if another additional axis is connected to a drive module it reduces the number of allowed tools that can be used with servo disconnect.

RAPID instructions

There are no RAPID instructions included in this option.

7.24 Application Dispensing

7.24.1 Dispensing

Dispensing Standard [3419-1]

DispenseWare for OmniCore is a software package that provides support for different types of dispensing processes such as gluing, sealing and similar.

The DispenseWare application provides fast and accurate positioning combined with a flexible process control. Communication with the dispensing equipment is carried out by digital and analogue outputs.

DispenseWare is a package that can be extensively customized. User data and routines can be adapted to suit a specific dispensing equipment and environmental situation.

Features

- Dispensing instructions for both linear and circular paths.
- Fast and accurate positioning and process control.
- Handling of on/off guns as well as proportional guns.
- Speed proportional or constant analogue outputs.
- Four different gun equipment can be handled in the same program, each controlled by 1-5 digital output signals and/or 1-2 analogue output signals.
- Possibility to use different anticipated times for the digital and analogue signals.
- Equipment delay compensation for the TCP speed proportional analogue signals.
- Dispensing in wet or dry mode.
- Possibility to restart an interrupted dispense sequence.
- Possibility to automatically reduce the robot acceleration/deceleration during dispensing.
- Wide customizing possibilities.

7.25 Application Arc welding

7.25.1 Arc welding

7.25.1.1 ArcWare for OmniCore

General

ArcWare for OmniCore is a software package for arc welding. It is distributed as a RobotWare Add-In and can be downloaded by means of RobotStudio. The package also contains a special function package *ArcWare for Collaborative robot CRB15000 (GoFa)*.

ArcWare has support for *Standard I/O welder interface*, *External RW Add-In loaded welder* and *Simulated welder*. Support of some specific power source brands is available as separate Add-Ins that can be downloaded by means of RobotStudio. The MultiMove options can be used with any ArcWare option.

Arc welding Standard [3416-1]

Arc welding Standard supports the following functionality:

- ArcWare Base
- Fronius TPSi
- Standard I/O welder (part of ArcWare Base)

All configuration and programming for these arc welding options is done in add-ins that are downloaded from RobotStudio.

Arc welding Premium [3416-2]

The Premium level includes all functionality from the Standard level, in addition to the premium functionality.

Arc welding Premium supports the following functionality:

- BullsEye
- Seamtracking with Fronius
- Seamtracking with WeldGuide
- SmarTac
- Torch Service Center
- WireSense for Fronius

All configuration and programming for these arc welding options is done in add-ins that are downloaded from RobotStudio.

Arc welding Premium+ [3416-3]

The Premium+ level includes all functionality from the Premium level, in addition to the premium+ functionality.

Arc welding Premium+ supports the following functionality:

- Optical tracking for arc welding

The functionality is released as separate Add-Ins in RobotStudio.

Continues on next page

7 Specification of controller & RobotWare options

7.25.1.1 ArcWare for OmniCore

Continued

RAPID instructions

See Application manual - ArcWare for OmniCore and Application manual - BullsEye.

Limitations

It is not possible to use more than one tracking option at the same time.

7.25.2 BullsEye stand alone SW

7.25.2.1 BullsEye SW [3424-1]

General

The BullsEye SW is a licenced standalone product, the *BullsEye for OmniCore Add-In*. This Add-In can be downloaded from the RobotStudio RobotWare Add-ins gallery. The Add-In works together with RobotWare 7.18 or later.

7.25.3 Torch service

BullsEye [3411-1]

The BullsEye scanning device is used together with the BullsEye software, included in the option *Arc welding Premium*. This provides completely automated Tool Center Point (TCP) definition for welding robots controlled by the OmniCore robot controller. By checking and updating the TCP alignment at regular intervals the robot will always operate with an accurate TCP.

Although BullsEye can be configured to handle any scan device orientation, it is easiest to setup BullsEye when the beam of the scanning device is in a plane parallel to the plane of the robot base.

The BullsEye should be bolted securely in a position where the robot can reach it and where it is not in the way of personnel working around the robot.

Requirements

This option requires the options [3032-1], [3015-2], and [3416-2], except for *MultiMove Additional robot*.

Torch Service Center [3411-2]

The *Torch Service Center* is a compact, multi-functional torch service station and is used exclusively in automatic robot gas metal arc welding for torch cleaning, wire cutting, and TCP gauging. This hardware is used together with the option *Arcwelding Premium*.

The Torch Service Center software option provides automatic cleaning of the welding torch. It automatically clears and reduces buildup of spatter, which ensures continuous and reliable operation of the robot cell. The Torch Service Center option includes software that is loaded into all arc welding motion tasks.

Available services

The available services consist of:

Automatic mechanical cleaning	Automatic mechanical cleaning of the contact tip and gas nozzle to remove welding spatter.
Automatic spraying	Automatic spraying of the contact tip and gas nozzle with a liquid weld spatter release agent.
Wire cutter	Automatic cut-off of the welding wire.

Requirements

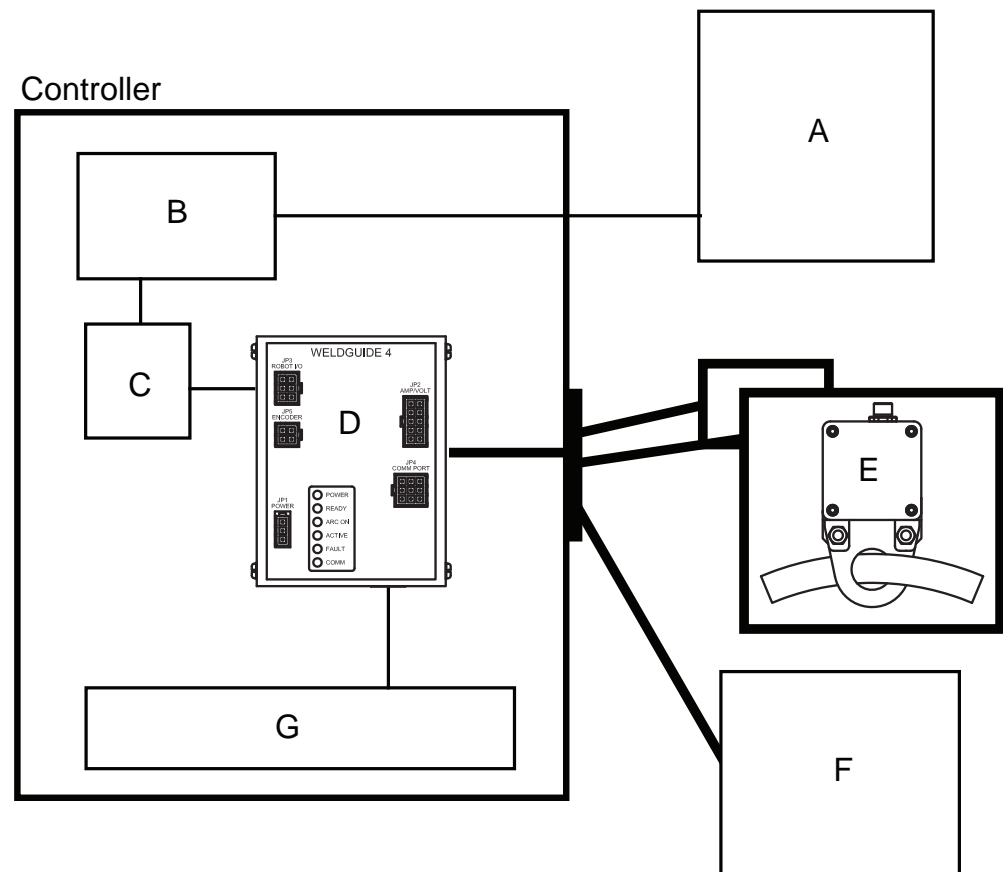
This option requires the options [3032-1], [3015-2], and [3416-2].

7.25.4 Weldguide

7.25.4.1 Weldguide IV

General

Weldguide IV is a Thru-Arc™ tracking sensor designed for a robotic welding system. Weldguide IV uses a microprocessor based weld sequence controller that is seamlessly integrated to the robot controller via Ethernet. The system gives a tracking functionality of the path, adjusting the robot to the actual path location. Weldguide IV measures current and voltage of the arc and sends path corrections to the robot. Measurements are made at the edge of the weave pattern. It is designed to track difficult welding joint variations due to cast components or other pre-process problems. It monitors and controls through-the-arc seam tracking.



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Pos	Description
A	Power source
B	Welding interface
C	I/O
D	Weldguide IV board
E	Voltage and current sensors
F	PC

Continues on next page

7 Specification of controller & RobotWare options

7.25.4.1 Weldguide IV

Continued

Pos	Description
G	Main computer in robot controller

Weldguide IV Standard [3420-1], Weldguide IV Premium [3421-1]

There are two versions of Weldguide, a basic (*Standard*) and an advanced (*Premium*) version.

	Weldguide Standard	Weldguide Premium
FlexPendant user interface	Yes	Yes
Height sensing ⁱ	Yes	Yes
Centerline tracking	Yes	Yes
Inverted centerline tracking	Yes	Yes
MultiPass ⁱⁱ	Yes	Yes
Adaptive fill ⁱⁱⁱ	No	Yes
Single side tracking	No	Yes

ⁱ Torch to Work tracking, Z direction

ⁱⁱ MultiPass capability with variable replay of paths

ⁱⁱⁱ Adaptive control of welding speed and weave width

Requirements

Requires option [3422-1] or [3423-1].

Requires options [3416-2], [3032-1], [3015-2].

Limitations

Cannot be combined with option [3006-1] or [3041-1].

Weldguide sensor options

The sensor can be either solid core or split core. The split core sensor can be opened and has more options for placement.

Option	Description	Note
3422-1	WG Solid core sensor	The cable must be manufactured as the sensor cannot be opened.
3423-1	WG Split core sensor	The sensor can be opened and placed around the cable.

7.26 Application Engineering

7.26.1 CAP and DAP Standard [3125-1]

General

Continuous Application Platform Standard (CAP) and Discrete Application Platform Standard (DAP) is a software platform for time-critical applications where a continuous process, for example, arc welding must be synchronized with the TCP movement of the robot, or where a discrete process shall be performed at specific robot positions, for example, spot welding.

Target users are advanced application software engineers and system integrators, for example for arc welding, laser welding, laser cutting, spot welding, drilling, measuring, quality control, etc.

The main advantages are achieved in the following areas:

- Development time
- Program execution time
- Similar look and feel between applications
- Stable software kernel

Features

- Special RAPID instructions and data types
- A single instruction for motion and process execution
- Combination of fine point positioning with the execution of up to 4 parallel processes
- Specialized process for monitoring of external process device, like spot welding controllers
- Supports encapsulation of the process and motion, in shell-routines provided to the end-user
- Flying start/flying end support

Application

Creation of advanced application software with a continuous or discrete process, for example, arc welding, laser cutting, laser welding, spot welding, drilling, measuring, quality control, etc.

Performance

The platform is designed to have an internal kernel, administrating the fast and quality secured application demands. The kernel calls RAPID routines, which are prepared by the application developer to fulfill the specific tasks. The application developer regulates the degree of flexibility of the end-user, by hiding process complexity.

Requirements

The option *Multitasking* is required for Discrete Application Platform (DAP) functionality if more than 1 DAP process is used.

Continues on next page

7 Specification of controller & RobotWare options

7.26.1 CAP and DAP Standard [3125-1]

Continued

RAPID instructions

See Application manual - Continuous Application Platform and Application manual - Discrete Application Protocol.

Limitations

It is not possible to use CAP and DAP together.

CAP and DAP can only be used on 6-axis robots and CRB 15000.

7.26.2 CAP and DAP Premium [3125-2]

General

The Premium level includes all functionality from the Standard level, in addition to the premium functionality.

For a description of the Standard level, see [CAP and DAP Standard \[3125-1\] on page 217](#).

Features: Tracking Interface

The *Tracking Interface* feature for CAP makes it possible to use external equipment as source of robot path corrections. The interface is easy to access: either by using analog input or output signals, or simply RAPID persistent data to provide corrections. The interface is set up simply using a RAPID instruction. Some areas of use are e.g. height control for Plasma welding or TIP TIG welding.

- At-Point-Tracking controlled by analog input signals.
- At-Point-Tracking controlled by analog output signals.
- At-Point-Tracking controlled by persistent variables.

The *Tracking Interface* can be used together with CAP.

Limitations

It is not possible to use CAP and DAP together.

CAP and DAP can only be used on 6-axis robots and CRB 15000.

7 Specification of controller & RobotWare options

7.26.3 Production Framework [3404-1]

7.26.3 Production Framework [3404-1]

General

Production Framework is a customizable modular platform for order based external control of an ABB robot system.

It shares some features with the older product *Production Manager* but is generally more focused on providing a flexible and customizable platform rather than a provided-as-is fixed solution.

The main purpose of the framework is to handle orders from an external source, typically a PLC in charge of managing the various equipment in the cell. These orders are then executed by the framework by running user-specified RAPID routines.

Features

- Safely transferring orders from the TRAP execution level to normal execution level
- A state-based production loop
- Events, which can be used by the programmer to run code at various times in the production loop, or when certain system events occur
- Multi-tasking and MultiMove abstraction layer for easier (compared to using the basic RAPID API) synchronization of orders and events that are running on several RAPID tasks
- Aborting orders
- Enqueueing orders
- Customizable order constraints
- General logging
- Traceability
- Running independently on any RAPID task, including background tasks
- Flexible architecture with customizable features

Add-In distributed

This option requires an Add-In (Production Framework), available through the RobotStudio Add-In repository.

Requirements

- Multitasking [3114-1]

7.27 Application Machining

7.27.1 Machining Standard [3418-1]

General

Machining Software provides the auto-calibration function that allows users to define calibration toolkits (eg. probe), cutters, additional axis and work objects. The calibrated data can be copied to and reused in RAPID for other projects, which simplifies the calibration process.



Note

The Machining Software application on FlexPendant is only supported by OmniCore controllers operating in RobotWare 7.X.

Key features

Machining Standard provides the following main features:

- Web-based access to machining projects (using PC)
- Dedicated Machining application for working with machining projects (using FlexPendant)
- Auto-calibration on calibration toolkit, cutters, additional axis and work objects

7 Specification of controller & RobotWare options

7.27.2 Machining Premium [3418-2]

7.27.2 Machining Premium [3418-2]

General

Machining Software complements the Machining PowerPac - Machining Functionality (hereinafter referred as Machining PowerPac) add-in in RobotStudio. After creating programs in Machining PowerPac, users can synchronize or load the programs to Machining Software and then perform program tuning in web browser on PC or in the dedicated Machining application on FlexPendant. Different from Machining PowerPac that provides offline programming functions, Machining Software can load the tuned programs to the connected controller (virtual or real) directly. This improves programming efficiency and reduce the onsite commissioning time.



Note

The Machining Software application on FlexPendant is only supported by OmniCore controllers operating in RobotWare 7.X.

Key features

Machining Premium provides the following main features:

- Web-based access to machining projects (using PC)
- Dedicated Machining application for working with machining projects (using FlexPendant)
- Tuning programs created by either Machining PowerPac or Machining Software itself including path smoothing and instruction editing
- Auto-calibration on calibration toolkit, cutters, additional axis and work objects

Versions

Machining Software provides two versions, Machining Standard (option 3418-1) and Machining Premium (option 3418-2), with different user access to functions. The following table lists the main functions to which the two options can access.

Function		Standard	Premium
File operations	File loading	X	X
	File export	X	X
Program tuning	Path smoothing		X
	Wave path setting		X
	Instruction editing		X
Auto-calibration	Toolkit calibration	X	X
	Cutter calibration	X	X
	Work object calibration	X	X

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Note

Only one version can be installed on a controller at a time.

For the web-based Machining Software, if the version is changed, clean the browser cache and restart the browser to make the new version take effect. Otherwise, a version incompatibility message will be displayed.

7 Specification of controller & RobotWare options

7.28.1 Force Control Standard [3415-1]

7.28 Application Force Control

7.28.1 Force Control Standard [3415-1]

General

Force Control are options that contain the RAPID instructions required to run force control.

The option *Force Control Standard* for CRB 15000 (GoFa) is using the built-in torque sensors in combination with the RAPID instructions to support different application/solutions based on making the robot compliant with external forces/process forces.

The options *Force Control* for other robots than GoFa are using external sensors in combination with the RAPID instructions to support different application/solutions based on making the robot compliant with external forces/process forces. The external sensors are selected in options 3039-X.

The Force Control options

The following options are available for *Force Control Standard*.

Features	Force Control Standard [3415-1]
Force Control Pressure	✓
Force Control Speed Change	✓
Force Control Assembly	✓
Built-in Torque sensors (GoFa)	✓

Assembly FC

Assembly FC (Force Control) is a set of functions, which will highly facilitate the use of robots for assembly tasks. Assembly is a very demanding application where parts with very small tolerances shall fit together, e.g shafts into gear wheels. Since tolerances are in the magnitude of robot repeatability, this normally requires high accuracy fixtures and robots with very high precision and still the risk for position failure, where parts are stuck or damaged, is very high. In many cases also parts are not fixed but can have random positions, and thus traditional position-controlled robots are not possible to use.

With *Assembly FC* and Force/Torque sensor the robot is equipped with "tactile" sense and thus can handle the parts like a human worker, that is search along a predefined pattern and try pushing until parts slip into position with only small contact forces used. If measured force gets larger than desired the robot would move back to decrease the force. This will save both installation cost and programming time but also reduce the process cycle time.

Other areas where *Assembly FC* is useful are:

- Product testing - apply the same amount of force to a product repetitive
- Part mating
- Automated fastening

Continues on next page

Assembly FC includes functions to use different predefined assembly patterns, designed for different tasks, but also possibility to combine some of them to create new patterns for more complex assembly tasks.

Assembly FC features

- Sensor calibration and load identification, which will calibrate the force sensor to remove offsets such as the gravity force. RAPID instructions: `FCCalib`, `FCLoadId`
- Activation and deactivation of Force Control. When activating Force Control for instance, the following can be set up.
- Force control coordinate system
- Damping, that is how the robot speed depends on the contact force. RAPID instructions: `FCAct`, `FCDeact`, `FCRefStart`
- Definition of reference values (desired force, torque and/or search pattern). When activating a force/torque reference, the robot will move in order to achieve the specified reference level. When activating a search reference, the robot will attempt to move according to the specified pattern, like circular, spiral or linear movement. RAPID instructions: `FCRefForce`, `FCRefLine`, `FCRefCircle`, `FCRefSpiral`, `FCRefSpringForce` etc.
- End conditions (how long to apply the force, torque and search pattern). The reference force, torque and movement are used to search for a fit. The end conditions are used to determine when this search has been successful. All conditions have a time-out that allows execution to continue even if the end condition is not met. RAPID instructions: `FCCondPos`, `FCCondForce`, `FCCondTime`, `FCCondWaitWhile` etc.
- Supervision, that is Force Control data can be supervised and limits set that must be met. Any data outside supervision conditions will result in an emergency stop. This can be used as a safety measurement by limiting the work area, robot speed, etc. RAPID instructions: `FCSupvForce`, `FCSupvPos` etc.
- Functions providing feedback from the process, which will give a snapshot of some process data like contact forces, actual load, speed, or if the condition was met or if timed out. RAPID functions: `FCGetForce`, `FCGetProcessData`, `FCIsForceMode`
- Data types supporting the instructions and functions
- Up to three robots can be controlled independently in a MultiMove cell.

Machining FC

Machining FC is a set of functions, which will highly facilitate the use of robots for machining applications. *Machining FC* includes solutions for using force control in different machining applications where the robot needs to be sensitive to process forces. *Machining FC* offers two kinds of process control, optimized for different kinds of machining, namely *FC Pressure* and *FC Speed Change*.

Continues on next page

7 Specification of controller & RobotWare options

7.28.1 Force Control Standard [3415-1]

Continued

FC Pressure functionality

With the FC Pressure functionality, the robot will always keep a constant force against a surface, resulting in that the robot will follow the curvature of the surface.

The FC Pressure functionality is for example advantageous to use in machining processes like grinding and polishing where the robot needs to obtain a defined pressure (force) between the tool and part for proper result. With FC Pressure functionality, the programmed path roughly needs to follow the surface as the robot position will be adjusted to achieve the defined contact force between tool and part. This will save programming time as well as improve the product quality.

FC Speed Change functionality

FC Speed Change will allow programming at the maximum process speed and automatically slow down the robot when the machining forces are too high.

The FC Speed Change functionality can for example be favorable to use in a machining process like deburring, where the robot needs to slow down when hitting excessive burr, or even retract for sequential machining. The robot is position controlled, that is it will follow the programmed path, in this functionality. With the FC Speed Change functionality the robot will vary the processing speed. This will save programming time but also reduce the process cycle time.

Functional description

Normally robots are position controlled, which means that the robot is forced to move to a certain ordered position. If the robot is prevented to reach the target, the servo will increase power until max torque or collision is detected.

With *Assembly FC* it will be possible to let the robot search along a surface while keeping a predefined contact force. Once the mounting hole is found, the part will fall into place and the robot will push the part in to the opening until correct position is reached.

A typical assembly task will for example be the mounting of axis and gear wheels in a clutch. Such a task will include several different movements to find the correct location and insert the axis. For any assembly task it will be possible to tailor the best optimum search pattern/movement and choose between a number of criteria for accepting/ending the operation.

With *Force Control for Machining* it will be possible to either let the robot maintain a constant force perpendicular to the path while following the surface curvature (FC Pressure) or let the robot slow down on the pre-defined path to reduce the force acting on the robot (FC Speed Change).

Continues on next page

About FC Pressure

The purpose of FC Pressure is to make the robot sensitive to contact forces perpendicular to the move direction. The robot can "feel" its surroundings and follow the surface of the processed part to obtain a certain pressure against an object. This means that the robot will change its position in order to apply a constant force/pressure on a surface, even if the exact position of the surface is not known. Since pressure is obtained by moving the robot path, this function is more suited for polishing, grinding and cleaning, where a surface should be made even and smooth. The material that is removed and the changes of the surface topology / dimensions depend on the process parameters like tooling, applied pressure, robot speed etc.

See below some examples from foundry and metal fabrication where FC Pressure is useful:

- Grinding of faucets
- Polishing of kitchen sinks
- Deflashing and cleaning of castings
- Deburring of castings

About FC Speed Change

In processes where path accuracy is important and where the finished result shall comply with specific dimensions, FC Speed Change is recommended. This function will be useful combined with force sensor or other input indicating excessive forces, which can negatively affect the finished result. When speed change is active and if machining forces exceed a certain value, then the path speed will automatically be reduced, thus decreasing forces, minimizing changed dimensions due to deflections of the robot arm and most probably avoid damaging the part/tool due to stress and heat. This will guarantee path accuracy even if much material shall be removed. Some examples where FC Speed Change may be used:

- (Wheel) Grinding unevenly distributed material on casted surfaces
- Milling along the edge of a work piece
- Deburring along contour of a work piece
- Deflashing unevenly distributed burr along a part line on castings
- Deburring of castings

Machining FC feature

- Instructions for programming FC Pressure start, movements and stop.
- Instructions for activating/deactivating FC Speed Change.
- Instruction to setup gravity compensation and sensor offset calibration.
- Instructions for defining reference values (desired force, speed change parameters or movement).
- Instructions for defining recover function for Speed Change
- Instructions for supervision.
- Functions returning data about load, detected forces or process status.
- Data types supporting the instructions and functions

Continues on next page

7 Specification of controller & RobotWare options

7.28.1 Force Control Standard [3415-1]

Continued

Example of setting up an assembly application

The following steps will illustrate how to set up a new assembly task:

- 1 Calibrate force sensor
- 2 Calibrate work piece weight and center of gravity
- 3 Done once for one type of work piece by executing a RAPID program
- 4 Determine start point to activate force control, that is where contact is possible
- 5 Determine nominal contact for magnitude and direction period during which assembly take place
- 6 Driving force to make two parts fit together
No motion command necessary during this sequence
- 7 Determine the search pattern magnitude, frequency and direction
- 8 Determine supervision criteria
Optional, may be used to prevent robot to move into fragile areas
- 9 Determine end point to deactivate force control
Typical point for the completion of assembly
- 10 Activate Force Control and references and wait until criteria are fulfilled
Robot will move until assembly end condition or time out is reached

Limitations for Force Control

- The total load, that is the sum of gravitational forces and external contact forces, must not exceed limits as specified in the load diagrams for a specific robot.
- If Force Control is used together with SafeMove the function Operational Safety Range must be used. See the SafeMove manual for more information.

When the robot is force controlled, the following functionality is *not* accessible:

- *Arc*
- *Collision Detection*
- *Conveyor tracking*
- *Independent axes*
- *MultiMove Coordinated*
- Joint soft servo (instruction `SoftAct`)
- *Path Offset*
- *PickMaster*
- RAPID instructions such as `FCAct`, `FCDeact`, `FCConditionWaitWhile`, and `FCRefStop` can only be called from normal level in a motion task.
- *Sensor or Analog synchronization*
- *Sensor interface*
- *SoftMove*
- Tracking functionality like *Conveyor Tracking*, *Optical Tracking*, and *Weld Guide*.

Continues on next page

- Force controlled pressure applications (FCPressL etc) and Force controlled speed change applications (FCSpdChgAct etc) cannot be combined with EGM instructions.
- *World Zones*

7 Specification of controller & RobotWare options

7.28.2 Force Ctrl Package [3039-X]

7.28.2 Force Ctrl Package [3039-X]

General

The force control package contains all required hardware and software to run the robot in force control mode.

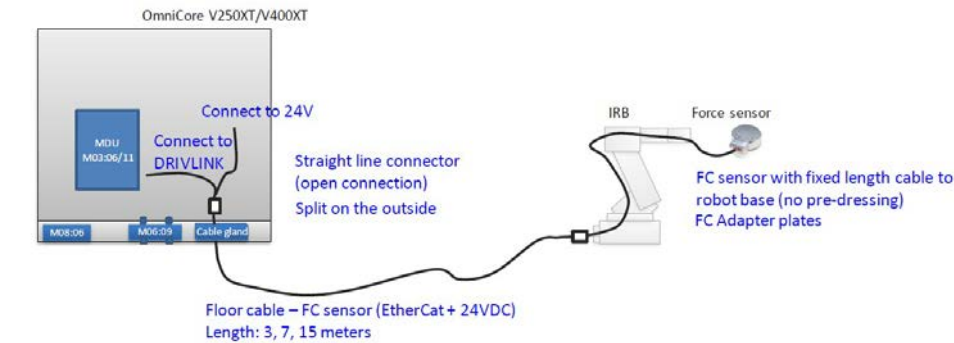
It contains the following components:

- Option *Force Control Standard [3415-1]*.
- Force sensor, adapter plate, and cabling as described below.

Option	Description
[3039-1]	Force Ctrl. Package 165
[3039-2]	Force Ctrl. Package 660
[3039-3]	Force Ctrl. Package 2500

Installation

The integrated force sensor can be mounted on the robot flange using an adapter plate. The force sensor can also be stationary mounted. A cable is supplied to connect the force sensor to the controller. Cable management must be arranged by the user.

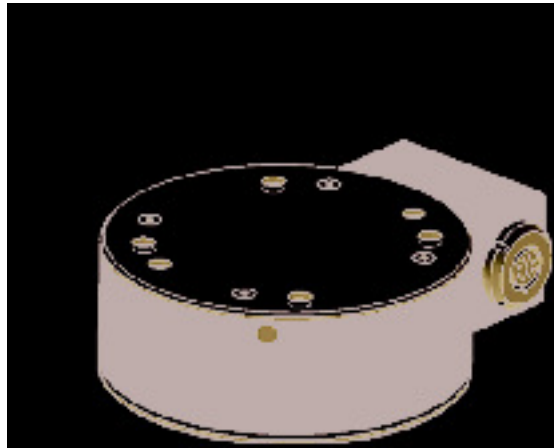


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Force sensor measurement

The force sensor measures all six components of force (F_x , F_y and F_z) and torque (M_x , M_y and M_z).

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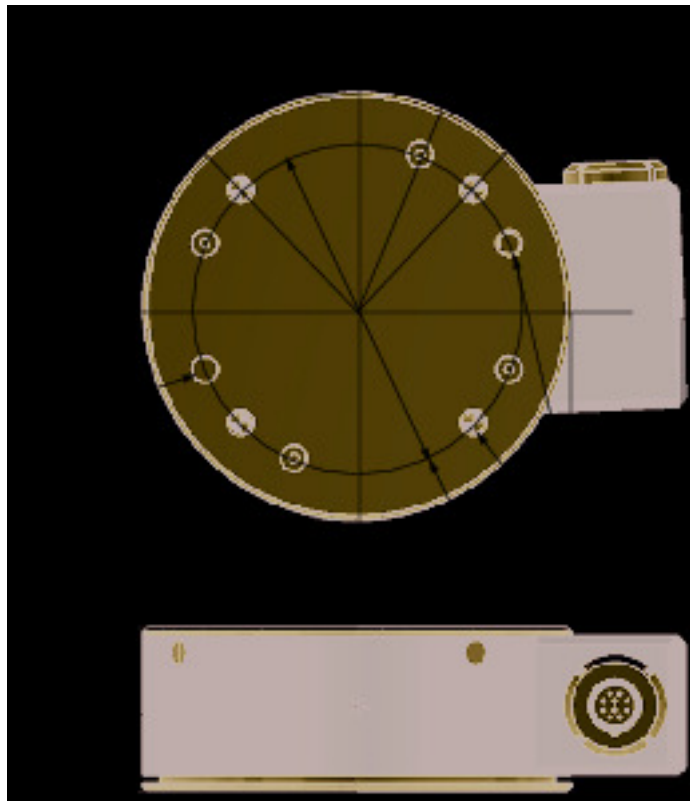
Dimensions



Note

Note that the adapter plate and force sensor will generate an offset and additional weight on the tool flange, and hence affect the available payload of the robot. See the load diagram for the respective robot.

Force sensor dimensions



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7 Specification of controller & RobotWare options

7.28.2 Force Ctrl Package [3039-X]

Continued

	Sensor package 165 and 660	Sensor package 2500
A	Diameter 104 mm	Diameter 168 mm
B	Height 40 mm	Height 62 mm
C	4 x M6 Min. thread length is 7.6 mm (on both sides)	4 x M10 Min. thread length is 15 mm (on both sides)
D	Diameter 80 mm	Diameter 124 mm
E	27 mm	27 mm
F	Diameter 6.02 ^{+0.02} , depth min. 7 mm (on both sides)	Diameter 8.02 ^{+0.02} , depth min. 9 mm (on both sides)
G	Diameter 5.02 ^{+0.02} , depth min. 7 mm (on both sides)	Diameter 10.02 ^{+0.02} , depth min. 9 mm (on both sides)

Adapter plate dimensions



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	Sensor package 165	Sensor package 660		Sensor package 2,500	
A	Ø 104 mm	Ø 104 mm	Ø 140 mm	Ø 165 mm	Ø 210 mm
B	10 mm	10 mm	10 mm	15 mm	15 mm
C	-	-	15 mm	15 mm	20 mm
Type	Single adapter	Single adapter	Double adapters	Double adapters	
Weight (B + C)	0.6 kg	0.6 kg	1.1 + 1.7 kg	2.3 + 2.5 kg	3.8 + 5.3 kg

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7 Specification of controller & RobotWare options

7.28.2 Force Ctrl Package [3039-X]

Continued

	Sensor pack- age 165	Sensor package 660		Sensor package 2,500	
Suitable robots	IRB 1200 IRB 1600 IRB 2400 IRB 2600	IRB 2400 IRB 2600	IRB 4400 IRB 4600	IRB 4400 IRB 4600	IRB 6650S IRB 6660

Force sensor specification

	Sensor package 165	Sensor package 660	Sensor package 2500
Capacity:			
Fx, Fy	165 N	660 N	2,500 N
Fz	495 N	1,980 N	6,250 N
Mx, My, Mz	15 Nm	60 Nm	400 Nm
Resolution:			
Fx, Fy	0.03	0.09	0.33
Fz	0.11	0.33	1
Mx, My, Mz	0.003	0.008	0.053
Overload capacity:			
Fx, Fy	1,650 N	6,600 N	25,000 N
Fz	4,950 N	19,800 N	62,500 N
Mx, My, Mz	150 Nm	600 Nm	4,000 Nm
Operating temperature	-40 to +100 °C	-40 to +100 °C	-40 to +100 °C
IP rating	IP65	IP65	IP65
Sensor weight	1.6 kg	1.7 kg	7.2 kg

Floor cables

Option	Description
3211-1	Force control 3 m
3211-2	Force control 7 m
3211-3	Force control 15 m

Requirements

The floor cables require option Force Ctrl Package [3039-X].

7.29 Warranty

Warranty

For the selected period of time, ABB will provide spare parts and labor to repair or replace the non-conforming portion of the equipment without additional charges. During that period, it is required to have a yearly *Preventative Maintenance* according to ABB manuals to be performed by ABB. If due to customer restrains no data can be analyzed with ABB Connected Services for robots with OmniCore controllers, and ABB has to travel to site, travel expenses are not covered. The *Extended Warranty* period always starts on the day of warranty expiration. Warranty Conditions apply as defined in the *Terms & Conditions*.



Note

This description above is not applicable for option *Stock warranty* [438-8]

Option	Type	Description
438-1	Standard warranty	Standard warranty is 12 months from <i>Customer Delivery Date</i> or latest 18 months after <i>Factory Shipment Date</i> , whichever occurs first. Warranty terms and conditions apply.
438-2	Standard warranty + 12 months	Standard warranty extended with 12 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-4	Standard warranty + 18 months	Standard warranty extended with 18 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-5	Standard warranty + 24 months	Standard warranty extended with 24 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-6	Standard warranty + 6 months	Standard warranty extended with 6 months from end date of the standard warranty. Warranty terms and conditions apply.
438-7	Standard warranty + 30 months	Standard warranty extended with 30 months from end date of the standard warranty. Warranty terms and conditions apply.
438-8	Stock warranty	<p>Maximum 6 months postponed start of standard warranty, starting from factory shipment date. Note that no claims will be accepted for warranties that occurred before the end of stock warranty. Standard warranty commences automatically after 6 months from <i>Factory Shipment Date</i> or from activation date of standard warranty in WebConfig.</p> <div> Note Special conditions are applicable, see <i>Robotics Warranty Directives</i>.</div>

8 Type change of the OmniCore controller

General

This section describes major design changes that are not backward compatible and still represents the same product with same functionality.

V250XT Type B

The V250XT Type B is introduced since 23D release, product specification revision J.

In V250XT Type B, a new main computer is introduced.

The main computer unit, DSQC1095, integrates a computing module, a robot safety controller, and a robot signal exchange proxy. It has separated AS/GS inputs for better flexibility and potential free E-stop-status output. It supports EtherCAT communication and provides extension slots for future extended functionality.

For more details, see *Product manual - OmniCore V250XT Type B*.

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