ROBOTICS

Product manual

IRB 2600

Trace back information:
Workspace 25A version a9
Checked in 2025-02-25
Skribenta version 5.6.018

Product manual

IRB 2600-20/1.65
IRB 2600-12/1.65
IRB 2600-12/1.85
IRB 2600-20/1.65 type C
IRB 2600-12/1.65 type C
IRB 2600ID-15/1.85
IRB 2600ID-8/2.0

IRC5, OmniCore

Document ID: 3HAC035504-001

Revision: AG

Keep for future reference.

Additional copies of this manual may be obtained from ABB.

Original instructions.

Table of contents

Overview of this manual

About this manual

This manual contains instructions for:

- mechanical and electrical installation of the IRB 2600/IRB 2600 ID
- maintenance of the IRB 2600/IRB 2600 ID
- mechanical and electrical repair of the IRB 2600/IRB 2600 ID

The robot described in this manual has the following protection types:

- *Standard*
- *Foundry Plus*

This manual describes the manipulator using either the IRC5 or the OmniCore controller.

Product manual scope

The manual covers all variants and designs of the IRB 2600/IRB 2600 ID. Some variants and designs may have been removed from the business offer and are no longer available for purchase.

Usage

This manual shall be used during:

- installation and commissioning, from lifting the product to its work site and securing it to the foundation, to making it ready for operation
- maintenance work
- repair work
- decommissioning work

Note

It is the responsibility of the integrator to conduct a risk assessment of the final application.

It is the responsibility of the integrator to provide safety and user guides for the robot system.

Who should read this manual?

This manual is intended for:

- installation personnel
- maintenance personnel
- repair personnel.

Prerequisites

A maintenance/repair/installation craftsman working with an ABB robot shall:

- be trained by ABB and have the required knowledge of mechanical and electrical installation/repair/maintenance work.
- be trained to respond to emergencies or abnormal situations.

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References

Tip

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

General

Reference	Document ID
Circuit diagram - IRB 2600	*3HAC029570-007*
Product manual, spare parts - IRB 2600	*3HAC049106-001*
Safety manual for robot - Manipulator and IRC5 or OmniCore controller i	*3HAC031045-001*
Operating manual - Emergency safety information	*3HAC027098-001*
Technical reference manual - Lubrication in gearboxes	*3HAC042927-001*

i This manual contains all safety instructions from the product manuals for the manipulators and the controllers.

OmniCore robots

Reference	Document ID
Product specification - IRB 2600	*3HAC085909-001*
Product manual - OmniCore V250XT Type B	*3HAC087112-001*
Product manual - OmniCore V400XT	*3HAC081697-001*
Operating manual - OmniCore	*3HAC065036-001*
Technical reference manual - System parameters	*3HAC065041-001*
Application manual - Additional axes	*3HAC082287-001*

IRC5 robots

Reference	Document ID
Product specification - IRB 2600	*3HAC035959-001*
Product manual - IRC5 IRC5 with main computer DSQC1000.	*3HAC047136-001*
Operating manual - IRC5 with FlexPendant	*3HAC050941-001*
Operating manual - Calibration Pendulum	*3HAC16578-1*
Operating manual - Service Information System	*3HAC050944-001*
Technical reference manual - System parameters	*3HAC050948-001*
Application manual - Additional axes and standalone controller	*3HAC051016-001*
Application manual - Electronic Position Switches	*3HAC050996-001*
Application manual - CalibWare Field	*3HAC030421-001*

Revisions

Revision	Description
-	First edition

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Revision	Description
A	The following updates and additions have been made in this revision: • Variant IRB 2600ID added throughout the manual. • Safety symbols updated throughout the manual. • Section *Safety signals in the manual on page 23* added in Safety chapter. • Added information about pressure relief valve in Safety chapter. • Force and Torque loads updated in section *Pre-installation procedure on page 44*. • Section *Installing an expansion container on page 94* added. • Interval for inspection of signal lamp added in section *Maintenance schedule on page 115*. • New design of frame added in sections *Inspecting oil level, axis-1 gearbox on page 119* and *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*. • Required oil level updated in section *Inspecting oil level, axis-1 gearbox on page 119*. • Required oil level updated in section *Inspecting the oil level, axis 3 gearbox on page 127*. • Required oil level updated in section *Inspecting the oil level, axis 4 gearbox on page 129*. • Required oil level updated in section *Inspecting oil level, gearbox axes 5 - 6 on page 131*.
B	The following updates and additions have been made in this revision: • The difference in weight between the different robot variants is minor, therefor the weight specification for the robot is simplified. See *Weight, robot on page 45*. • Figure and describing text edited for the stress forces. See *Loads on foundation, robot on page 46*. • Removed Foundry from table with protection classes. See *Protection classes, robot on page 48*. • Text added for the maximum levelness. See *Requirements, foundation on page 47*. • Length of roundslings for lifting the robot is changed from 4 m to 2 m. See *Lifting robot with roundslings on page 57*. • Note about fan cabling added in the cable list. See *Robot cabling and connection points on page 102*. • Minor editorial changes made throughout the maintenance chapter. • Note about ambient temperature deleted from the maintenance schedule. See *Maintenance schedule on page 115*. • Added figure of suspended robot in maintenance sections for axis 1 gearbox. See *Inspecting oil level, axis-1 gearbox on page 119* and *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*. • A new block, about general illustrations, added in section *How to read the product manual on page 20*. • Figure of axis 1 stop pin is updated. See *Replacing stop pin axis 1 on page 293*. • Figure of axis 1 gearbox is updated. See *Replacing gearbox axis 1 on page 365*. • Figure with movement directions of axes added. See *Calibration movement directions for all axes on page 407*. • Figure of suspended robot added. See *Lifting and turning a suspended mounted robot on page 60*. • Warning of heavy weight is changed to include the complete robot instead of only the arm system, section *Replacing the base on page 296*. • Separated robot dimensions and mounting hole measurements in drawings. See *Fitting equipment on robot on page 72*.

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Revision	Description
	• Added section *Setting the system parameters for a suspended or tilted robot on page 61*. • Corrected spare part numbers for axes 3, 4, 5 and 6 motors. See *Upper arm* and *Upper arm ID*. • Added VK covers to the instruction for upper arm cabling replacement, IRB 2600ID. See *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*. • Changed information about which attachment screws to remove when removing the base from the robot. Previously the instruction said "Remove the attachment screws securing the gearbox to the frame", now it says "Remove the attachment screws that secure the base to the axis 1 gearbox". See step in the end of the removal procedure in section *Replacing the base on page 296*. • Changed information about the robot position when removing motor. See *Removing motors on page 308*. • Added step about removing/refitting axis 1 motor when replacing the axis 1 gearbox. Also added information about guide pins. See *Replacing gearbox axis 1 on page 365*. Also minor additions concerning the mating of gearbox and motor, in all such instructions. • Added information about lifting accessories and how to attach them to the upper arm of the robot, see *Attaching the lifting accessories to the upper arm on page 256*. • Additional information in the procedure for replacing the base with improved lifting instruction etc., see *Replacing the base on page 296*. • Added a second roundsling to the lifting instruction for the complet robot, see *Lifting robot with roundslings on page 57*. • Changed type of oil in axes 1, 2 and 4 gearboxes. See *Type of lubrication in gearboxes on page 148*.
C	The following updates and changes have been made in this revision: • Added instructions for how to measure the play of axis 5 and 6 of an ID upper arm. See sections *Measuring the play, axis 5 (ID upper arm) on page 279* and *Required equipment on page 282*. • Deleted the spare part number for harnesses in *Spare parts - lower arm* and instead inserted a reference to the *Electrical connections*. • Corrected the spare part numbers for cable harnesses, see *Electrical connections*. • Corrected measurement that belong to figure xx0300000187, when fitting tools for measuring the play of axis 5, see *Measuring the play, axis 5 on page 275*. • Corrected faulty information about attachment screws between upper and lower arm (figure, screw dimension and tightening torque), see *Replacing the complete upper arm on page 251*. • Added information about releasing the motor brakes in order to set the weight of different axes onto lifting accessories, see *Replacing the complete upper arm on page 251*, *Replacing gearbox axis 3 on page 391* and *Replacing gearbox axis 2 on page 378*. • Changed the instruction for how to replace the axes 2 and 3 gearboxes without having to remove the cable harness, see *Replacing gearbox axis 3 on page 391* and *Replacing gearbox axis 2 on page 378*. • Added safety information about preventing roundslings from sliding when lifting the upper arm tube, see *Replacing complete tubular shaft unit on page 261*. • Added information about removing painting, if any, from assembly surfaces when replacing gearboxes and motors. • Corrected the specified weight for the tubular shaft unit to 30 kg. • Added tip to speed up the draining of axis 4 gearbox, see *Changing the oil, axis-4 gearbox on page 171*.

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Revision	Description
	• Corrected data for which motor pins to connect when releasing the brakes, see *Removing motors on page 308* and *Refitting motors on page 321*. • Added information about o-ring and made other minor improvements to the instruction for replacing wrist unit, see *Replacing wrist unit on page 268*. • Added information about disconnecting the battery cable when removing the cable harness, see *Removing the complete cable harness on page 199*. • Corrected the figure that shows location of oil plugs of axis 3 gearbox, added a funnel to equipment list, see *Changing the oil, axis-3 gearbox on page 167*. • Corrected the figure that shows location of oil plugs of axis 3 gearbox and adjusted the oil level, see *Inspecting the oil level, axis 3 gearbox on page 127*. • Changed instruction for replacing the wrist unit so that the wrist do not need to be drained, see *Replacing wrist unit on page 268*. • Added Profibus to the section about connections to extra equipment, see *Customer connection on robot on page 106*. • New section added to the manual, see *Installation of Foundry Plus Cable guard (option) on page 98*. • Some general tightening torques have been changed/added, see updated values in *Screw joints on page 452*. • The method of changing the axis-1 gearbox oil in suspended robots is improved, see the new section *Changing the oil, axis-1 gearbox on suspended robots on page 158*. • Corrected the motor connector pin numbers used for releasing the motor brakes with external power supply, see *Removing motors on page 308* and *Refitting motors on page 321*. • Complete process wrist for IRB 2600ID is added to the spare part list and to the service instructions, see *Spare parts*and *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*, also the section Wrist unit is deleted from the spare part list, since the wrist unit spare part number already is specified in the upper arm spare part list. • Added instructions for adjusting the play on motors, see *Adjusting the play on page 360*. • Added information about batteries.
D	The following updates and changes have been made in this revision: • Removed faulty information about motors when rebuilding the robot, see *Rebuilding parts*. • Removed faulty information about expansion container for wall mounted robots, see *Changing the oil, axis-1 gearbox on suspended robots on page 158*. Expansion container is not used on wall mounted robots. • Added ID variants to the information about lower arm when rebuilding the robot, see *Rebuilding parts*. Also corrected the ID information in the spare part list for the lower arm. • Added correct variant descriptions to the information about IRB 2600ID upper arms. See *Upper arm (IRB 2600ID)*. • Mounting angles and values for tilted the variant of the robot added. • Corrected the spare part numbers for cable harnesses, see *Electrical connections*. • Corrected the spare part number for o-ring pos (5). See *Base and frame unit*. • Spare part number for VK cover, pos 41 was wrong. Has been corrected. See *Upper arm (IRB 2600ID)*. • Corrected tightening torque value for oil plugs on axis-1 and axis-2 gearboxes. Correct value is 24 Nm. (Earlier incorrect value: 60 Nm.)

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Revision	Description
	• Information about the type and amount of oil has been removed from the manual and can now be found in *Technical reference manual - Lubrication in gearboxes*. For article number see *References on page 10*. • Information about sealing washer oil plugs on the axis-1 and axis-2 gearbox changed. Also spare part number is added. • New frame introduced throughout the manual. • A new SMB unit and battery is introduced, with longer battery lifetime.
E	The following updates and changes have been made in this revision: • Corrected links to lubrication in gearboxes. • Spare part numbers in general corrected. • Added information about risks when scrapping a decommissioned robot, see *Scrapping of robot on page 442*. • *Spare parts and exploded views* are not included in this document but delivered as a separate document. See *Product manual, spare parts - IRB 2600*.
F	The following updates have been made in this revision: • Illustration changes in *Dimension, mounting surface and guide bushing on page 69*. • Term "Guide sleeves" changed to "Guide bushings", see *Dimension, mounting surface and guide bushing on page 69*. • Information in 2.3.4 Manually releasing the brakes has been updated and two figures are added. • Motors Type B added for IRB 2600 and IRB 2600ID. • A new **WARNING**! is added in the section about motor replacement, informing not to mix different motor types. • Minor corrections.
G	The following updates have been made in this revision: • Information about removing the mech stop bracket added in section 2.4.1 • Illustrations of cable harness and motors in upper arm, improved throughout the manual.
H	The following updates have been made in this revision: • Turning disk fixture is removed from special tools for Levelmeter calibration. • Valid serial numbers changed to type designations (Type A and Type B) in the section "Checking the oil level" to avoid confusion between different serial number series. • Oil levels adjusted.
J	The following updates have been made in this revision: • Information about expansion container added. • Updated number of screws and sizes of screws in Replacing the lower arm.
K	Published in release R16.2. The following updates are done in this revision: • Corrections due to updates in SAP terminology. • New standard calibration method is introduced (Axis Calibration). See *Calibration on page 399*. • Clarifications in maintenance schedule. • Information about grounding point added. See *Robot cabling and connection points on page 102*.
L	Published in release R17.1. The following updates are done in this revision: • Added information about how to handle cabling in the upper arm tube, and upper arm housing, during wrist removal and cable replacement, see *Removing the wrist unit on page 351* and *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*.

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Revision	Description
	• Changed the tightening torque of the oil plug located on axis-1 gearbox. • Recommendation about changing oil in axis-2 gearbox in floor standing position added. • Clarification for types of motors, *Motors on page 308*.
M	Published in release R17.2. The following updates are done in this revision: • Information about coupled axes in *Updating revolution counters on IRC5 robots on page 408*. • Caution about removing metal residues added in sections about SMB boards. • Information added into calibration procedure regarding installation of calibration tool on turning disc, see *Overview of the calibration procedure on the FlexPendant on page 423*. • Information about minimum resonance frequency added. • Bending radius for static floor cables added. • Updated list of applicable standards. • Article number for the Calibration tool box, Axis Calibration is changed. • Added text regarding overhaul in section specification of maintenance intervals. • Updated the section *Start of robot in cold environments on page 101*. • Information about isolating arc welding manipulator added. • Updated information regarding replacement of brake release board. • Updated information regarding disconnecting and reconnecting battery cable to serial measurement board. • Definition of reference calibration clarified.
N	Published in release R18.1. The following updates are done in this revision: • Information added about fatigue to Axis Calibration tool, see *Calibration tools for Axis Calibration on page 417*. • Added sections in *General procedures on page 190*. • Illustration updated in dimension, mounting surface and guide bushing. • Safety restructured. • Added information about harness customer ethernet connection. • Updated spare parts number for Brake release boards. • Note added to calibration chapter to emphasize the requirement of equally dressed robot when using previously created reference calibration values. • Information about myABB Business Portal added. • Added Nickel in Environmental information.
P	Published in release R18.2. The following updates are done in this revision: • Updates related to mechanical stop pin. • Changed the method for replacing the axis-1 gearbox and the base.
Q	Published in release R18.2. The following updates are done in this revision: • Updated reference.
R	Published in release 19B. The following updates are made in this revision: • Added information about IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C to the manual. **NOTE! The Type C robot is not available until later release.** • New touch up color Graphite White available. See *Cut the paint or surface on the robot before replacing parts on page 197*. • New article numbers for manipulator cables in section *Robot cabling and connection points on page 102*. • Levelmeter 2000 kit (6369901-347) no longer available.

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Revision	Description
S	Published in release 19B. The following updates are made in this revision: • Type C variants (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) are removed from the manual, due to later sales start.
T	Published in release 19C. The following updates are made in this revision: • Release date for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is removed in section *Robot description on page 443*. • Note added about need to calibrate if the robot is other than floor mounted. See *When to calibrate on page 403*. • Procedure for changing oil in axis-5/6 gearbox is updated with information valid for IRB 2600ID.
U	Published in release 19D. The following updates are made in this revision: • Updated oil level in axis-1 gearbox for robots IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C. • Updated installation procedure for expansion container, see *Installing an expansion container on page 94*.
V	Published in release 20A. The following updates are made in this revision: • Added information about IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C to the manual. • Replaced article number and name of grease, previously 3HAB3537-1. • Clarified and added information in mounting instructions for rotating sealings, see *Mounting instructions for sealings on page 193*. • Clarified text about position of robot and added table with dependencies between axes during Axis Calibration.
W	Published in release 20B. The following updates are made in this revision: • Article number of Calibration tool box, Axis Calibration is changed from 3HAC062326-001 to 3HAC074119-001. • Added information about Wrist Optimization in calibration chapter.
X	Published in release 20C. The following updates are made in this revision: • Added note about differences in type of oil pre-filled in axis-4 gear compared to recommended oil for field maintenance. • Clarified information regarding brake release on motor connectors when removing motors. • Updated section about customer connections in regard to Ethernet etc. See *Customer connection on robot on page 106*. • Added illustration of base hole configuration for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C, see *Orienting and securing the robot on page 68*.
Y	Published in release 20D. The following updates are made in this revision: • Removed inspection of axis-5 gear oil level from maintenance schedule (IRB 2600ID). • Added information about refilling oil in the axis-5 gear after replacing the axis-5 motor (IRB 2600ID). • Added tightening torque and inspection step for axis-5 gear oil plug, after refilling oil during axis-5 motor replacement (IRB 2600ID).
Z	Published in release 21A. The following updates are made in this revision: • Changed grease to Loctite 574 on o-ring when refitting motor axes 1 and 2. • Note regarding maximum leakage current for attached equipment. See *Customer connection on robot on page 106*.
AA	Published in release 21B. The following updates are made in this revision: • Information regarding documentation of Installation of Foundry Plus Cable guard (option no. 908-1) is changed since DVDs are removed. See *Installation of Foundry Plus Cable guard (option) on page 98*.

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Revision	Description
	• Text regarding fastener quality is updated, see *Fastener quality on page 84*.
AB	Published in release 21C. The following updates are made in this revision: • Information regarding option 224-2 (expansion tank) when in inverted mounting. See *Installing an expansion container on page 94*.
AC	Published in release 23A. The following updates are done in this revision: • Added support for OmniCore V250XT. • Updated information about Gleitmo treated screws, see *Screw joints on page 452*.
AD	Published in release 23B. The following updates are done in this revision: • Added axis positions for most stable transport position and removed information about shipping position. • Updated the tightening torque for axis 5 oil plug.
AE	Published in release 23D. The following updates are done in this revision: • Added illustrations to the section Cleaning. • Added support for OmniCore V400XT.
AF	Published in release 24D. The following updates are done in this revision: • Updated wording "foundation" to "steel structure foundation" in section Orienting and securing the robot.
AG	Published in release 25A. The following updates are done in this revision: • Updated section for installation of cooling fans, the option is now also available for OmniCore. • Corrected the maximum tilt angle in *Technical data on page 45*.

Product documentation

Categories for user documentation from ABB Robotics

The user documentation from ABB Robotics is divided into a number of categories. This listing is based on the type of information in the documents, regardless of whether the products are standard or optional.

Tip

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

Product manuals

Manipulators, controllers, DressPack, and most other hardware is delivered with a **Product manual** that generally contains:

- Safety information.
- Installation and commissioning (descriptions of mechanical installation or electrical connections).
- Maintenance (descriptions of all required preventive maintenance procedures including intervals and expected life time of parts).
- Repair (descriptions of all recommended repair procedures including spare parts).
- Calibration.
- Troubleshooting.
- Decommissioning.
- Reference information (safety standards, unit conversions, screw joints, lists of tools).
- Spare parts list with corresponding figures (or references to separate spare parts lists).
- References to circuit diagrams.

Technical reference manuals

The technical reference manuals describe reference information for robotics products, for example lubrication, the RAPID language, and system parameters.

Application manuals

Specific applications (for example software or hardware options) are described in **Application manuals**. An application manual can describe one or several applications.

An application manual generally contains information about:

- The purpose of the application (what it does and when it is useful).
- What is included (for example cables, I/O boards, RAPID instructions, system parameters, software).
- How to install included or required hardware.
- How to use the application.

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- Examples of how to use the application.

Operating manuals

The operating manuals describe hands-on handling of the products. The manuals are aimed at those having first-hand operational contact with the product, that is production cell operators, programmers, and troubleshooters.

How to read the product manual

Reading the procedures

The procedures contain references to figures, tools, material, and so on. The references are read as described below.

References to figures

The procedures often include references to components or attachment points located on the manipulator/controller. The components or attachment points are marked with *italic text* in the procedures and completed with a reference to the figure where the current component or attachment point is shown.

The denomination in the procedure for the component or attachment point corresponds to the denomination in the referenced figure.

The table below shows an example of a reference to a figure from a step in a procedure.

	Action	Note/Illustration
8.	Remove the *rear attachment screws, gearbox.*	Shown in the figure *Location of gearbox on page xx*.

References to required equipment

The procedures often include references to equipment (spare parts, tools, etc.) required for the different actions in the procedure. The equipment is marked with *italic text* in the procedures and completed with a reference to the section where the equipment is listed with further information, that is article number and dimensions.

The designation in the procedure for the component or attachment point corresponds to the designation in the referenced list.

The table below shows an example of a reference to a list of required equipment from a step in a procedure.

	Action	Note/Illustration
3.	Fit a new *sealing, axis 2* to the gearbox.	Art. no. is specified in *Required equipment on page xx.*

Safety information

The manual includes a separate safety chapter that must be read through before proceeding with any service or installation procedures. All procedures also include specific safety information when dangerous steps are to be performed.

Read more in the chapter *Safety on page 21*.

Illustrations

The robot is illustrated with general figures that does not take painting or protection type in consideration.

Likewise, certain work methods or general information that is valid for several robot models, can be illustrated with illustrations that show a different robot model than the one that is described in the current manual.

1 Safety

1.1 Safety information

1.1.1 Limitation of liability

Limitation of liability

Any information given in this manual regarding safety must not be construed as a warranty by ABB that the industrial robot will not cause injury or damage even if all safety instructions are complied with.

The information does not cover how to design, install and operate a robot system, nor does it cover all peripheral equipment that can influence the safety of the robot system.

In particular, liability cannot be accepted if injury or damage has been caused for any of the following reasons:

- Use of the robot in other ways than intended.
- Incorrect operation or maintenance.
- Operation of the robot when the safety devices are defective, not in their intended location or in any other way not working.
- When instructions for operation and maintenance are not followed as intended.
- Non-authorized design modifications of the robot.
- Repairs on the robot and its spare parts carried out by in-experienced or non-qualified personnel.
- Foreign objects.
- Force majeure.

Spare parts and equipment

ABB supplies original spare parts and equipment which have been tested and approved for their intended use. The installation and/or use of non-original spare parts and equipment can negatively affect the safety, function, performance, and structural properties of the robot. ABB is not liable for damages caused by the use of non-original spare parts and equipment.

1.1.2 Requirements on personnel

General

Only personnel with appropriate training are allowed to install, maintain, service, repair, and use the robot. This includes electrical, mechanical, hydraulics, pneumatics, and other hazards identified in the risk assessment.

Persons who are under the influence of alcohol, drugs or any other intoxicating substances are not allowed to install, maintain, service, repair, or use the robot.

The plant liable must make sure that the personnel is trained on the robot, and on responding to emergency or abnormal situations.

Personal protective equipment

Use personal protective equipment, as stated in the instructions.

1.2 Safety signals and symbols

1.2.1 Safety signals in the manual

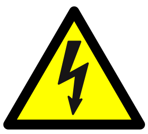
Introduction to safety signals

This section specifies all safety signals used in the user manuals. Each signal consists of:

- A caption specifying the hazard level (DANGER, WARNING, or CAUTION) and the type of hazard.
- Instruction about how to reduce the hazard to an acceptable level.
- A brief description of remaining hazards, if not adequately reduced.

Hazard levels

The table below defines the captions specifying the hazard levels used throughout this manual.

Symbol	Designation	Significance
	DANGER	Signal word used to indicate an imminently hazardous situation which, if not avoided, will result in serious injury.
	WARNING	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in serious injury.
	ELECTRICAL SHOCK	Signal word used to indicate a potentially hazardous situation related to electrical hazards which, if not avoided, could result in serious injury.
	CAUTION	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in slight injury.
	ELECTROSTATIC DISCHARGE (ESD)	Signal word used to indicate a potentially hazardous situation which, if not avoided, could result in severe damage to the product.
	NOTE	Signal word used to indicate important facts and conditions.

Continues on next page

Symbol	Designation	Significance
	TIP	Signal word used to indicate where to find additional information or how to do an operation in an easier way.

1.2.2 Safety symbols on manipulator labels

Introduction to symbols

This section describes safety symbols used on labels (stickers) on the manipulator.

Symbols are used in combinations on the labels, describing each specific warning. The descriptions in this section are generic, the labels can contain additional information such as values.

Note

The symbols on the labels on the product must be observed. Additional symbols added by the integrator must also be observed.

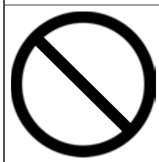
Types of symbols

Both the manipulator and the controller are marked with symbols, containing important information about the product. This is important for all personnel handling the robot, for example during installation, service, or operation.

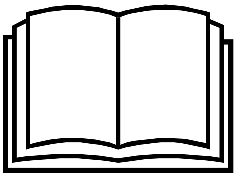
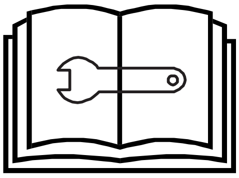
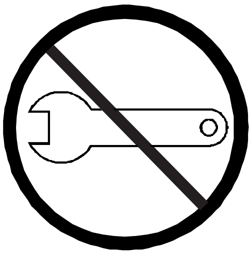
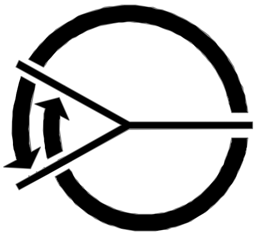
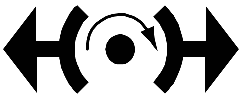
The safety labels are language independent, they only use graphics. See *Symbols on safety labels on page 25*.

The information labels can contain information in text.

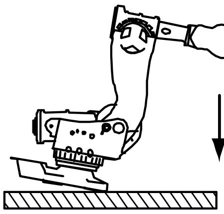
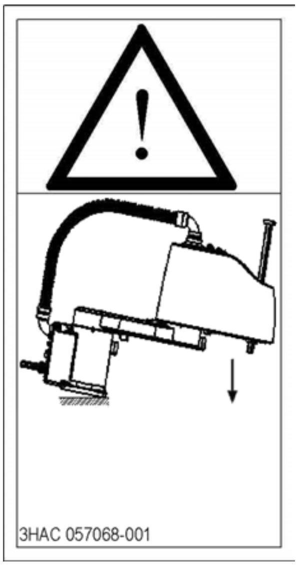
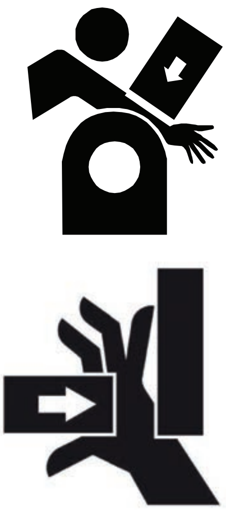
Symbols on safety labels

Symbol	Description
 xx0900000812	**Warning!** Warns that an accident *may* occur if the instructions are not followed that can lead to serious injury, possibly fatal, and/or great damage to the product. It applies to warnings that apply to danger with, for example, contact with high voltage electrical units, explosion or fire risk, risk of poisonous gases, risk of crushing, impact, fall from height, etc.
 xx0900000811	**Caution!** Warns that an accident may occur if the instructions are not followed that can result in injury and/or damage to the product. It also applies to warnings of risks that include burns, eye injury, skin injury, hearing damage, crushing or slipping, tripping, impact, fall from height, etc. Furthermore, it applies to warnings that include function requirements when fitting and removing equipment where there is a risk of damaging the product or causing a breakdown.
 xx0900000839	**Prohibition** Used in combinations with other symbols.

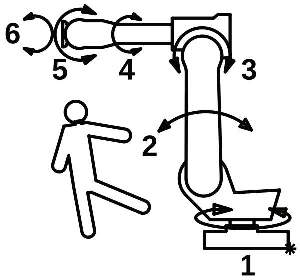
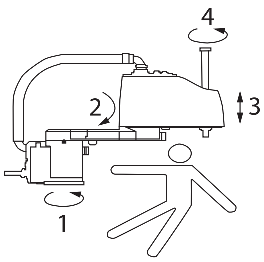
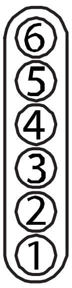
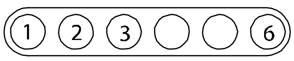
Continues on next page

Symbol	Description
 xx0900000813	**See user documentation** Read user documentation for details. Which manual to read is defined by the symbol: • No text: *Product manual*. • EPS: *Application manual - Electronic Position Switches*.
 xx0900000816	**Before disassembly, see product manual**
 xx0900000815	**Do not disassemble** Disassembling this part can cause injury.
 xx0900000814	**Extended rotation** This axis has extended rotation (working area) compared to standard.
 xx0900000808	**Brake release** Pressing this button will release the brakes. This means that the robot arm can fall down.

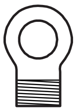
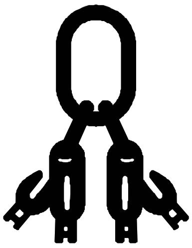
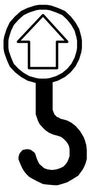
Continues on next page

Symbol	Description
 xx0900000810  xx1500002402	**Tip risk when loosening bolts** The robot can tip over if the bolts are not securely fastened.
 xx0900000817	**Crush** Risk of crush injuries.

Continues on next page

Symbol	Description
 xx0900000818  xx1300001087	**Heat** Risk of heat that can cause burns. (Both signs are used)
 xx2400000736  xx1500002616	**Moving robot** The robot can move unexpectedly.
 xx0900000820  xx1000001140	**Brake release buttons**

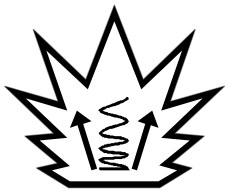
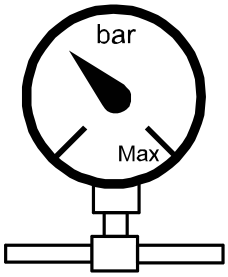
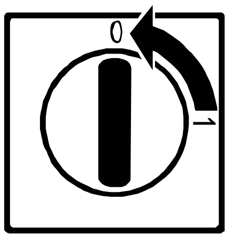
Continues on next page

Symbol	Description
 xx0900000821	**Lifting bolt**
 xx1000001242	**Adjustable chain sling with shortener**
 xx0900000822	**Lifting of robot**
	Swivel eye bolt The exclamation mark indicates required usage of swivel eye bolts at the lifting points.
 xx0900000823	**Oil** Can be used in combination with prohibition if oil is not allowed.
 xx0900000824	**Mechanical stop**
 xx1000001144	**No mechanical stop**

Continues on next page

1.2.2 Safety symbols on manipulator labels

Continued

Symbol	Description
 xx0900000825	**Stored energy** Warns that this part contains stored energy. Used in combination with *Do not disassemble* symbol.
 xx0900000826	**Pressure** Warns that this part is pressurized. Usually contains additional text with the pressure level.
 xx0900000827	**Shut off with handle** Use the power switch on the controller.
 xx1400002648	**Do not step** Warns that stepping on these parts can cause damage to the parts.

1.3 Robot stopping functions

Protective stop and emergency stop

The protective stops and emergency stops are described in the product manual for the controller.

For more information see:

- *Product manual - OmniCore V250XT*
- *Product manual - OmniCore V250XT Type A*
- *Product manual - IRC5*
- *Product manual - IRC5 Panel Mounted Controller*

1.4 Safety during installation and commissioning

National or regional regulations

The integrator of the robot system is responsible for the safety of the robot system.

The integrator is responsible that the robot system is designed and installed in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

The integrator of the robot system is required to perform a risk assessment.

Layout

The robot integrated to a robot system shall be designed to allow safe access to all spaces during installation, operation, maintenance, and repair.

If robot movement can be initiated from an external control panel then an emergency stop must also be available.

If the manipulator is delivered with mechanical stops, these can be used for reducing the working space.

A perimeter safeguarding, for example a fence, shall be dimensioned to withstand the following:

- The force of the manipulator.
- The force of the load handled by the robot if dropped or released at maximum speed.
- The maximum possible impact caused by a breaking or malfunctioning rotating tool or other device fitted to the robot.

The maximum TCP speed and the maximum velocity of the robot axes are detailed in the section *Robot motion* in the product specification for the respective manipulator.

Consider exposure to hazards, such as slipping, tripping, and falling.

Hazards due to the working position and posture for a person working with or near the robot shall be considered.

Hazards due to noise emission from the robot needs to be considered.

Consider hazards from other equipment in the robot system, for example, that guards remain active until identified hazards are reduced to an acceptable level.

Allergenic material

See *Environmental information on page 440* for specification of allergenic materials in the product, if any.

Securing the robot to the foundation

The robot must be properly fixed to its foundation/support, as described in the respective product manual.

When the robot is installed at a height, hanging, or other than mounted directly on the floor, there will be additional hazards.

Continues on next page

Using lifting accessories and other external equipment

Ensure that all equipment used during installation, service and all handling of the robot are in correct condition for the intended use.

Electrical safety

Incoming mains must be installed to fulfill national regulations.

The power supply wiring to the robot must be sufficiently fused and if necessary, it must be possible to disconnect it manually from the mains power.

The power to the robot must be turned off with the main switch and the mains power disconnected when performing work inside the controller cabinet. Lock and tag shall be considered.

Harnesses between controller and manipulator shall be fixed and protected to avoid tripping and wear.

Wherever possible, power on/off or rebooting the robot controller shall be performed with all persons outside the safeguarded space.

Note

Use a CARBON DIOXIDE (CO_2) extinguisher in the event of a fire in the robot.

Safety devices

The integrator is responsible for that the safety devices necessary to protect people working with the robot system are designed and installed correctly.

When integrating the robot with external devices to a robot system:

- The integrator of the robot system must ensure that emergency stop functions are interlocked in accordance with applicable standards.
- The integrator of the robot system must ensure that safety functions are interlocked in accordance with applicable standards.

Other hazards

A robot may perform unexpected limited movement.

WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

The risk assessment should also consider other hazards arising from the application, such as, but not limited to:

- Water
- Compressed air
- Hydraulics

End-effector hazards require particular attention for applications which involve close human collaboration with the robot.

Continues on next page

Pressure relief valves

The pressure relief valve prevents too much air pressure being built up inside the robot. The air pressure must not exceed the rated limit for the manipulator, or there is a risk of personal injury and mechanical damage.

Pressure relief valves must be kept clean.

Pneumatic or hydraulic related hazards

> **Note**
>
> The pressure in the complete pneumatic or hydraulic systems must be released before service and maintenance.
>
> All components in the robot system that remain pressurized after switching off the power to the robot must be marked with clearly visible drain facilities and a warning sign that indicates the hazard of stored energy.

Loss of pressure in the robot system may cause parts or objects to drop.

Dump valves should be used in case of emergency.

Shot bolts should be used to prevent tools, etc., from falling due to gravity.

All pipes, hoses, and connections have to be inspected regularly for leaks and damage. Damage must be repaired immediately.

Verify the safety functions

Before the robot system is put into operation, verify that the safety functions are working as intended and that any remaining hazards identified in the risk assessment are mitigated to an acceptable level.

1.5 Safety during operation

Automatic operation

Verify the application in the operating mode manual reduced speed, before changing mode to automatic and initiating automatic operation.

Unexpected movement of robot arm

WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.

WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

1.6 Safety during maintenance and repair

1.6.1 Safety during maintenance and repair

General

Corrective maintenance must only be carried out by personnel trained on the robot.

Maintenance or repair must be done with all electrical, pneumatic, and hydraulic power switched off, that is, no remaining hazards.

Hazards due to stored mechanical energy in the manipulator for the purpose of counterbalancing axes must be considered before maintenance or repair.

Never use the robot as a ladder, which means, do not climb on the controller, manipulator, including motors, or other parts. There are hazards of slipping and falling. The robot might be damaged.

Make sure that there are no tools, loose screws, turnings, or other unexpected parts remaining after maintenance or repair work.

When the work is completed, verify that the safety functions are working as intended.

Hot surfaces

Surfaces can be hot after running the robot, and touching these may result in burns. Allow the surfaces to cool down before maintenance or repair.

Allergic reaction

Warning	Description	Elimination/Action
Allergic reaction	When working with lubricants there is a risk of an allergic reaction.	Make sure that protective gear like goggles and gloves are always worn.

Gearbox lubricants (oil or grease)

When handling oil, grease, or other chemical substances the safety information of the respective manufacturer must be observed.

Note

Take special care when handling hot lubricants.

Warning	Description	Elimination/Action
Hot oil or grease	Changing and draining gearbox oil or grease may require handling hot lubricant heated up to 90 °C.	Make sure that protective gear like goggles and gloves are always worn during this activity.

Continues on next page

Warning	Description	Elimination/Action
Allergic reaction	When working with lubricants there is a risk of an allergic reaction.	Make sure that protective gear like goggles and gloves are always worn.
Possible pressure build-up in gearbox	When opening the oil or grease plug, there may be pressure present in the gearbox, causing hot lubricant to spray from the opening.	Open the plug carefully and keep away from the opening. Do not overfill the gearbox when filling. Put oil absorbent cloth, bags or paper at appropriate locations to catch any oil residues. Use appropriate protective gear such as heat-resistant gloves, goggles/protective visor, or a body suit if necessary.
Do not overfill	Overfilling of gearbox lubricant can lead to internal over-pressure inside the gearbox which in turn may: • damage seals and gaskets • completely press out seals and gaskets • prevent the robot from moving freely.	Make sure not to overfill the gearbox when filling it with oil or grease. After filling, verify that the level is correct.
Do not mix types of oil	Mixing types of oil may cause severe damage to the gearbox.	When filling gearbox oil, do not mix different types of oil unless specified in the instructions. Always use the type of oil specified for the product.
Oil residues	Oil residues might be present in a drained gearbox and spilled when separating a motor and gearbox during repair.	Make sure that protective gear like goggles/protective visor, gloves and arm protection are always worn during this activity. Put oil absorbent cloth, bags or paper at appropriate locations to catch any oil residues.
Heat up the oil	Warm oil drains quicker than cold oil.	Run the robot before changing the gearbox oil, if possible.
Specified amount depends on drained volume	The specified amount of oil or grease is based on the total volume of the gearbox. When changing the lubricant, the amount refilled may differ from the specified amount, depending on how much has previously been drained from the gearbox.	After filling, verify that the level is correct.

Continues on next page

Warning	Description	Elimination/Action
 **Contaminated oil in gearboxes**	For lifetime reasons always drain as much oil as possible from the gearbox. The magnetic oil plugs will gather residual metal chips.	

Hazards related to batteries

Under rated conditions, the electrode materials and liquid electrolyte in the batteries are sealed and not exposed to the outside.

There is a hazard in case of abuse (mechanical, thermal, electrical) which leads to the activation of safety valves and/or the rupture of the battery container. As a result under certain circumstances, electrolyte leakage, electrode materials reaction with moisture/water or battery vent/explosion/fire may follow.

Do not short circuit, recharge, puncture, incinerate, crush, immerse, force discharge or expose to temperatures above the declared operating temperature range of the product. Risk of fire or explosion.

Operating temperatures are listed in *Operating conditions, robot on page 48*.

See safety instructions for the batteries in *Material/product safety data sheet - Battery pack* (*3HAC043118-001*).

Unexpected movement of robot arm

>  **WARNING**
>
> Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.

>  **WARNING**
>
> Manipulator movements can cause serious injuries on users and may damage equipment.

Related information

See also the safety information related to installation and operation.

1.6.2 Emergency release of the robot axes

Description

In an emergency situation, the brakes on a robot axis can be released manually by pushing a brake release button.

How to release the brakes is described in the section:

- *Manually releasing the brakes on page 65*.

The robot may be moved manually on smaller robot models, but larger models may require using an overhead crane or similar equipment.

Increased injury

Before releasing the brakes, make sure that the weight of the manipulator does not result in additional hazards, for example, even more severe injuries on a trapped person.

DANGER

When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways.

Make sure no personnel is near or beneath the robot.

Prerequsites for access to brake release buttons

Make sure that the brake release buttons on the manipulator are within reach and quickly accessible in case of emergency situations, even when the manipulator is installed on a height, on a wall, or suspended.

1.6.3 Brake testing

When to test

During operation, the holding brake of each axis normally wears down. A test can be performed to determine whether the brake can still perform its function.

How to test

The function of the holding brake of each axis motor may be verified as described below:

1. Run each axis to a position where the combined weight of the manipulator and any load is maximized (maximum static load).
2. Switch the motor to the MOTORS OFF.
3. Inspect and verify that the axis maintains its position.

   If the manipulator does not change position as the motors are switched off, then the brake function is adequate.

Note

It is recommended to run the service routine *BrakeCheck* as part of the regular maintenance, see the operating manual for the robot controller.

For robots with the option SafeMove, the *Cyclic Brake Check* routine is recommended. See the manual for SafeMove in *References on page 10*.

1.7 Safety during troubleshooting

General

When troubleshooting requires work with power switched on, special considerations must be taken:

- Safety circuits might be muted or disconnected.
- Electrical parts must be considered as *live*.
- The manipulator can move unexpectedly at any time.

DANGER

Troubleshooting on the controller while powered on must be performed by personnel trained by ABB or by ABB field engineers.

CAUTION

Risk of hot surfaces that can cause burns.

A risk assessment must be done to address both robot and robot system specific hazards.

WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.

WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

Related information

See also the safety information related to installation, operation, maintenance, and repair.

1.8 Safety during decommissioning

General

See section *Decommissioning on page 439*.

If the robot is decommissioned for storage, take extra precaution to reset safety devices to delivery status.

Unexpected movement of robot arm

WARNING

Hazards due to the use of brake release devices and/or gravity beneath the manipulator shall be considered.

A robot may perform unexpected limited movement.

WARNING

Manipulator movements can cause serious injuries on users and may damage equipment.

2 Installation and commissioning

2.1 Introduction to installation and commissioning

General

This chapter contains assembly instructions and information for installing the IRB 2600/IRB 2600 ID at the working site.

See also the product manual for the robot controller.

The installation must be done by qualified installation personnel in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

The technical data is detailed in section *Technical data on page 45*.

Safety information

Before any installation work is commenced, all safety information must be observed.

There are general safety aspects that must be read through, as well as more specific safety information that describes the danger and safety risks when performing the procedures. Read the chapter *Safety on page 21* before performing any installation work.

Note

Always connect the IRB 2600/IRB 2600 ID and the robot to protective earth and residual current device (RCD) before connecting to power and starting any installation work.

For more information see:

- *Product manual - OmniCore V250XT*
- *Product manual - OmniCore V250XT Type A*
- *Product manual - IRC5*
- *Product manual - IRC5 Panel Mounted Controller*

2.2 Unpacking

2.2.1 Pre-installation procedure

Introduction

This section is intended for use when unpacking and installing the robot for the first time. It also contains information useful during later re-installation of the robot.

Prerequisites for installation personnel

Installation personnel working with an ABB product must:

- be trained by ABB and have the required knowledge of mechanical and electrical installation/maintenance/repair work
- conform to all national and local codes.

Checking the pre-requisites for installation

	Action
1	Make a visual inspection of the packaging and make sure that nothing is damaged.
2	Remove the packaging.
3	Check for any visible transport damage. **Note** Stop unpacking and contact ABB if transport damages are found.
4	Clean the unit with a lint-free cloth, if necessary.
5	Make sure that the lifting accessory used (if required) is suitable to handle the weight of the robot as specified in: *Weight, robot on page 45*
6	If the robot is not installed directly, it must be stored as described in: *Storage conditions, robot on page 48*
7	Make sure that the expected operating environment of the robot conforms to the specifications as described in: *Operating conditions, robot on page 48*
8	Before taking the robot to its installation site, make sure that the site conforms to: • *Loads on foundation, robot on page 46* • *Protection classes, robot on page 48* • *Requirements, foundation on page 47*
9	Before moving the robot, please observe the stability of the robot: *Risk of tipping/stability on page 54*
10	When these prerequisites are met, the robot can be taken to its installation site as described in section: *On-site installation on page 57*
11	Install required equipment, if any. • *Safety lamp (option for IRC5) on page 99*

2.2.2 Technical data

Weight, robot

The table shows the weight of the robot.

Robot model	Weight
IRB 2600/IRB 2600 ID	280 kg

Note

The weight does not include tools and other equipment fitted on the robot.

Mounting positions

The table shows valid mounting options for the manipulator.

Mounting option	Installation angle	Note
Floor mounted	0°	
Wall mounted	90°	
Suspended	180° [i]	
Tilted	0-45°	Contact ABB for further information about acceptable loads.

[i] IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is not available for suspended installation.

Note

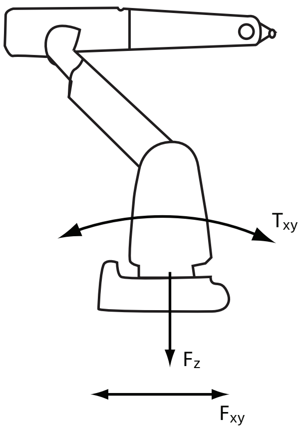
The actual mounting angle must always be configured in the system parameters, otherwise the performance and lifetime is affected. See *Setting the system parameters for a suspended or tilted robot on page 61*.

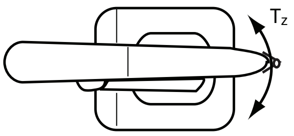
Continues on next page

Loads on foundation, robot

The illustration shows the directions of the robots stress forces.

The directions are valid for all floor mounted, suspended and inverted robots.





xx1100000521

F_{xy}	Force in any direction in the XY plane
F_z	Force in the Z plane
T_{xy}	Bending torque in any direction in the XY plane
T_z	Bending torque in the Z plane

The table shows the various forces and torques working on the robot during different kinds of operation.

Note

These forces and torques are extreme values that are rarely encountered during operation. The values also never reach their maximum at the same time!

WARNING

The robot installation is restricted to the mounting options given in following load table(s).

Floor mounted

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	±2330 N	±5450 N
Force z	2750 ±1420 N	2750 ±3970 N
Torque xy	±3360 Nm	±7690 Nm
Torque z	±1120 Nm	±3050 Nm

Continues on next page

Wall mounted

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	2750 ±880 N	2750 ±4600 N
Force z	±1780 N	±4560 N
Torque xy	1470 ±1990 Nm	1470 ±5620 Nm
Torque z	±1150 Nm	±3130 Nm

Suspended

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	±2250 N [i]	±5380 N [i]
Force z	-2750 ±1420 N [i]	-2750 ±4280 N [i]
Torque xy	±3440 Nm [i]	±7800 Nm [i]
Torque z	±1110 Nm [i]	±3050 Nm [i]

i Only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is not available for suspended installation.

Requirements, foundation

The table shows the requirements for the foundation where the weight of the installed robot is included:

Requirement	Value	Note
Flatness of foundation surface	0.5 mm	Flat foundations give better repeatability of the resolver calibration compared to original settings on delivery from ABB. The value for levelness aims at the circumstance of the anchoring points in the robot base. In order to compensate for an uneven surface, the robot can be recalibrated during installation. If resolver/encoder calibration is changed this will influence the absolute accuracy.
Minimum resonance frequency	25 Hz **Note** It may affect the manipulator life-time to have a lower resonance frequency than recommended.	The value is recommended for optimal performance. Due to foundation stiffness, consider robot mass including equipment. [i] For information about compensating for foundation flexibility, see the application manual of the controller software, section *Motion Process Mode*.

i The minimum resonance frequency given should be interpreted as the frequency of the robot mass/inertia, robot assumed stiff, when a foundation translational/torsional elasticity is added, i.e., the stiffness of the pedestal where the robot is mounted. The minimum resonance frequency should not be interpreted as the resonance frequency of the building, floor etc. For example, if the equivalent mass of the floor is very high, it will not affect robot movement, even if the frequency is well below the stated frequency. The robot should be mounted as rigid as possibly to the floor.
Disturbances from other machinery will affect the robot and the tool accuracy. The robot has resonance frequencies in the region 10 – 20 Hz and disturbances in this region will be amplified, although somewhat damped by the servo control. This might be a problem, depending on the requirements from the applications. If this is a problem, the robot needs to be isolated from the environment.

Continues on next page

Storage conditions, robot

The table shows the allowed storage conditions for the robot:

Parameter	Value
Minimum ambient temperature	-25° C
Maximum ambient temperature	+55° C
Maximum ambient temperature (less than 24 hrs)	+70° C
Maximum ambient humidity	95% at constant temperature (gaseous only)

Operating conditions, robot

The table shows the allowed operating conditions for the robot:

Parameter	Value
Minimum ambient temperature	+5°C
Maximum ambient temperature	+45°C
Maximum ambient humidity	95% at constant temperature

Protection classes, robot

The table shows the available protection types of the robot, with the corresponding protection class.

Protection type	Protection class[i]
Manipulator, protection type Standard	IRB 2600: IP 67 IRB 2600ID upper arm: IP 54
Manipulator, protection type Foundry Plus	IP 67

i According to IEC 60529.

2.2.3 Working range and type of motion

Working range

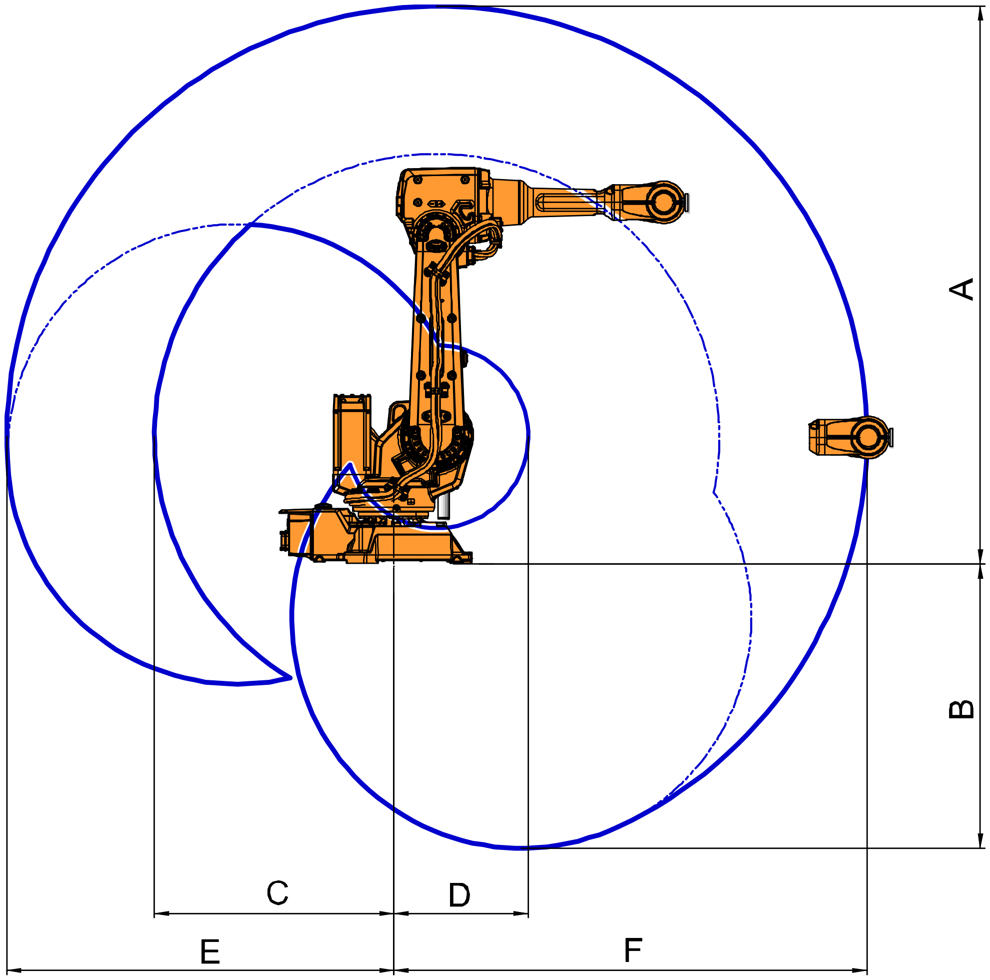
The figures show the working ranges of the robot variants mounted in different ways.

The extreme positions of the robot arm are specified at the wrist center (dimensions in mm).

Working range, floor mounted

The illustration shows the unrestricted working range for a floor mounted robot.

IRB 2600 Standard

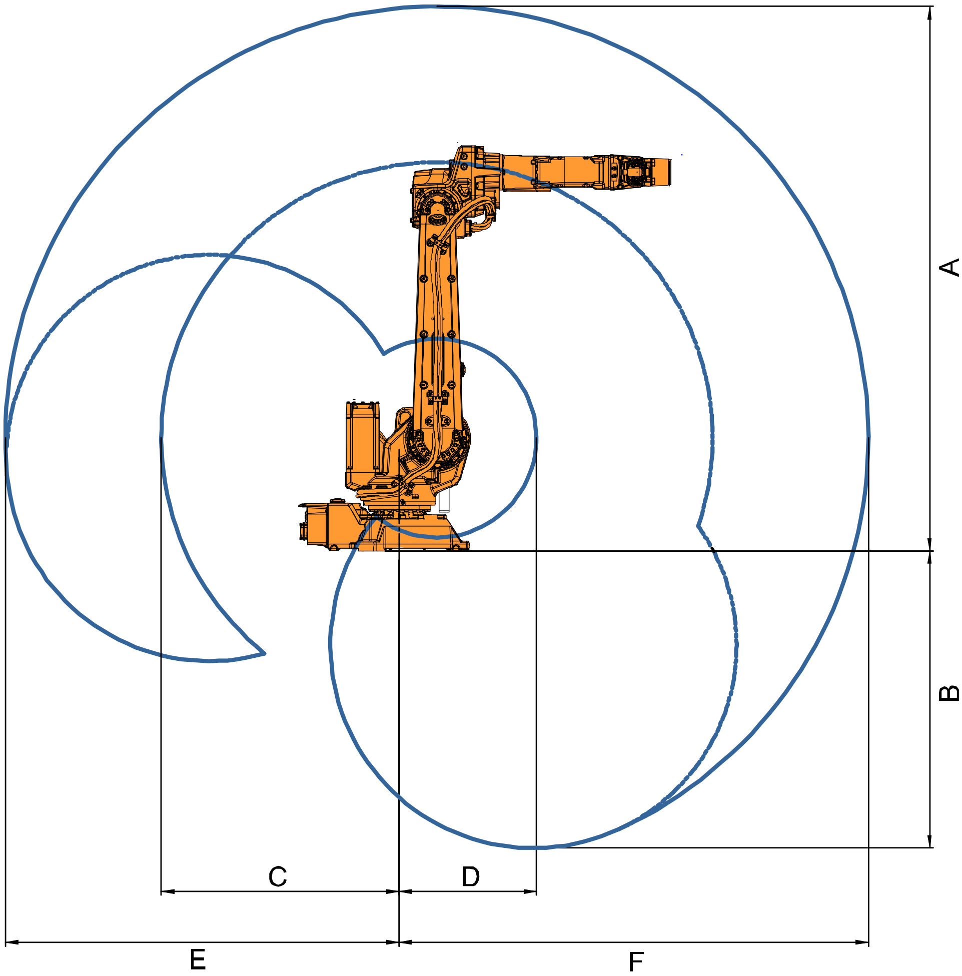


xx0900000194

Variant	Pos. A	Pos. B	Pos. C	Pos. D	Pos. E	Pos. F
IRB 2600-20/1.65 IRB 2600-12/1.65 IRB 2600 Type C-20/1.65 IRB 2600 Type C-12/1.65	1948 mm	993 mm	837 mm	469 mm	1353 mm	1653 mm
IRB 2600-12/1.85	2148 mm	1174 mm	967 mm	506 mm	1553 mm	1853 mm

Continues on next page

IRB 2600ID



xx1000000300

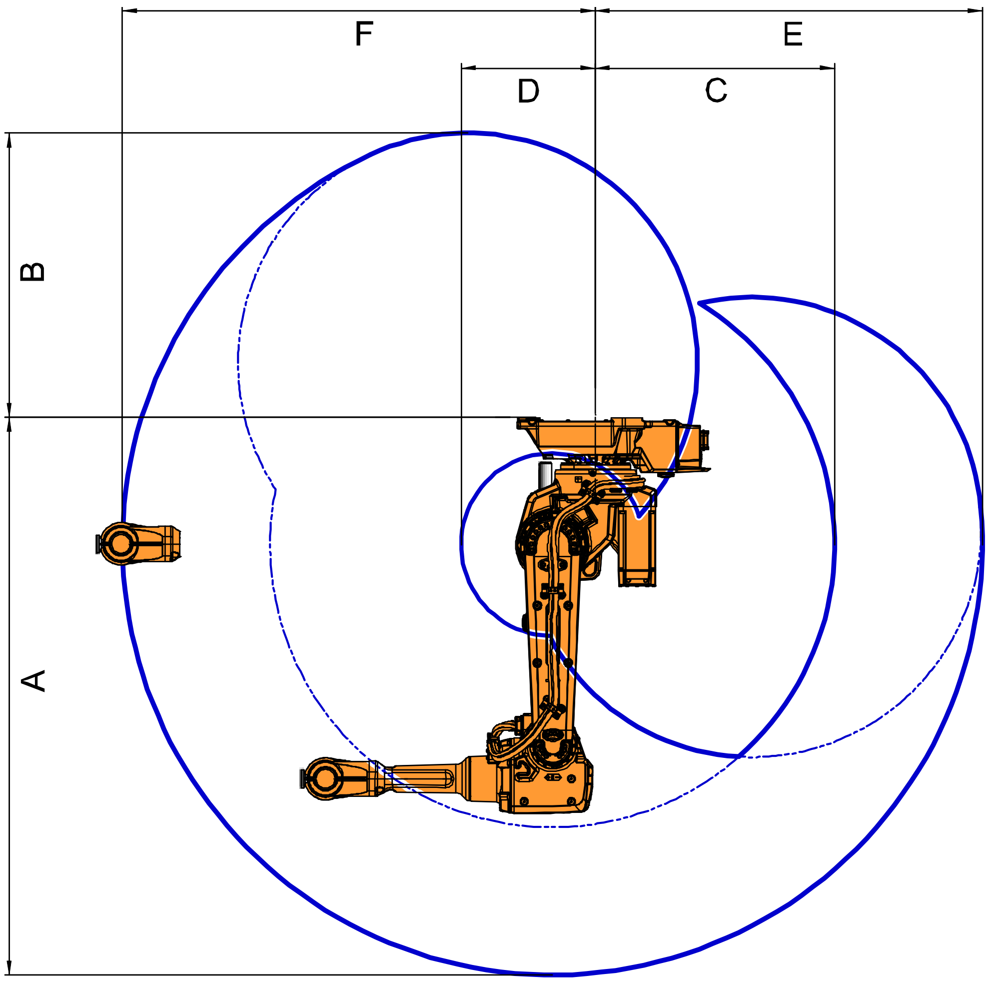
Variant	Pos. A	Pos. B	Pos. C	Pos. D	Pos. E	Pos. F
IRB 2600ID-15/1.85	2145 mm	1171 mm	936 mm	542 mm	1550 mm	1850 mm
IRB 2600ID-8/2.00	2295 mm	1321 mm	1051 mm	539 mm	1700 mm	2000 mm

Working range, suspended mounted

This section is only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.

The illustration shows the unrestricted working range for a suspended mounted robot.

Continues on next page



xx0900000195

Variant	Pos. A	Pos. B	Pos. C	Pos. D	Pos. E	Pos. F
IRB 2600 - 20/1.65	1948 mm	993 mm	837 mm	469 mm	1353 mm	1653 mm
IRB 2600 - 12/1.65	1948 mm	993 mm	837 mm	469 mm	1353 mm	1653 mm
IRB 2600 - 12/1.85	2148 mm	1174 mm	967 mm	506 mm	1553 mm	1853 mm

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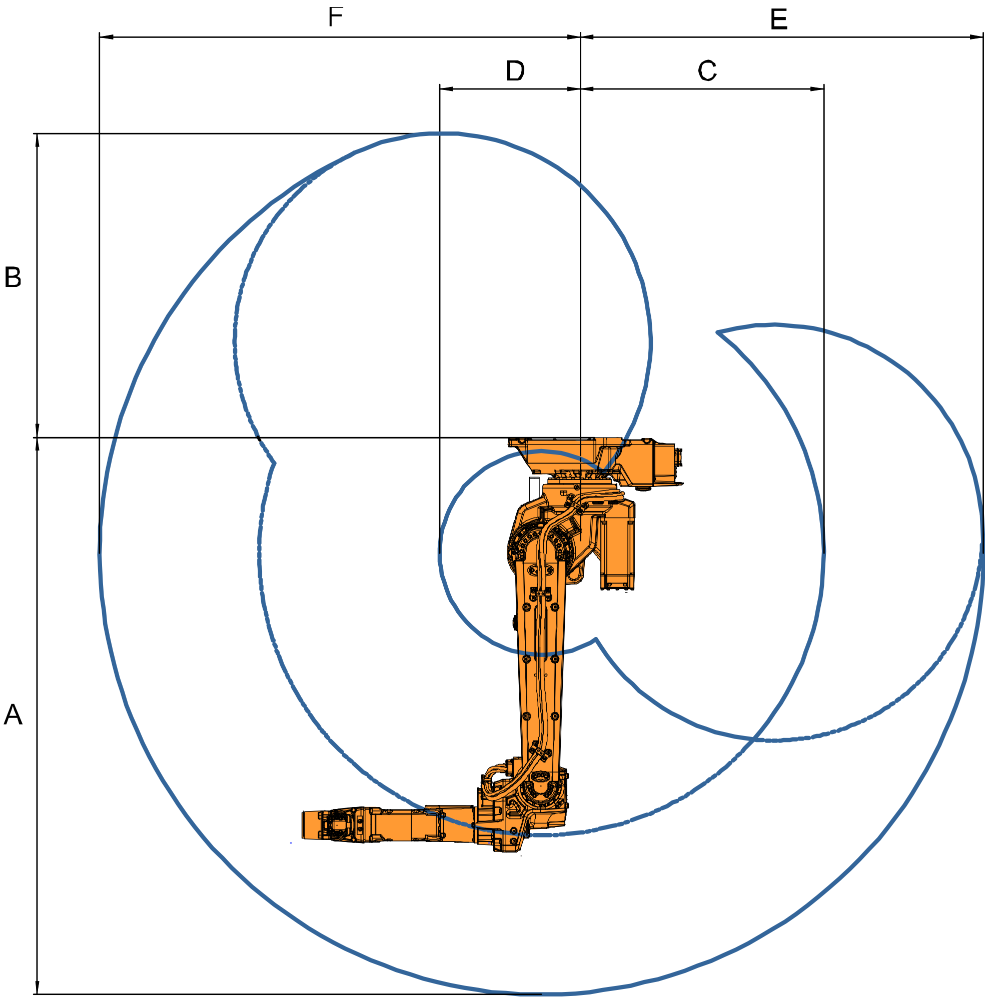

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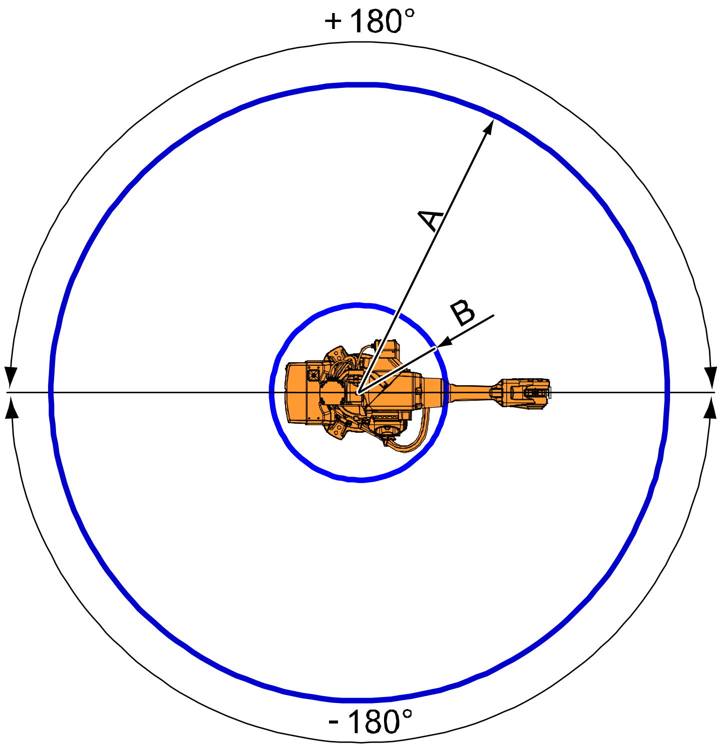
Variant	Pos. A	Pos. B	Pos. C	Pos. D	Pos. E	Pos. F
IRB 2600ID-15/1.85	2145 mm	1171 mm	936 mm	542 mm	1550 mm	1850 mm
IRB 2600ID-8/2.00	2295 mm	1321 mm	1051 mm	539 mm	1700 mm	2000 mm

Turning radius

The turning radius of the robot that is floor or suspended mounted is shown in the figure.

Continues on next page



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Variant	Pos. A	Pos. B
IRB 2600-20/1.65 IRB 2600-12/1.65 IRB 2600 Type C-20/1.65 IRB 2600 Type C-12/1.65	R1653	R469
IRB 2600-12/1.85	R1853	R506
IRB 2600ID-15/1.85	R1850	R542
IRB 2600ID-8/2.00	R2000	R539

Robot motion,

The table specifies the types and ranges of motion in every axes.

Location of motion	Type of motion	Range of movement
Axis 1	Rotation motion	±180°
Axis 2	Arm motion	+155° / -95°
Axis 3	Arm motion	+75° / -180°
Axis 4 (IRB 2600 standard)	Wrist motion	±400°
Axis 4 (IRB 2600ID)	Wrist motion	±175°
Axis 5	Bend motion	±120°
Axis 6	Turn motion	±400°

2.2.4 Risk of tipping/stability

Risk of tipping

If the robot is not fastened to the foundation while moving the arm, the robot is not stable in the whole working area. Moving the arm will displace the center of gravity, which may cause the robot to tip over.

The transportation position is the most stable position.

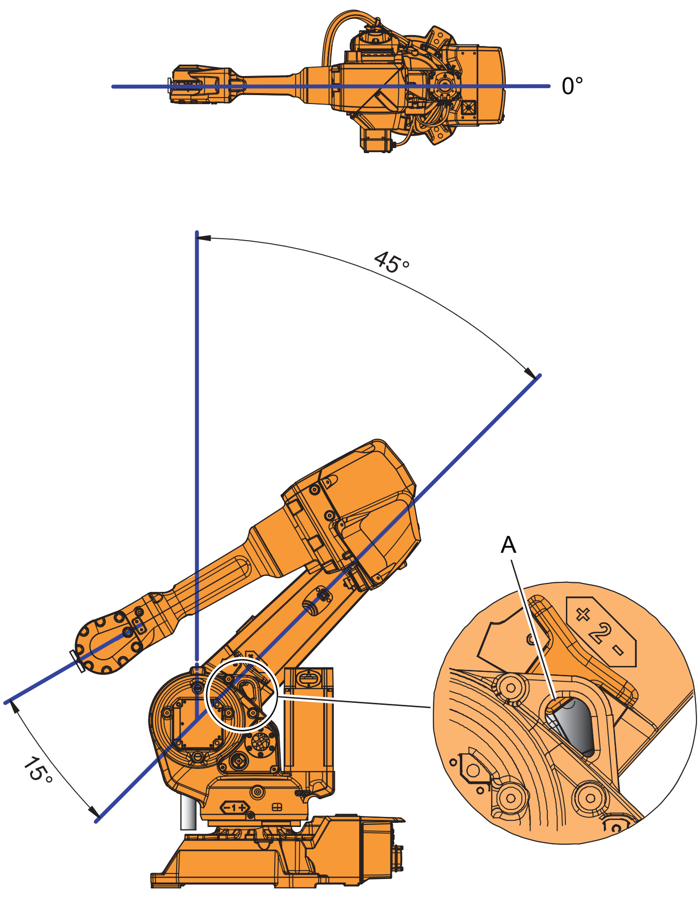
Do not change the robot position before securing it to the foundation!

Transportation position

This figure shows the robot in its transportation position.

The figure shows IRB 2600 but is also valid for IRB 2600ID. Best position of IRB 2600ID axis 4 is ±90°.

The position where part of the lower arm (A) is beginning to show in the hole, is approximate.



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Axis number	Angle of axis
Axis 1	0°
Axis 2	-45°
Axis 3	+75°

Continues on next page

Axis number	Angle of axis
Axis 4	IRB 2600: 0° IRB 2600ID: ±90°
Axis 5	+0°
Axis 6	0°

Note

The robot might be positioned in a different position at delivery, due to actual configurations and options (for example DressPack).

WARNING

The robot will be mechanically unstable if not properly secured to the foundation.

2.2.5 The unit is sensitive to ESD

Description

ESD (electrostatic discharge) is the transfer of electrical static charge between two bodies at different potentials, either through direct contact or through an induced electrical field. When handling parts or their containers, personnel not grounded may potentially transfer high static charges. This discharge may destroy sensitive electronics.

Safe handling

Use one of the following alternatives:

- Use a wrist strap.

  Wrist straps must be tested frequently to ensure that they are not damaged and are operating correctly.
- Use an ESD protective floor mat.

  The mat must be grounded through a current-limiting resistor.
- Use a dissipative table mat.

  The mat should provide a controlled discharge of static voltages and must be grounded.

2.3 On-site installation

2.3.1 Lifting robot with roundslings

Introduction

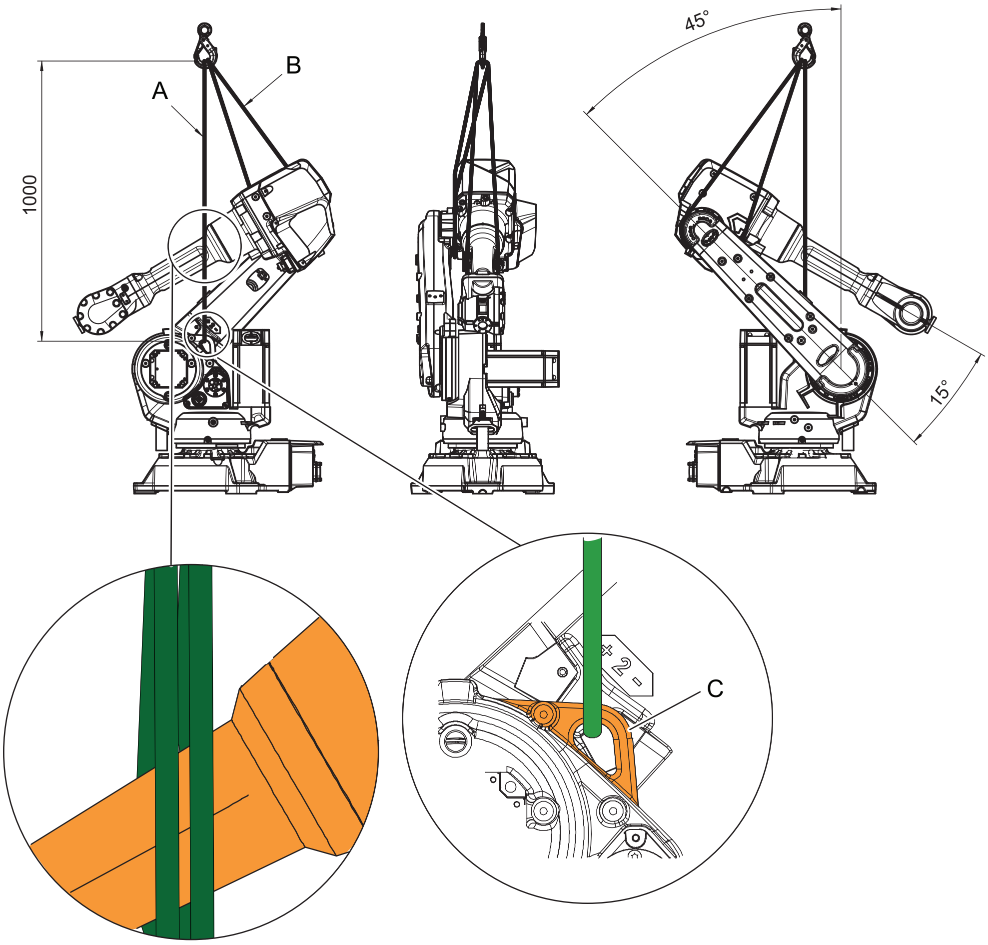
When lifting the robot use roundslings and an overhead crane.

Required equipment

Equipment	Note
Overhead crane	Lifting capacity 1 000 kg (Max load at 90°)
Roundslings (2 pcs)	• Lifting capacity/roundsling: 1 000 kg • Lengths: 2 m, 1.5 m

Lifting

Attach the roundslings as shown in the figure.



xx0900000236

A	Roundsling, length 2 m (put folded in U-shape around the upper arm)
B	Roundsling, length 1.5 m (put folded in U-shape around gearbox axis 3)
C	Lifting lug

Continues on next page

Lifting instructions

Use this procedure to lift the robot in a safe way.

	Action	Note
1	**CAUTION** The IRB 2600/IRB 2600 ID robot weighs 280 kg. All lifting accessories used must be sized accordingly!	
2	**CAUTION** Attempting to lift the robot in any other position than that recommended may result in the robot tipping over and causing severe damage or injury!	
3	**WARNING** Personnel must not, under any circumstances, be present under the suspended load!	
4	Move the robot to its most stable position. For robot versions IRB 2600ID: The best position of axis 4 is ±90°.	Detailed in section: • *Risk of tipping/stability on page 54*
5	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
6	Attach *roundsling A* to the lifting lug on the frame, and put folded in a U-shape on either side of the upper arm.	See the figure in: • *Lifting on page 57*
7	Attach *roundsling B* at axis 3 gearbox by running it folded in a U-shape around the gearbox.	See the figure in: • *Lifting on page 57*
8	Make sure the roundslings do not rub against any sharp edges.	

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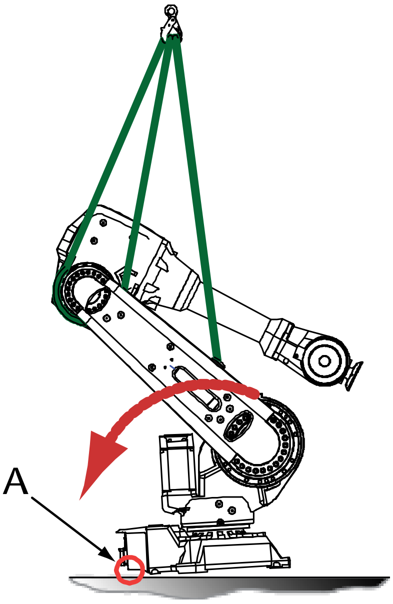
	Action	Note
9	When the robot is lifted the roundslings will adjust themselves. **CAUTION** When lifting, the robot will tilt slightly backwards! Be careful not to damage the *connection box* at the base of the robot!	 xx0800000291 • A: Area where the connection box can be damaged while lifting.
10	Lift the robot with an overhead crane.	Lifting capacity: • See *Required equipment on page 57*

2.3.2 Lifting and turning a suspended mounted robot

Validity of this section

This section is only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.

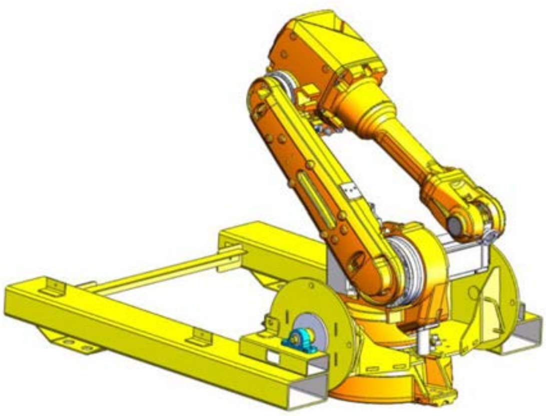
Introduction

How to lift and turn the robot to a suspended position using the turning accessory is described in the lifting instruction delivered with the turning accessory. Article numbers for the accessory and the instruction is specified in *Special tools on page 457*. Any additional equipment required is specified in the instruction for the lifting accessory. Contact ABB for more information.

How to lift and turn the robot into position for **wall** position: Contact ABB for more information.

How to lift and turn the robot into position for **tilted** position: Contact ABB for more information.

Illustration



xx1500002117

2.3.3 Setting the system parameters for a suspended or tilted robot

General

The robot is configured for mounting parallel to the floor, without tilting, on delivery. If the robot is mounted in any other angle than 0°, then the system parameters that describe the mounting angle (how the robot is oriented relative to the gravity) must be re-defined.

Note

With inverted installation, make sure that the gantry or corresponding structure is rigid enough to prevent unacceptable vibrations and deflections, so that optimum performance can be achieved.

Note

The mounting positions are described in *Mounting positions on page 45*, and the requirements on the foundation are described in *Requirements, foundation on page 47*.

Note

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is not available for suspended installation.

System parameters

Note

The mounting angle must be configured correctly in the system parameters so that the robot system can control the movements in the best possible way. An incorrect definition of the mounting angle will result in:

- Overloading the mechanical structure.
- Lower path performance and path accuracy.
- Some functions will not work properly, for example *Load Identification* and *Collision detection*.

Gravity Beta

If the robot is mounted upside down or on a wall (rotated around the y-axis), then the robot base frame and the system parameter *Gravity Beta* must be redefined. *Gravity Beta* should then be π (+3.141593) if the robot is mounted upside down (suspended), or ±π/2 (±1.570796) if mounted on a wall.

The *Gravity Beta* is a positive rotation direction around the y-axis in the base coordinate system. The value is set in radians.

Continues on next page

Gravity Alpha

If the robot is mounted on a wall (rotated around the x-axis), then the robot base frame and the system parameter *Gravity Alpha* must be redefined. The value of *Gravity Alpha* should then be ±π/2 (±1.570796).

The *Gravity Alpha* is a positive rotation direction around the x-axis in the base coordinate system. The value is set in radians.

Note

The system parameter *Gravity Alpha* is not supported for all robot types. It is not supported for IRB 140, IRB 1410, IRB 1600ID, IRB 2400, IRB 4400, IRB 6400R, IRB 6400 (except for IRB 6400 200/2.5 and IRB 6400 200/2.8), IRB 6600, IRB 6650, IRB 6650S and IRB 7600 (except for IRB 7600 325/3.1).

If the robot does not support *Gravity Alpha*, then use *Gravity Beta* along with the recalibration of axis 1 to define the rotation of the robot around the x-axis.

Note

The parameter is supported for all robots on track when the system parameter *7 axes high performance motion* is set, see *Technical reference manual - System parameters*.

Gamma Rotation

Gamma Rotation defines the orientation of the robot foot on the travel carriage (track motion).

Mounting angles and values

The parameter *Gravity Beta* (or *Gravity Alpha*) specifies the mounting angle of the robot in radians. It is calculated in the following way.

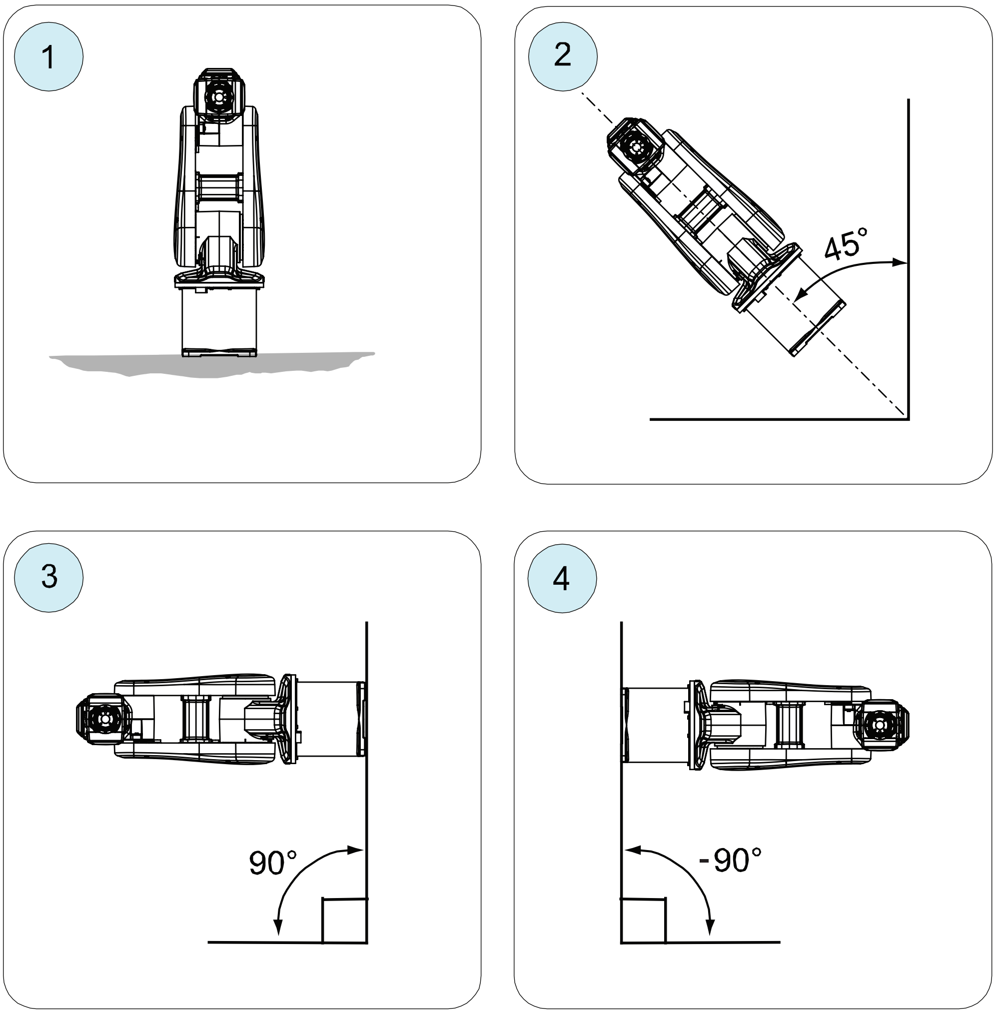
`Gravity Beta = A° x 3.141593/180 = B radians`, where `A` is the mounting angle in degrees and `B` is the mounting angle in radians.

Example of position	Mounting angle (A°)	Gravity Beta
Floor mounted	0°	0.000000 (Default)
Tilted mounting	15°	0.261799
Wall mounting	90°	1.570796
Suspended mounting	180°	3.141593

Examples of mounting angles tilted around the X axis (*Gravity Alpha*)

The following illustration shows the IRB 120, but the same principle applies for all robots.

Continues on next page



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Pos	Mounting angle	Gravity Alpha
1	0° (Floor mounted)	0
2	45° (Tilted)	0.785398
3	90° (Wall)	1.570796
4	-90° (Wall)	-1.570796

Note

For suspended robots (180°), it is recommended to use *Gravity Beta* instead of *Gravity Alpha*.

Defining the parameter in RobotWare

The value of the system parameters that define the mounting angle must be redefined when changing the mounting angle of the robot. The parameters belong to the type *Robot*, in the topic *Motion*.

How to calculate a new value is detailed in *Mounting angles and values on page 62*.

Continues on next page

The system parameters are described in *Technical reference manual - System parameters*.

The system parameters are configured in RobotStudio or on the FlexPendant.

2.3.4 Manually releasing the brakes

General

The section below describes how to release the holding brakes of each axis' motor.

This can be done in one of three ways:

- using the push-button when the robot is connected to the controller.
- using the push-button on the robot with an external power supply.
- using an external voltage supply directly on the respective brake.

DANGER

When releasing the holding brakes with push-buttons, the robot must be properly attached!

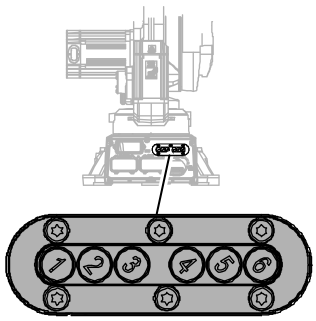
DANGER

When releasing the holding brakes, the robot axes may move very quickly and sometimes in unexpected ways!

Make sure no personnel is near or beneath the robot arm!

Using the push-button when the robot is connected to the controller

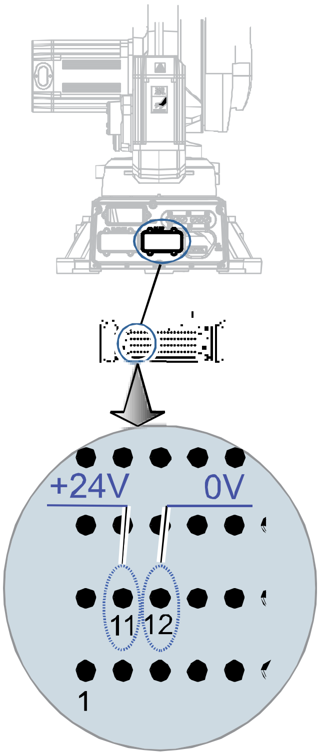
This procedure details how to release the holding brakes with push-buttons, when the robot is connected to the controller.

	Action	Note
1	The internal brake release unit is located at the base of the robot.	 xx0800000272
2	The brake release unit is equipped with six buttons for controlling the axes brakes. The buttons are numbered according to the numbers of the axes.	
3	Release the holding brake on a particular axis by pressing the corresponding button on the push-button unit and keeping it depressed.	
4	The brake will function again as soon as the button is released.	

Continues on next page

Using the push-button on the robot with an external power supply

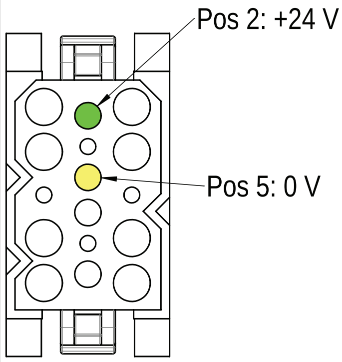
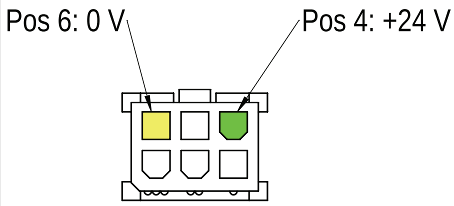
This procedure details how to release the holding brakes with the push-buttons, when the robot is **not** connected to the controller.

	Action	Note
1	Connect an external 24VDC power supply to the connector R1.MP on the robot base. **Note** Be careful not to interchange the 24V and 0V pins! If they are mixed up, damage can be caused to the brake release unit and the system board! **WARNING** **Incorrect connections can cause all brakes to be released simultaneously!**	 xx0800000269 Connect to connector R1.MP: • 0V to pin 12 • +24V to pin 11
2	Release the holding brake on a particular axis by pressing the corresponding button on the push-button unit and keeping it depressed.	The brake release unit is equipped with six buttons for controlling the axes brakes. The buttons are numbered according to the numbers of the axes. See the previous figure.
3	The brake will function again as soon as the button is released.	

Continues on next page

Using an external voltage supply directly on the respective brake

This procedure details how to release the holding brake of a specific axis by supplying external voltage directly on the brake.

	Action	Note
1	Every axis has a holding brake built into the axis motor. This holding brake may be released by connecting 24VDC power supply directly to one of the connectors in the motor. **DANGER** When power is connected directly to the brake cable, the brake will be released immediately when the power is switched on. This may cause some unexpected robot movements!	Make the connection to the current motor according to the Circuit Diagram. See chapter *Circuit diagram on page 463*.
2	Connect an external 24 VDC power supply to the motor, according to the figures. **Note** Be careful not to interchange the 24V and 0V pins! If they are mixed up, damage can be caused to the intergrated quenching circuits. **WARNING** **Incorrect connections can cause all brakes to be released simultaneously!**	**Axes 1, 2 and 3:**  xx1400001984
		Axes 4, 5 and 6:  xx1400001985

2.3.5 Orienting and securing the robot

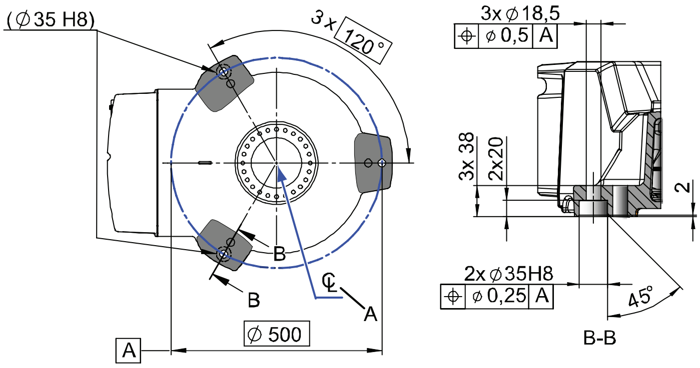
Introduction

This section describes how to orient and secure the robot to the steel structure foundation or base plate in order to run the robot safely. The requirements made on the foundation are shown in sections *Loads on foundation, robot on page 46* and *Requirements, foundation on page 47*.

Hole configuration, base

The illustration shows the hole configuration used when securing the robot.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



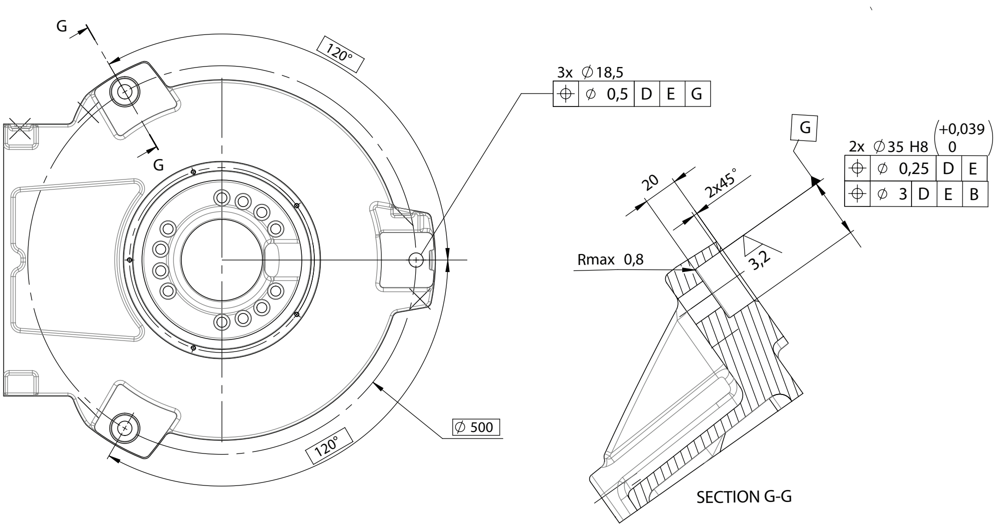
xx0900000193

A	Center axis 1

Note

Only the three outer holes are used to secure the robot!

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



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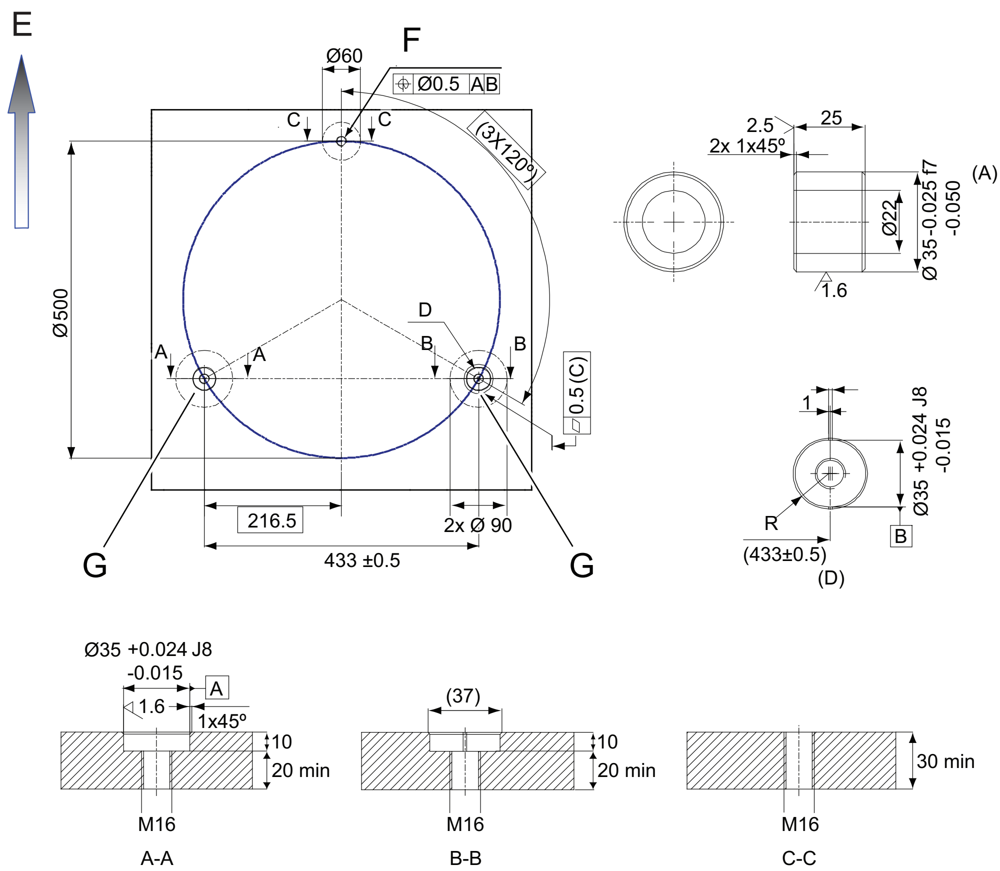
Dimension, mounting surface and guide bushing

The figure shows the dimension of the mounting surface and guide bushings.



xx1700001492

(C)	3x common zone
E	Position of the front of the robot
F	M16 (3 pcs)
G	Guide bushings (2 pcs)

Specification, attachment screws

The table specifies the type of securing screws and washers to be used to secure the robot to the steel structure foundation or base plate.

Securing parts/Facts	Dimension	Note
Securing screws, oiled	M16 x 60 Quality 8.8	3 pcs 200 Nm
Washers	17 x 30 x 3	3 pcs

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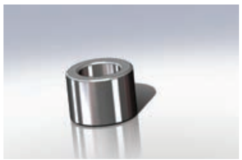
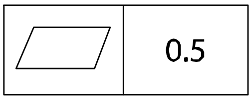
Securing parts/Facts	Dimension	Note
Guide bushings		Article number: 21510024-169. Added to the rear bolt holes, to allow the same robot to be re-mounted without program adjustments.  xx1200000885
Level surface requirements	 xx0300000251	

Orienting and securing the robot

Use this procedure to orient and secure the robot.

	Action	Note
1	Make sure the installation site for the robot conforms to the specifications in section *Pre-installation procedure on page 44*.	
2	Prepare the installation site with attachment holes.	Hole configuration of the base is shown in the figure in: • *Hole configuration, base on page 68*
3	**CAUTION** The IRB 2600/IRB 2600 ID robot weighs 280 kg. All lifting accessories used must be sized accordingly!	
4	**CAUTION** When the robot is put down after being lifted or transported, there is a risk of it tipping, if not properly secured.	
5	Lift the robot to its installation site.	How to lift the robot is described in section: • *Lifting robot with roundslings on page 57*
6	Fit two *guide bushings* to the *rear bolts* in the base.	
7	Guide the robot gently, using the attachment screws while lowering it into its mounting position.	Make sure the robot base is correctly fitted onto the guide sleeves.

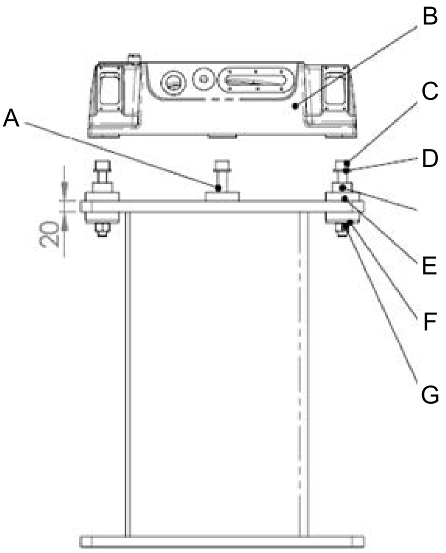
Continues on next page

	Action	Note
8	Fit the *securing screws* and *washers* in the attachment holes of the base.	
9	Tighten the bolts in a criss-cross pattern to ensure that the base is not distorted.	

Isolating AW manipulator

CAUTION

If the manipulator is used for arc welding and is mounted on a pedestal, make sure that the manipulator is isolated from the pedestal with isolators.



xx1400000831

A	Attachment point, front (no guide sleeve)
B	Manipulator base
C	Screw M16x120
D	Plain washer
E	Guide sleeve
F	Isolator
G	Nut M16

Securing robot on a mounting plate

When bolting a mounting plate or frame to a concrete floor, follow the general instructions for expansion-shell bolts.

Screw joints must be able to withstand the stress loads defined in section *Loads on foundation, robot on page 46*.

2.3.6 Fitting equipment on robot

Introduction

The robot features mounting holes for additional equipment.

Access to any of the following mounting holes may be obstructed by any additional cabling, equipment, etc., fitted by the robot user. Make sure the required mounting holes are accessible when planning the robot cell.

Note

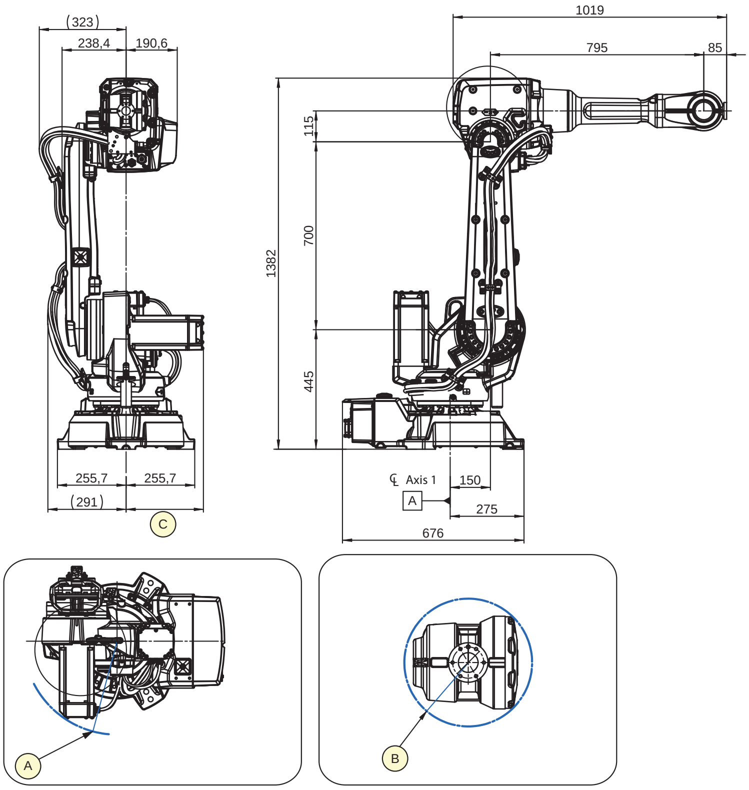
All equipment and cables used on the robot, must be designed and fitted not to damage the robot and/or its parts.

Note

Never drill a hole in the robot without first consulting ABB!

Robot dimensions

Dimensions IRB 2600-20(12)/1.65, IRB 2600 Type C-20(12)/1.65



xx0900000481

Pos	Description
A	R 337 Minimum turning radius of axis 1
B	R 98 Minimum turning radius of axis 4

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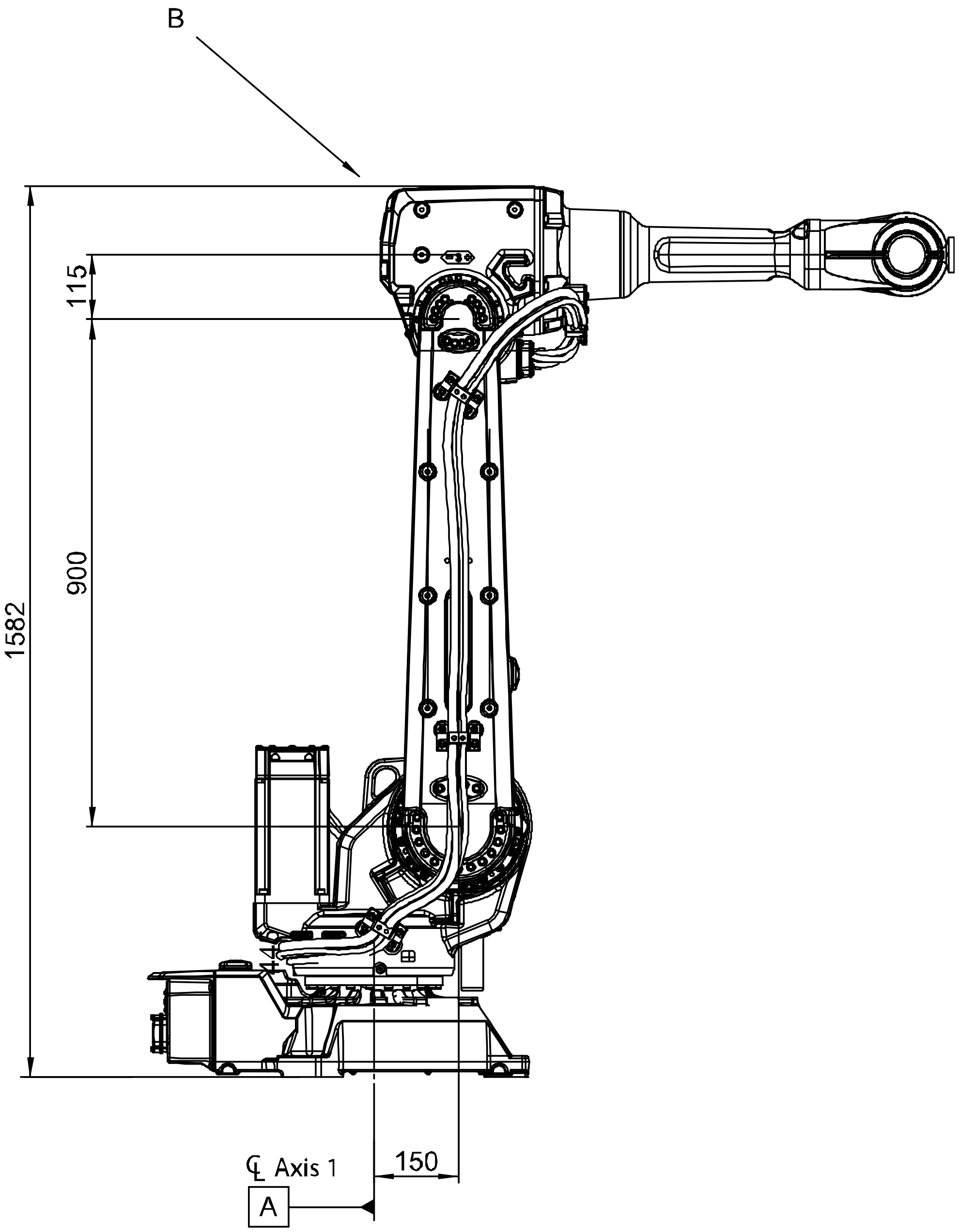
Pos	Description
C	IRB 2600ID = 281 mm Other types than Type A (IRB 2600ID) = 276 mm

Dimensions IRB 2600-12/1.85



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Pos	Description
B	For all other dimensions see IRB 2600-20(12)/1.65

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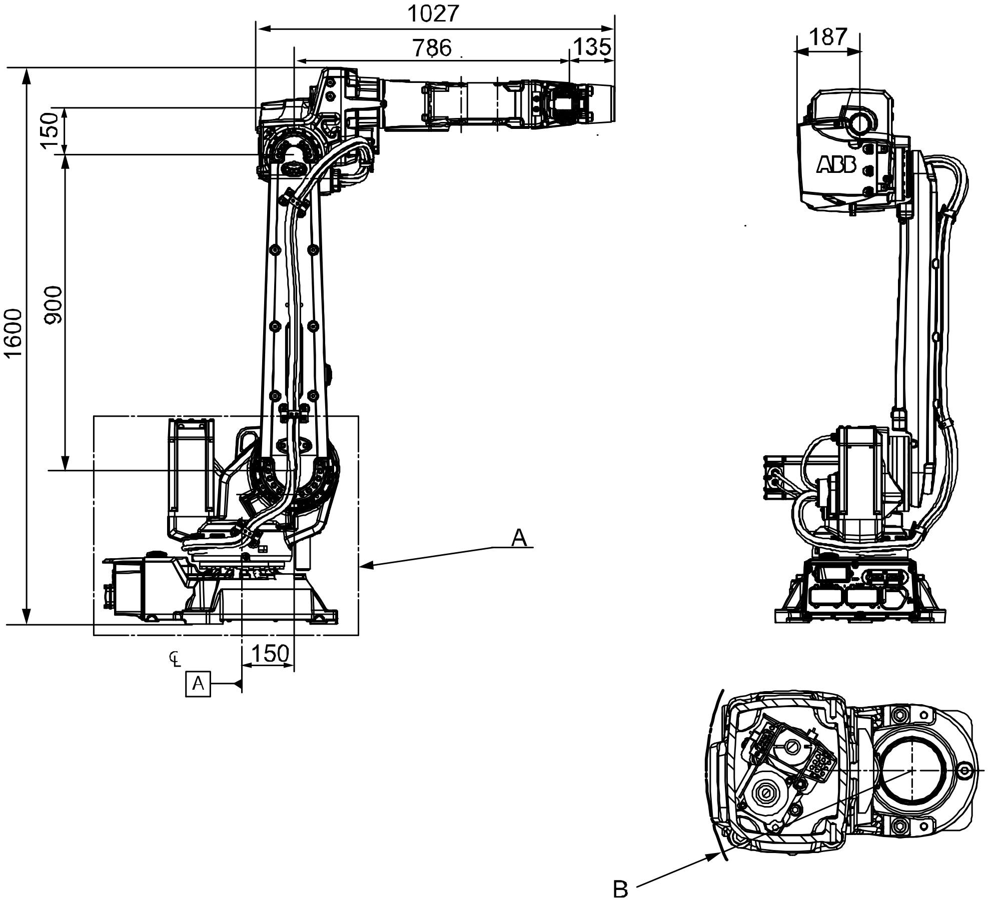
Dimensions IRB 2600ID-15/1.85



xx1000000962

Pos	Description
A	For dimensions, see IRB 2600-X/1.85
B	R 172 Minimum turning radius for axis 4

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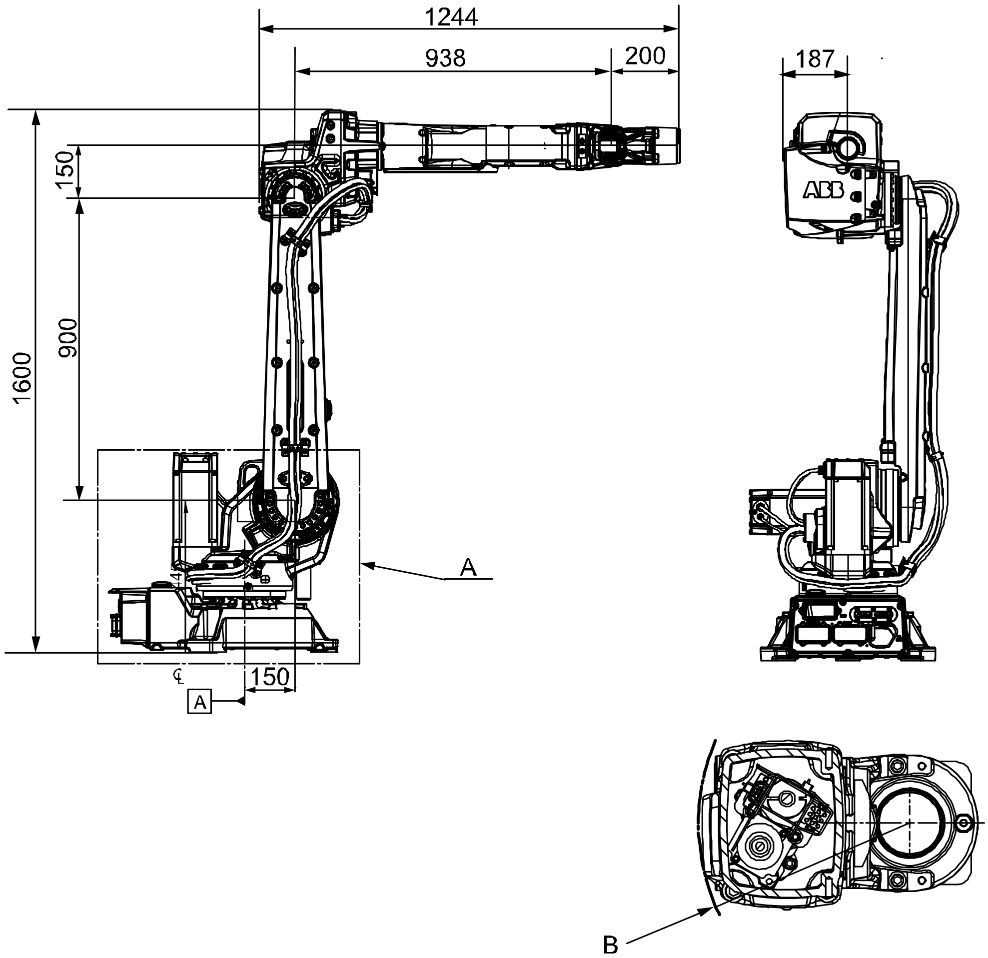
Dimensions IRB 2600ID-8/2.00



xx1000000963

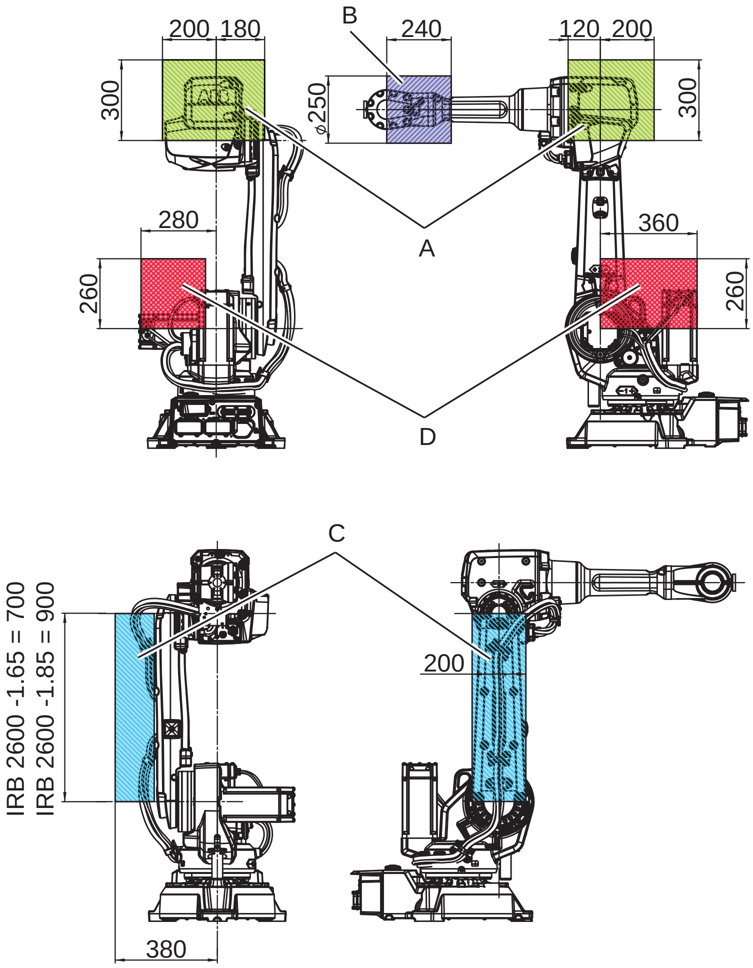
Pos	Description
A	For dimensions, see IRB 2600-X/1.85
B	R 172 Minimum turning radius for axis 4

Fitting equipment on robot - Load areas

The shaded area indicates the permitted positions (center of gravity) for any extra equipment fitted in the holes intended for this purpose.

Continues on next page

IRB 2600 standard

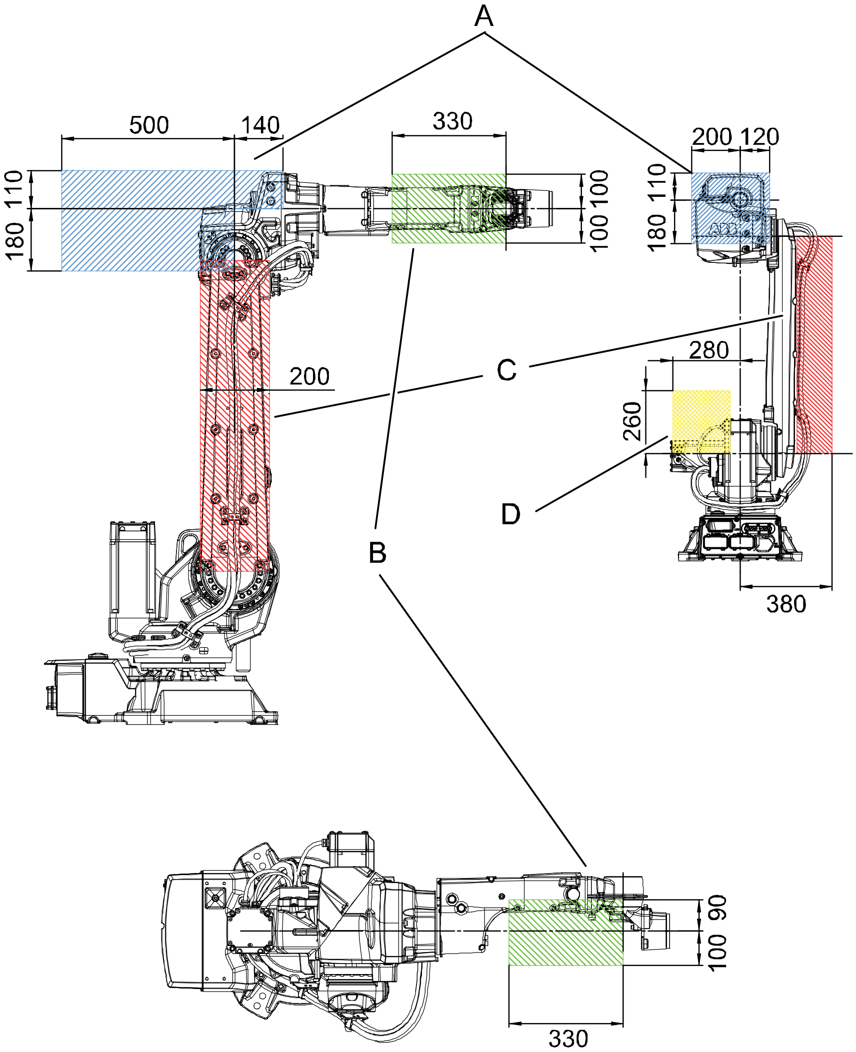


xx0900000189

Variant	Max load A	Max load B	Max load C	Max load A+C	Max load D
IRB 2600-20/1.65 IRB 2600 Type C-20/1.65 IRB 2600-12/1.85	10 kg	1 kg	10 kg	10 kg	35 kg
IRB 2600-12/1.65 IRB 2600 Type C-12/1.65	15 kg	1 kg	15 kg	15 kg	35 kg

Continues on next page

IRB 2600ID



xx1000000319

Variant	Max load A	Max load B	Max load C	Max load A+C	Max load D
IRB 2600ID-15/1.85	10 kg	1 kg	10 kg	10 kg	35 kg
IRB 2600ID-8/2.00	15 kg	1 kg	15 kg	15 kg	35 kg

Note

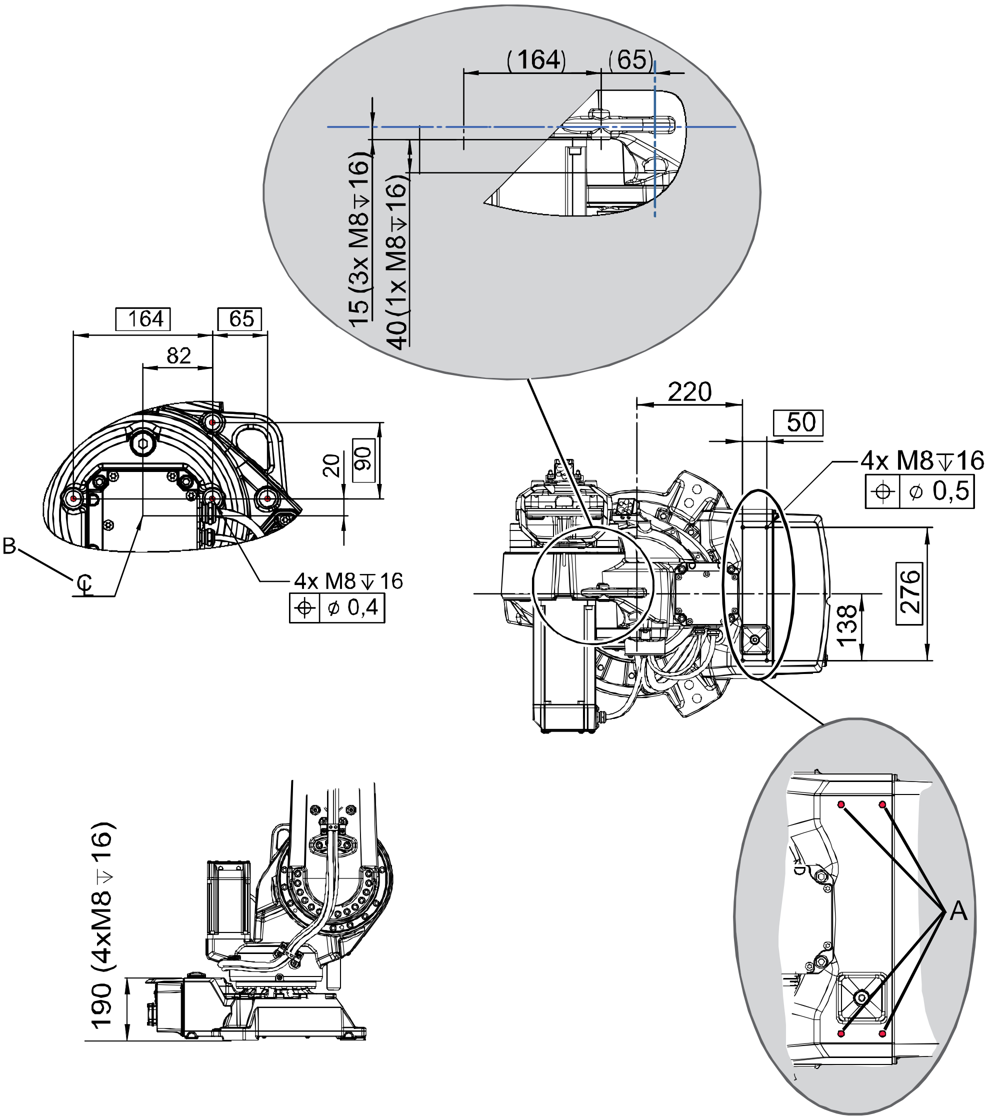
Maximum loads must never be exceeded!

Fitting equipment on base and frame

The illustrations show the fitting holes available for fitting extra equipment on the base and frame of the robot.

Continues on next page

IRB 2600 Standard & ID.



xx0900000227

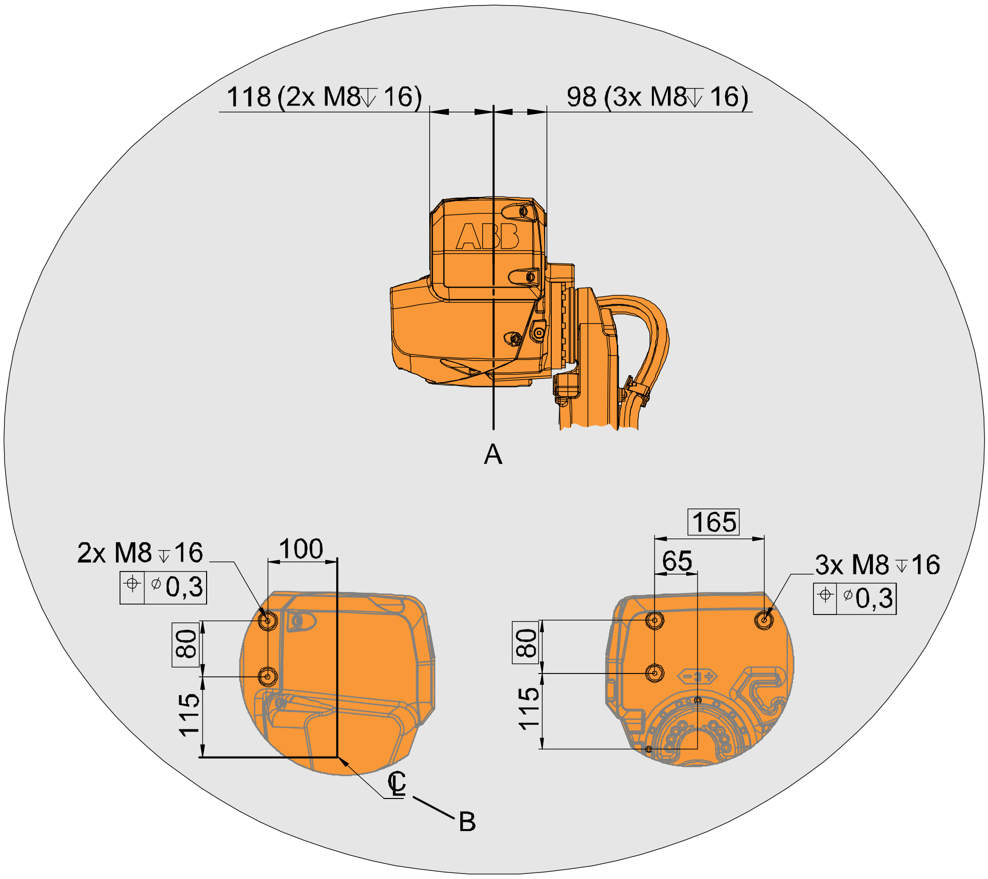
A	Attachment holes on base
B	Center axis 2

Fitting equipment on lower and upper arm

The illustrations show the fitting holes available for fitting extra equipment on the lower and upper arms of the robot.

Continues on next page

IRB 2600 standard



xx0900000234

A	Center axis 4
B	Center axis 3

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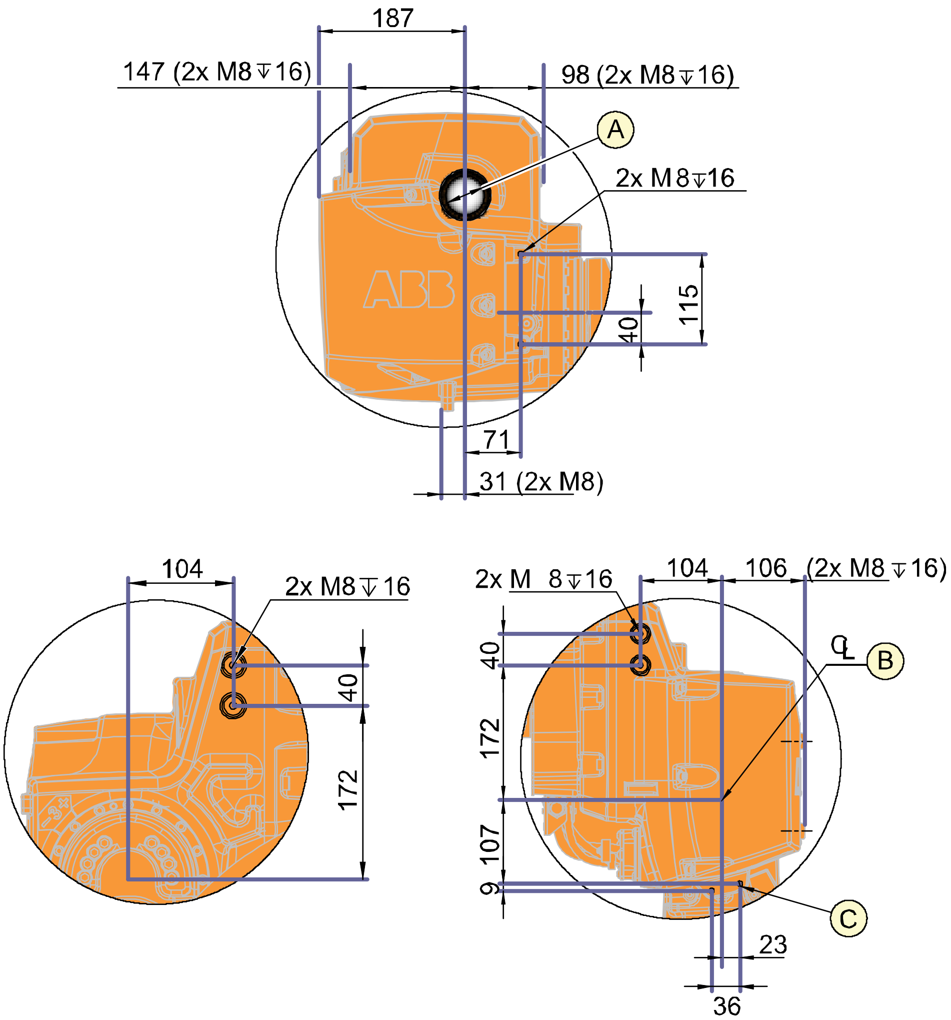
IRB 2600ID



xx1000000707

A	Hole through axis 4, diameter 50
B	Center axis 3
C	2x M8 through

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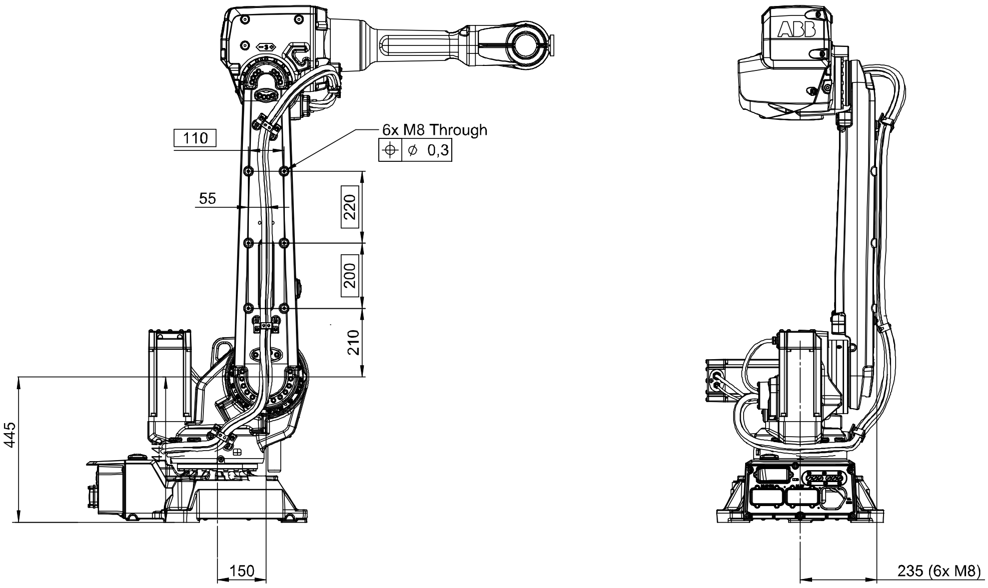
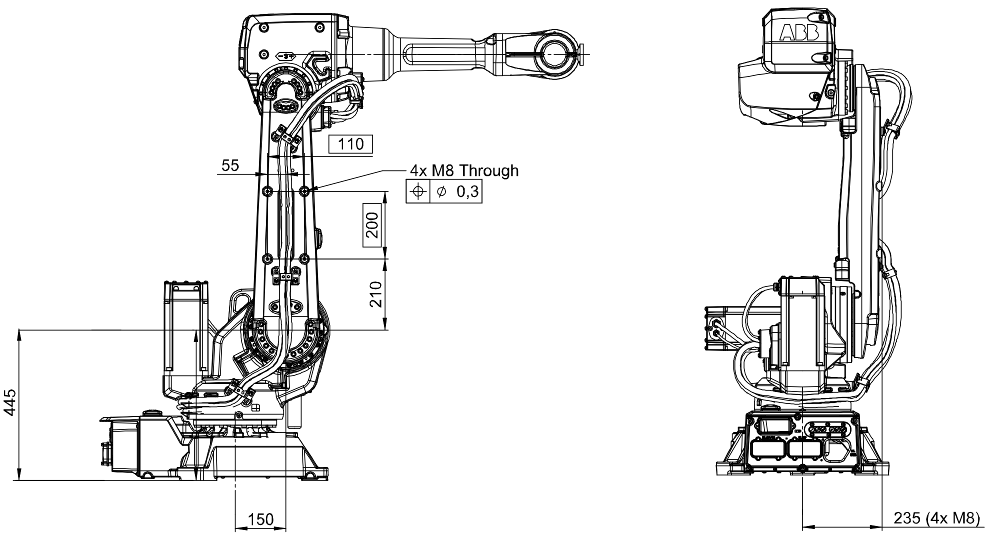
Lower arm of IRB 2600 -12/1.85, IRB 2600ID -15/1.85 and -8/2.00



xx0900000492

-	The uppermost holes for fitting equipment on the lower arm are only applicable to variant IRB 2600 -12/1.85.

Lower arm of IRB 2600 -20/1.65 and -12/1.65, IRB 2600 Type C-20(12)/1.65



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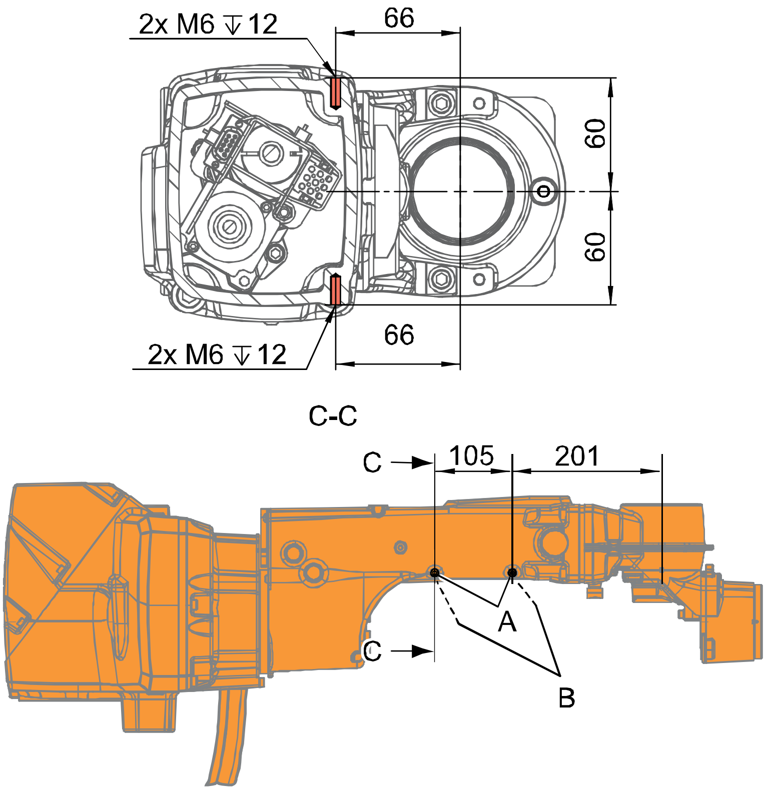
Upper arm



xx1000000823

A	Holes on top of upper arm, 2 pcs
B	Holes on other side (symmetrical to A), 2 pcs

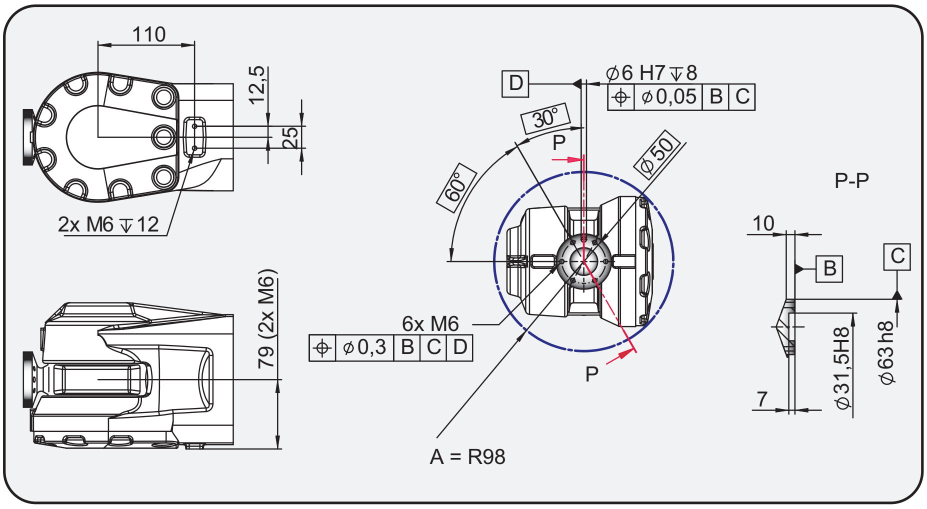
Fitting equipment on wrist and mounting flange IRB 2600/IRB 2600 ID.

The illustration shows the fitting holes available for fitting extra equipment on the wrist of the robot.

The illustration also shows the mechanical interface for the mounting flange.

Continues on next page

IRB 2600 standard



xx0800000278

A	Smallest circumscribed radius axis 4

Note

Use attachment screws M6, quality 12.9 and 10 mm *used* thread length.

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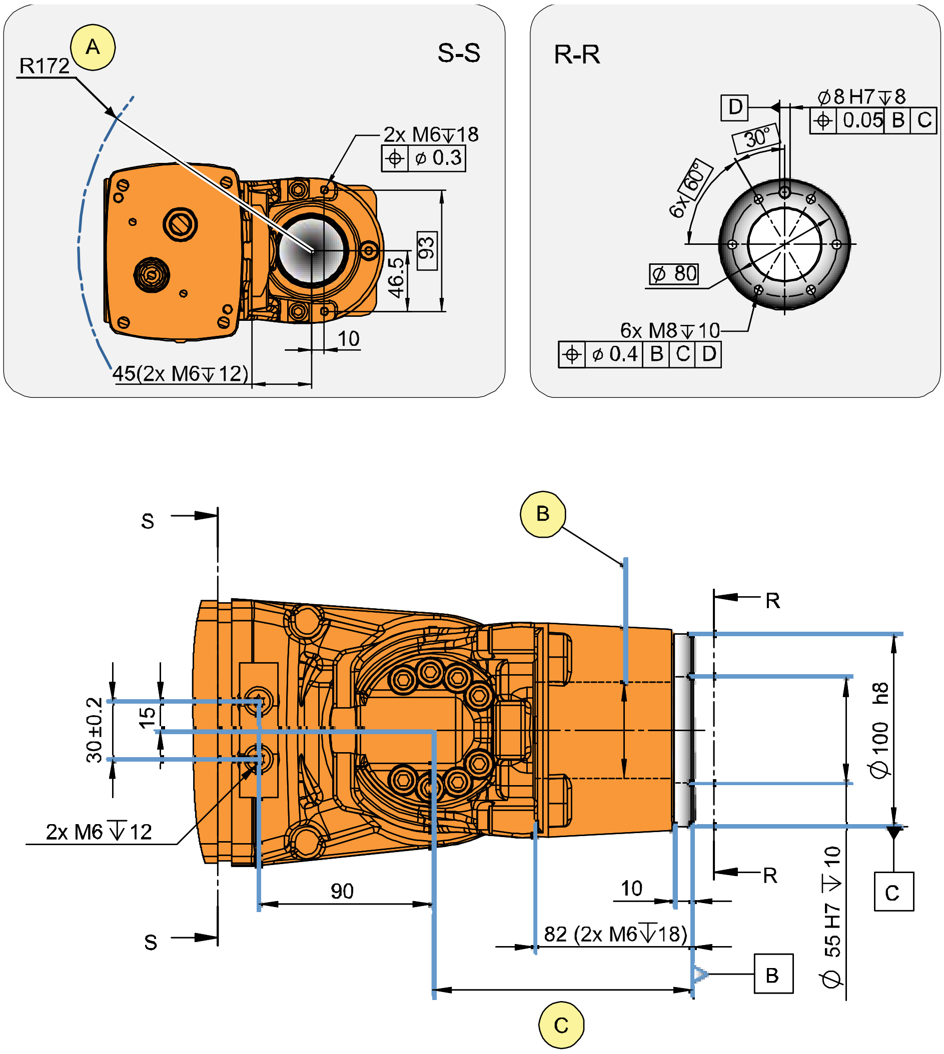
IRB 2600ID



xx1000000822

A	Smallest circumscribed radius axis 5
B	Hole through axis 6, diameter 50 mm
C	See table below!

Variant	C mm
IRB 2600ID-15/1.85	135
IRB 2600ID-8/2.00	200

Fastener quality

When fitting tools on the tool flange, only use screws with quality 12.9. For other equipment use suitable screws and tightening torque for your application.

2.3.7 Loads fitted to the robot, stopping time and braking distances

General

Any loads mounted on the robot must be defined correctly and carefully (with regard to the position of center of gravity and mass moments of inertia) in order to avoid jolting movements and overloading motors, gears and structure.

CAUTION

Incorrectly defined loads may result in operational stops or major damage to the robot.

References

Load diagrams, permitted extra loads (equipment) and their positions are specified in the product specification. The loads must be defined in the software.

- *Operating manual - IRC5 with FlexPendant*
- *Operating manual - OmniCore*

Stopping time and braking distances

The performance of the motor brake depends on if there are any loads attached to the robot. For more information, see product specification listed in *References on page 10*.

2.4 Restricting the working range

2.4.1 Axes with restricted working range

General

When installing the robot, make sure that it can move freely within its entire working space. If there is a risk that it may collide with other objects, its working space should be limited.

The working range of the following axes may be restricted:

- Axis 1, hardware (mechanical stop) and software
- Axis 2, software
- Axis 3, software.

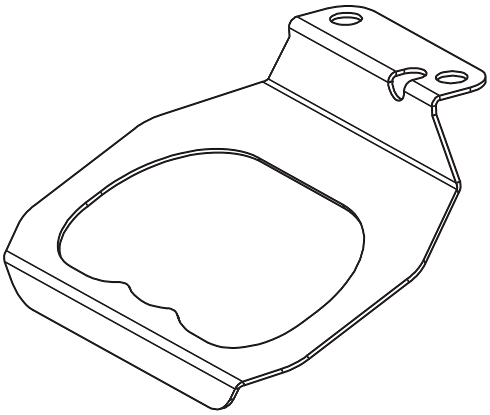
This section describes how to install hardware that restricts the working range.

Note

Adjustments must also be made in the robot configuration software (system parameters). References to relevant manuals are included in the installation procedures.

WARNING

Remove the mechanical stop bracket if the robots full working range is from one mechanical stop to another mechanical stop. Otherwise the mechanical stop pin will be worn out.



xx1500000253

2.4.2 Mechanically restricting the working range of axis 1

Mechanically restricting the working range

The information in this section is valid both for the floor and the suspended mounted robot.

The working range of axis 1 is limited by fixed mechanical stops. The working range can be reduced further by adding movable mechanical stops.

The mechanical turning range can be limited in steps of 22.5° from the synchronization position, between values defined in the table. The values differ depending on which design of the gearbox (and base) the robot is equipped with.

Robot variant	Limitation in mechanical turning range, calculated from synchronization position
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C	±126° to ±13.5° in steps of 22.5°
IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0	±129° to ±16.5° in steps of 22.5°

Note

The software working range limitations must be adjusted to correspond to the changes in the mechanical limitations of the working range. The system parameters that must be changed (*Upper joint bound* and *Lower joint bound*) are described in *Technical reference manual - System parameters*.

Required equipment

Equipment, etc.	Art. no.	Note
Mechanical stop, axis 1	See *Spare part lists on page 461*.	Includes two additional stop lugs, attachment screws, washers and instruction
Attachment screw	See *Spare part lists on page 461*.	2 pcs/stop lug Hex socket head cap screw M12x40, quality 8.8-A3F
Washer	See *Spare part lists on page 461*.	2 pcs/lug 13x24x2.5
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Additional stops

The additional stops are fitted as shown in the figure.

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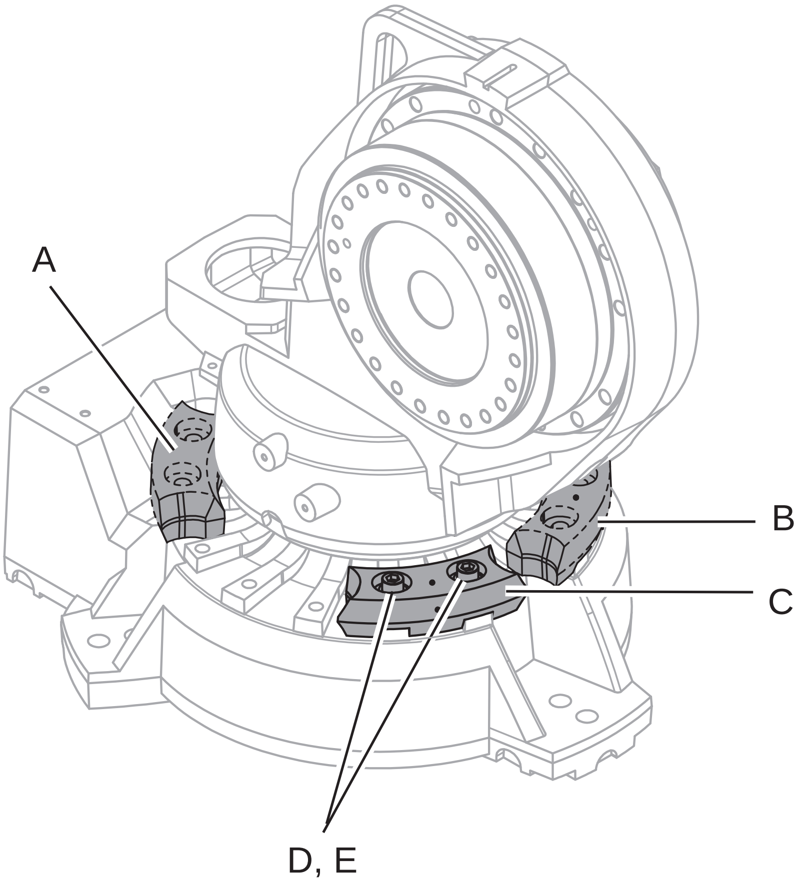


xx0800000273

A	Movable mechanical stop. Limited to: • -126° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • -129° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
B	Movable mechanical stop. Limited to: • +13.5° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • +16.5° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
C	Movable mechanical stop. Limited to: • -13.5° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • -16.5° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
D	Attachment screws
E	Washers

Fitting, mechanical stop axis 1

How to fit the additional mechanical stop to the base is described in the procedure.

Mounting instructions are also supplied with the kit.

	Action	Note
1	Determine the position of the stop lugs.	See the figure *Additional stops on page 87* for guidance.

Continues on next page

	Action	Note
2	Fit the stop lugs firmly with *attachment screws and washers* according to the figure *Additional stops on page 87*.	Specified in *Required equipment on page 87*. Tightening torque: 82 Nm

2.5 Installing options

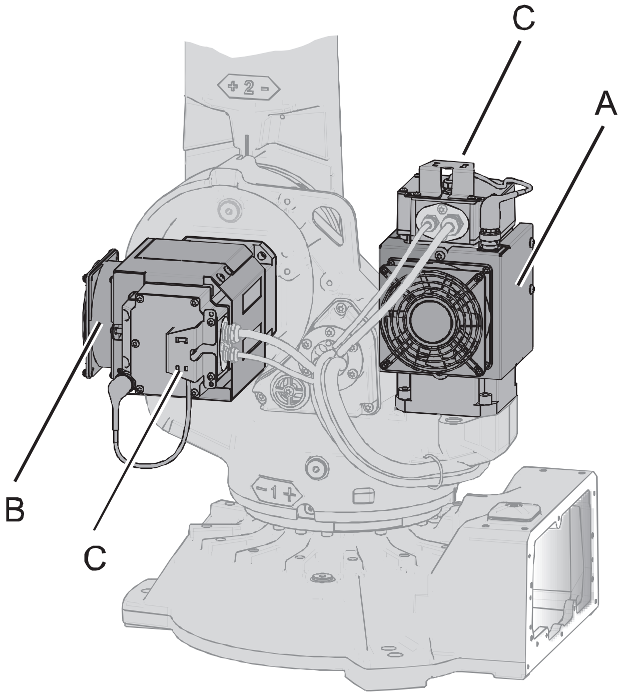
2.5.1 Installation of cooling fan for motors (option)

General

A cooling fan can be installed on motor axis 1 and/or axis 2.

Location of cooling fans

The fans are installed on the motors, axes 1 or 2, as shown in the figure below.



xx0900000232

A	Fan, motor axis 1
B	Fan, motor axis 2
C	Protection cover

Cooling fan

The details of the cooling fan are shown in the figure below.

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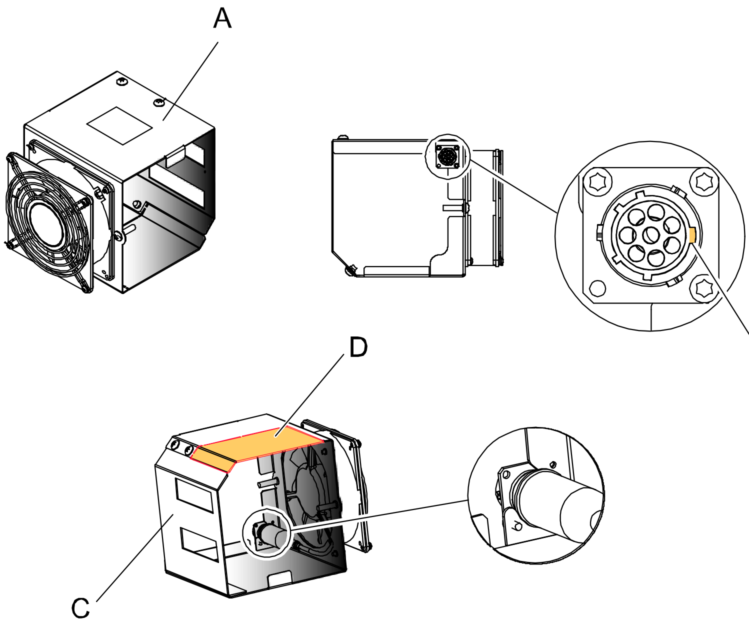

xx0900000137

A	Fanbox
B	Groove in the connector
C	Back plate
D	Part of the fanbox that can be removed, if needed. **NOTE! Only valid on motor axis 1!**

Required equipment

Equipment	Article number	Note
Cooling fans axes 1 and 2	-	For Spare part no. see chapter *Spare parts*: • *Spare part lists on page 461*
Additional cabling to the controller	-	Specified in section *Fan cables (option) on page 104*.
Locking liquid	-	Loctite 2400 (or equivalent Loctite 243) Used for the three tightening screws.
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Circuit diagram	-	See chapter *Circuit diagram on page 463*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

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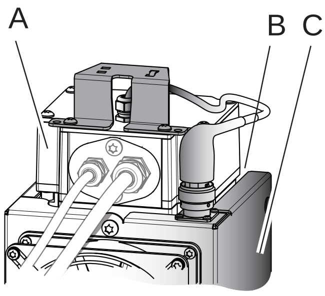
Installation, fan on motor axis 1 and 2

Use this procedure to install the cooling fan on motor axis 1 and 2.

	Action	Note
1	**DANGER** Turn off all: • electric power supply to the robot • hydraulic pressure supply to the robot • air pressure supply to the robot Before entering the robot working area.	
2	Remove the back plate of the fanbox.	See the figure in: • *Cooling fan on page 90*
3	Place the fanbox around motor axis 1 and 2.	See the figure in: • *Cooling fan on page 90*
4	Refit the back plate of the fanbox.	
5	**Tip** **Only applicable to fan fitted on axis 1!** If there is a lack of space between motor and robot, it is possible to remove part of the fanbox.	See the figure in: • *Cooling fan on page 90*
6	Push the fanbox in line with the connection box.	Align the upper part of the fan with the lower part of the connection box.  xx1000000124 Parts: • A: Connection box • B: Position where the fan shall be aligned with connection box • C: Fan
7	Fit the fanbox with two attachment screws M6x25.	

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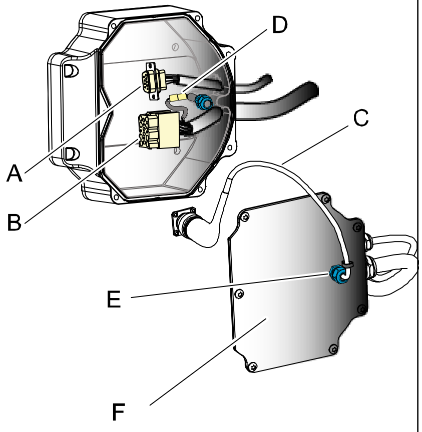
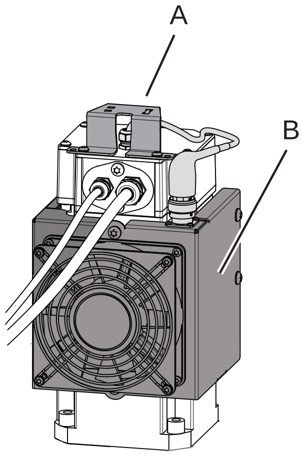
	Action	Note
8	Connect the fan connector to motor and fan.	 xx0900000405 Parts: • A: Connector, signal • B: Connector, power • C: Fan cable • D: Connector, fan • E: Cable gland • F: Motor cover, with fan cable
9	After fitting the motor cover, fit the **protection cover** using two attachment screws for the motor cover.	 xx0900000406 Parts: • A: Protection cover • B: Fan
10	Secure the fan cable to the protection cover with a cable strap.	

2.5.2 Installing an expansion container

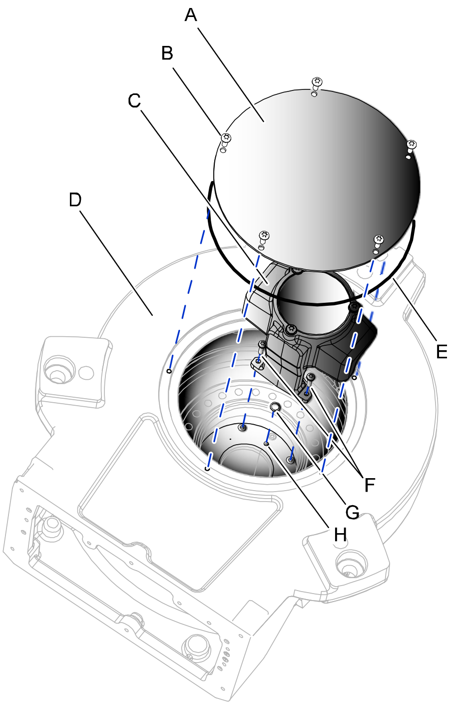
Validity of this section

This section is only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.

Introduction to the expansion container

The expansion container is needed on suspended robots (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) to make sure that the amount of oil in gearbox axis 1 covers all important parts. Robots ordered as suspended robots have the expansion container installed on delivery. If a manipulator delivered for floor mounting is planned to be mounted in suspended position, an expansion container must be installed.

Expansion container



xx1000000318

A	Cover
B	Attachment screw M6x16, quality 8.8-A2F (5 pcs)
C	Oil expansion container with cover
D	Base
E	O-ring D220x5
F	Attachment screw M5x20, quality 8.8-A2F and washer (2+2 pcs)
G	O-ring D1=9.5 D2=1.6
H	Oil plug (to be removed)

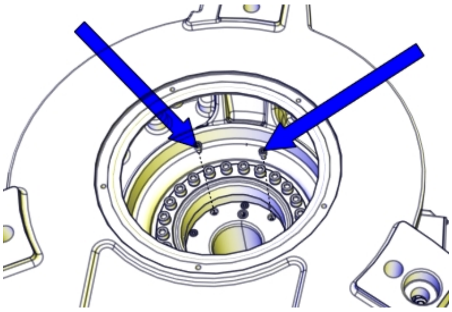
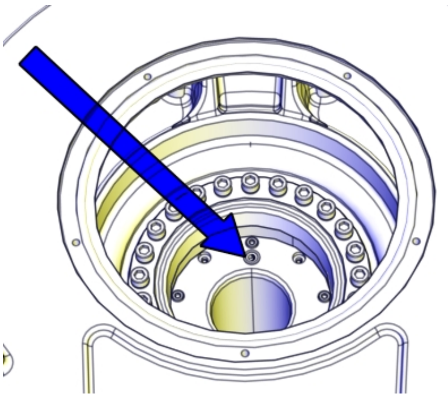
Continues on next page

Required equipment

Equipment	Note
Expansion container	Kit including oil.
Lifting accessory	3HAC034766-001
Lifting instruction	Included with the lifting accessory.
Grease	-
Locking liquid	- Loctite 2400 (or equivalent Loctite 243)
O-ring for base cover	Replace if damaged.

Installing an expansion container

Use this procedure to install the expansion container.

	Action	Information
1	Lift the robot using the lifting accessory and place it in suspended position with the base free for installation work.	See *Lifting and turning a suspended mounted robot on page 60*.
2	Remove the *cover* and the *o-ring* from the *base*.	
3	Remove two existing *attachment screws* as shown in the figure.	 xx1500001958 The screws must be replaced with longer screws.
4	Remove the *oil plug* from the base.	 xx1900001818

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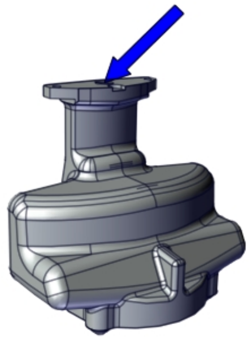
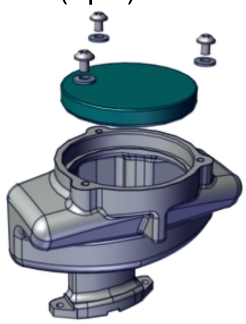
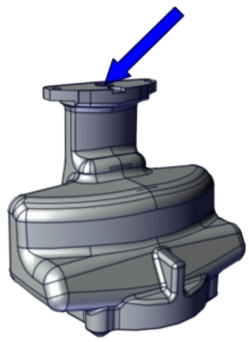
	Action	Information
5	Fit a *plastic plug* in the expansion container drain hole.	 xx1500001956
6	Fill the expansion container with oil.	Oil volume: 0.4 l
7	Apply locking liquid to the three screw holes in the expansion container. Knock in the *VK-cover* with a rubber mallet. Secure with three screws and washers.	Locking liquid: Loctite 2400 (or equivalent Loctite 243) Screws: M6x8 (3 pcs).  xx1500001957
8	Remove the *plastic plug*.	 xx1500001956
9	Apply some grease on the small *o-ring* and place it in the recess on the expansion container.	

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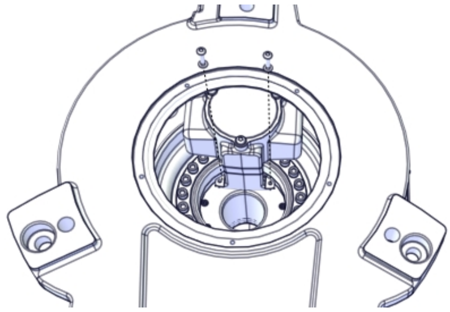
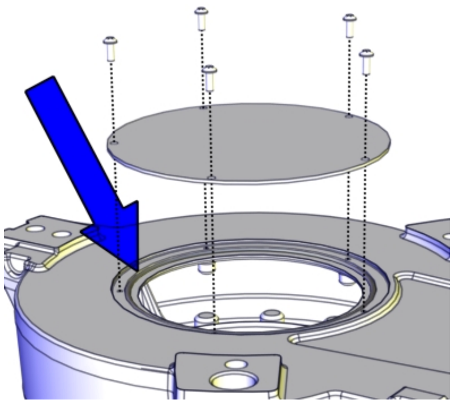
	Action	Information
10	Place the *expansion container* in the base and place it so the drain holes match. **Tip** Turn and install the container quickly to avoid oil spill.	
11	Secure the expansion container with the *attachment screws* and *washers*. Wipe off any oil residuals before continuing.	xx1500001959 Tightening torque 6 Nm.
12	Check the *o-ring* used on the cover. Replace it if damaged.	 xx1900001819
13	Refit the *cover* on the base with its *attachment screws*.	
14	Turn the robot so it is not suspended.	
15	Turn the robot to suspended position.	
16	Inspect the oil level.	See procedure for suspended robot, *Inspecting oil level, axis-1 gearbox on page 119*.

2.5.3 Installation of Foundry Plus Cable guard (option)

Introduction

Separate instructions for IRB 2600, 4600, 6620, 6640, 6650S, 6660 and 7600 are available in English, German, French, Spanish, and Italian and can be found for registered users on myABB Business Portal (*www.abb.com/myabb*) and delivered with the Cable guard, article number 3HAC035933-001.

2.5.4 Safety lamp (option for IRC5)

Description

A signal lamp with a yellow fixed light can be mounted on the robot, as a safety device.

Installation

See the assembly instruction delivered with the signal lamp.

Function

The lamp is active in MOTORS ON mode.

Further information

Further information about the MOTORS ON/MOTORS OFF mode may be found in the product manual for the controller.

2.6 Robot in hot environments

2.6.1 Start of robot in hot environments

Introduction

This procedure describes how to start the robot in a hot environment. This procedure must be performed the first time the robot is started in a hot environment or if it has not been used for some time in a hot environment.

There is a possibility that some overpressure has been built up in the system. This overpressure must be released before starting up the robot.

Releasing overpressure in gearboxes

Use this procedure before the start of the robot in a hot environment to release potential overpressure being built up in gearboxes.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**CAUTION** Components may be hot.	
3	**Note** Before opening the oil plug, make certain that the oil plug is above the oil level. Place the robot accordingly.	
4	Open oil plug filling *very carefully*! **Note** Open the oil plug just enough for the overpressure to be released.	**Tip** Hold a cloth or some paper over the oil plug while opening it to prevent surplus oil causing burns or other injuries.
5	Let the overpressure leave the gearbox.	
6	Refit the oil plug.	
7	Continue releasing the overpressure on all gearboxes.	

2.7 Robot in cold environments

2.7.1 Start of robot in cold environments

Introduction

This section describes how to start the robot in a cold environment if it is not starting the normal way.

Problems with starting the robot

Event message from Motion Supervision

Use this procedure if an event message indicates a problem with Motion supervision at start-up. More information about Motion Supervision is found in *Technical reference manual - System parameters*.

	Action	Note
1	Turn off Motion Supervision.	
2	Start the robot.	
3	When the robot has reached normal working temperature, the Motion Supervision can be turned on again.	

Robot stopping with other event message

Use this procedure if the robot is not starting.

	Action	Note
1	Start the robot with its normal program but with reduced speed.	The speed can be regulated with the RAPID instruction `VelSet`.

Adjusting the speed and acceleration during warm-up

Depending on how cold the environment is and what program is being used, the speed might need to be ramped up until reached maximum. The table shows examples of how to adjust the speed:

Work cycles	`AccSet`	Speed/velocity
3 Work cycles	20, 20	v100 (100 mm/s)
5 Work cycles	40, 40	v400 (400 mm/s)
5 Work cycles	60, 60	v600 (600 mm/s)
5 Work cycles	100, 100	v1000 (1000 mm/s)
More than 5 Work cycles	100, 100	Max.

If the program consists of large wrist movements, it is possible that the reorientation velocity, which is always high in predefined velocities, needs to be included in the ramping up.

2.8 Electrical connections

2.8.1 Robot cabling and connection points

Introduction

Connect the robot and controller to each other after securing them to the foundation. The lists below specify which cables to use for each respective application.

CAUTION

Connect the male and female connectors perfectly aligned horizontally to avoid any kind of tilt or skew.

CAUTION

Verify that the serial number is according to the number(s) in the *Declaration of Incorporation* (DoI).

Main cable categories

All cables between the robot and controller are divided into the following categories:

Cable category	Description
Robot cables	Handles power supply to and control of the robot's motors as well as feedback from the serial measurement board. Specified in the table *Robot cables on page 102*.
Fan cables (option)	Handles supply to and feedback from any cooling fan on the robot. Specified in the table *Fan cables (option) on page 104*.
Customer cables (option)	Handles communication with equipment fitted on the robot by the customer, low voltage signals and high voltage power supply + protective ground. The customer cables also handle databus communication. See the product manual for the controller, see document number in *References on page 10*.
External axes cables (option)	Handles power supply to and control of the external axes' motors as well as feedback from the servo system. See *Application manual - Additional axes and standalone controller (IRC5) or Application manual - Additional axes (OmniCore)*, document number in *References on page 10*.

Robot cables

These cables are included in the standard delivery. They are completely pre-manufactured and ready to plug in.

Cable sub-category	Description	Connection point, cabinet	Connection point, robot
Robot cable, power	Transfers drive power from the drive units in the control cabinet to the robot motors.	XS1 (IRC5 controllers) X1 (OmniCore controllers)	R1.MP

Continues on next page

Cable sub-category	Description	Connection point, cabinet	Connection point, robot
Robot cable, signals	Transfers resolver data from and power supply to the serial measurement board.	XS2 (IRC5 controllers) X2 (OmniCore controllers)	R1.SMB

Robot cable, power

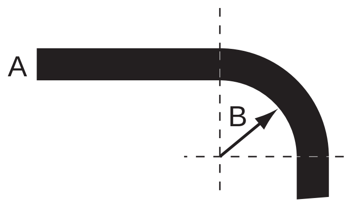
Cable	Art. no.
Robot cable, power: 7 m	3HAC026787-001
Robot cable, power: 15 m	3HAC026787-002
Robot cable, power: 22 m	3HAC026787-003
Robot cable, power: 30 m	3HAC026787-004

Robot cable, signals

Cable	Art. no.
Robot cable signal, shielded: 7 m	3HAC068917-001
Robot cable signal, shielded: 15 m	3HAC068918-001
Robot cable signal, shielded: 22 m	3HAC068919-001
Robot cable signal, shielded: 30 m	3HAC068920-001

Bending radius for static floor cables

The minimum bending radius is 10 times the cable diameter for static floor cables.



xx1600002016

A	Diameter
B	Diameter x10

Grounding and bonding point on manipulator

There is a grounding/bonding point on the manipulator base. The grounding/bonding point is used for potential equalizing between control cabinet, manipulator and any peripheral devices.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0

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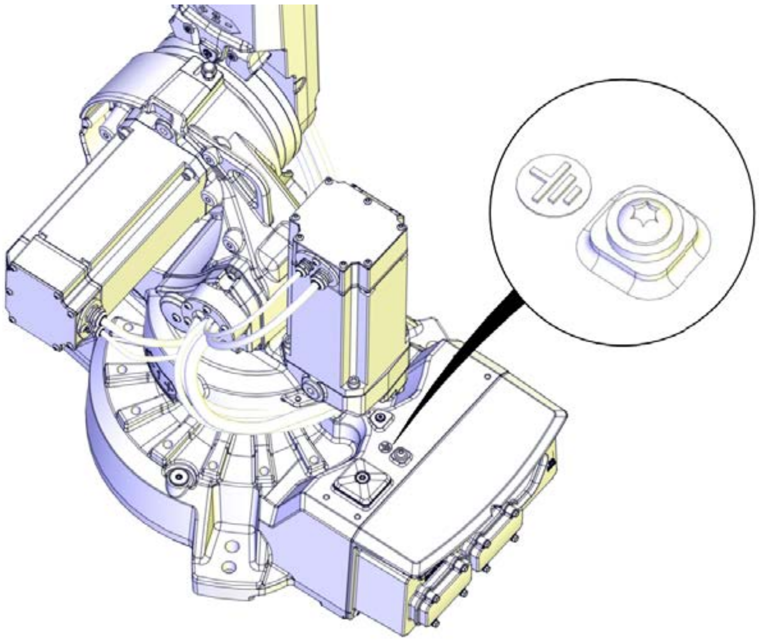

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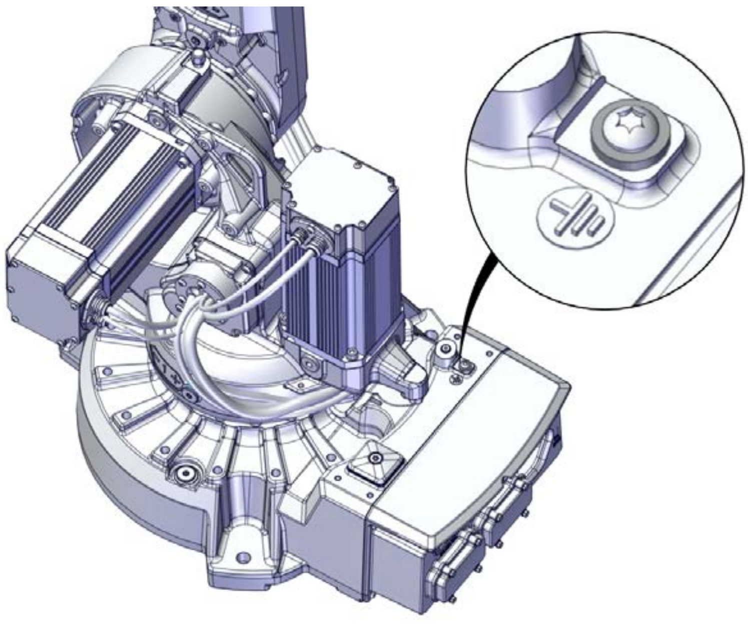
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



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Fan cables (option)

These cables are only included in the delivery if the fan option is ordered. The cables are completely pre-manufactured and ready to plug in.

Cabling to be installed on the robot is specified in section *Installation of cooling fan for motors (option) on page 90*.

Continues on next page

Cabling between robot base and control cabinet, cooling fans

The following cables are used when the robot is equipped with cooling fans. The cabling for the cooling fans run from the robot base to the controller cabinet, and connecting inside with a distribution cable. For instructions on how to connect the distribution cable inside the controller, see the product manual for the robot controller.

Fans can also be ordered without cables.

If cooling fans are added to an existing installation, use the cabling specified below.

Cable	Art. no.	Connection point
Harness - cooling, 7 m	3HAC022723-001	Distributing cable: R1.FAN.SW2/3 Inside cabinet: A43.X10 and A43.X11 (IRC5) Inside cabinet: A43.X10/A43.X11 - A2.X23 (OmniCore)
Harness - cooling, 15 m	3HAC022723-004	Distributing cable: R1.FAN.SW2/3 Inside cabinet: A43.X10 and A43.X11 (IRC5) Inside cabinet: A43.X10/A43.X11 - A2.X23 (OmniCore)
Harness - cooling, 22 m	3HAC022723-005	Distributing cable: R1.FAN.SW2/3 Inside cabinet: A43.X10 and A43.X11 (IRC5) Inside cabinet: A43.X10/A43.X11 - A2.X23 (OmniCore)
Harness - cooling, 30 m	3HAC022723-006	Distributing cable: R1.FAN.SW2/3 Inside cabinet: A43.X10 and A43.X11 (IRC5) Inside cabinet: A43.X10/A43.X11 - A2.X23 (OmniCore)

2.8.2 Customer connection on robot

Location of customer connection

For the connection of extra equipment to the robot, cables and air hose are integrated into the robot´s cabling, and there can be two UTOW71210SH06 and one UTOW71626SH06 connector on the front part of the upper arm.

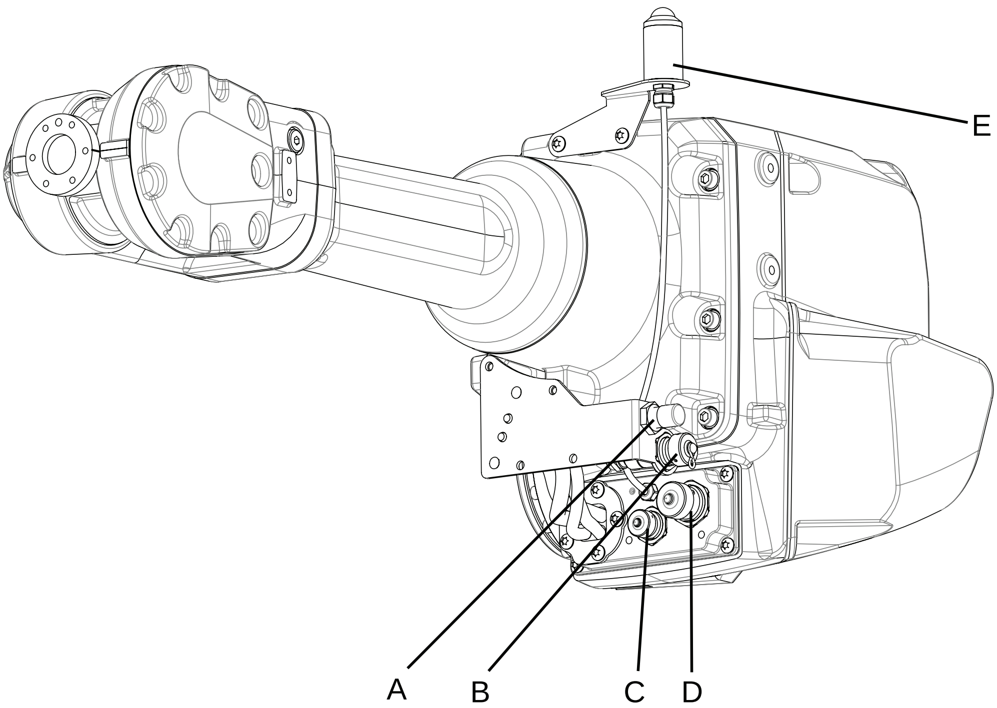
Note

The maximum leakage current for attached equipment must not exceed 10mA.

The customer connections are located on the robot as shown in the figure.

Customer connections on upper arm with signal lamp

The figure shows the customer connections on the upper arm, including the optional signal lamp that can be fitted to the arm house.



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A	R2.PROC1 Air M16x1.5 (24° cone sealing)
B	R2.ETHERNET
C	R2.CP or R2.CBUS
D	R2.CS or R2.CP/CS
E	Signal lamp
-	R3.H1 +, R3.H2 - (inside the arm house, not shown in figure)

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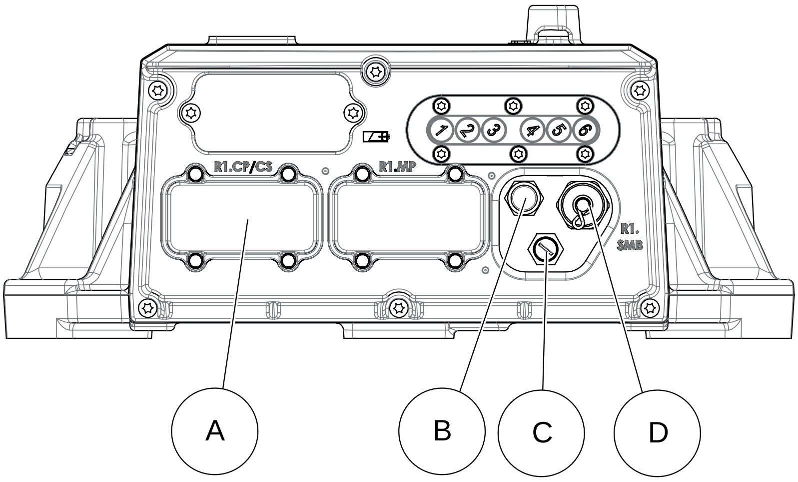
Customer connections base



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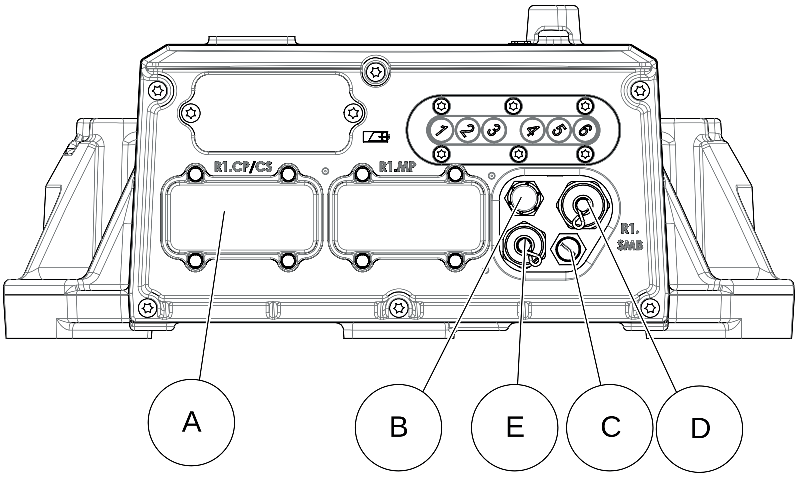
A	R1.CP/CS
B	R1.PROC1 (Air M16x1.5)
C	R1.ETHERNET
D	R1.SMB

Customer connections base with 7th axis



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A	R1.CP/CS
B	R1.PROC1 (Air M16x1.5)
C	R1.ETHERNET
D	R1.SMB
E	R2.FB7

Continues on next page

Extra equipment connections

Connections to the:

- air hose (3/8") is located on the front part of the upper arm and at the base. Max. 8 bar. Inner diameter of the air hose: 9.5 mm.

Number of signals, customer connections option Parallel&Air (803-1):

- 23 (50V, 0.5A)
- 9 (300V, 2A). 8 are double crimped in R1.CP/CS and 1 is only accessible in the robot base.
- 1 protective ground

Number of signals, customer connections option Ethernet, Parallel&Air (803-2) and DeviceNet, Parallel&Air (803-3):

- 8 (50V, 0.5A)
- 3 (300V, 2A)
- 2 DeviceNet
- 4 EtherNet
- 1 protective ground

Number of signals, customer connections option Profibus, Parallel&Air (803-4):

- 8 (50V, 0.5A)
- 2 (300V, 2A)
- 2 Profibus
- 1 protective ground

Connection sets

To connect power and signal conductors to the robot base/upper arm connectors, the following parts are recommended.

Connection set	Connector	Art. no.	Content
PROC1 on base	R1.CP/CS	3HAC16667-1	• Sockets for cable area of 0.14-2.5 mm^2 • Hood foundry • Hinged frame, hood • Multicontact-module, female
Connector set on base	R1.ETHER-NET	3HAC033181-001	• Hose coupling • M12 connector, male
R2.CP/R2.CS	R2.CP/R2.CS	3HAC025396-001	• Pins for cable area 0.21 - 0.93 mm^2 • Bottle shaped shrinking hose • Angle shaped shrinking hose • Hose coupling
Connector set upper arm	R2.ETHER-NET	3HAC070439-001	• Pins for cable area 0.21 - 0.93 mm^2 • Bottle shaped shrinking hose • Angle shaped shrinking hose

Continues on next page

Power supply connections on the robot

Signal name	Customer Terminal Controller	Customer Contact on Upper arm, R2	Customer Contact on robot base (cable between robot and controller not supplied)
CPA	XP6.1	R2.CP.A	R1.CP/CS.d1
CPB	XP6.2	R2.CP.B	R1.CP/CS.d6
CPC	XP6.3	R2.CP.C	R1.CP/CS.d3
CPD	XP6.4	R2.CP.D	R1.CP/CS.d4
CPE	XP6.1	R2.CP.E	R1.CP/CS.d1
CPF	XP6.2	R2.CP.F	R1.CP/CS.d6
CPG	-	R2.CP.G (Earth)	-
CPH	-	R2.CP.H	R1.CP/CS.d7
CPJ	XP6.3	R2.CP.J	R1.CP/CS.d3
CPK	XP6.4	R2.CP.K	R1.CP/CS.d4

Signal connection on the robot

Signal name	Customer Terminal Controller	Customer Contact on Upper arm, R2	Customer Contact on robot base (cable between robot and controller not supplied)
CSA	XP5.1.1	R2.CS.A	R1.CP/CS.b1
CSB	XP5.1.2	R2.CS.B	R1.CP/CS.b2
CSC	XP5.2.1	R2.CS.C	R1.CP/CS.b3
CSD	XP5.2.2	R2.CS.D	R1.CP/CS.b4
CSE	XP5.2.3	R2.CS.E	R1.CP/CS.b5
CSF	XP5.2.4	R2.CS.F	R1.CP/CS.b6
CSG	XP5.1.9	R2.CS.G	R1.CP/CS.b7
CSH	XP5.1.10	R2.CS.H	R1.CP/CS.b8
CSJ	XP5.1.11	R2.CS.J	R1.CP/CS.b9
CSK	XP5.1.12	R2.CS.K	R1.CP/CS.b10
CSL	XP5.1.3	R2.CS.L	R1.CP/CS.b11
CSM	XP5.1.4	R2.CS.M	R1.CP/CS.b12
CSN	XP5.1.5	R2.CS.N	R1.CP/CS.b13
CSP	XP5.1.6	R2.CS.P	R1.CP/CS.b14
CSR	XP5.3.1	R2.CS.R	R1.CP/CS.b15
CSS	XP5.3.2	R2.CS.S	R1.CP/CS.b16
CST	XP5.3.3	R2.CS.T	R1.CP/CS.b18
CSU	XP5.3.4	R2.CS.U	R1.CP/CS.b19
CSV	XP5.3.5	R2.CS.V	R1.CP/CS.b20
CSW	XP5.3.6	R2.CS.W	R1.CP/CS.b21
CSX	XP5.2.9	R2.CS.X	R1.CP/CS.b22

Continues on next page

Signal name	Customer Terminal Controller	Customer Contact on Upper arm, R2	Customer Contact on robot base (cable between robot and controller not supplied)
CSY	XP5.2.10	R2.CS.Y	R1.CP/CS.b23
CSZ	XP5.2.11	R2.CS.Z	R1.CP/CS.b24

2.9 Test run after installation, maintenance, or repair

Safe handling

Use the following procedure after installation, maintenance, or repair, before initiating motion.

DANGER

Initiating motion without fulfilling the following aspects, may increase the risk for injury or cause damage to the robot.

	Action
1	Remove all tools and foreign objects from the robot and its working area.
2	Verify that the robot is properly secured to its position by all screws, before it is powered up.
3	Verify that any safety equipment installed to secure the position or restrict the robot motion during service activity is removed.
4	Verify that the fixture and work piece are well secured, if applicable.
5	Verify that all safety equipment is installed, as designed for the application.
6	Verify that no personnel are inside the safeguarded space.
7	If maintenance or repair has been done, verify the function of the part that was maintained.
8	Verify the application in the operating mode manual reduced speed.

Collision risks

CAUTION

When programming the movements of the robot, always identify potential collision risks before initiating motion.

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3 Maintenance

3.1 Introduction

Structure of this chapter

This chapter describes all the maintenance activities recommended for the IRB 2600/IRB 2600 ID.

It is based on the maintenance schedule found at the beginning of the chapter. The schedule contains information about required maintenance activities including intervals, and refers to procedures for the activities.

Each procedure contains all the information required to perform the activity, including required tools and materials.

The procedures are gathered in different sections and divided according to the maintenance activity.

Safety information

Observe all safety information before conducting any maintenance work.

There are general safety aspects that must be read through, as well as more specific safety information that describes the danger and safety risks when performing the procedures. Read the chapter *Safety on page 21* before performing any maintenance work.

The maintenance must be done by qualified personnel in accordance with the safety requirements set forth in the applicable national and regional standards and regulations.

Note

If the IRB 2600/IRB 2600 ID is connected to power, always make sure that the IRB 2600/IRB 2600 ID is connected to protective earth and a residual current device (RCD) before starting any maintenance work.

For more information see:

-
- *Product manual - OmniCore V250XT Type A*
- *Product manual - IRC5*
- *Product manual - IRC5 Panel Mounted Controller*
- *Robot cabling and connection points on page 102*.

3.2 Maintenance schedule and expected component life

3.2.1 Specification of maintenance intervals

Introduction

The intervals are specified in different ways depending on the type of maintenance activity to be carried out and the working conditions of the IRB 2600/IRB 2600 ID:

- Calendar time: specified in months regardless of whether the system is running or not.
- Operating time: specified in operating hours. More frequent running means more frequent maintenance activities.
- SIS: specified by the robot's SIS (Service Information System). A typical value is given for a typical work cycle, but the value will differ depending on how hard each part is run.

  The SIS used in M2004 is further described in the *Operating manual - Service Information System* (IRC5) or *Operating manual - OmniCore*.

  The SIS used in OmniCore is further described in the *Operating manual - OmniCore*.

Robots with the functionality *Service Information System* activated can show active counters in the device browser in RobotStudio, or on the FlexPendant.

Overhaul

Depending on application and operational environment a complete overhaul may be necessary in average around 40000 hours.

ABB Connected Services and its Assessment tools can help you to identify the real stress level of your robot, and define the optimal ABB support to maintain your robot working.

Contact your local ABB Customer Service to get more information.

3.2.2 Maintenance schedule

General

The robot must be maintained regularly to ensure proper function. The maintenance activities and intervals are specified in the following table.

Non-predictable situations also give rise to inspections of the robot. Any damage must be attended to immediately.

The inspection intervals *do not* specify the life of each component. Values for these are specified in the section *Expected component life on page 118*

Instructions for how to perform the different maintenance activities are found in sections:

- *Inspection activities on page 119*
- *Replacement / Changing activities on page 148*
- *Cleaning on page 184*

Activities and intervals, standard equipment

The following table specifies the required maintenance activities and intervals.

Maintenance activity	Equipment	Interval
Cleaning	Robot	*Cleaning the IRB 2600/IRB 2600 ID on page 184*
Inspection	Oil level in axis-1 gearbox	Every 12 months.
Inspection	Oil level in axis-2 gearbox	Every 12 months.
Inspection	Oil level in axis-3 gearbox	Every 12 months.
Inspection	Oil level in axis-4 gearbox	Every 12 months.
Inspection	Oil level in axis-5 gearbox (ID)	No inspection needed.
Inspection	Oil level in axis-5-6 gearbox	Every 12 months.
Inspection	Oil level in axis-5-6 gearbox (ID)	Every 12 months.
Inspection	Robot harness	Every 12 months[i].
Inspection	Information labels	Every 12 months.
Inspection	Dampers	Every 12 months.
Inspection	Pressure relief valve	Every 12 months[ii].
Inspection	Mechanical stop	Every 12 months.
Change	Oil in axis-1 gearbox	First change when DTC [iii] reads: • 6,000 hours Second change when DTC[iii] reads: • 24,000 hours Following changes: • Every 24,000 hours.

Continues on next page

Maintenance activity	Equipment	Interval
Change	Oil in axis-2 gearbox	First change when DTC [iii] reads: • 6,000 hours Second change when DTC [iii] reads: • 24,000 hours Following changes: • Every 24,000 hours.
Change	Oil in axis-3 gearbox	First change when DTC [iii] reads: • 6,000 hours Second change when DTC [iii] reads: • 24,000 hours Following changes: • Every 24,000 hours.
Change	Oil in axis-4 gearbox	No change needed.
Change	Oil in axis-5 gearbox (ID)	No change needed.
Change	Oil in axis-5-6 gearbox	First change when DTC [iii] reads: • 6,000 hours Second change when DTC [iii] reads: • 24,000 hours Following changes: • Every 24,000 hours.
Change	Oil in axis-5-6 gearbox (ID)	First change when DTC [iii] reads: • 6,000 hours Second change when DTC [iii] reads: • 24,000 hours Following changes: • Every 24,000 hours.
Overhaul	Robot	Every: • 40,000 hours .
Replacement	Battery pack, measurement system of type RMU101 or RMU102 (3-pole battery contact)	36 months or battery low alert [iv]
Replacement	Battery pack, measurement system with 2-pole battery contact, e.g. DSQC633A	Battery low alert [v]

i Replace when damage or cracks is detected or life limit is approaching that specified in section *Expected component life on page 118*.

ii Check more often if the environment is very contaminated.

iii DTC = Duty Time Counter. Shows the operational time of the robot.

iv The battery low alert (38213 **Battery charge low**) is displayed when the battery needs to be replaced. The recommendation to avoid an unsynchronized robot is to keep the power to the controller turned on until the battery is to be replaced.

See the replacement instruction for more details.

v The battery low alert (38213 **Battery charge low**) is displayed when remaining backup capacity (robot powered off) is less than 2 months. The typical lifetime of a new battery is 36 months if the robot is powered off 2 days/week or 18 months if the robot is powered off 16 h/day. The lifetime can be extended with a battery shutdown service routine. See the operating manual for the robot controller for instructions.

Continues on next page

Activities and intervals, optional equipment

The following table specifies the required maintenance activities and intervals for common optional equipment. The maintenance of other external equipment for the robot is detailed in separate documents.

Maintenance activity	Equipment	Interval	Note
Inspection	Signal lamp	Every: 12 months	
Inspection	Additional mechanical stop, axis 1	Every: 12 months	
Inspection	Motor fan	Every 12 months	Inspect the fan for contamination that could hinder the air supply. Clean if necessary.

3.2.3 Expected component life

General

The expected life of a specific component of the robot can vary greatly depending on how hard it is run.

Expected component life - protection type Standard

Component	Expected life	Note
Cable harness Normal usage [i]	40,000 hours [ii]	Not including: • Possible SpotPack harnesses • Optional upper arm harnesses
Cable harness Extreme usage [iii]	20,000 hours [ii]	Not including: • Possible SpotPack harnesses • Optional upper arm harnesses
Gearboxes [iv]	40,000 hours	

i Examples of "normal usage" in regard to movement: most material handling applications.

ii Severe chemical or thermal environments, or similar environments, can result in shortened life expectancy.

iii Examples of "extreme usage" in regard to movement: press tending, very severe palletizing applications, major use of axis 1 movement.

iv Depending on application, the lifetime can vary. The Service Information System (SIS), integrated in the robot software, can be used as a guidance for planning service of gearbox for the individual robot. This applies to gearboxes on axes 1, 2 and 3. The lifetime of gearbox axes 4, 5 and 6 is not calculated by SIS (See the *Operating manual - Service Infomation System*) In applications such as Foundry or Washing the robot can be exposed to chemicals, high temperature or humidity which can have an effect on the lifetime of gearboxes. Contact the local *ABB Robotics Service team* for more information.

The SIS for an IRC5 system is described in the *Operating manual - Service Information System*.

3.3 Inspection activities

3.3.1 Inspecting oil level, axis-1 gearbox

Different versions of the gearbox

There are two different versions of the axis-1 and axis-2 gearboxes. The different versions affect the mechanical structure of the base, frame and lower arm. Differences in the mechanical structure are pointed out in the procedure as valid for different robot version:

- IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0
- IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

Further information about the differences are given in *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

Mounting position of the robot

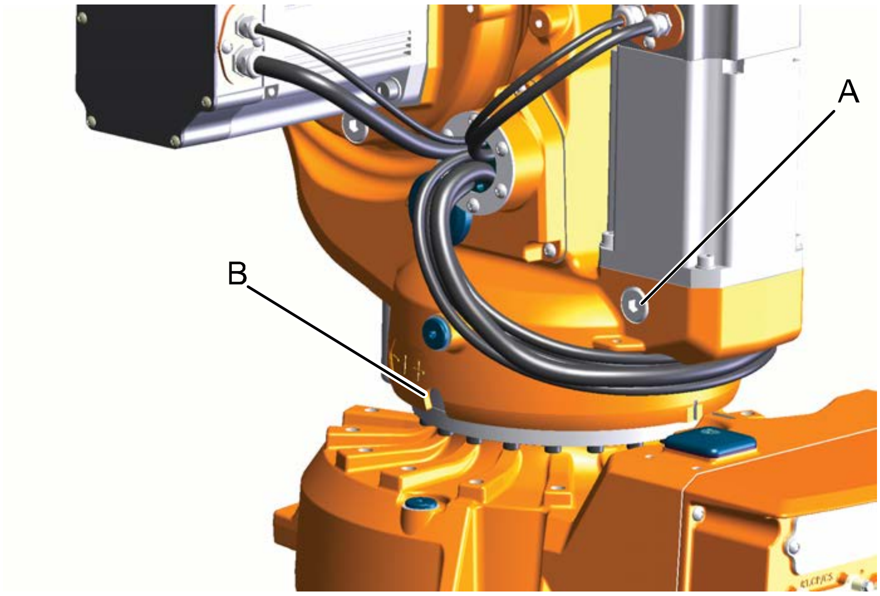
If the robot is floor mounted, follow the procedures in *Inspecting oil level, axis-1 gearbox (floor mounted) on page 121*.

If the robot is suspended, follow the procedures in *Inspecting oil level, axis-1 gearbox (suspended robot) on page 122*.

Location of oil plugs (floor mounted)

The axis 1 gearbox is located between the frame and base of the robot. The oil plug for inspection is shown in the figure.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



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A	Oil plug, inspection
B	Oil plug, gearbox, with sealing washer

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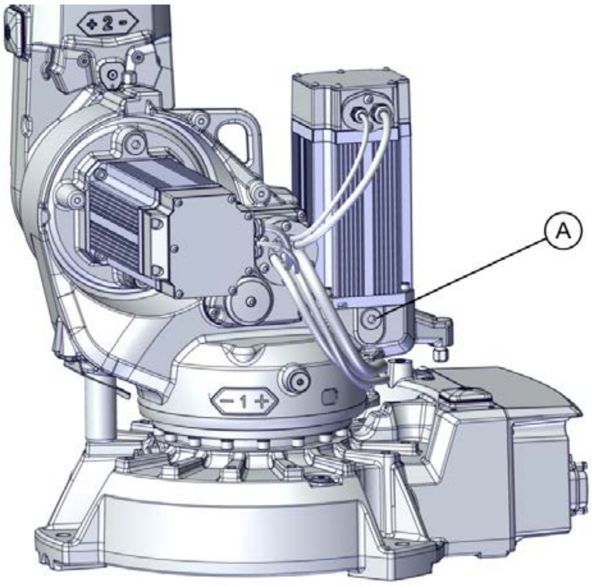
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



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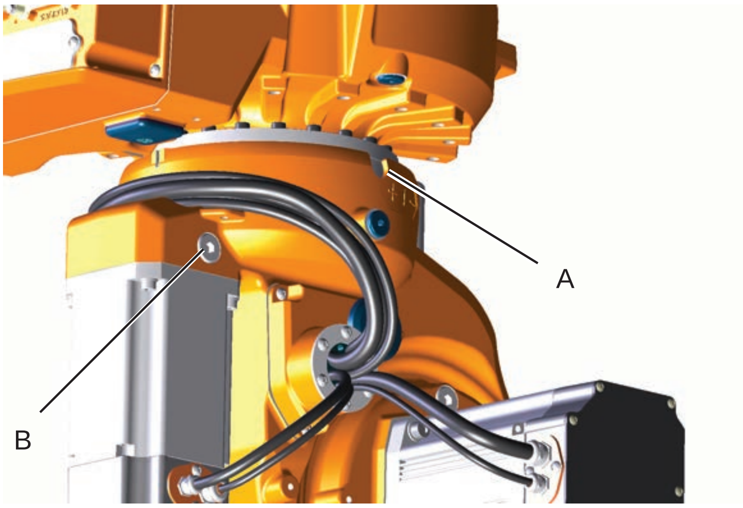
A	Oil plug, inspection

Location of oil plugs (suspended mounted)

The axis 1 gearbox is located between the frame and base of the robot. The oil plug for inspection is shown in the figure.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



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A	Oil plug, inspection, with sealing washer
B	Oil plug

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is not available for suspended installation.

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Required equipment

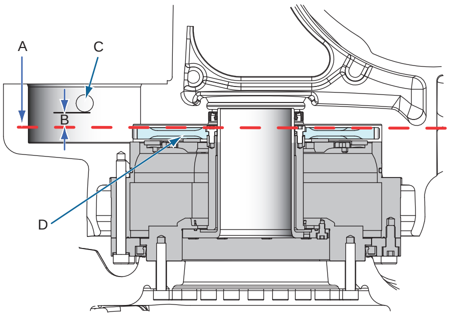
Equipment	Note
Oil plug sealing washer, gearbox	3HAC029646-001
Lubrication oil	See section *Type of lubrication in gearboxes on page 148*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting oil level, axis-1 gearbox (floor mounted)

Use this procedure to inspect the oil level in the axis-1 gearbox, when the robot is floor mounted.

	Action	Note
1	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Open the *oil plug, inspection*.	See *Location of oil plugs (floor mounted) on page 119*.

Continues on next page

	Action	Note
5	Measure the oil level at the oil plug hole. Required oil level for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0: • 10 mm ± 3 mm below the lower edge of the oil plug inspection hole. Required oil level for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C: • 8 mm ± 3 mm below the lower edge of the oil plug inspection hole.	 xx1200001352 Parts: A Oil level B Measurement of required oil level C Oil plug hole inspection D Gear
6	Add oil if required.	How to fill oil is described in section: • *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*
7	Refit the oil plug, inspection.	Tightening torque: • 24 Nm

Inspecting oil level, axis-1 gearbox (suspended robot)

Use this procedure to inspect the oil level in the axis-1 gearbox for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.

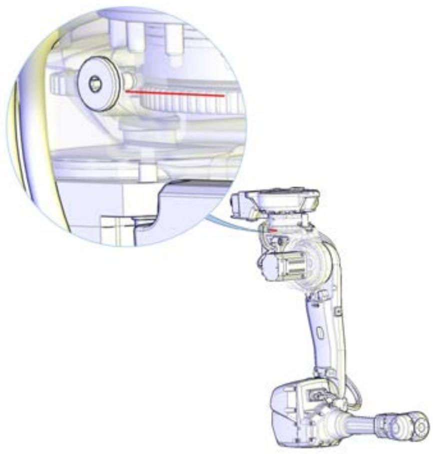
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C is not available for suspended installation.

CAUTION

If the robot has the earlier design of the frame, and the robot is filled with an amount of oil suited for an inverted position, the oil level of the axis-1 gearbox will be above the oil plug hole when the robot is standing on the floor, which will result in oil leakage if the plug is opened while robot stands on the floor! The oil level of axis-1 gearbox can therefore only be inspected when the robot is mounted in an inverted position!

	Action	Note
1	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	

Continues on next page

	Action	Note
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Open the *oil plug inspection* on the axis 1 gearbox.	See the figure in: • *Location of oil plugs (suspended mounted) on page 120*
5	Required oil level: • up to the lower edge of the oil plug hole. **Note** The oil plugs on gearbox axis 1 are now on top.	 xx1100000008
6	Add oil if required.	How to fill oil is described in section: • *Changing the oil, axis-1 gearbox on suspended robots on page 158*
7	Refit the oil plug. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug sealing washer with a new one. If not there is a risk of leakage.	Tightening torque: • 3-8 Nm

3.3.2 Inspecting the oil level, axis 2 gearbox

Different versions of the gearbox

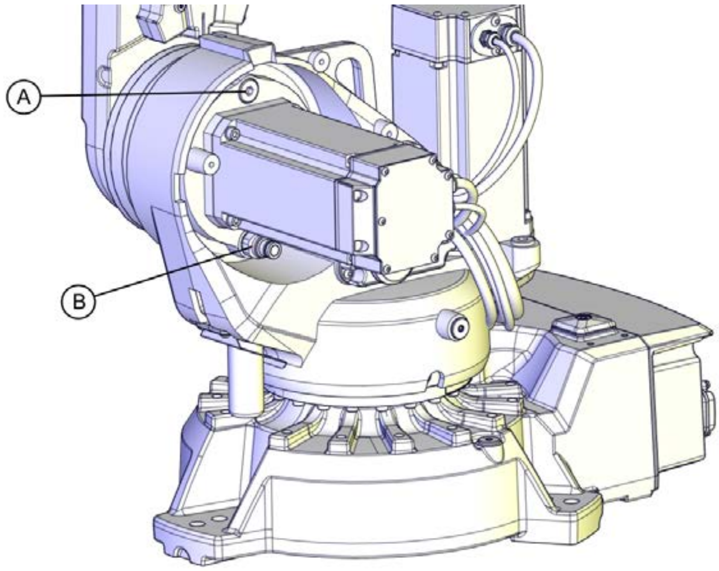
There are two different versions of the axis-1 and axis-2 gearboxes. The different versions affect the mechanical structure of the base, frame and lower arm. Differences in the mechanical structure are pointed out in the procedure as valid for different robot version:

- IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0
- IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

Further information about the differences are given in *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

Location of axis 2 gearbox

The axis 2 gearbox is located in the lower arm rotational center, underneath the motor attachment. The oil plugs are shown in the figure.



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A	Oil plug, inspection, when robot is floor mounted
B	Oil plug, inspection, when robot is suspended (Quick connect fitting)

Required equipment

Equipment	Note
Oil plug sealing washer, gearbox	3HAC029646-001
Lubrication oil	See section *Type of lubrication in gearboxes on page 148*.
Oil plug (Quick connect fitting)	For article number see *Spare part lists on page 461*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Continues on next page

Equipment	Note
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting oil level, axis 2 gearbox

Use this procedure to inspect the oil level in the axis 2 gearbox.

	Action	Note
1	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Open the *oil plug, inspection* (location depends on how the robot is mounted). **Note** Always open the oil plug on top, depending how the robot is mounted.	See the figure in: • *Location of axis 2 gearbox on page 124*
5	Measure the oil level at the oil plug hole. Required oil level: • 42 mm ± 5 mm below the lower edge of the oil plug hole (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0). 28 mm ± 3 mm below the lower edge of the oil plug hole (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C).	
6	Add oil if required.	How to fill oil is described in section • *Changing the oil, axis-2 gearbox on page 163*

Continues on next page

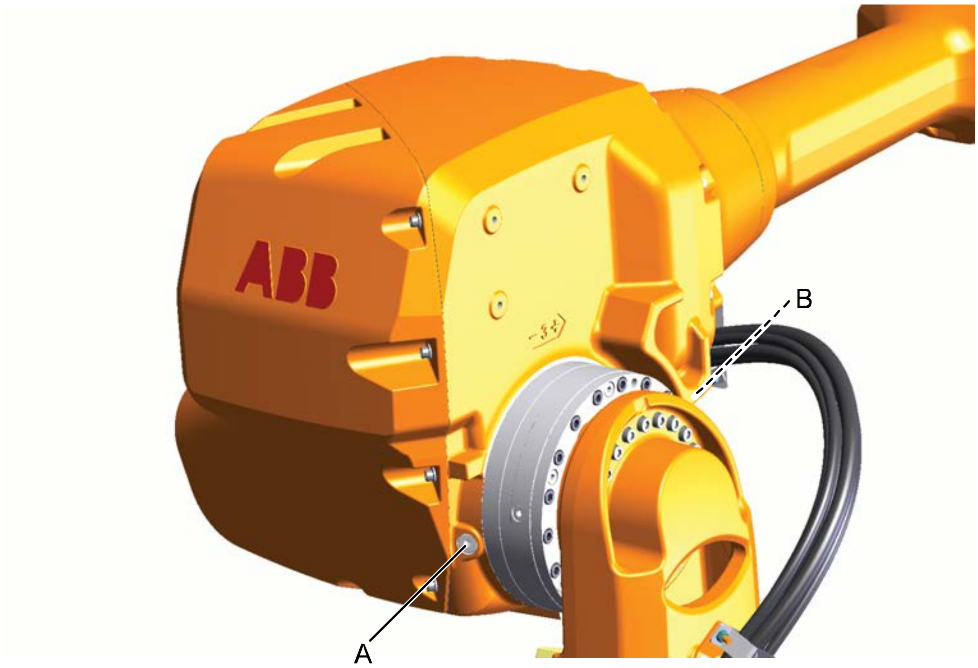
	Action	Note
7	Refit the oil plug. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug sealing washer with a new one. If not there is a risk of leakage.	Tightening torque: • 24 Nm

3.3.3 Inspecting the oil level, axis 3 gearbox

Location of axis 3 gearbox

The axis 3 gearbox is located in the upper arm rotational center, underneath the motor attachment. The oil plug for inspection is shown in the figure.

The figure shows IRB 2600 Standard but the position of plugs are approximately the same on IRB 2600ID.



xx0800000306

A	Oil plug, armhouse
B	Oil plug, gearbox (not visible in this figure)

Required equipment

Equipment	Note
Lubrication oil	See section *Type of lubrication in gearboxes on page 148*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Continues on next page

Inspecting the oil level, axis 3 gearbox

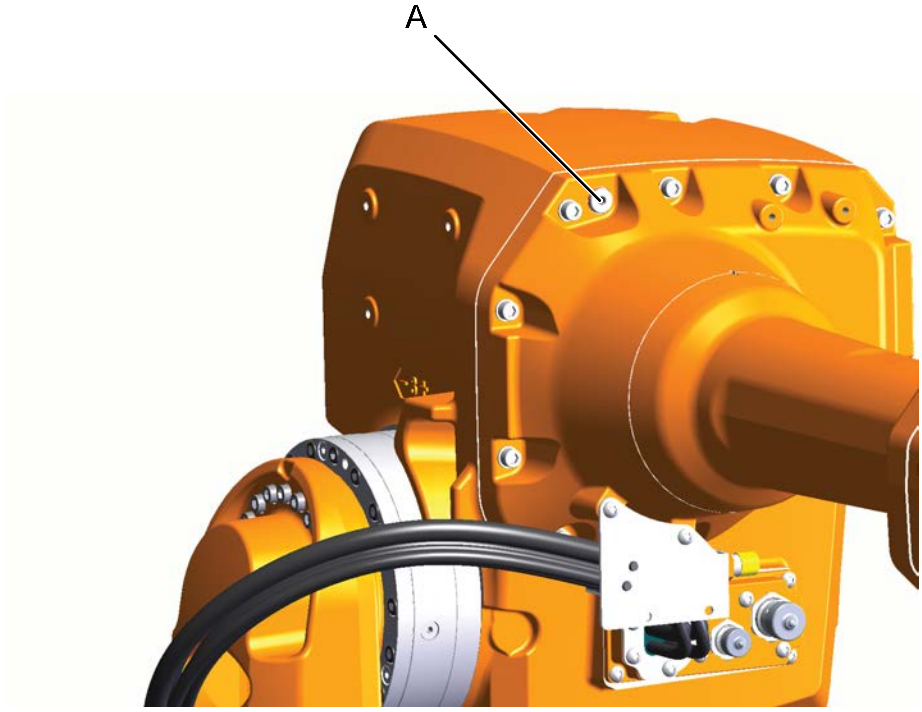
Use this procedure to inspect the oil level in the axis 3 gearbox.

	Action	Note
1	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
2	**IRB 2600**: Move the robot to where the upper arm points either straight up or straight down. **IRB 2600ID**: Move the robot to where the upper arm points straight up.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
5	Open the *upper oil plug*.	See the figure in: • *Location of axis 3 gearbox on page 127*
6	Measure the oil level at the oil plug hole. Required oil level: • **IRB 2600**: 45 ± 5 mm from the upper edge of oil plug hole. • **IRB 2600ID**: 70 ± 3 mm from the upper edge of oil plug hole.	
7	Add oil if required.	How to fill oil is described in section: • *Changing the oil, axis-3 gearbox on page 167*
8	Refit the oil plug.	Tightening torque: • in armhouse: 10 Nm • in gearbox: 3 Nm

3.3.4 Inspecting the oil level, axis 4 gearbox

Location of axis 4 gearbox

The axis 4 gearbox is located in the upper armhouse. The oil plug is shown in the figure.



xx0800000307

A	Oil plug, for filling and draining

Required equipment

Equipment	Note
Lubrication oil	See section *Type of lubrication in gearboxes on page 148*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting the oil level, axis 4 gearbox

Use this procedure to inspect the oil level in the axis 4 gearbox.

	Action	Note
1	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	

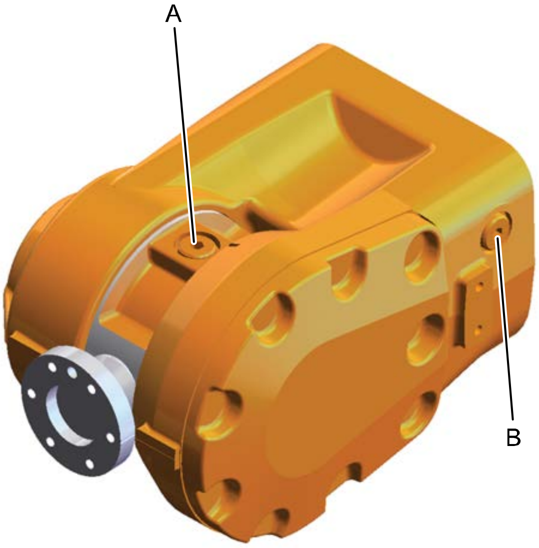
Continues on next page

	Action	Note
2	Move the robot to where the upper arm points straight up and the oil plug hole is on top of the axis 4 gearbox.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
5	Open the *oil plug*.	See the figure in: • *Location of axis 4 gearbox on page 129*
6	Measure the oil level at the oil plug hole. Required oil level: • IRB 2600: 15 ±3 mm below the oil plug flange. IRB 2600ID: 30 ±5 mm below the oil plug flange.	
7	Add oil if required.	How to fill oil is described in section: • *Changing the oil, axis-4 gearbox on page 171*
8	Refit the oil plug, filling.	Tightening torque: • 10 Nm

3.3.5 Inspecting oil level, gearbox axes 5 - 6

Location of gearbox, axes 5-6

The gearbox axes 5-6 is located in the wrist unit. The oil plug is shown in the figure.



xx0900000139

A	Oil plug, tilthouse
B	Oil plug, wrist (also used as air inlet when draining from oil plug A)

Required equipment

Equipment	Note
Lubrication oil	See section *Type of lubrication in gearboxes on page 148*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting oil level, gearbox axes 5-6 - wrist 12/20 kg

Use this procedure to fill oil in the gearbox.

	Action	Note
1	IRB 2600: Move the robot to a position where the upper arm is close to horizontal and axis 4 in the calibration position. IRB 2600ID: Move the robot to a position where axis 4 is placed in -25°.	

Continues on next page

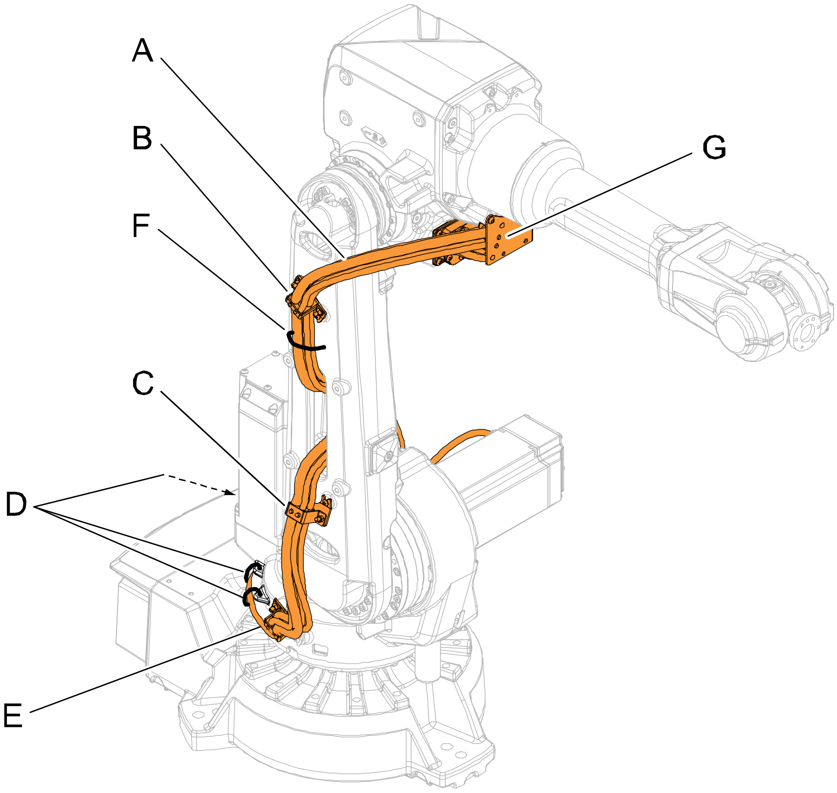
	Action	Note
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Remove the *oil plug, wrist*.	See the figure in: • *Location of gearbox, axes 5-6 on page 131*
5	Required oil level: • IRB 2600: 3 ± 3 mm from the lower edge of the oil plug in the wrist house. Open the oil plug in the tilthouse to allow the oil level between axis 5 and 6 to level. • IRB 2600ID: Oil shall be visible in the rear oil plug hole, almost on its way to pour out of the hole.	
6	If necessary, refill oil.	How to fill oil is described in section: • *Changing oil, axes-5 and -6 gearboxes on page 175*
7	Refit the oil plug.	Tightening torque: • 10 Nm

3.3.6 Inspecting the cable harness

Location of cable harness

The figure shows the location of the cable harness.

The figure shows IRB 2600 with standard upper arm.



xx0900000384

A	Cable harness
B	Bracket, lower arm
C	Bracket, lower arm
D	Cable straps, one not visible here (steel)
E	Bracket, frame
F	Cable strap, lower arm (plastic)
G	Bracket, upper arm

Required equipment

Equipment	Note
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.
Circuit diagram	See chapter *Circuit diagram on page 463*.

Continues on next page

Inspecting the cable harness

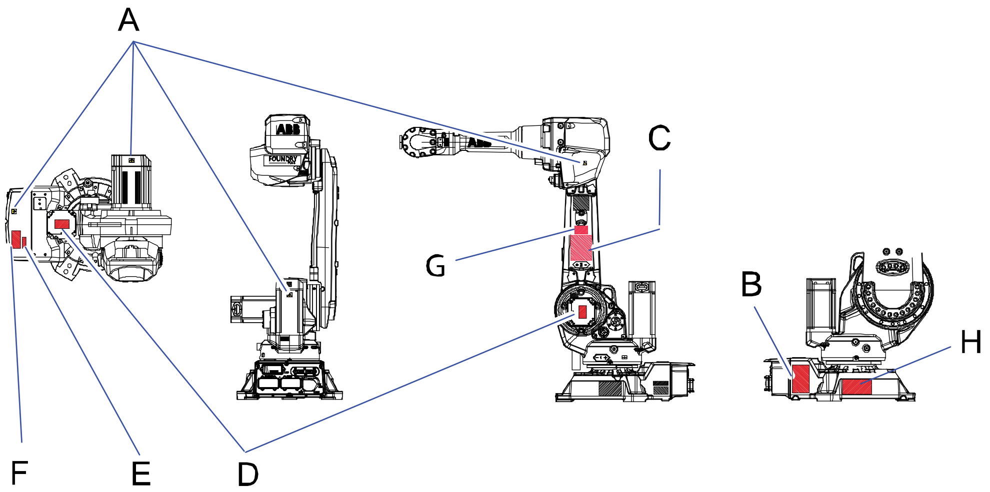
Use this procedure to inspect the cable harness. The inspection points are shown in the figure *Location of cable harness on page 133*

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Make an overall visual inspection of the cable harness in order to detect wear or damage.	
3	Check the *connectors at the base*.	
4	Check the *connectors at the armhouse*.	
5	Check that all *brackets* and *straps* are properly attached to the robot.	
6	Replace the cable harness if wear, cracks or damage is detected.	How to replace the cable harness is described in *Repair on page 189*.

3.3.7 Inspecting information labels

Location of information labels

The figure shows the location of the information labels to be inspected.



xx1000000205

A	Warning - Symbol of flash (4 pcs)
B	Warning - Risk of tipping
C	Label - Lifting instruction
D	Warning - "High temperature"
E	Label - Max. air pressure
F	Warning - Brake release unit
G	Label - Calibration
H	Label - Suspended robot

Required equipment

Equipment	Spare part number	Note
Labels	See *Spare part lists on page 461*.	

Inspecting labels

Use this procedure to inspect the labels on the robot.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

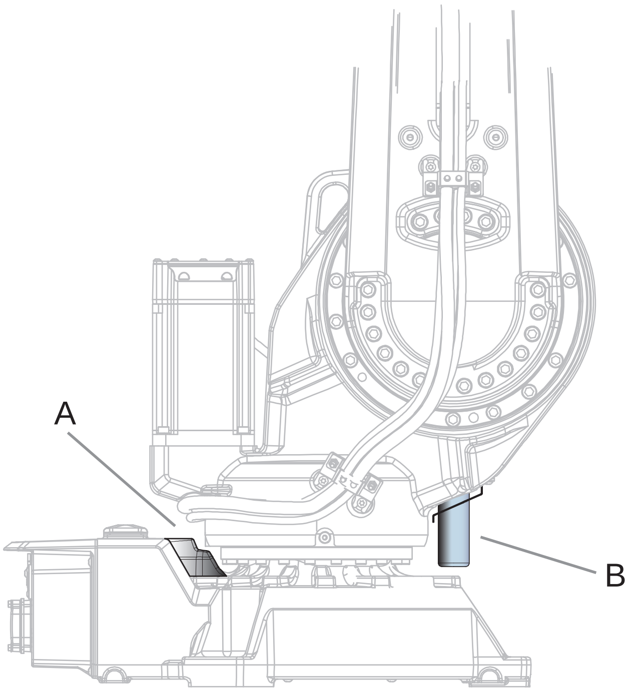
Continues on next page

	Action	Note
2	Check all labels.	See the figure in *Location of information labels on page 135*.
3	Replace any missing or damaged labels.	

3.3.8 Inspecting the mechanical stop pin, axis 1

Location of mechanical stop pin, axis 1

The mechanical stop pin is located on the frame as shown in the figure.



xx0800000298

A	Fixed stop
B	Mechanical stop pin, axis 1

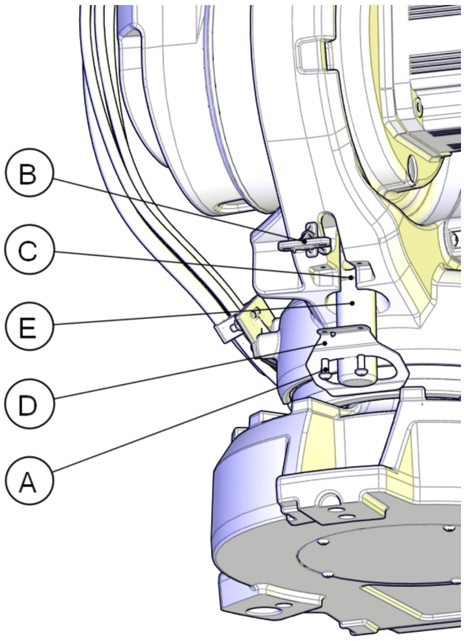
Required equipment

Equipment	Article number	Note
Mechanical stop pin axis 1	See *Spare part lists on page 461*.	
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Continues on next page

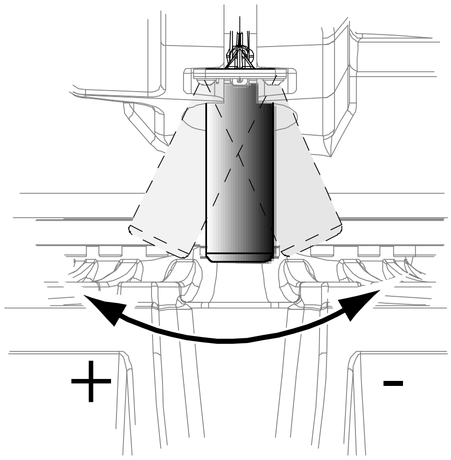
Inspection of mechanical stop pin, axis 1

Use this procedure to inspect the mechanical stop pin, axis 1.

<table>
<tr><th></th><th>Action</th><th>Note</th></tr>
<tr><td>1</td><td>DANGER
Turn off all:
electric power supply
hydraulic pressure supply
air pressure supply
to the robot, before entering the robot working area.</td><td></td></tr>
<tr><td>2</td><td>Regularly check that the mechanical stop pin is not bent or damaged in any other way.</td><td>See the figure in:
Location of mechanical stop pin, axis 1 on page 137</td></tr>
<tr><td>3</td><td>Note
If the mechanical stop pin has been deformed or damaged, all of its mounting parts have to be replaced.


xx0800000045
Parts:
A Attachment screws
B Bracket
C O-ring (2 pcs) - Not used if bracket (D) is installed.
D Bracket
E Stop pin</td><td>How to replace the stop pin is described in section Replacing stop pin axis 1 on page 293.</td></tr>
<tr><td>4</td><td>Check that the mechanical stop pin is properly attached.</td><td></td></tr>
</table>

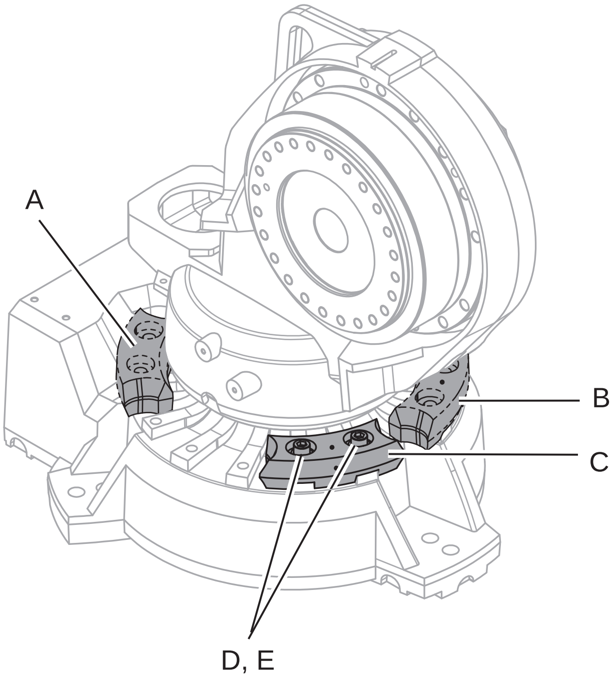
Continues on next page

	Action	Note
5	Check that the *mechanical stop pin* can move freely in both directions and the *bracket* works as it is supposed to.	 xx1000000222

3.3.9 Inspecting additional mechanical stops

Location of additional mechanical stops

The figure shows the location of the additional stops.



xx0800000273

A	Movable mechanical stop. Limited to: • -126° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • -129° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
B	Movable mechanical stop. Limited to: • +13.5° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • +16.5° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
C	Movable mechanical stop. Limited to: • -13.5° (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) • -16.5° (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)
D	Attachment screws
E	Washers

Required equipment

Equipment etc.	Note
Mechanical stop set, axis 1	Includes: • Stop • Attachment screws plus washers • Document for movable mechanical stop For spare part number see *Spare part lists on page 461*.

Continues on next page

Equipment etc.	Note
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting additional mechanical stops

Use this procedure to inspect the additional mechanical stops on axis 1.

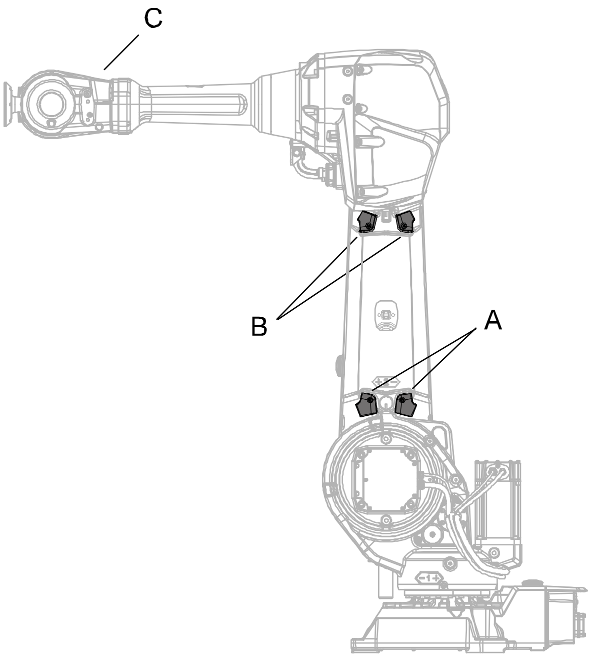
	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Check the *additional mechanical stops* on axis 1 for damage.	See the figure in: • *Location of additional mechanical stops on page 140*
3	Make sure the stops are properly attached.	Tightening torque: • 82 Nm
4	If any damage on stops or attachment screws etc. is detected, the *mechanical stops* must be replaced!	Attachment screws: • M12x40, quality 8.8-A3F • 2 pcs/stop lug

3.3.10 Inspecting dampers

Location of dampers

The figure shows the location of all dampers to be inspected.

The figure shows IRB 2600 with Standard upper arm.



xx0800000297

A	Dampers axis 2 (IRB 2600 Standard and ID)
B	Dampers axis 3 (IRB 2600 Standard and ID)
C	Damper axis 5 (only on IRB 2600 Standard)

Required equipment

Equipment	Spare part no.	Note
Damper	See *Spare part lists on page 461*.	
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.

Continues on next page

Inspecting dampers

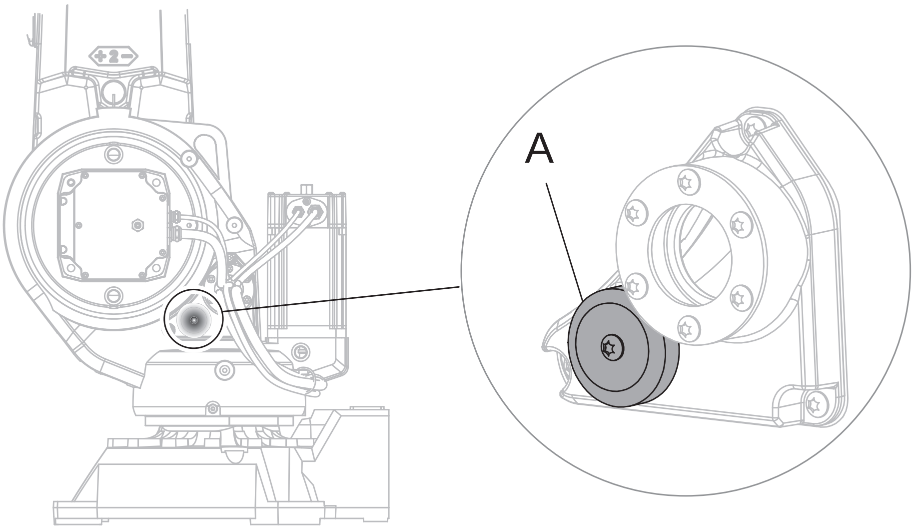
Use this procedure to inspect the dampers.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Check all *dampers* for damage or cracks.	See the figure in: • *Location of dampers on page 142*
3	Check all dampers for existing impressions larger than 2-3 mm.	
4	Check attachment screws for deformation.	
5	If any damage is detected the damper must be replaced.	

3.3.11 Inspecting the pressure relief valve

Location of the pressure relief valve

The figure shows the location of the pressure relief valve.



xx0900000131

A	Pressure relief valve

Required equipment

Equipment	Note
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Inspecting pressure relief valve

Use this procedure to inspect the pressure relief valve.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**DANGER** It is important to keep the pressure relief valve open and clean. If the air pressure is stopped up, too much pressure can be built up which can be hazardous.	

Continues on next page

	Action	Note
3	Check if the pressure relief valve is contaminated or covered with litter.	
4	Clean if necessary. **Note** Use a cloth or a brush.	

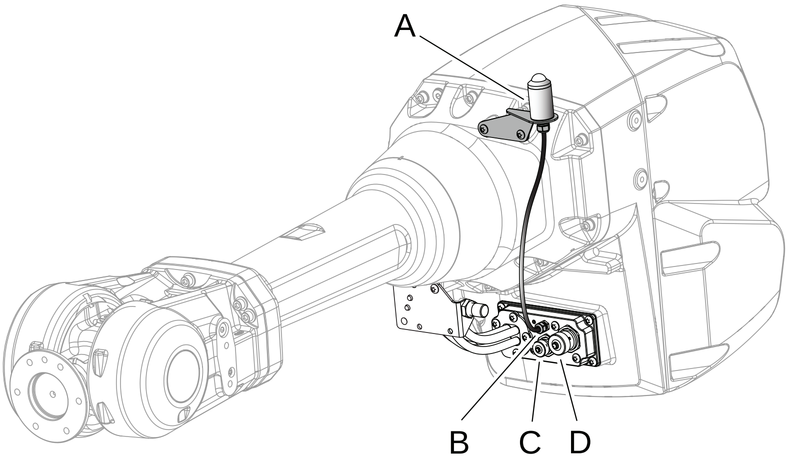
3.3.12 Inspecting Signal lamp (option)

Location of signal lamp

Signal lamp is an option.

Located as shown in the figure.

The figure shows IRB 2600 Standard.



xx0800000290

A	Signal lamp
B	R3.H1 +, R3.H2 -
C	R2.CP
D	R2.CS

Required equipment

Equipment	Note
Signal lamp	For spare parts no. see Spare parts - *Spare parts options* in *Product manual, spare parts - IRB 2600*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Inspecting signal lamp

Use this procedure to inspect the function of the signal lamp.

Note

If the signal lamp is damaged, it shall be replaced!

	Action	Note
1	Check that the signal lamp is lit when motors are put in operation ("MOTORS ON").	

Continues on next page

	Action	Note
2	If the signal lamp is not lit, continue tracing the fault with the steps below.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Check whether the signal lamp is broken. If so, replace.	
5	Check the cable connections.	
6	Measure the voltage in connectors, motor axis 3.	24V
7	Check the cabling. If a fault is detected, replace.	
8	Seal and paint the joints that have been opened. Also repair possible damages of the special Foundry Prime paint coat of the robot. See *Cut the paint or surface on the robot before replacing parts on page 197*.	

3.4 Replacement / Changing activities

3.4.1 Type of lubrication in gearboxes

Introduction

This section describes where to find information about the type of lubrication, article number and the amount of lubrication in the specific gearbox. It also describes the equipment needed when working with lubrication.

Type and amount of oil in gearboxes

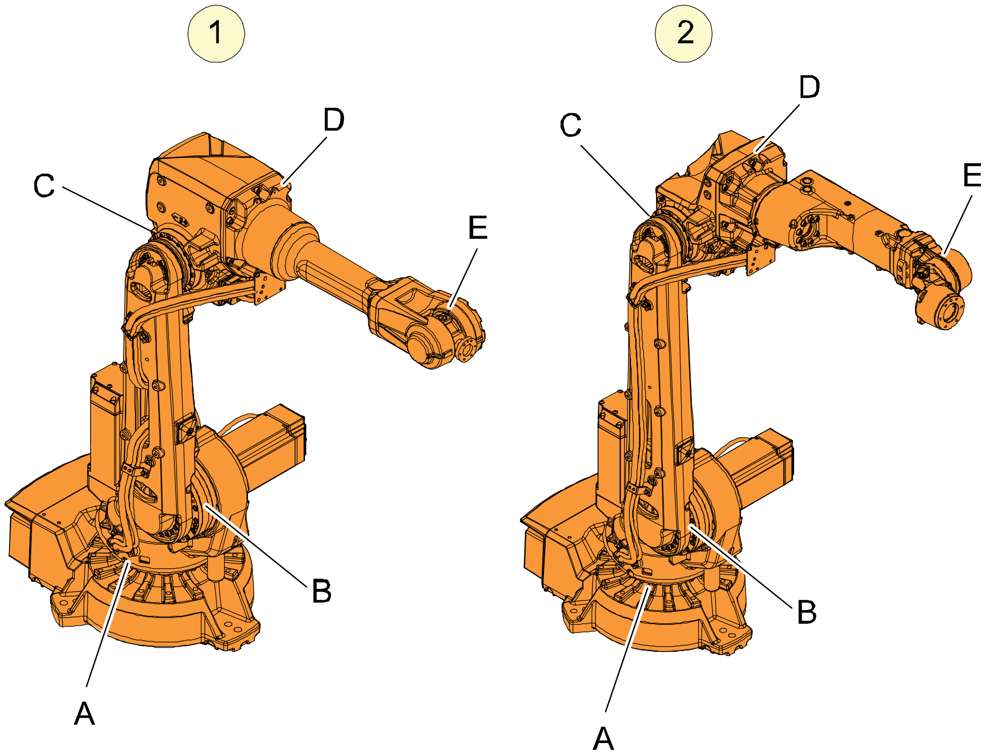
Information about the type of lubrication, article number as well as the amount in the specific gearbox can be found in *Technical reference manual - Lubrication in gearboxes* available for registered users on myABB Business Portal, www.abb.com/myABB.

> **Note**
>
> The type of oil pre-filled in axis-4 gear differs from the type of oil recommended for field maintenance, due to differences in factory and customer sites prerequisites. The two types of oil are fully equal and compatible.
>
> Use the type of oil specified in *Technical reference manual - Lubrication in gearboxes*, even though it differs from the oil specified in WebConfig.

Location of gearboxes

The figure shows the location of the gearboxes.

Continues on next page



xx0900000312

1	IRB 2600 Standard
2	IRB 2600ID
A	Gearbox, axis 1
B	Gearbox, axis 2
C	Gearbox, axis 3
D	Gearbox, axis 4
E	Gearbox, axis 5-6

Equipment

Equipment	Note
Oil dispenser	Includes pump with outlet pipe. Use the suggested dispenser or a similar one: • Orion OriCan article number 22590 (pneumatic)
Nipple for quick connect fitting, with o-ring	Used on the axis-2 gearbox (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0). Used on the axis-1 and axis-2 gearboxes (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C).
Expansion container, gearbox axis 1	Used when the robot is fitted in a suspended position. (valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0)

3.4.2 Changing the oil, axis 1 gearbox on floor mounted robots

General

This section describes how to change the axis-1 gearbox oil in a floor mounted robot.

Different versions of the gearbox

There are two different versions of the axis-1 and axis-2 gearboxes. The different versions affect the mechanical structure of the base, frame and lower arm. Differences in the mechanical structure are pointed out in the procedure as valid for different robot version:

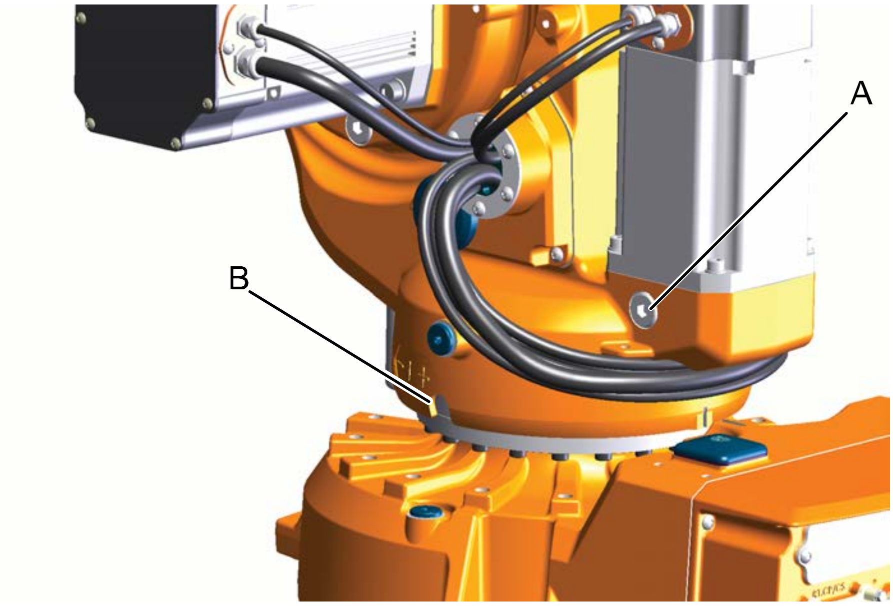
- IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0
- IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

Further information about the differences are given in *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

Location of oil plugs

The oil plugs are located according to following figures.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



xx0800000304

A	Oil plug, filling and venting
B	Oil plug, draining, with sealing washer

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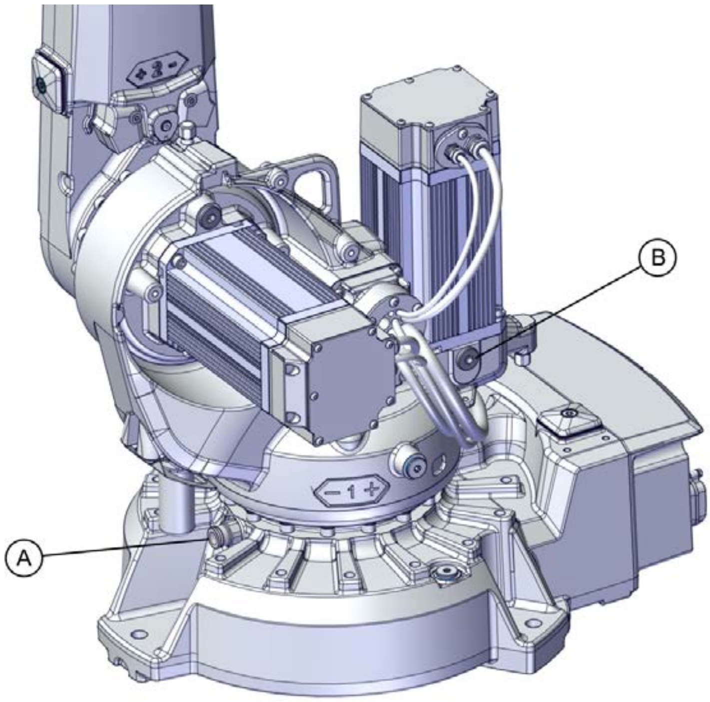
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



xx1800001135

A	Oil plug, filling and draining
B	Oil plug, venting

Required equipment

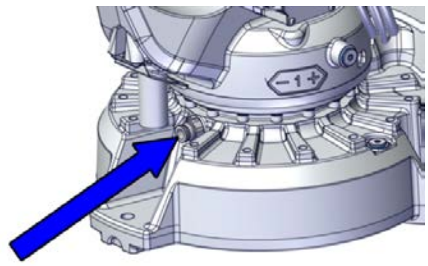
Equipment	Note
Oil plug sealing washer, gearbox	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0** 3HAC029646-001
Lubricating oil	See section *Type of lubrication in gearboxes on page 148*.
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Oil dispenser	One example of oil dispenser can be found in section: • *Type of lubrication in gearboxes on page 148*
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Continues on next page

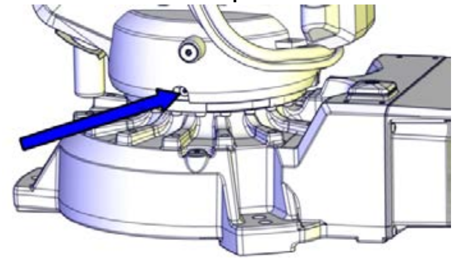
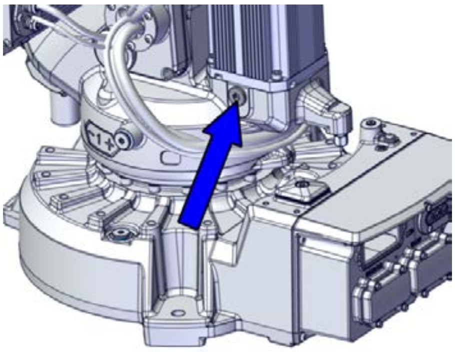
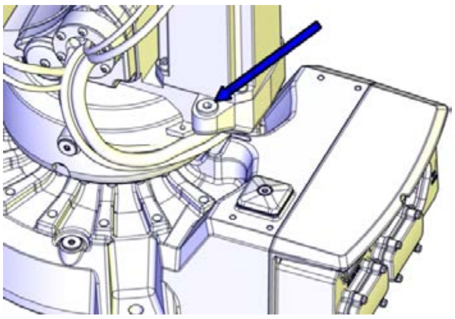
Draining, axis 1 gearbox

Use this procedure to drain the gearbox of oil.

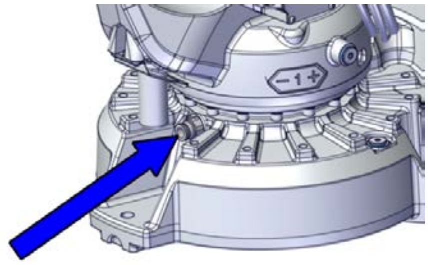
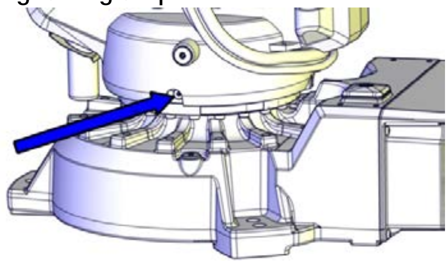
The oil must be sucked out from the gearbox. It is recommended to use a pneumatic oil dispenser to drain oil from the gearbox.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Remove the protective cap from the oil nipple and connect the oil dispenser.	 xx1800001136

Continues on next page

	Action	Note
5	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** • Put an *oil collecting vessel* as close as possible to the draining hole of the gearbox. • Replace *oil plug draining* quickly with a nipple (M10x1.5) where a draining hose is fitted and connect the *oil dispenser*.	The capacity of the vessel must be sufficient to take the complete amount of oil.  xx1800001138 **Note** Draining is time-consuming. Elapsed time varies depending on the temperature of the oil. One example of oil dispenser can be found in section: • *Type of lubrication in gearboxes on page 148*
6	Remove the plug from the vent hole. **WARNING** If the oil plug for venting is not open when the oil dispenser is working, there is a risk of damaging vital parts in the gearbox!	Different position due to design differences:  xx1800001137  xx1800001139
7	Suck out the oil with the oil dispenser. **Note** There will be some oil left in the gear after draining.	

Continues on next page

	Action	Note
8	**WARNING** Used oil is hazardous material and must be disposed of in a safe way. See section *Decommissioning on page 439* for more information.	
9	Remove the oil dispenser.	
10	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Refit the protective cap on the nipple.	 xx1800001136
11	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Refit the *oil plug, draining*. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug gasket with a new gasket. If not there is a risk of leakage.	Tightening torque: 3-8 Nm  xx1800001138

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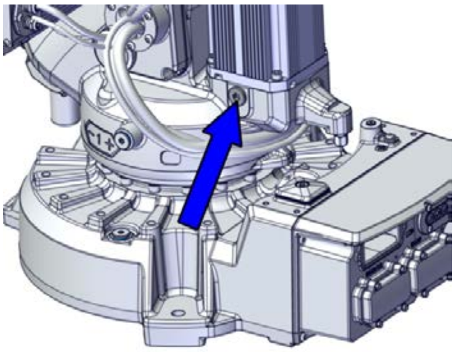
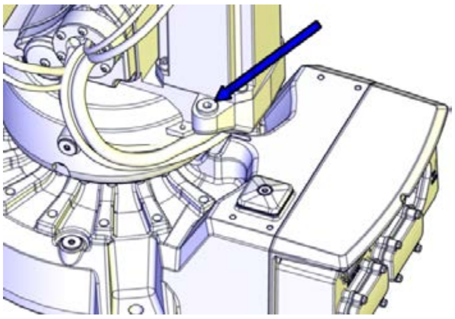
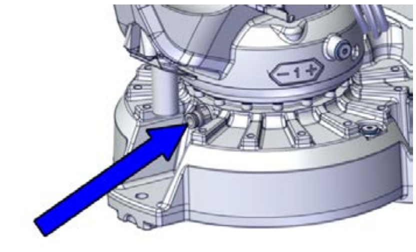
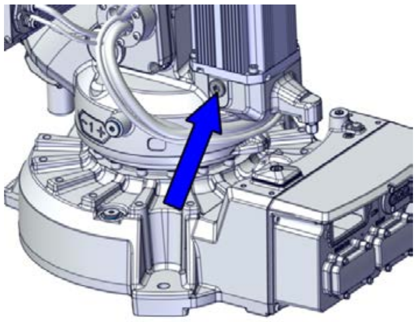
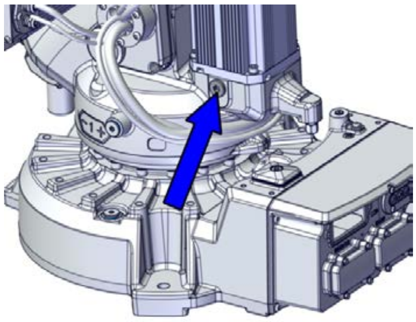
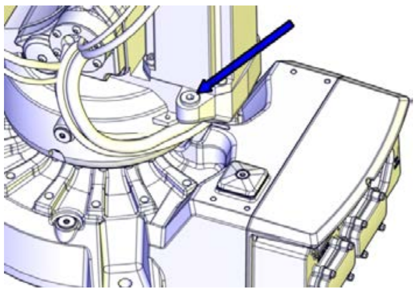
	Action	Note
12	Refit the *oil plug, venting*.	Tightening torque: 24 Nm Different position due to design differences:  xx1800001137  xx1800001139

Filling oil, axis 1 gearbox

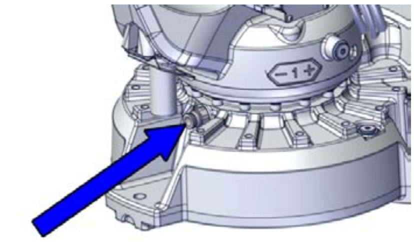
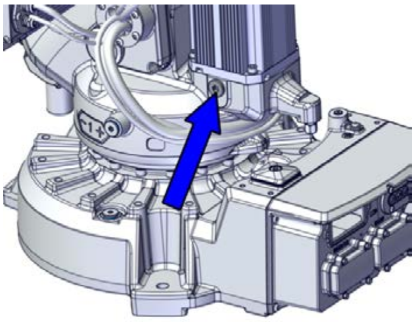
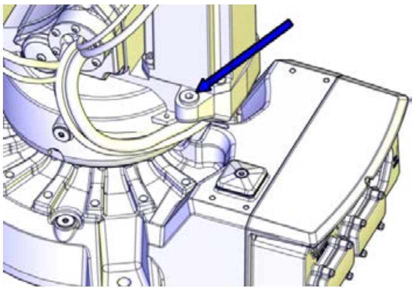
Use this procedure to fill the gearbox with oil.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	

Continues on next page

	Action	Note
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Remove the protective cap from the oil nipple and connect the oil dispenser.	 xx1800001136
5	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Remove the plug from the vent hole. **Note** The vent hole is opened to let out air during the filling process.	 xx1800001137
6	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Open the *oil plug, filling*.	Different position due to design differences:  xx1800001137  xx1800001139

Continues on next page

	Action	Note
7	Refill the gearbox with *lubrication oil*. **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Use the oil dispenser. **Note** The amount of oil to be filled depends on the amount previously being drained.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
8	Inspect the oil level.	How to inspect the oil level is described in section: • *Inspecting oil level, axis-1 gearbox on page 119*
9	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Remove the oil dispenser and refit the protective cap to the nipple.	 xx1800001136
10	Refit the *oil plug*.	Tightening torque: 24 Nm Different position due to design differences:  xx1800001137  xx1800001139

3.4.3 Changing the oil, axis-1 gearbox on suspended robots

Validity of this section

This section is only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.

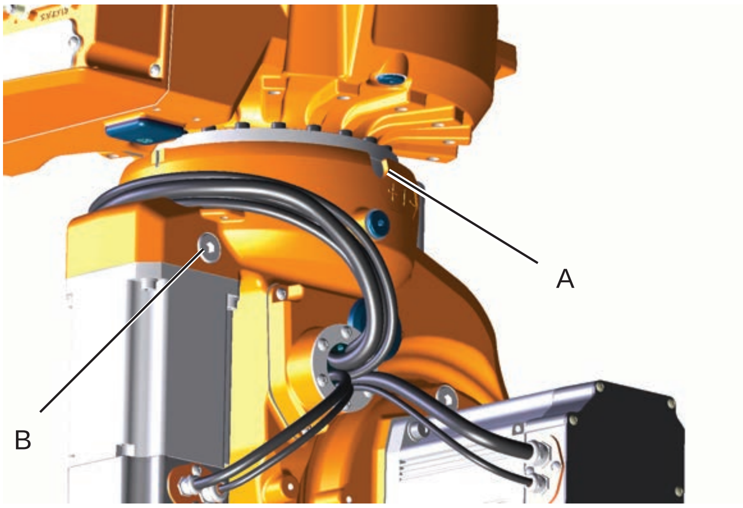
General

This section describes how to change the axis-1 gearbox oil in a suspended robot.

Location of oil plugs

The oil plugs in axis 1 gearbox are located according to the following figures

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



xx1200000883

A	Oil plug, venting
B	Oil plug, draining and filling

Required equipment

Equipment	Note
Oil plug sealing washer, gearbox	3HAC029646-001
Lubricating oil	See section *Type of lubrication in gearboxes on page 148*
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Oil dispenser	One example of oil dispenser can be found in section: • *Type of lubrication in gearboxes on page 148*
Oil change equipment	
Hose	Used with the oil dispenser
Standard toolkit	Content is defined in section *Standard tools on page 456*.

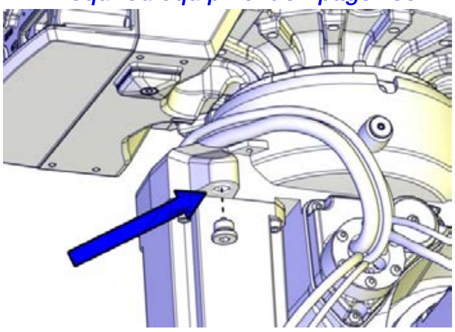
Continues on next page

Draining, axis-1 gearbox

Use this procedure to drain the gearbox of oil.

Tip

In order to save time, a pneumatic oil dispenser can be used to suck the oil out from the gearbox.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Connect the *oil dispenser* to the *oil plug for draining*.	See *Required equipment on page 158*.  xx1800001271
5	Put the end of the hose in an *oil collecting vessel*.	The capacity of the vessel must be sufficient to take the complete amount of oil.
6	Open the end plug of the hose.	

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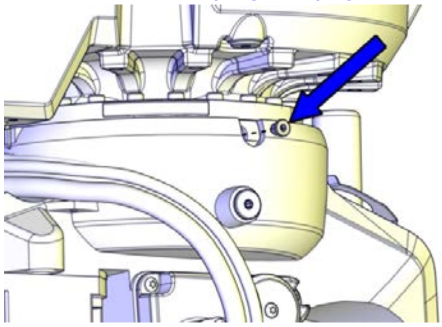
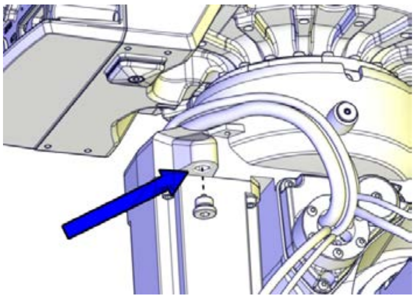
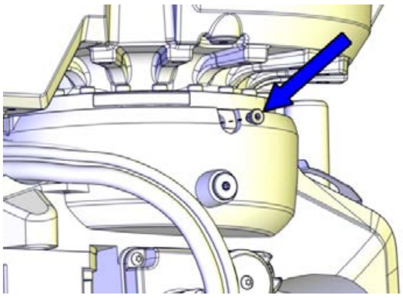
	Action	Note
7	Open the *oil plug, venting*.	See *Location of oil plugs on page 158*.  xx1800001272
8	Using a low air pressure, start sucking the oil out from the gearbox with the oil change equipment.	
9	**WARNING** Used oil is hazardous material and must be disposed of in a safe way. See section *Decommissioning on page 439* for more information.	
10	Let the oil drain until the gearbox is empty. **Note** There will be some oil left in the gearbox after draining. Measure the volume of the drained oil in the vessel.	**Tip** Make a note how much oil was drained. The same amount shall later be refilled.
11	Remove the hose and clean it.	

Filling oil, axis-1 gearbox

Use this procedure to fill the gearbox with oil.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	

Continues on next page

	Action	Note
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Verify that the hose of the oil change equipment is clean and then fit the quick connection to the *oil plug for filling*.	 xx1800001271
5	Open the oil *plug for venting*.	 xx1800001272
6	Prepare oil change equipment with the same amount of *lubrication oil* that was drained. **Note** The amount of oil to be filled depends on the amount previously being drained.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
7	Inspect the oil level.	How to inspect the oil level is described in section: • *Inspecting oil level, axis-1 gearbox on page 119*
8	Disconnect the oil change equipment and put on the protective hood on the oil plug.	
9	Refit the *oil plug for venting*. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug sealing washer with a new one. If not there is a risk of leakage.	Tightening torque: • 3-8 Nm

Expansion container axis-1 gearbox, suspended mounted robots

When the robot is fitted in a suspended mounted position, an expansion container for oil must be fitted on gearbox axis 1.

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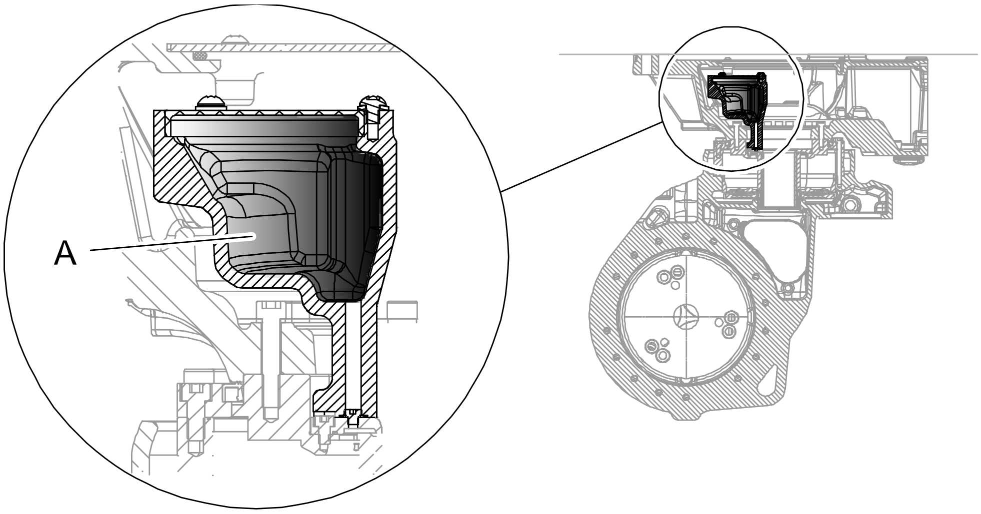


xx0900000129

A	Expansion container

Note

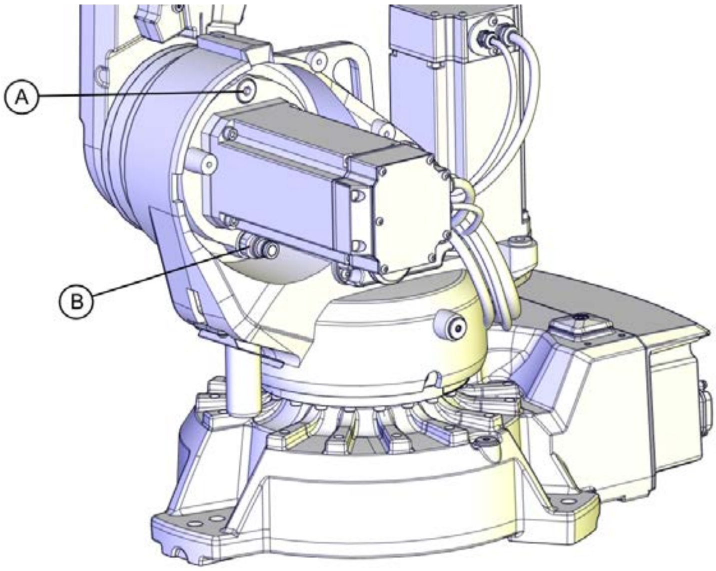
The expansion container is installed on delivery on the robot if ordered as option suspended/inverted mounted. If a floor mounted robot shall be fitted in a suspended mounted position, an expansion container must be installed. See *Installing an expansion container on page 94*.

3.4.4 Changing the oil, axis-2 gearbox

Location of oil plugs

The axis-2 gearbox is located in the lower arm rotational center, underneath the motor attachment.

Oil plugs are shown in the figure.



xx0800000305

A	Oil plug, filling (draining when robot is suspended)
B	Oil plug, draining (filling when robot is suspended) (Quick connect fitting)

Note

On a wall-mounted IRB 2600 the oil plugs are rotated into such a position that it is not possible to drain the oil, or fill the correct amount of oil. Therefore it is recommended that the manipulator is being taken down when changing oil.

Required equipment

Equipment	Note
Oil plug sealing washer, gearbox	3HAC029646-001
Lubricating oil	Information about the oil is found in *Technical reference manual - Lubrication in gearboxes*. See *Type and amount of oil in gearboxes on page 148*.
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Nipple (TEMA IF 3820 S06)	To be fitted on a hose, and then used for draining connected to the *quick connect fitting*. See *Location of oil plugs on page 163*.

Continues on next page

Equipment	Note
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Draining, axis-2 gearbox

Use this procedure to drain the gearbox of oil.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Either • connect a nipple to the *quick connect fitting* in the hole for draining or • remove the *quick connect fitting*.	See the figure in: • *Location of oil plugs on page 163*
5	Open the *oil plug, filling*.	See the figure in: • *Location of oil plugs on page 163* **Note** Drainage will be quicker if the oil plug, filling is removed.
6	Drain the gearbox oil using an *oil collecting vessel*.	**Note** Draining is time-consuming. Elapsed time varies depending on the temperature of the oil.

Continues on next page

	Action	Note
7	**WARNING** Used oil is hazardous material and must be disposed of in a safe way. See section *Decommissioning on page 439* for more information.	
8	**Note** There will be some oil left in the gearbox after draining.	
9	Refit *oil plug*. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug sealing washer with a new one. If not there is a risk of leakage.	Tightening torque: • 24 Nm

Filling oil, axis-2 gearbox

Use this procedure to fill the gearbox with oil.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
3	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
4	Open *oil plug, filling*.	See the figure in: • *Location of oil plugs on page 163*

Continues on next page

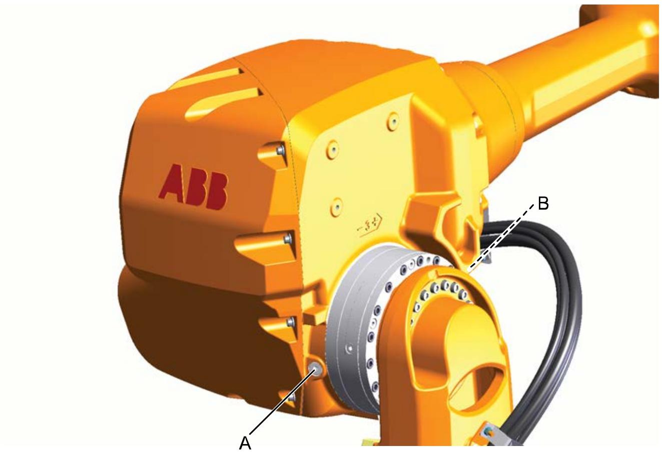
	Action	Note
5	Refill the gearbox with *lubrication oil*. **Note** The amount of oil to be filled depends on the amount previously being drained.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
6	Inspect the oil level.	How to inspect the oil level is described in section: • *Inspecting the oil level, axis 2 gearbox on page 124*
7	Refit *oil plug*. **Note** Before refitting the oil plug in the gearbox, always replace the oil plug sealing washer with a new one. If not there is a risk of leakage.	Tightening torque: • 24 Nm

3.4.5 Changing the oil, axis-3 gearbox

Location of oil plugs

The axis-3 gearbox is located in the upper arm rotational center.

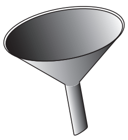
Oil plugs are shown in the figure.



xx0800000306

A	Oil plug, armhouse
B	Oil plug, gearbox (not visible in this figure)

Required equipment

Equipment	Note
Lubricating oil	Information about the oil is found in *Technical reference manual - Lubrication in gearboxes*. See *Type and amount of oil in gearboxes on page 148*.
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Oil dispenser	One example of oil dispenser can be found in section: • *Type of lubrication in gearboxes on page 148*
Funnel	 xx1200000862
Standard toolkit	Content is defined in section *Standard tools on page 456*.

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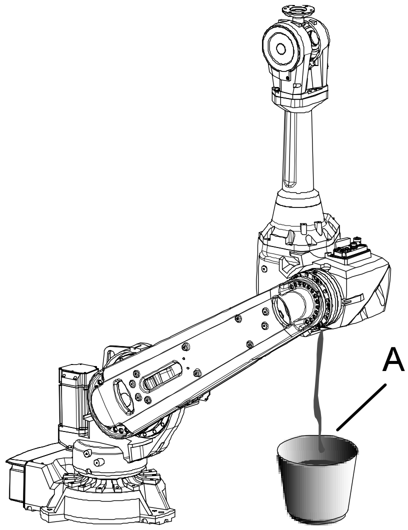
Draining, axis-3 gearbox

Use this procedure to drain the gearbox of oil.

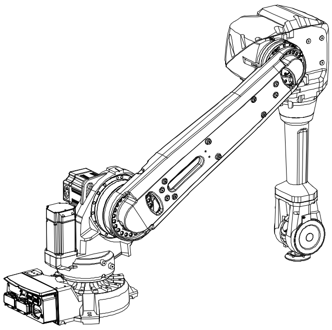
	Action	Note
1	Move the robot to an upright position as shown in the figure.	 xx0800000327 • A: Oil collecting vessel
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
5	Open the *oil plug, armhouse*	See the figure in: • *Location of oil plugs on page 167*
6	Open the *oil plug, gearbox* and use it as a ventilation hole.	See the figure in: • *Location of oil plugs on page 167*

Continues on next page

	Action	Note
7	Drain the gearbox oil using an *oil collecting vessel*.	**Note** Draining is time-consuming. Elapsed time varies depending on the temperature of the oil.
8	**WARNING** Used oil is hazardous material and must be disposed of in a proper way. See section *Decommissioning* for more information.	
9	Refit oil plugs.	Tightening torque: • in armhouse: 10 Nm • in gearbox: 3 Nm

Filling oil, axis-3 gearbox

Use this procedure to fill the gearbox with oil.

	Action	Note
1	Move the upper arm to a position where the wrist is pointing towards the floor as shown in the figure.	 xx0800000329
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	

Continues on next page

	Action	Note
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
5	Open the *oil plug, armhouse*.	See the figure in: • *Location of oil plugs on page 167*
6	Refill the gearbox with *lubricating oil*. **Tip** Use a funnel. **Note** The amount of oil to be filled depends on the amount previously being drained.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
7	Inspect the *oil level*.	How to inspect oil is described in section: • *Inspecting the oil level, axis 3 gearbox on page 127*
8	Refit the *oil plug*.	Tightening torque: • in armhouse: 10 Nm • in gearbox: 3 Nm

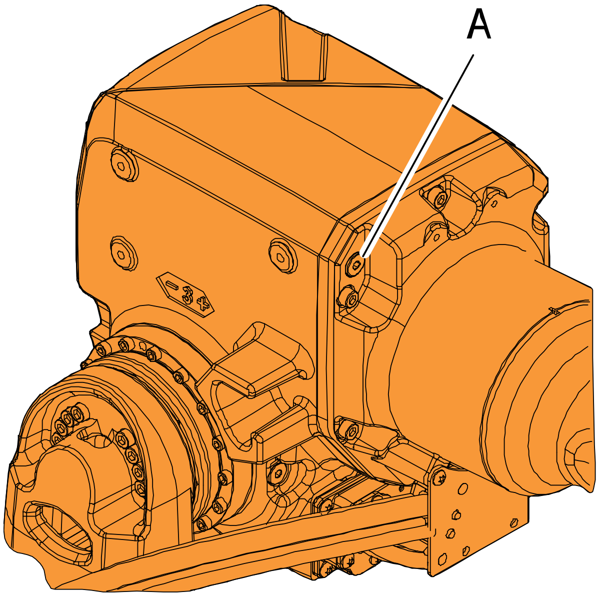
3.4.6 Changing the oil, axis-4 gearbox

Location of oil plugs

The axis-4 gearbox is located in the front of the upper armhouse.

The oil plug is shown in the figure.

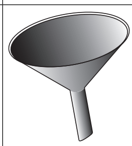
The figure shows IRB 2600 Standard but the position of oil plug is the same on IRB2600ID.



xx0900000311

A	Oil plug, for filling and draining

Required equipment

Equipment	Note
Lubricating oil	Where to find information of the *type of oil*, *article number* and the *amount* in the gearbox, see section *Type of lubrication in gearboxes on page 148*
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Plastic hose	Used for venting the gearbox during draining. A suitable hose would be a hose normally used for compressed air. Length: minimum 300 mm. Diameter: 5 mm.
Funnel	 xx1200000862
Standard toolkit	Content is defined in section *Standard tools on page 456*.

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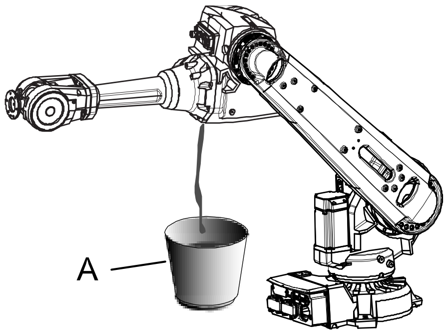
Draining oil

Use this procedure to drain oil from the gearbox.

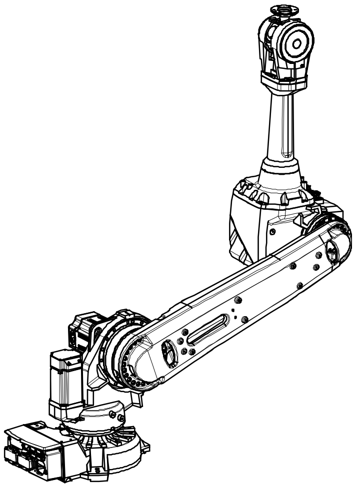
	Action	Note
1	Move the robot to the position shown in the figure.	 xx0800000328 • A: Oil collecting vessel
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	
5	Open *oil plug, draining*.	See the figure in: • *Location of oil plugs on page 171*
6	Drain the gearbox oil using an *oil collecting vessel*. **Tip** Insert a compressed air hose approximately 100 mm into the gearbox, to vent the gearbox. This speeds up the draining significantly.	**Note** Draining is time-consuming. Elapsed time varies depending on the temperature of the oil.

Continues on next page

	Action	Note
7	**WARNING** Used oil is hazardous material and must be disposed of in a safe way. See section *Decommissioning on page 439* for more information.	
8	Refit the oil plug.	Tightening torque: 10 Nm.

Filling oil

Use this procedure to fill oil in the gearbox.

	Action	Note
1	Move the upper arm to the position shown in the figure.	 xx0800000330
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
4	**CAUTION** The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.	

Continues on next page

	Action	Note
5	Open the *oil plug, filling*.	See the figure in: • *Location of oil plugs on page 171*
6	Refill the gearbox with *lubricating oil*. **Tip** Use a funnel. **Note** The amount of oil to be filled depends on the amount previously being drained.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
7	Refit the *oil plug*.	Tightening torque: 10 Nm.

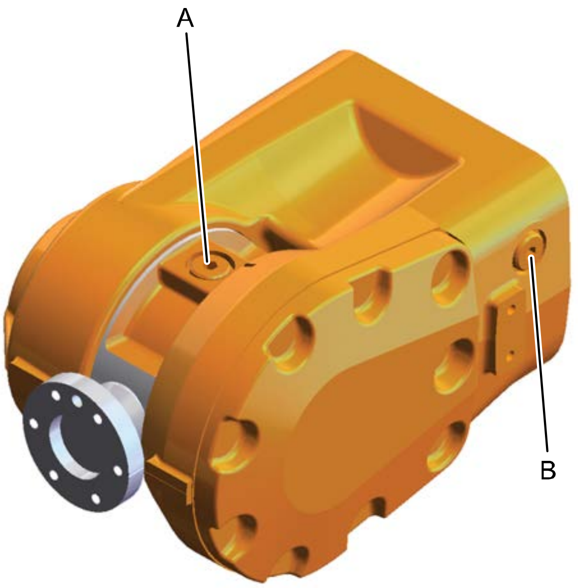
3.4.7 Changing oil, axes-5 and -6 gearboxes

Location of oil plugs

The axes-5 and -6 gearboxes are located in the wrist unit.

The oil plug is shown in the figure.

The figure shows wrist variant 12/20 kg



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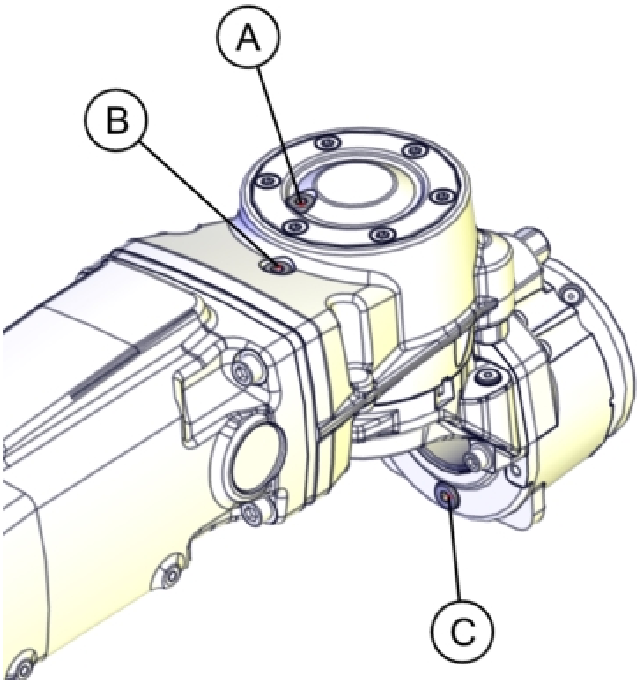
A	Oil plug, tilthouse
B	Oil plug, wrist (also used as air inlet when draining from oil plug A)

Continues on next page

Wrist IRB 2600ID shown in position for filling.



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A	Oil plug, filling
B	Oil plug, draining
C	Oil plug, venting

Note

The gearboxes for axes-5 and -6 are the same.

Required equipment

Equipment	Note
Lubrication oil	Where to find information of the *type of oil*, *article number* and the *amount* in the gearbox, see section: *Type of lubrication in gearboxes on page 148*
Oil collecting vessel	The capacity of the vessel must be sufficient to take the complete amount of oil.
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Draining axes-5 and -6 gearbox - wrist 12/20 kg

Use this procedure to drain oil from the gearbox.

Continues on next page

CAUTION

The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.

	Action	Note
1	Move the upper arm to a horizontal position.	
2	IRB 2600: Turn axis-4 to the calibration position. IRB 2600ID: Turn axis-4 +90° so that the oil plug for filling is on top.	See the figure in *Location of oil plugs on page 175*.
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
5	Remove the *oil plugs* in the wrist. IRB 2600ID: The oil plug, venting can stay seated until the wrist is rotated.	See the figure in *Location of oil plugs on page 175*.
6	Turn axis-4 through so that the oil plug on the side of the wrist points downwards. IRB 2600ID: Open the oil plug, venting.	
7	IRB 2600: Then turn axis-4 another 90°.	
8	IRB 2600: Let the remaining oil run out through the oil plug hole, tilthouse.	

Filling oil axes-5 and -6 gearbox - wrist 12/20 kg

Use this procedure to fill oil in the gearbox.

CAUTION

The gearbox can contain an *excess of pressure* that can be hazardous. Open the oil plug carefully in order to let out the excess pressure.

Continues on next page

	Action	Note
1	Run the upper arm to a horizontal position.	
2	IRB 2600: Turn axis-4 to the calibration position. IRB 2600ID: Turn axis-4 to +90° so that the oil plug for filling is on top.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
5	IRB 2600: Open the *oil plug, tilthouse*. IRB 2600ID: Open all oil plugs, also for the venting hole.	See in figure: • *Location of oil plugs on page 175*
6	Refill the gearbox with *lubrication oil*. **Note** The amount of oil to be filled depends on the amount previously being drained. IRB 2600ID: The venting hole at the bottom needs to be open to make the oil run into the axis-6 gear. If oil starts to run out through the venting hole, refit the oil plug. If it is difficult to get oil into the axis-6 gear, the venting hole can also be used for filling oil into the gear.	Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
7	Inspect the oil level.	How to inspect the oil level is described in section: • *Inspecting oil level, gearbox axes 5 - 6 on page 131*
8	**Note** If the robot is fitted in a suspended position, the wrist should be turned 180°.	
9	Refit the oil plugs.	Tightening torque: • IRB 2600: 10 Nm IRB 2600ID: 3 Nm

3.4.8 Replacing SMB battery

Note

The battery low alert (38213 **Battery charge low**) is displayed when the battery needs to be replaced. The recommendation to avoid an unsynchronized robot is to keep the power to the controller turned on until the battery is to be replaced.

For an SMB board with 3-pole battery contact (RMU101 3HAC044168-001 or RMU102 3HAC043904-001), the lifetime of a new battery is typically 36 months.

For an SMB board with 2-pole battery contact, the typical lifetime of a new battery is 36 months if the robot is powered off 2 days/week or 18 months if the robot is powered off 16 h/day. The lifetime can be extended for longer production breaks with a battery shutdown service routine. See *Operating manual - IRC5 with FlexPendant* or *Operating manual - OmniCore* for instructions.

WARNING

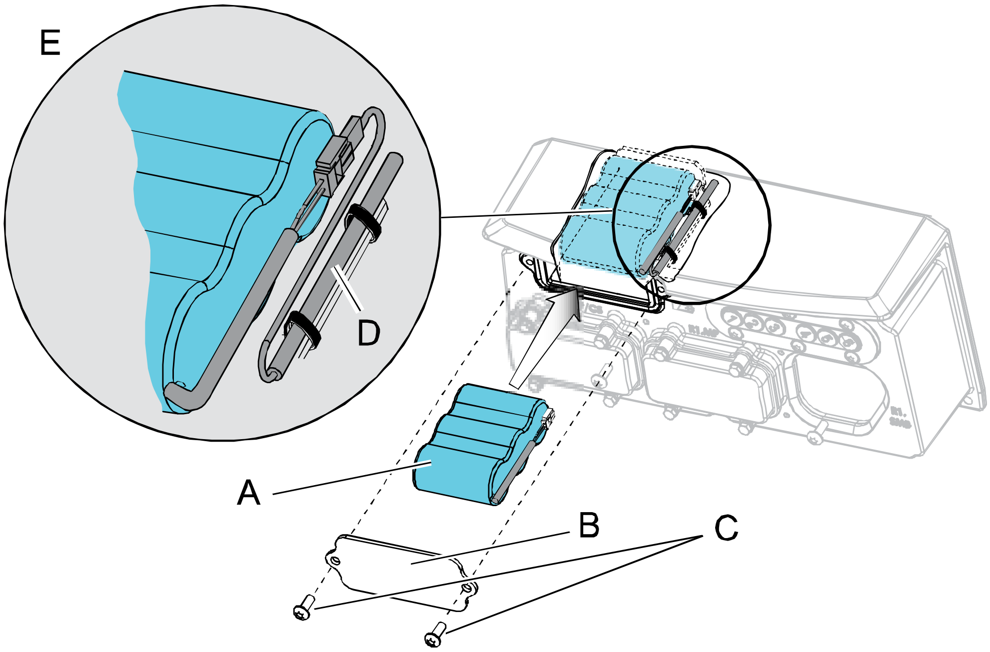
See *Hazards related to batteries on page 38*.

Location of SMB battery

The SMB battery is located at the base of the robot, as shown in the figure.

Continues on next page

DSQC 633A



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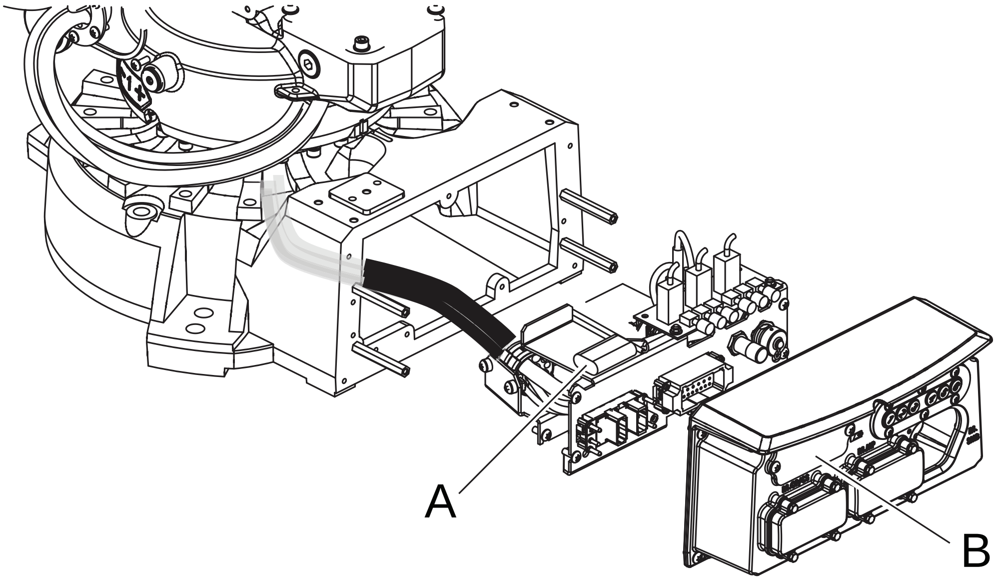
A	SMB battery (2-pole battery contact)
B	Battery cover
C	Attachment screws
D	SMB battery cable
E	How to arrange the battery cable

Continues on next page

RMU 101



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A	SMB battery (3-pole battery contact)
B	Battery cover

Required equipment

Note

There are two variants of SMB units and batteries. One with 2-pole battery contact and one with 3-pole battery contact. The variant with the 3-pole battery contact has longer lifetime for the battery.

It is important that the SMB unit uses the correct battery. Make sure to order the correct spare parts. Do not replace the battery contact!

Equipment	Note
SMB battery pack	Battery includes protection circuits. Replace it only with given spare part no. or an ABB approved equivalent. See *Spare part lists on page 461*.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Circuit diagram	See chapter *Circuit diagram on page 463*.

Removing SMB battery

Use this procedure to remove the SMB battery.

	Action	Note
1	Move the robot to its calibration position.	This is done in order to facilitate the updating of the revolution counter.

Continues on next page

	Action	Note
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	**ELECTROSTATIC DISCHARGE (ESD)** The unit is sensitive to ESD. Before handling the unit please read the safety information in the section *The unit is sensitive to ESD on page 56*	
4	Remove the *SMB battery cover*. **CAUTION** Clean cover from metal residues before opening. Metal residues can cause shortage on the boards which can result in hazardous failures.	See the figure in *Location of SMB battery on page 179*.
5	Pull out the *SMB battery*.	See the figure in *Location of SMB battery on page 179*.
6	Disconnect the *battery cable* and remove the battery.	See the figure in *Location of SMB battery on page 179*.
7	How to dispose of the used SMB battery, see chapter *Decommissioning on page 439*.	

Refitting SMB battery

Use this procedure to refit the SMB battery.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**ELECTROSTATIC DISCHARGE (ESD)** The unit is sensitive to ESD. Before handling the unit please read the safety information in the section *The unit is sensitive to ESD on page 56*	
3	Reconnect the *battery cable* to the *SMB battery*.	See the figure in *Location of SMB battery on page 179*.

Continues on next page

	Action	Note
4	Put the battery unit into its recess while arranging the SMB cables as shown in the figure.	See the figure in *Location of SMB battery on page 179*.
5	Secure the *SMB cover* with its *attachment screws*.	See the figure in *Location of SMB battery on page 179*.
6	Update the revolution counter.	Detailed in *Updating revolution counters on IRC5 robots on page 408*.
7	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

3.5 Cleaning

3.5.1 Cleaning the IRB 2600/IRB 2600 ID

DANGER

Turn off all:

- electric power supply
- hydraulic pressure supply
- air pressure supply

to the robot, before entering the safeguarded space.

General

To secure high uptime it is important that the IRB 2600/IRB 2600 ID is cleaned regularly. The frequency of cleaning depends on the environment in which the product works.

Different cleaning methods are allowed depending on the type of protection of the IRB 2600/IRB 2600 ID.

Note

Always verify the protection type of the robot before cleaning.

Oil spills

Oil spills from gearboxes

Use the following procedure if any oil spills are detected that can be suspected to originate from a gearbox.

1. Inspect that the oil level in the suspected gearbox is according to the recommendations, see *Inspection activities on page 119*.
2. Write down the oil level.
3. Inspect the oil level again after, for example, 6 months.
4. If the oil level is decreased then replace the gearbox.

Special cleaning considerations

This section specifies some special considerations when cleaning the robot.

- Always use cleaning equipment as specified. Any other cleaning equipment may shorten the life of the robot.
- Always check that all protective covers are fitted to the robot before cleaning.
- Never point the water jet at connectors, joints, sealings, or gaskets.
- Do not use compressed air to clean the robot.
- Never use solvents that are not approved by ABB to clean the robot.
- Do not spray from a distance closer than 0.4 m.

Continues on next page

- Do not remove any covers or other protective devices before cleaning the robot.

Cleaning methods

The following table defines what cleaning methods are allowed depending on the protection type.

Note

Rinsing with water is not allowed for a robot with integrated dressing (ID variants).

Protection type	Cleaning method			
	Vacuum cleaner	Wipe with cloth	Rinse with water[i]	High pressure water or steam
Standard	Yes	Yes. With mild cleaning detergent.	Yes. It is highly recommended that the water contains a rust-prevention solution and that the manipulator is dried afterwards.	No
Foundry Plus	Yes	Yes. With mild cleaning detergent or spirit.	Yes. It is highly recommended that the water contains a rust-prevention solution.	Yes[ii]. It is highly recommended that the water and steam contains rust preventive, without cleaning detergents.

i Rinsing with water is not allowed for a robot with integrated dressing (ID variants)!
ii Perform according to section *Cleaning with water and steam on page 185*.

Cleaning with water and steam

Instructions for rinsing with water

ABB robots with protection types *Standard*, *Foundry Plus*, *Wash*, or *Foundry Prime* can be cleaned by rinsing with water (water cleaner), provided that the robot is not equipped with the option of motor cooling fans.[1 2]

The following list defines the prerequisites:

- Maximum water pressure at the nozzle: 700 kN/m^2 (7 bar) [I]
- Fan jet nozzle should be used, min. 45° spread
- Minimum distance from nozzle to encapsulation: 0.4 meters
- Maximum flow: 20 liters/min [I]

1 See *Cleaning methods on page 185* for exceptions.
2 If the robot is equipped with a sleeve, do not open Axis 2 and 3 before rinsing, as this will damage the sealing ring.

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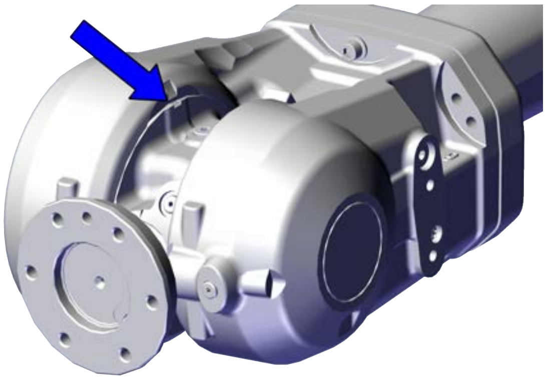
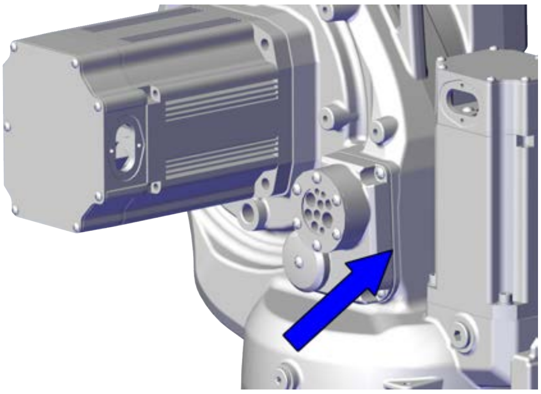
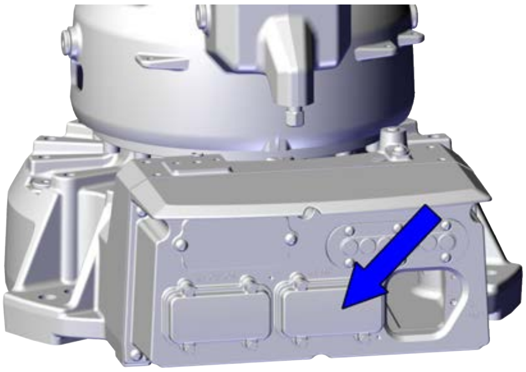
- Never point the nozzle at the following positions (example images):

Position	Example of position
Rotational sealings	 xx2300001604
Gaskets	 xx2300001605
Connectors	 xx2300001606

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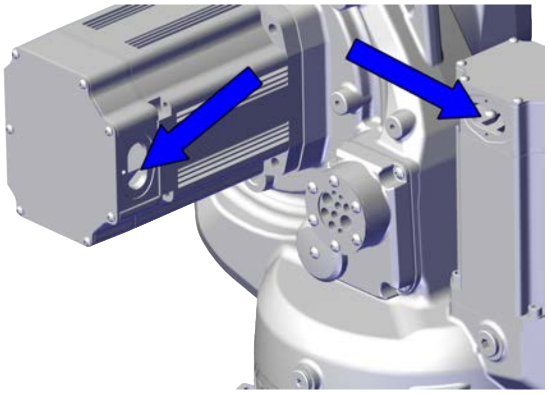
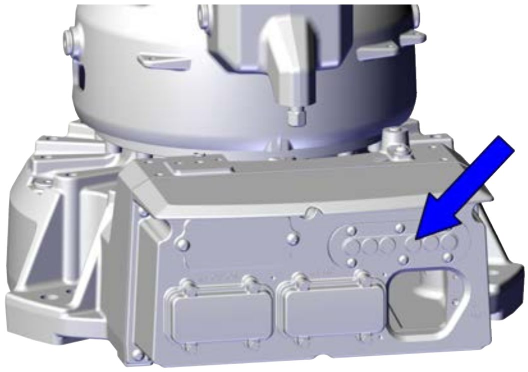
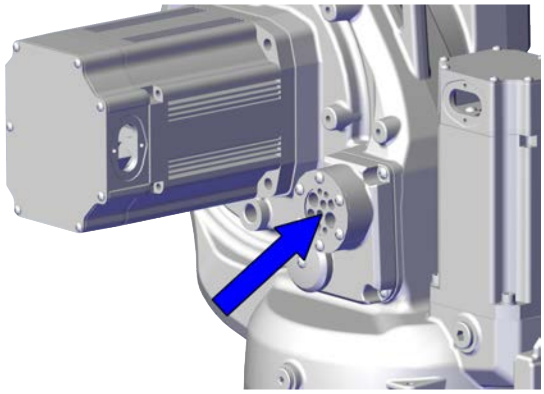
Position	Example of position
Cable inlets	 xx2300001607
Brake release buttons	 xx2300001608
Press relief valve	 xx2300001609

1 Typical tap water pressure and flow

Instructions for steam or high pressure water cleaning

ABB robots with protection types *Foundry Plus*, *Wash*, or *Foundry Prime* can be cleaned using a steam cleaner or high pressure water cleaner.[3]

The following list defines the prerequisites:

- Maximum water pressure at the nozzle: 2500 kN/m^2 (25 bar)
- Fan jet nozzle should be used, min. 45° spread
- Minimum distance from nozzle to encapsulation: 0.4 meters

3 See *Cleaning methods on page 185* for exceptions.

Continues on next page

- Maximum water temperature: 80° C

Cables

Movable cables need to be able to move freely:

- Remove waste material, such as sand, dust and chips, if it prevents cable movement.
- Clean the cables if they have a crusty surface, for example from dry release agents.

Cooling fans

Inspect the air supply inlet of the the motor cooling fans. Clean to remove any contamination that could hinder the air supply.

4 Repair

4.1 Introduction

Structure of this chapter

This chapter describes repair activities for the IRB 2600/IRB 2600 ID. Each procedure contains the information required to perform the activity, for example spare parts numbers, required special tools, and materials.

WARNING

Repair activities not described in this chapter must only be carried out by ABB.

Report replaced units

Note

When replacing a part on the IRB 2600/IRB 2600 ID, report to your local ABB the serial number, the article number, and the revision of both the replaced unit and the replacement unit.

This is particularly important for safety equipment to maintain the safety integrity of the installation.

Safety information

Make sure to read through the chapter *Safety on page 21* before commencing any service work.

Note

If the IRB 2600/IRB 2600 ID is connected to power, always make sure that the IRB 2600/IRB 2600 ID is connected to protective earth and a residual current device (RCD) before starting any repair work.

For more information see:

-
- *Product manual - OmniCore V250XT Type A*
- *Product manual - IRC5*
- *Product manual - IRC5 Panel Mounted Controller*

4.2 General procedures

4.2.1 Performing a leak-down test

When to perform a leak-down test

After refitting any motor and gearbox, the integrity of all seals enclosing the gearbox oil must be tested. This is done in a leak-down test.

The gearbox must be drained of oil before performing the leak-down test.

Required equipment

Equipment, etc.	Article number	Note
Leak-down tester	-	
Leak detection spray	-	

Performing a leak-down test

	Action	Note
1	Finish the refitting procedure of the motor or gear in question, but **do not** refill the gearbox with oil before performing the leak-down test.	
2	Remove the upper oil plug on the gear and replace it with the leak-down tester. Regulators, which are included in the leak-down test, may be required.	
3	Use caution, apply compressed air and raise the pressure with the knob until the correct value is shown on the manometer. **CAUTION** The pressure must under no circumstance be higher than 0.25 bar (20-25 kPa). Also during the time when the pressure is raised.	Correct value: 0.2-0.25 bar (20-25 kPa)
4	Disconnect the compressed air supply.	
5	Wait for approximately 8-10 minutes and make sure that no pressure loss occurs.	If the compressed air is significantly colder or warmer than the gearbox to be tested, a slight pressure increase or decrease may occur. This is quite normal.
6	If any pressure drop occurred, then localize the leak as described in step *7*. If no pressure drop occurred, then remove the leak-down tester and refit the oil plug. The test is complete.	
7	Spray any suspected leak areas with the leak detection spray. Bubbles indicate a leak.	
8	When the leak has been localized, take the necessary measures to correct the leak.	

4.2.2 Mounting instructions for bearings

General

This section describes how to mount and grease different types of bearings on the robot.

Equipment

Equipment, etc.	Article number	Note
Grease	3HAC042536-001	Shell Gadus S2 Used to grease the bearings, if not specified otherwise.

Assembly of all bearings

Attend to the following instructions while mounting a bearing on the robot.

	Action	Note
1	To avoid contamination, let a new bearing remain in its wrapping until it is time for fitting.	
2	Ensure that the parts included in the bearing fitting are free from burrs, grinding waste, and other contamination. Cast components must be free of foundry sand.	
3	Bearing rings, inner rings, and roller elements must not be subjected to direct impact. The roller elements must not be exposed to any stresses during the assembly work.	

Assembly of tapered bearings

Follow the preceding instructions for the assembly of the bearings when mounting a tapered bearing on the robot.

In addition to those instructions, the following procedure must be carried out to enable the roller elements to adjust to the correct position against the race flange.

	Action	Note
1	Tension the bearing gradually until the recommended pre-tension is achieved. **Note** The roller elements must be rotated a specified number of turns before pre-tensioning is carried out and also rotated during the pre-tensioning sequence.	
2	Make sure the bearing is properly aligned as this will directly affect the durability of the bearing.	

Greasing of bearings

Note

This instruction is not valid for solid oil bearings.

Continues on next page

The bearings must be greased after assembly according to the following instructions:

- The bearings must not be completely filled with grease. However, if space is available beside the bearing fitting, the bearing may be totally filled with grease when mounted, as excessive grease will be pressed out from the bearing when the robot is started.
- During operation, the bearing should be filled to 70-80% of the available volume.
- Ensure that grease is handled and stored properly to avoid contamination.

Grease the different types of bearings as following description:

- *Grooved ball bearings* must be filled with grease from both sides.
- *Tapered roller bearings* and axial needle bearings must be greased in the split condition.

4.2.3 Mounting instructions for sealings

General

This section describes how to mount different types of sealings.

Equipment

Consumable	Article number	Note
Grease	3HAC042536-001	Shell Gadus S2

Rotating sealings

The following procedures describe how to fit rotating sealings.

CAUTION

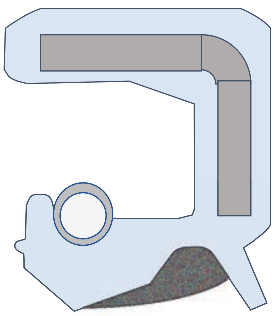
Please observe the following before commencing any assembly of sealings:

- Protect the sealing during transport and mounting, especially the main lip on radial sealings.
- Keep the sealing in its original wrappings or protect it well before actual mounting.
- The fitting of sealings and gears must be carried out on clean workbenches.
- Use a protective sleeve for the main lip during mounting, when sliding over threads, keyways or other sharp edges.
- Do not lubricate a static side of a sealing with grease, since this may result in movement of the sealing during operation.

  The only exception for lubrication of static sides of a sealing, is to use P-80 rubber lubrication gel against certain aluminium surfaces. If usage of P-80 is relevant, it is stated in the repair procedures.

Radial sealings

A radial sealing consists of a flexible rubber lip bonded to a rigid metal case. Only one side of the sealing is static with a metal insert.



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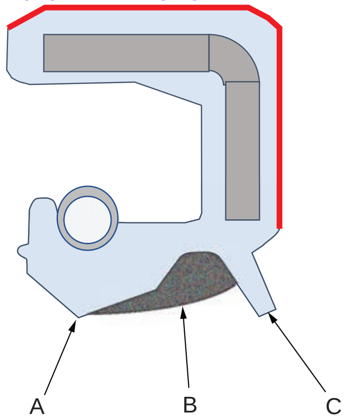
	Action	Note
1	Check the sealing to ensure that: • The sealing is of the correct type. • There is no damage on the main lip.	
2	Inspect the shaft surface before mounting. If scratches or damage are found, the shaft must be replaced since it may result in future leakage. Do not try to grind or polish the shaft surface to get rid of the defect.	
3	Lubricate the sealing with grease just before fitting. (Not too early - there is a risk of dirt and foreign particles adhering to the sealing.) Fill 2/3 of the space between the dust lip and the main lip with grease. If the sealing is without dust lip, just lubricate the main lip with a thin layer of grease.	Article number is specified in *Equipment on page 193*.  xx2000000071 A Main lip B Grease C Dust lip **Note** Ensure that no grease is applied to the red marked surface.

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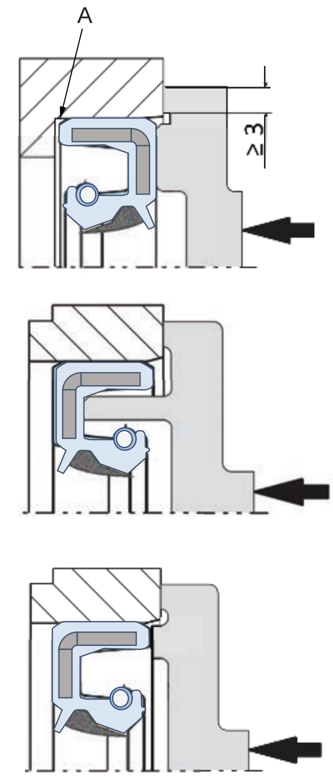
	Action	Note
4	Mount the sealing correctly with a mounting tool. Never hammer directly on the sealing as this may result in leakage.	 xx2000000072 A Gap

Flange sealings and static sealings

The following procedure describes how to fit flange sealings and static sealings.

	Action
1	Check the flange surfaces. They must be even and free from pores. It is easy to check flatness using a gauge on the fastened joint (without sealing compound). If the flange surfaces are defective, the parts may not be used because leakage could occur.
2	Clean the surfaces properly in accordance with the recommendations of ABB.
3	Distribute the sealing compound evenly over the surface.
4	Tighten the screws evenly when fastening the flange joint.

O-rings

The following procedure describes how to fit o-rings.

	Action	Note
1	Ensure that the correct o-ring size is used.	
2	Check the o-ring for surface defects, burrs, shape accuracy, or deformation.	Defective o-rings, including damaged or deformed o-rings, may not be used.

Continues on next page

	Action	Note
3	Check the o-ring grooves and mating surfaces. They should be free of pores, contamination and obvious scratches/damage.	
4	Lubricate the o-ring with grease.	
5	Tighten the screws evenly while assembling.	
6	Check that the o-ring is not squashed outside the o-ring groove.	

4.2.4 Cut the paint or surface on the robot before replacing parts

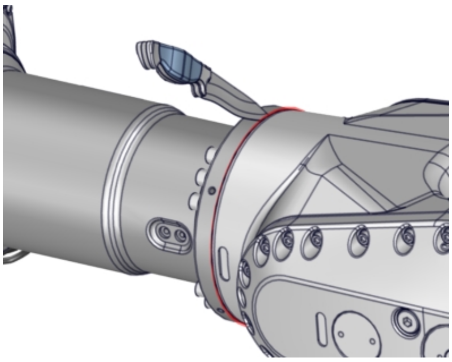
General

Follow the procedures in this section whenever breaking the paint of the robot during replacement of parts.

Required equipment

Equipment	Spare parts	Note
Cleaning agent		Ethanol
Knife		
Lint free cloth		
Touch up paint Standard/Foundry Plus	3HAC067974-001	Graphite White
Touch up paint Standard/Foundry Plus	3HAC037052-001	ABB Orange

Removing

	Action	Description
1	Cut the paint with a knife in the joint between the part that will be removed and the structure, to avoid that the paint cracks.	 xx2300000950
2	Carefully grind the paint edge that is left on the structure to a smooth surface.	

4.2.5 The brake release buttons may be jammed after service work

Description

The brake release unit has push-buttons for the brake release of each axis motor. When service work is performed inside the SMB recess that includes removal and refitting of the brake release unit, the brake release buttons may be jammed after refitting.

DANGER

If the power is turned on while a brake release button is jammed in depressed position, the affected motor brake is released. This may cause serious personal injuries and damage to the robot.

Elimination

To eliminate the danger after service work has been performed inside the SMB recess, follow the procedure below.

	Action
1	Make sure the power is turned off.
2	Remove the push-button guard, if necessary.
3	Verify that the push-buttons of the brake release unit are working by pressing them down, one by one. Make sure none of the buttons are jammed in the tube.
4	If a button gets jammed in the depressed position, the alignment of the brake release unit must be adjusted so that the buttons can move freely in their tubes.

4.3 Complete robot

4.3.1 Removing the complete cable harness

Introduction

This procedure describes how to remove the cable harness on the different variants of IRB 2600:

- IRB 2600 Standard: Axes 1, 2, 3, 4, 5 and 6
- IRB 2600ID: Axes 1, 2, 3 and 4. How to remove the cable harness on axes 5 and 6 is described in section *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*.

How to refit the cable harness is described in section *Refitting the complete cable harness on page 212*.

The removal procedure is presented in the order the work is recommended to be performed. Therefore the order is different in the two procedures removal and refitting of the cable harness. Cross references will make it easy to find what is needed to know as the work continues.

The section *Removing the complete cable harness* consists of the following parts presented in the order the work is recommended to be performed:

- Removal in the *base* *Removing cable harness in base on page 202*
- Removal in the *frame* *Removing cable harness in frame on page 207*
- Removal in *lower arm* and *armhouse* *Removing cable harness in lower arm and armhouse on page 208*.

How to replace the SMB unit, brake release unit and motors can be found in:

- SMB unit *Removing the SMB unit on page 241*
- Brake release unit *Removing the brake release board on page 247*
- Motors *Removing motors on page 308*

Location of the cable harness

The location of the cable harness in the base, frame and lower arm is shown in the figures.

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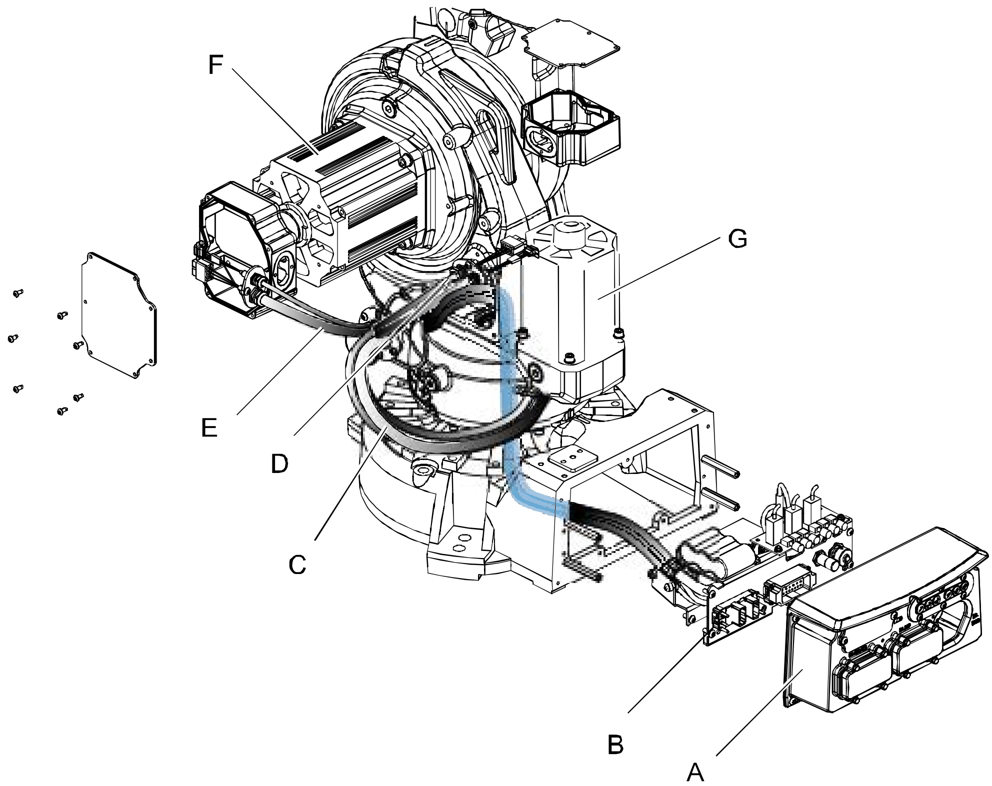
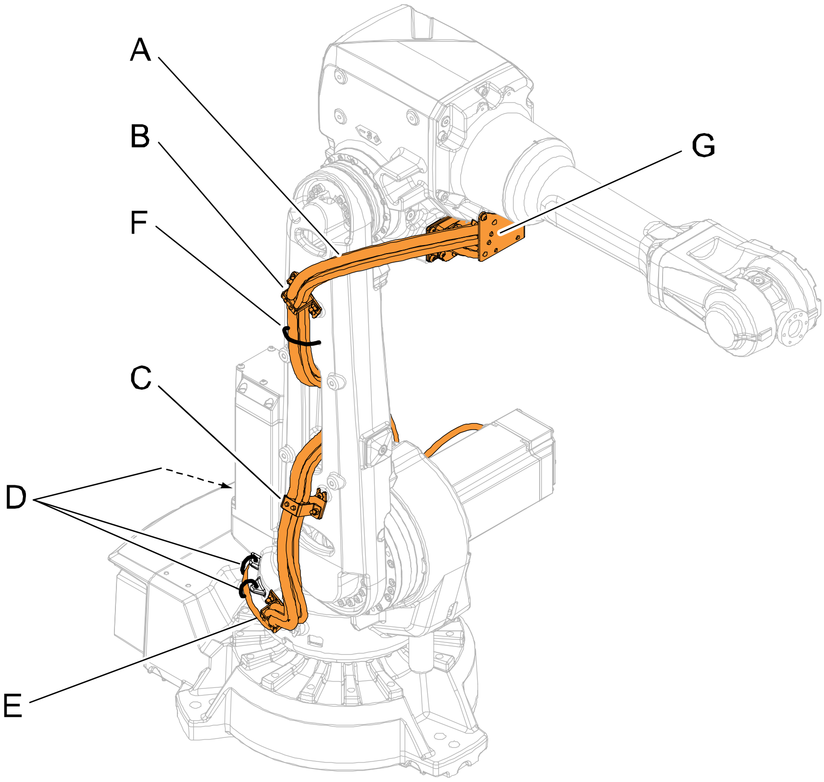
Cable harness, base and frame.



xx0900000009

A	Cover base
B	Bracket
C	Cable harness
D	Axis-1 motor cable
E	Axis-2 motor cable
F	Axis-2 motor
G	Axis-1 motor

Continues on next page



xx0900000384

A	Cable harness
B	Bracket, lower arm
C	Bracket, lower arm
D	Cable straps, one not visible here (steel)
E	Bracket, frame
F	Cable strap, lower arm (plastic)
G	Bracket, upper arm

Required equipment

Equipment	Note
Deep well hexagon socket	Width 30 mm
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Continues on next page

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

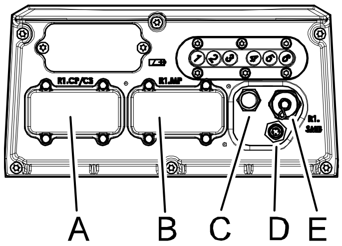
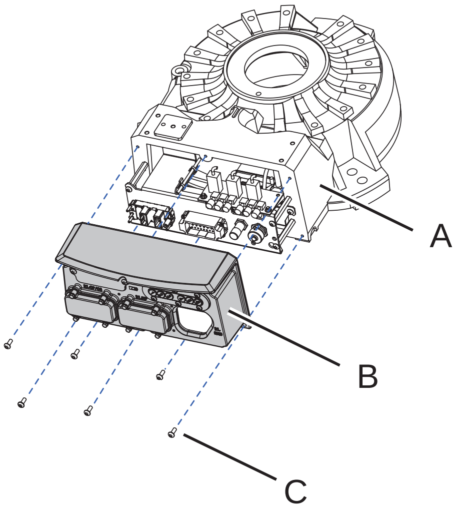
	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing cable harness in base

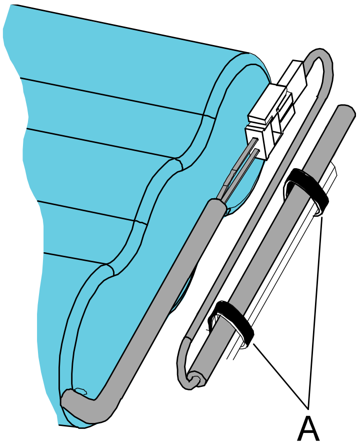
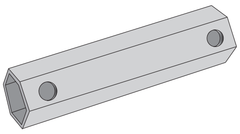
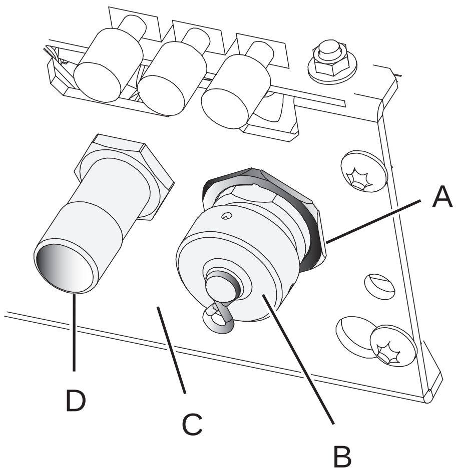
Use this procedure to remove the cable harness in the base.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

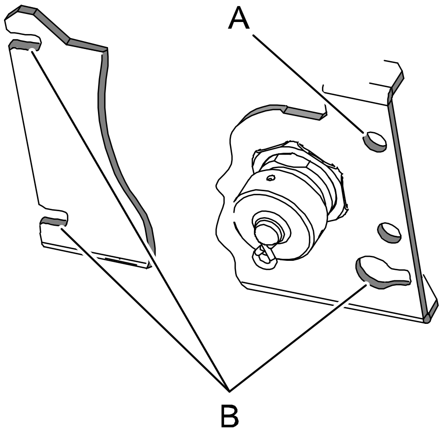
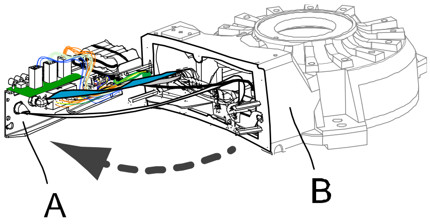
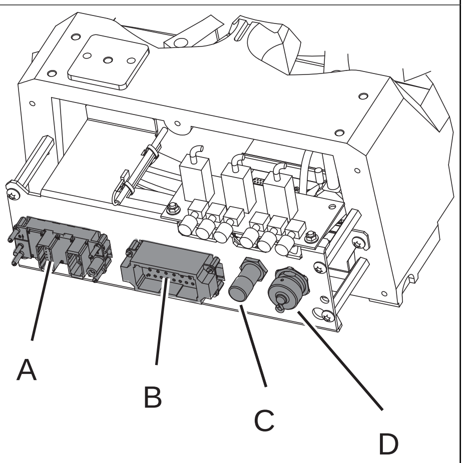
Continues on next page

	Action	Note
3	Disconnect the following connectors on the *base cover*: • R1.CP/CS • R1.MP • R1.ETHERNET (if used) **Tip** Do not remove the *R1.SMB-connector* and *air hose connector* at this stage. It will be easier to remove these two when the cover base has been removed.	 xx0900000014 Parts: • A: R1.CP/CS • B: R1.MP • C: Air hose connector • D: Position of R1.ETHERNET (if used) • E: R1.SMB
4	Remove the *cover base*.	 xx0800000456 A Base B Cover base C Attachment screws
5	Disconnect connectors on the brake release unit: • X8 • X9 • X10	

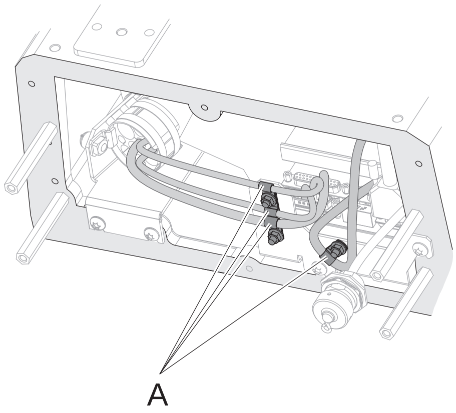
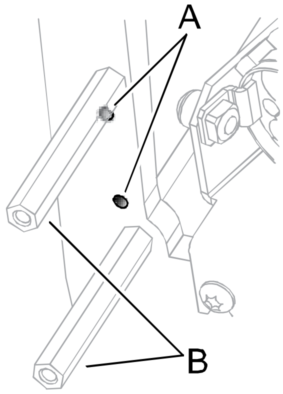
Continues on next page

	Action	Note
6	Cut the *cable straps* securing the battery cable.	 xx0900000099 Parts: • A: Cable straps (2 pcs)
7	Disconnect the battery cable.	
8	Unscrew the thin nut securing the R1.SMB connector on the outside of the bracket. **Tip** Use a deep well hexagon socket, width 30 mm (like the ones used for spark plugs, or similar).  xx1200000888	 xx1200000889 A Thin nut, width 30 mm B R1.SMB C Bracket D Air connector
9	Unscrew the nut for the air connection on the inside of the bracket.	

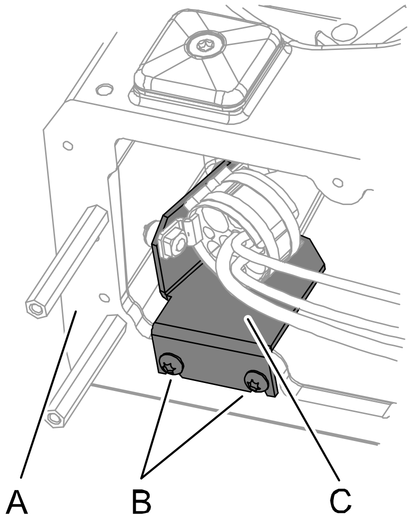
Continues on next page

	Action	Note
10	Remove the screw that secures the bracket and unscrew the three other screws a little just enough to be able to slide the bracket sideways.	 xx0900000100 Parts: • A: Screw to be removed • B: Screws to be unscrewed (3 pcs)
11	Remove the *bracket* by sliding it off the remaining three attachment screws and put it at a 90° angle from the base. Putting the bracket at a 90° angle facilitates the disconnecting of cables from the bracket. **Note** Use caution when performing this procedure in order not to damage cables or other components!	 xx0900000013 Parts: • A: Bracket at a 90° angle • B: Base
12	Remove connectors and air hose connector completely from the *bracket*: • R1.CP/CS • R1.MP • R1.SMB • Air hose connector • R1.ETHERNET (if used)	 xx1200000890 A R1.CP/CS B R1.MP C Air hose connector D R1.SMB
13	Remove the *SMB unit* from its attachment screws. Leave the screws in the base.	How to remove the *SMB unit* is described in section: • *Removing the SMB unit on page 241*

Continues on next page

	Action	Note
14	Disconnect connectors on the SMB unit: • R1.SMB1-2 • R1.SMB2-6 • R2.SMB	
15	Disconnect the *screen connections* of: • R1.SMB1-2 • R1.SMB2-6	 xx0900000035 Parts: • A: Screen connection (4 pcs)
16	Disconnect the *earth cables*.	 xx0900000015 Parts: • A: Earth • B: Distance screws

Continues on next page

	Action	Note
17	Remove the *bracket* securing the cable package inside the base on the left side, by following these steps: • Unscrew the attachment screws just enough to be able to remove the bracket. • Lift the bracket off the screws.	 xx0900000018 Parts: • A: Base • B: Attachment screws • C: Bracket
18	Continue removal of the cable package from the frame.	How to remove the cable package from the frame is described in section • *Removing cable harness in frame on page 207*

Removing cable harness in frame

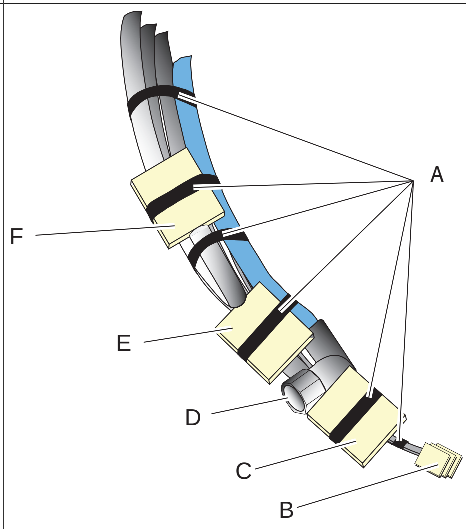
Use this procedure to remove the cable harness in the frame.

Tip

Before starting this procedure, first remove the cable harness in the base. See *Removing the complete cable harness on page 199*.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Disconnect the *motor cables* on the axis-1 and axis-2 motors.	How to remove the motor cables is described in section: • *Removing motors on page 308*
3	Remove the *bracket* securing the cable package to the frame.	See the figure in: • *Location of the cable harness on page 199*

Continues on next page

	Action	Note
4	Cut the *cable straps* securing the cable harness to the frame and lower arm.	See the figure in: • *Location of the cable harness on page 199*
5	Prepare the end of the cable package in the base with tape as shown in the figure. **Tip** In order to protect the connectors from getting residual grease on the cable harness, put some plastic over them prior to pushing it through the hole in the frame.	 xx1200000886 A Tape B Connectors to SMB unit and Brake release unit C R1.CP/CS D Air hose E R1.MP F R1.SMB (Connector bent and taped upwards)
6	Pull out the cable package through the hole in the frame. **Note** Use caution when performing this procedure in order not to damage cables or other components!	
7	Continue the removal of the cable package from the lower arm and armhouse.	How to remove the cable package from the lower arm and armhouse is described in section: • *Removing cable harness in lower arm and armhouse on page 208*

Removing cable harness in lower arm and armhouse

Use this procedure to remove the cable harness in the lower arm and armhouse.

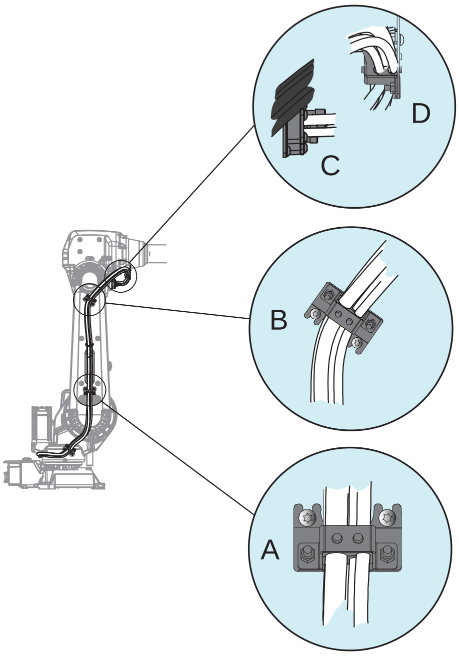
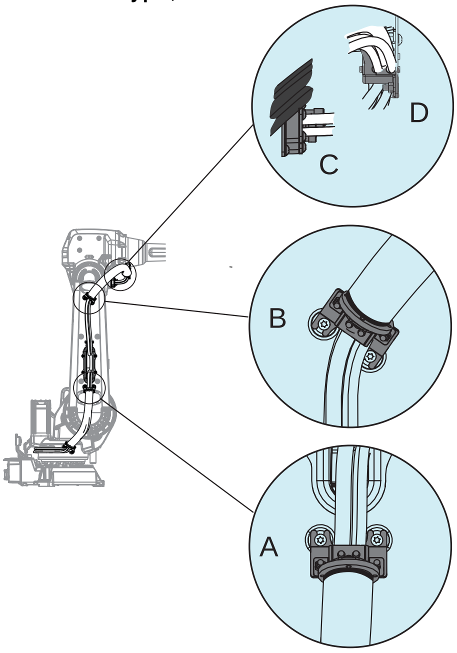
Tip

Before starting this procedure, first remove the cable harness in the base *Removing the complete cable harness on page 199* and frame *Removing the complete cable harness on page 199*.

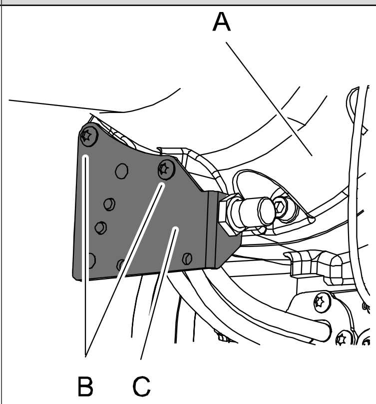
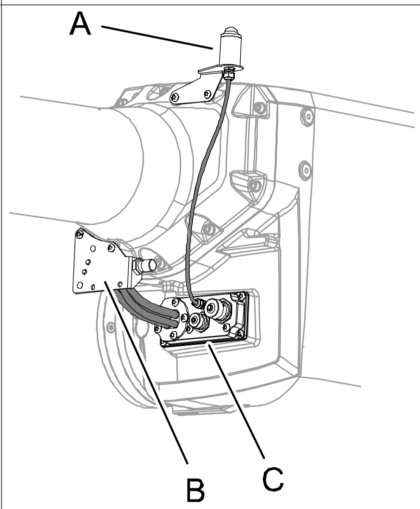
Continues on next page

	Action	Note
1	⚠ **DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Cut the *cable strap* on the lower arm.	See the figure in: • *Location of the cable harness on page 199* (Cable harness, lower arm)

Continues on next page

	Action	Note
3	Remove the *brackets* on the lower arm.	 xx0900000020 Protection type, Clean Room  xx2300001190 Parts: • A: Bracket, lower arm • B: Bracket, lower arm • C: Bracket, armhouse • D: Cable bracket

Continues on next page

	Action	Note
4	Remove the *bracket* on the armhouse.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws • C: Bracket, armhouse
5	Remove the *cable cover* on the armhouse.	 xx0800000338 Parts: • A: Signal lamp • B: Bracket • C: Cable cover, armhouse
6	Remove signal lamp if used.	
7	**IRB 2600 Standard:** Continue the removal of the cable package by disconnecting the motor cables of the axis-3, axis-4, axis-5 and axis-6 motors.	How to remove the *motor cables* from the *axis-3, axis-4, axis-5 and axis-6 motors* see section: • *Removing motors on page 308*
8	**IRB 2600ID:** Continue the removal of the cable package by disconnecting the motor cables of motors axes 3 and 4.	How to remove the motor cables from motors axes 3 and 4 see section: • *Removing motors on page 308*
9	**IRB 2600ID:** Remove the cable package in the upper arm.	See section • *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*

4.3.2 Refitting the complete cable harness

Introduction

This procedure describes how to refit the cable harness on the different variants of IRB 2600:

- IRB 2600 Standard: Axes 1, 2, 3, 4, 4, 5 and 6
- IRB 2600ID: Axes 1, 2, 3 and 4. How to refit the cable harness on axes 5 and 6 is described in section *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*.

How to remove the cable harness is described in *Removing the complete cable harness on page 199*.

The refitting procedure is presented in the order the work is recommended to be performed.

Therefore the order is different in the two procedures removal and refitting of the cable harness. Cross references will make it easy to find what is needed to know as the work continues.

The section *Refitting the complete cable harness* consists of the following parts presented in the order the work is recommended to be performed:

- Refitting in the frame *Refitting the cable harness in the frame on page 215*
- Refitting in the base *Refitting the cable harness in the base on page 218*
- Refitting in the lower arm and armhouse *Refitting the cable harness in the lower arm and armhouse on page 224*.

How to refit the SMB unit, brake release unit and motors can be found in:

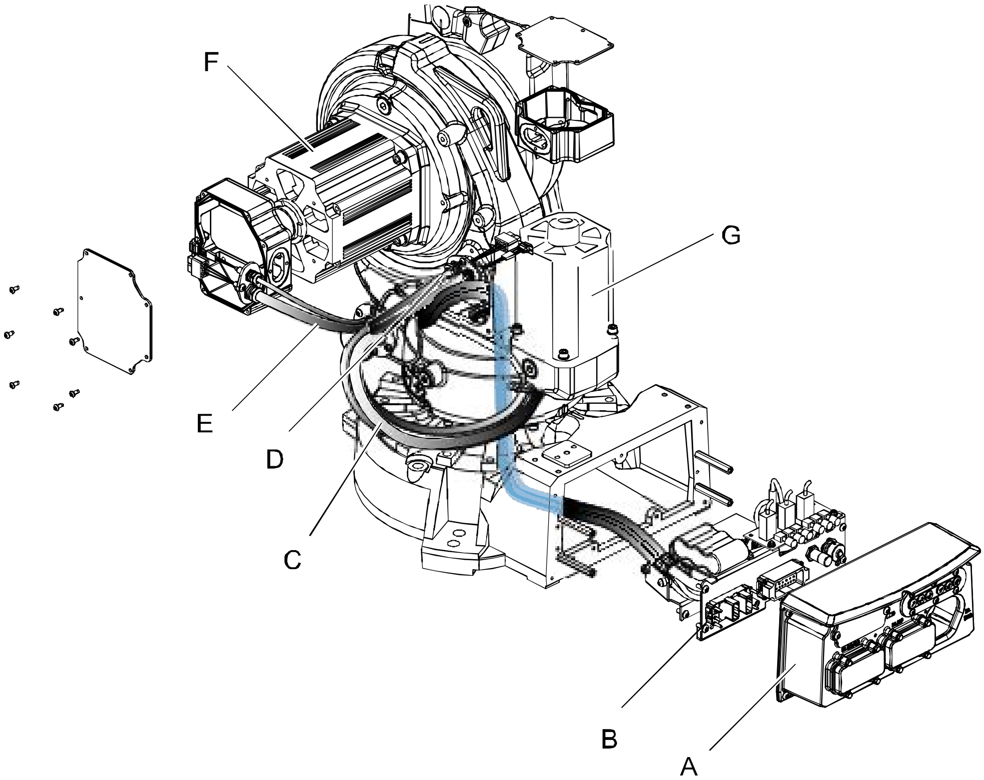
- SMB unit *Refitting the SMB unit on page 244*
- Brake release unit *Refitting the brake release board on page 248*
- Motors *Refitting motors on page 321*

Location of the cable harness

The location of the cable harness in the base, frame and lower arm is shown in the figures.

Continues on next page

Cable harness, base and frame.

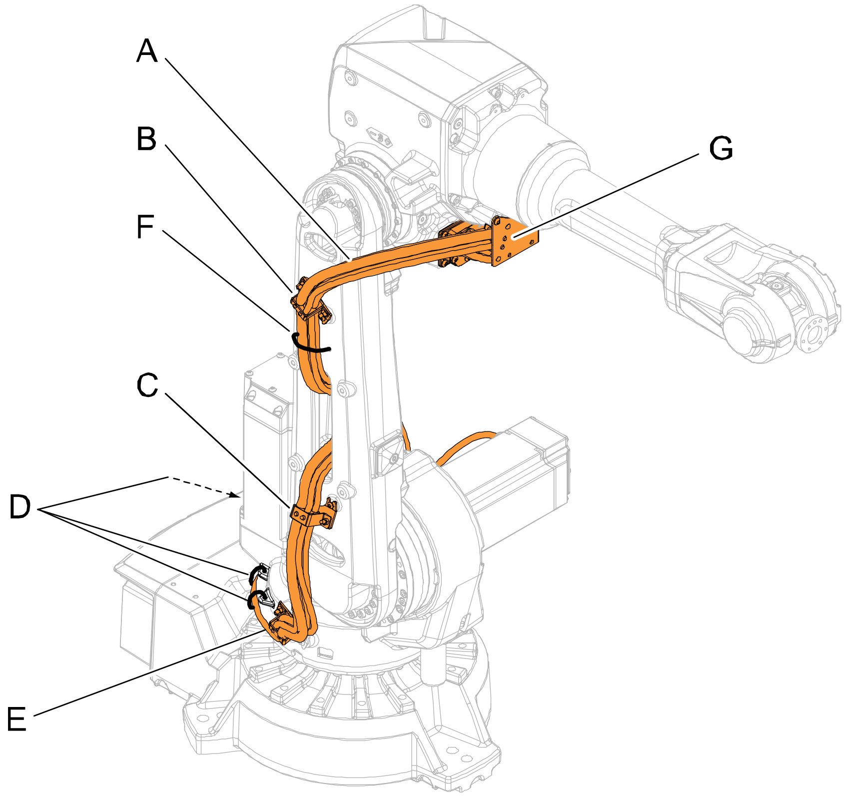


xx0900000009

A	Cover base
B	Bracket
C	Cable harness
D	Axis-1 motor cable
E	Axis-2 motor cable
F	Axis-2 motor
G	Axis-1 motor

Continues on next page

The figure shows IRB 2600 Standard but is also valid for IRB 2600ID.



xx0900000384

A	Cable harness
B	Bracket, lower arm
C	Bracket, lower arm
D	Cable straps, one not visible here (steel)
E	Bracket, frame
F	Cable strap (plastic)
G	Bracket, upper arm

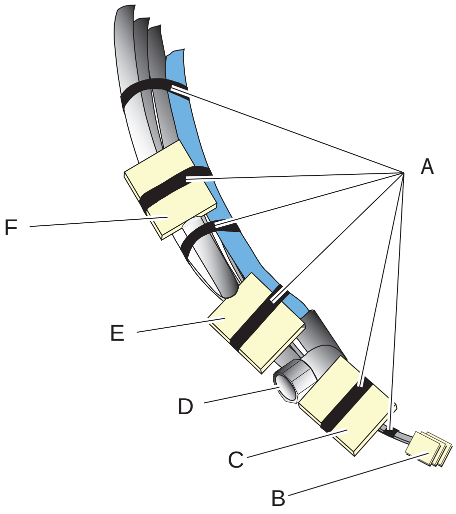
Required equipment

Equipment	Note
Deep well hexagon socket	Width 30 mm
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.
Cable grease	3HAC042536-001 (Shell Gadus S2)

Continues on next page

Refitting the cable harness in the frame

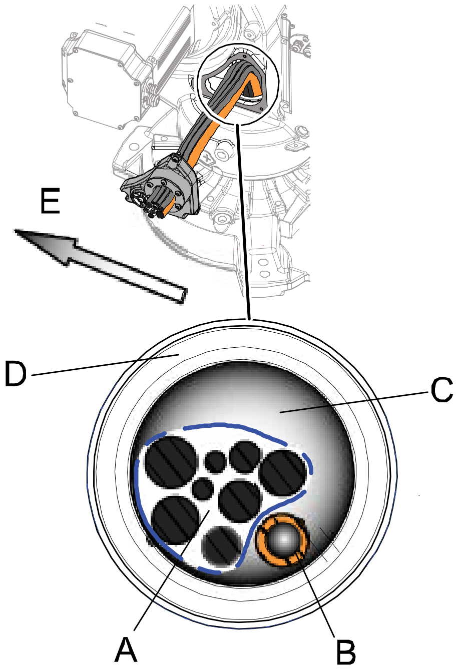
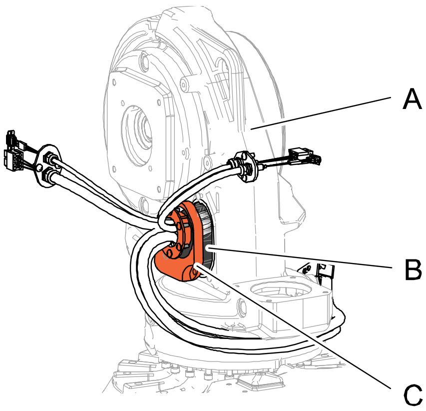
Use this procedure to refit the cable harness in the frame.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Apply **cable grease** on these surfaces: • cable guide inside the hole • the part of the cable harness that runs through the cable guide.	Cable grease is specified in: • *Required equipment on page 214*
3	**Note** Two alternative methods to insert the cable package in frame and base are presented below. Chose one of the methods.	
4	*Use this procedure when replacing the old cable harness:* **Method 1, step 1:** Prepare the end of the cable package in the base with tape as shown in the figure. **Tip** In order to protect the connectors from getting residual grease on the cable harness, put some plastic over them prior to pushing it through the hole in the frame.	 xx1200000886 A Tape B Connectors to SMB unit and Brake release unit C R1.CP/CS D Air hose E R1.MP F R1.SMB (Connector bent and taped upwards)

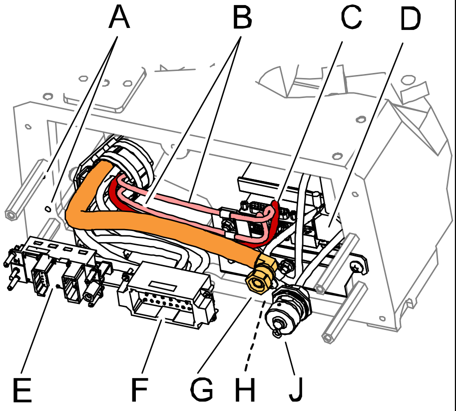
Continues on next page

	Action	Note
5	*Use this procedure when replacing the old cable harness:* **Method 1, step 2:** Push the cable package carefully in through the base and up through the hole in the frame. **Note** Use caution when performing this procedure in order not to damage cables or other components!	
6	*Use this procedure when replacing the old cable harness:* **Method 2:** Push the cable harness carefully into the **hole in the frame** and out of the hole in the base. Perform the procedure in the following order: • R1.MP • R1.CP/CS • R1.SMB1-2 and R1.SMB3-6 • Air hose. **Note** Use caution when performing this procedure in order not to damage cables or other components! **Tip** In order to protect the connectors from getting residual grease on the cable harness, put some plastic over them prior to pushing it through the hole in the frame.	
7	*Use this procedure when fitting a new cable harness:* Without removing the plastic around cables and hose, push the cable harness through the hole in the frame. **Note** Use caution when performing this procedure in order not to damage cables or other components!	**Note** Check that cables and air hose are placed as shown in the figure above.

Continues on next page

	Action	Note
8	**Note** It is vital that the position of the air hose is correct, as shown in the figure!	 xx0900000096 Parts: • A: Cables • B: Air hose • C: Hole in frame • D: Cable guide • E: Position of the front of the robot
9	Secure the *cover* to the frame with its attachment screws.	 xx0900000016 Parts: • A: Frame • B: Hole in frame • C: Cover
10	Connect the axis-1 and axis-2 **motor cables**.	How to refit the motor cables is described in section: • *Refitting motors on page 321*

Continues on next page

	Action	Note
11	Sort out the different cables the way they later will be fit on the bracket in the base.	 xx0900000017 Connections: • A: Earth cables • B: R1.SMB1-2 • C: R1.SMB3-6 • D: R2.SMB • E: R1.CP/CS • F: R1.MP • G: Air hose • H: Position of R1.ETHERNET (if used) • J: R1.SMB
12	Continue the refitting of the cable harness in the base.	How to refit the cable harness in the base is described in section: • *Refitting the cable harness in the base on page 218*

Refitting the cable harness in the base

Use this procedure to refit the cable harness in the base.

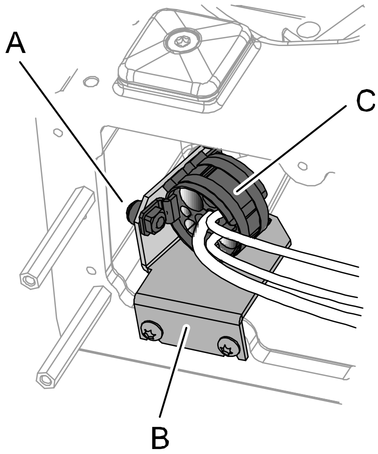
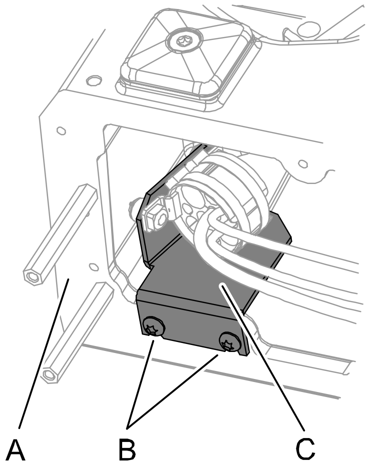
Tip

Before starting this procedure, first refit the cable harness in the *frame*. See:

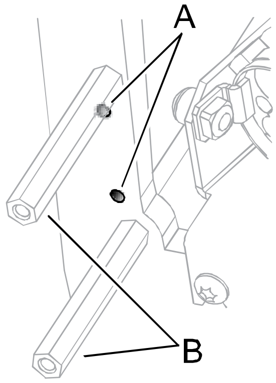
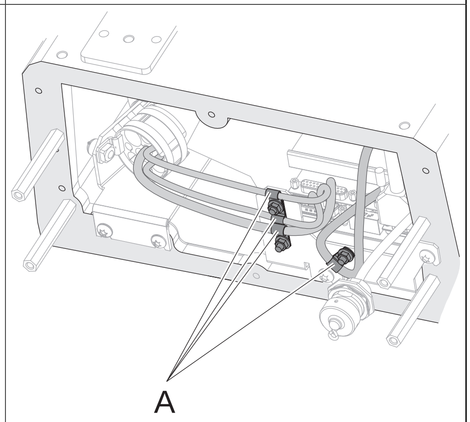
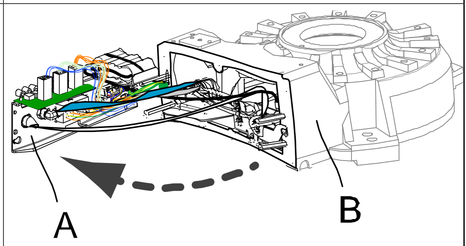
- *Refitting the complete cable harness on page 212*

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the safeguarded space.	

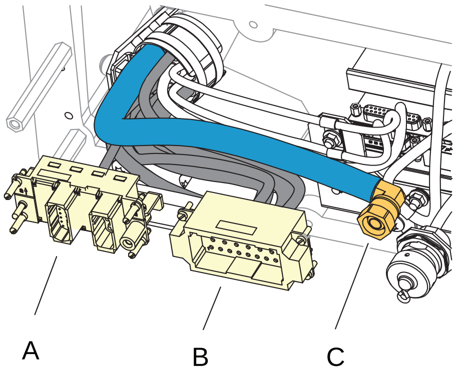
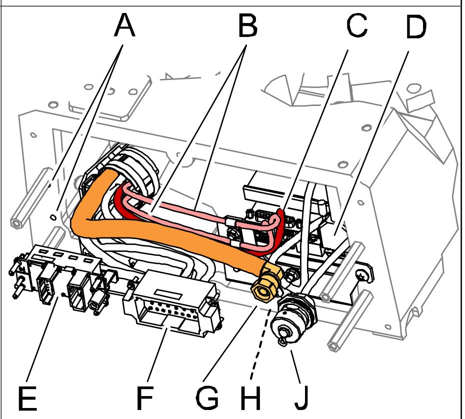
Continues on next page

	Action	Note
2	Attach the *cable harness* to the bracket.	 xx0900000098 Parts: • A: Attachment screw and nut • B: Bracket • C: Cable harness
3	Secure the *bracket* on its *attachment screws* in the base. **Tip** Perform this in the following order: • Put the *attachment screws* in the holes but do not tighten them yet (if they have been removed earlier). • Place the *bracket* on the attachment screws. • Secure the bracket with its attachment screws.	 xx0900000018 Parts: • A: Base • B: Attachment screws (2 pcs) • C: Bracket

Continues on next page

	Action	Note
4	Refit the *earth cables*.	 xx0900000015 Parts: • A: Earth • B: Distance screws
5	Connect the contacts on the SMB unit: • R1.SMB1-2 • R1.SMB3-6 • R2.SMB	
6	Refit the SMB unit.	How to refit the SMB unit is described in section: • Refitting the SMB unit on page 244
7	Refit the cables with the *screen connections*.	 xx0900000035 Parts: • A: Screen connections (4 pcs)
8	**Tip** When refitting connectors on the *bracket*, put it at a 90° angle.	 xx0900000013 Parts: • A: Bracket • B: Base

Continues on next page

	Action	Note
9	Before refitting the connectors on the bracket, arrange cables and connectors as shown in the figure.	 xx1200000857 A R1.CP/CS B R1.MP C Air hose
10	Refit the *connectors* and *air hose* on the bracket: • R1.CP/CS • R1.ETHERNET (if used) • R1.MP **Tip** Do not refit the *R1.SMB-connector* and *air hose* at this stage. It will be easier to refit these two when the bracket has been fitted to the distance screws.	 xx0900000017 Connectors: • A: Earth cables • B: R1.SMB1-2 • C: R1.SMB3-6 • D: R2.SMB • E: R1.CP/CS • F: R1.MP • G: Air hose • H: Position of R1.ETHERNET (if used) • J: R1.SMB

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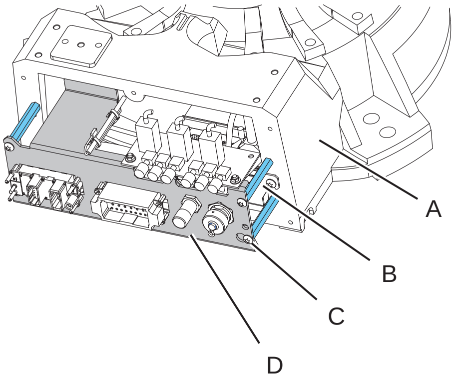
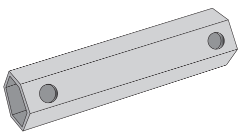
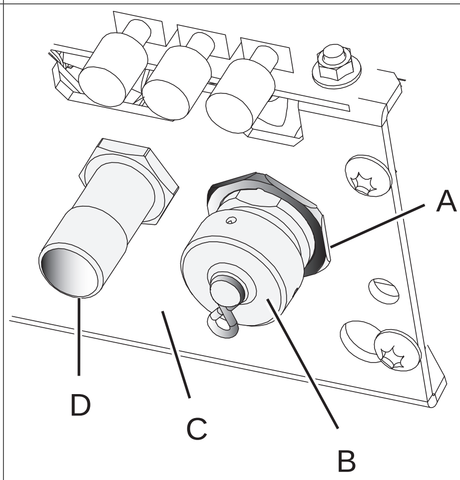
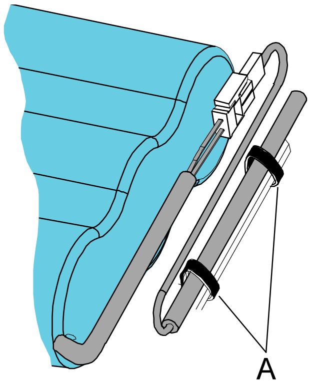
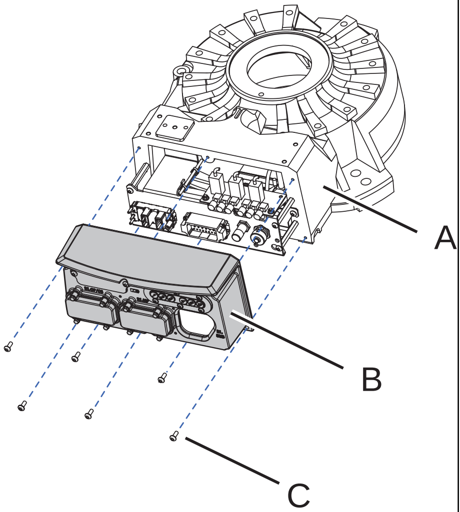
<table>
<tr><th></th><th>Action</th><th>Note</th></tr>
<tr><td>11</td><td>Secure the bracket on the distance screws.</td><td>

xx1200000887
A Base
B Distance screw
C Attachment screw
D Bracket</td></tr>
<tr><td>12</td><td>Reconnect connectors on the brake release unit:
X8
X9
X10</td><td></td></tr>
<tr><td>13</td><td>Refit the R1.SMB-connector on the bracket.
Tip
Use a deep well hexagon socket, width 30 mm (like the ones used for spark plugs, or similar).

xx1200000888</td><td>

xx1200000889
A Thin nut, width 30 mm
B R1.SMB
C Bracket
D Air connector</td></tr>
<tr><td>14</td><td>Refit the air hose connector on the bracket.
Note
Check that there is no leakage from the air hose.</td><td></td></tr>
<tr><td>15</td><td>Reconnect the battery cable.</td><td></td></tr>
</table>

Continues on next page

	Action	Note
16	Secure the battery cable with *cable straps*.	 xx0900000099 Parts: • A: Cable straps (2 pcs)
17	Use caution when pushing the *base cover* into position while at the same time checking that no cables are damaged.	 xx0800000456 Parts: • A: Base • B: Base cover • C: Attachment screws (6 pcs)
18	Secure the *base cover* with its attachment screws.	
19	Refit the *bracket* on the frame.	See the figure in: • *Location of the cable harness on page 212*
20	Refit the *cable straps* securing the cable harness to the frame.	See the figure in: • *Location of the cable harness on page 212*
21	Continue the refitting of the cable package on lower arm and armhouse.	How to refit the cable harness on the *lower arm and armhouse* is described in section: • *Refitting the cable harness in the lower arm and armhouse on page 224*

Continues on next page

Refitting the cable harness in the lower arm and armhouse

Use this procedure to refit the cable harness in the *lower arm* and *armhouse*.

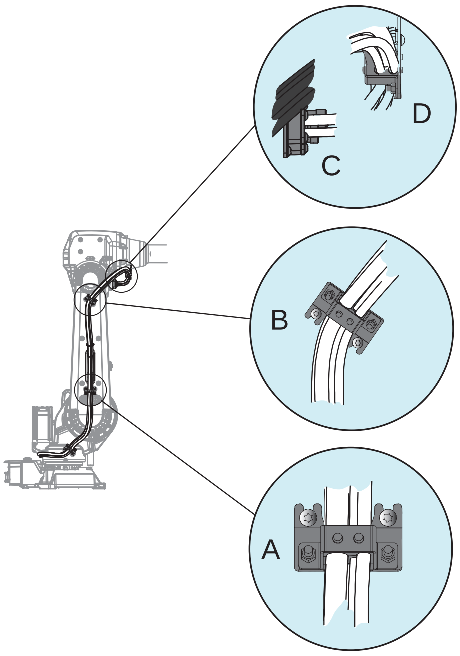
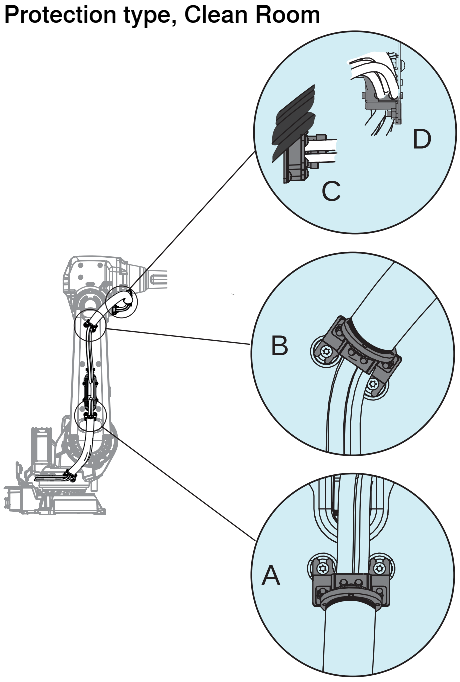
Tip

Before starting this procedure, first refit the cable harness in the *frame* and *base*. See:

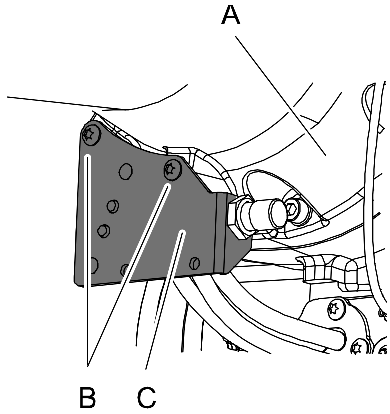
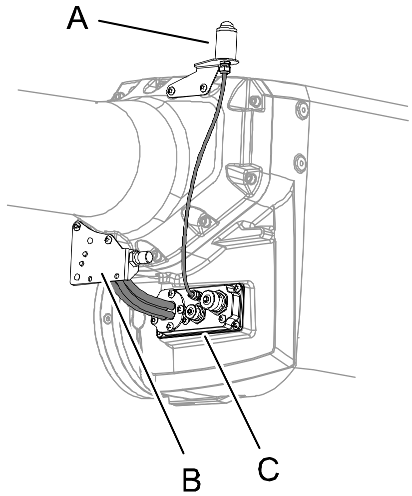
- *Refitting the complete cable harness on page 212*
- *Refitting the complete cable harness on page 212*

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
2	Secure the *brackets* on the lower arm.	 xx0900000020 Protection type, Clean Room  xx2300001190 Parts: • A: Bracket, lower arm • B: Bracket, lower arm • C: Bracket, armhouse • D: Cable bracket
3	Refit the *cable straps* securing the cable harness to the lower arm.	See the figure in: • *Location of the cable harness on page 212* (Cable harness, lower arm)

Continues on next page

	Action	Note
4	Push the cable harness carefully into the armhouse.	
5	Secure the *bracket, armhouse* with its attachment screws.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws • C: Bracket, armhouse
6	Secure the *bracket* to the armhouse with its attachment screws.	 xx0800000338 Parts: • A: Signal lamp • B: Bracket, armhouse • C: Cable bracket
7	*IRB 2600 Standard:* Reconnect the axis-3, axis-4, axis-5 and axis-6 *motor cables*.	How to connect the axis-3, axis-4, axis-5 and axis-6 motor cables, see: • *Refitting motors on page 321*
8	*IRB 2600ID:* Reconnect the axis-3 and axis-4 *motor cables*.	How to connect the axis-3 and axis-4 motor cables, see section: • *Refitting motors on page 321*
9	*IRB 2600ID:* Refit the cable package in the upper arm.	See section • *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*

Continues on next page

	Action	Note
10	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
11	**WARNING** The cover on the armhouse must be fitted when the robot is running. It is a vital part for the stability of the robot.	
12	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.3.3 Replacing the cable harness in the upper arm - IRB 2600ID

Introduction

This procedure describes how to replace the cable harness in the upper arm on IRB 2600ID.

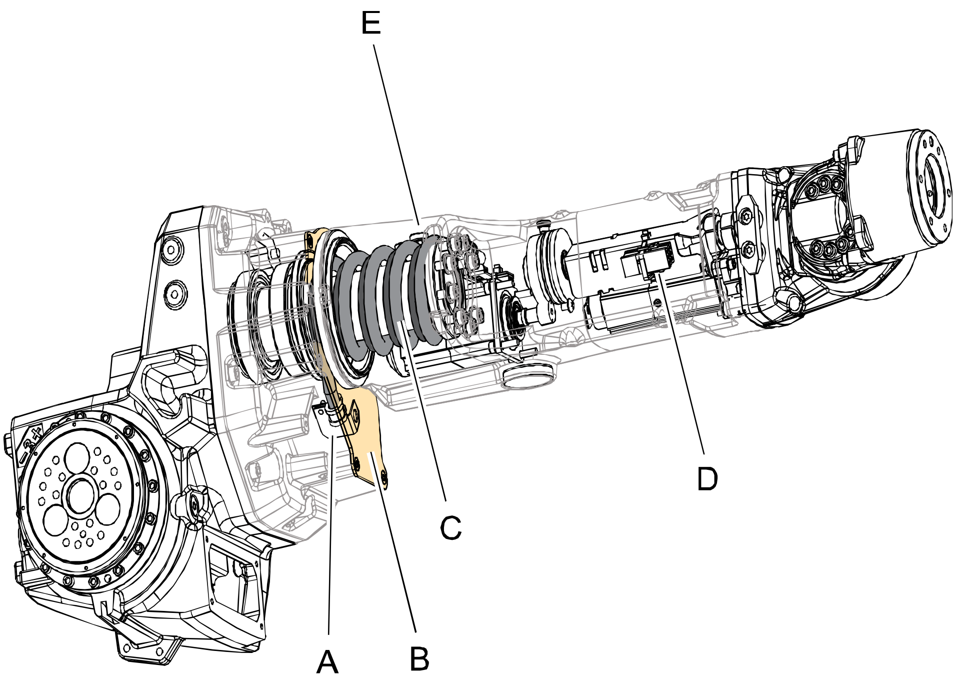
Note

In order to perform this procedure it is necessary to follow instructions in these sections as well:

- *Replacing motor axis 5 - IRB 2600ID on page 337*
- *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*

Location of the cable harness in the upper arm - IRB 2600ID

The location of the cable harness in the upper arm is shown in the figure.



xx1000001000

A	Bracket (inside armhouse)
B	Cover
C	Cable harness
D	Connectors motor axis 6 (2 pcs)
E	Bracket (securing cable harness to arm tube)

Continues on next page

Required equipment

Equipment	Note
VK cover	2 pcs. Art. no. is specified in *Spare part lists on page 461*.
Sikaflex 521FC	Art. no. 3HAC026759-001
Flange sealant	- Loctite 574 (or equivalent)
Grease	3HAC042536-001 Shell Gadus S2 For lubrication of the cable spiral.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Deciding calibration routine

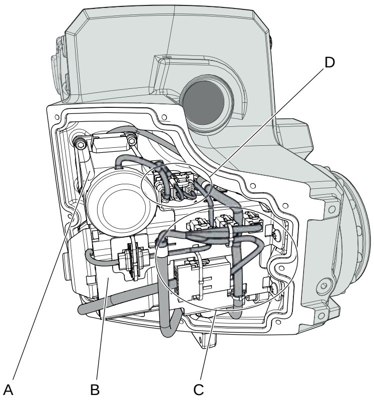
Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

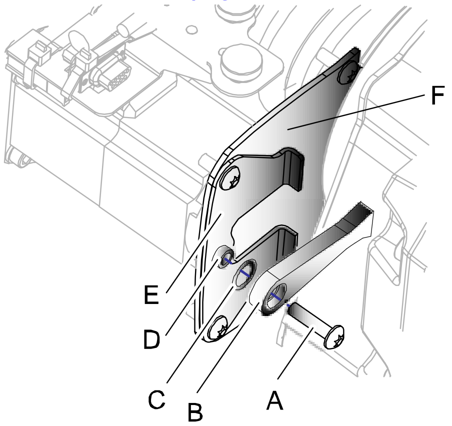
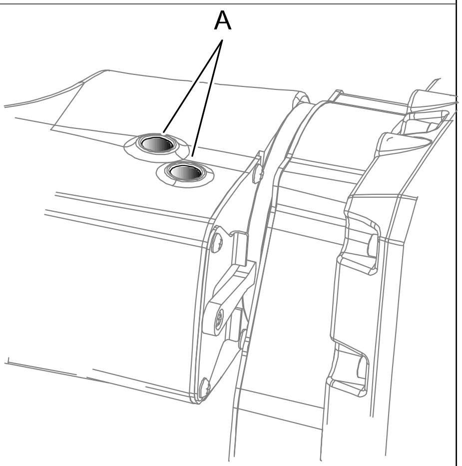
Continues on next page

Removing the cable harness

Use this procedure to remove the cable harness.

	Action	Information
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Move the robot to synchronization position.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Remove all extra equipment fitted on the upper arm and wrist.	
5	Secure the upper arm with roundslings in an overhead crane or similar.	
6	Remove the cover on the arm house.	
7	Disconnect the cables to motors axes 3, 4, 5 and 6.	 xx1000000991 Parts: A Motor axis 4 B Motor axis 3 C MP connectors axes 3, 4, 5 and 6 (see markings for axis) D FP connectors axes 3, 4, 5 and 6 (see markings for axis)
8	Remove the *wrist*. (This is done in order to be able to disconnect the motor cables of motor axis 6)	See section • *Removing the wrist unit on page 351* **Note** No need to remove the axis-6 motor. Only the motor cables need to be disconnected.

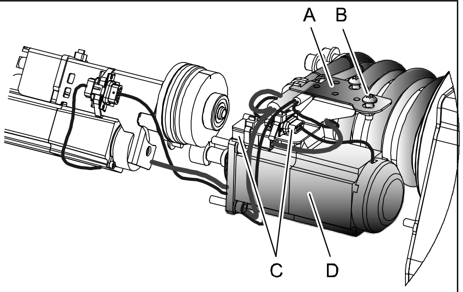
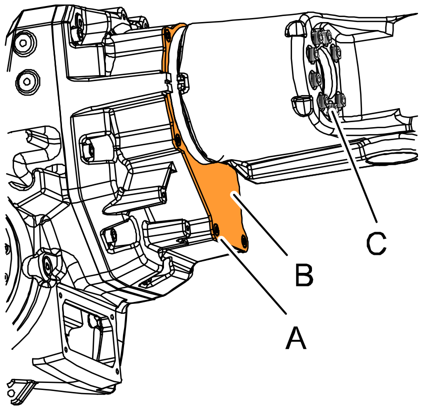
Continues on next page

	Action	Information
9	Remove the *mechanical stop, bracket and cover* .	See section • *Replacing motor axis 5 - IRB 2600ID on page 337*  xx1000000879 Parts: A Attachment screws (5 pcs) B Mechanical stop C O-ring D Distance ring E Bracket F Cover
10	Remove the two *VK-covers*, covering the attachment screws securing the cable harness to the arm tube.	 xx1000000934 Parts: A VK-covers (2 pcs)

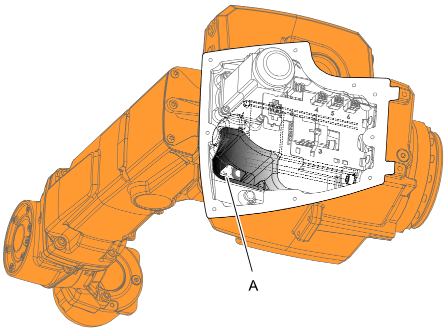
Continues on next page

4.3.3 Replacing the cable harness in the upper arm - IRB 2600ID

Continued

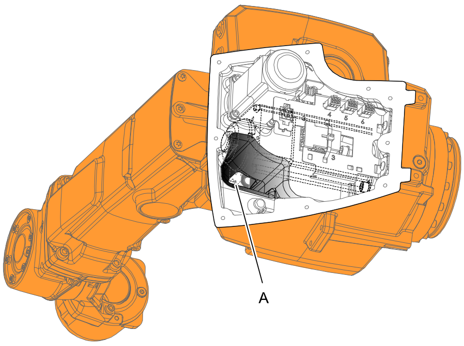
	Action	Information
11	Remove the *attachment screws* (2 pcs), securing the cable harness *bracket* to the arm tube. **Note** The arm tube is not shown here.	 xx1000000998 Parts: A Bracket B Attachment screws (2 pcs) C Connectors motor axis 5 D Motor axis 5
12	Remove the *attachment screws (A)* securing the *cover (B)* on the arm house.	 xx1000001001 Parts: A Attachments screws (6 pcs) B Cover C Attachment screws (8 pcs) securing arm tube
13	Remove the *attachment screws (C)* (8 pcs) securing the arm tube.	
14	Pull out the tube of the arm house a little, enough to be able to disconnect cables to the axis-5 motor.	
15	Disconnect *connectors* to motor axis 5.	How to remove the motor cables, see: • *Replacing motor axis 5 - IRB 2600ID on page 337* **Note** No need to remove motor axis 5!
16	Pull carefully out the cable harness off the arm house at the same time as the tube of the arm house is pulled out.	**CAUTION** Pull the cable harness out carefully! The space in the armhouse is cramp.
17	Place the upper arm tube somewhere safe.	

Continues on next page

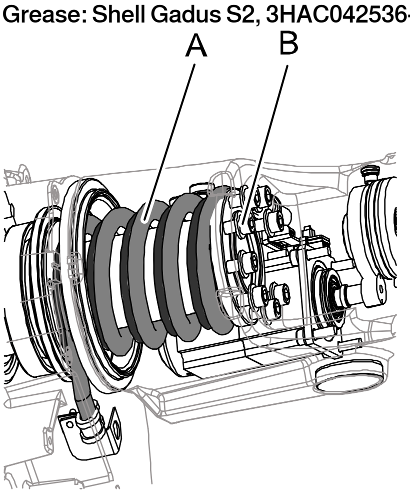
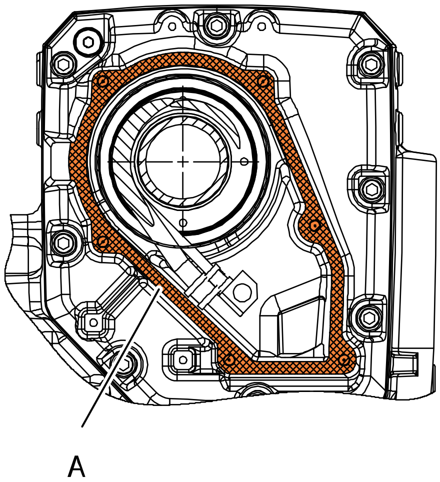
	Action	Information
18	Pull carefully out the cables off the *hole* in the arm house from the arm house where the connectors are.	 xx1000000996 Part: A Hole in arm house
19	Remove the cable harness.	

Refitting cable harness

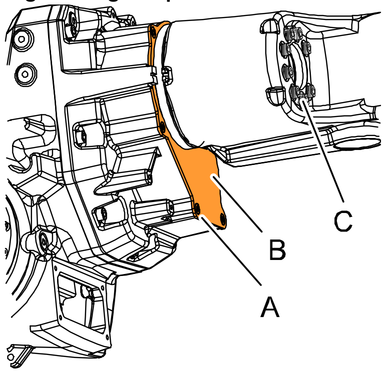
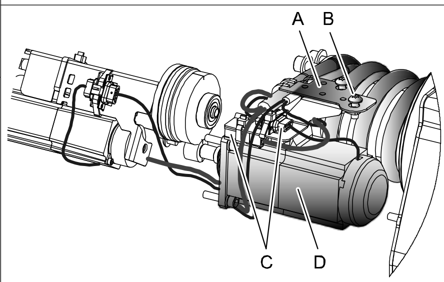
Use this procedure to refit the cable harness.

	Action	Information
1	Push carefully in the cables to the connectors for motors axes 3, 4, 5 and 6 through the *hole* in the arm house.	 xx1000000996 Part: A Hole for cables

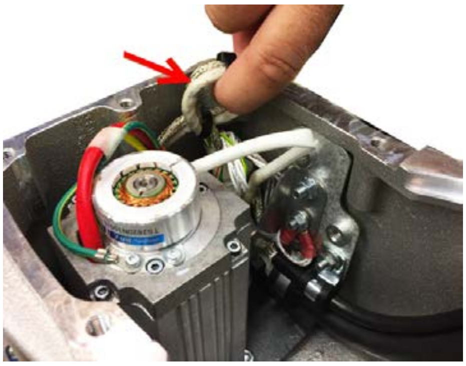
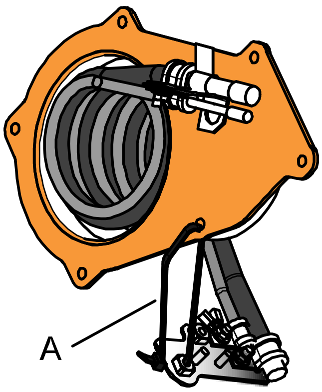
Continues on next page

	Action	Information
2	Place the *cable harness spiral* into its position in the arm house. Lubricate the cables in the spiral with grease. **Note** Do not cut the strap used as transport protection of the cable harness spiral at this point!	Grease: Shell Gadus S2, 3HAC042536-001.  xx1000001005 Parts: A Cable harness spiral B Attachment screws (8 pcs) M8x25 quality Steel 12.9 Gleitmo
3	Apply *flange sealant* on the surface where the cover shall be fitted. See figure!	 xx1000001006 Part: A Flange sealant: Loctite 574 (or equivalent), -

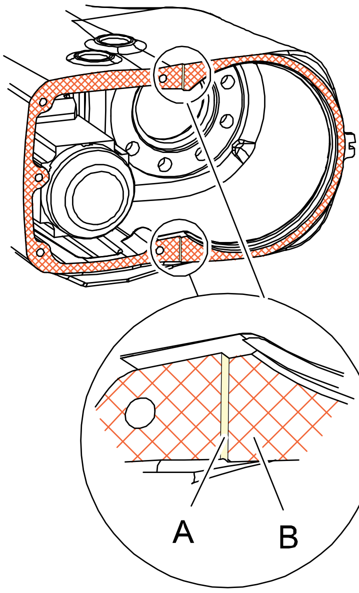
Continues on next page

	Action	Information
4	Secure the *cover* with its *attachment screws*.	Tightening torque: 10 Nm.  xx1000001001 Parts: A Attachment screws (6 pcs) M6x20 quality 8.8-A2F B Cover C Attachment screws (8 pcs) M8x25 quality Steel 12.9 Gleitmo
5	Use an overhead crane (or similar) and lift the upper arm tube almost all the way into its position.	**Note** It must still be possible to reach inside the armtube for the remaining assembly inside.
6	Push the motor cables for the axis-6 motor through the upper arm tube.	
7	Connect the *connectors* to the axis-5 motor.	 xx1000000998 Parts: A Bracket B Attachment screws (2 pcs) C Connectors motor axis 5 D Motor axis 5
8	Fit the bracket (A) to the arm house.	

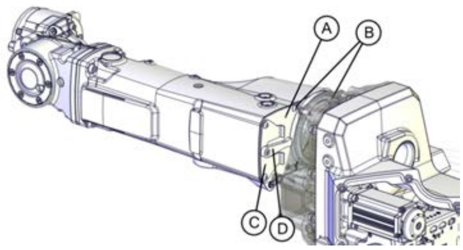
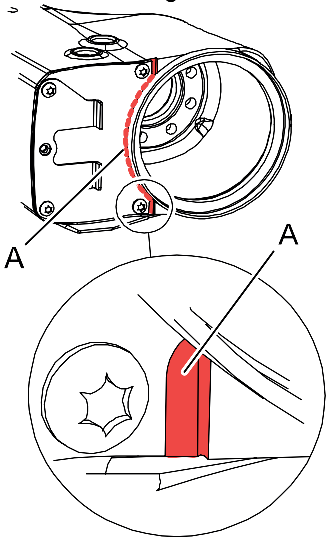
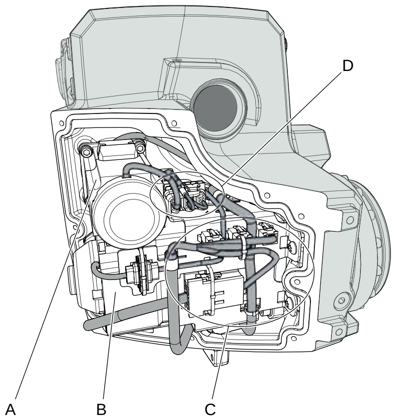
Continues on next page

	Action	Information
9	For IRB 2600ID - 8/2.0: cut the cable tie that holds the harness loop together to loosen the cabling and make it longer. Fasten the cabling to the MP5 cable. Tighten the cable ties gently with hand force. For IRB 2600ID - 15/1.85: remake the harness loop if it is missing. Fasten the loop to the MP5 cable. Tighten the cable ties gently with hand force. Diameter of the loop should be approximately Ø40 mm.	 xx1600001494
10	Check that axis 4 is in the same position as it was when the cable harness was removed.	**Note** If axis 4 is being moved in the continued refitting process it must be returned to the position it was when the mechanical stop was removed in order to get the cable harness spiral fitted correctly.
11	**CAUTION** When the spiral of the cable harness is arranged check that: • none of the cables are twisted • the two cables running in the spiral runs parallel to each other all the way • the cables are not arranged too tight or too loose.	
12	Hold the cable harness with one hand and cut the *cable strap* used as transport protection. **CAUTION** When the cable strap is cut, the spiral of the cable harness can unwind and the cables can start to cross each other.	 xx1000001004 Part: A Cable strap used as transport protection

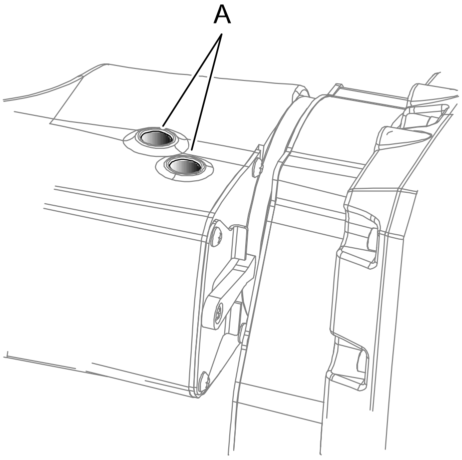
Continues on next page

	Action	Information
13	Check that the cable harness is fitted correctly by releasing the brakes on the axis-4 motor and manually moving axis 4 very carefully all the way to each end position. **CAUTION** Too much force when turning axis 4 can result in damage to the cable harness!	**Note** If axis 4 is not running correctly the spiral of the cable harness must be refitted.
14	Apply *flange sealant* Loctite 574 (or equivalent) on the surface B, shown in the figure. **Note** Do not apply flange sealant on the surfaces where Sikaflex 521FC shall be applied! See figure!	 xx1000001003 Parts: A Surface where Sikaflex 521FC shall be applied B Surface where Loctite 574 (or equivalent) shall be applied.
15	Secure the upper arm tube with its attachment screws.	Tightening torque: 35 Nm.
16	Refit the *wrist*.	See section • *Refitting the wrist on page 356*

Continues on next page

	Action	Information
17	Refit the cover (A) with two screws (B).	 xx1600001557 Parts: A Cover B Attachment screws for the cover (2 pcs of totally 5 pcs) C Bracket (including 2 cover attachment screws) D Mechanical stop (including o-ring and one cover attachment screw)
18	Refit the bracket (C) with two screws.	
19	Apply *Sikaflex 521FC* on the surfaces A shown in the figure.  xx1600001558	
20	Refit the o-ring and the mechanical stop (D) with one screw.	
21	Connect the connectors to motors axes 3, 4, 5 and 6 in the arm house.	 xx1000000991 Parts: A Motor axis 4 B Motor axis 3 C MP connectors axes 3, 4, 5 and 6 (see markings for axis) D FP connectors axes 3, 4, 5 and 6 (see markings for axis)
22	Refit the *cover* on the arm house with its attachment screws.	Tightening torque: 14 Nm.

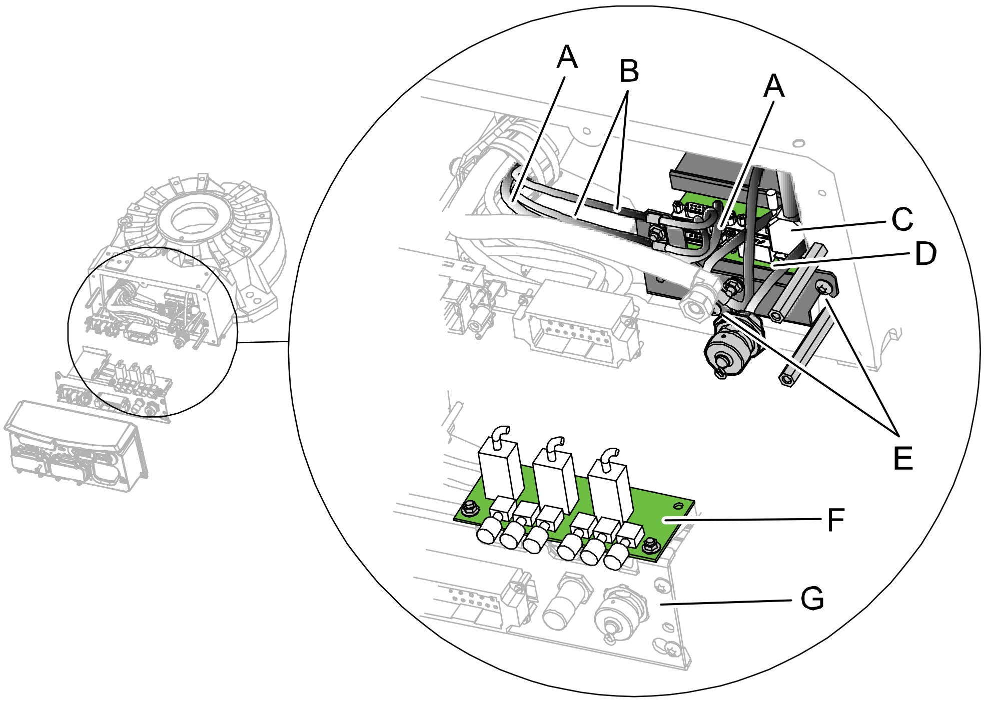
Continues on next page

	Action	Information
23	Fit new VK covers to the arm tube.	 xx1000000934 Parts: A VK-covers (2 pcs). See article number in section *Spare part lists on page 461*.
24	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
25	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.3.4 Replacing SMB unit

Location of SMB unit

The SMB unit (SMB = Serial measurement board) is located in the base below the brake release unit, as shown in the figure.



xx0800000466

A	R1.SMB3-6
B	R1.SMB1-2
C	R2.SMB
D	SMB unit
E	Attachment screws M6x16 quality 8.8-A2F (2 pcs)
F	Brake release unit
G	Bracket

Required equipment

Note

There are different variants of SMB units and batteries. The variant with the 3-pole battery contact (RMU) has longer lifetime for the battery.

It is important that the SMB unit uses the correct battery. Make sure to order the correct spare parts. Do not replace the battery contact!

Equipment	Note
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Continues on next page

Equipment	Note
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.
SMB unit	For spare part no. see chapter Spare parts, section: • *Spare part lists on page 461*

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

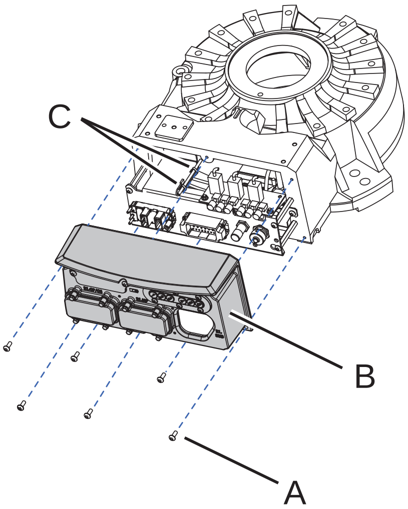
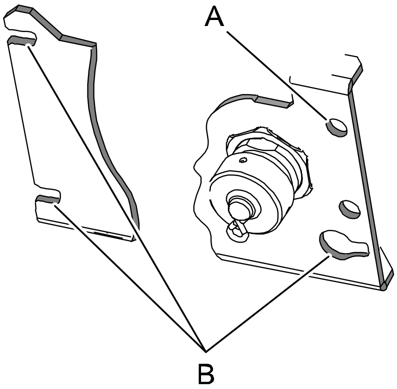
	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing the SMB unit

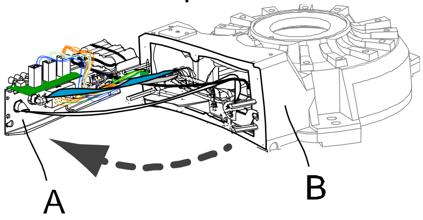
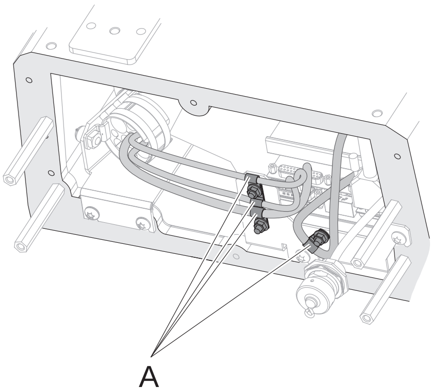
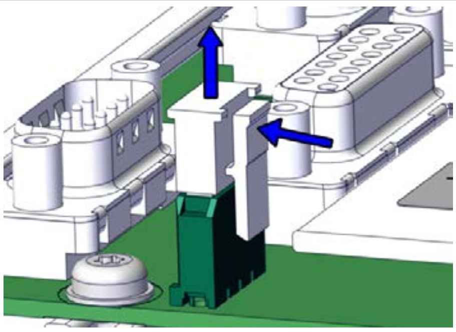
Use this procedure to remove the SMB unit.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
3	Remove the *base cover*. **CAUTION** Clean cover from metal residues before opening. Metal residues can cause shortage on the boards which can result in hazardous failures.	 xx0900000103 Parts: A Attachment screws (6 pcs) B Base cover C Cable straps, securing the battery cable (2 pcs)
4	Cut the *cable straps* securing the battery cable.	
5	Remove the screw that secures the bracket and unscrew the three other screws a little just enough to be able to slide the bracket sideways. **Note** It is not needed to remove these three screws.	 xx0900000100 Parts: A Screw to be removed B Screws to be unscrewed a little (3 pcs)

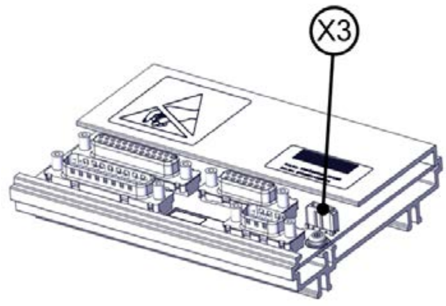
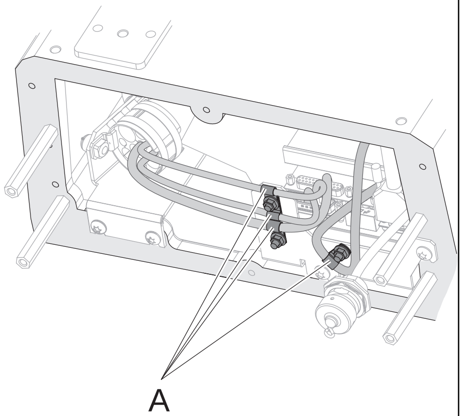
Continues on next page

	Action	Note
6	Remove the *bracket* by sliding it off the remaining three attachment screws and put it at a 90° angle from the base. Putting the bracket at a 90° angle facilitates the disconnecting of cables from the bracket. **Note** Use caution when performing this procedure order not to damage cables or other components!	Cable harness can stay connected to all connectors except to the SMB unit.  xx0900000013 Parts: A Bracket at a 90° angle B Base
7	Disconnect cable clamps.	 xx0900000035 Parts: A Cable clamps
8	Unscrew the *attachment screws* securing the SMB unit just enough to be able to remove the SMB unit.	See the figure in: • *Location of SMB unit on page 240*
9	Remove the SMB unit.	
10	Disconnect the battery cable by pressing down the upper lip of the R1.G connector to release the lock while pulling the connector upwards.	 xx1700000993
11	Disconnect the remaining connectors on the SMB unit: • R1.SMB1-2 • R1.SMB3-6 • R2.SMB	See the figure in: • *Location of SMB unit on page 240*

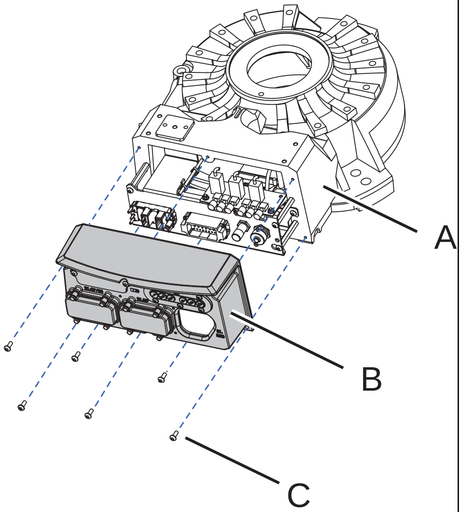
Continues on next page

Refitting the SMB unit

Use this procedure to refit the SMB unit.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Reconnect contacts on the SMB unit: • R1.SMB1-2 • R1.SMB3-6 • R2.SMB • Battery cable R1.G (X3) Make sure the lock snaps into place during refitting.	 xx1700000994
3	Place the SMB unit on its *attachment screws*.	See the figure in: • *Location of SMB unit on page 240*
4	Secure the SMB unit with its attachment screws.	
5	Refit the *cable clamps*.	 xx0900000035 Parts: A Cable clamps
6	Put back the cable harness in the base and refit the bracket on the distance screws. **Note** Use caution when performing this procedure order not to damage cables or other components!	See the figure in: • *Location of SMB unit on page 240*

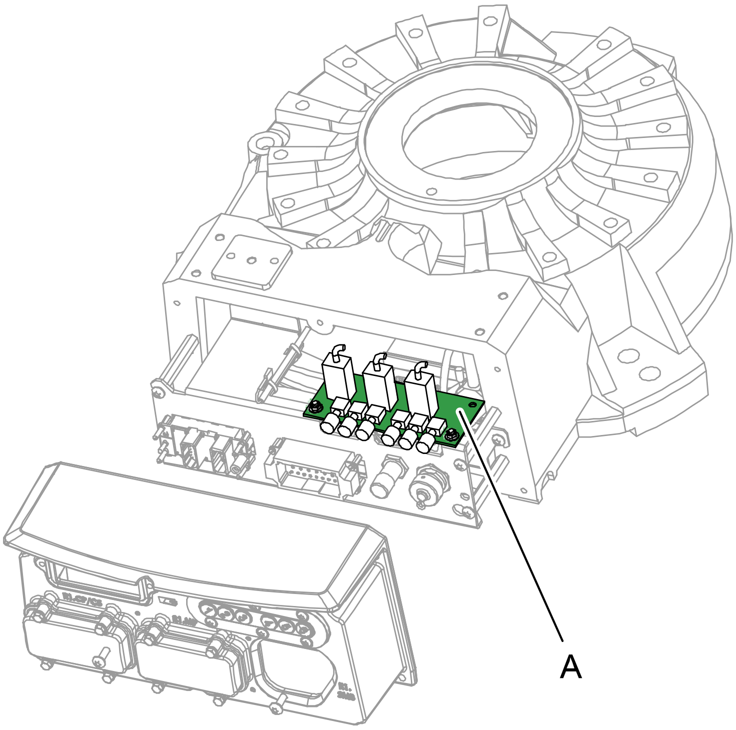
Continues on next page

	Action	Note
7	Secure the battery cable with cable straps.	
8	Use caution when pushing the *base cover* into position while at the same time checking that no cables are damaged.	 xx0800000456 Parts: A Attachment screws (6 pcs) B Base cover C Base
9	Secure the *base cover* with the attachment screws.	
10	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
11	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.3.5 Replacing the brake release board

Location of brake release board

The brake release board is located as shown in the figure.

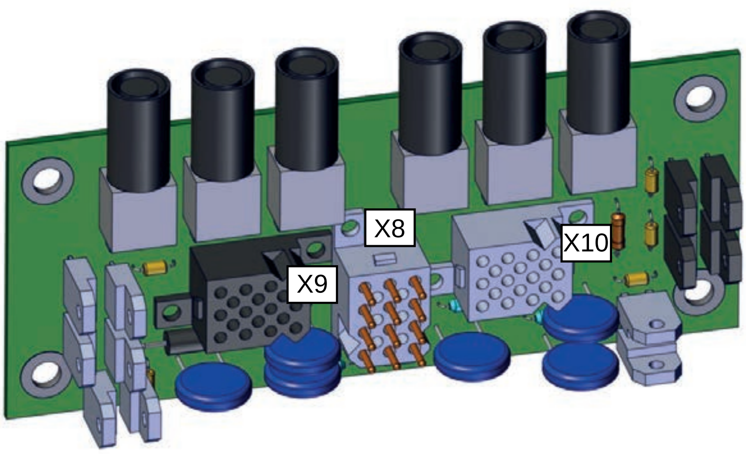


xx0900000101

A	Brake release board

Connectors on push-button board

The connectors X8, X9 and X10 are placed on the push-button board as shown in the figure below.



xx1700000978

Continues on next page

Required equipment

Equipment		Note
Brake release board	3HAC065020-001 [i] 3HAC062021-001 [ii]	DSQC1050 DSQC1052
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

i Valid for robots that are equipped with motors of Type A and Type B (see *Product manual, spare parts - IRB 2600*).
Includes brake release board and harness.

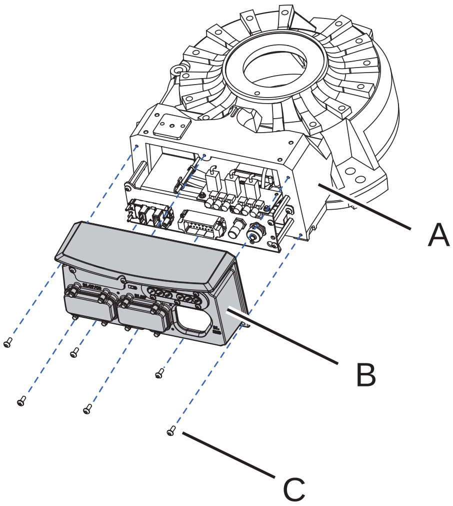
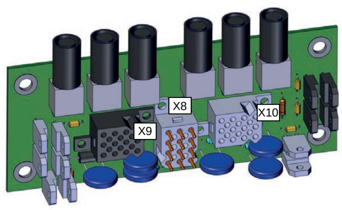
ii Valid for robots that are equipped with motors of Type B (see *Product manual, spare parts - IRB 2600*).
Includes brake release board and harness.

Removing the brake release board

Use this procedure to remove the brake release board.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**ELECTROSTATIC DISCHARGE (ESD)** The unit is sensitive to ESD. Before handling the unit read the safety information in section *The unit is sensitive to ESD on page 56*.	
3	Remove the *push button guard* from the SMB cover.	The guard must be removed to ensure a correct refitting of the brake release board.

Continues on next page

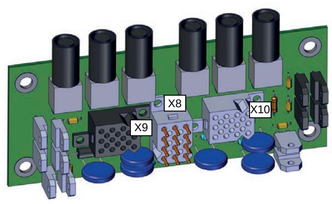
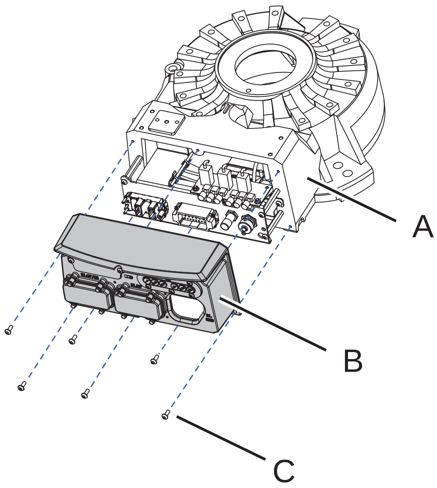
	Action	Note
4	Remove the *base cover*.  **CAUTION** Clean cover from metal residues before opening. Metal residues can cause shortage on the boards which can result in hazardous failures.	 xx0800000456 Parts: A Base B Base cover C Attachment screws M6x16 quality 8.8-A2F (6 pcs)
5	Take a picture or make notes of how the robot cabling is positioned in regard to the brake release board.	
6	Disconnect *connectors X8, X9* and *X10* from the brake release board.	 xx1700000978
7	Remove the *nuts* securing the brake release board.	
8	Remove the brake release board.	

Refitting the brake release board

Use this procedure to refit the brake release board.

	Action	Note
1	 **DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
2	**ELECTROSTATIC DISCHARGE (ESD)** The unit is sensitive to ESD. Before handling the unit read the safety information in section *The unit is sensitive to ESD on page 56*.	
3	Secure the brake release board to the *bracket* with its *nuts with flange*.	Maximum tightening torque: 5 Nm. See the figure in: • *Location of brake release board on page 246*
4	Reconnect *connectors X8*, *X9* and *X10* to the brake release board. Be careful not to damage the sockets or pins. Make sure the connector and its locking arms are snapped down properly.	 xx1700000978
5	Verify that the robot cabling is positioned correctly, according to previously taken picture/notes. **WARNING** Screened cables must not get in contact with the brake release board after installation. Eliminate all risks of contact between screened cables and the brake release board.	
6	Use caution when pushing the *base cover* into position while at the same time checking that no cables are damaged.	 xx0800000456 Parts: A Base B Base cover C Attachment screws M6x16 quality 8.8-A2F (6 pcs)
7	Secure the *base cover* with its *attachment screws*.	

Continues on next page

	Action	Note
8	**WARNING** Before continuing any service work, follow the safety procedure in section *The brake release buttons may be jammed after service work on page 198*!	
9	Refit the *push button guard* to the SMB cover.	
10	Press the push buttons 1 to 6, one at a time, to make sure that the buttons are moving freely and do not stay in any locked position.	
11	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

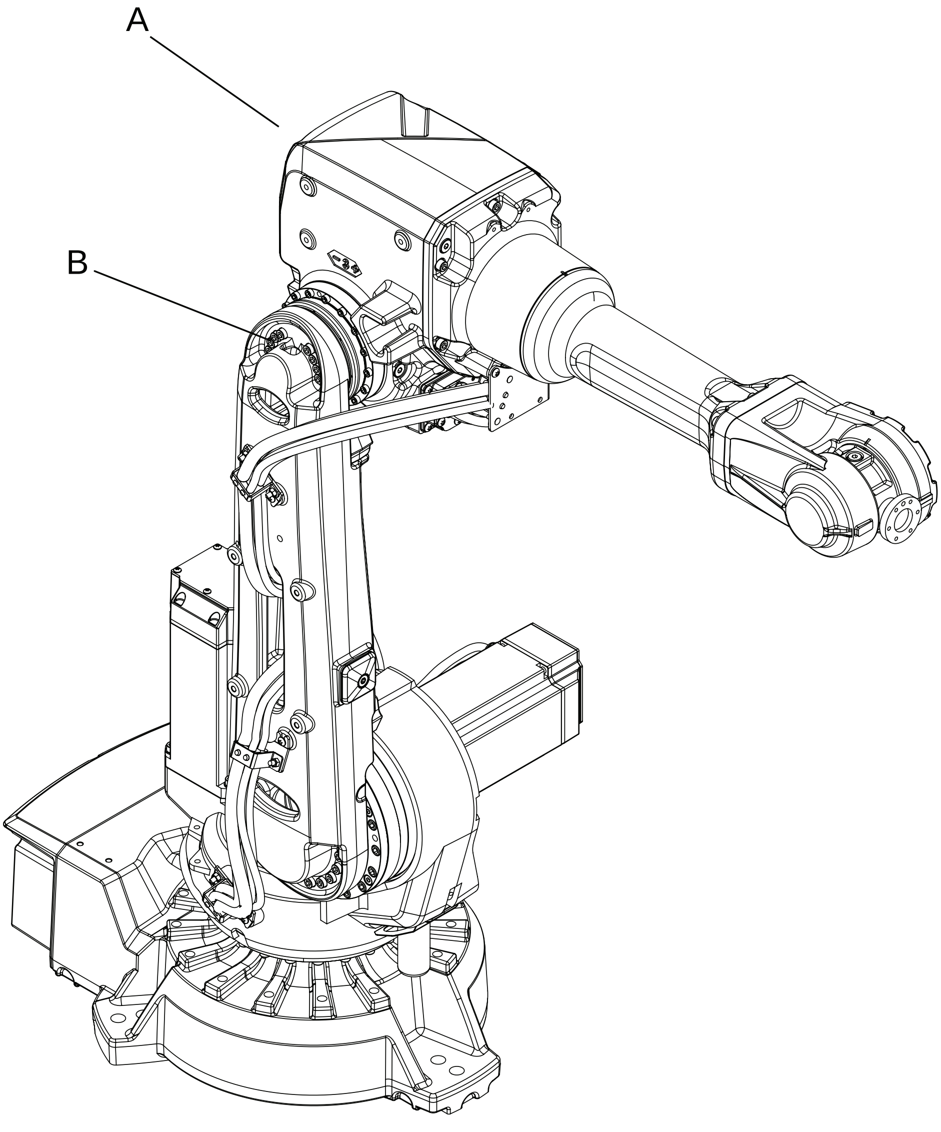
4.4 Upper arm

4.4.1 Replacing the complete upper arm

Location of the complete upper arm

The complete upper arm is located as shown in the figure.

The figure shows IRB 2600 Standard but is also valid for IRB 2600ID.

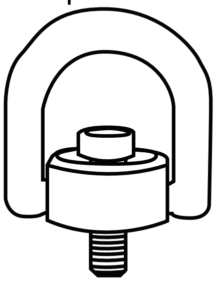


xx1100000947

A	Upper arm
B	Attachment screws M8x40, quality steel 12.9 gleitmo (12 pcs)

Continues on next page

Required equipment

Equipment	Note
Armhouse	For spare parts no. see Spare parts - *Upper arm (2.05/2.50/2.55)* in *Product manual, spare parts - IRB 2600*.
Tubular shaft unit	For spare parts no. see Spare parts - *Upper arm (2.05/2.50/2.55)* in *Product manual, spare parts - IRB 2600*.
Rotating lifting point	2 pcs. Dimension: M8. Example: Gunnebo RLP GrabiQ M8-10.  xx1100000564
Washer	Required if the screw in the rotating lifting point bottoms. Inner diameter: 12 mm. Outer diameter: min. 23 mm. Thickness: enough to prevent the screw in the rotating lifting point to bottom.
Roundslings	3 pcs. Lengths: 1.5 m (1 pc, run around the wrist unit), 2 m (2 pcs). Lifting capacity: 500 kg.
Screws	2 pcs. Used to prevent the roundsling at the wrist from sliding. Dimension: • M6. Length: 70 mm. Quality: 8.8.
Guide pins	M8 (2 pcs)
Locking liquid	Loctite 2400 (or equivalent Loctite 243) Clean Room robots
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Continues on next page

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing the complete upper arm

Use this procedure to remove the complete upper arm. This procedure can be done without draining the axis 3 gearbox.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Run the robot to the position shown in the figure. The robot must be floor mounted and the upper arm must be horizontally positioned.	 xx0800000336

Continues on next page

	Action	Note
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**CAUTION** The weight of the complete upper arm (including the wrist) is 65 kg All lifting accessories used must be sized accordingly.	
5	Attach the lifting accessories to the upper arm.	See *Attaching the lifting accessories to the upper arm on page 256*.
6	Unload the weight of the upper arm by stretching the roundslings. **Tip** Turn on the power temporarily and release the brakes of axis 3 to rest the weight onto the roundslings.	
7	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
8	Disconnect all *motor cables* from motors axes 3, 4, 5 and 6.	How to disconnect cables from motors is detailed in sections: • *Removing motors on page 308*

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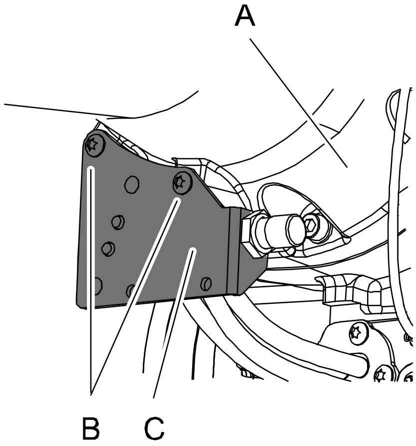
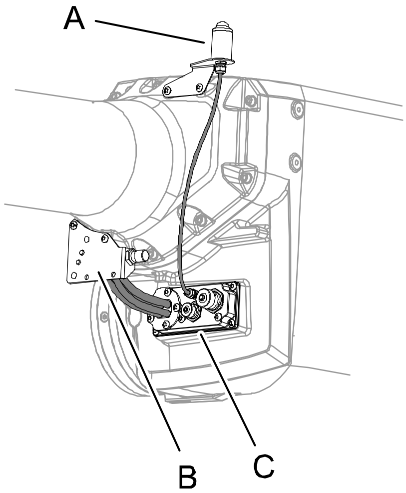
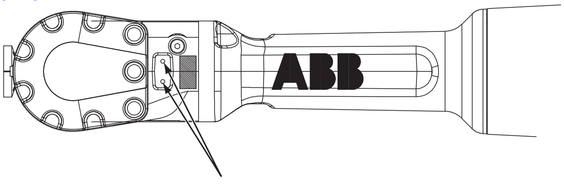
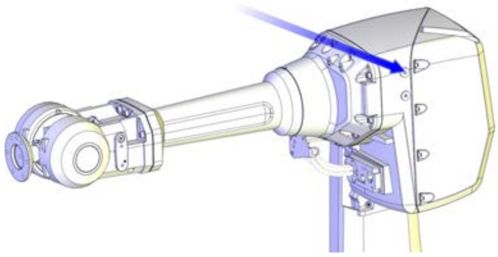
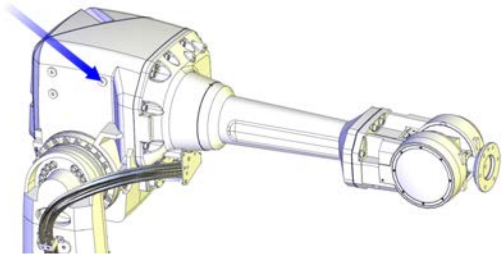
	Action	Note
9	Remove the *bracket* fitted on the tubular shaft unit.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws M6x16 quality 8.8-A2F (2 pcs) • C: Bracket
10	Remove the *signal lamp*, if used.	
11	Remove the *cable bracket* on the armhouse.	 xx0800000338 Parts: • A: Signal lamp • B: Bracket • C: Cable bracket
12	Using caution, pull the cable package out of the hole where the cable bracket was fitted.	
13	Remove the *attachment screws* securing the upper arm to the lower arm.	See the figure in: • *Location of the complete upper arm on page 251* **Note** Do not remove the attachment screws securing the gearbox axis 3 to the armhouse!

Continues on next page

	Action	Note
14	Remove the complete upper arm.	

Attaching the lifting accessories to the upper arm

Attaching the lifting accessories

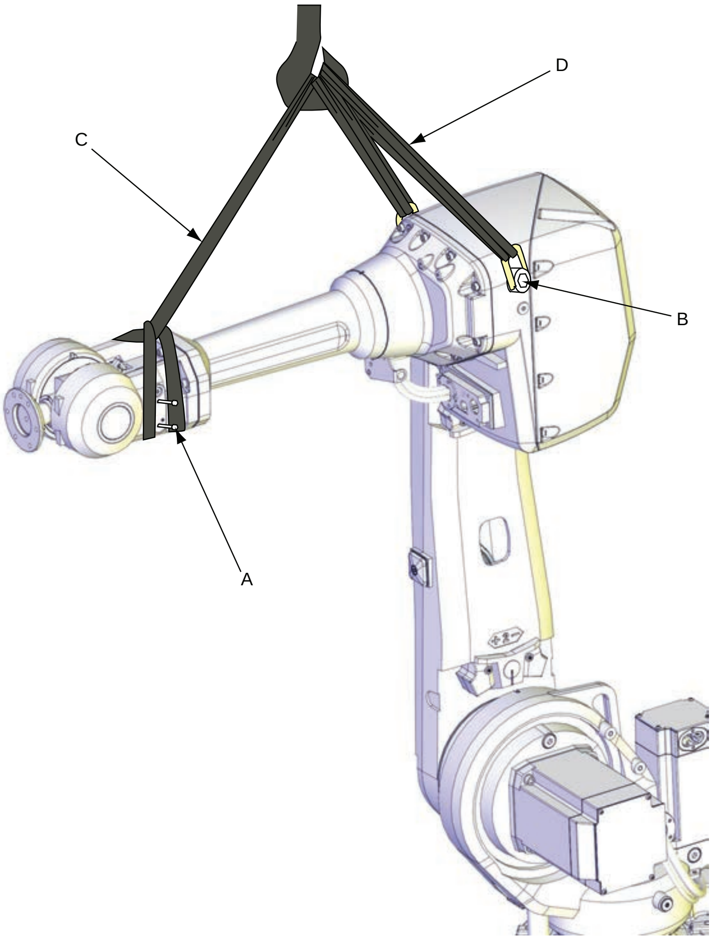
	Action	Note
1	Fit two *screws* in the wrist unit. The purpose of these screws is to prevent the roundsling from sliding. The wrist unit of IRB 2600ID looks a bit different. Either run the roundsling around the ID wrist in such a way that the sling can not slide, or remove the mechanical stop at the wrist temporarily and use the attachment holes to fit the screws to prevent the sling from sliding.	Dimension is specified in *Required equipment on page 252*.  xx1100000581
2	Fit two *rotating lifting points* to the attachment holes in the arm house, see the figure. Secure the lifting point tightly against the arm house, but at the same time making sure that the screw does not bottom. Use an extra *washer* if the screw does bottom. Tightening torque: 30 Nm.	Dimension is specified in *Required equipment on page 252*. The figures show IRB 4600 but the same attachment holes are used also for IRB 2600.  xx1100000565  xx1100000566
3	Run a *roundsling* through each rotating lifting point and fasten both ends at the lifting hook. Use the longest roundslings (2 m).	Dimension is specified in *Required equipment on page 252*. See figure *Attaching the roundslings to the upper arm on page 257*.

Continues on next page

	Action	Note
4	Make a loop of the third *round-sling*, running it around the wrist unit. Run the roundsling on both sides of the screws and fasten the free end of the roundsling to the lifting hook. Use the shortest roundsling (1.5 m).	Dimension is specified in *Required equipment on page 252*. See figure *Attaching the roundslings to the upper arm on page 257*.

Attaching the roundslings to the upper arm

The figure shows IRB 4600 but the principle is the same for IRB 2600. Make sure the roundsling looped around the wrist unit is run on both sides of the screws.



xx1100000567

A	Screws to prevent the roundsling from sliding, 2 pcs
B	Rotating lifting point, 2 pcs
C	Roundsling around wrist unit Length: 1.5 m.
D	Roundsling attached to arm house, 2 pcs Length: 2 m

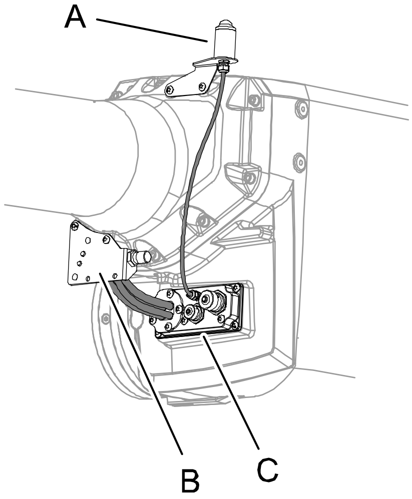
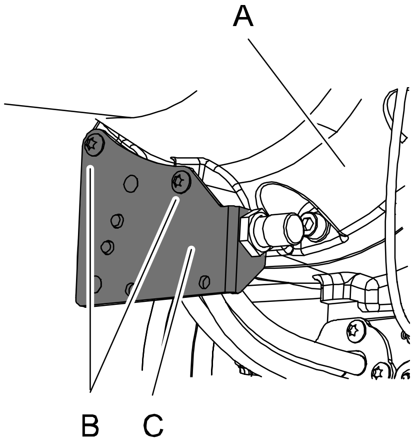
Continues on next page

Refitting the complete upper arm

Use this procedure to refit the complete upper arm.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**CAUTION** The weight of the complete upper arm (including the wrist) is 65 kg All lifting accessories used must be sized accordingly.	
3	Clean all assembly surfaces.	
4	Attach the lifting accessories to the upper arm.	See *Attaching the lifting accessories to the upper arm on page 256*.
5	Fit *guide pins* to the upper arm.	Specified in *Required equipment on page 252*.
6	Lift the upper arm to the robot using an overhead crane.	
7	Release the brakes of the axis 3 motor.	
8	Refit the upper arm to the lower arm with its *attachment screws*. It may be necessary to turn the gear by rotating the motor pinion with a *rotation tool, motor* beneath the motor cover.	See the figure in: • *Location of the complete upper arm on page 251* Tightening torque : • 35 Nm

Continues on next page

	Action	Note
9	Using caution, push the cable package through the hole where the cable bracket will be fitted.	 xx0800000338 Parts: • A: Signal lamp • B: Bracket • C: Cable bracket
10	Refit the *cable bracket* with its attachment screws.	
11	Reconnect all *motor cables*.	How to connect motor cables is detailed in sections: • *Refitting motors on page 321*
12	Refit the *bracket* on the *tubular shaft unit*.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws M6x16 quality 8.8-A2F (2 pcs) • C: Bracket
13	Refit the *signal lamp*, if used.	

Continues on next page

	Action	Note
14	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
15	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

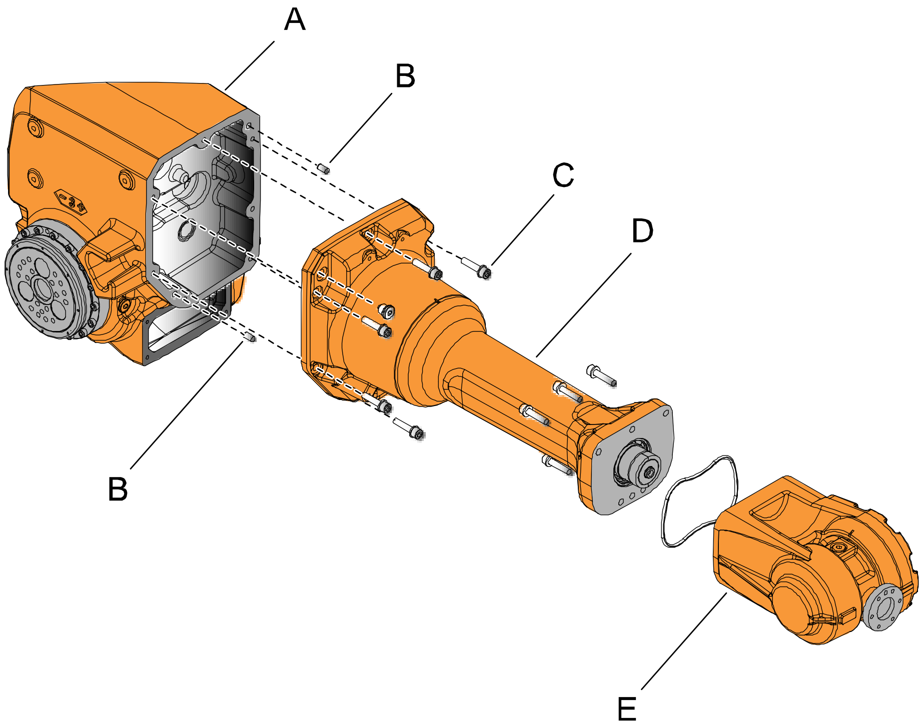
4.4.2 Replacing complete tubular shaft unit

Introduction

This section is not valid for IRB 2600ID.

Location of tubular shaft unit

The tubular shaft unit is located as shown in the figure.



xx0900000385

A	Armhouse
B	Parallel pin, hardened M8x16 m6 (2 pcs)
C	Attachment screws M8x35 quality 8.8-A2F and washers (6+6 pcs)
D	Tubular shaft unit
E	Wrist

Required equipment

Equipment	Note
Tubular shaft unit	For spare parts no. see Spare parts - *Upper arm (2.05/2.50/2.55)* in *Product manual, spare parts - IRB 2600*.
Guide pins	2 pcs. Dimension: M8.
Cleaning agent	Isopropanol
Sealing liquid	Loctite 574
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Continues on next page

Equipment	Note
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

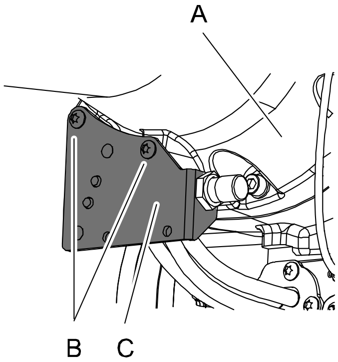
	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing complete tubular shaft unit

Use this procedure to remove the complete tubular shaft unit.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Drain *oil* from gearbox axis 4.	How to drain the oil from the gearbox is described in section: • *Changing the oil, axis-4 gearbox on page 171*

Continues on next page

	Action	Note
3	Move the robot to the position shown in the figure.	 xx0800000336
4	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
5	Remove the *bracket* securing the cable package to the tubular shaft unit by removing its attachment screws.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws M6x16 quality 8.8-A2F (2 pcs) • C: Bracket
6	Place the cable package in a way that it will not be damaged in the continued removal procedure.	
7	Remove motors axes 4, 5 and 6.	How to remove motors is described in section: • Removing motors on page 308
8	**Tip** If only the tubular shaft unit shall be replaced, it is a good idea to remove the *wrist unit* at this stage.	How to remove the wrist unit is detailed in section: • Removal of wrist unit on page 270

Continues on next page

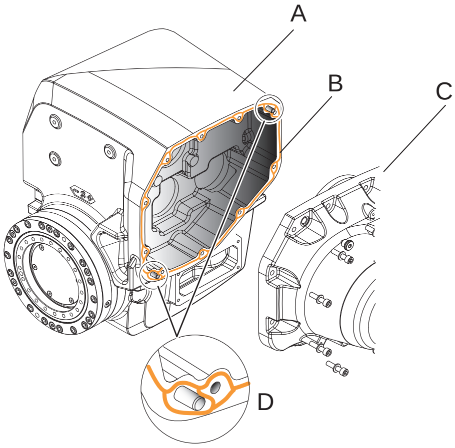
	Action	Note
9	**CAUTION** The robot arm tube weighs 30 kg. All lifting accessories used must be sized accordingly.	
10	Secure the *tubular shaft unit* with roundslings in an overhead crane. **CAUTION** Prevent the slings from sliding! For example a small plate can be fitted to the lower attachment hole for the cable bracket (removed in a previous step). The plate should be fitted so it points downwards and functions as a mechanical stop for the roundsling. At the other end of the tubular shaft unit, a shackle can be fitted if the wrist unit is removed.	
11	Remove the *attachment screws* that secure the tubular shaft unit.	See the figure in: • *Location of tubular shaft unit on page 261*
12	Remove the *tubular shaft unit* using caution. The tubular shaft unit is fitted with Loctite. **CAUTION** Do not damage the gears when removing the tubular shaft unit. **CAUTION** Remaining oil will drain out from the gearbox cavity when the tubular shaft is lifted out.	**Note** There are two parallel pins guiding the tubular shaft unit into its place. See figure in *Replacing complete tubular shaft unit on page 261*.

Refitting complete tubular shaft unit

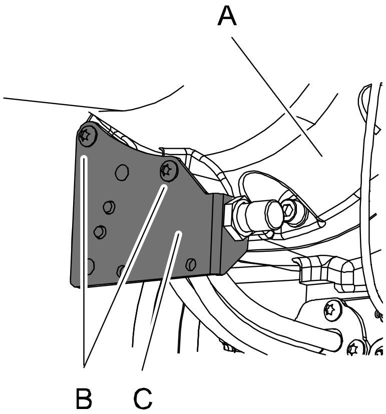
Use this procedure to refit the tubular shaft unit.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
2	Remove residues of old Loctite and other contaminations from the assembly surfaces. Remove any painting from the assembly surfaces, with a knife.	
3	Apply sealing liquid (Loctite 574) on the surface between the tubular shaft unit and the armhouse. Make sure to apply the sealing liquid in circles around each of the attachment holes.	 xx0800000457 Parts: A Armhouse B Surface where Loctite 574 shall be applied C Tubular shaft unit D Cylindrical pin (2 pcs)
4	**CAUTION** The robot arm tube weighs 30 kg. All lifting accessories used must be sized accordingly!	
5	Secure the tubular shaft unit with a roundsling in an overhead crane. **CAUTION** Prevent the slings from sliding! For example a small plate can be fitted to the lower attachment hole for the cable bracket (removed in a previous step). The plate should be fitted so it points downwards and functions as a mechanical stop for the roundsling. At the other end of the tubular shaft unit, a shackle can be fitted if the wrist unit is removed.	
6	Fit *guide pins* in the upper arm house.	Specified in *Required equipment on page 261*.

Continues on next page

	Action	Note
7	Refit the tubular shaft unit, using caution. **CAUTION** Do not damage the gears when refitting the tubular shaft unit.	**Note** There are two parallel pins guiding the tubular shaft unit into its place.
8	Secure the tubular shaft unit with its *attachment screws*.	See the figure in: • *Location of tubular shaft unit on page 261* Tightening torque: 22 Nm
9	Refit *motors axes 4, 5 and 6*.	How to refit motors is described in section: • *Refitting motors on page 321*
10	Perform a leak-down test.	See *Performing a leak-down test on page 190*.
11	Refit the *bracket* securing the cable package to the tubular shaft unit, with its *attachment screws*.	 xx0800000335 Parts: • A: Tubular shaft unit • B: Attachment screws M6x16 quality 8.8-A2F (2 pcs) • C: Bracket
12	If the *wrist unit* has been removed from the tubular shaft unit, refit it now.	How to refit the wrist unit is detailed in section: • *Refitting of wrist unit on page 271*
13	Refill gearbox axis 4 with oil.	How to refill oil in gearbox is described in section: • *Changing the oil, axis-4 gearbox on page 171*
14	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.

Continues on next page

	Action	Note
15	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.4.3 Replacing wrist unit

Introduction

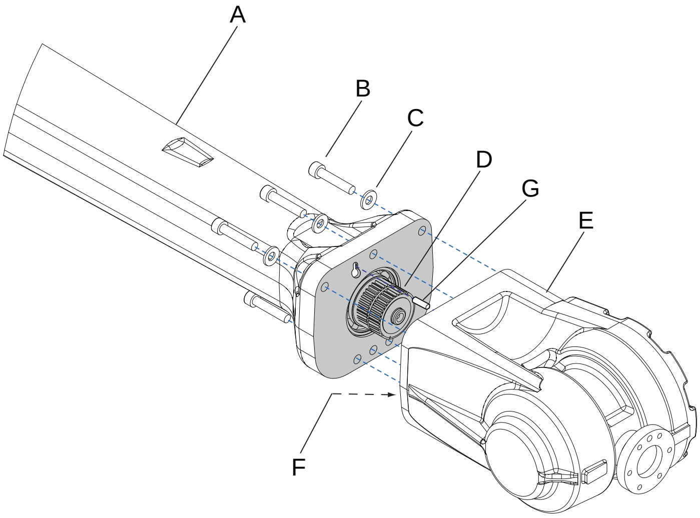
This section describes how to replace the wrist on IRB 2600 Standard.

How to remove and refit the wrist unit on IRB 2600ID is described in section *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*.

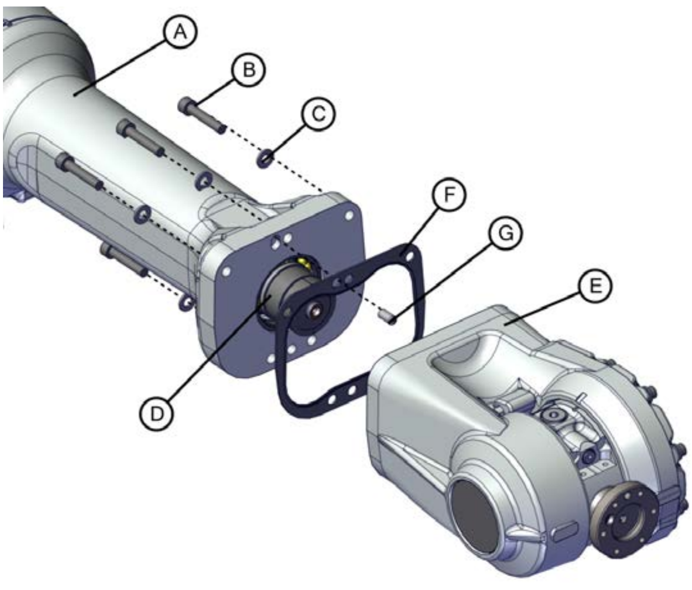
Location of wrist unit

The wrist unit is located in the upper arm as shown in the figures.

There are two versions of the wrist, one with an o-ring and one with a sealing. Make sure to order the correct spare parts.



xx0800000341



xx1800003343

A	Upper arm
B	Attachment screw M8x40, quality steel 12.9 Gleitmo (5 pcs)

Continues on next page

C	Spring washer, conical 8.4x18x2, quality steel-mZn12c (5 pcs)
D	Gears
E	Wrist unit
F	O-ring (Placed on the wrist, not visible) Sealing (lower image)
G	Guide pin (only available for robots that are calibrated with Axis Calibration) (not available on IRB 2600ID)

Required equipment

Equipment	Note
Wrist unit	For spare parts no. see Spare parts - *Upper arm (2.05/2.50/2.55)* in *Product manual, spare parts - IRB 2600*.
O-ring	For spare parts no. see Spare parts - *Upper arm (2.05/2.50/2.55)* in *Product manual, spare parts - IRB 2600*.
Sealing	
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Deciding calibration routine

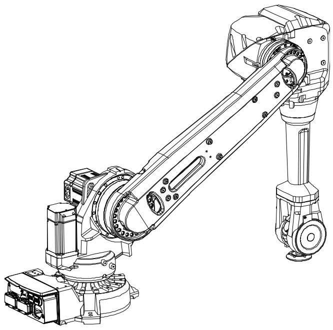
Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Continues on next page

Removal of wrist unit

Use this procedure to remove the wrist unit.

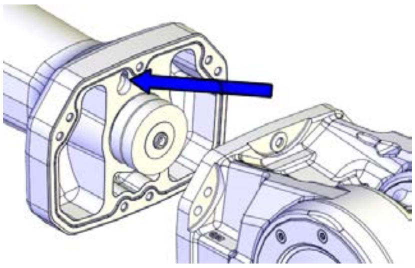
	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Move the upper arm to a position where the wrist is pointing towards the floor as shown in the figure. This way the wrist can be removed without drainage.	 xx0800000329
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	**WARNING** Handling gearbox oil involves several safety risks, see *Gearbox lubricants (oil or grease) on page 36*.	
5	**CAUTION** The robot wrist unit weighs 15 kg. All lifting accessories used must be sized accordingly!	
6	Remove the *attachment screws* and carefully remove the wrist unit. **CAUTION** Do not damage the gears. **WARNING** The wrist unit is filled with oil. Perform removal with care.	See the figure in: • *Location of wrist unit on page 268*

Continues on next page

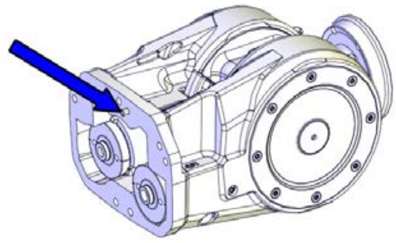
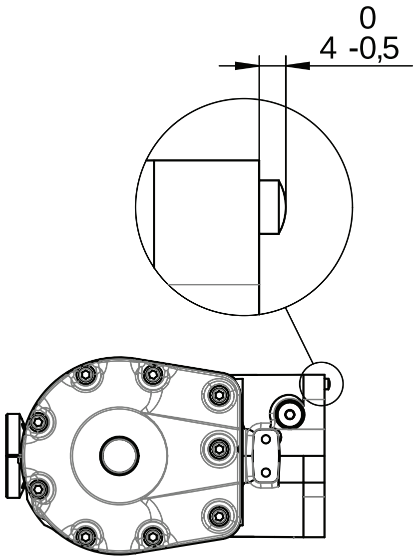
	Action	Note
7	Pour out the oil from the wrist unit.	See the figure in • *Location of wrist unit on page 268*

Refitting of wrist unit

Use this procedure to refit the wrist unit.

	Action	Note
1	 **DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Check if there is a parallel pin hole in the upper arm tube. The hole is available on robots that are calibrated with the Axis Calibration method.	 xx1600000690

Continues on next page

	Action	Note
3	If there is a hole, fit the parallel pin into the corresponding hole in the wrist (enclosed with the new wrist spare part). **Note** If the parallel pin is not installed on a robot calibrated with Axis Calibration, the calibration result will be affected negatively.	 xx1600000689 Verify that the parallel pin sticks out from the wrist according to the measurement given below.  xx1600000703
4	Clean all assembly surfaces. Remove any painting from the assembly surfaces with a knife.	

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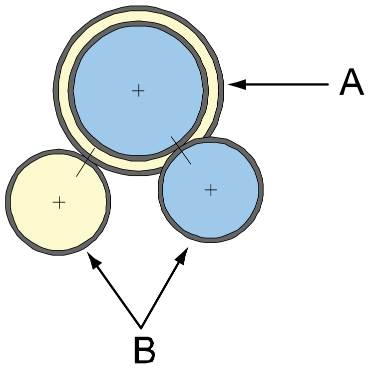
	Action	Note
5	Check the o-ring or sealing. Replace if damaged.	See the figure in: • *Location of wrist unit on page 268*
6	Prepare the refitting of the wrist by inserting the attachment screws and washers in the upper arm tube.	
7	**CAUTION** The robot wrist unit weighs 15 kg. All lifting accessories used must be sized accordingly.	
8	Carefully put the *wrist unit* in its place on the *upper arm*. **CAUTION** Do not damage the gears. **CAUTION** Make sure that the o-ring stays in place on the wrist unit.	
9	Adjust the play of the wrist by following these steps: • Push the wrist as shown in the figure to locate the smallest play in the same way as for adjustment of motors for axes 4, 5 and 6. See *Refitting motors on page 321*.	 xx1000000223 Parts: • A: Gears on drive shaft unit, axes 5-6 • B: Gears on the wrist
10	Secure the wrist unit with its *attachment screws* and *washers*.	See the figure in • *Location of wrist unit on page 268* Tightening torque: 35 Nm.
11	*Measure the play* by moving axes 5 and 6 with the measuring tool.	How to measure the play is described in sections: • *Measuring the play, axis 5 on page 275* • *Measuring the play, axis 6 on page 277* • *Measuring the play, axis 5 (ID upper arm) on page 279* • *Measuring the play, axis 6 (ID upper arm) on page 282*

Continues on next page

	Action	Note
12	Perform a leak-down test.	See *Performing a leak-down test on page 190*.
13	Refill *oil* in gearbox axes 5-6.	How to fill oil in gearbox axes 5-6 is described in section: • *Changing oil, axes-5 and -6 gearboxes on page 175*
14	Re-calibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
15	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.4.4 Measuring the play, axis 5

General

This section is only valid for IRB 2600. For IRB 2600ID, see section *Measuring the play, axis 5 (ID upper arm) on page 279*.

After reassembly due to repair work or any other reason, the play in axis 5 and 6 must be checked to ensure the repetition accuracy of the robot positioning. The procedure for axis 5 is detailed below.

Required equipment

Equipment, etc.	Article number	Note
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Measurement, axis 5

The procedure below details how to measure the play of axis 5.

	Action	Information
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Move the robot to calibration position and turn the axis 4 90°.	
3	Fit the *measuring tool, play* to the turning disc.	Article number is specified in *Required equipment on page 275*.

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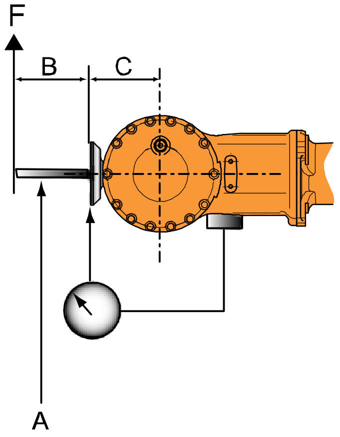
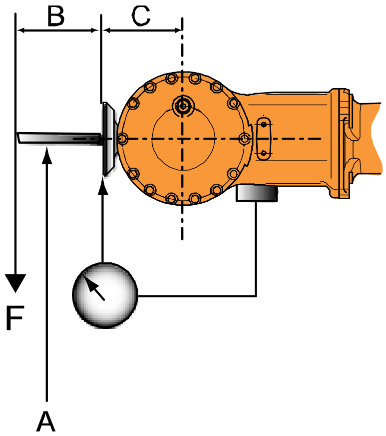
	Action	Information
4	Apply load F in one direction, as shown in the figure to the right.	 xx0300000186 **Values for IRB 2600 -20/1.65, -12/1.65, -12/1.85:** • A: Measuring tool, play • B: 140 mm • C: 85 mm • F: 40N
5	Remove the load and set the dial indicator to zero.	
6	Apply load F in the opposite direction, as shown in the figure to the right.	 xx0300000187 **Values for IRB 2600 - 20/1.65, -12/1.65, -12/1.85:** • A: Measuring tool, play • B: 140 mm • C: 85 mm • F: 40N
7	Remove the load and measure the play by reading the dial indicator.	The maximum play allowed at the given distance from the center of axis 5 is, for robot version: • IRB 2600 -20/1.65, -12/1.65, -12/1.85: **0.12 mm**

4.4.5 Measuring the play, axis 6

General

This section is only valid for IRB 2600. For IRB 2600ID, see section *Measuring the play, axis 6 (ID upper arm) on page 282*.

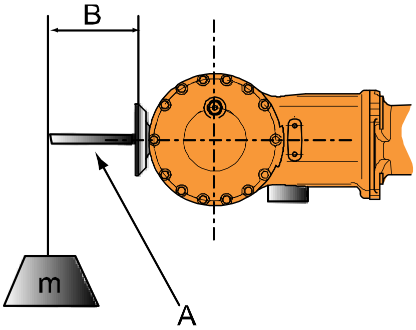
After reassembly due to repair work or any other reason, the play in axis 5 and 6 must be checked to ensure the repetition accuracy of the robot positioning. The procedure for axis 6 is detailed below.

Required equipment

Equipment	Article number	Note
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Measurement, axis 6

The procedure below details how to measure the play in axis 6.

	Action	Information
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Fit the *measuring tool, play* to the turning disc.	Article number is specified in *Required equipment on page 277*.
3	Attach a weight (m) at a distance (B) from the wrist flange, in order to avoid the effects of play on axis 5.	 xx0300000188 **Values for robot versions IRB 2600 -20/1.65, -12/1.65, -12/1.85:** • A: Measuring tool, play • B: 140 mm • m: 10 kg

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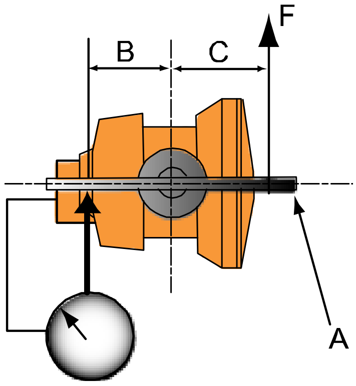
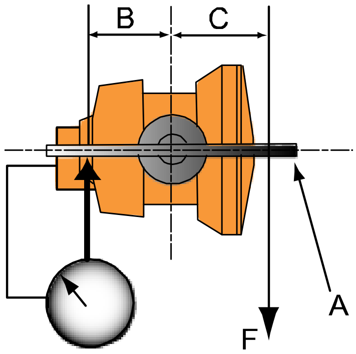
	Action	Information
4	Apply load F in one direction.	 xx0300000189 **Values for robot versions IRB 2600 -20/1.65, -12/1.65, -12/1.85:** • A: Measuring tool, play • B: 100 mm • C: 150 mm • F: 40N
5	Remove the load and set the dial indicator to zero.	
6	Apply load F in the opposite direction, as shown in the figure to the right.	 xx0300000190 **Values for robot versions IRB 2600 -20/1.65, -12/1.65, -12/1.85:** • A: Measuring tool, play • B: 100 mm • C: 150 mm • F: 40N
7	Remove the load and measure the play by reading the dial indicator.	The maximum play allowed at the given distance (B) from the center of axis 6 is, for robot version: • Values for IRB 2600 -20/1.65, -12/1.65, -12/1.85: **0.22 mm**

4.4.6 Measuring the play, axis 5 (ID upper arm)

General

This section is only valid for IRB 2600ID. For measuring the play of IRB 2600, see *Measuring the play, axis 5 on page 275*.

After reassembly due to repair work or any other reason, the play in axis 5 and 6 must be checked to ensure the repetition accuracy of the robot positioning.

Required equipment

Equipment, etc.	Art. no.	Note
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Turning disk adapter	3HAC027717-020	
Measuring tool	3HAB9238-1	For measuring play.
Measuring bracket	3HAC032976-001	
Dial indicator with a magnetic foot	-	
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Measurement, axis 5

Use this procedure to measure the play of axis 5.

	Action	Information
1	Move the robot to calibration position. Turn axis 4 to +90°.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	Fit the *turning disk adapter* to the turning disk.	Art. no. is specified in *Required equipment on page 279*.
4	Fit the *measuring tool* to the turning disk adapter.	Art. no. is specified in *Required equipment on page 279*.

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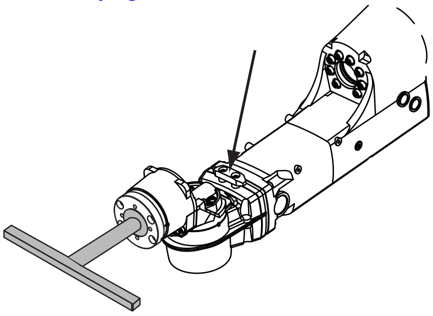
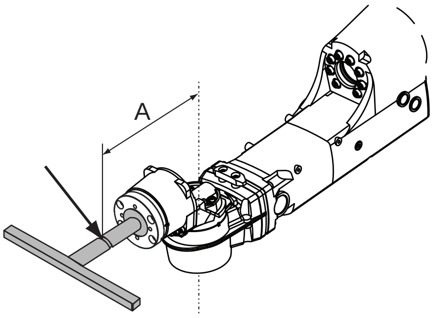
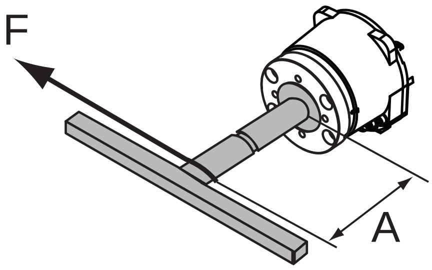
	Action	Information
5	Fit the *measuring bracket* to the wrist. Use the holes that are pointed out in the figure.	Art. no. is specified in *Required equipment on page 279*.  xx1100000688
6	Fit the magnetic foot of the *dial indicator* on the measuring bracket.	
7	Place the tip of the dial indicator on the milled surface of the measuring tool shaft.	 xx1100000689 Distance from the center line of axis 5. IRB 2600ID - 15/1.85: A 235 mm IRB 2600ID - 8/2.00: A 300 mm
8	Verify that axis 5 is put in calibration position.	
9	Apply load F=30N with a dynamometer at the distance A from the turning disk.	 xx1100000691 A 140 mm
10	Remove the load and set the dial indicator to zero.	

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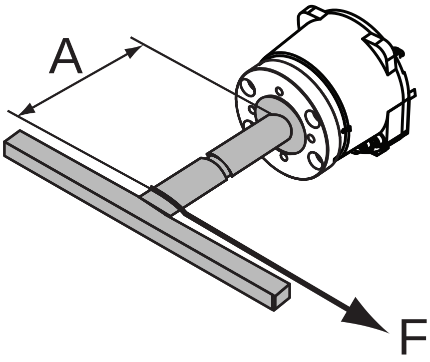
	Action	Information
11	Apply load F=30N in the opposite direction (180°), at the distance A from the turning disk.	 xx1100000693 A 140 mm
12	Remove the load and measure the play by reading the dial indicator.	The maximum play allowed is: • IRB 2600ID - 15/1.85: 0.25 mm • IRB 2600ID - 8/2.00: 0.32 mm
13	Turn axis 5 to +90°.	
14	Repeat *step 9* to *step 12*.	
15	Turn axis 5 to -90°.	
16	Repeat *step 9* to *step 12*.	

4.4.7 Measuring the play, axis 6 (ID upper arm)

General

This section is only valid for IRB 2600ID. For measuring the play of IRB 2600, see *Measuring the play, axis 6 on page 277*.

After reassembly due to repair work or any other reason, the play in axis 5 and 6 must be checked to ensure the repetition accuracy of the robot positioning.

Required equipment

Equipment, etc.	Art. no.	Note
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Turning disk adapter	3HAC027717-020	
Measuring tool	3HAB9238-1	For measuring play.
Measuring bracket	3HAC032976-001	
Dial indicator with magnetic foot	-	
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Measurement, axis 6

Use this procedure to measure the play of axis 6.

	Action	Information
1	Move the robot to calibration position. Turn axis 4 to +90°.	
2	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
3	Fit the *turning disk adapter* to the turning disk.	Art. no. is specified in *Required equipment on page 282*.
4	Fit the *measuring tool* to the turning disk adapter.	Art. no. is specified in *Required equipment on page 282*.

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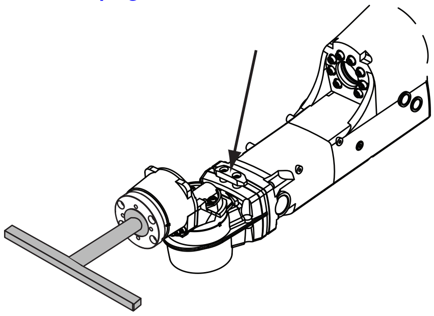
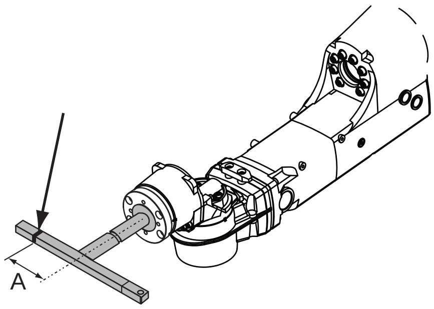
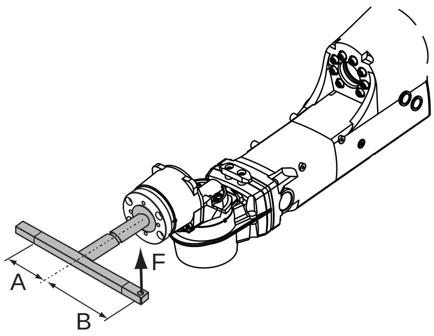
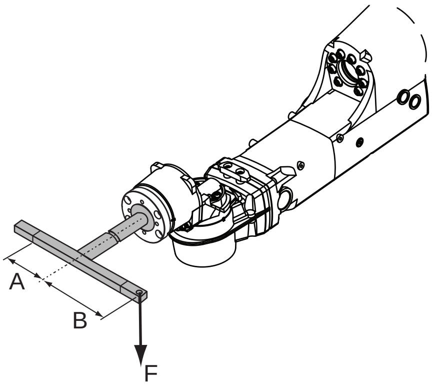
	Action	Information
5	Fit the *measuring bracket* to the wrist. Use the holes that are pointed out in the figure.	Art. no. is specified in *Required equipment on page 282*.  xx1100000688
6	Fit the magnetic foot of the *dial indicator* on the measuring bracket.	
7	Place the tip of the dial indicator on the marking.	 xx1100000690 Distance from the rotation center of axis 6: A 100 mm
8	Verify that axis 6 is put in calibration position.	
9	Apply load F=40N upwards with a dynamometer on the opposite side of the dial indicator, at a distance B from the rotation center of axis 6.	 xx1100000692 A 100 mm (dial indicator) B 140 mm
10	Remove the load and set the dial indicator to zero.	

Continues on next page

	Action	Information
11	Apply load F=40N downwards at a distance B from the rotation center of axis 6.	 xx1100000694 A 100 mm (dial indicator) B 140 mm
12	Remove the load and measure the play by reading the dial indicator.	The maximum play allowed is: • IRB 2600ID - 15/1.85: 0.20 mm • IRB 2600ID - 8/2.00: 0.22 mm
13	Turn axis 6 to +180°.	
14	Repeat *step 9* to *step 12*.	

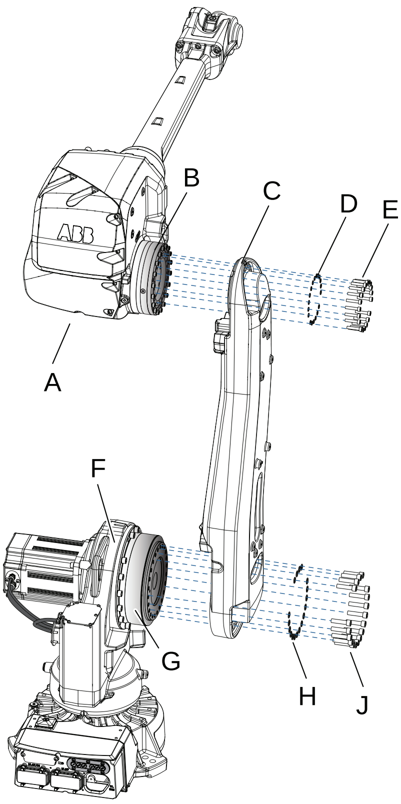
4.5 Lower arm

4.5.1 Replacing the lower arm

Location of lower arm

The lower arm is located as shown in the figure.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



xx0800000360

A	Upper arm
B	Gearbox axis 3
C	Lower arm
D	Washer (12 pcs)
E	Attachment screws M8x40 quality Steel 12.9 Gleitmo (12 pcs)
F	Frame
G	Gearbox axis 2
H	Washer (17 pcs)
J	Attachment screws M8x40 quality Steel 12.9 Gleitmo (17 pcs)

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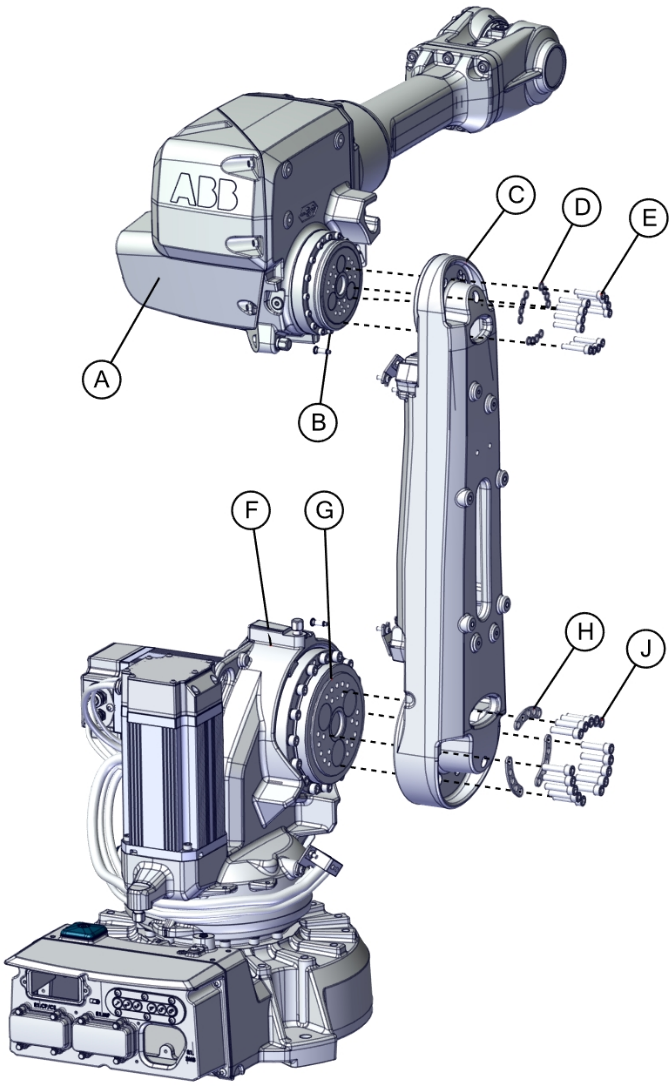
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



xx1800000933

A	Upper arm
B	Gearbox axis 3
C	Lower arm
D	Washer (12 pcs)
E	Attachment screws M8x40 quality Steel 12.9 Gleitmo (12 pcs)
F	Frame
G	Gearbox axis 2
H	Washer (3 pcs)
J	Attachment screws M10x40 12.9 Gleitmo 603+Geomet 500 (15 pcs)

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Required equipment

Equipment	Note
Lower arm	For spare parts no. see Spare parts - *Lower arm and motors* in *Product manual, spare parts - IRB 2600*.
Lifting eye	M8
Locking liquid	Loctite 2400 (or equivalent Loctite 243) Clean Room robots
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing the lower arm

Use this procedure to remove the lower arm.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	

Continues on next page

	Action	Note
2	Move the robot to the position shown in the figure.	 xx0800000336
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Remove the *cable package* from all axes except in the base.	How to remove the cable package in frame, lower arm and armhouse is described in sections: • *Removing cable harness in frame on page 207* • *Removing cable harness in lower arm and armhouse on page 208*
5	Secure the upper arm with a roundsling in an overhead crane.	
6	Remove the *complete upper arm* and put it on a loading pallet.	How to remove the complete upper arm is described in section: • *Removing the complete upper arm on page 253*
7	**CAUTION** The robot lower arm weighs . 35 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 30 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	

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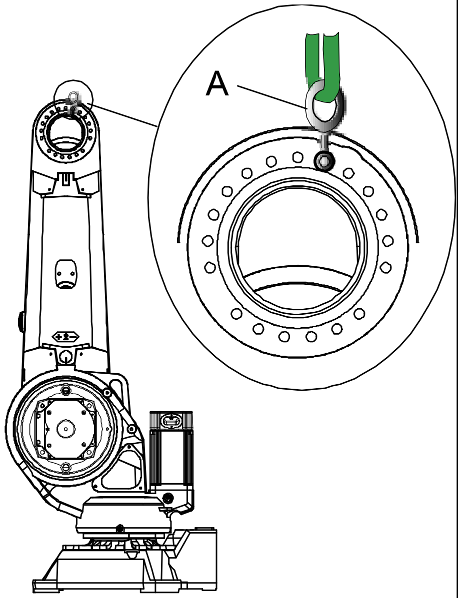
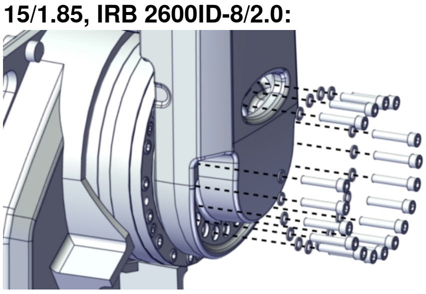
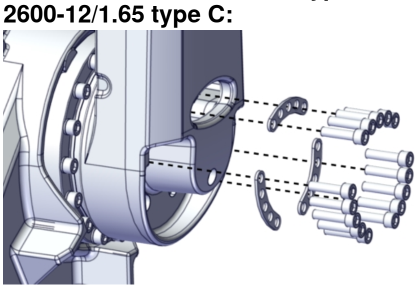
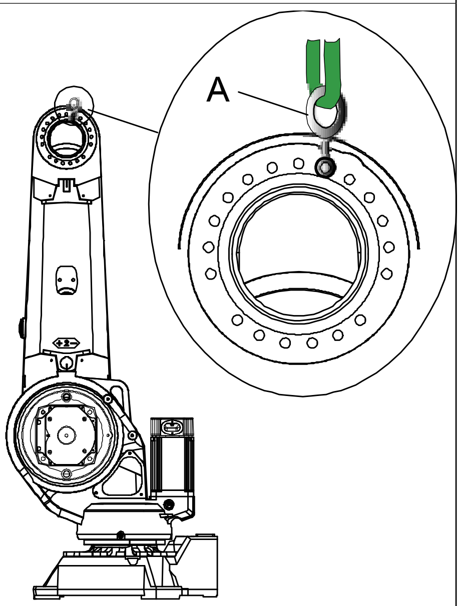
	Action	Note
8	Fit a *lifting lug* in one of the upper holes in the lower arm, for the attachment screws.	 xx0800000379 Parts: • A: Lifting lug
9	Remove the *attachment screws and washers* that secure the lower arm to the axis-2 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:**  xx1800000935 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:**  xx1800000934
10	Remove the lower arm.	

Continues on next page

Refitting the lower arm

Use this procedure to refit the lower arm.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**CAUTION** The robot lower arm weighs . 35 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 30 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	
3	Fit a *lifting lug* in one of the upper holes in the lower arm, for the attachment screws.	 xx0800000379 Parts: • A: Lifting lug
4	Secure the lower arm with a roundsling in an overhead crane and lift it to the robot.	

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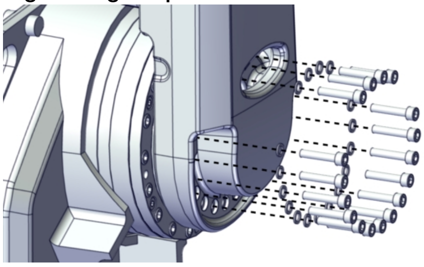
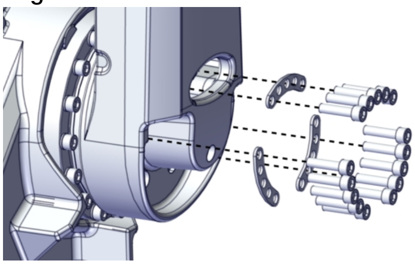
	Action	Note
5	Refit the *attachment screws and washers* to secure the lower arm to the axis-2 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Attachment screws: M8x40 quality steel Gleitmo 12.9 (17 pcs) Washers: 3HAA1001-172 (17 pcs) Tightening torque: 35 Nm.  xx1800000935 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Attachment screws: M10x40 12.9 Gleitmo 603+Geomet 500 (15 pcs) Washers: 3HAC043534-001 (3 pcs) Tightening torque: 50 Nm ± 5 Nm and 90° angle ± 10°.  xx1800000934
6	Secure the complete upper arm with roundslings in an overhead crane and lift it to the robot.	
7	Refit the *complete upper arm*.	How to refit the complete upper arm is described in section: • *Refitting the complete upper arm on page 258*
8	Refit the *cable package*.	How to refit the cable package in frame, lower arm and armhouse is described in sections: • *Refitting the cable harness in the frame on page 215* • *Refitting the cable harness in the lower arm and armhouse on page 224*

Continues on next page

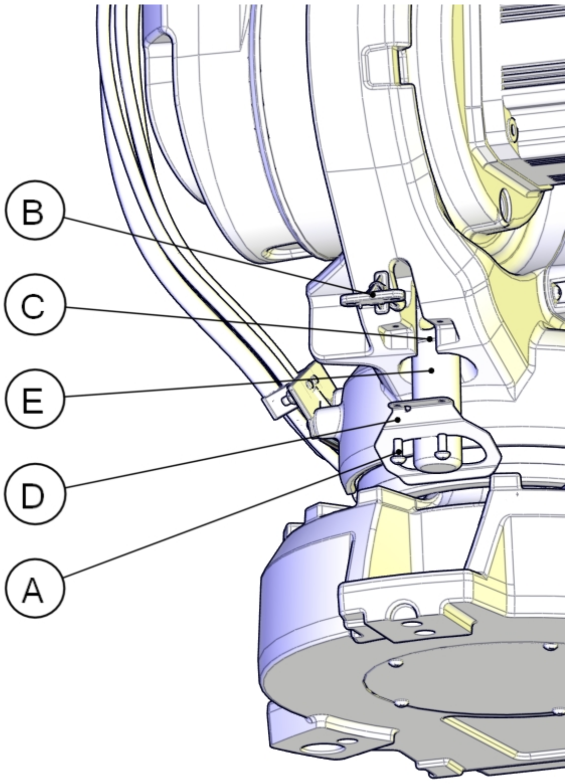
	Action	Note
9	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
10	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.6 Frame and base

4.6.1 Replacing stop pin axis 1

Location of stop pin axis 1

The stop pin axis 1 is located as shown in the figure.



xx0800000045

A	Attachment screws M6x16 quality 8.8-A2F (2 pcs)
B	Bracket
C	O-ring (2 pcs) - Not used if bracket (D) is installed.
D	Bracket
E	Stop pin

Required equipment

Equipment	Note
Stop pin	For spare parts number, see Spare parts - *Frame and base* in *Product manual, spare parts - IRB 2600*.
Locking liquid	Loctite 2400 (or equivalent Loctite 243)
Standard toolkit	Content is defined in section *Standard tools on page 456*.

Continues on next page

Equipment	Note
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Removing the stop pin, axis 1

Use this procedure to remove the stop pin axis 1.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Remove the *attachment screws* securing the *bracket* and *stop pin*.	See the figure in • *Location of stop pin axis 1 on page 293*
3	Remove the *bracket* and *stop pin*.	See the figure in • *Location of stop pin axis 1 on page 293*

Refitting the stop pin, axis 1

Use this procedure to refit the stop pin axis 1.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Fit the two *o-rings* on the stop pin. **Note** The o-rings are not used when bracket (D) is installed.	See the figure in • *Location of stop pin axis 1 on page 293*

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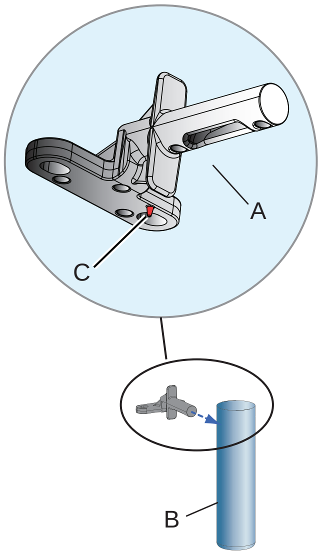
	Action	Note
3	Fit the *stop pin* on the *bracket*. **Note** The small spike on the bracket shall be pointing downwards for correct fitting of the stop pin.	 xx0800000453 Parts: • A: Bracket • B: Stop pin • C: Small spike
4	Secure the stop pin together with bracket (D) on the frame with its *attachment screws*. Use Locking liquid	Loctite 2400 (or equivalent Loctite 243) Tightening torque: 10 Nm See the figure in • *Location of stop pin axis 1 on page 293*
5	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.6.2 Replacing the base

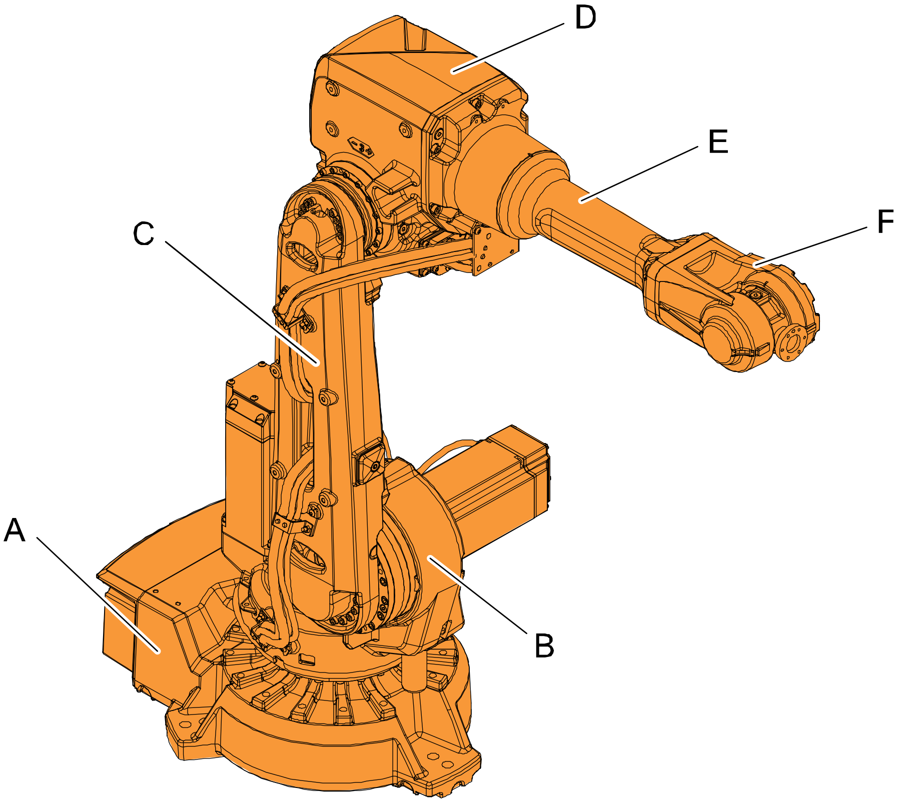
Location of base and complete arm system

The complete arm system is defined as:

- complete upper arm (includes: wrist unit, tubular shaft unit and armhouse)
- lower arm
- frame
- axis-1 gearbox

The location of the base and the complete arm system is shown in the figure.

The figure shows IRB 2600 Standard but is also valid for IRB 2600ID.



xx0900000320

A	Base
B	Frame
C	Lower arm
D	Arm house (part of complete upper arm)
E	Tubular shaft (part of complete upper arm)
F	Wrist unit (part of complete upper arm)

Continues on next page

Required equipment

Equipment	Article number	Note
Roundslings	-	Lengths: 2 m (1 pcs), 1.5 m (1 pcs) Lifting capacity: 1,000 kg.
Support legs	3HAC15535-1	3 pcs
Guide pin, M8x150	3HAC15520-2	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.** Always use guide pins in pairs.
Guide pin, M12x150	3HAC13056-2	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C.** Always use guide pins in pairs.
Lifting eye	-	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.** M8 3 pcs
Lifting eye	-	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C.** M12 3 pcs
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.
Gasket	3HAC065190-001	Included with spare part base. 3 pcs
Cleaning agent	-	Loctite 7063 For cleaning.
Flange sealant **Only valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.**	-	Loctite 574 (or equivalent) For sealing.

Continues on next page

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

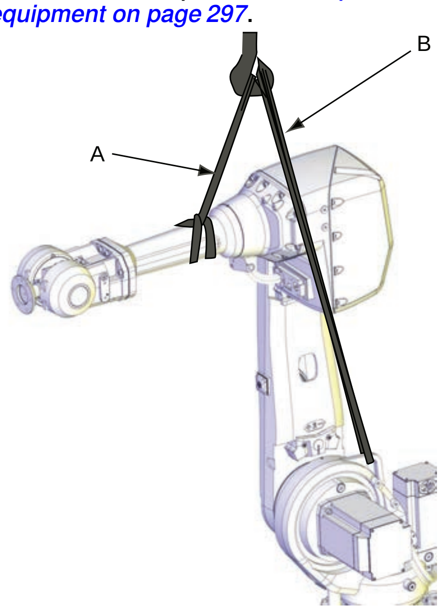
	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing the base

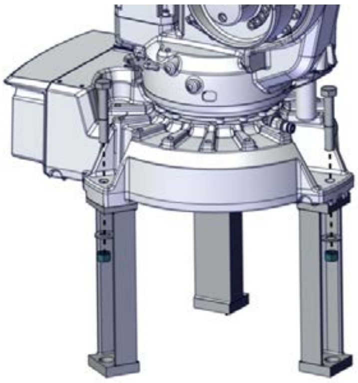
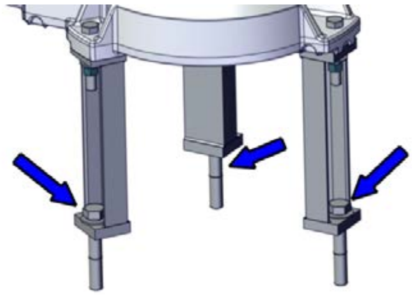
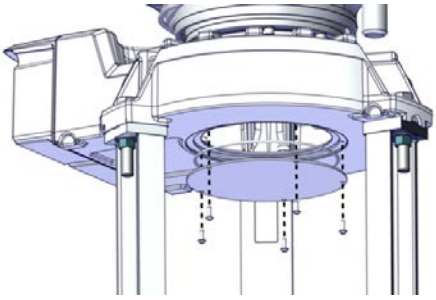
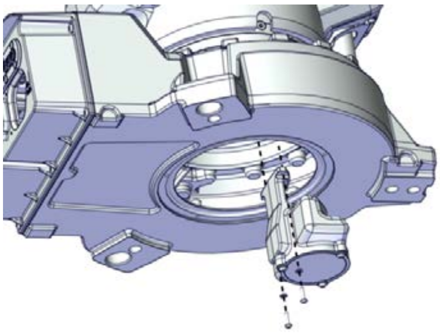
Use this procedure to remove the complete arm system from the base.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Jog the robot to: • Axis 1: 0° • Axis 2: 0° • Axis 3: -10° • Axis 4: 0° • Axis 5: 0° • Axis 6: 0°	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the safeguarded space.	

Continues on next page

	Action	Note
4	Drain the axis-1 gearbox. **Note** Draining is time-consuming. Elapsed time varies depending on the temperature of the oil.	How to drain oil is detailed in section • *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*
5	Remove the *cable harness* in the base, the frame and the lower arm of the robot. **Tip** Wrap up the cabling against the frame to keep it undamaged during the remaining work.	How to remove the cable harness in base and frame is detailed in sections: • *Removing cable harness in base on page 202* • *Removing cable harness in frame on page 207* • *Removing cable harness in lower arm and armhouse on page 208*
6	Secure the robot with *roundslings* in an overhead crane. Stretch the roundslings so that the robot weight is secured when removing foundation bolts in next step.	Dimensions are specified in *Required equipment on page 297*.  xx1800001211 A Roundsling 1.5 m B Roundsling 2 m
7	**CAUTION** The IRB 2600/IRB 2600 ID robot weighs 280 kg. All lifting accessories used must be sized accordingly!	
8	Remove the bolts that secure the robot to the foundation.	

Continues on next page

	Action	Note
9	Lift the robot and fit three support legs to the robot base, using bolts, washers and nuts. **DANGER** Working underneath the manipulator without safely securing the support legs between the robot base and the foundation will result in serious or fatal injury. Make sure the robot is stable and safely secured to the foundation via the support legs, before working underneath the robot. Keep the lifting accessories stretched for extra safety precautions.	 xx1800000874
10	Lower the robot and secure the support legs to the foundation, using bolts and washers.	 xx1800000875
11	Remove the *cover plate* at the bottom of the base.	 xx1800000879
12	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Remove the expansion container, if available.	 xx1800000881

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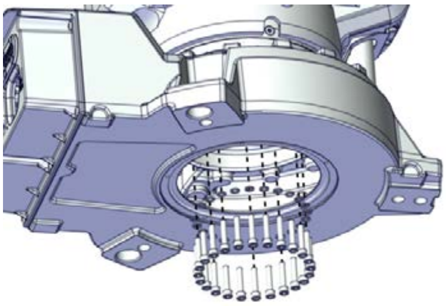
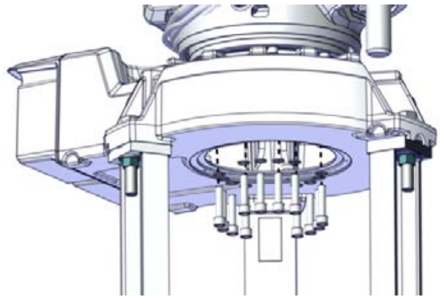
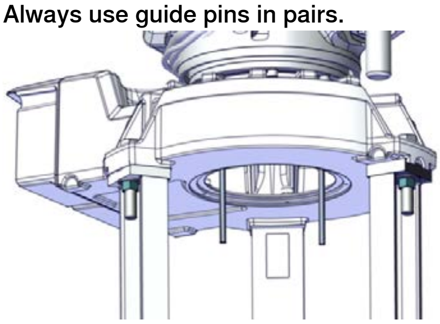
	Action	Note
13	Remove the base attachment screws and washers.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:**  xx1800000882 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:**  xx1800000880
14	Fit two guide pins in opposite holes in the axis-1 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Guide pin, M8x150: 3HAC15520-2 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Guide pin, M12x150: 3HAC13056-2 Always use guide pins in pairs.  xx1800000883
15	**CAUTION** The arm system and axis-1 gearbox weighs 235 kg together. All lifting accessories must be sized accordingly.	

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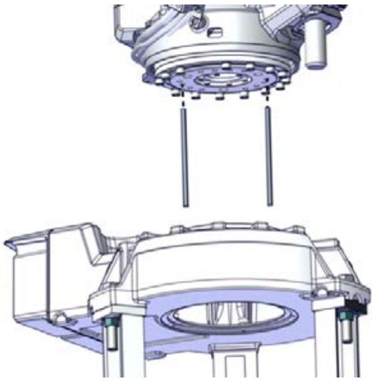
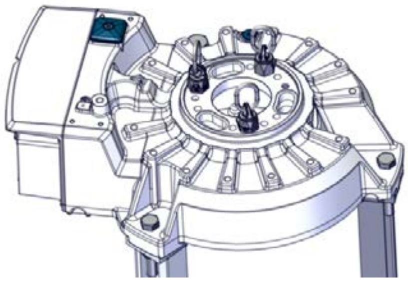
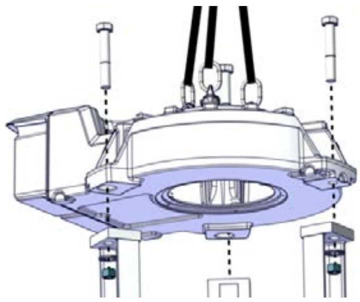
	Action	Note
16	Lift away the robot arm system. Remove the guide pins, if the arm system is about to be laid down on the floor. See *Illustration of robot put down on its side on page 368*.	 xx1800000884
17	**CAUTION** The weight of the base is 49 kg All lifting accessories used must be sized accordingly.	
18	Fit three lifting eyes to the base and secure with roundslings in an overhead crane or similar.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Lifting eye: M8 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Lifting eye: M12  xx1800000931
19	Remove the support legs attachments screws and remove the base from the support legs.	 xx1800000885

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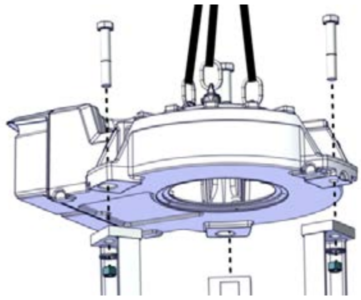
Refitting the base

Use this procedure to refit the complete arm system to the base.

	Action	Note
1	**CAUTION** The weight of the base is 49 kg All lifting accessories used must be sized accordingly.	
2	Fit three lifting eyes to the base and secure with roundslings in an overhead crane or similar.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Lifting eye: M8 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Lifting eye: M12
3	Fit the new base to the support legs and secure with the attachment screws.	 xx1800000885
4	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Remove residues of old Loctite and other contaminations from surfaces before applying new Loctite 574.	**Tip** Use Loctite 7063 (or similar) for cleaning.

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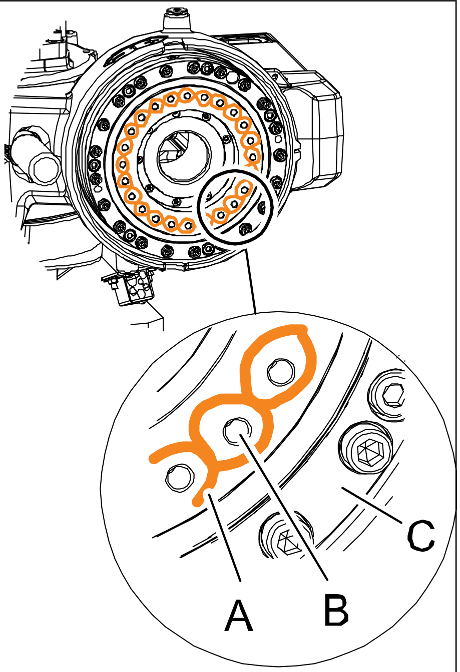
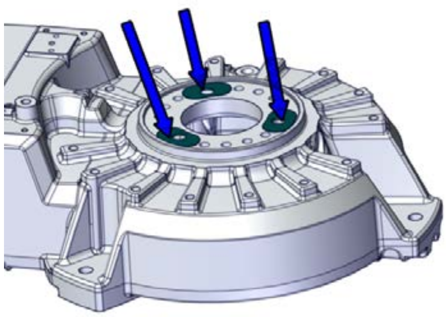
	Action	Note
5	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Apply *Loctite 574* around the *screw holes* on the axis-1 gearbox as shown in the figure.	 xx0800000353 Parts A Loctite 574 B Screw hole in axis-1 gearbox C Axis-1 gearbox
6	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Fit three new gaskets to the base. The gaskets are included with the gearbox spare part.	 xx1800000797
7	**CAUTION** The arm system and axis-1 gearbox weighs 235 kg together. All lifting accessories must be sized accordingly.	
8	Lift the arm system to the mounting site.	

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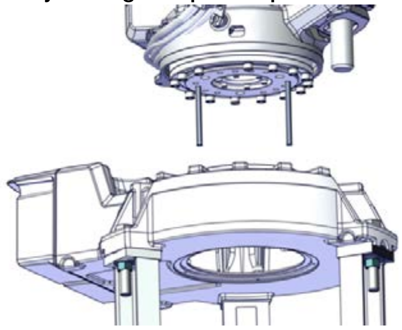
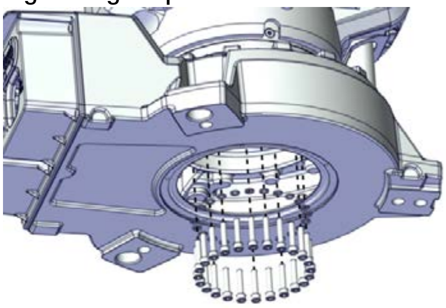
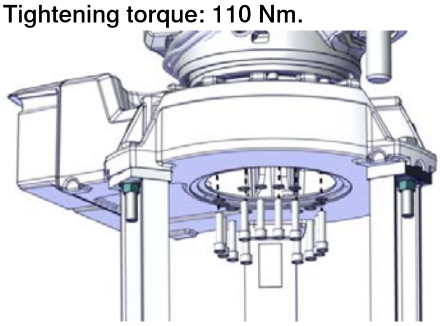
	Action	Note
9	Fit two guide pins in opposite holes in the axis-1 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Guide pin, M8x150: 3HAC15520-2 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Guide pin, M12x150: 3HAC13056-2 Always use guide pins in pairs.  xx1800000932
10	Lower the arm system against the base and secure with the *attachment screws* and *washers*.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Attachment screws: M8x40 quality Steel 12.9 Gleitmo and washers (24+24 pcs). Tightening torque: 35 Nm.  xx1800000882 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Attachment screws: M12x50 12.9 Gleitmo 603+Geomet 500 and washers (12+12 pcs). Tightening torque: 110 Nm.  xx1800000880

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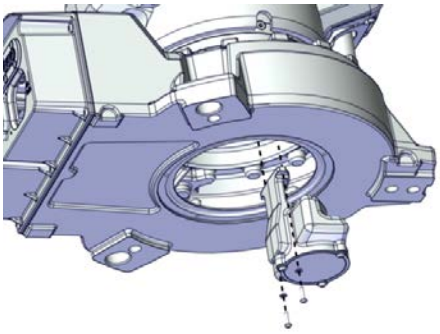
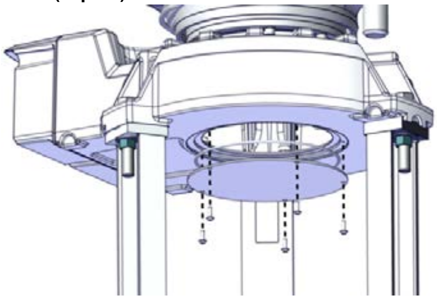
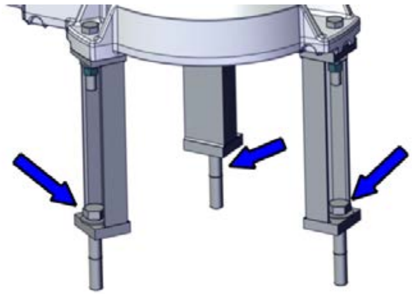
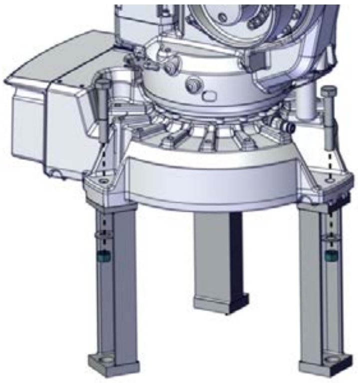
	Action	Note
11	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Refit the expansion container, if available.	 xx1800000881
12	Apply some grease to the *o-ring* and refit the o-ring between the cover and base.	
13	Refit the *cover plate* at the bottom of the base with its attachment screws.	Attachment screws: M6x16 quality 8.8-A2F (5 pcs)  xx1800000879
14	Remove the screws that secure the support legs to the foundation. **DANGER** Stretch the roundslings to make sure that the robot weight is secured.	 xx1800000875
15	Lift the complete robot and remove the support legs from the base.	 xx1800000874

Continues on next page

	Action	Note
16	Lower the robot and secure it to the foundation.	See *Orienting and securing the robot on page 68*.
17	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
18	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.7 Motors

4.7.1 Removing motors

Introduction

This procedure describes how to remove motors on all axes of the robot.

Note

For IRB 2600ID this section describes motors axes 1, 2, 3 and 4. Motors axes 5 and 6 are described in sections:

- Motor axis 5, section *Replacing motor axis 5 - IRB 2600ID on page 337*
- Motor axis 6, section *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*.

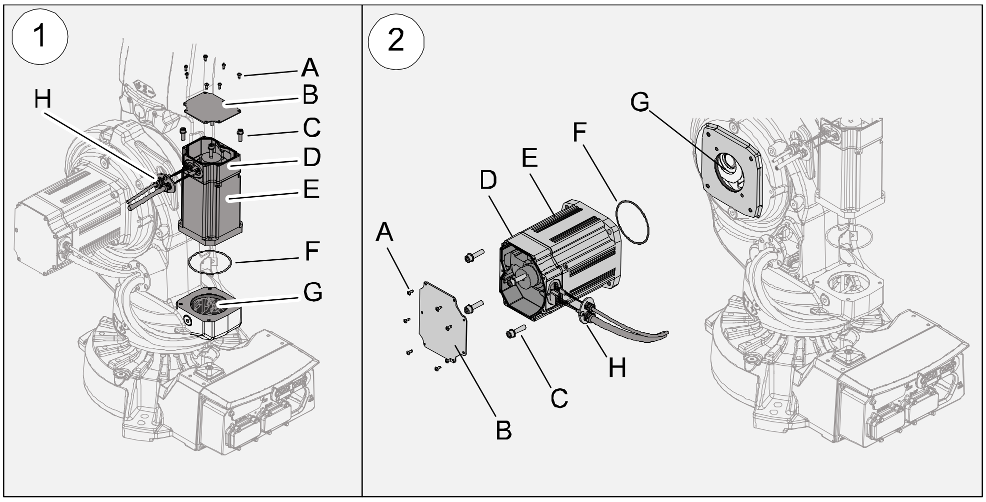
Location of axis-1 and axis-2 motors

The axis-1 and axis-2 motors are located as shown in the figure.

Motors:

(1) = Axis-1 motor

(2) = Axis-2 motor



xx0900000302

A	Attachment screws M5x16, quality Steel 8-A2F (7 pcs)
B	Motor cover
C	Attachment screws, axis-1 motor (4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
C	Attachment screws, axis-2 motor (4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
D	Connection box
E	Axis-1 motor
E	Axis-2 motor

Continues on next page

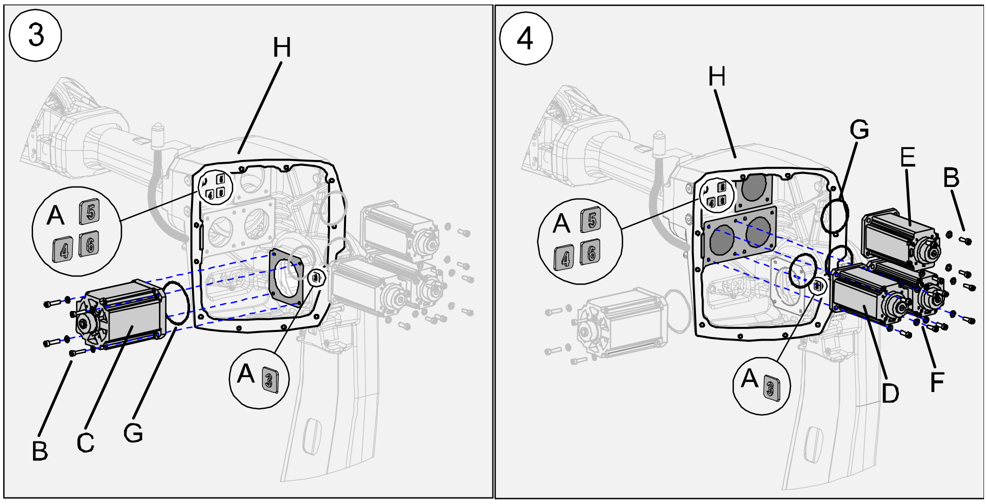
F	O-ring
G	Hole
H	Cable gland cover

Location of axis-3, axis-4, axis-5 and axis-6 motors

The axis-3, axis-4, axis-5 and axis-6 motors are located as shown in the figures.

IRB 2600 Standard.

Motors: (3) = Axis-3 motor. (4) = Axis-4, axis-5 and axis-6 motors.



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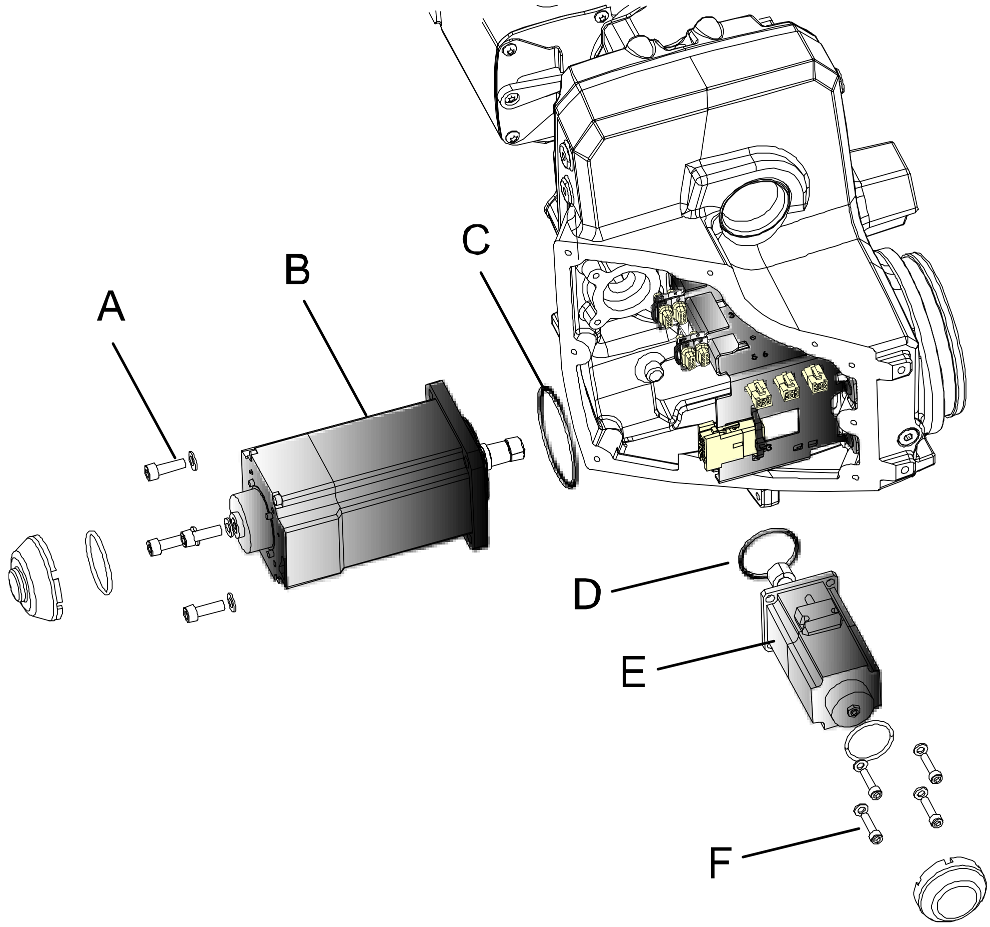
A	Markings inside armhouse, identifying the position of each motor
B	Attachment screws, axis-3 motor (4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
B	Attachment screws, axis-4, axis-5 and axis-6 motors (3x4 pcs) + washers. *Tightening torques and attachment screws on page 328*
C	Axis-3 motor
D	Axis-4 motor
E	Axis-5 motor
F	Axis-6 motor
G	O-ring (axis-4, axis-5 and axis-6)
H	Armhouse

Continues on next page

IRB 2600ID



xx1000000990

A	Attachment screws (4 pcs)
B	Motor axis 3
C	O-ring
D	O-ring
E	Motor axis 4
F	Attachment screws (4 pcs)

Connectors, motors axes 3 - 6

The figures shows the connectors in the armhouse.

- IRB 2600 Standard: Axes 3-6
- IRB 2600ID: Axes 3-4

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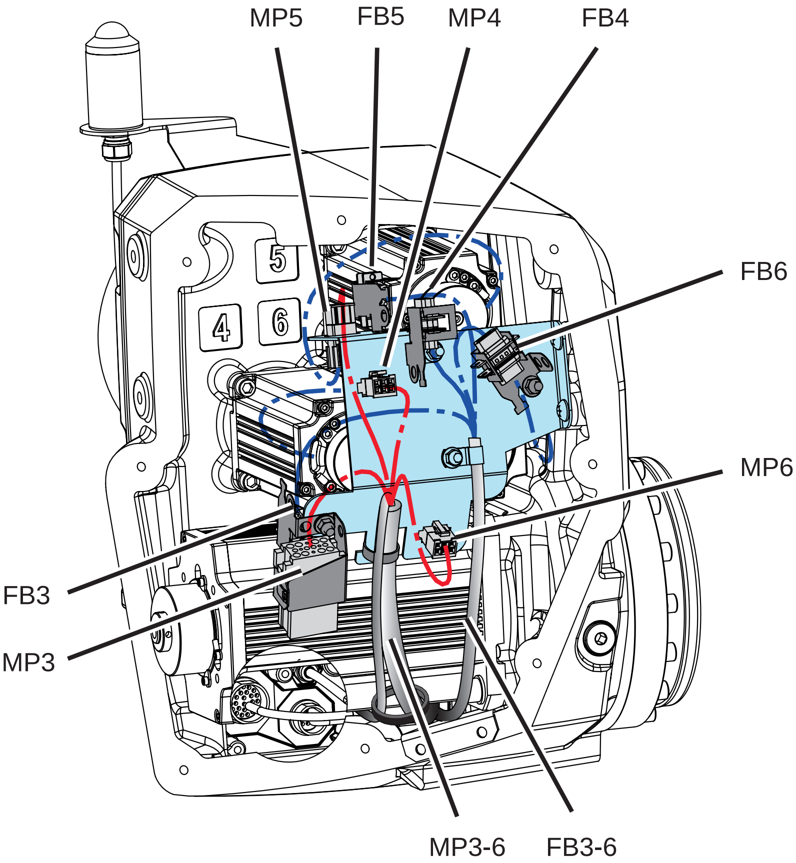
IRB 2600 Standard, motor type B



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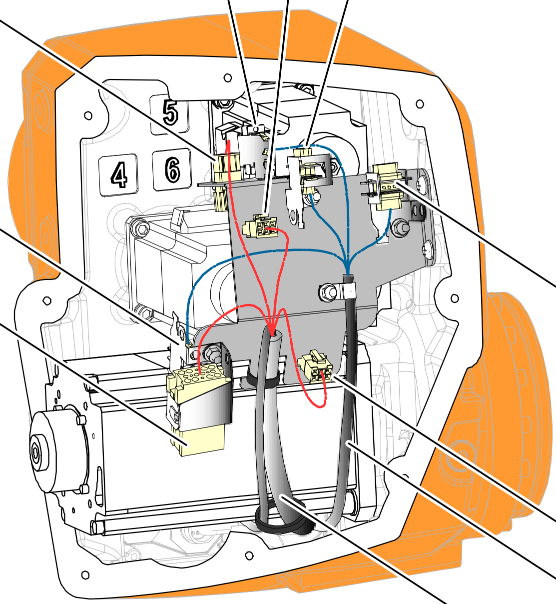
IRB 2600 Standard, motor type A



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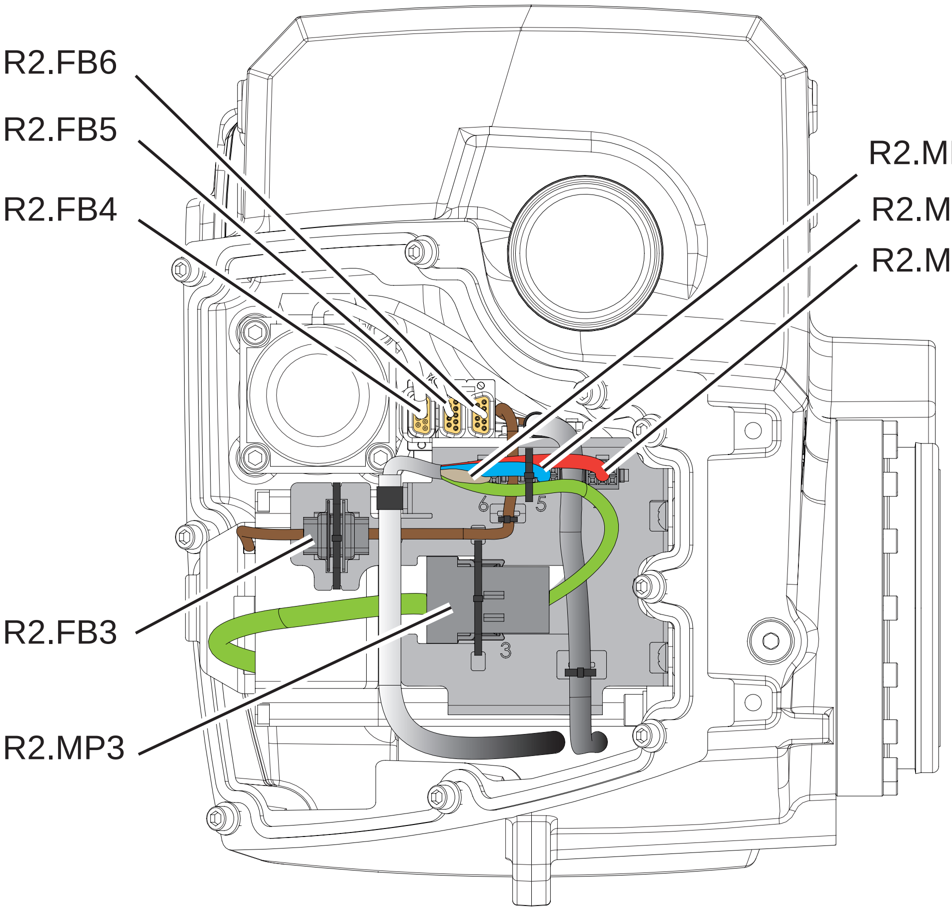
IRB 2600ID



xx1400002578

Required equipment

Equipment	Note
Threaded bar	2 pcs. Dimension: M8. Used for pressing out the axis-1 and axis-2 motors.
Extended reach hex bit socket head	Required for: • Axis-2 motor replacement: M6, length minimum 260 mm. • Axis-3 motor replacement: M6, length minimum 160 mm.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Continues on next page

Weights

The motors for the different axes weighs according to the table:

Motor	Weight in kg
Axis-1 motor	13 kg
Axis-2 motor	13 kg
Axis-3 motor	8 kg
Axis-4 motor	6.5 kg
Axis-5 motor	6.5 kg
Axis-6 motor	6.5 kg

CAUTION

All lifting equipment must be sized accordingly!

Deciding calibration routine

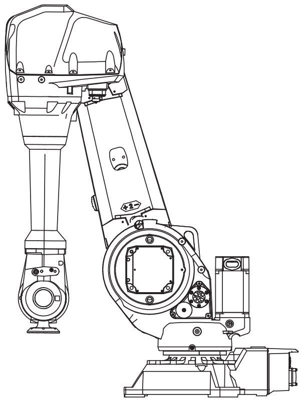
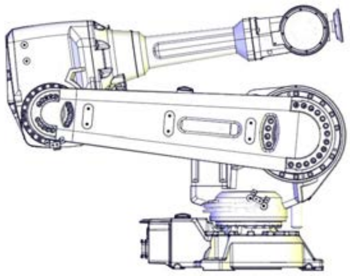
Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Continues on next page

Position of robot

Use this procedure to place the robot in the position recommended in order to facilitate replacement of motors.

	Action	Information
	Axis-1, axis-4, axis-5 and axis-6 motor (**IRB 2600 Standard**) Axis-1 and axis-4 motors (**IRB 2600ID**) • Move the robot to a position where the wrist is pointing to the floor, as shown in the figure. This will make it possible to remove the motors without draining the oil from the gearbox.	 xx0800000388
	Axis-2 motor • Move the robot to a position where the lower arm rests firmly on the damper of axes 2 and 3. Release the brake of axis 2 to be sure that the lower arm rests in the end position.	 xx1100000548
	Axis-3 motor • Move axis-2 to 0° and axis-3 to maximal +. Release the brake of axis-3 to be sure that the upper arm is completely vertical and rests against the damper of axis-2 and axis-3.	

Draining gearbox

Use this procedure to drain gearboxes, if needed.

> **Note**
>
> Draining of gearbox is only needed when removing the axes 2 and 3 motors.

	Action	Note
1	Axis-1 motor: • Draining of gearbox is not needed.	-
2	Axis-2 motor: • The gearbox has to be drained before removing the motor.	How to drain the gearbox is described in section: • *Changing the oil, axis-2 gearbox on page 163*

Continues on next page

	Action	Note
3	Axis-3 motor: • The gearbox has to be drained before removing the motor.	How to drain the gearbox is described in section: • *Changing the oil, axis-3 gearbox on page 167*
4	**IRB 2600** - axes 4, 5, 6: • Draining of gearbox is not needed if robot is positioned as recommended. **IRB 2600ID** - axis 4: • Draining of gearbox is not needed if robot is positioned as recommended.	-

Removing motors

Use this procedure to remove the axis-1, axis-2, axis-3, axis-4, axis-5 and axis-6 motors.

Note

How to replace motors axes 5 and 6 on IRB 2600ID is described in sections:

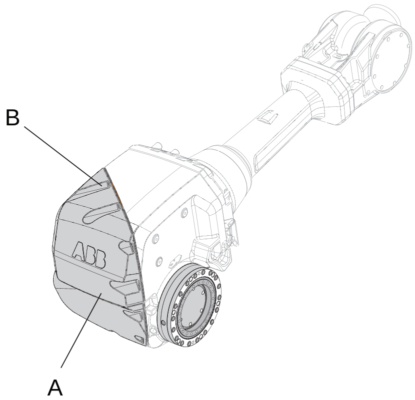
- *Replacing motor axis 5 - IRB 2600ID on page 337*
- *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*

Note

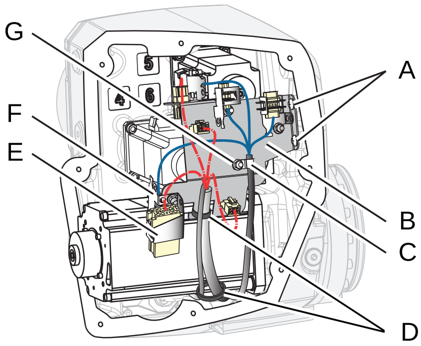
The procedure contains information how to remove motors on all axes of the robot. Some steps are only applicable to a certain motor. Follow the steps carefully in order not to miss vital information!

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Move the robot to the recommended position for the motor that shall be removed.	Also see • *Position of robot on page 315*
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Check if the gearbox needs to be drained.	Also see • *Draining gearbox on page 315*

Continues on next page

	Action	Note
5	**Only applicable to axis-3, axis-4, axis-5 and axis-6 motors!** Remove the cover in the back of the arm house. **WARNING** The robot must never be run without the cover in the armhouse fitted! It is a vital supporting part of the robot.	 xx0800000389 Parts: • A: Cover • B: Attachment screws (8 pcs) + washers.
6	**Only applicable to motors on axes 1 and 2 with fan fitted!** Remove the fan before starting the removal!	How to remove the fan is detailed in section: • *Installation of cooling fan for motors (option) on page 90*
7	**Only applicable to axis-1 and axis-2 motors!** Remove the motor cover.	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*
8	**Only applicable to axis-1 and axis-2 motors!** Remove the cable gland cover.	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*
9	**Only applicable to axis-1 and axis-2 motors!** Remove the connection box. **Note** Only needed if the motor shall be replaced with a new one.	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*
10	Disconnect the *motor cables*.	**Note** When removing motors 4,5 or 6 the cables of motor axis 3 must be disconnected too. This must be done in order to be able to remove the bracket on top of motors axes 4, 5 and 6.

Continues on next page

	Action	Note
11	**Only applicable to motors axes 3, 4, 5 and 6 on IRB 2600 Standard and axes 3 and 4 on IRB 2600ID!** Remove the *bracket* to reach the attachment screws of the motors.	The figure shows IRB 2600 Standard.  xx0900000372 Parts: • A: Attachment screws, M6x16 quality 8.8-A2F (2 pcs) • B: Bracket • C: Clamp • D: Cable straps • E: Connection bracket • F: Connection bracket • G: Hexagon nut, M5 quality steel 8-A2F

Continues on next page

	Action	Note
12	In order to release the brakes of the motor to be removed, connect the 24 VDC power supply to the motor connector. **Tip** **For axis-2 and axis-3 motors:** release the motor brake until the arm firmly rests on the damper for each axis respectively. See positions in *Position of robot on page 315*.	Connectors and pins: • Axis-1 motor: R2.MP1 - + : pin 2 - -: pin 5 • Axis-2 motor: R2.MP2 - + : pin 2 - -: pin 5 • Axis-3 motor: R2.MP3 - + : pin 2 - -: pin 5 • Axis-4 motor: R2.MP4 - + : pin 4 - - : pin 6 • Axis-5 motor: R2.MP5 - + : pin 4 - - : pin 6 • Axis-6 motor: R2.MP6 **IRB 2600:** - + : pin 4 - - : pin 6 **IRB 2600ID:** - + : pin 7 - -: pin 8 **CAUTION** The connections for the motor brakes (24 VDC connection) are phase dependent. If the connection on the pins is switched, it can cause severe damage to vital parts.
13	**Note** Whenever parting/mating motor and gearbox, the gears may be damaged if excessive force is used!	
14	Remove the attachment screws securing the motor. If needed use a 300 mm extension for bits 1/2" (Motor axis 1).	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*
15	If required, press the motor out of position by fitting two threaded bars in the threaded holes in the motor flange.	**Note** Always use removal tools in pairs diagonal to each other.
16	Remove the motor!	**CAUTION** Lift the motor gently in order not to damage pinion or gears.

Continues on next page

	Action	Note
17	**Only applicable to motor axis 1!** Cover the hole if replacement of motor axis 1 is not immediate, in order to avoid contamination.	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*
18	**Only applicable to motors axes 4, 5 and 6!** Check that the o-ring also is removed. It might stay in the armhouse when the motor is removed.	See the figure in: • *Location of axis-1 and axis-2 motors on page 308*

4.7.2 Refitting motors

Introduction

This procedure describes how to refit motors on all axes of the robot.

WARNING

When a motor is replaced, make sure to use the correct type of new motor. Motors of different types may not be compatible. See the *Spare parts manual* on myABB business portal (*www.abb.com/myABB*).

Note

For IRB 2600ID this section describes motors axes 1, 2, 3 and 4. Motors axes 5 and 6 are described in sections:

- Motor axis 5, see section *Replacing motor axis 5 - IRB 2600ID on page 337*
- Motor axis 6, see section *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*.

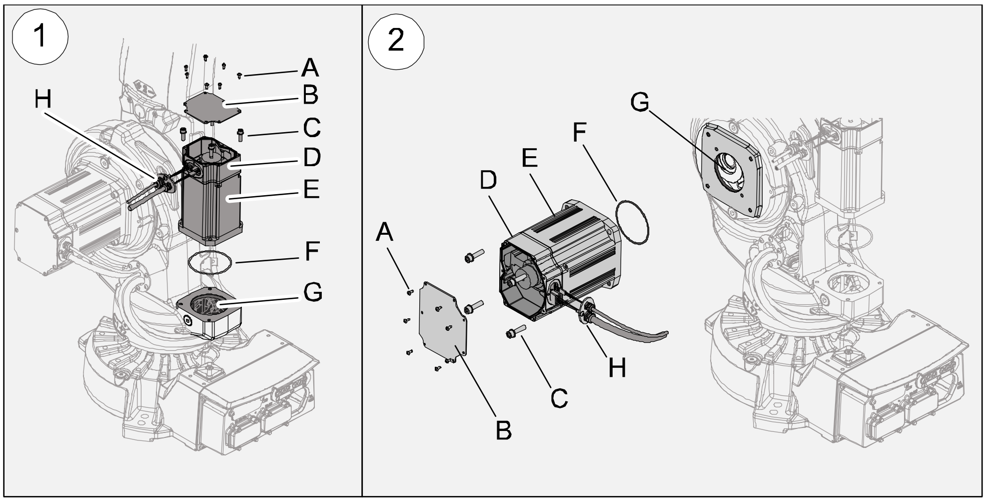
Location of axis-1 and axis-2 motors

The axis-1 and axis-2 motors are located as shown in the figure.

Motors:

(1) = Axis-1 motor

(2) = Axis-2 motor



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A	Attachment screws M5x16, quality Steel 8-A2F (7 pcs)
B	Motor cover
C	**Axis-1 motor:** Attachment screws(4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
C	**Axis-2 motor:** Attachment screw (4 pcs) + washers. See *Tightening torques and attachment screws on page 328*

Continues on next page

D	Connection box
E	Axis-1 motor
E	Axis-2 motor
F	O-ring
G	Hole
H	Cable gland cover

Location of axis-3, axis-4, axis-5 and axis-6 motors

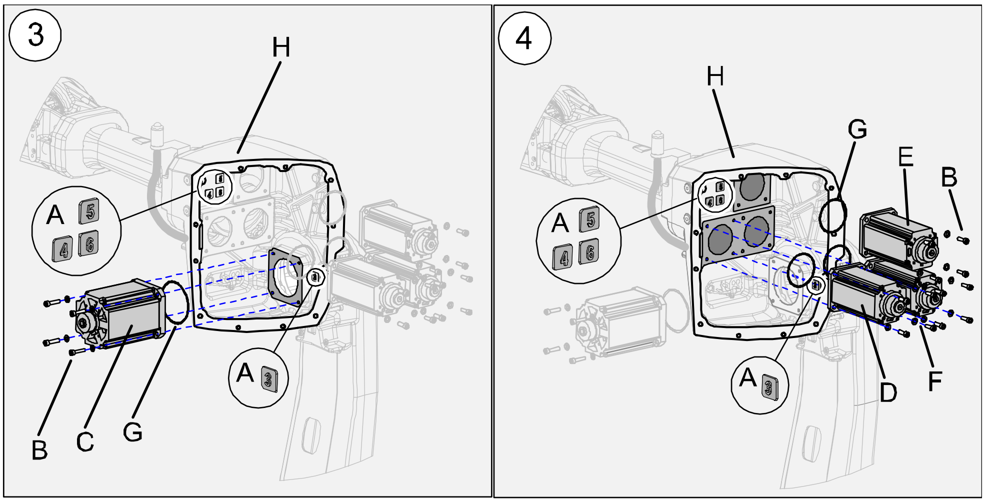
The axis-3, axis-4, axis-5 and axis-6 motors are located as shown in the figures.

IRB 2600 Standard.

Motors:

(3) = Axis-3 motor

(4) = Axis-4, axis-5 and axis-6 motors



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A	Markings inside armhouse, identifying the position of each motor
B	Attachment screws, axis-3 motor, (4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
B	Attachment screws, axis-4, axis-5 and axis-6 motors, (3x4 pcs) + washers. See *Tightening torques and attachment screws on page 328*
C	Axis-3 motor
D	Axis-4 motor
E	Axis-5 motor
F	Axis-6 motor
G	O-ring (axis-4, axis-5 and axis-6)
H	Armhouse

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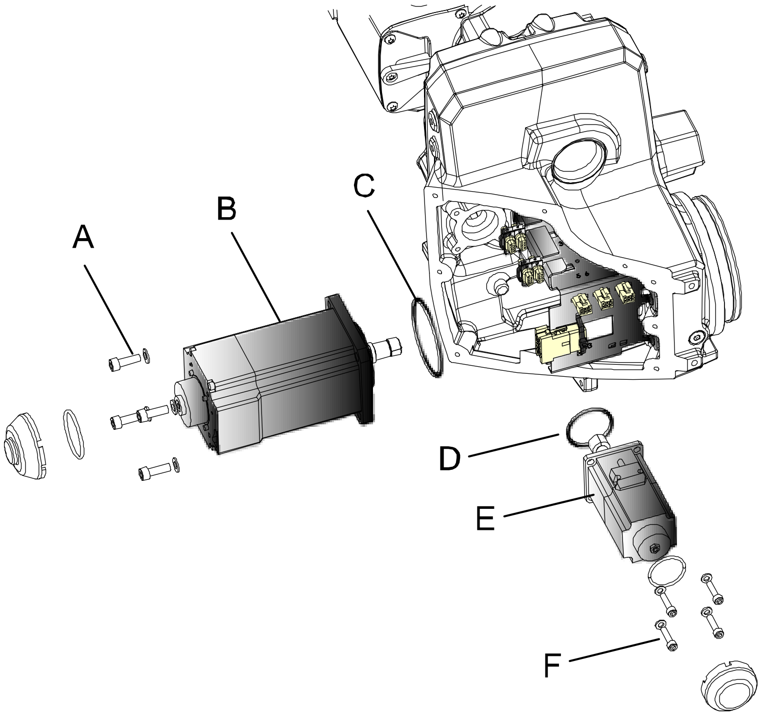
IRB 2600ID



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A	Attachment screws (4 pcs)
B	Axis-3 motor
C	O-ring
D	O-ring
E	Axis-4 motor
F	Attachment screws (4 pcs)

Connectors, motors axes 3 - 6

The figures shows the connectors in the armhouse:

- IRB 2600 Standard: Axes 3-6
- IRB 2600ID: Axes 3-4.

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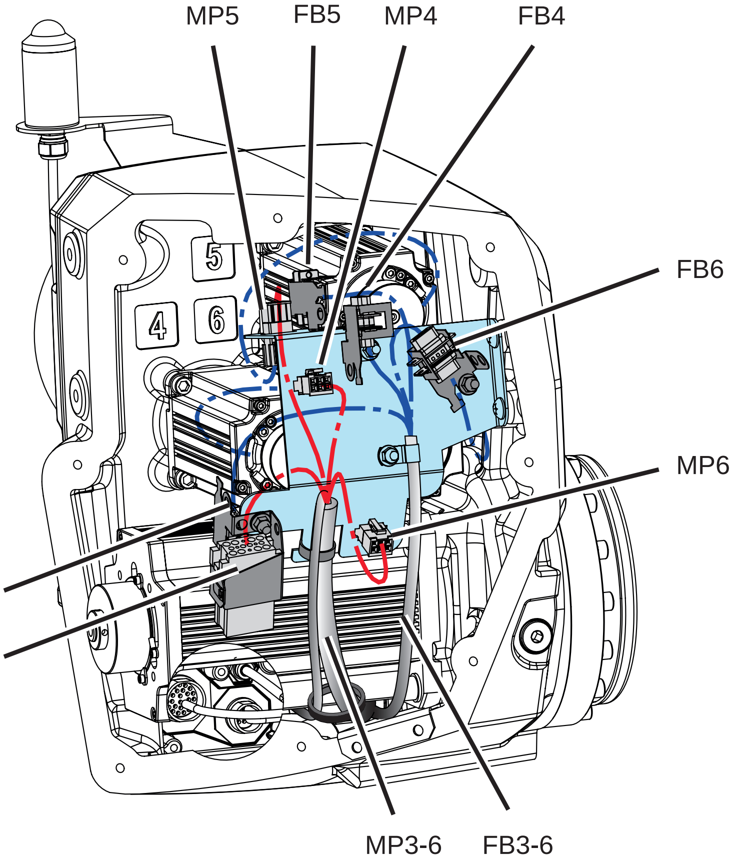
IRB 2600 Standard, motor type B



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Note

On IRB 2600 standard, motor type B the connector FB6 shall be fitted in a 30° angle.

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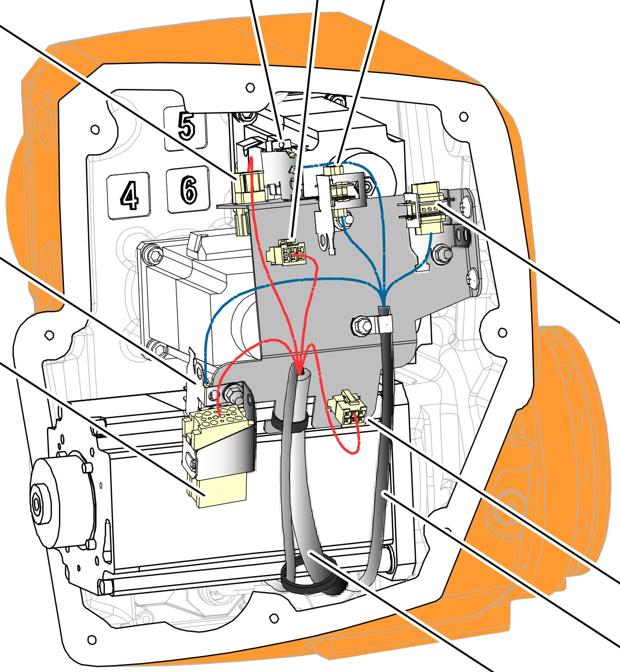
IRB 2600 Standard, motor type A



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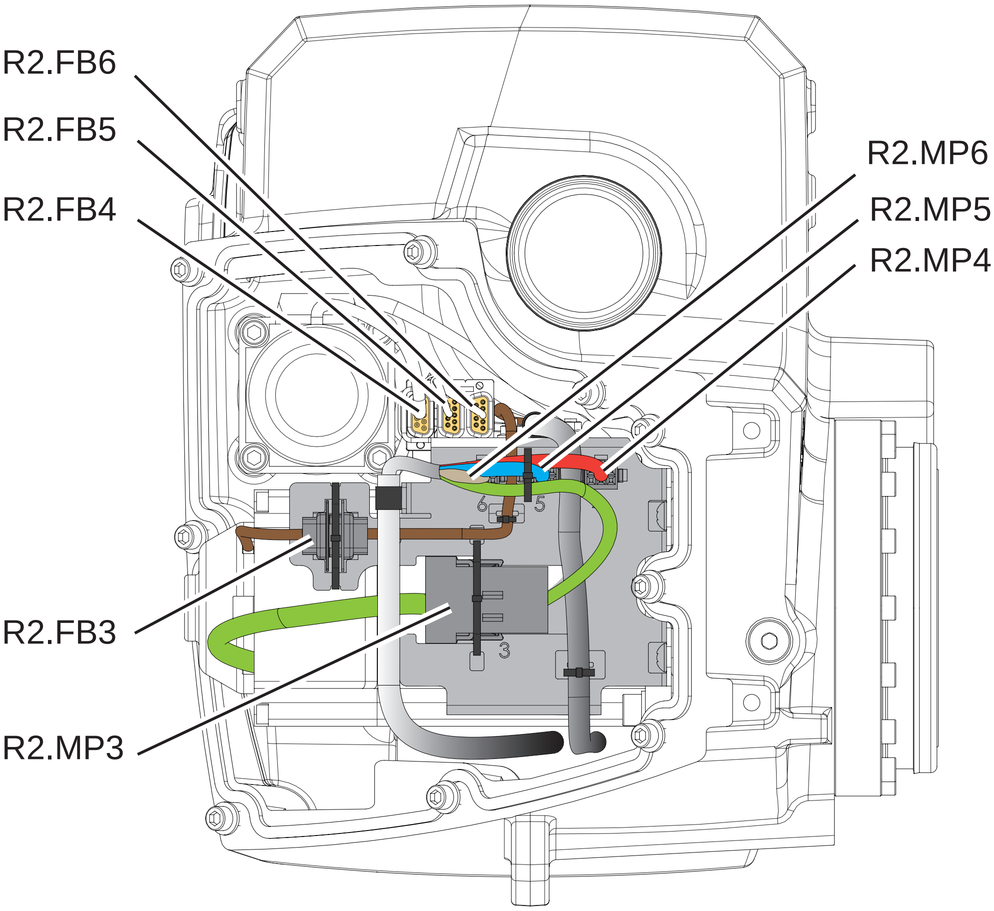
IRB 2600ID



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Required equipment

Equipment	Note
Extended reach hex bit socket head	Required for: • Axis-2 motor replacement: M6, length minimum 260 mm. • Axis-3 motor replacement: M6, length minimum 160 mm.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.
Lifting tool, axis-2	For art. no. see *Reference information*.
Lifting tool, axis-3	For art. no. see *Reference information*.
Motors	For spare part no. see *Spare part lists on page 461*.

Continues on next page

Weights

The motors for the different axes weighs according to the table:

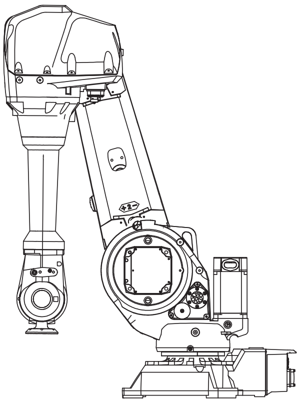
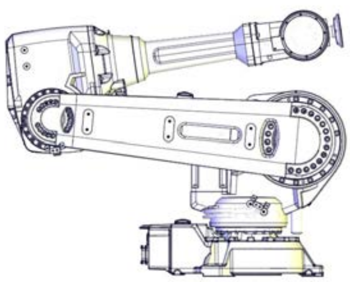
Motor	Weight in kg
Axis-1 motor	13 kg
Axis-2 motor	13 kg
Axis-3 motor	8 kg
Axis-4 motor	6.5 kg
Axis-5 motor	6.5 kg
Axis-6 motor	6.5 kg

CAUTION

All lifting equipment must be sized accordingly!

Position of robot

Use this procedure to place the robot in the position recommended in order to facilitate replacement of motors.

	Action	Information
	Axis-1, axis-4, axis-5 and axis-6 motors (**IRB 2600 Standard**) Axis-1 and axis-4 motors (**IRB 2600ID**) • Move the robot to a position where the wrist is pointing to the floor, as shown in the figure. This will make it possible to remove the motors without draining the oil from the gearbox.	 xx0800000388
	Axis-2 motor • Move the robot to a position where the lower arm rests firmly on the axis-3 damper. Release the axis-2 brake to be sure that the lower arm rests in the end position.	 xx1100000548
	Axis-3 motor • Move axis-2 to 0° and axis-3 to maximal +. Release the axis-3 brake to be sure that the upper arm is completely vertical and rests against the damper.	

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Filling oil in gearbox

Use this procedure to fill oil in gearbox, if needed.

Note

Filling oil in the gearbox is only needed when refitting motors axes 2 and 3.

	Action	Note
1	Axis-1 motor: • Filling gearbox oil not needed.	-
2	Axis-2 motor: • Refill oil in gearbox after refitting.	How to fill oil in gearbox is described in section: • *Changing the oil, axis-2 gearbox on page 163*
3	Axis-3 motor: • Refill oil in gearbox after refitting.	How to fill oil in gearbox is described in section: • *Changing the oil, axis-3 gearbox on page 167*
4	**IRB 2600 Standard** - axes 4, 5, 6: • Filling oil not needed, provided it has not been drained. **IRB 2600ID** - axes 4: • Filling oil not needed, provided it has not been drained.	-

Tightening torques and attachment screws

The table shows the tightening torques for all motors.

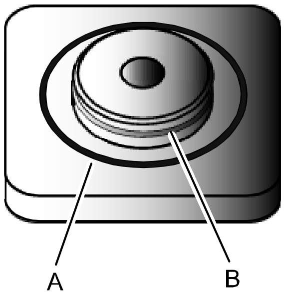
Motor	Attachment screw	Quality	Tightening torque
Motor, axis 1	M8x25	8.8-A2F	22 Nm
Motor, axis 2	M8x25	8.8-A2F	22 Nm
Motor, axis 3	M8x25	8.8-A2F	22 Nm
Motor, axis 4	M6x25	8.8-A2F	10 Nm
Motor, axis 5	M6x25	8.8-A2F	10 Nm
Motor, axis 6	M6x25 (Standard) M5x25 (IRB 2600ID)	8.8-A2F	10 Nm (Standard) 6 Nm (IRB 2600ID)

Preparations before the refitting of motors

Use this procedure to make necessary preparations before refitting motors.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
2	Grind the paint on the surface carefully to get a smoth surface.	
3	Clean the surface from contamination such as oil and dirt. Remove any painting from the assembly surfaces, with a knife.	
4	Make sure that the motor and the pinion are not damaged or scratched.	
5	Apply *Loctite 574* on the o-ring.	
6	Make sure the *o-ring* on the flange of the motor is seated properly.	 xx0900000082 Parts: • A: Correct position of o-ring • B: Incorrect position of o-ring ! Replace with a new o-ring if damaged!
7	In order to release the brakes, connect the 24 VDC power supply.	Connectors: • Motor axis 1: R2.MP1 • Motor axis 2: R2.MP2 • Motor axis 3: R2.MP3 • Motor axis 4: R2.MP4 • Motor axis 5: R2.MP5 • Motor axis 6: R2.MP6 Connect to pins: **Axes 1, 2 and 3:** • + : pin 2 • -: pin 5 **Axes 4 and 5:** • + : pin 4 • - : pin 6 **Axis 6 IRB 2600:** • + : pin 4 • - : pin 6 **Axis 6 IRB 2600ID:** • + : pin 7 • -: pin 8 **CAUTION** The connections for the motor brakes (24 VDC connection) are phase dependent. If the connection on the pins is switched, it can cause severe damage to vital parts.

Continues on next page

Note

A fan is recommended to be used to avoid overheating of motor and gear in applications with intensive motion (high average torque and/or short wait time) of axes 1 and 2. IP54 is valid for cooling fan.

A fan is also recommended to be used if the environmental temperature is high.

How to install a fan is described in section *Installation of cooling fan for motors (option) on page 90*.

Refitting motors

Use this procedure to refit motors axes 1, 2, 3, 4, 5 and 6.

Note

How to refit motors axes 5 and 6 on IRB 2600ID is described in sections:

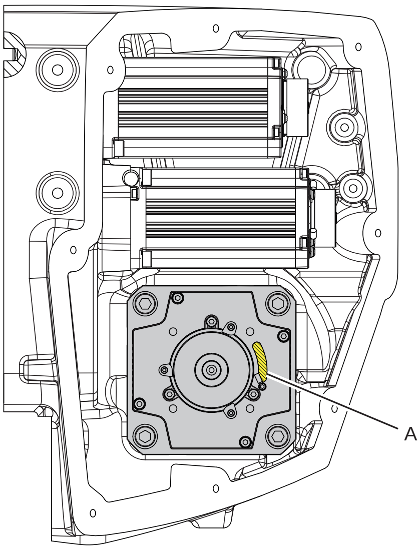
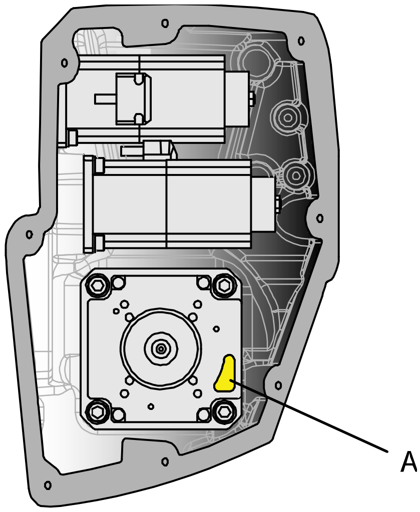
- *Replacing motor axis 5 - IRB 2600ID on page 337*
- *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*.

Note

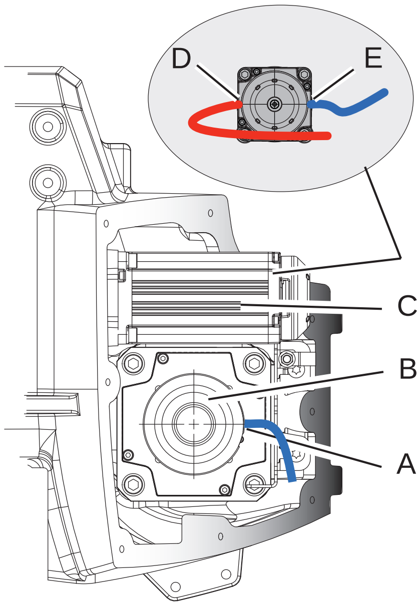
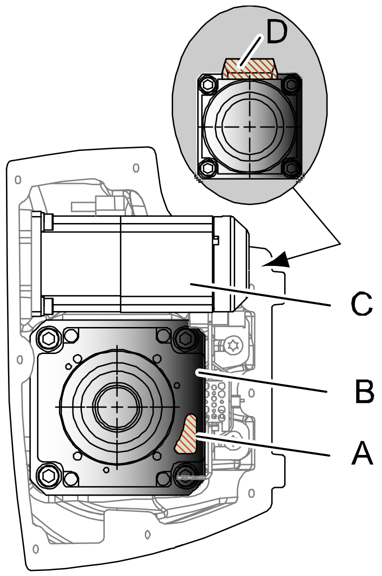
The procedure contains information how to refit motors on all axes of the robot. Some steps are only applicable to a certain motor. Follow the steps carefully in order not to miss vital information!

	Action	Information
1	**Note** Before starting the refitting of the motor, first make the necessary preparations!	Also see • *Preparations before the refitting of motors on page 328*
2	**Note** Whenever parting/mating motor and gearbox, the gears may be damaged if excessive force is used!	
3	Place the motor carefully in the gearbox.	
4	Fit the motor, making sure the motor pinion is properly mated to the gear in the gearbox.	Make sure that: • the motor is turned the correct way • the pinion or gear of the motor does not get damaged!

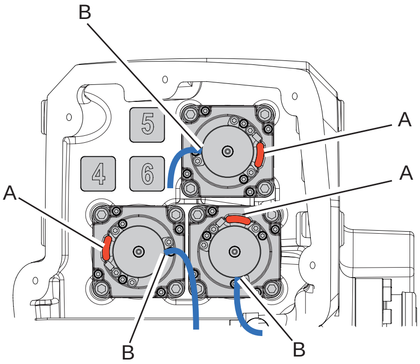
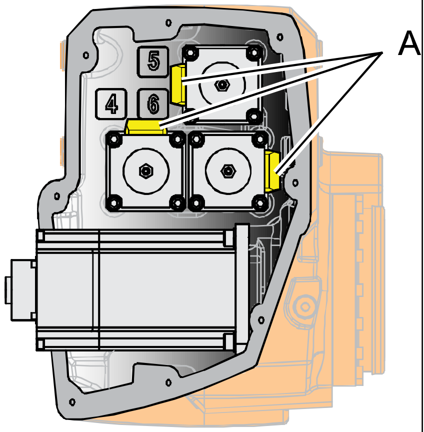
Continues on next page

	Action	Information
5	**IRB 2600 standard, motor type B** **Applicable to motor axis 3!** Make sure that the wire exit holes of motor axis 3 is in the correct position. See illustration!	 xx1400002570 Parts: • A: Wire exit hole, motor axis 3
6	**IRB 2600 standard, motor type A** **Applicable to motor axis 3!** Make sure that the wire exit holes of motor axis 3 is in the correct position. See illustration!	 xx0900000375 Parts: • A: Wire exit hole, motor axis 3

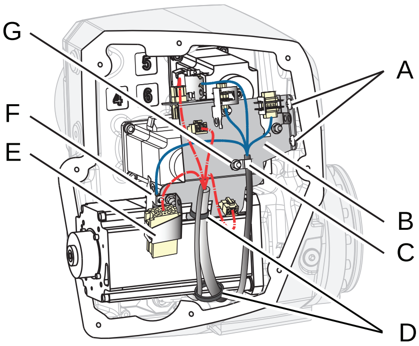
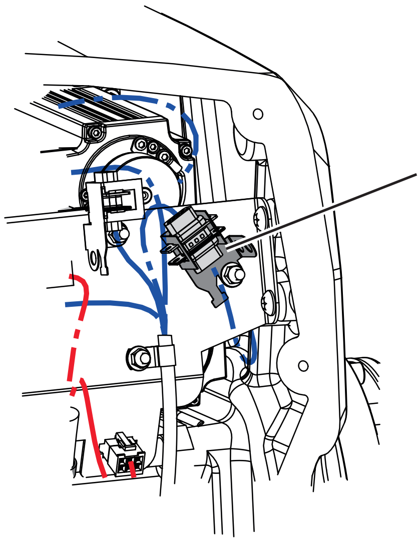
Continues on next page

	Action	Information
7	**IRB 2600ID, motor type B** Make sure that the wire exit holes of motors axes 3 and 4 are in the correct position. See illustration!	 xx1400002573 Parts: A Wire exit hole, motor axis 3 B Motor axis 3 C Motor axis 4 D Power wire exit hole, motor axis 4 E Signal cable exit hole, motor axis 4
8	**IRB 2600ID, motor type A** Make sure that the wire exit holes of motors axes 3 and 4 are in the correct position. See illustration!	 xx1000000992 Parts: A Wire exit hole, motor axis 3 B Motor axis 3 C Motor axis 4 D Wire exit hole, motor axis 4

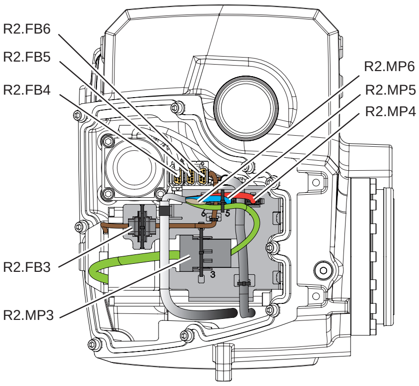
Continues on next page

	Action	Information
9	**IRB 2600 standard, motor type B** **Applicable to motors axes 4, 5 and 6!** Make sure that the orientation of the motor is in the correct position! See illustration!	 xx1400002571 Parts: • A: Wire exits of motors axes 4, 5 and 6
10	**IRB 2600 standard, motor type A** **Applicable to motors axes 4, 5 and 6!** Make sure that the orientation of the motor is in the correct position! See illustration!	 xx0900000376 Parts: • A: Wire exits of motors axes 4, 5 and 6
11	**Only applicable to motors axes 4, 5 and 6!** Adjust the play of the motor.	See *Adjusting the play on page 360*.
12	Secure the motor with its **attachment screws** and **washers**. **Note** Apply the correct tightening torque!	Tightening torque and attachment screws are specified in the table: • *Tightening torques and attachment screws on page 328*
13	Disconnect the brake release voltage.	
14	**Only applicable to motors axes 1 and 2!** Refit the connection box (if it has been removed). **Note** Make sure that the o-ring is in place!	See the figure in: • *Location of axis-1 and axis-2 motors on page 321*

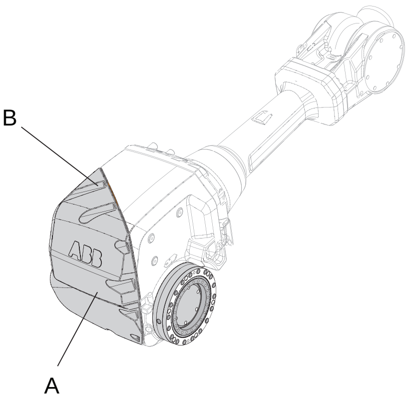
Continues on next page

<table>
<tr><th></th><th>Action</th><th>Information</th></tr>
<tr><td>15</td><td>IRB 2600 Standard, motor type A
Applicable to motors axes 3, 4, 5 and 6!
Refit the bracket in the armhouse on top of motors axes 4, 5 and 6.</td><td>
xx0900000372
Parts:
A Attachment screws, M6x16 quality 8.8-A2F (2 pcs)
B Bracket
C Clamp
D Cable straps
E Connection bracket
F Connection bracket
G Hexagon nut, M5 quality steel 8-A2F</td></tr>
<tr><td>16</td><td>IRB 2600 Standard, motor type B
Note
Connection bracket for FB6 shall be fitted in a 30° angle. See figure!</td><td>
xx1400002569</td></tr>
</table>

Continues on next page

	Action	Information
17	**IRB 2600ID** Refit the *bracket* in the armhouse with its attachment screws.	IRB 2600ID  xx1400002578
18	Reconnect the motor cables.	
19	**Applicable to motor axes 1 and 2!** Refit the *cable gland* and **motor covers**. Make sure that the *o-ring* is in place!	See the figure in: • *Location of axis-1 and axis-2 motors on page 321* **Note** Make sure that the cover is tightly sealed!
20	**Applicable to motors axis 2!** Refill gearbox oil.	How to fill oil in the gearbox is described in sections: • *Changing the oil, axis-2 gearbox on page 163* • *Changing the oil, axis-3 gearbox on page 167*
21	**Applicable to motors axes 3, 4, 5 and 6!** Make sure that the gasket on the cover on the armhouse is intact.	If the gasket is damaged, it need to be replaced.

Continues on next page

	Action	Information
22	**Applicable to motors axes 3, 4, 5 and 6!** Refit the cover in the back of the armhouse with its attachment screws and washers. **WARNING** The cover on the armhouse must be fitted when the robot is running. It is a vital part for the stability of the robot.	Make sure that the cover is tightly sealed.  xx0800000389 Parts: • A: Cover • B: Attachment screws M6x25, quality 8.8-A2F (8 pcs) Tightening torque: • 14 Nm
23	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
24	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.7.3 Replacing motor axis 5 - IRB 2600ID

Introduction

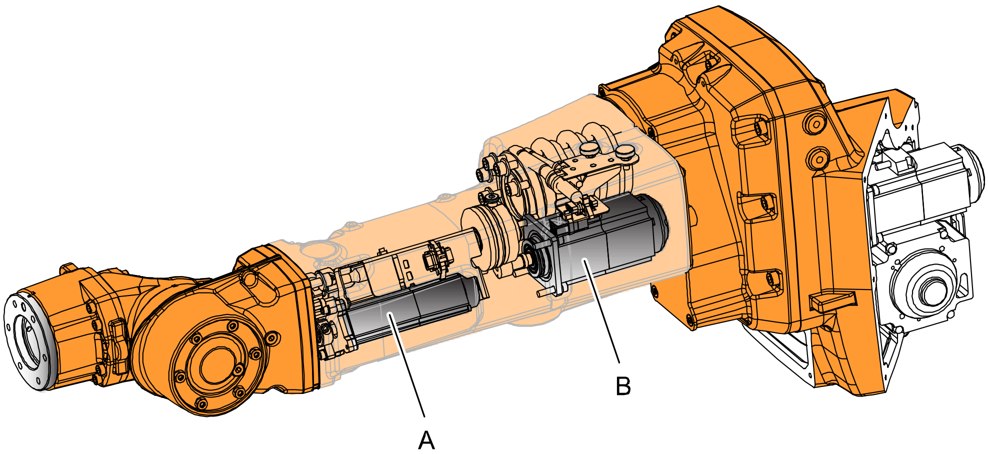
This procedure describes how to replace motor axis 5 on IRB 2600ID.

WARNING

When a motor is replaced, make sure to use the correct type of new motor. Motors of different types may not be compatible. See the *Spare parts manual* delivered as a separate document on myABB business portal (*www.abb.com/myABB*).

Location of motor axis 5

Motor axis 5 is located inside the upper arm tube as shown in the figure.



xx1000000877

A	Motor axis 6
B	Motor axis 5

Required equipment

Equipment	Art. no.	Note
Sikaflex 521FC	3HAC026759-001	
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Continues on next page

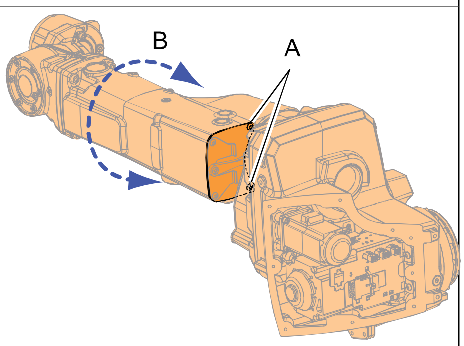
Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

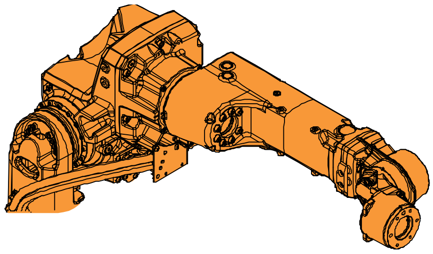
	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing motor axis 5

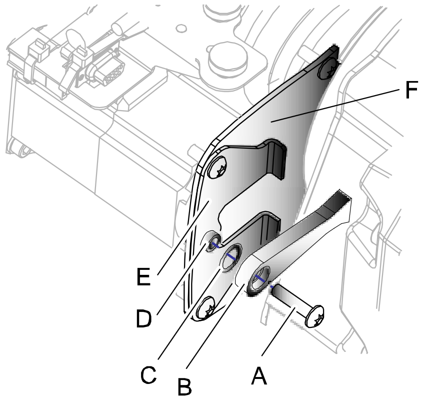
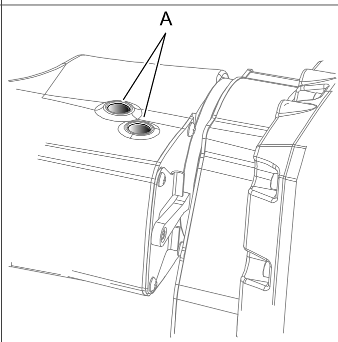
Use this procedure to remove motor axis 5.

	Action	Information
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Rotate the upper arm in order to access the two *inner attachment screws* securing the cover and remove them.	 xx1000000961 Parts: • A: Inner attachment screws (2 pcs) • B: Directions of rotation

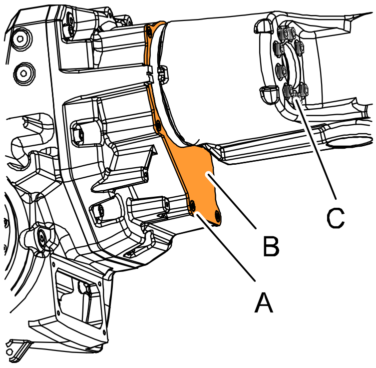
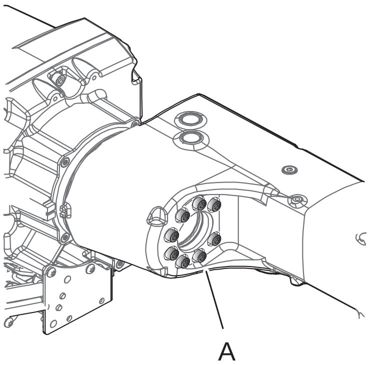
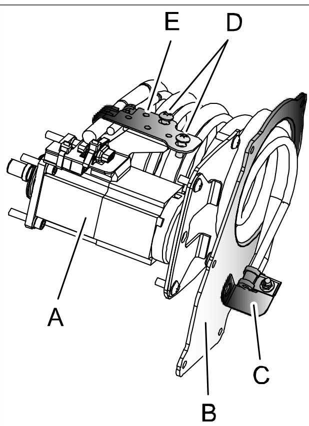
Continues on next page

	Action	Information
3	Move the upper arm to sync. position.	 xx1000001007
4	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
5	Remove all extra equipment fitted on the upper arm and wrist.	
6	Remove the *wrist*. This is done in order to be able to disconnect cables to motor axis 6.	How to remove the wrist see section: • *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*
7	**Note** Make a note of the position of axis 4 before continueing the removal process. It is important to refit the mechanical stop and cable harness spiral, with axis 4 in the same position as it was before the removal. If axis 4 has been moved, it must be returned to the position it was when the mechanical stop was removed. This is due to risk of damage to the cable harness.	

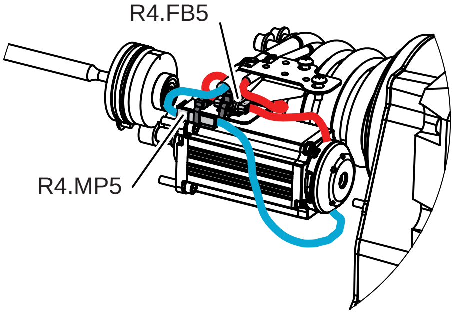
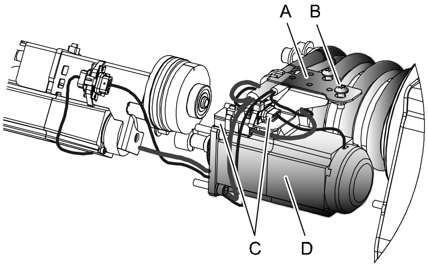
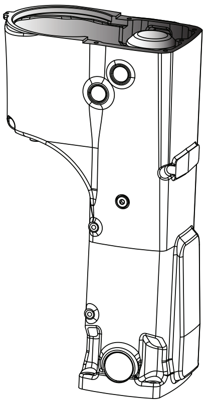
Continues on next page

	Action	Information
8	Remove the *mechanical stop*. **Note** Don't loose the o-ring and distance ring in the removal process!	 xx1000000879 Parts: • A: Attachment screws (5 pcs) • B: Mechanical stop • C: O-ring • D: Distance ring • E: Bracket • F: Cover
9	Remove the *bracket*.	See figure above!
10	Remove the *cover* on the upper arm tube.	See figure above!
11	Remove the two *VK-covers*, covering the attachment screws securing the cable harness to the arm tube.	 xx1000000934 Parts: • A: VK-covers (2 pcs)

Continues on next page

	Action	Information
12	Remove the *attachment screws* (A) securing the *cover* (B) on the armhouse.	 xx1000001001 Parts: A Attachment screws (6 pcs) B Cover C Attachment screws (8 pcs) securing arm tube
13	Remove the *attachment screws* (8 pcs) securing the tube of the armhouse.	 xx1000000936 Parts: • A: Attachment screws (8 pcs)
14	Unscrew the *attachment screws* securing the cable harness bracket to the upper arm tube. **Note** The arm tube is not shown.	 xx1000000939 Parts: • A: Motor axis 5 • B: Cover • C: Bracket (inside armhouse) • D: Attachment screws (2 pcs) • E: Bracket (upper arm tube)

Continues on next page

	Action	Information
15	Pull carefully out the upper arm tube a little. Not more than it is possible to reach the connectors for motor axis 5. **CAUTION** Be careful not to damage the cable harness in the process. The space is cramp.	
16	**IRB 2600ID, motor type B**: Disconnect connectors R4.MP5 and R4.FB5 to motor axis 5.	 xx1400002576
17	**IRB 2600ID, motor type A** Disconnect the *connectors* to motor axis 5.	 xx1000000998 Parts: A Bracket B Attachment screws (2 pcs) C Connectors motor axis 5 D Motor axis 5
18	Pull out the cable harness from motor axis 6 through the upper arm tube and secure the cable harness with a roundsling or similar to the armhouse.	
19	Remove the upper arm tube.	
20	Secure the upper arm tube with motor axis 5 pointing upwards. This is done in order to avoid draining the oil when motor axis 5 is removed.	 xx1000000938

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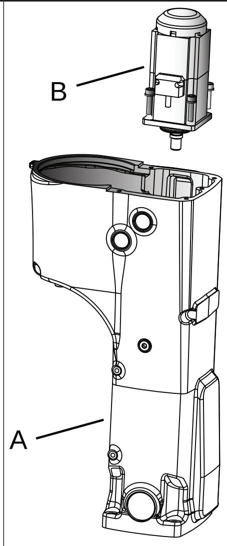
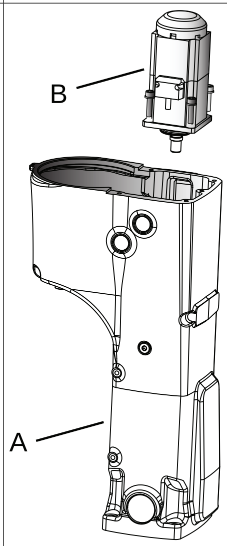
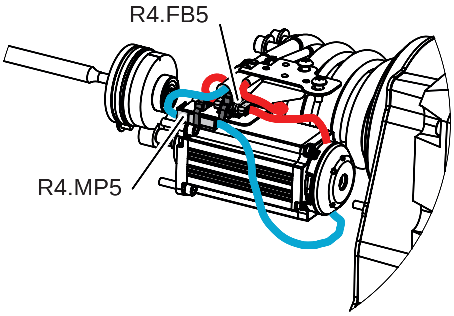
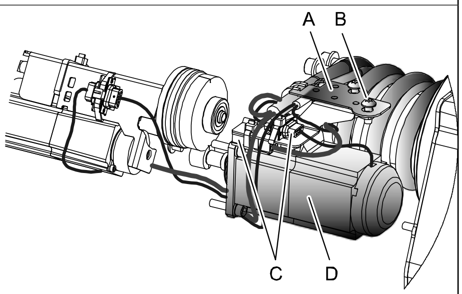
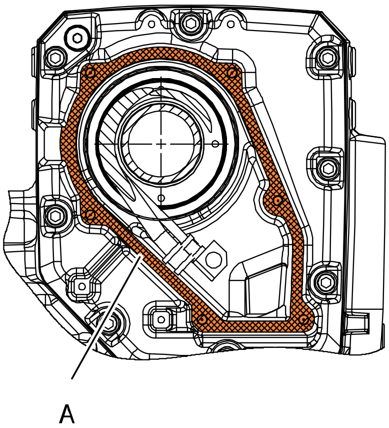
	Action	Information
21	Remove *motor axis 5* by unscrewing its attachment screws.	 xx1000000937 Parts: • A: Upper arm tube • B: Motor axis 5

Refitting motor axis 5

Use this procedure to refit motor axis 5.

	Action	Information
1	Place motor axis 5 in the upper arm tube.	
2	Tighten the attachment screws just enough to still be able to move the motor.	 xx1000000937 Parts: • A: Upper arm tube • B: Motor axis 5
3	Adjust the play by finding the smallest play.	
4	Secure the motor with its attachment screws.	Tightening torque: 10 Nm.
5	Lift the upper arm tube to the robot.	

Continues on next page

	Action	Information
6	Push the cables to motor axis 6 into the upper arm tube.	
7	**IRB 2600, motor type B** Connect connectors R4.MP5 and R4.FB5 to motor axis 5.	 xx1400002576
8	**IRB 2600, motor type A** Connect the *connectors* to motor axis 5.	 xx1000000998 Parts: A Bracket B Attachment screws (2 pcs) C Connectors to motor axis 5 D Motor axis 5
9	Apply *flange sealing* (Loctite 574) on the surface where the cover shall be fitted. See figure!	 xx1000001006 Part: A Flange sealing (Loctite 574)

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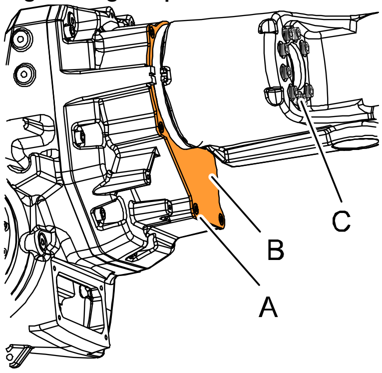
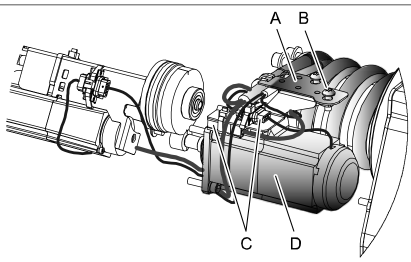
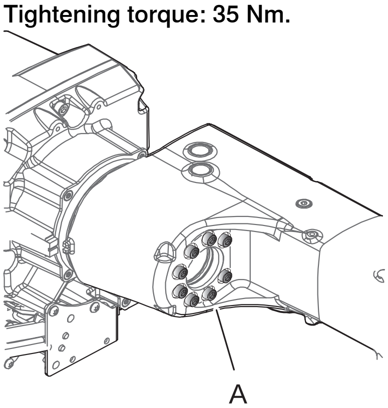
	Action	Information
10	Secure the *cover* with its *attachment screws*.	Tightening torque: 10 Nm.  xx1000001001 Parts: A Attachment screws (6 pcs) M6x20 quality 8.8-A2F B Cover C Attachment screws (8 pcs) M8x25 quality Steel 12.9 Gleitmo
11	Secure the cable harness with its attachment screws to the upper armtube.	 xx1000000998 Parts: A Bracket B Attachment screws (2 pcs) C Connectors motor axis 5 D Motor axis 5
12	Check that the *spiral of the cable harness* is fitted correctly.	See section • *Replacing the cable harness in the upper arm - IRB 2600ID on page 228*
13	Secure the upper arm tube with its *attachment screws*.	Tightening torque: 35 Nm.  xx1000000936 Parts: A Attachment screws (8 pcs)

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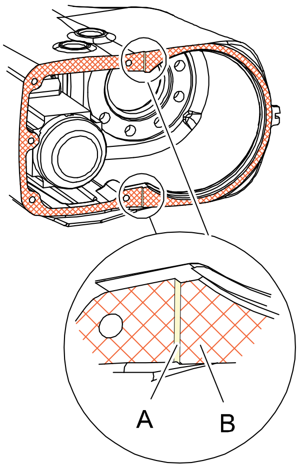
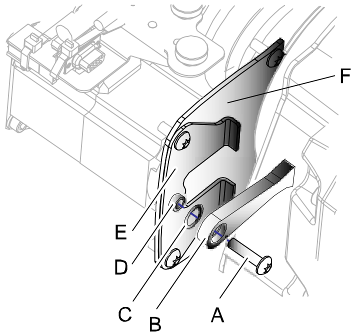
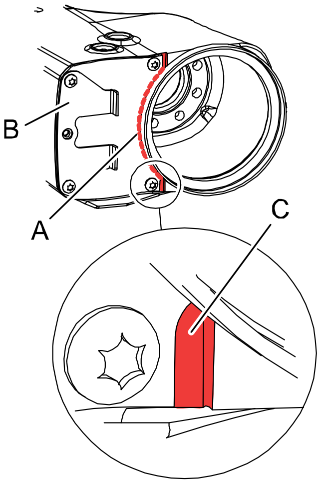
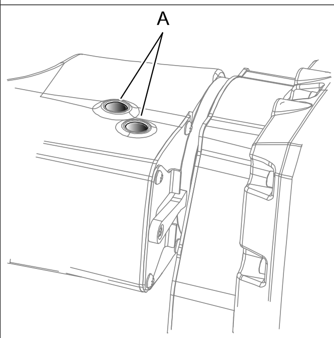
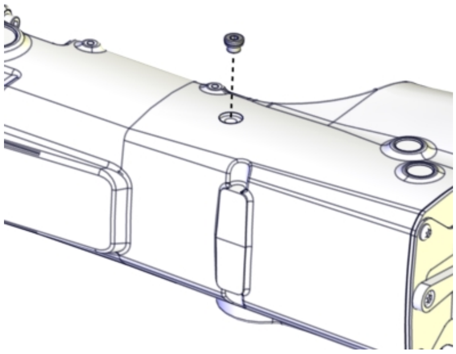
	Action	Information
14	Apply *flange sealing (Loctite 574)* on the surface shown in the figure. **Note** Do not apply flange sealing on the surfaces where Sikaflex 521FC shall be applied! See figure!	 xx1000001003 Parts: A Surface where Sikaflex 521FC shall be applied B Surface where Loctite 574 shall be applied.
15	Refit the *cover* with two inner *attachment screws*.	 xx1000000879 Parts: A Attachment screws (5 pcs) B Mechanical stop C O-ring D Distance ring E Bracket F Cover
16	Refit the *bracket* with the remaining *attachment screws*.	See figure above.

Continues on next page

	Action	Information
17	Apply *Sikaflex 521FC* on the surfaces shown in the figure.	 xx1000001002 Parts: A Sikaflex 521FC B Cover C Surface where to apply Sikaflex 521FC
18	Connect the cable to motor axis 6.	
19	Refit the *mechanical stop*.	
20	Fit new *VK-covers*.	 xx1000000934 Parts: A VK cover (2 pcs)
21	Refit the *wrist*.	See section • *Replacing motor axis 6 and wrist unit - IRB 2600ID on page 349*

Continues on next page

	Action	Information
22	Remove the oil plug, and refill the axis-5 gear with *lubricating oil*.	 xx2000002311 Where to find type of oil and total amount is detailed in *Type and amount of oil in gearboxes on page 148*.
23	Inspect the oil plug regarding thickness and condition of the sealing. Replace the complete oil plug if the sealing thickness is less than 1.5 mm or if the sealing is damaged. **CAUTION** Risk of damage to internal components of the axis-5 gear. Tighten the oil plug with correct torque and make sure the sealing thickness is minimum 1.5 mm.	Oil plug with sealing: 3HAC048968-001.
24	Refit the oil plug with sealing.	Tightening torque: 3.8 Nm.
25	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
26	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.7.4 Replacing motor axis 6 and wrist unit - IRB 2600ID

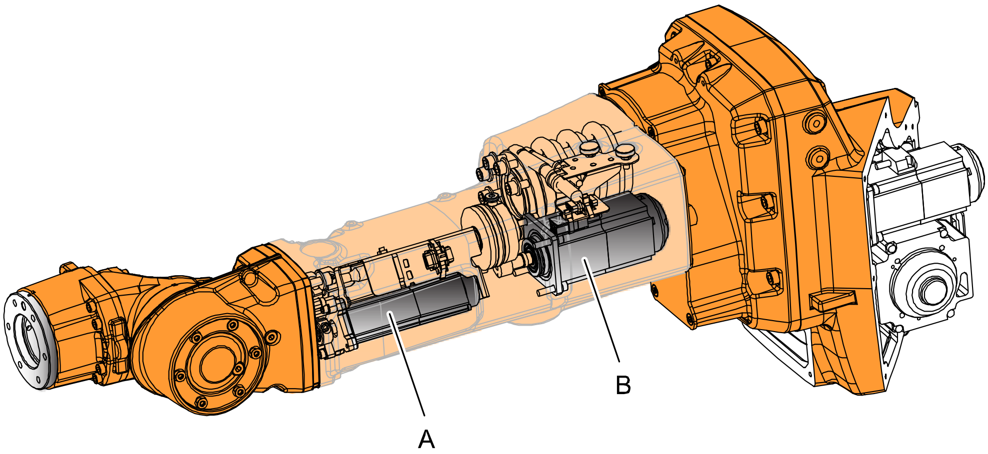
Introduction

This procedure describes how to replace the axis-6 motor on IRB 2600ID.

The replacement of the motor also contains the procedure for how to remove and refit the wrist unit on IRB 2600ID

Location of motor axis 6

Motor axis 6 is located inside the upper arm tube, as shown in the figure.



xx1000000877

A	Motor axis 6
B	Motor axis 5

Required equipment

Equipment	Art. no.	Note
Motor, axis 6	For spare part number, see: • *Spare part lists on page 461*	
Wrist unit, ID	For spare part number, see: • *Spare part lists on page 461*	
VK cover	For spare part number, see: • *Spare part lists on page 461*	Always replace with a new when removed. One VK cover at the axis-5 flexible coupling. One VK cover underneath the arm tube.
Locking liquid	-	Loctite 574
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Continues on next page

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing axis-6 motor and wrist unit

Use this procedure to remove the axis-6 motor and the wrist unit.

Preparations before removing the wrist unit

	Action	Information
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Move the upper arm to synchronization position.	
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Remove all extra equipment fitted on the upper arm.	

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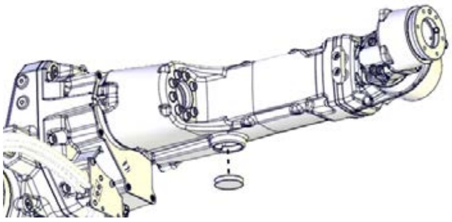
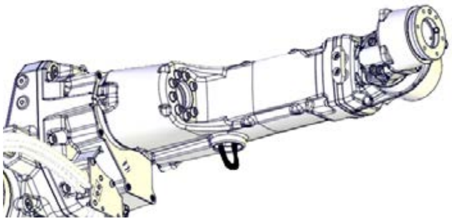
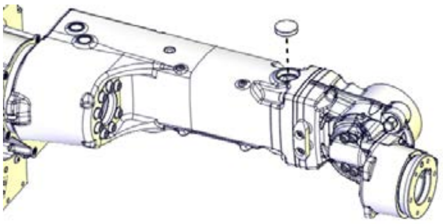
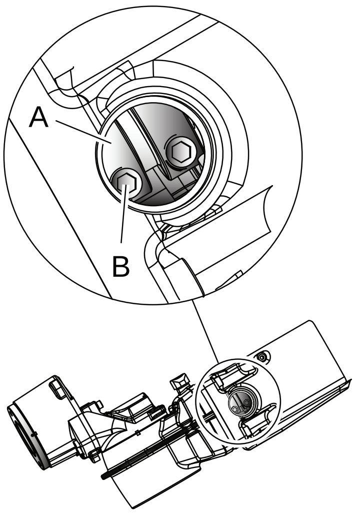
Removing the wrist unit

	Action	Information
1	Remove the VK cover.	 xx1600001486
2	Pull out the cabling from the upper arm cavity through the VK cover hole and release the cable loop by straightening the cables. This is done in order not to damage the cabling when the wrist is pulled out from the arm tube with the axis-6 motor connectors still connected.	 xx1600001487
3	Remove the VK cover.	 xx1000000873
4	Open the *flexible coupling* that secures the axis-5 motor, on the side facing the wrist.	 xx1000000874 Parts: A Coupling B Attachment screw

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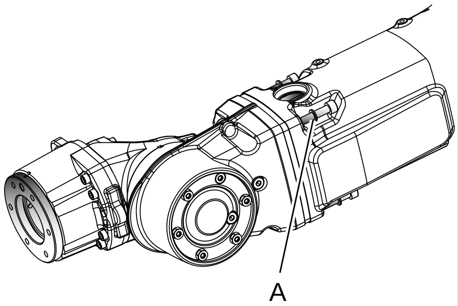
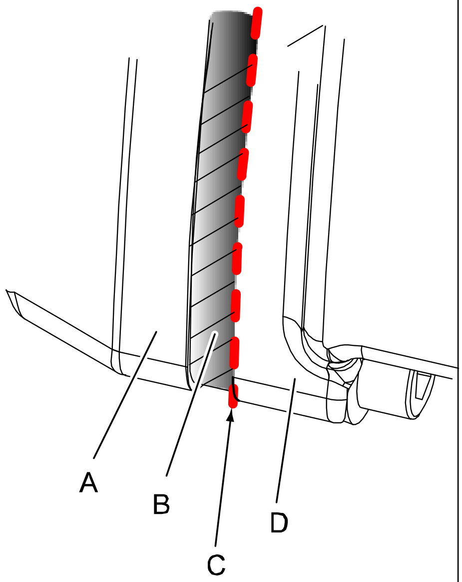
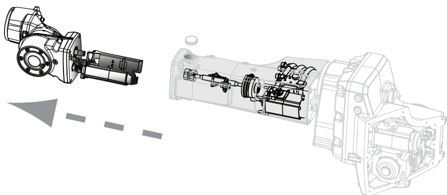
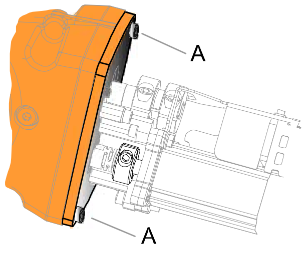
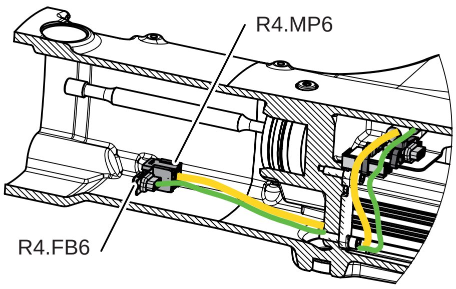
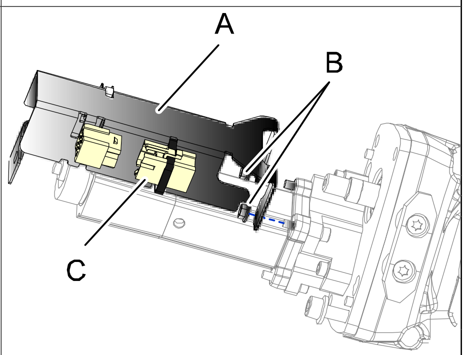
	Action	Information
5	Remove the *attachment screws* that secure the wrist.	 xx1000000875 Part: A Attachment screws (4 pcs)
6	Separate wrist and upper arm tube at the marked *division point* (along the dotted line in the figure). **Note** There is oil inside the wrist. The cover is only secured with Loctite. If opened in the wrong place oil will spill out.	 xx1000000933 Parts: A Wrist B Cover (glued with Loctite to the wrist) C Division point D Upper arm tube
7	Pull the wrist carefully out a little, in order to be able to disconnect the motor cables to the axis-6 motor. **Note** The wrist is fitted on cylindrical pins.	 xx1000000876

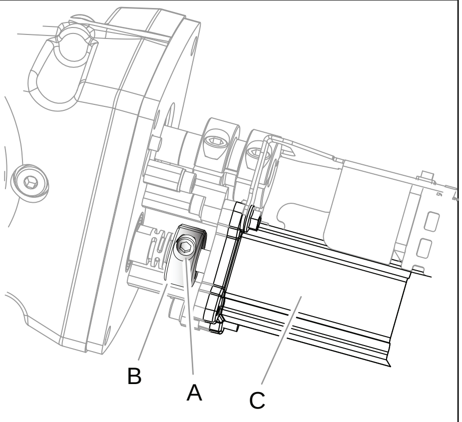
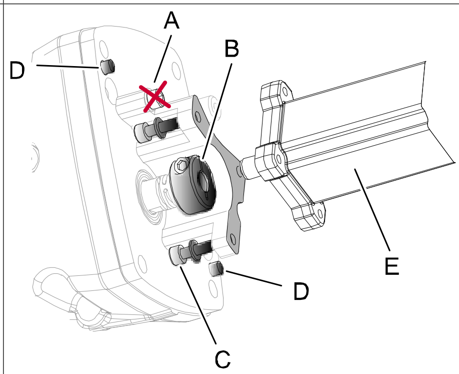
Continues on next page

	Action	Information
8	Fit two *short screws* in the holes for the attachment screws in order to temporarily secure that the cover is not opened.	 xx1000000932 Parts: A Short screws (2 pcs)
9	Disconnect the cables R4.MP6 and R4.FB6 to the axis-6 motor.	 xx1400002575
10	Put the wrist on a work bench.	

Removing the axis-6 motor

	Action	Information
1	**Note** Do not move the gears in the wrist when the motor is removed! When refitting the motor the gears in the wrist shall be in the same position as they were before the removal.	
2	Remove the *cable protection* by removing the nuts securing it.	 xx1000000931 Parts: A Cable protection B Nuts (2 pcs) C Connector motor axis 6

Continues on next page

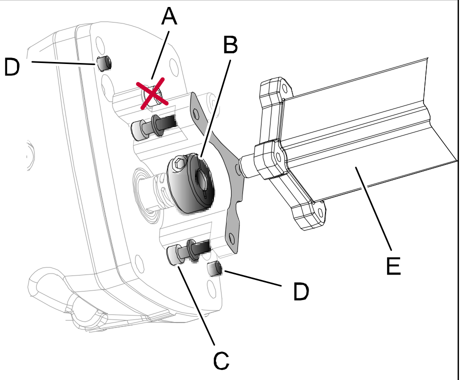
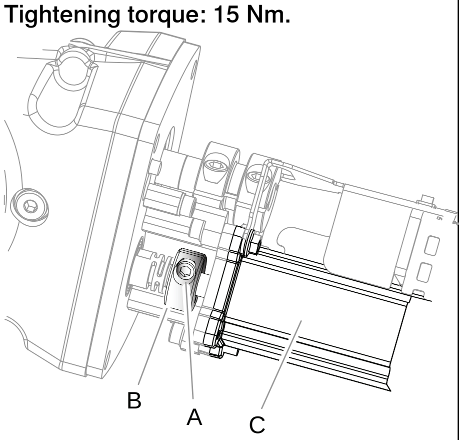
	Action	Information
3	Open the *flexible coupling* securing motor axis 6.	 xx1000000930 Parts: A Attachment screw, coupling B Flexible coupling C Motor, axis 6
4	Remove the *attachment screws* that secure the axis-6 motor and remove the motor. **Note** Do not remove the attachment screws securing the motor bracket.	 xx1000000929 Parts: A Attachment screws, bracket B Flexible coupling C Attachment screws, motor (3 pcs) D Cylindrical pins (2 pcs) E Motor axis 6

Refitting axis-6 motor and wrist unit

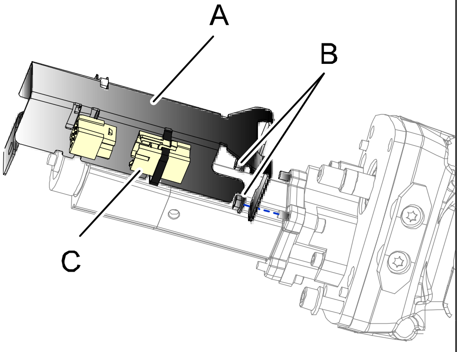
Use this procedure to refit the axis-6 motor and the wrist unit.

Continues on next page

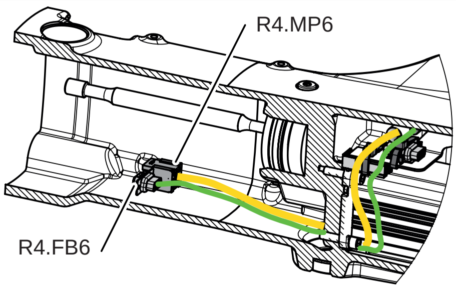
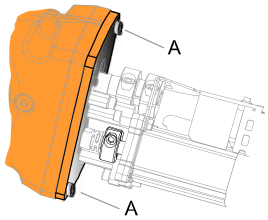
Refitting the motor

	Action	Information
1	Place the motor axis into the axis-6 *flexible coupling*.	 xx1000000929 Parts: A Attachment screws, bracket B Flexible coupling C Attachment screws, motor (3 pcs) D Cylindrical pins (2 pcs) E Motor axis 6
2	Secure the motor with its *attachment screws*.	Tightening torque: 6 Nm.
3	Secure the motor axis with the *flexible coupling* with its *attachment screw*.	Tightening torque: 15 Nm.  xx1000000930 Parts: A Attachment screw, coupling B Flexible coupling C Motor axis 6

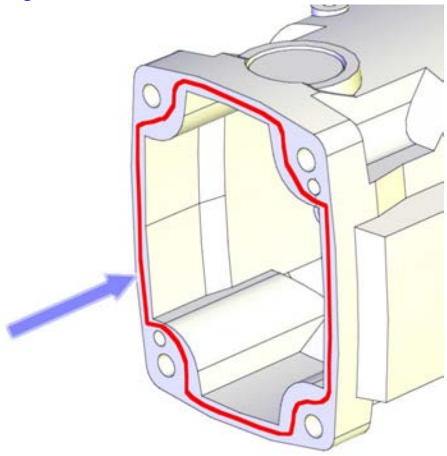
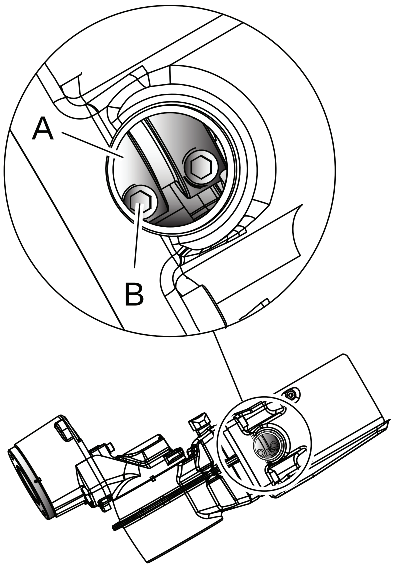
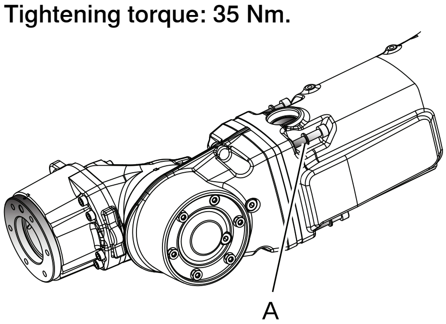
Continues on next page

	Action	Information
4	Fit the *cable protection* with its *nuts*.	 xx1000000931 Parts: A Cable protection B Nuts (2 pcs) C Connector motor axis 6

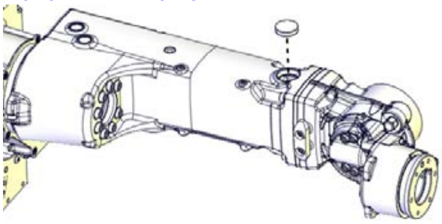
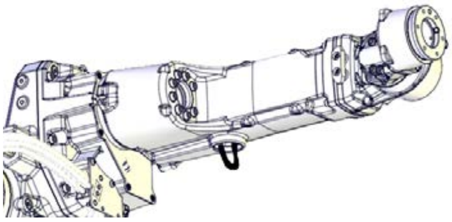
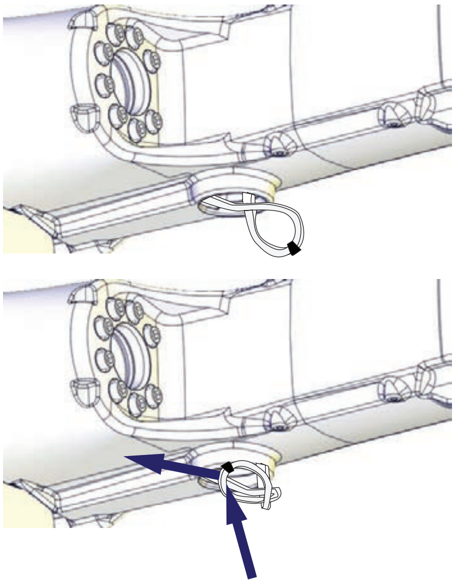
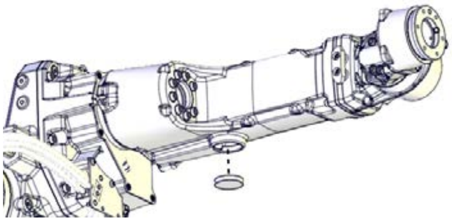
Refitting the wrist

	Action	Information
1	Clean all assembly surfaces. Remove any painting from the assembly surfaces, with a knife.	
2	Place the wrist with the axis-6 motor fitted a little into the upper arm tube.	
3	Reconnect the cables R4.MP6 and R4.FB6 to the axis-6 motor.	 xx1400002575
4	Remove the *short screws* temporarily used to secure from leakage from the wrist.	 xx1000000932 Parts: A Short screws (2 pcs)

Continues on next page

	Action	Information
5	Apply *locking liquid* to the assembly surface on the upper arm tube.	Specified in *Required equipment on page 349*.  xx1200000063
6	Push the wrist and the axis-6 motor into its position onto the cylindrical pins. **Tip** Look through the hole for the VK cover when fitting the axis into the *flexible coupling* of motor axis 5.	 xx1000000874 Parts: A Flexible coupling axis 5; B Attachment screw
7	Secure the wrist with its *attachment screws* and washers.	Tightening torque: 35 Nm.  xx1000000875 Parts: A Attachment screws (4 pcs)

Continues on next page

	Action	Information
8	Secure the axis-5 flexible coupling with its attachment screw.	Tightening torque: 15 Nm.
9	Fit a new *VK cover*.	Article number is specified in *Required equipment on page 349*.  xx1000000873
10	Pull out the cabling from the upper arm cavity through the VK cover hole.	 xx1600001487
11	Add a cable tie to the middle of the loop. Then twist the cables into the shape of an "8", fold the loop and insert the bundle into the cavity in the upper arm tube, with direction against the arm house. **WARNING** If placing the cables into the cavity at the opposite side, with direction against the wrist, there is a risk of cable damage due to rotating parts inside the arm tube.	 xx1600001515
12	Fit a new *VK cover*.	Article number is specified in *Required equipment on page 349*.  xx1600001486

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Concluding procedure

	Action	Information
1	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
2	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.7.5 Adjusting the play

Same instruction for all motors

This section describes how to adjust the play in the motors. The method is the same for all motors. The illustrations show how to adjust the play in the axis-4 motor, but the same method can also be applied when adjusting the play of the axis-5 and axis-6 motor.

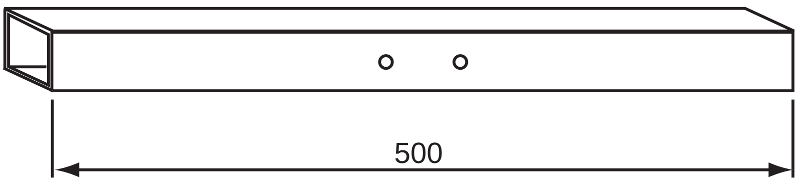
Required equipment

Equipment, etc.	Art. no.	Note
Rotation tool	3HAB7887-1	M3 screw is included. Used for feeling the play during adjustment
Tool for adjusting play in motors	-	See *Drawing for adjustment tool on page 360*.
Standard toolkit	-	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Drawing for adjustment tool

Find or make a tool as described in the figure.

Drill holes in the middle so that they match the existing holes that are used to place extra equipment at the wrist unit.



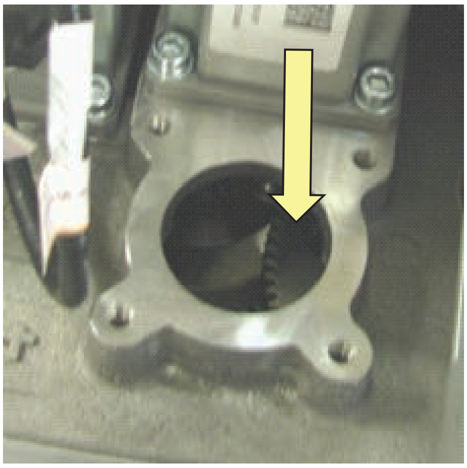
xx1200000066

> **Note**
>
> Do NOT drill holes in the robot!

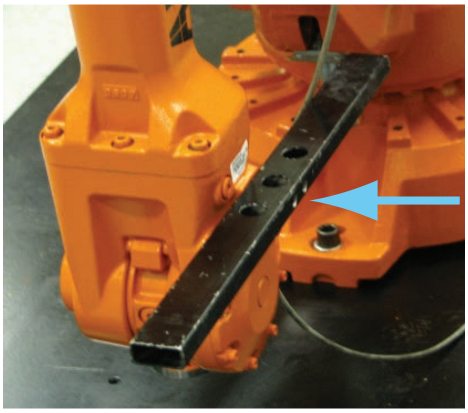
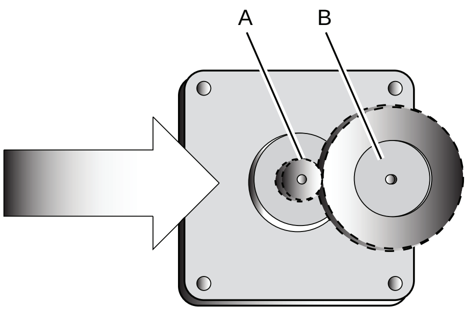
Continues on next page

Adjusting the play

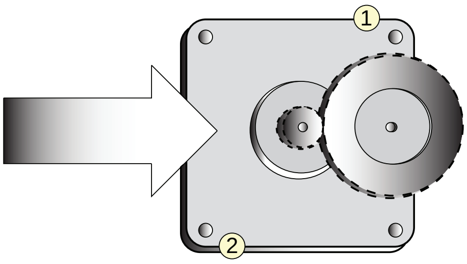
Use this procedure to adjust the play of the motor. The figures show adjustment of the axis-4 motor, but the method is also the same for the axis-5 and axis-6 motors.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Before fitting the motor, look into the hole to find the position of the gear. When adjusting to the correct play, the motor pinion is pressed against the gear. How to do this is detailed further on in this procedure.	 xx1200000098
3	**CAUTION** Whenever parting/mating motor and gearbox, the gears may be damaged if excessive force is used!	
4	Place the motor carefully in the hole without damaging the gear or pinion. Put the attachment screws in the holes on the motor and fit them a few revolutions. Do not tighten the attachment screws yet!	

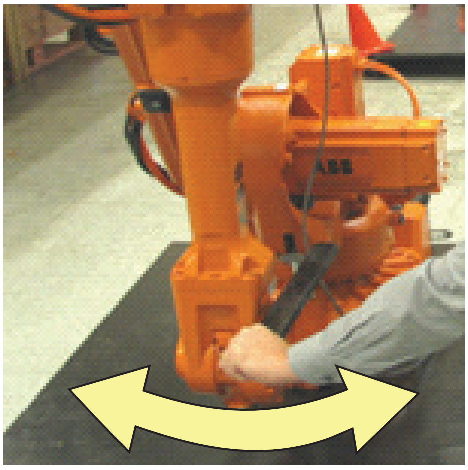
Continues on next page

	Action	Note
5	Fit the *rotation tool* on the motor axis with the M3 attachment screw.	 xx1200000099 Article number is specified in *Required equipment on page 360*.
6	Fit the tool for adjusting the play on the axis in question.	 xx1200000096
7	Release the brakes on the motor.	
8	Push the motor, firmly in the direction of the gear, as shown in figure. **Note** Do not use too much force!	 xx1200000093 Parts: • A: Motor pinion • B: Gear

Continues on next page

	Action	Note
9	Tighten attachment screws number 1 and 2 diagonally, alternatingly between the screws, while at the same time pushing the motor in the direction of the gear.	 xx1200000094
10	Secure all four attachment screws. For tightening torque, see *Tightening torques and attachment screws on page 328*.	
11	Check the play by holding the rotation tool fitted on the motor with one hand and moving the tool fitted on the wrist back and forth with the other.	 xx1200000097 The figure shows how to do this on the axis-4 motor.
12	If play is felt in the tool fitted on the motor axis, unscrew the attachment screws of the motor and repeat steps *7* to *10*. Then check the play again according to step *11*. If no play can be felt in the tool fitted on the motor axis, it means that the play is adjusted correctly.	
13	When the play is adjusted correctly, rotate the motor five revolutions and check the play again.	

Continues on next page

	Action	Note
14	If no play is detected, continue to rotate the motor and check the play in steps of five revolutions until the motor has been rotated 20 revolutions. (Rotate five revolutions - check play - rotate five revolutions - check play - and so on)	
15	If play is felt in the tool fitted on the motor axis, unscrew the attachment screws of the motor and repeat steps *7* to *10*. Then check the play again starting with step *11*.	
16	Perform a final check of the play by rotating the motor back and forth with the tool fitted (in the case of axis-4 motor) on the wrist, to check that it is running smoothly. There should be no unnormal noices.	 xx1200000100
17	If motor and gear is not running smoothly or if unnormal noice comes from the gears, the play must be readjusted.	

4.8 Gearboxes

4.8.1 Replacing gearbox axis 1

Different versions of the gearbox

There are two different versions of the axis-1 and axis-2 gearboxes. The different versions affect the mechanical structure of the base, frame and lower arm.

Differences in the mechanical structure are pointed out in the procedure as valid for different robot version:

- IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0
- IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

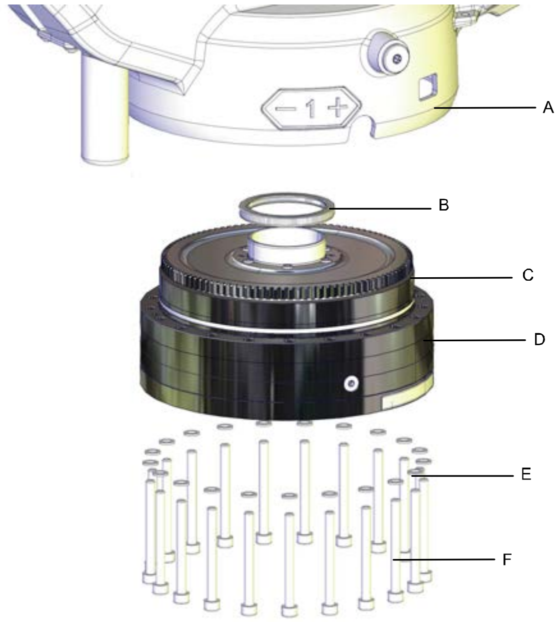
Further information about the differences are given in *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

Location of gearbox

The gearbox is located as shown in the figure. The exploded view only shows the principle of the assembly. The actual replacing is recommended to be done with the robot resting on its side.

Continues on next page

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0

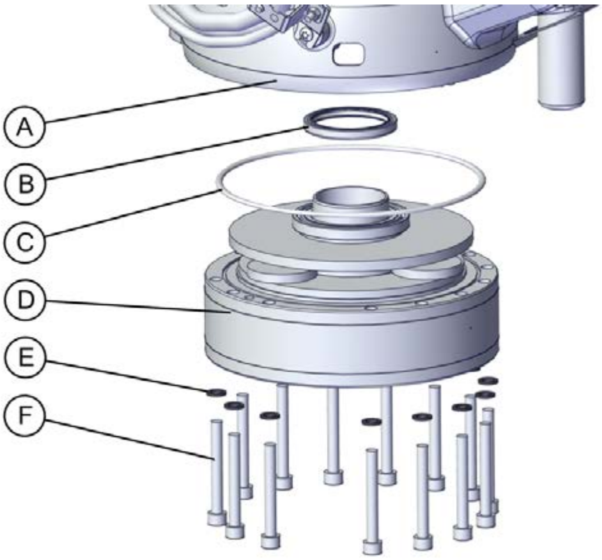


xx0800000400

	Spinea gearbox
A	Frame
B	Radial sealing
C	O-ring
D	Gearbox axis 1
E	Washer (21 pcs)
F	Attachment screws M8x80 quality Steel 12.9 Gleitmo (21 pcs)

Continues on next page

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



xx1800000800

	Nabtesco gearbox
A	Frame
B	Radial sealing
C	O-ring
D	Gearbox axis 1
E	Washer (14 pcs)
F	Attachment screws M10x80 quality Steel 12.9 Gle 603+Geo500 (14 pcs)

Required equipment

Equipment	Note
Gearbox	See *Spare part lists on page 461*.
Guide pins	Guide pin, M8x150: 3HAC15520-2 Used to guide the gearbox during removal/refitting. Always use guide pins in pairs.
Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C: Guide pin, M8x100	3HAC15520-1 Always use guide pins in pairs. Additional pins to guide the gearbox during removal/refitting.
Standard toolkit	Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.	These procedures include references to the tools required.

Continues on next page

Deciding calibration routine

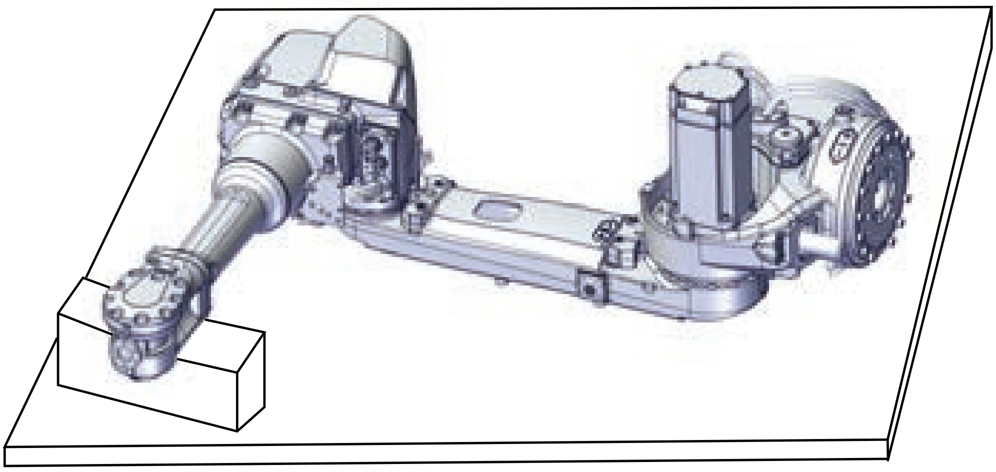
Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Illustration of robot put down on its side

The robot is put down on its side for a safe removal of the axis-1 gearbox. Prepare an area on the floor with cardboard, plastic foam or similar and prepare higher support for the wrist.

Make sure the cabling brackets on the lower arm are unfastened and moved out of the way so that the cabling is not getting squeezed.

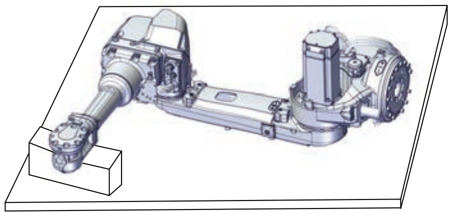


xx1800000593

Continues on next page

Removing gearbox axis 1

Use this procedure to remove the gearbox.

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Drain the oil from the gearbox.	How to drain the oil from the gearbox is described in section: • *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*
3	Jog the robot to: • Axis 1: 0° • Axis 2: 0° • Axis 3: -10° • Axis 4: 0° • Axis 5: 0° • Axis 6: 0°	
4	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the safeguarded space.	
5	Remove the axis-1 motor.	See *Removing motors on page 308*.
6	Remove the complete arm system from the base and lay down the robot on its side.	See *Removing the base on page 298*.  xx1800000593

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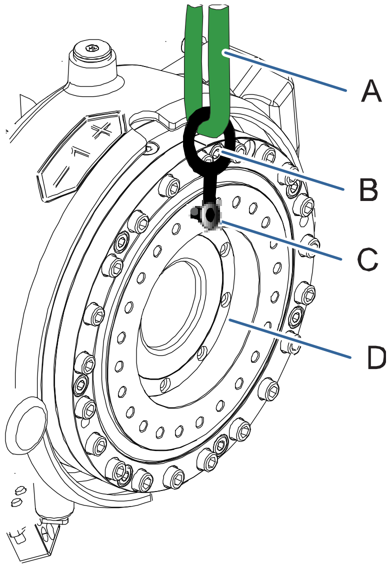
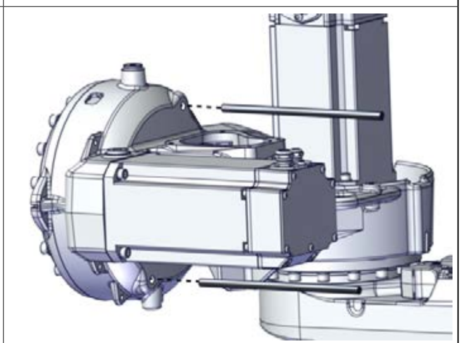
	Action	Note
7	Fit a lifting lug in the uppermost hole for the base attachment screws.	 xx0800000440 A Roundsling B Lifting lug C Uppermost base attachment hole D Axis-1 gearbox
8	**CAUTION** The gearbox weighs . 27 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 24 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	
9	Secure the gearbox in an overhead crane or similar.	
10	Remove the *attachment screws* securing the gearbox.	See the figure in: • *Location of gearbox on page 365*
11	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Fit two guide pins to the gearbox through the holes in the frame.	 xx1800000788 Guide pin, M8x100: 3HAC15520-1 Always use guide pins in pairs!

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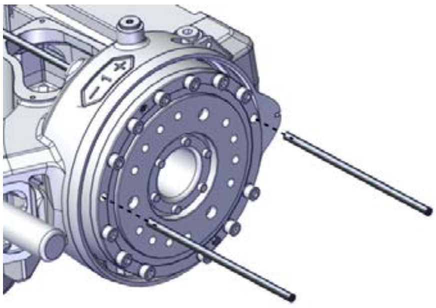
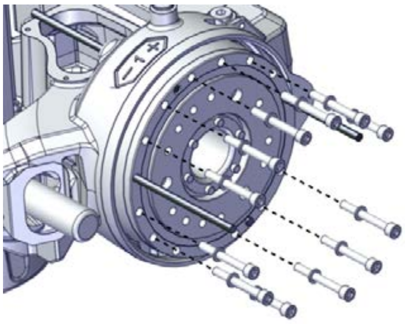
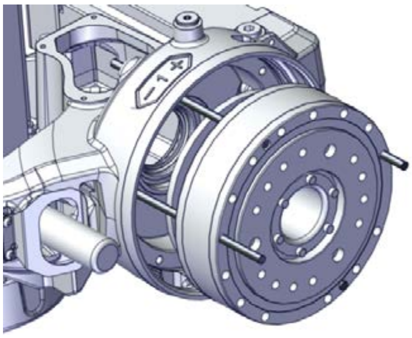
	Action	Note
12	Remove two gearbox attachment screws opposite to each other and fit two guide pins into the holes.	 xx1800000789 Guide pin, M8x150: 3HAC15520-2 Always use guide pins in pairs!
13	Remove the remaining attachment screws and washers.	 xx1800000790
14	**Note** Whenever parting/mating motor and gearbox, the gears may be damaged if excessive force is used!	
15	**Note** There will be some excess oil running out of the gearbox when it is removed. Use some absorbent material to catch the oil.	

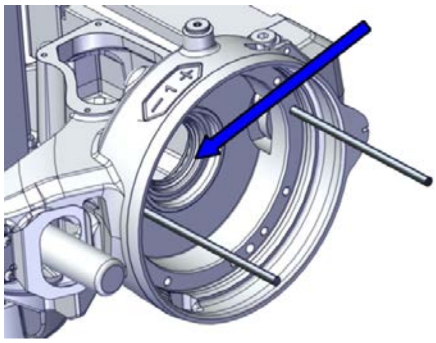
Continues on next page

	Action	Note
16	Slide the gearbox out onto the guide pins and lift it away. If necessary use removal tools to remove the gearbox.	**Note** Always use removal tools in pairs diagonal to each other.  xx1800000791

Refitting gearbox axis 1

Use these procedures to refit the gearbox.

Refitting the gearbox to the frame

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	Check the radial sealing in the frame. Replace if damaged.	 xx1800000794

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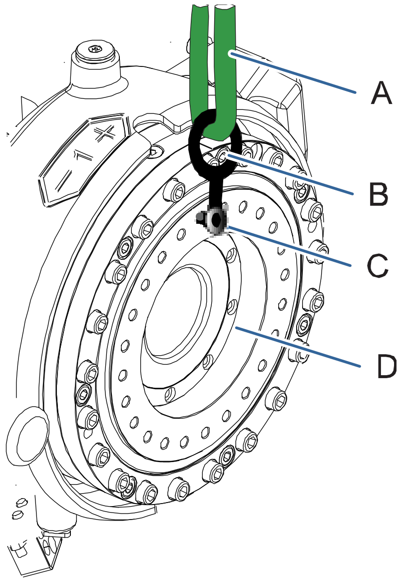
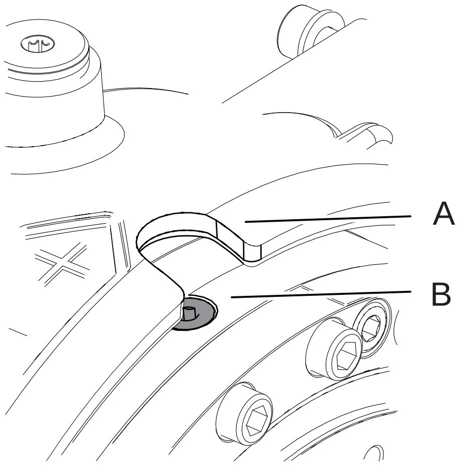
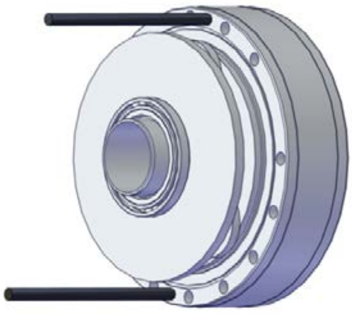
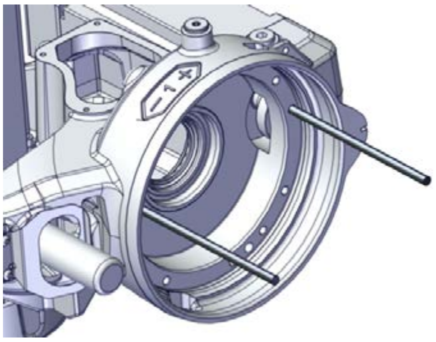
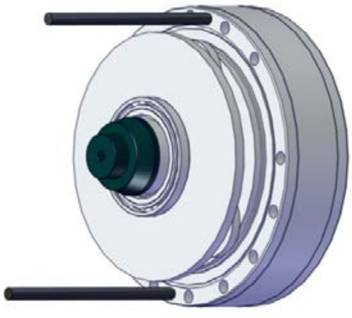
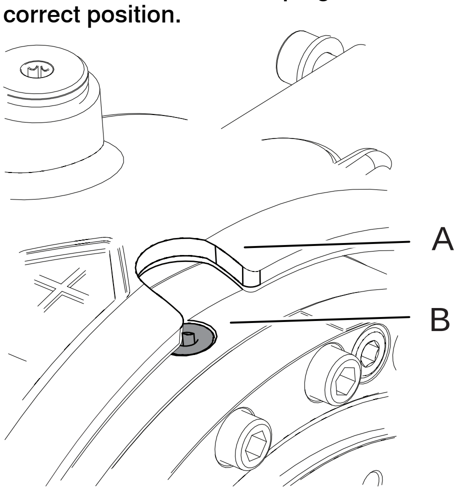
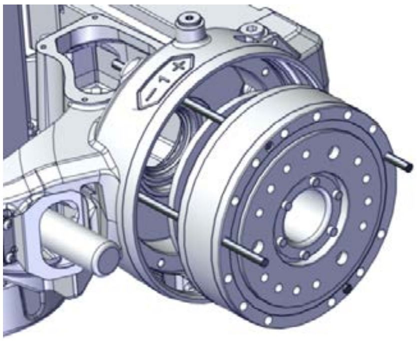
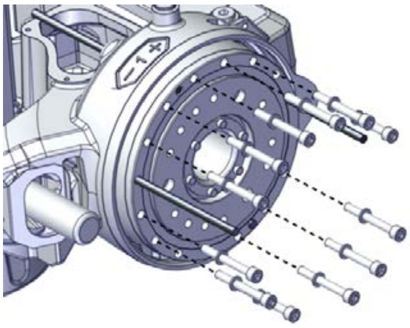
	Action	Note
3	Fit a lifting lug in the uppermost hole for the base attachment screws.	 xx0800000440 A Roundsling B Lifting lug C Uppermost base attachment hole D Axis-1 gearbox
4	**Note** Check, when fitting the lifting lug, that **both** *oil plugs* will be placed in the correct position after the gearbox is fitted as shown in the figure. The oil plugs shall be placed in the *openings* in the frame. (not valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C)	 xx0800000441 A Opening for oil plug in frame B Oil plug
5	Apply grease on the *o-ring*.	See the figure in: • *Location of gearbox on page 365* Replace o-ring if damaged.
6	Clean all assembly surfaces. Remove any painting from the assembly surfaces, with a knife.	

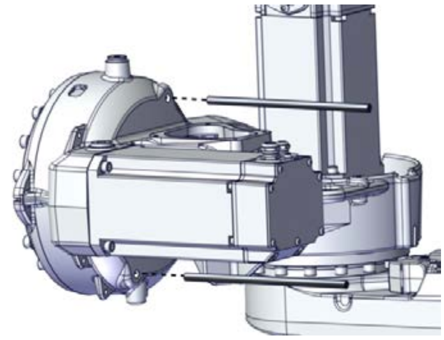
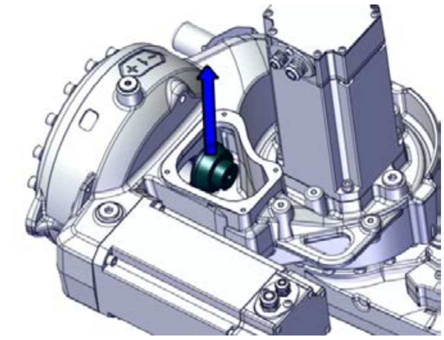
Continues on next page

	Action	Note
7	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Fit two guide pins to the gearbox.	 xx1800000792 Guide pin, M8x100: 3HAC15520-1 Always use guide pins in pairs!
8	Fit two guide pins to the frame.	 xx1800000793 Guide pin, M8x150: 3HAC15520-2 Always use guide pins in pairs!
9	Fit the guide for the gear on top of the protection tube. It protects the radial sealing from being damaged during refitting.	 xx1800000795
10	**CAUTION** The gearbox weighs . 27 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 24 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	

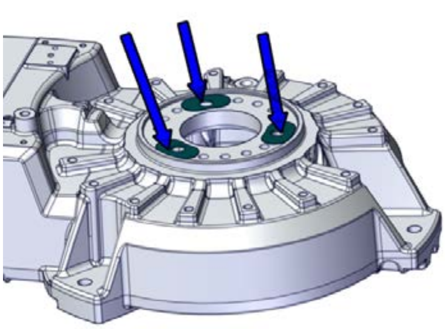
Continues on next page

	Action	Note
11	Lift the gearbox onto the guide pins and slide it into position, using caution. Check that the radial sealing in the frame tube does not get damaged. **Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Double check that the oil plugs are in the correct position.  xx0800000441 A Opening for oil plug in frame B Oil plug	 xx1800000791
12	Secure the gearbox with its attachment screws and washers.	 xx1800000790 **Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Tightening torque: 35 Nm. **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Tightening torque: 50 Nm.
13	Remove the guide pins from the frame and secure the remaining two screws.	

Continues on next page

	Action	Note
14	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Remove the two guide pins from the gearbox.	 xx1800000788
15	Remove the guide from the protection tube.	 xx1800000796

Refitting the arm system to the base

	Action	Note
1	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** 1 Remove the three gaskets on the base. 2 Wipe out the oil from the holes in the base and wipe the sealing surfaces dry. 3 Fit three new gaskets to the base. The gaskets are included with the gearbox spare part.	 xx1800000797
2	Refit the complete arm system to the base.	See *Refitting the base on page 303*.
3	Refit the axis-1 motor.	See *Refitting motors on page 321*.
4	Refit the cable harness in the base, the frame and the lower arm.	Also see • *Refitting the cable harness in the base on page 218* • *Refitting the cable harness in the frame on page 215* • *Refitting the cable harness in the lower arm and armhouse on page 224* .

Continues on next page

	Action	Note
5	Refill oil in the gearbox.	See *Changing the oil, axis 1 gearbox on floor mounted robots on page 150*.
6	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
7	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.8.2 Replacing gearbox axis 2

Different versions of the gearbox

There are two different versions of the axis-1 and axis-2 gearboxes. The different versions affect the mechanical structure of the base, frame and lower arm. Differences in the mechanical structure are pointed out in the procedure as valid for different robot version:

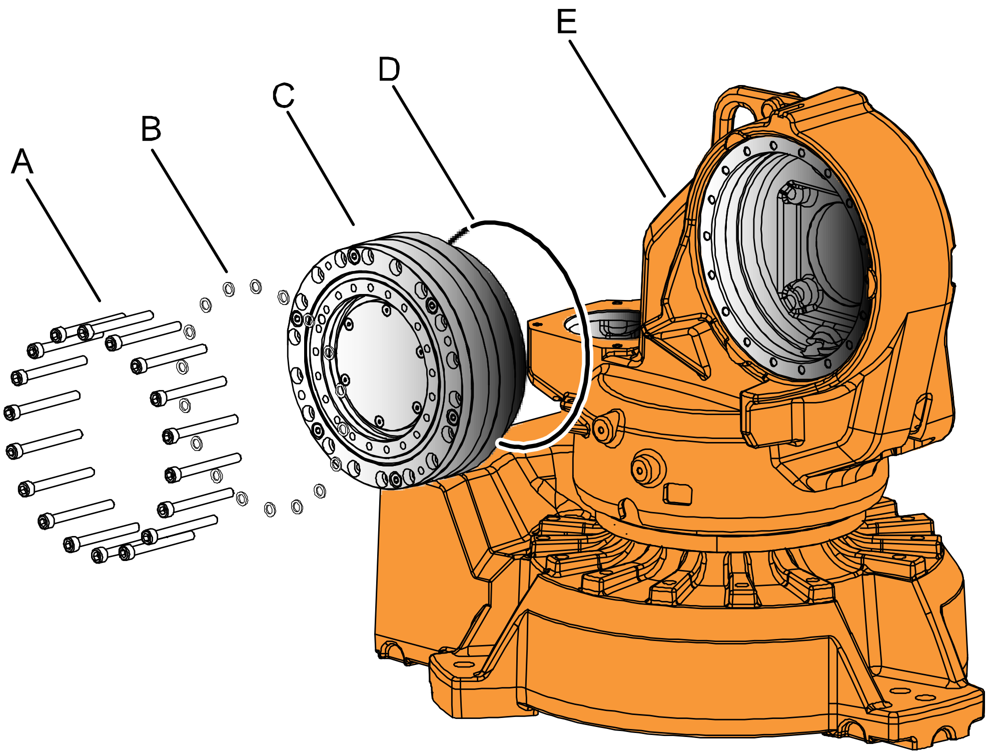
- IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0
- IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C

Further information about the differences are given in *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

Location of gearbox axis 2

The gearbox is located as shown in the figure.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



xx0900000380

A	Attachment screws M8x80 quality steel 12.9 Gleitmo (17 pcs)
B	Washers (17 pcs)
C	Gearbox axis 2
D	O-ring
E	Frame

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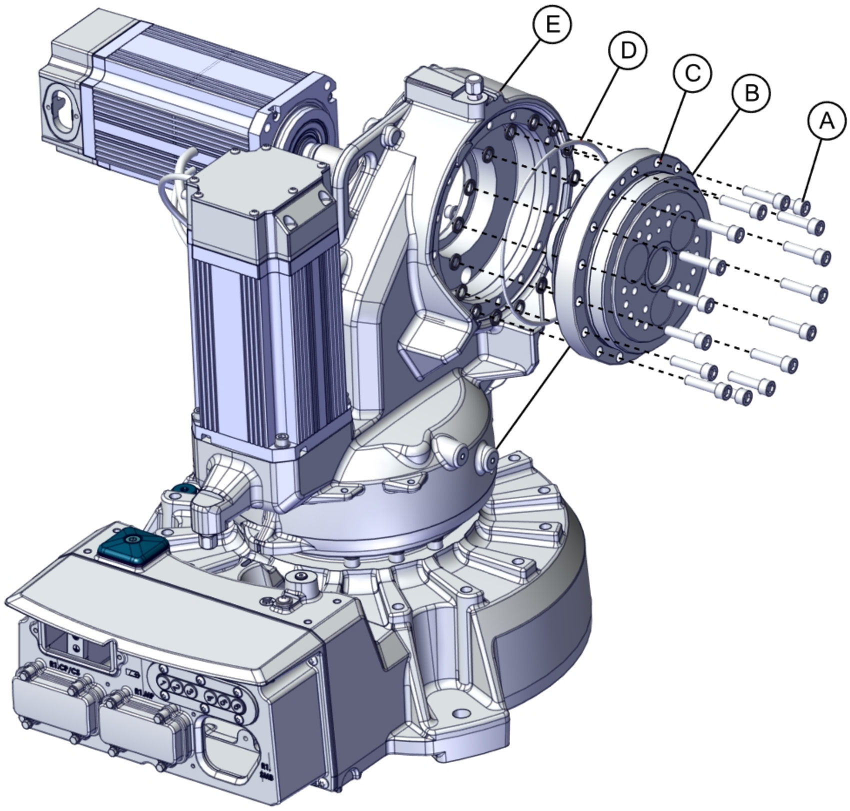
IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



xx1800000940

A	Attachment screws M10x40 12.9 Gleitmo 603+Geomet 500 (16 pcs)
B	Washers (16 pcs)
C	Gearbox axis 2
D	O-ring
E	Frame

Required equipment

Equipment	Article number	Note
Gearbox	See *Spare part lists on page 461*.	
Rotation tool	3HAB7887-1	
Lifting accessories	-	Roundslings.
Guide pin, M8x150	3HAC15520-2	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0.** Always use guide pins in pairs.
Guide pin, M10x150	3HAC15521-2	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C.** Always use guide pins in pairs.

Continues on next page

Equipment	Article number	Note
Locking liquid		Loctite 2400 (or equivalent Loctite 243) Clean Room robots
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

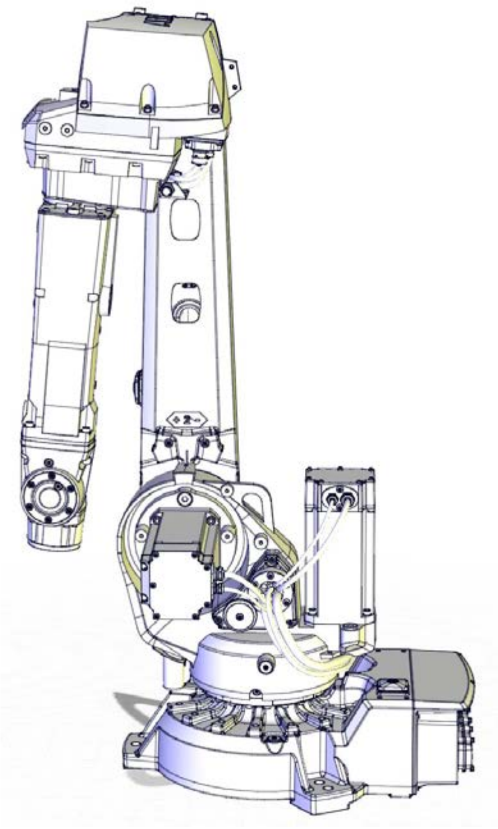
Removing gearbox axis 2

Use this procedure to remove the gearbox.

WARNING

The procedure details how to replace the gearbox without removing the cable harness, only by loosening it. This means that the upper and lower arm will be separated from the frame but still be connected to the frame through the cabling. Be careful not to damage the cables!

Continues on next page

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	
2	Move the robot to the position shown in the figure. Upper arm should rest on the axis-3 damper.	 xx1200000068
3	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
4	Drain the gearbox.	How to drain the gearbox is described in section: • *Changing the oil, axis-2 gearbox on page 163*

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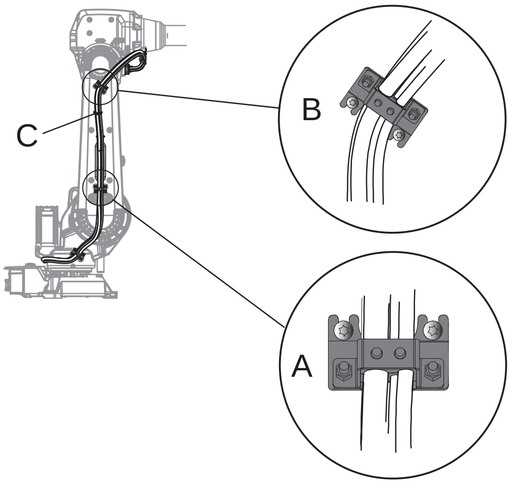
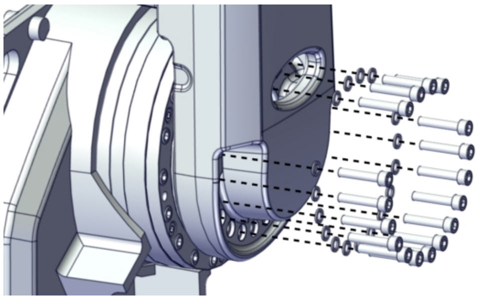
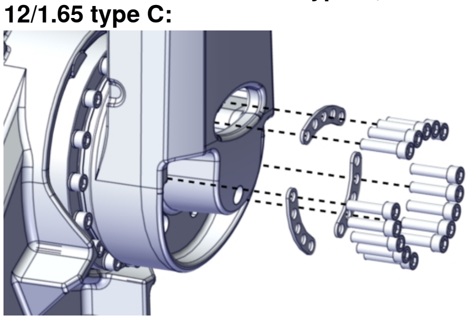
	Action	Note
5	Loosen the cabling from the lower arm by removing two cable brackets and a cable strap.	 xx1100000946 A Cable bracket B Cable bracket C Cable strap
6	**CAUTION** The weight of the complete upper and lower arm together is 100 kg All lifting accessories used must be sized accordingly.	
7	Attach a roundsling around the upper arm house.	
8	Unload the weight of the lower and upper arm package by stretching the roundslings with the overhead crane. Turn on the power temporarily and release the brakes of axis 2 to rest the weight onto the roundslings.	
9	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	

Continues on next page

	Action	Note
10	Remove the *attachment screws and washers* that secure the lower arm to the axis-2 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:**  xx1800000935 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:**  xx1800000934
11	Remove the lower and upper arm package from the frame. **WARNING** The cable harness is still installed on the robot! Make sure not to damage the cables or the cable brackets on the robot.	
12	**CAUTION** The gearbox weighs 23 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 14 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	

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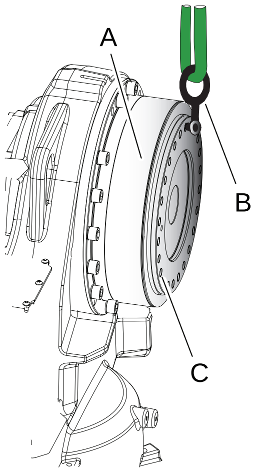
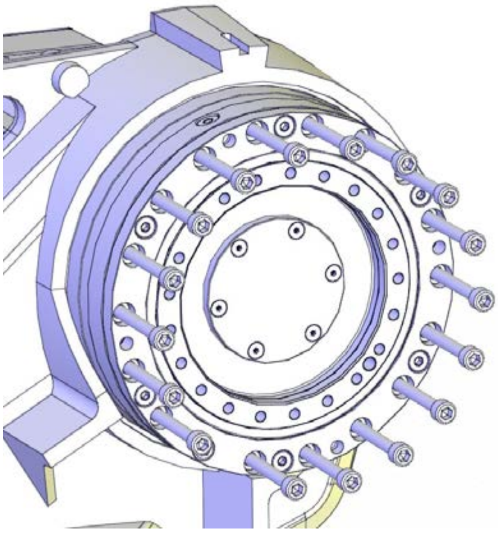
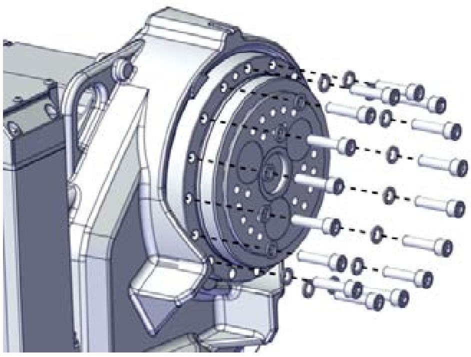
	Action	Note
13	Fit a *lifting lug* in the uppermost hole for the attachment screws that secure the lower arm to the gearbox.	 xx0800000445 Parts: • A: Gearbox axis 2 • B: Lifting lug • C: Holes for attachment screws that secure the lower arm to the axis-2 gearbox
14	Secure the gearbox with a roundsling in an overhead crane or similar.	

Continues on next page

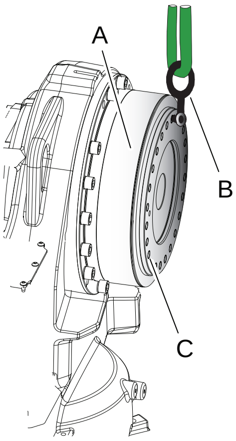
	Action	Note
15	Remove the *attachment screws and washers* that secure the gearbox to the frame.  **CAUTION** **Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Notice that there are six screws that must not be removed! These six screws keep the gearbox assembled. Removing these screws would cause the gearbox to fall apart! Only remove the screws that secure the gearbox to the frame, shown in the figure!	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:**  xx1200000086 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:**  xx1800000939
16	Fit guide pins to help guiding the gearbox out from the frame.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Guide pin, M8x150: 3HAC15520-2 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Guide pin, M10x150: 3HAC15521-2 Always use guide pins in pairs.
17	If necessary, use removal tools to remove the gearbox.	 **Note** Always use removal tools in pairs diagonal to each other.

Continues on next page

	Action	Note
18	Remove the gearbox. **CAUTION** Use caution in order not to damage gearbox or pinion!	

Refitting gearbox axis 2

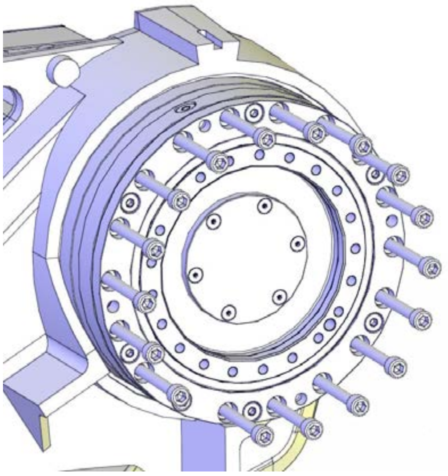
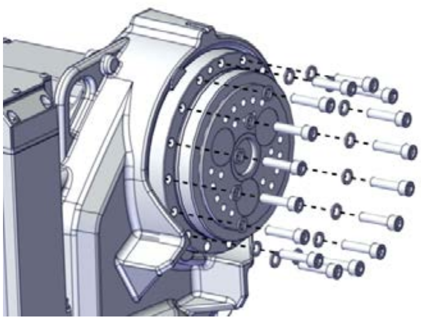
Use this procedure to refit the gearbox.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**CAUTION** The gearbox weighs 23 kg (IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0) 14 kg (IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C) All lifting accessories used must be sized accordingly!	
3	Fit a **lifting lug** in the uppermost hole for the attachment screws securing the lower arm to the gearbox.	 xx0800000445 Parts: • A: Gearbox axis 2 • B: Lifting lug • C: Holes for attachment screws securing the lower arm to gearbox axis 2.

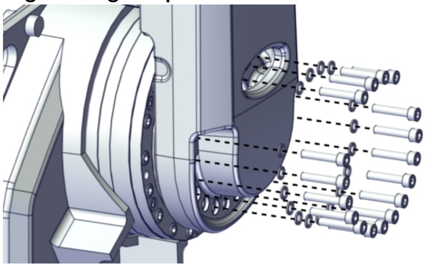
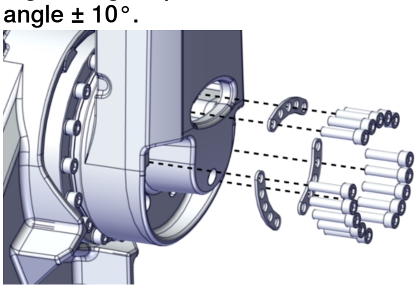
Continues on next page

	Action	Note
4	Clean all assembly surfaces. Remove any painting from the assembly surfaces, with a knife.	
5	Apply some grease on the o-ring before fitting. **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Replace if damaged.	**Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** O-ring: 3HAB3772-106. See the figure in: • *Location of gearbox axis 2 on page 378*
6	Fit two guide pins in opposite holes in the frame.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Guide pin, M8x150: 3HAC15520-2 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Guide pin, M10x150: 3HAC15521-2 Always use guide pins in pairs.
7	Secure the gearbox with a roundsling in an overhead crane or similar.	
8	Release the brakes of the axis 2 motor.	
9	Lift the gearbox onto the guide pins and slide it into position while rotating the motor pinion to find the mating position. Use a *rotation tool*.	Article number is specified in *Required equipment on page 379*.

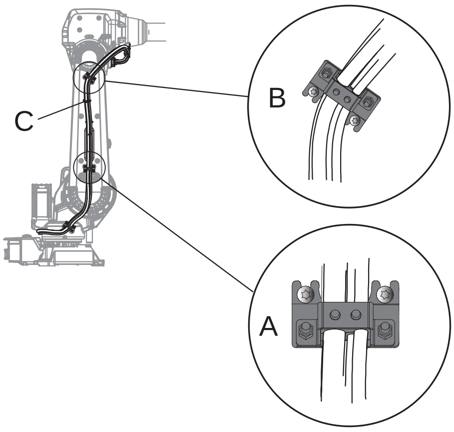
Continues on next page

	Action	Note
10	Secure the gearbox with its *attachment screws* and *washers*.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Attachment screws: M8x80 quality steel 12.9 Gleitmo (17 pcs) Tightening torque: 35 Nm.  xx1200000086 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Attachment screws M10x40 12.9 Gleitmo 603+Geomet 500 (16 pcs) Tightening torque: 68 Nm.  xx1800000939
11	Perform a leak-down test.	See *Performing a leak-down test on page 190*.
12	Fit the guide pins to the gearbox.	
13	**CAUTION** The weight of the complete upper and lower arm together is 100 kg All lifting accessories used must be sized accordingly.	

Continues on next page

	Action	Note
14	Lift the upper and lower arms into mounting position and guide them in place with the guide pins. It might be necessary to rotate the motor pinion with the rotating tool to find the mating position.	
15	Refit the *attachment screws and washers* to secure the lower arm to the axis-2 gearbox.	**Valid for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0:** Attachment screws: M8x40 quality steel Gleitmo 12.9 (17 pcs) Washers: 3HAA1001-172 (17 pcs) Tightening torque: 35 Nm.  xx1800000935 **Valid for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C:** Attachment screws: M10x40 12.9 Gleitmo 603+Geomet 500 (15 pcs) Washers: 3HAC043534-001 (3 pcs) Tightening torque: 50 Nm ± 5 Nm and 90° angle ± 10°.  xx1800000934

Continues on next page

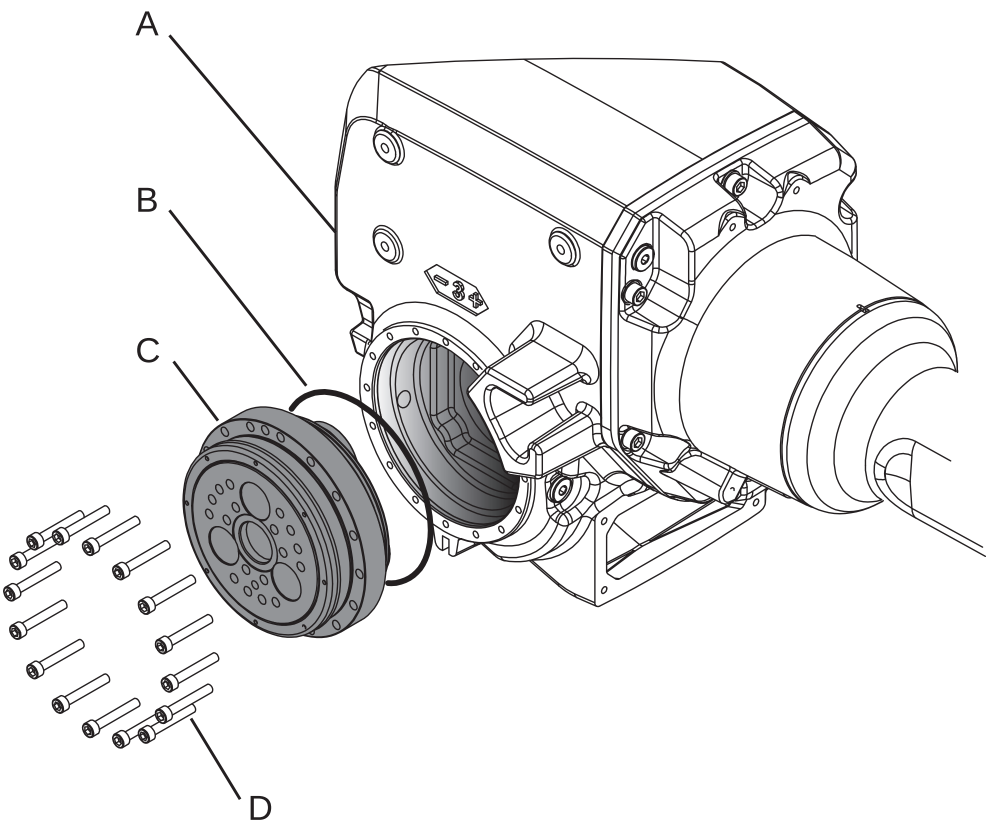
	Action	Note
16	Refit the cable brackets and cable strap to the lower arm.	 xx1100000946 A Cable bracket B Cable bracket C Cable strap
17	Refill the gearbox with *lubrication oil*.	How to fill the gearbox with oil is described in section: • *Changing the oil, axis-2 gearbox on page 163*
18	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.
19	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

4.8.3 Replacing gearbox axis 3

Location of gearbox axis 3

The gearbox is located as shown in the figure.

The figure shows the standard version of IRB 2600. Assembly is the same for IRB 2600ID.



xx0900000381

A	Upper arm
B	O-ring
C	Gearbox, axis 3
D	Attachment screws M6x40 quality Steel 12.9 Gleitmo (16 pcs)

Required equipment

Equipment	Art. no.	Note
Gearbox		See *Spare part lists on page 461*.
Guide pins		2 pcs, dimension: M6. 2 pcs, dimension: M8. Used to guide the gearbox and the upper arm during removal/refitting.
Locking liquid		Loctite 2400 (or equivalent Loctite 243) Clean Room robots

Continues on next page

Equipment	Art. no.	Note
Rotation tool	3HAB7887-1	
Standard toolkit		Content is defined in section *Standard tools on page 456*.
Other tools and procedures may be required. See references to these procedures in the step-by-step instructions below.		These procedures include references to the tools required.

Deciding calibration routine

Decide which calibration routine to be used, based on the information in the table. Depending on which routine is chosen, action might be required prior to beginning the repair work of the robot, see the table.

	Action	Note
1	Decide which calibration routine to use for calibrating the robot. • Reference calibration. External cable packages (DressPack) and tools can stay fitted on the robot. • Fine calibration. All external cable packages (DressPack) and tools must be removed from the robot.	
	If the robot is to be calibrated with reference calibration: Find previous reference values for the axis or create new reference values. These values are to be used after the repair procedure is completed, for calibration of the robot. If no previous reference values exist, and no new reference values can be created, then reference calibration is not possible.	Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values. Creating new values requires possibility to move the robot. Read more about reference calibration for Axis Calibration in *Reference calibration routine on page 415*.
	If the robot is to be calibrated with fine calibration: Remove all external cable packages (DressPack) and tools from the robot.	

Removing gearbox axis 3

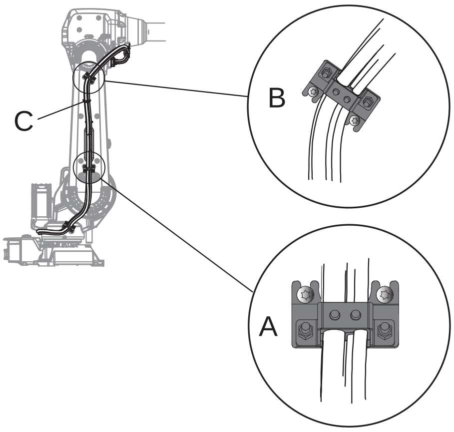
Use this procedure to remove the gearbox.

WARNING

The procedure details how to replace the gearbox without removing the cable harness. This means that the upper and lower arm will be separated but still be connected to eachother through the cabling. Be careful not to damage the cables!

	Action	Note
1	Decide which calibration routine to use, and take actions accordingly prior to beginning the repair procedure.	

Continues on next page

	Action	Note
2	Drain the gearbox.	How to drain the gearbox is described in section: • *Changing the oil, axis-3 gearbox on page 167*
3	Move the robot to the position shown in the figure.	 xx0800000336
4	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
5	Unscrew the attachment screws securing the cable harness to the lower arm by the two cable brackets and a cable strap.	 xx1100000946 A Cable bracket B Cable bracket C Cable strap
6	Loosen the cabling from the lower arm by unhooking the two cable brackets. **CAUTION** The cable harness is still mounted in other parts of the robot. Make sure not to damage the cable harness or any cable brackets in the continued removal.	

Continues on next page

	Action	Note
7	Attach the lifting accessories to the upper arm.	See *Attaching the lifting accessories to the upper arm on page 256*
8	Connect the 24 VDC power supply to the axis-3 motor and release the brakes.	
9	Releasing the brakes of the axis-3 motor unloads the weight of the upper arm by stretching the roundslings.	
10	Remove the *attachment screws* that secure the upper arm to the lower arm. **Note** Do not remove the attachment screws securing the gearbox axis 3 to the armhouse!	See the figure in: • *Location of the complete upper arm on page 251*
11	**CAUTION** The robot upper arm weighs 65 kg. All lifting accessories used must be sized accordingly!	
12	Remove the upper arm from the lower arm and leave it hanging in the air. **CAUTION** When the upper arm no longer is attached to the robot, the armhouse has a tendency to drop down a little. In order to prevent this is to rise the front end of the upper arm a little before removing the attachment screws securing the upper arm.	**WARNING** The cable harness is still installed on the robot! Make sure not to damage the cable harness or the cable brackets on the robot.
13	**CAUTION** The gearbox weighs 6 kg. All lifting accessories used must be sized accordingly!	
14	Remove two attachment screws diagonally located and insert guide pins.	Always use guide pins in pairs!
15	Remove the remaining *attachment screws* that secures the gearbox.	See the figure in: • *Location of gearbox axis 3 on page 391*
16	**Note** There will be some surplus oil in the gearbox. Place some absorbant cloth or similar under the gearbox.	

Continues on next page

	Action	Note
17	Slide the gearbox carefully out onto the guide pins and lift it away. If necessary, use a pair of screws to push out the gearbox. **CAUTION** Remaining oil will drain out from the gearbox cavity when the gearbox is lifted out.	**Note** Always use removal tools in pairs diagonal to each other.

Refitting the gearbox axis 3

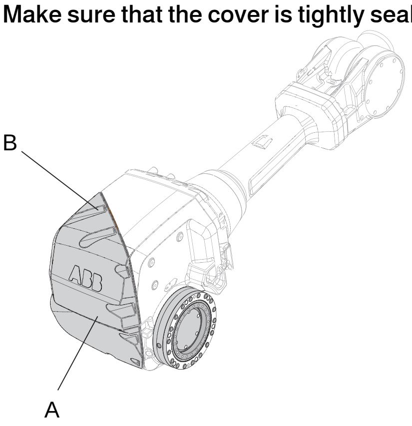
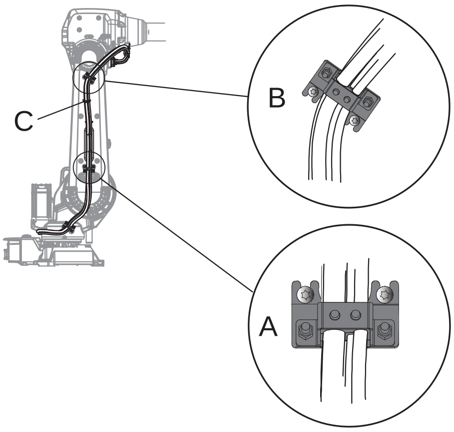
Use this procedure to refit the gearbox.

	Action	Note
1	**DANGER** Turn off all: • electric power supply • hydraulic pressure supply • air pressure supply to the robot, before entering the robot working area.	
2	**CAUTION** The gearbox weighs 6 kg. All lifting accessories used must be sized accordingly!	
3	Clean all assembly surfaces. Remove any painting or other contamination from the assembly surfaces, with a knife.	
4	Apply some grease on the o-ring before fitting it to the gearbox.	See the figure in: • *Location of gearbox axis 3 on page 391*
5	Fit two guide pins in two opposite screw holes in the upper arm.	Always use guide pins in pairs!
6	Remove the arm house cover.	
7	Attach the rotation tool on the axis-3 motor.	
8	Release the brakes of the axis 3 motor.	
9	Lift the gearbox onto the guide pins.	
10	**Note** Whenever parting/mating motor and gearbox, the gears may be damaged if excessive force is used!	

Continues on next page

	Action	Note
11	Slide the gearbox into position while rotating the motor pinion to find the mating position. Use a *rotation tool*. **Tip** Two persons are required for this step since the upper arm is hanging freely in the air. One person needs to hold the upper arm still while the other fits the gearbox into the upper arm.	Article number for the rotation tool is specified in *Required equipment on page 391*.
12	Rotate the motor pinion and slide the gear-box into position.	
13	Secure the gearbox with its *attachment screws*.	See the figure in: • *Location of gearbox axis 3 on page 391* Tightening torque: 17 Nm.
14	Remove the guide pins and replace them with the remaining attachment screws.	
15	Perform a leak-down test.	See *Performing a leak-down test on page 190*.
16	Fit *guide pins* in the upper arm.	Specified in *Required equipment on page 391*.
17	Move the upper arm to its mounting position. (With the brakes of the axis 3 motor still released.)	
18	Refit the upper arm to the lower arm with its *attachment screws*.	See the figure in: • *Location of the complete upper arm on page 251* Tightening torque: • 35 Nm
19	Remove the guide pins and replace with the remaining attachment screws.	
20	Remove the 24 VDC power supply.	

Continues on next page

	Action	Note
21	Refit the upper armhouse cover with its attachment screws and washers. **WARNING** The cover on the armhouse must be fitted when the robot is running. It is a vital part for the stability of the robot.	Tightening torque: 14 Nm. Make sure that the cover is tightly sealed.  xx0800000389 Parts: • A: Cover • B: Attachment screws M6x25, quality 8.8-A2F (8 pcs)
22	Refit the two cable brackets and a cable strap to the lower arm.	 xx1100000946 A Cable bracket B Cable bracket C Cable strap
23	Refill the gearbox with *lubrication oil*.	How to fill the gearbox with oil is described in section: • *Changing the oil, axis-3 gearbox on page 167*
24	Recalibrate the robot.	Pendulum Calibration is described in *Operating manual - Calibration Pendulum*, enclosed with the calibration tools. Axis Calibration is described in *Calibrating with Axis Calibration method on page 414*. General calibration information is included in section *Calibration on page 399*.

Continues on next page

	Action	Note
25	**DANGER** Make sure all safety requirements are met when performing the first test run. See *Test run after installation, maintenance, or repair on page 111*.	

5 Calibration

5.1 Introduction to calibration

5.1.1 Introduction and calibration terminology

Calibration information

This chapter includes general information about the recommended calibration methods and also the detailed procedures for updating the revolution counters, checking the calibration position etc.

Detailed instructions of how to perform Axis Calibration are given on the FlexPendant during the calibration procedure. To prepare calibration with Axis Calibration method, see *Calibrating with Axis Calibration method on page 414*.

Detailed instructions of how to perform Pendulum Calibration are given in the documentation enclosed with the calibration tools.

Calibration terminology

Term	Definition
Calibration method	A collective term for several methods that might be available for calibrating the ABB robot. Each method contains calibration routines.
Synchronization position	Known position of the complete robot where the angle of each axis can be checked against visual synchronization marks.
Calibration position	Known position of the complete robot that is used for calibration of the robot.
Standard calibration	A generic term for all calibration methods that aim to move the robot to calibration position.
Fine calibration	A calibration routine that generates a new zero position of the robot.
Reference calibration	A calibration routine that in the first step generates a reference to current zero position of the robot. The same calibration routine can later on be used to recalibrate the robot back to the same position as when the reference was stored. This routine is more flexible compared to fine calibration and is used when tools and process equipment are installed. Requires that a reference is created before being used for recalibrating the robot. Requires that the robot is dressed with the same tools and process equipment during calibration as during creation of the reference values.
Update revolution counter	A calibration routine to make a rough calibration of each manipulator axis.
Synchronization mark	Visual marks on the robot axes. When marks are aligned, the robot is in synchronization position.

5.1.2 Calibration methods

Overview

This section specifies the different types of calibration and the calibration methods that are supplied by ABB.

Types of calibration

Type of calibration	Description	Calibration method
Standard calibration	The calibrated robot is positioned at calibration position. Standard calibration data is found on the SMB (serial measurement board) or EIB in the robot.	Axis Calibration or Calibration Pendulum [i]
Absolute accuracy calibration (optional)	Based on standard calibration, and besides positioning the robot at synchronization position, the Absolute accuracy calibration also compensates for: • Mechanical tolerances in the robot structure • Deflection due to load Absolute accuracy calibration focuses on positioning accuracy in the Cartesian coordinate system for the robot. Absolute accuracy calibration data is found on the serial measurement board (SMB) or other robot memory. For IRC5 robots, the absolute accuracy calibration data is delivered in a file, absacc.cfg, supplied with the robot at delivery. The file replaces the calib.cfg file and identifies motor positions as well as absolute accuracy compensation parameters. A robot calibrated with Absolute accuracy has a sticker next to the identification plate of the robot (IRC5). A robot calibrated with Absolute accuracy has the option information printed on its name plate (OmniCore). To regain 100% Absolute accuracy performance, the robot must be recalibrated for absolute accuracy after repair or maintenance that affects the mechanical structure.  xx0400001197	CalibWare

Continues on next page

Type of calibration	Description	Calibration method
Optimization	Optimization of TCP reorientation performance. The purpose is to improve reorientation accuracy for continuous processes like welding and gluing. Wrist optimization will update standard calibration data for axes 4, 5 and 6. **Note** For advanced users, it is also possible to use the do the wrist optimization using the RAPID instruction `WristOpt`, see *Technical reference manual - RAPID Instructions, Functions and Data types*. This instruction is only available for OmniCore robots.	Wrist Optimization

i The robot is calibrated by either Calibration Pendulum or Axis Calibration at factory. Always use the same calibration method as used at the factory.
Information about valid calibration method is found on the calibration label or in the calibration menu on the FlexPendant.
If no data is found related to standard calibration, contact the local ABB Service.

Brief description of calibration methods

Calibration Pendulum method

Calibration Pendulum is a standard calibration method for calibration of some ABB robots. On OmniCore, this calibration method is only used on IRB 1510, IRB 1520, IRB 2400, and IRB 4400.

Two different routines are available for the Calibration Pendulum method:

- Calibration Pendulum II
- Reference calibration

The calibration equipment for Calibration Pendulum is delivered as a complete toolkit, including the *Operating manual - Calibration Pendulum*, which describes the method and the different routines further.

Axis Calibration method

Axis Calibration is a standard calibration method for calibration of IRB 2600/IRB 2600 ID. It is the recommended method in order to achieve proper performance.

The following routines are available for the Axis Calibration method:

- Fine calibration
- Update revolution counters
- Reference calibration

The calibration equipment for Axis Calibration is delivered as a toolkit.

An introduction to the calibration method is given in this manual, see *Calibrating with Axis Calibration method on page 414*.

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

Continues on next page

Wrist Optimization method

Wrist Optimization is a method for improving reorientation accuracy for continuous processes like welding and gluing and is a complement to the standard calibration method.

The actual instructions of how to perform the wrist optimization procedure is given on the FlexPendant.

CalibWare - Absolute Accuracy calibration

The CalibWare tool guides through the calibration process and calculates new compensation parameters. This is further detailed in the *Application manual - CalibWare Field*.

If a service operation is done to a robot with the option Absolute Accuracy, a new absolute accuracy calibration is required in order to establish full performance. For most cases after replacements that do not include taking apart the robot structure, standard calibration is sufficient.

The Absolute Accuracy option varies according to the robot mounting position. This is printed on the robot name plate for each robot. The robot must be in the correct mounting position when it is recalibrated for absolute accuracy.

References

Article numbers for the calibration tools are listed in the section *Special tools on page 457*.

The calibration equipment for Calibration Pendulum is delivered as a complete toolkit, including the *Operating manual - Calibration Pendulum*, which describes the method and the different routines further.

5.1.3 When to calibrate

When to calibrate

The system must be calibrated if any of the following situations occur.

The resolver values are changed

If resolver values are changed, the robot must be re-calibrated using the calibration methods supplied by ABB. Calibrate the robot carefully with standard calibration, according to information in this manual.

If the robot has *absolute accuracy* calibration, it is also recommended, but not always necessary to calibrate for new absolute accuracy.

The resolver values will change when parts affecting the calibration position are replaced on the robot, for example motors or parts of the transmission.

The revolution counter memory is lost

If the revolution counter memory is lost, the counters must be updated. See *Updating revolution counters on page 408*. This will occur when:

- The battery is discharged
- A resolver error occurs
- The signal between a resolver and measurement board is interrupted
- A robot axis is moved with the control system disconnected

The revolution counters must also be updated after the robot and controller are connected at the first installation.

The robot is rebuilt

If the robot is rebuilt, for example, after a crash or when the reachability of a robot is changed, it needs to be re-calibrated for new resolver values.

If the robot has *absolute accuracy* calibration, it needs to be calibrated for new absolute accuracy.

Robot is not floor mounted

The original calibration data delivered with the robot is generated when the robot is floor mounted. If the robot is not floor mounted, then the robot accuracy could be affected. The robot needs to be calibrated after it is mounted.

5.2 Synchronization marks and axis movement directions

5.2.1 Synchronization marks and synchronization position for axes

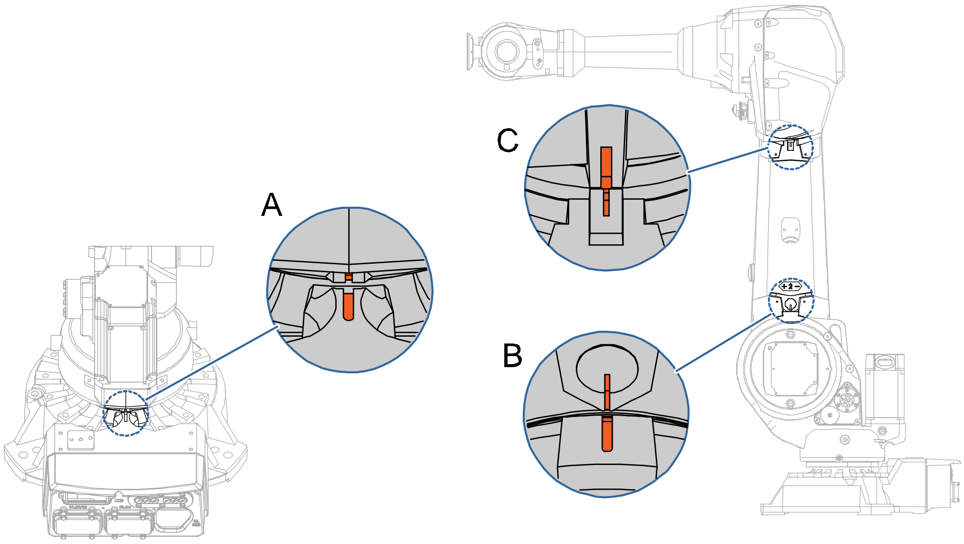
Introduction

This section shows the position of the synchronization marks and the synchronization position for each axis.

Synchronization marks, IRB 2600 and 2600ID

IRB 2600-20/1.65, -12/1.65, -12/1.85

IRB 2600 Type C-20/1.65, -12/1.65



xx0800000312

A	Synchronization mark, axis 1
B	Synchronization mark, axis 2
C	Synchronization mark, axis 3

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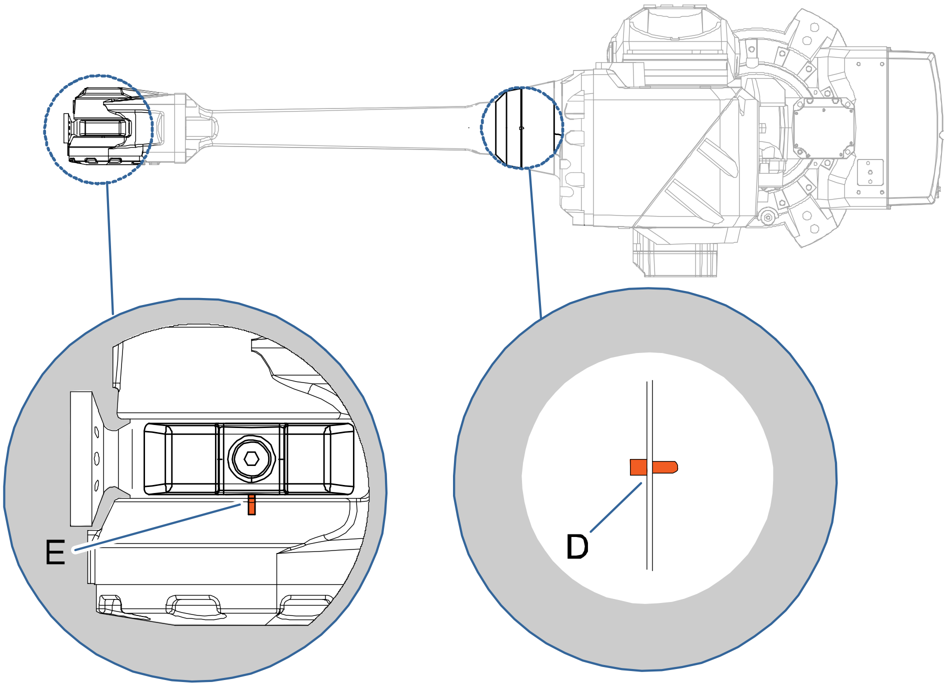
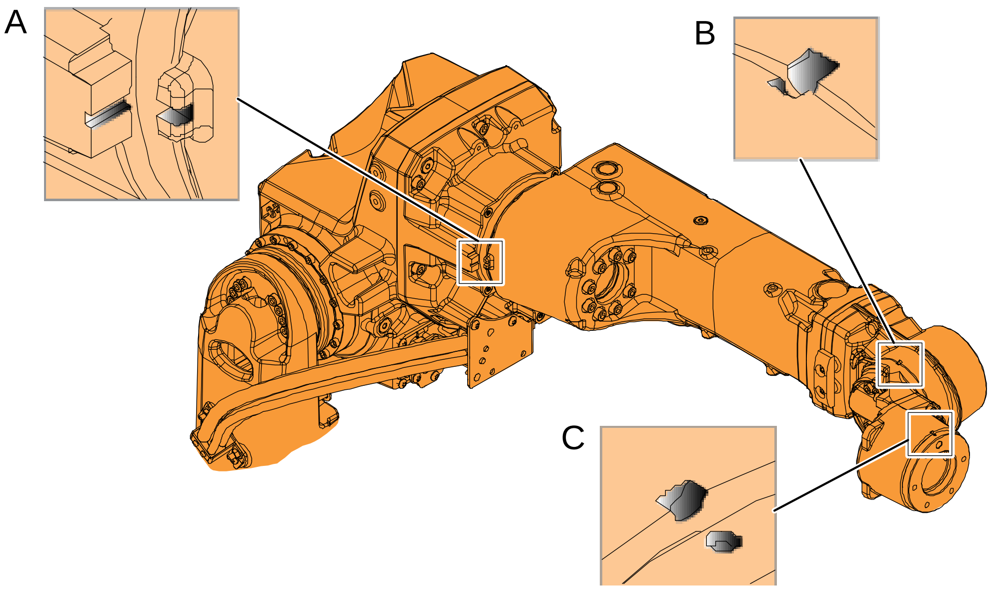
IRB 2600 -20/1.65, -12/1.65, -12/1.85



xx0800000320

D	Synchronization mark, axis 4
E	Synchronization mark, axis 5

IRB 2600ID -15/1.85, -8/2.00

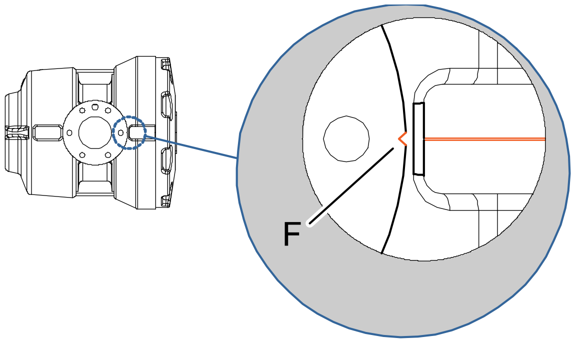


xx1000000445

A	Synchronization mark, axis 4
B	Synchronization mark, axis 5
C	Synchronization mark, axis 6

Continues on next page

IRB 2600 -20/1.65, -12/1.65, -12/1.85



xx0800000321

F	Synchronization mark, axis 6

5.2.2 Calibration movement directions for all axes

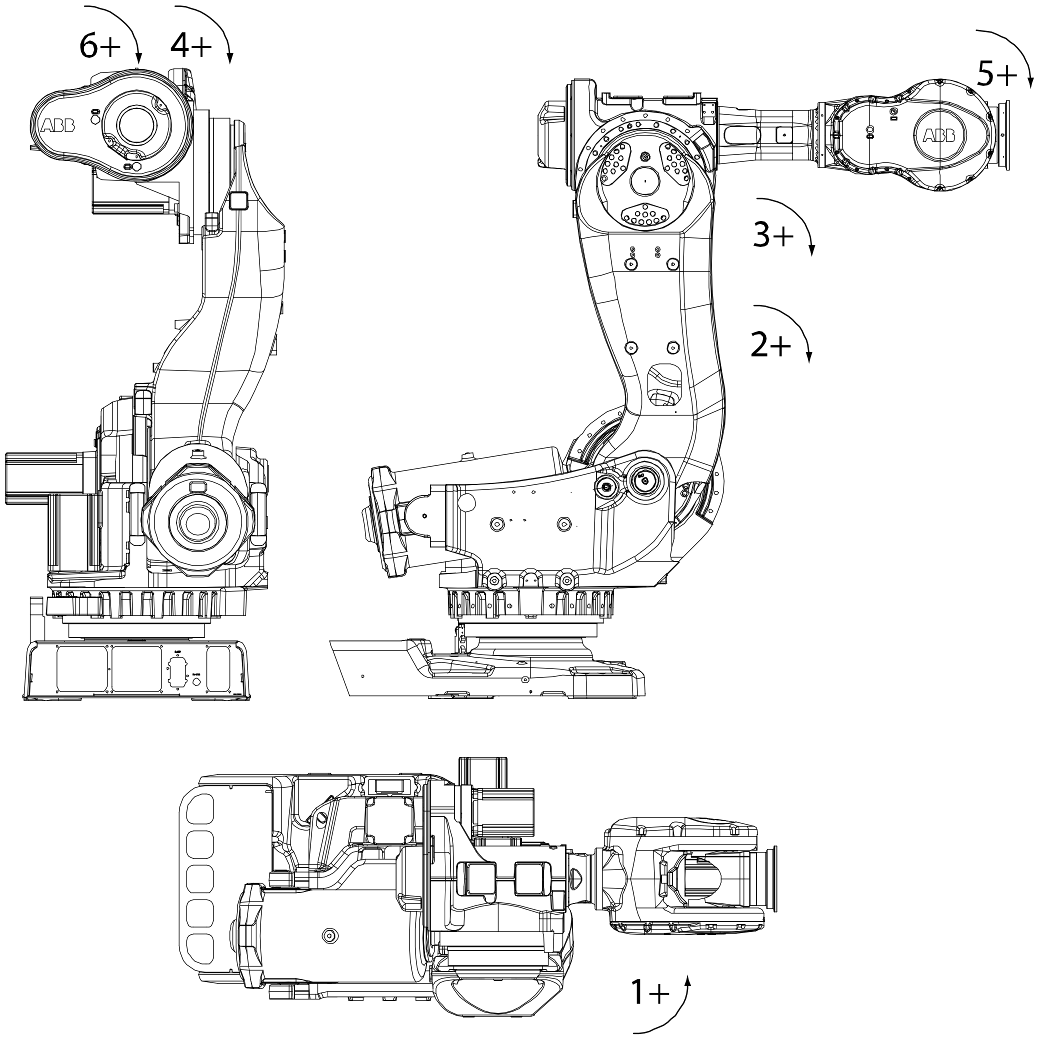
Overview

When calibrating, the axis must consistently be run towards the calibration position in the same direction in order to avoid position errors caused by backlash in gears and so on. Positive directions are shown in the graphic below.

Calibration service routines will handle the calibration movements automatically and these might be different from the positive directions shown below.

Manual movement directions, 6 axes

Note! The graphic shows an IRB 7600. The positive direction is the same for all 6-axis robots, except the positive direction of axis 3 for IRB 6400R, which is in the opposite direction!



xx0200000089

5.3 Updating revolution counters

5.3.1 Updating revolution counters on IRC5 robots

Introduction

This section describes how to do a rough calibration of each manipulator axis by updating the revolution counter for each axis, using the FlexPendant.

Coupled axes

When updating the revolution counters for a coupled axis, also the axis it is coupled to needs to be at its synchronization position for the update to be correct; i.e. axis 4 needs to be in synchronization position when updating axis 5 and 6.

With reversed coupled joints, the relationship is the opposite, i.e. axis 4 needs to be in synchronization position to update axis 3.

Coupled axes	IRB 1410	IRB 1510	IRB 1520	IRB 1600	IRB 1600ID	IRB 1660ID	IRB 910 SC	IRB 2400	IRB 2600	IRB 2600ID	IRB 4400	IRB 4450S	IRB 4600
Axis 4, 5, 6				x				x	x		x	x	x
Axis 5, 6	x	x	x		x	x				x			
Axis 4, 3							x						

Step 1 - Manually running the manipulator to the synchronization position

Use this procedure to manually run the manipulator to the synchronization position.

	Action	Note
1	Select axis-by-axis motion mode.	
2	Jog the manipulator to align the synchronization marks.	See *Synchronization marks and synchronization position for axes on page 404*.
3	When all axes are positioned, update the revolution counter.	*Step 2 - Updating the revolution counter with the FlexPendant on page 409*.

Correct calibration position of axis 4 and 6

When jogging the manipulator to synchronization position, it is extremely important to make sure that axes 4 and 6 of the following mentioned manipulators are positioned correctly. The axes can be calibrated at the wrong turn, resulting in an incorrect manipulator calibration.

Make sure the axes are positioned according to the correct calibration values, not only according to the synchronization marks. The correct values are found on a label, located either on the lower arm, underneath the flange plate on the base or on the frame.

Continues on next page

At delivery the manipulator is in the correct position. Do NOT rotate axis 4 or 6 at power up before the revolution counters are updated.

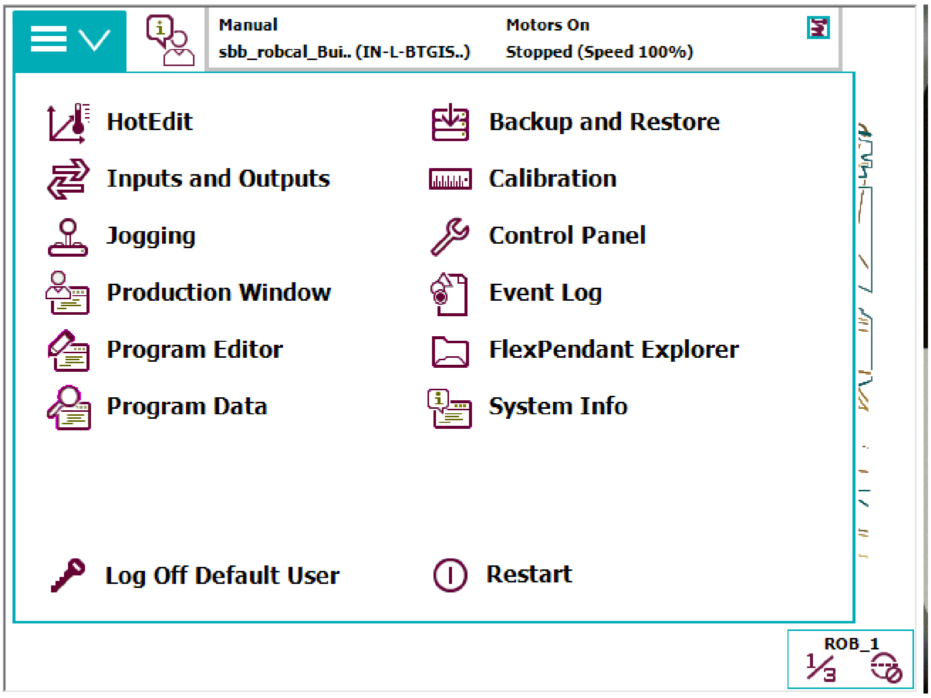
If one of the following mentioned axes are rotated one or more turns from its calibration position before updating the revolution counter, the correct calibration position will be lost due to non-integer gear ratio. This affects the following manipulators:

Manipulator variant	Axis 4	Axis 6
IRB 2600	No	No

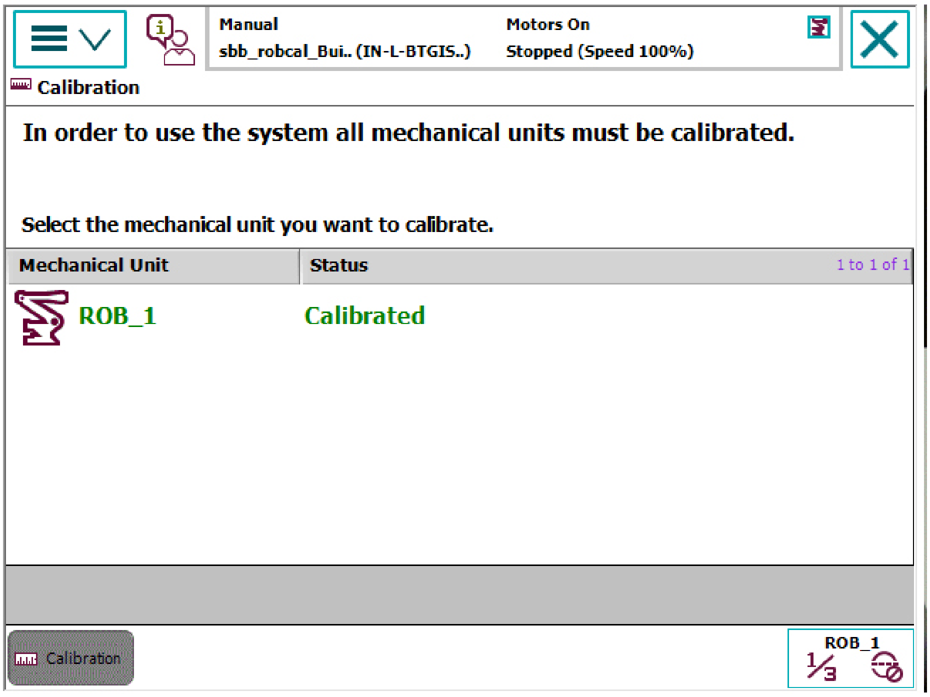
If the synchronization marks seem to be wrong (even if the motor calibration data is correct), try to rotate the axis one turn, update the revolution counter and check the synchronization marks again (try both directions, if needed).

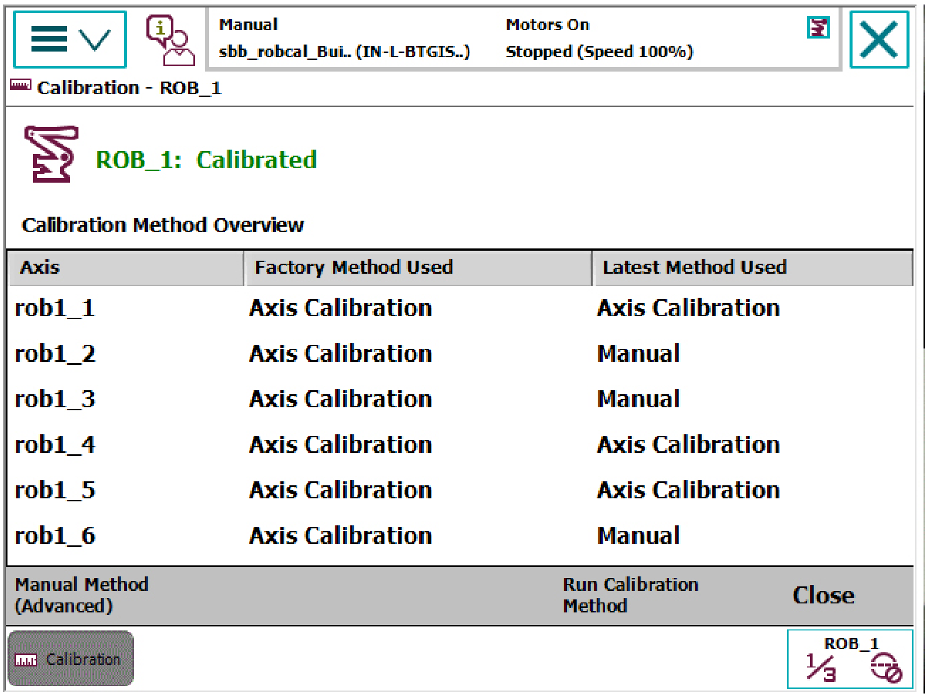
Step 2 - Updating the revolution counter with the FlexPendant

Use this procedure to update the revolution counter with the FlexPendant (IRC5).

	Action
1	On the **ABB** menu, tap **Calibration**.  xx1500000942

Continues on next page

<table>
<tr><th></th><th>Action</th></tr>
<tr><td>2</td><td>All mechanical units connected to the system are shown with their calibration status.
Tap the mechanical unit in question.


xx1500000943</td></tr>
<tr><td>3</td><td>This step is valid for RobotWare 6.02 and later.
Calibration method used at factory for each axis is shown, as well as calibration method used during last field calibration.
Tap Manual Method (Advanced).


xx1500000944</td></tr>
</table>

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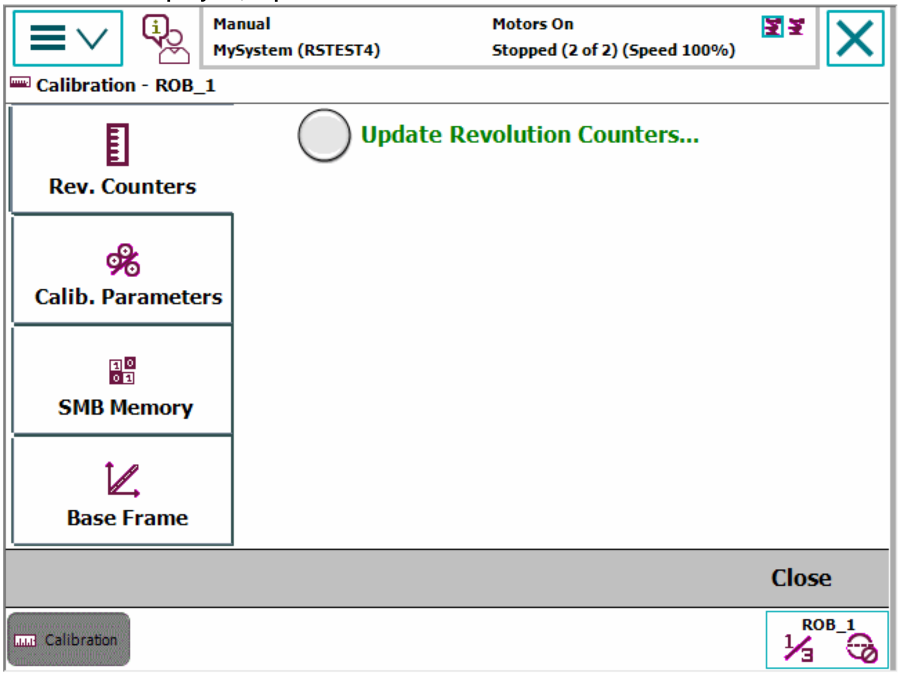
	Action
4	A screen is displayed, tap **Rev. Counters**.  en0400000771
5	Tap **Update Revolution Counters...**. A dialog box is displayed, warning that updating the revolution counters may change programmed robot positions: • Tap **Yes** to update the revolution counters. • Tap **No** to cancel updating the revolution counters. Tapping **Yes** displays the axis selection window.
6	Select the axis to have its revolution counter updated by: • Ticking in the box to the left • Tapping **Select all** to update all axes. Then tap **Update**.
7	A dialog box is displayed, warning that the updating operation cannot be undone: • Tap **Update** to proceed with updating the revolution counters. • Tap **Cancel** to cancel updating the revolution counters. Tapping **Update** updates the selected revolution counters and removes the tick from the list of axes.
8	**CAUTION** If a revolution counter is incorrectly updated, it will cause incorrect manipulator positioning, which in turn may cause damage or injury! Check the synchronization position very carefully after each update. See *Checking the synchronization position on page 435*.

5.3.2 Updating revolution counters on OmniCore robots

Introduction

This section describes how to do a rough calibration of each manipulator axis by updating the revolution counter for each axis, using the FlexPendant.

Step 1 - Manually running the manipulator to the synchronization position

Use this procedure to manually run the manipulator to the synchronization position.

	Action	Note
1	Select axis-by-axis motion mode.	
2	Jog the manipulator to align the synchronization marks.	See *Synchronization marks and synchronization position for axes on page 404*.
3	When all axes are positioned, update the revolution counter.	*Step 2 - Updating the revolution counter with the FlexPendant on page 412*.

Correct calibration position of axis 4 and 6

When jogging the manipulator to synchronization position, it is extremely important to make sure that axes 4 and 6 of the following mentioned manipulators are positioned correctly. The axes can be calibrated at the wrong turn, resulting in an incorrect manipulator calibration.

Make sure the axes are positioned according to the correct calibration values, not only according to the synchronization marks. The correct values are found on a label, located either on the lower arm, underneath the flange plate on the base or on the frame.

At delivery the manipulator is in the correct position. Do NOT rotate axis 4 or 6 at power up before the revolution counters are updated.

If one of the following mentioned axes are rotated one or more turns from its calibration position before updating the revolution counter, the correct calibration position will be lost due to non-integer gear ratio. This affects the following manipulators:

Manipulator variant	Axis 4	Axis 6
IRB 2600	No	No

If the synchronization marks seem to be wrong (even if the motor calibration data is correct), try to rotate the axis one turn, update the revolution counter and check the synchronization marks again (try both directions, if needed).

Step 2 - Updating the revolution counter with the FlexPendant

Use this procedure to update the revolution counter with the FlexPendant (OmniCore).

	Action
1	On the start screen, tap **Calibrate**. The calibration summary page for the mechanical unit is displayed.
2	In the **Calibration Methods** menu, select **Revolution Counters**.

Continues on next page

	Action
3	In the **Selection** column select the axes for which revolution counters need to be updated.
4	Tap **Update**. A dialog box is displayed warning that the updating operation cannot be undone.
5	Tap **OK** to update the revolution counter.
6	**CAUTION** If a revolution counter is incorrectly updated, it will cause incorrect manipulator positioning, which in turn may cause damage or injury! Check the synchronization position very carefully after each update. See *Checking the synchronization position on page 435*.

5.4 Calibrating with Axis Calibration method

5.4.1 Description of Axis Calibration

Instructions for Axis Calibration procedure given on the FlexPendant

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

This manual contains a brief description of the method, additional information to the information given on the FlexPendant, article number for the tools and images of where to fit the calibration tools on the robot.

Overview of the Axis Calibration procedure

The Axis Calibration procedure applies to all axes, and is performed on one axis at the time. The robot axes are both manually and automatically moved into position, as instructed on the FlexPendant.

A fixed calibration pin/bushing is installed on each robot axis at delivery.

The Axis Calibration procedure described roughly:

1. A removable calibration tool is inserted by the operator into a calibration bushing on the axis chosen for calibration, according to instructions on the FlexPendant.

   WARNING

   Calibrating the robot with Axis Calibration requires special calibration tools from ABB. Using other pins in the calibration bushings may cause severe damage to the robot and/or personnel.

   WARNING

   The calibration tool must be fully inserted into the calibration bushing, until the steel spring ring snaps into place.

2. During the calibration procedure, RobotWare moves the robot axis chosen for calibration so that the calibration tools get into contact. RobotWare records values of the axis position and repeats the coming-in-contact procedure several times to get an exact value of the axis position.

   WARNING

   Risk of pinching! The contact force for large robots can be up to 150 kg. Keep a safe distance to the robot.

3. The axis position is stored in RobotWare with an active choice from the operator.

Continues on next page

Routines in the calibration procedure

The following routines are available in the Axis Calibration procedure, given at the beginning of the procedure on the FlexPendant.

Fine calibration routine

Choose this routine to calibrate the robot when there are no tools, process cabling or equipment fitted to the robot.

Reference calibration routine

Choose this routine to create reference values and to calibrate the robot when the robot is dressed with tools, process cabling or other equipment.

Also choose this routine if the robot is wall mounted or suspended.

Note

When calibrating the robot with the reference calibration routine, the robot must be dressed with the same tools, process cabling and any other equipment as when the reference values were created.

Note

When using reference calibration with some tools, typically large or flexible tools, oscillations in the robot can cause issues leading to failure of the calibration.

If calibrating the robot with reference calibration there must be reference values created before repair is made to the robot, if values are not already available. Creating new values requires possibility to move the robot. The reference values contain positions of all axes, torque of axes and technical data about the tool installed. A benefit with reference calibration is that the current state of the robot is stored and not the state when the robot left the ABB factory. The reference value will be named according to tool name, date etc.

Follow the instructions given in the reference calibration routine on the FlexPendant to create reference values.

When reference calibration is performed, the robot is restored to the status given by the reference values.

Update revolution counters

Choose this routine to make a rough calibration of each manipulator axis by updating the revolution counter for each axis, using the FlexPendant.

Validation

In the mentioned routines, it is also possible to validate the calibration data.

Position of robot axes

The robot axes should be positioned close to 0 degrees before commencing the calibration program. The axis chosen for calibration is then automatically run by the calibration program to its exact calibration position during the calibration procedure.

Continues on next page

It is possible to position some of the other axes in positions different from 0 degrees. Information about which axes are allowed to be jogged is given on the FlexPendant. These axes are marked with **Unrestricted** in the FlexPendant window. Also the following table shows the dependencies between the axes.

Requirements for axis positioning during calibration

	Axis to calibrate					
Required position of axis	**Axis 1**	**Axis 2**	**Axis 3**	**Axis 4**	**Axis 5**	**Axis 6**
Axis 1	-	*	*	*	*	*
Axis 2	0	-	0	*	*	*
Axis 3	0	0	-	*	*	*
Axis 4	*	*	*	-	0[i] / *[ii]	0[i] / *[ii]
Axis 5	*	*	*	*	-	0
Axis 6	*	*	*	*	*	-

i Valid for IRB 2600.
ii Valid for IRB 2600ID.

-	Axis to be calibrated
*	Unrestricted. Axis is allowed to be jogged to other position than 0 degrees.
0	Axis must be put in position 0 degrees.

System containing SafeMove

SafeMove will lose its synchronization to the controller if a new calibration is done. New calibration values have to be downloaded to SafeMove, and a new SafeMove calibration has to be done. Make sure that the user rights admit to change the safety settings and to synchronize SafeMove.

For robots with EPS, the same applies as for SafeMove.

How to calibrate a suspended or wall mounted robot

The IRB 2600/IRB 2600 ID is fine calibrated floor standing in factory, prior to shipping.

To calibrate a suspended or wall mounted robot, reference calibration could be used. Reference values for a suspended or a wall mounted robot must be created with the robot mounted at its working position, not standing on a floor.

To calibrate a suspended or wall mounted robot with the fine calibration routine, the robot must first be taken down and mounted standing on the floor.

5.4.2 Calibration tools for Axis Calibration

Calibration tool set

The calibration tools used for Axis Calibration are designed to meet requirements for calibration performance, durability and safety in case of accidental damage.

The calibration tool will eventually break from fatigue after longer period of use and then needs to be replaced. There is no risk for bad calibrations as long as the calibration tool is in one piece.

WARNING

Calibrating the robot with Axis Calibration requires special calibration tools from ABB. Using other pins in the calibration bushings may cause severe damage to the robot and/or personnel.

Equipment, etc.	Article number	Note
Calibration tool box, Axis Calibration	3HAC074119-001	Delivered as a set of calibration tools. Required if Axis Calibration is the valid calibration method for the robot. Contains a removal tool for removing special protection plugs on the turning disc.

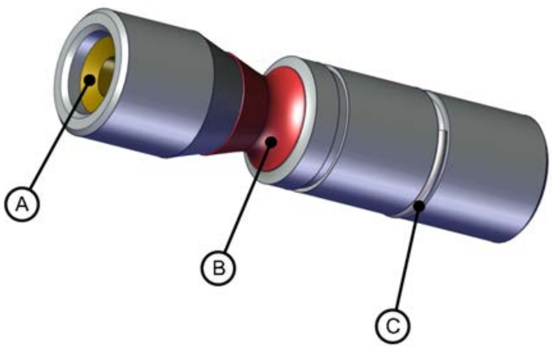
Examining the calibration tool

Check prior to usage

Before using the calibration tool, make sure that the tube insert, the plastic protection and the steel spring ring are present.

WARNING

If any part is missing or damaged, the tool must be replaced immediately.



xx1500001914

A	Tube insert
B	Plastic protection
C	Steel spring ring

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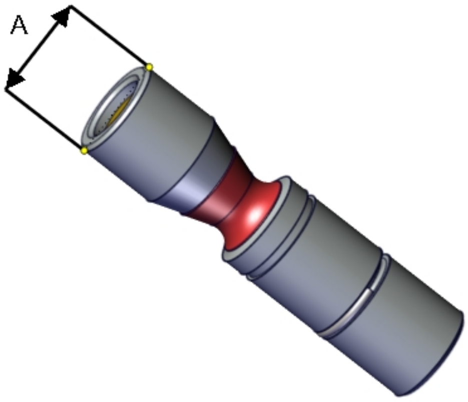
Periodic check of the calibration tool

If including the calibration tool in a local periodic check system, the following measures should be checked.

- Outer diameter within Ø12g4 mm, Ø8g4 mm or Ø6g5 mm (depending on calibration tool size).
- Straightness within 0.005 mm.



xx1500000951

A	Outer diameter

5.4.3 Installation locations for the calibration tools

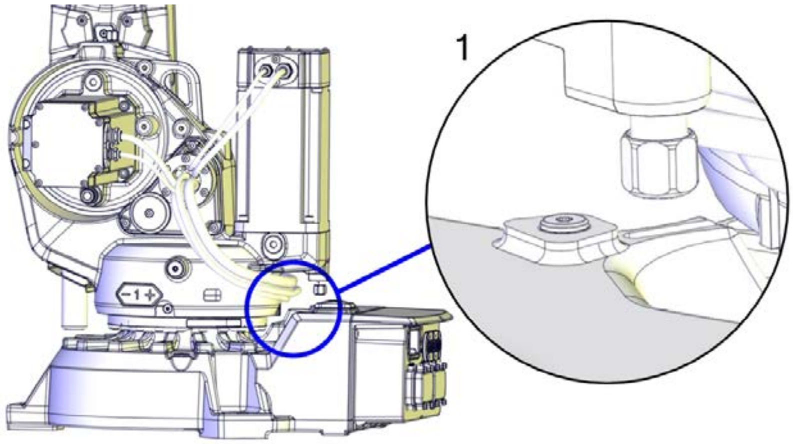
Location of fixed calibration items

This section shows how the robot is equipped with items for installation of calibration tools for Axis Calibration (fixed calibration pins and/or bushings). Installed calibration tools are not shown.

A fixed calibration pin and a bushing for the movable calibration tool are located on each axis as follows.

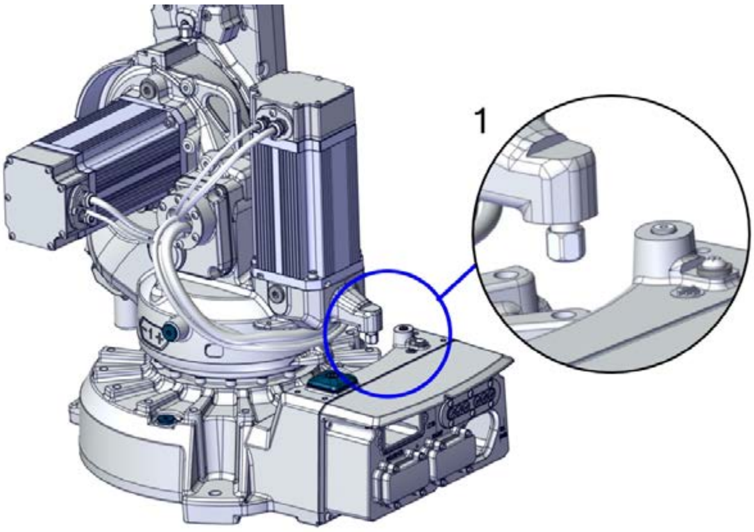
If there is not enough space on an axis to install a fixed calibration pin, the axis is equipped with two bushings instead, for installation of two calibration tools when calibration is carried out. This is shown in the figure.

IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0



xx1800000963

IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C



xx1800000964

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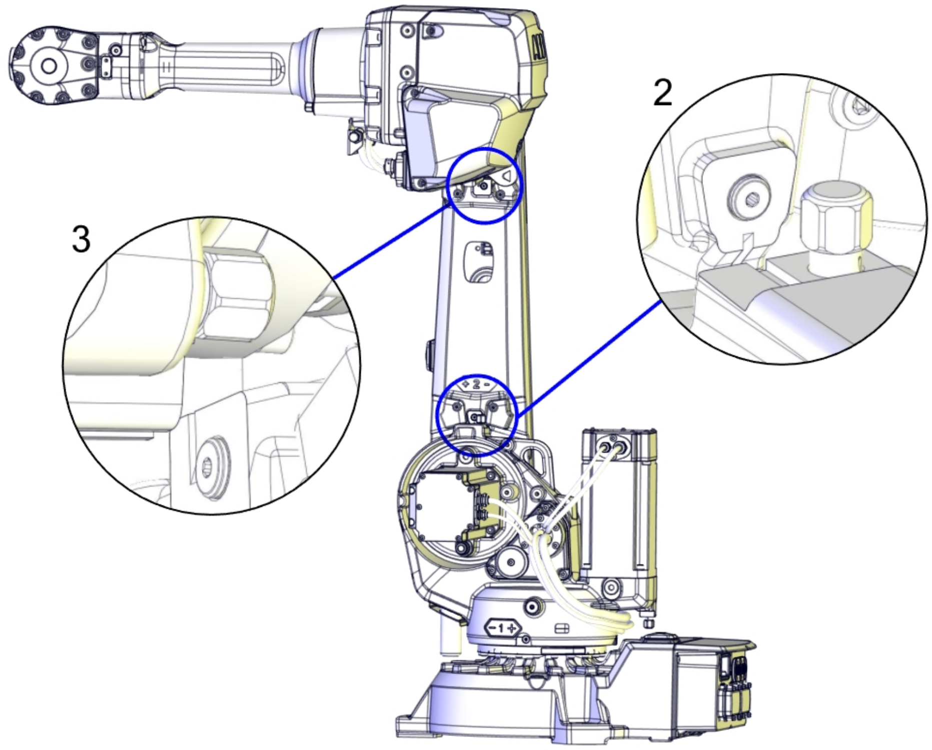
IRB 2600, IRB 2600ID



xx1600000521

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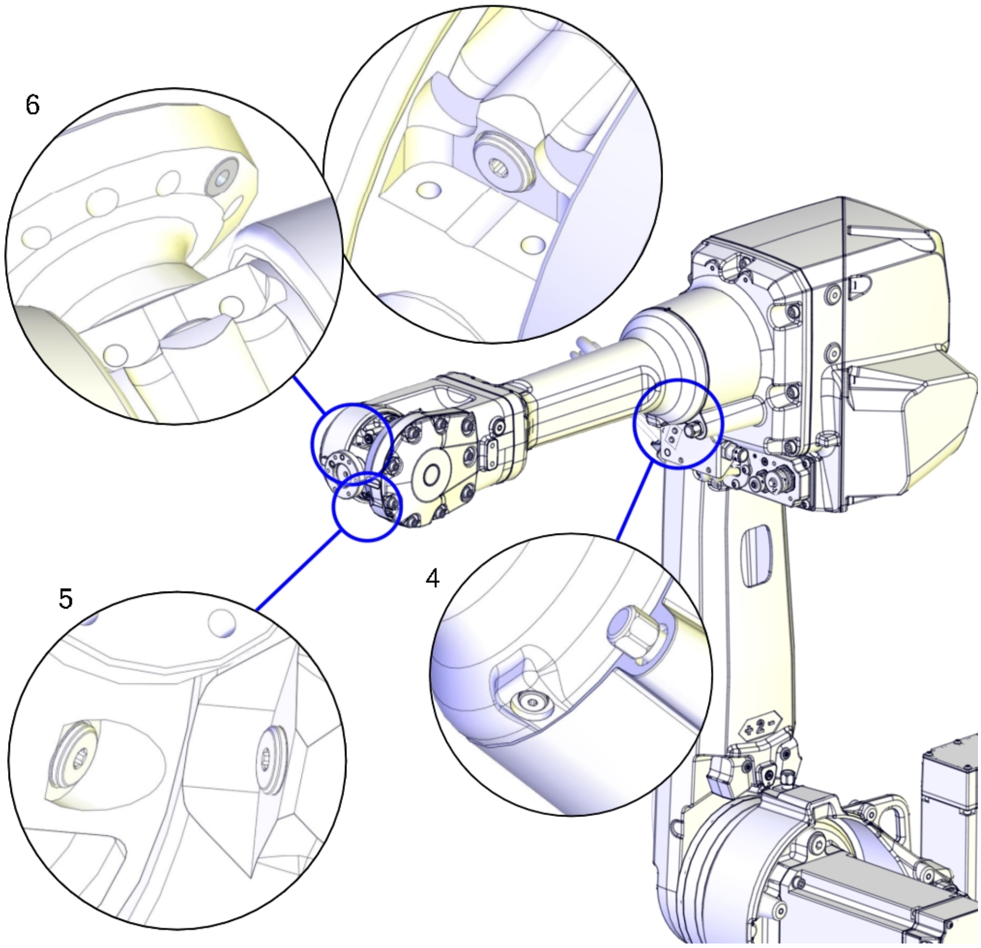
IRB 2600



xx1600000522

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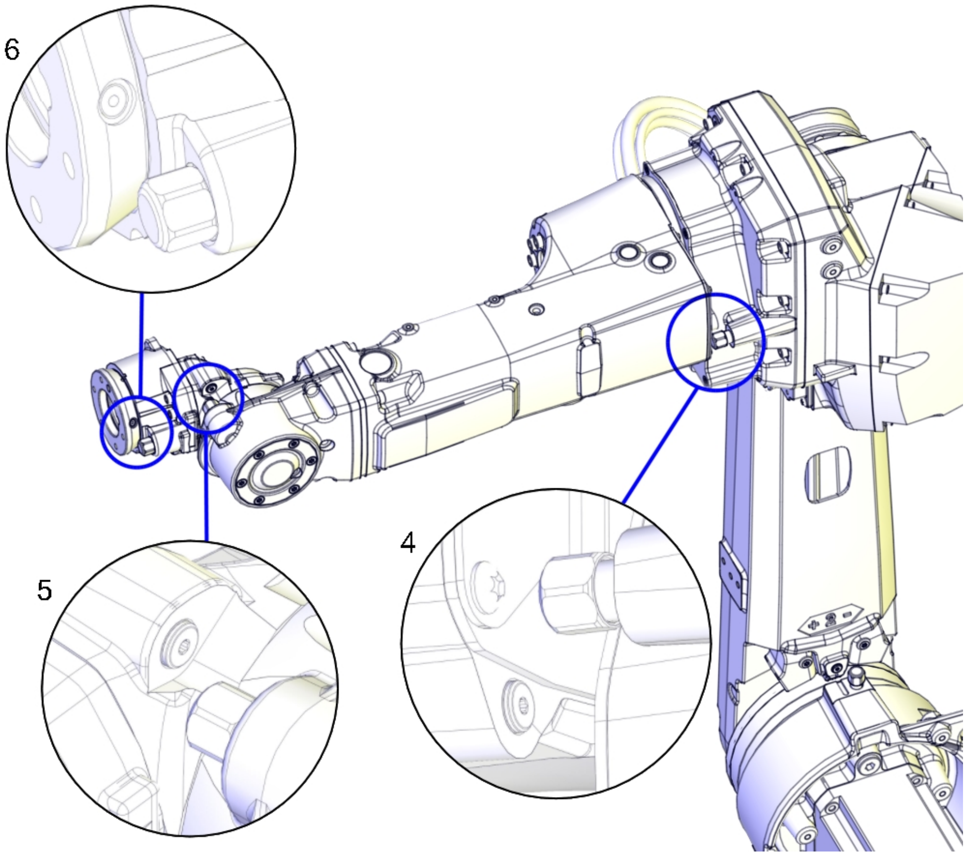
IRB 2600ID



xx1600000523

Spare parts

When calibration is not being performed, a protective cover and an o-ring should always be installed on the fixed calibration pin as well as a protective plug, included a sealing, in the bushing. Replace damaged parts with new.

Spare part	Article number	Note
Protection cover and plug set	3HAC059487-001	Contains replacement calibration pin covers and protective plugs for the bushing.
Protective plug on turning disc	3HAC057676-001 (IRB 2600ID) 3HAC057511-001 (IRB 2600)	Replace if damaged or missing.

5.4.4 Axis Calibration - Running the calibration procedure

Required tools

The calibration tools used for Axis Calibration are designed to meet requirements for calibration performance, durability and safety in case of accidental damage.

WARNING

Calibrating the robot with Axis Calibration requires special calibration tools from ABB. Using other pins in the calibration holes may cause severe damage to the robot and/or personnel.

Equipment, etc.	Article number	Note
Calibration tool box, Axis Calibration	3HAC074119-001	Delivered as a set of calibration tools. Required if Axis Calibration is the valid calibration method for the robot. Contains a removal tool for removing special protection plugs on the turning disc.

Required consumables

Consumable	Article number	Note
Clean cloth	-	

Spare parts

Spare part	Article number	Note
Protection cover and plug set	3HAC059487-001	Contains replacement calibration pin covers and protective plugs for the bushing.
Protective plug on turning disc	3HAC057676-001 (IRB 2600ID) 3HAC057511-001 (IRB 2600)	Replace if damaged or missing.

Overview of the calibration procedure on the FlexPendant

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

Use the following list to learn about the calibration procedure before running the RobotWare program on the FlexPendant. It gives you a brief overview of the calibration procedure.

After the calibration method has been started on the FlexPendant, the following sequence will be run.

1. Choose calibration routine. The routines are described in *Routines in the calibration procedure on page 415*.
2. Choose which axis/axes to calibrate.
3. The robot moves to synchronization position.

Continues on next page

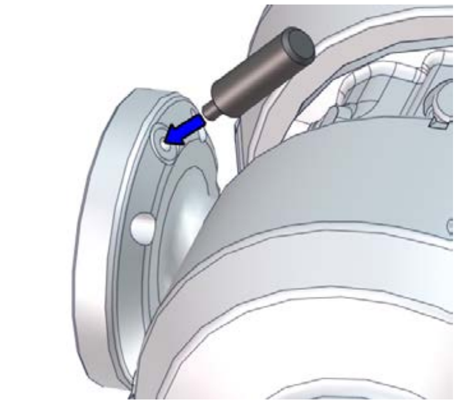
4 Validate the synchronization marks.

5 The robot moves to preparation position.

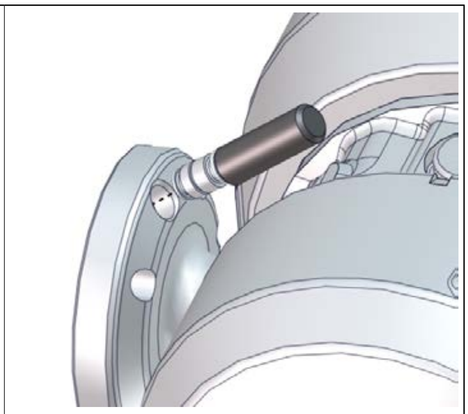
6 Remove the protective cover from the fixed pin and the protection plug from the bushing, if any, and install the calibration tool.

Use the removal tool included in the calibration tool box to remove the special protection plug(s) on the turning disc.

IRB 2600

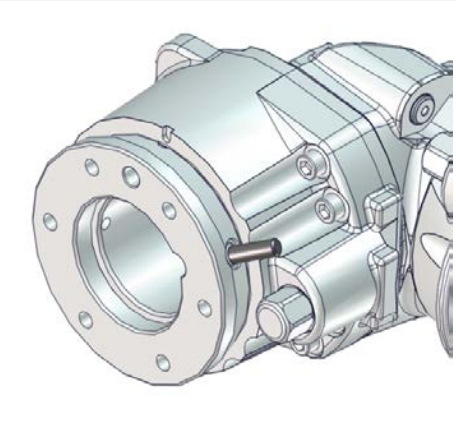


xx1700000407

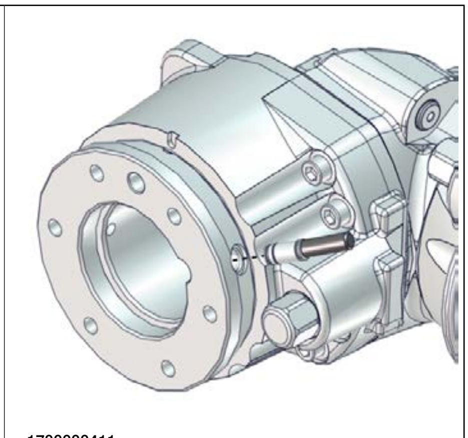


xx1700000408

IRB 2600ID



xx1700000410



xx1700000411

When calibrating axis 6, push in the calibration tool into the turning disc until the snap ring engages, no further.

7 The robot performs a measurement sequence by rotating the axis back and forth.

8 Remove the calibration tool and reinstall the protective cover on the fixed pin and the protection plug in the bushing, if any.

Refit the protection plug(s) to the turning disc, push until the steel spring ring snaps into place.

9 The robot moves to verify that the calibration tool is removed.

10 Choose whether to save the calibration data or not.

Calibration of the robot is not finished until the calibration data is saved, as last step of the calibration procedure.

Continues on next page

Preparation prior to calibration

The calibration procedure is described in the FlexPendant while conducting it.

	Action	Note
1	**DANGER** While conducting the calibration, the robot needs to be connected to power. Make sure that the robot's working area is empty, as the robot can make unpredictable movements.	
2	Wipe the calibration tool clean. **Note** The calibration method is exact. Dust, dirt or color flakes will affect the calibration value.	Use a clean cloth.
3	Check if the standard calibration data for axes 4, 5 or 6 are updated with wrist optimization. This is shown in the calibration overview/summary window on the FlexPendant.	If the data is optimized, the calibration routine **Wrist Optimization** must be re-run after standard calibration. See *Calibrating with Wrist Optimization method on page 432*.

Starting the calibration procedure

Use this procedure to start the Axis Calibration routine on the FlexPendant.

	Action	Note
1	Tap the calibration icon and enter the calibration main page.	
2	All mechanical units connected to the system are shown with their calibration status. Tap the mechanical unit in question. **Note** For RobotWare 7, the mechanical unit page is displayed only if there is more than one mechanical unit available.	
3	The calibration method used at ABB factory for each axis is shown, as well as calibration method used for the robot during last field calibration.	The FlexPendant will give all information needed to proceed with Axis Calibration.
4	**Valid for RobotWare 6** Tap **Call Calibration Method**. The software will automatically call for the procedure for the valid calibration method. If not, tap **Call Routine** and then tap **Axis calibration**.	
5	**Valid for RobotWare 7** Tap **Calibration Methods** on the right pane and then tap **Calibration**. The software will automatically call for the procedure for the valid calibration method.	

Continues on next page

	Action	Note
6	Follow the instructions given on the FlexPendant.	A brief overview of the sequence that will be run on the FlexPendant is given in *Overview of the calibration procedure on the FlexPendant on page 423*.

Restarting an interrupted calibration procedure

If the Axis Calibration procedure is interrupted before the calibration is finished, the RobotWare program needs to be started again. Use this procedure to take required action.

Situation	Action
The three-position enabling device on the FlexPendant has been released during robot movement.	Press and hold the three-position enabling device and press **Play**.
The RobotWare program is terminated with **PP to Main**.	Remove the calibration tool, if it is installed, and restart the calibration procedure from the beginning. See *Starting the calibration procedure*. If the calibration tool is in contact the robot axis needs to be jogged in order to release the calibration tool. Jogging the axis in wrong direction will cause the calibration tool to break. Directions of axis movement is shown in *Calibration movement directions for all axes on page 407*

Axis Calibration with SafeMove option

To be able to run Axis Calibration, SafeMove needs to be unsynchronized. The Axis Calibration routine recognizes if the robot is equipped with SafeMove and will force SafeMove to unsynchronize automatically.

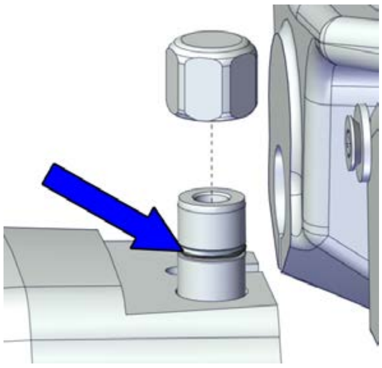
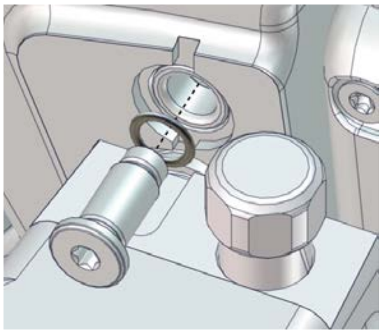
However, SafeMove may generate other warning messages anytime during the Axis Calibration routine. When a warning message is displayed, tap **Acknowledge** to confirm the unsynchronized state and continue Axis Calibration procedure.

CAUTION

SafeMove must be synchronized after the calibration is completed.

Continues on next page

After calibration

	Action	Note
1	Check the o-ring on the fixed calibration pin. Replace if damaged or missing.	 xx1600002102 Protection cover and plug set: 3HAC059487-001.
2	Reinstall the protective cover on the fixed calibration pin on each axis, directly after the axis has been calibrated. Replace the cover with new spare part, if missing or damaged.	
3	Reinstall the protective plug and sealing in the bushing on each axis, directly after the axis has been calibrated. Ensure that the sealing is not damaged. Replace the plug and the sealing with new spare part, if missing or damaged.	 xx1500000952 Protection cover and plug set: 3HAC059487-001.

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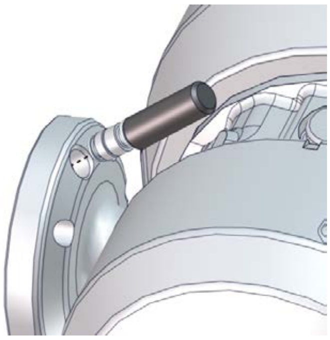
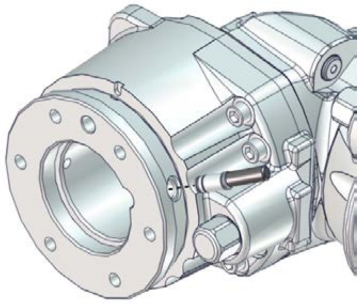
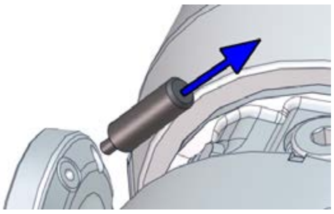
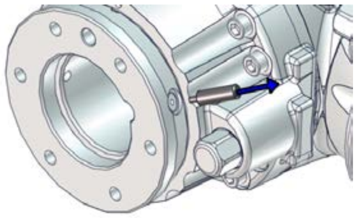
	Action	Note
4	Refit the special protection plug to the turning disc using the tool included in the calibration tool box.	IRB 2600  xx1700000408 IRB 2600ID  xx1700000411
5	Remove the tool from the protection plug.	IRB 2600  xx1700000901 IRB 2600ID  xx1700000902
6	If the standard calibration data for axes 4, 5 or 6 should be updated with wrist optimization, run the calibration routine **Wrist Optimization**.	See *Calibrating with Wrist Optimization method on page 432*.

5.4.5 Reference calibration

Brief introduction to Reference Calibration

Reference calibration is a faster method compared to Fine calibration, as it refers to a previously made calibration.

1. Create a backup of the current robot system.
2. Check that the active calibration offset values corresponds to the values on the calibration label (located on the lower arm or the base).
3. Jog the manipulator so that all axes are in zero position (ex use `MoveAbsJ` instruction). Check that all axis scales are aligned with calibration marks.
4. If the scales differ from calibration marks it might depend on wrong turns of the revolution counters. Make a marker line on the corresponding axis to be able to validate the result of the calibration. If more than one motor revolutions are wrong, the calibration will fail.
5. Use a verification position. This is especially recommended if all axes were not aligned with the synchronization marks (step 3). Reuse an existing position that is suitable and accurate so it can be used to validate the repair. Use a position where a deviation in axis calibration gives a big deviation in positioning. Note! Check the position after each repair in one axis.
6. Use Reference calibration to save reference values for all axes that is to be replaced. Make sure that the values are saved in RobotStudio or FTP program. The files are located in "Active system folder name/HOME/RefCalibFiles".
7. Perform the repair.
8. Make sure that the tooling and process equipment are the same as when creating the reference. Use Reference calibration to update the system with new calibration offset value for the repaired axis.
9. Check the position against the verification position (step 5).
10. Proceed with the repair of the next axis, if necessary, and repeat (step 8-9) for every axis.
11. (For system containing SafeMove or EPS) Download new calibration values to SafeMove. Use Visual SafeMove in RobotStudio.(For system containing SafeMove) Download new calibration values to SafeMove. Use Visual SafeMove in RobotStudio.
12. (For system containing SafeMove or EPS) Synchronize SafeMove to activate SafeMove.(For system containing SafeMove) Synchronize SafeMove to activate SafeMove.
13. Perform test run.
14. Update the calibration label with new resolver values (calibration values).

Manual tuning of calibration offset

Manual tuning of calibration offset is normally not needed, but can be useful in some situations. The requirement to do manual tuning is that there is a known accurate position, that worked accurately before the repair (step 5, see *Brief introduction to Reference Calibration on page 429*).

Continues on next page

Example "Adjust axis 4":

1. Create a backup.
2. Run the manipulator to the verification position. (The manipulator position is now deviating from the verification position.)
3. Read and note current axis 4 value in degrees (example: 96.3 degrees).
4. Manually jog, only axis 4, so that the manipulator is correctly positioned to the verification position.
5. Read and note current axis 4 value in degrees (example: 94.2 degrees).
6. Move the manipulator to its calibration position.
7. Calculate the angle difference (ie 96.3-94.2=2.1 degrees).
8. Manually jog axis 4 the calculated angle difference (-2.1). NOTE! The direction +/- shall be the same direction as the direction used when axis 4 was manually jogged to coincide with the verification process. In the example -2.1 degrees.
9. Make a new manual fine calibration of axis 4 with axis in -2.1 degrees position.
10. Check again against the verification position.
11. Repeat the manual tuning if needed.
12. Create a new reference if the intention is to use the reference in the future.

5.5 Calibrating with Calibration Pendulum method

Where to find information for Calibration Pendulum

The calibration equipment for Calibration Pendulum is delivered as a complete toolkit, including the *Operating manual - Calibration Pendulum*, which describes the method and the different routines further.

5.6 Calibrating with Wrist Optimization method

When to run Wrist Optimization

Wrist Optimization routine is run to improve TCP reorientation performance.

Calibrating the robot with standard calibration method overwrites the optimized positions of axes 4, 5, 6. Re-run the **Wrist Optimization** routine after standard calibration to re-achieve the optimized positions of the wrist axes.

Overview of the calibration procedure on the FlexPendant

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

Use the following list to learn about the calibration procedure before running the RobotWare program on the FlexPendant. It gives you a brief overview of the calibration procedure sequence.

After the calibration method has been called for on the FlexPendant, the following sequence will be run.

1. Choose calibration routine Wrist Optimization.
2. Modify targets for 4-point tool frame definition, in Wrist Optimization routine.

   Tip

   Select positions with large reorientations around the TCP. For best results, make sure that axis 4 and 5 have large movements.

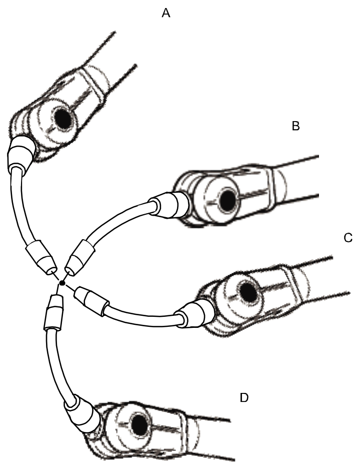
   a. Jog the robot to an appropriate position, A, for the first approach point.

      Use small increments to accurately position the tool tip as close to the reference point as possible.

   b. Tap **Modify Position** to define the point.

   c. Repeat for each approach point to be defined, positions B, C, and D.

      Jog away from the fixed world point to achieve the best result. Just changing the tool orientation will not give as good a result.



en0400000906

3. Improved calibration data to the wrist axes is identified and presented.
4. Optimized positions for the wrist axes are presented.
5. The robot moves to the optimized positions for the wrist axes and automatically overwrites previous calibration data.

Continues on next page

> **WARNING**
>
> Robot moves automatically when pressing **Calibrate**.

6 Wrist optimization is finished.

7 Redefine / verify TCP for all tools.

5.7 Verifying the calibration

Introduction

Always verify the results after calibrating *any* robot axis to verify that all calibration positions are correct.

Verifying the calibration

Use this procedure to verify the calibration result.

	Action	Note
1	Run the calibration home position program twice. Do not change the position of the robot axes after running the program!	See *Checking the synchronization position on page 435*.
2	Adjust the *synchronization marks* when the calibration is done, if necessary.	This is detailed in section *Synchronization marks and synchronization position for axes on page 404*.
3	Write down the values on a new label and stick it on top of the calibration label. The label is located on the lower arm.	

5.8 Checking the synchronization position

Introduction

Check the synchronization position of the robot before beginning any programming of the robot system. This may be done:

- Using a `MoveAbsJ` instruction with argument zero on all axes.
- Using the **Jogging** window on the FlexPendant.Using the **Jog** window on the FlexPendant.

Continues on next page

5.8.1 Checking the synchronization position on IRC5 robots

Using a `MoveAbsJ` instruction

Use this procedure to create a program that runs all the robot axes to their synchronization position.

	Action	Note
1	On ABB menu tap **Program editor**.	
2	Create a new program.	
3	Use **MoveAbsJ** in the **Motion&Proc** menu.	

4	Create the following program:
	`MoveAbsJ [[0,0,0,0,0,0],`
	`[9E9,9E9,9E9,9E9,9E9,9E9]]`
	`\NoEOffs, v1000, fine, tool0`	

5	Run the program in manual mode.	
6	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See *Synchronization marks and synchronization position for axes on page 404* and *Updating revolution counters on page 408*.

Using the jogging window

Use this procedure to jog the robot to the synchronization position of all axes.

	Action	Note
1	On the **ABB** menu, tap **Jogging**.	
2	Tap **Motion mode** to select group of axes to jog.	
3	Tap to select the axis to jog, axis 1, 2, or 3.	
4	Manually run the robots axes to a position where the axis position value read on the FlexPendant, is equal to zero.	
5	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See *Synchronization marks and synchronization position for axes on page 404* and *Updating revolution counters on page 408*.

5.8.2 Checking the synchronization position on OmniCore robots

Using a `MoveAbsJ` instruction

Use this procedure to create a program that runs all the robot axes to their synchronization position.

	Action	Note
1	Tap **Code**.	
2	Create a new program.	
3	Use **MoveAbsJ** in the **Add Instruction** menu.	

4	Create the following program:
	`MoveAbsJ [[0,0,0,0,0,0],`
	`[9E9,9E9,9E9,9E9,9E9,9E9]]`
	`\NoEOffs, v1000, fine, tool0`	

5	Run the program in manual mode.	
6	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See *Synchronization marks and synchronization position for axes on page 404* and *Updating revolution counters on page 408*.

Using the jogging window

Use this procedure to jog the robot to the synchronization position of all axes.

	Action	Note
1	Tap **Jog**.	
2	From the **Mechanical unit** list select a mechanical unit.	
3	From the **Motion mode** section, select an axis-set that need to be jogged. For example, to jog axis 2, select the axis set **Axis 1-3**.	
4	Follow the screen instruction on joystick movements to understand the direction of the axis that you want to move and move the joystick.	
5	Manually run the robots axes to a position where the axis position value read on the FlexPendant, is equal to zero.	
6	Check that the synchronization marks for the axes align correctly. If they do not, update the revolution counters.	See *Synchronization marks and synchronization position for axes on page 404* and *Updating revolution counters on page 408*.

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6 Decommissioning

6.1 Introduction to decommissioning

Introduction

This section contains information to consider when taking a product, robot or controller, out of operation.

It deals with how to handle potentially dangerous components and potentially hazardous materials.

Note

The decommissioning process shall be preceded by a risk assessment.

Disposal of materials used in the robot

All used grease/oils and dead batteries **must** be disposed of in accordance with the current legislation of the country in which the robot and the control unit are installed.

If the robot or the control unit is partially or completely disposed of, the various parts **must** be grouped together according to their nature (which is all iron together and all plastic together), and disposed of accordingly. These parts **must** also be disposed of in accordance with the current legislation of the country in which the robot and control unit are installed.

See also *Environmental information on page 440*.

Transportation

Prepare the robot or parts before transport, this to avoid hazards.

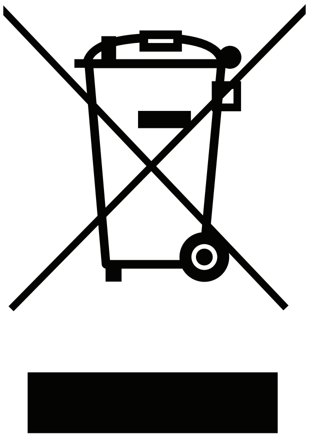
6.2 Environmental information

Introduction

ABB robots contain components in different materials. During decommissioning, all materials shall be dismantled, recycled, or reused responsibly, according to the relevant laws and industrial standards. Robots or parts that can be reused or upcycled helps to reduce the usage of natural resources.

Disposal symbol

The following symbol indicates that the product must not be disposed of as common garbage. Handle each product according to local regulations for the respective content (see table below).



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Materials used in the product

The table specifies some of the materials in the product and their respective use throughout the product.

Dispose components properly according to local regulations to prevent health or environmental hazards.

Material	Example application
Aluminium	Covers, synchronization brackets
Batteries, Lithium	Serial measurement board
Cast iron/nodular iron	Base, lower arm, upper arm
Copper	Cables, motors
Neodymium	Brakes, motors
Nickel	Turning disc (foundry)
Oil, grease	Gearboxes
Plastic/rubber	Cables, connectors, drive belts, and so on.
Steel	Gears, screws, base, frame, and so on.

Continues on next page

Oil and grease

Where possible, arrange for oil and grease to be recycled. Dispose of via an authorized person/contractor in accordance with local regulations. Do not dispose of oil and grease near lakes, ponds, ditches, down drains, or onto soil. Incineration must be carried out under controlled conditions in accordance with local regulations.

Also note that:

- Spills can form a film on water surfaces causing damage to organisms. Oxygen transfer could also be impaired.
- Spillage can penetrate the soil causing ground water contamination.

6.3 Scrapping of robot

Note

The decommissioning process shall be preceded by a risk assessment.

Important when scrapping the robot

DANGER

The risk assessment should consider hazards arising in the decommissioning, such as, but not limited to:

- Always remove all batteries. If a battery is exposed to heat, for example from a blow torch, it will explode.
- Always remove all oil/grease in gearboxes. If exposed to heat, for example from a blow torch, the oil/grease will catch fire.
- When motors are removed from the robot, the robot will collapse if it is not properly supported before the motor is removed.
- A used robot does not have the same performance as on delivery. Springs, brakes, bearings, and other parts might be worn or broken.

7 Robot description

7.1 Robot types

Robot types

There are different versions of the IRB 2600, the initial version, Type A, and Type B. The following table explains the differences.

There is also a Type C of IRB 2600, but it only affects two variants of the robot, see the table and see *Non-compatible versions of axis-1 and axis-2 gearboxes on page 444*.

	IRB 2600 (standard variants)	IRB 2600ID
Initial version	motor type A	motor type A
IRB 2600 Type A	Axis 2 changes gearbox	Axis 1-5 change to motor type B Axis 6 keeps motor type A
IRB 2600 Type B	Axis 1-6 change to motor type B	
IRB 2600 Type C - only IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C.	Axis 1 and 2 changes gearbox and motor pinion Axis 3, 4, 5 and 6 has motor type B	

7.2 Non-compatible versions of axis-1 and axis-2 gearboxes

Gearboxes from different suppliers are not compatible

There are two different versions of the axis-1 and axis-2 gearboxes for robot variants IRB 2600-20/1.65 and IRB 2600-12/1.65.

- Version 1 for IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0 (supplier Spinea).
- Version 2 for IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C (supplier Nabtesco).

The different versions affect the surrounding mechanical structure of the robot. Following parts are unique for each version of the gearbox.

- Axis-1 gearbox
- Axis-2 gearbox
- Frame
- Base
- Lower arm
- Axis-1 motor pinion
- Axis-2 motor pinion
- Cable harness

The listed parts are not interchangeable.

The gearbox oils are not interchangeable.

Designation label on lower arm

At delivery there is a designation label fitted to the lower arm of the Type C version of the robot, informing that the robot is a Type C version.

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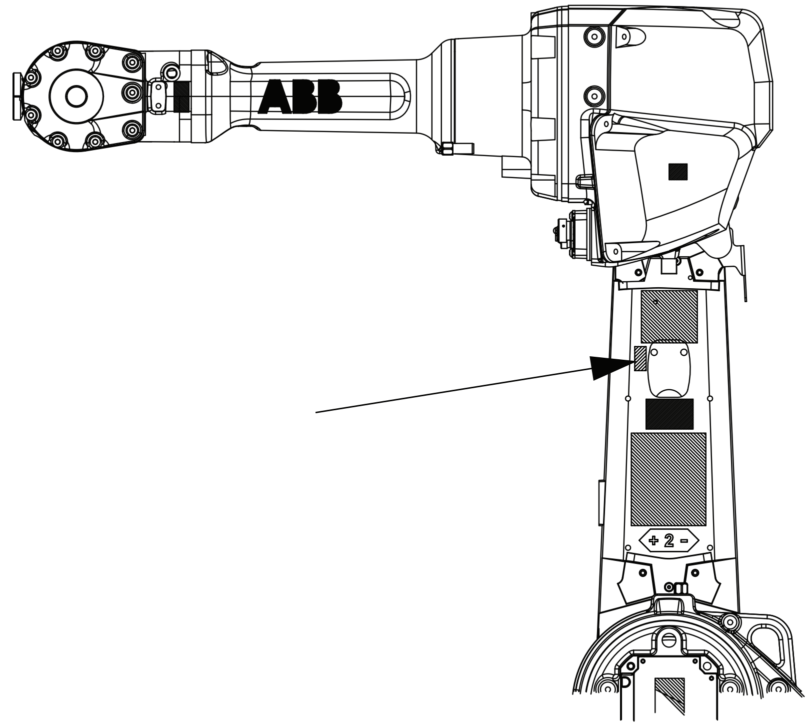

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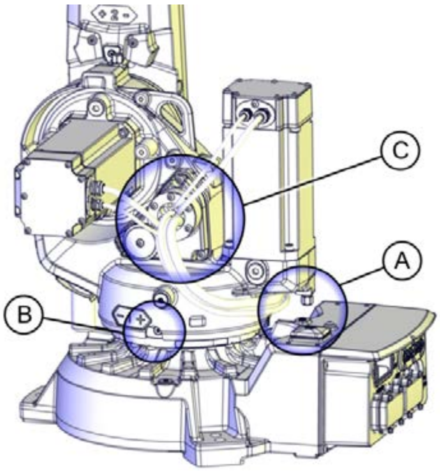
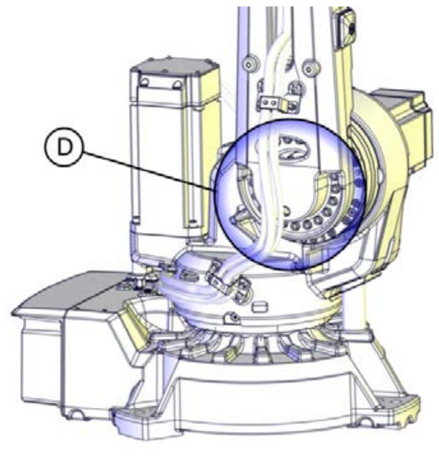
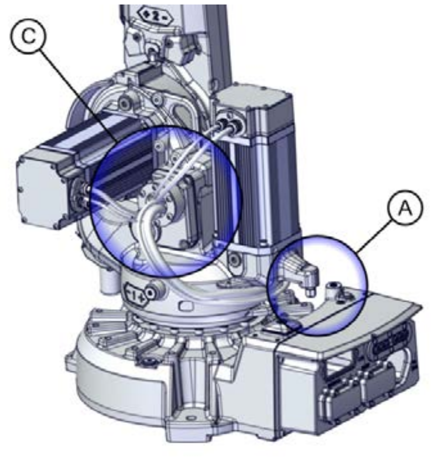
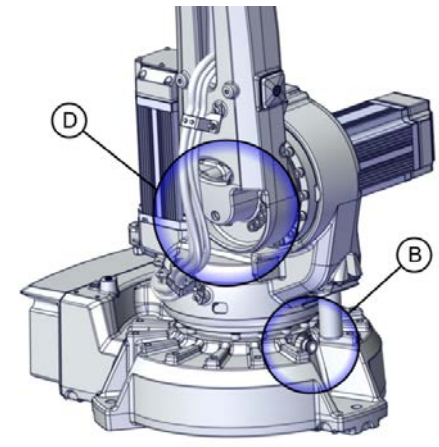
Identifying the gearbox version visually

The mechanical structure of the robot differs depending on which axis-1 and axis-2 gearbox the robot is equipped with. Some of the differences are visible, as shown in the table.

	Identification of gearbox - mechanical structure **IRB 2600-20/1.65, IRB 2600-12/1.65, IRB 2600-12/1.85, IRB 2600ID-15/1.85, IRB 2600ID-8/2.0**	**Identification of gearbox - mechanical structure** **IRB 2600-20/1.65 type C, IRB 2600-12/1.65 type C**
	 xx1800000551  xx1800000554	 xx1800001133  xx1800001134
A	The fixed calibration pin for Axis Calibration is located straight below the motor flange. The bushing for the calibration tool is centered on the base.	The fixed calibration pin for Axis Calibration is located on a casted arm on the motor flange. The bushing for the calibration tool is located to the right on the base.
B	The oil plug for drainage is located on the left side of the gearbox and visible through an opening in the frame (when robot is standing in synchronization position).	The oil plug for drainage is located in front of the gearbox (when robot is standing in synchronization position).
C	The cable cover shape is triangular.	The cable cover shape is rectangular.
D	Hole pattern for 17 screws that fasten the lower arm to the gearbox.	Hole pattern for 16 screws that fasten the lower arm to the gearbox.

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Identifying the gearbox version by article number

Only robot variants IRB 2600-20/1.65 and IRB 2600-12/1.65 are affected by different gearbox suppliers.

Use the table to identify which gearbox versions are installed on the robot, by article number. If needed, contact your local ABB for further assistance regarding the robot type.

Robot type	Article number, axis-1 gearbox	Article number, axis-2 gearbox
IRB 2600-20/1.65	3HAC028837-001	3HAC039109-001
IRB 2600 Type C-20/1.65	3HAC043130-001	3HAC043134-001
IRB 2600 - 12/1.65	3HAC028837-001	3HAC039109-001
IRB 2600 Type C-12/1.65	3HAC043130-001	3HAC043134-001

Identifying the robot type on the FlexPendant

For an IRC5 robot, the robot type is shown on the **System Info** view on the FlexPendant, in **System properties**, **Drive modules** and **Robot1**, and then tap **Options**.

For an OmniCore robot, the robot type is shown in the **System Info** view, available from the QuickSet menu **Info**.

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8 Reference information

8.1 Introduction

General

This chapter includes general information, complementing the more specific information in the different procedures in the manual.

8.2 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
UL 1740 (option) CSA Z434 (option)	Standards For Safety - Robots and Robotic Equipment Industrial robots and robot Systems - General safety requirements Valid for USA and Canada.

8.3 Unit conversion

Converter table

Use the following table to convert units used in this manual.

Quantity	Units		
Length	1 m	3.28 ft.	39.37 in
Weight	1 kg	2.21 lb.	
Weight	1 g	0.035 ounces	
Pressure	1 bar	100 kPa	14.5 psi
Force	1 N	0.225 lbf	
Moment	1 Nm	0.738 lbf-ft	
Volume	1 L	0.264 US gal	

8.4 Screw joints

General

This section describes how to tighten the various types of screw joints on ABB robots.

The instructions and torque values are valid for screw joints comprised of metallic materials and do *not* apply to soft or brittle materials.

UNBRAKO screws

UNBRAKO is a special type of screw recommended by ABB for certain screw joints. It features special surface treatment (Gleitmo as described below) and is extremely resistant to fatigue.

Whenever used, this is specified in the instructions, and in such cases, *no other type of replacement screw* is allowed. Using other types of screws will void any warranty and may potentially cause serious damage or injury.

Gleitmo treated screws

Gleitmo is a special surface treatment to reduce the friction when tightening the screw joint. It is recommended by ABB for M6-M20 screw joints. Screws treated with Gleitmo may be reused 3-4 times before the coating disappears. After this the screw must be discarded and replaced with a new one.

When handling screws treated with Gleitmo, protective gloves of **nitrile rubber** type should be used.

Generally, screws are lubricated with *Gleitmo 603* mixed with *Geomet 500* or *Geomet 702* in proportion 1:3. *Geomet* thickness varies according to screw dimensions, refer to the following.

Dimension	Lubricant	Geomet thickness
M6-M20 (any length except M20x60)	*Gleitmo 603* + *Geomet 500*	3-5 µm
M6-M20 (any length except M20x60)	*Gleitmo 603* + *Geomet 720*	3-5 µm
M20x60	*Gleitmo 603* + *Geomet 500*	8-12 µm
M20x60	*Gleitmo 603* + *Geomet 720*	6-10 µm

Screws lubricated in other ways

Screws lubricated with Molykote 1000 or Molykote P1900 should *only* be used when specified in the repair, maintenance or installation procedure descriptions.

In such cases, proceed as follows:

1. Apply lubricant to the screw thread.
2. Apply lubricant between the plain washer and screw head.
3. Screw dimensions of M8 or larger must be tightened with a torque wrench. Screw dimensions of M6 or smaller may be tightened without a torque wrench *if* this is done by trained and qualified personnel.

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Lubricant	Article number
Molykote 1000 (molybdenum disulphide grease)	3HAC042472-001
Molykote P1900 (molybdenum disulphide grease)	3HAC070875-001

Tightening torque

Before tightening any screw, note the following:

- Determine whether a **standard** tightening torque or **special** torque is to be applied. The **standard torques** are specified in the following tables. Any **special torques** are specified in the repair, maintenance or installation procedure descriptions. **Any special torque specified overrides the standard torque!**
- Use the *correct tightening torque* for each type of screw joint.
- Only use *correctly calibrated* torque keys.
- Always *tighten the joint by hand,* and never use pneumatic tools.
- Use the *correct tightening technique*, that is *do not* jerk. Tighten the screw in a slow, flowing motion.
- Maximum allowed total deviation from the specified value is **10%**!

Tightening torque for oil-lubricated screws with slotted or cross-recess head screws

The following table specifies the recommended standard tightening torque for *oil-lubricated screws* with *slotted or cross-recess head screws.*

Note

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Tightening torque for oil-lubricated screws with allen head screws

The following table specifies the recommended standard tightening torque for *oil-lubricated screws* with *allen head screws.*

Note

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Dimension	Tightening torque (Nm) Class 8.8, oil-lubricated	Tightening torque (Nm) Class 10.9, oil-lubricated	Tightening torque (Nm) Class 12.9, oil-lubricated
M5	6	-	-
M6	10	-	-
M8	24	34	40
M10	47	67	80
M12	82	115	140
M16	200	290	340
M20	400	560	670

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Dimension	Tightening torque (Nm) Class 8.8, oil-lubricated	Tightening torque (Nm) Class 10.9, oil-lubricated	Tightening torque (Nm) Class 12.9, oil-lubricated
M24	680	960	1150

Tightening torque for lubricated screws (Molykote, Gleitmo or equivalent) with allen head screws

The following table specifies the recommended standard tightening torque for *screws lubricated with Molycote 1000, Gleitmo 603 or equivalent* with *allen head screws.*

Note

A special torque specified in the repair, maintenance or installation procedure overrides the standard torque.

Dimension	Tightening torque (Nm) Class 10.9, lubricated [i]	Tightening torque (Nm) Class 12.9, lubricated [i]
M5		8
M6		14
M8	28	35
M10	55	70
M12	96	120
M16	235	300
M20	460	550
M24	790	950

i Lubricated with Molycote 1000, Gleitmo 603 or equivalent

8.5 Weight specifications

Definition

In installation, repair, and maintenance procedures, weights of the components handled are sometimes specified. All components exceeding 22 kg (50 lbs) are highlighted in this way.

To avoid injury, ABB recommends the use of a lifting accessory when handling components with a weight exceeding 22 kg. A wide range of lifting accessories and devices are available for each manipulator model.

Example

Following is an example of a weight specification in a procedure:

	Action	Note
	CAUTION The arm weighs 25 kg. All lifting accessories used must be sized accordingly.	

8.6 Standard tools

General

All service (repairs, maintenance, and installation) procedures contains lists of tools required to perform the specified activity.

All special tools required are listed directly in the procedures while all the tools that are considered standard are gathered in the standard toolkit and defined in the following table.

This way, the tools required are the sum of the standard toolkit and any tools listed in the instruction.

Contents, standard toolkit

Qty	Tool
1	Ring-open-end spanner 8-19 mm
1	Socket head cap 2.5-17 mm
1	Torx socket no: 20-60
1	Small screwdriver
1	Plastic mallet
1	Ratchet head for torque wrench 1/2"
1	Socket head cap no: 5, socket 1/2" bit L 20 mm
1	Socket head cap no: 6, socket 1/2" bit L 20 mm
1	Socket head cap no: 8, socket 1/2" bit L 20 mm
1	Small cutting plier
1	T-handle with ball head

8.7 Special tools

General

All service instructions contain lists of tools required to perform the specified activity. The required tools are a sum of standard tools, defined in the section *Standard tools on page 456*, and of special tools, listed directly in the instructions and also gathered in this section.

Measuring tools, play

The tools listed for measuring the play are used after service work on axes 5 and 6.

Description	Robot variant	Art. no.
Measuring tool, play	IRB 2600 - 20/1.65, -12/1.65, 12/1.85	3HAB6337-1
Measuring tool, play	IRB 2600ID	3HAB9238-1
Turning disk adapter	IRB 2600ID	3HAC027717-020
Measuring bracket	IRB 2600ID	3HAC032976-001
Rotation tool (Used on motor axis. M3 screw is included.)	IRB 2600, IRB 2600ID	3HAB7887-1
Tool for adjusting play in motors	IRB 2600, IRB 2600ID	See *Drawing for adjustment tool on page 360*.

Calibration equipment, Levelmeter (alternative method)

The following table specifies the calibration equipment required when calibrating the robot with the alternative method, Levelmeter Calibration.

Description	Art. no.	Note
Angle bracket	68080011-LP	
Calibration bracket	3HAC13908-9	
Calibration tool ax1	3HAC13908-4	
Measuring pin	3HAC13908-5	
Sensor fixture	68080011-GM	
Sensor plate	3HAC0392-1	
Sync. adapter	3HAC13908-1	

Calibration equipment, Calibration Pendulum

The following table specifies the calibration equipment needed when calibrating the robot with the Calibration Pendulum method.

The robot is calibrated by either Calibration Pendulum or Axis Calibration at factory. Always use the same calibration method as used at the factory.

Information about valid calibration method is found on the calibration label or in the calibration menu on the FlexPendant.

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If no data is found related to standard calibration, Calibration Pendulum is used as default.

Description	Art. no.	Note
Calibration Pendulum toolkit	3HAC15716-1	Complete kit that also includes operating manual.

Calibration equipment, Axis Calibration

The following table specifies the calibration equipment needed when calibrating the robot with the Axis Calibration method.

The robot is calibrated by either Calibration Pendulum or Axis Calibration at factory. Always use the same calibration method as used at the factory.

Information about valid calibration method is found on the calibration label or in the calibration menu on the FlexPendant.

If no data is found related to standard calibration, Calibration Pendulum is used as default.

Description	Art. no.	Note
Calibration tool box, Axis Calibration	3HAC074119-001	Delivered as a set of calibration tools. Required if Axis Calibration is the valid calibration method for the robot. Contains a removal tool for removing special protection plugs on the turning disc.

Turning tool for suspended mounting

The following table specifies the lifting tool required when fitting the robot in a suspended position.

Description	Art. no.	Note
Turning tool (includes lifting instruction)	3HAC034766-001	
Turning tool (includes lifting instruction 3HAC051688-001)	3HAC048502-001	

Special tools

This table specifies the special tools required during several of the service procedures. The tools are specified directly in concerned instructions.

Description	Qty	Article no.
Guide for reduction gear	1	3HAC068109-001 Used to guide axis-1 gear and frame during refitting.

8.8 Lifting accessories and lifting instructions

General

Many repair and maintenance activities require different pieces of lifting accessories, which are specified in each procedure.

The use of each piece of lifting accessories is *not* detailed in the activity procedure, but in the instruction delivered with each piece of lifting accessories.

The instructions delivered with the lifting accessories should be stored for later reference.

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9 Spare part lists

9.1 Spare part lists and illustrations

Location

Spare parts and exploded views are not included in the manual but delivered as a separate document for registered users on myABB Business Portal, *www.abb.com/myABB*.

Tip

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

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10 Circuit diagram

10.1 Circuit diagrams

Overview

The circuit diagrams are not included in this manual, but are available for registered users on myABB Business Portal, www.abb.com/myABB.

See the article numbers in the tables below.

Controllers

Product	Article numbers for circuit diagrams
Circuit diagram - OmniCore V250XT	*3HAC074000-008*
Circuit diagram - IRC5	*3HAC024480-011*
Circuit diagram - IRC5 Panel Mounted Controller	*3HAC026871-020*

Manipulators

Product	Article numbers for circuit diagrams
Circuit diagram - IRB 120	*3HAC031408-003*
Circuit diagram - IRB 140 type C	*3HAC6816-3*
Circuit diagram - IRB 260	*3HAC025611-001*
Circuit diagram - IRB 360	*3HAC028647-009*
Circuit diagram - IRB 390	*3HAC060545-009*
Circuit diagram - IRB 460	*3HAC036446-005*
Circuit diagram - IRB 660	*3HAC025691-001*
Circuit diagram - IRB 760	*3HAC025691-001*
Circuit diagram - IRB 1200	*3HAC046307-003*
Circuit diagram - IRB 1410	*3HAC2800-3*
Circuit diagram - IRB 1600/1660	*3HAC021351-003*
Circuit diagram - IRB 1510	*3HAC087368-003*
Circuit diagram - IRB 1520	*3HAC039498-007*
Circuit diagram - IRB 2400	*3HAC6670-3*
Circuit diagram - IRB 2600	*3HAC029570-007*
Circuit diagram - IRB 4400/4450S	*3HAC9821-1*
Circuit diagram - IRB 4600	*3HAC029038-003*
Circuit diagram - IRB 6620	*3HAC025090-001*
Circuit diagram - IRB 6620 / IRB 6620LX	*3HAC025090-001*
Circuit diagram - IRB 6640	*3HAC025744-001*
Circuit diagram - IRB 6650S	*3HAC13347-1* *3HAC025744-001*

Continues on next page

Product	Article numbers for circuit diagrams
Circuit diagram - IRB 6660	*3HAC025744-001* *3HAC029940-001*
Circuit diagram - IRB 6700 / IRB 6790	*3HAC043446-005*
Circuit diagram - IRB 7600	*3HAC13347-1* *3HAC025744-001*
Circuit diagram - IRB 14000	*3HAC050778-003*
Circuit diagram - IRB 910SC	*3HAC056159-002*

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