FANUC Robot R-1000*i*A

MECHANICAL UNIT
OPERATOR'S MANUAL

B-83004EN/11

- **Original Instructions**

Thank you very much for purchasing FANUC Robot.
Before using the Robot, be sure to read the "FANUC Robot series SAFETY HANDBOOK (B-80687EN)" and understand the content.

SAFETY PRECAUTIONS

This chapter describes the precautions which must be followed to enable the safe use of the robot. Before using the robot, be sure to read this chapter thoroughly.

For detailed functions of the robot operation, read the relevant operator's manual to understand fully its specification.

For the safety of the operator and the system, follow all safety precautions when operating a robot and its peripheral equipment installed in a work cell.
For safe use of FANUC robots, you must read and follow the instructions in the “FANUC Robot series SAFETY HANDBOOK (**B-80687EN)**”.

1 PERSONNEL

Personnel can be classified as follows.

Operator:
- Turns the robot controller power ON/OFF
- Starts the robot program from operator panel

Programmer or Teaching operator:
- Operates the robot
- Teaches the robot inside the safeguarded space

Maintenance technician:
- Operates the robot
- Teaches the robot inside the safeguarded space
- Performs maintenance (repair, adjustment, replacement)

- The operator is not allowed to work in the safeguarded space.
- The programmer or teaching operator and maintenance technician are allowed to work in the safeguarded space. Work carried out in the safeguarded space include transportation, installation, teaching, adjustment, and maintenance.
- To work inside the safeguarded space, the person must be trained on proper robot operation.

Table 1 (a) lists the work outside the safeguarded space. In this table, the symbol "O" means the work allowed to be carried out by the specified personnel.

Table 1 (a) List of work outside the Safeguarded Space

	Operator	Programmer or Teaching operator	Maintenance technician
Turn power ON/OFF to Robot controller	O	O	O
Select operating mode (AUTO/T1/T2)		O	O
Select remote/local mode		O	O
Select robot program with teach pendant		O	O
Select robot program with external device		O	O
Start robot program with operator's panel	O	O	O
Start robot program with teach pendant		O	O
Reset alarm with operator's panel		O	O
Reset alarm with teach pendant		O	O
Set data on teach pendant		O	O
Teaching with teach pendant		O	O
Emergency stop with operator's panel	O	O	O
Emergency stop with teach pendant	O	O	O
Operator's panel maintenance			O
Teach pendant maintenance			O

During robot operation, programming and maintenance, the operator, programmer, teaching operator and maintenance technician take care of their safety using at least the following safety protectors:

- Use clothes, uniform, overall adequate for the work
- Safety shoes
- Helmet

2 DEFINITION OF SAFETY NOTATIONS

To ensure the safety of users and prevent damage to the machine, this manual indicates each precaution on safety with "**WARNING**" or "**CAUTION**" according to its severity. Supplementary information is indicated by "**NOTE**". Read the contents of each **"WARNING"**, "**CAUTION**" and "**NOTE**" before using the robot.

Symbol	Definitions
⚠**WARNING**	Used if hazard resulting in the death or serious injury of the user will be expected to occur if he or she fails to follow the approved procedure.
⚠**CAUTION**	Used if a hazard resulting in the minor or moderate injury of the user, or equipment damage may be expected to occur if he or she fails to follow the approved procedure.
NOTE	Used if a supplementary explanation not related to any of WARNING and CAUTION is to be indicated.

3 PROCEDURE TO MOVE ARM WITHOUT DRIVE POWER IN EMERGENCY OR ABNORMAL SITUATIONS

(1) For emergency or abnormal situations (e.g. persons trapped in or pinched by the robot), brake release unit can be used to move the robot axes without drive power. Please order following unit and cable.

Name	Specification
Brake release unit	A05B-2450-J350 (Input voltage AC100-115V single phase) A05B-2450-J351 (Input voltage AC200-240V single phase)
Robot connection cable	A05B-2450-J360 (5m) A05B-2450-J361(10m)
Power cable	A05B-2525-J010 (5m) (AC100-115V Power plug) (*) A05B-2525-J011(10m) (AC100-115V Power plug) (*) A05B-2450-J364 (5m) (AC100-115V or AC200-240V No power plug) A05B-2450-J365(10m) (AC100-115V or AC200-240V No power plug)

(*) These do not support CE marking.

(2) Please make sure that adequate numbers of brake release units are available and readily accessible for robot system before installation.

(3) Regarding how to use brake release unit, please refer to Robot controller maintenance manual.

NOTE

Robot systems installed without adequate number of brake release units or similar means are not in compliance with EN ISO 10218-1 and the Machinery Directive and therefore cannot bear the CE Marking.

⚠ WARNING

Robot arm would fall down by releasing its brake because of gravity.
Therefore it is strongly recommended to take adequate measures such as hanging Robot arm by a crane before releasing a brake.

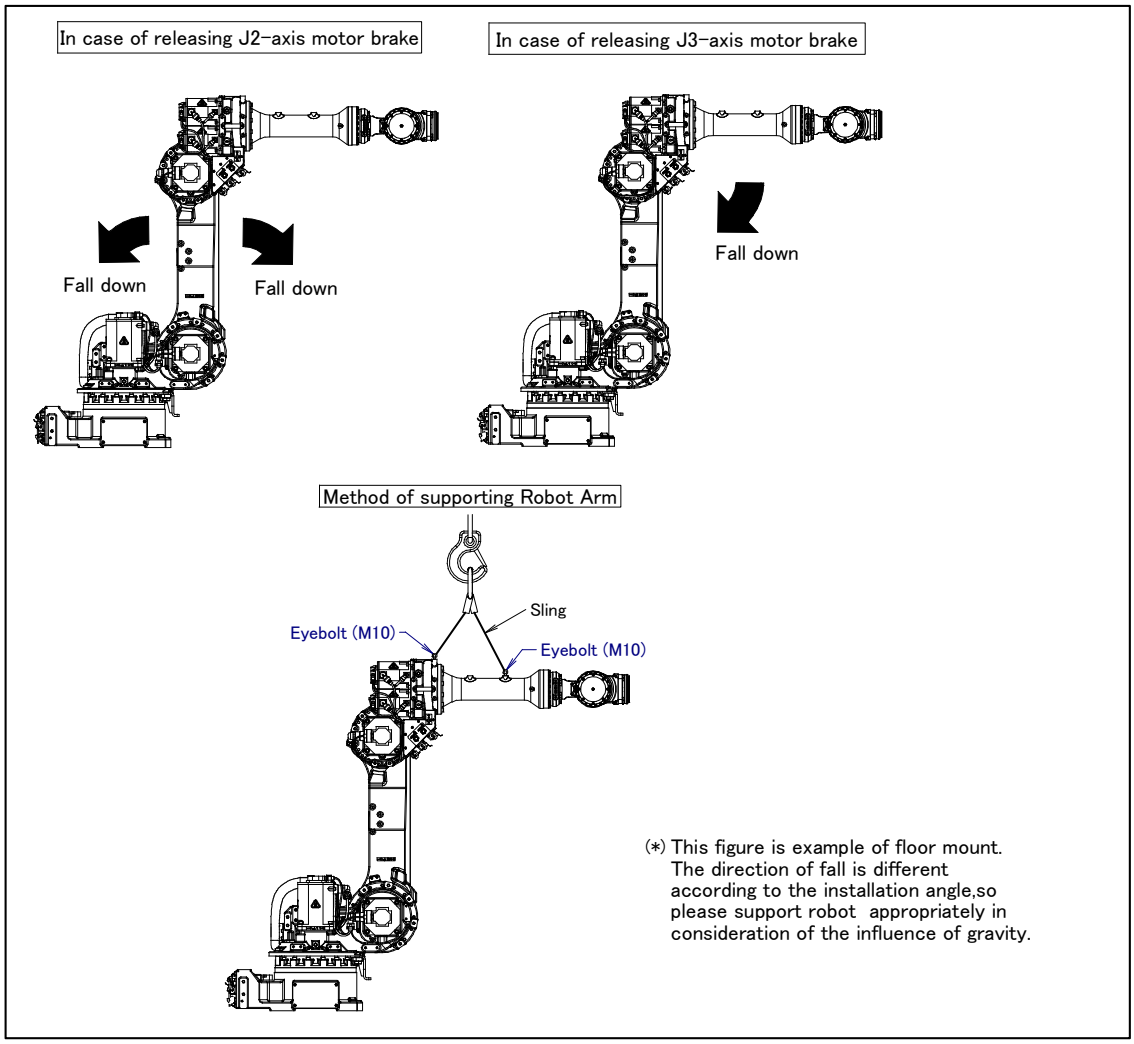


Fig. 3 (a) Arm operation by the release of J2/J3-axis motor brake and measures

4 WARNING & CAUTION LABEL

(1) Greasing and degreasing label

Fig. 4 (a) Greasing and Degreasing Label

Description

When greasing and degreasing, observe the instructions indicated on this label.

1) When greasing, be sure to keep the grease outlet open.
2) Use a manual pump to grease.
3) Be sure to use specified grease.

> ⚠ **CAUTION**
> See Chapter 7 CHECKS AND MAINTENANCE for explanations about specified grease, the grease amount, and the locations of grease inlets and outlets for individual models.

(2) Step-on prohibitive label

Fig. 4 (b) Step-on Prohibitive Label

Description

Do not step on or climb the robot or controller as it may adversely affect the robot or controller and you may get hurt if you lose your footing as well.

(3) High-temperature warning label

Fig. 4 (c) High-temperature warning label

Description

Be cautious about a section where this label is affixed, as the section generates heat. If you have to inevitably touch such a section when it is hot, use a protective tool such as heat-resistant gloves.

(4) Transportation label

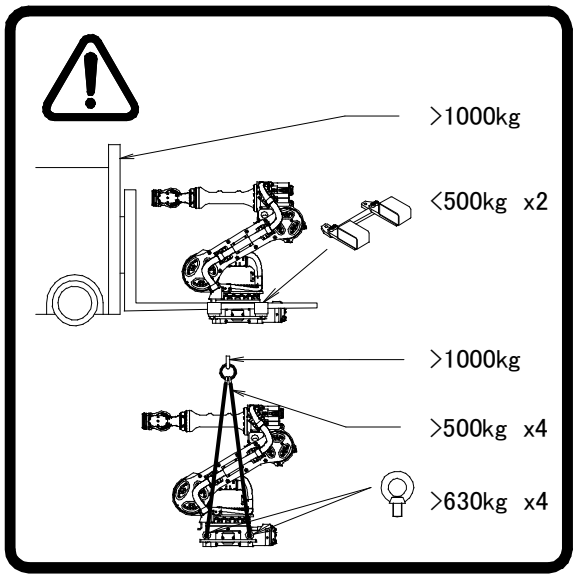


Fig. 4 (d) Transportation label

Description

When transporting the robot, observe the instructions indicated on this label. The above label indicates the following:

1) Using a forklift
- Use a forklift having a load capacity of 1000 kg or greater.
- Keep the total weight of the robot to be transported to within 9800 N (1000 kgf), because the load capacity of the forklift bracket (option) is 4900N (500kgf).

2) Using a crane
- Use a crane with a load capacity of 1000 kg or greater.
- Use four slings with each load capacity 500 kg or greater.
- In case of using eyebolts, use four eyebolts with each allowable load of 6174 N (630 kgf) or greater.
- Keep the total weight of the robot to be transported to within 9800 N (1000 kgf), because the load capacity of the forklift bracket (option) is 4900N (500kgf).

> ⚠ **CAUTION**
> See Section 1.1 TRANSPORTATION for explanations about the posture a specific model should take when it is transported.

(5) Operation space and payload label

Below label is added when CE specification is specified.

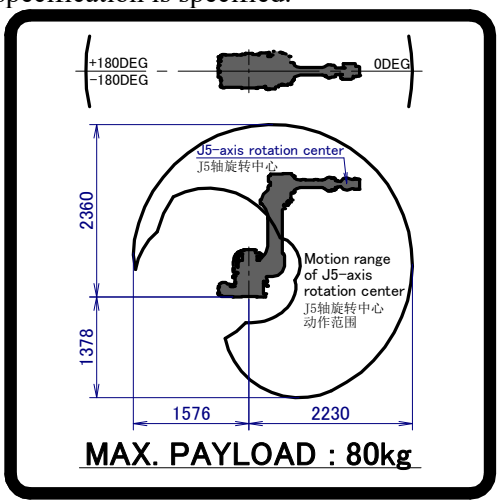


Fig. 4 (e) Operation space and payload label (example of R-1000*i*A/80F)

(6) Transportation caution label

(When transport equipment option is specified)

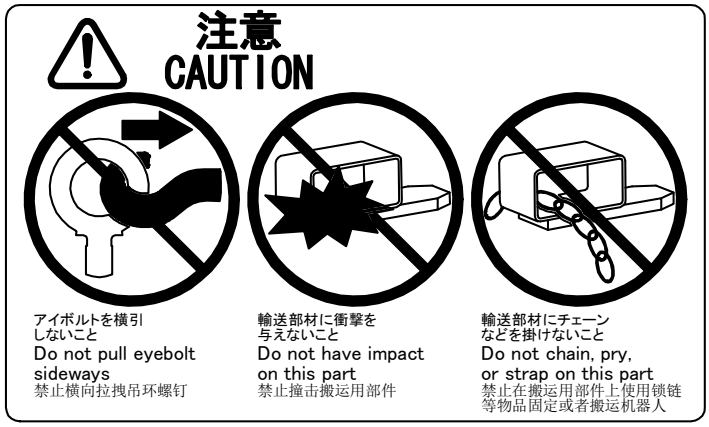


Fig. 4 (f) Transportation caution label (When transport equipment option is specified)

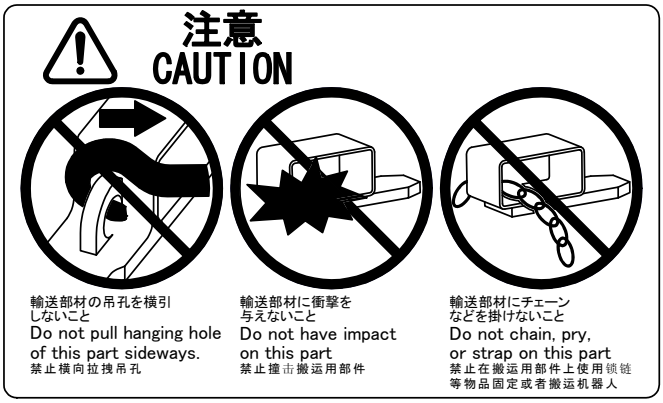


Fig. 4 (g) Transportation caution label (When transport equipment option is specified)

Description

Keep the following in mind when transporting the robot.

1) Do not pull eyebolts sideways.
2) Do not pull hanging hole of this part sideways.
3) Prevent the forks of the forklift from having impact on a transport equipment.
4) Do not thread a chain or the like through a transport equipment.

(7) Transportation caution label (For transport equipment option of R-1000*i*A/120F-7B J1 base type)

Fig. 4 (h) Transportation caution label (For transport equipment option of R-1000*i*A/120F-7B J1 base type)

Description

Remove all eyebolts before transporting with a forklift.

PREFACE

This manual explains maintenance procedures for the following mechanical units:

Model name	Mechanical unit specification No.	Maximum load
FANUC Robot R-1000*i*A/80F	A05B-1330-B201	80kg
FANUC Robot R-1000*i*A/100F	A05B-1330-B205	100kg
FANUC Robot R-1000*i*A/130F	A05B-1330-B215	130kg
FANUC Robot R-1000*i*A/120F-7B	A05B-1330-B225	120kg
	A05B-1330-B226	
FANUC Robot R-1000*i*A/80H	A05B-1330-B271	80kg

The label stating the mechanical unit specification number is affixed in the following position. Before reading this manual, verify the specification number of the mechanical unit.

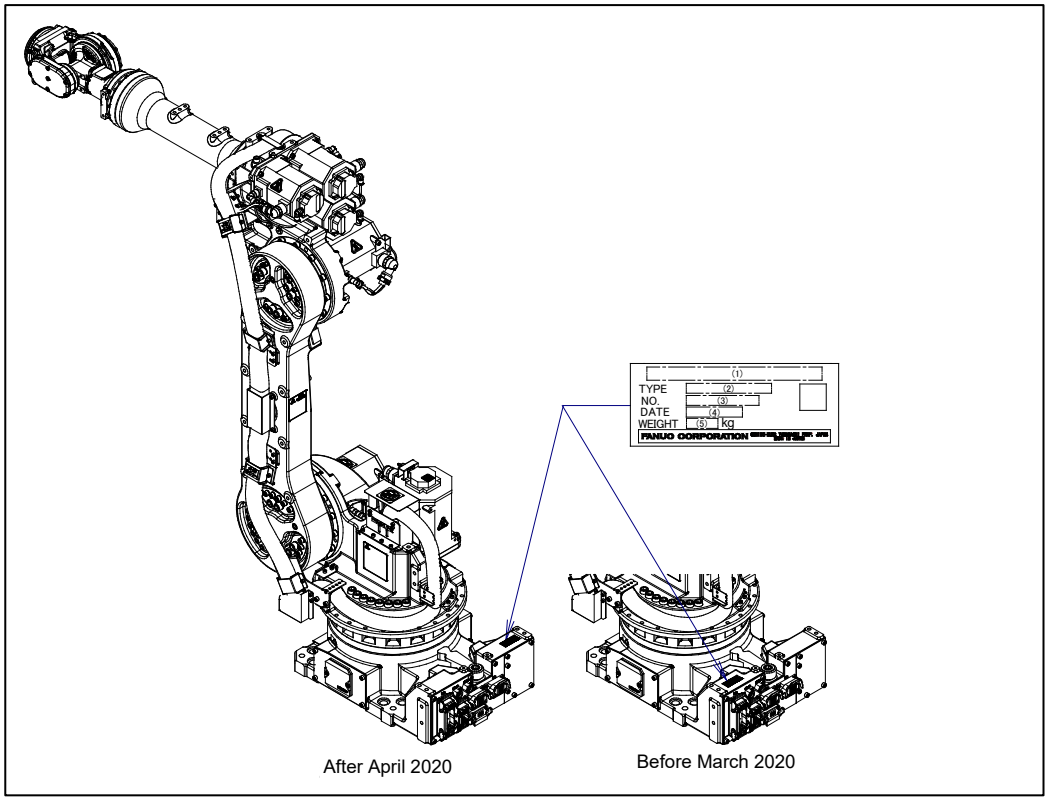


Fig. 1 (a) Position of label indicating mechanical unit specification number

TABLE 1 (a)

	(1)	(2)	(3)	(4)	(5)
CONTENTS	**MODEL NAME**	**TYPE**	**No.**	**DATE**	**WEIGHT kg (without controller)**
LETTERS	FANUC Robot R-1000*i*A/80F	A05B-1330-B201	SERIAL NO. IS PRINTED	PRODUCTION YEAR AND MONTH ARE PRINTED	620
	FANUC Robot R-1000*i*A/100F	A05B-1330-B205			665
	FANUC Robot R-1000*i*A/130F	A05B-1330-B215			675
	FANUC Robot R-1000*i*A/120F-7B	A05B-1330-B225			790
		A05B-1330-B226			
	FANUC Robot R-1000*i*A/80H	A05B-1330-B271			610

RELATED MANUALS

For the FANUC Robot series, the following manuals are available:

SAFETY HANDBOOK **B-80687EN** All persons who use the FANUC Robot and system designer must read and understand thoroughly this handbook		Intended readers: Operator, system designer Topics: Safety items for robot system design, operation, maintenance
R-30*i*A controller	Operations manual SPOT TOOL+ **B-83124EN-1** HANDLING TOOL **B-83124EN-2** DISPENSE TOOL **B-83124EN-4** ALARM CODE LIST **B-83124EN-6** Servo Gun Function **B-82634EN**	Intended readers: Operator, programmer, maintenance technician, system designer Topics: Robot functions, operations, programming, setup, interfaces, alarms Use: Robot operation, teaching, system design
	Maintenance manual **B-82595EN** **B-82595EN-1** **(For Europe)** **B-82595EN-2** **(For RIA)**	Intended readers: Maintenance technician, system designer Topics: Installation, start-up, connection, maintenance Use: Installation, start-up, connection, maintenance
R-30*i*B/ **R-30*i*B Mate/** **R-30*i*B Plus/** **R-30*i*B Mate Plus controller**	Operations manual Basic Operation **B-83284EN** Alarm Code List **B-83284EN-1** Optional Function **B-83284EN-2** Spot Welding Function **B-83284EN-4** Dispense Function **B-83284EN-5** Servo Gun Function **B-83264EN**	Intended readers: Operator, programmer, maintenance technician, system designer Topics: Robot functions, operations, programming, setup, interfaces, alarms Use: Robot operation, teaching, system design
	Maintenance manual **R-30*i*B, R-30*i*B Plus:** **B-83195EN** **R-30*i*B Mate, R-30*i*B Mae Plus:** **B-83525EN**	Intended readers: Maintenance technician, system designer Topics: Installation, start-up, connection, maintenance Use: Installation, start-up, connection, maintenance

This manual uses following terms.

Name	Terms in this manual
Connection cable between robot and controller	Robot connection cable
Robot mechanical unit	Mechanical unit

TABLE OF CONTENTS

1 TRANSPORTATION AND INSTALLATION

1.1 TRANSPORTATION

Use a crane or a forklift to transport the robot. When transporting the robot, be sure to change the posture of the robot to that shown below and lift it by using the eyebolts and the transport equipment properly. Transport equipment is common in crane and forklift.

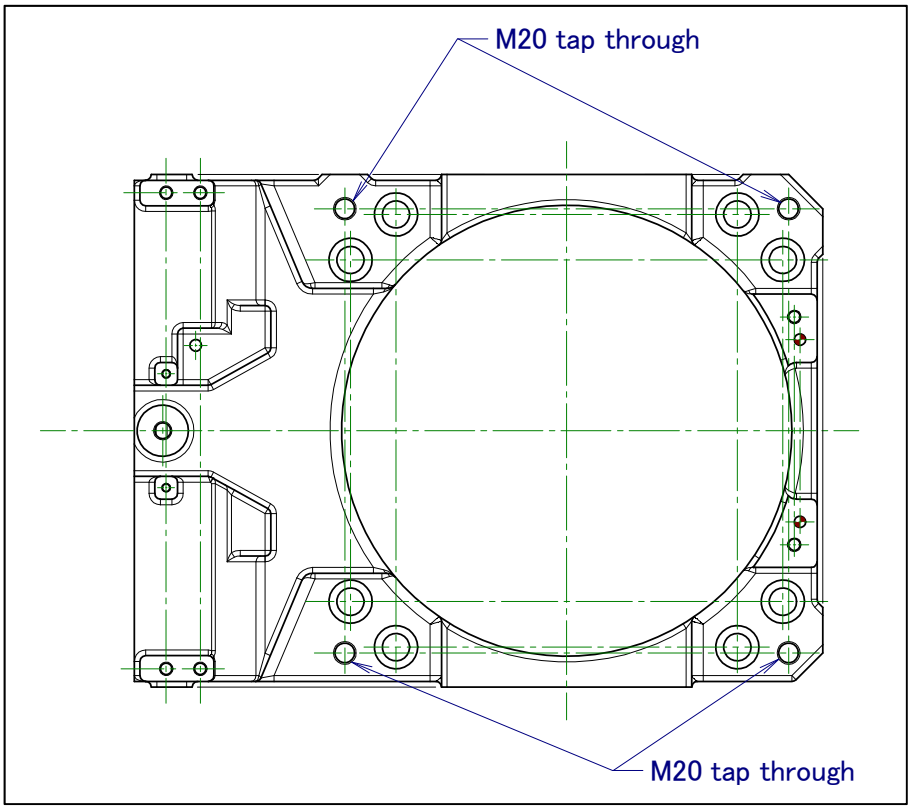


Fig. 1.1 (a) Position of the transport equipment mounting

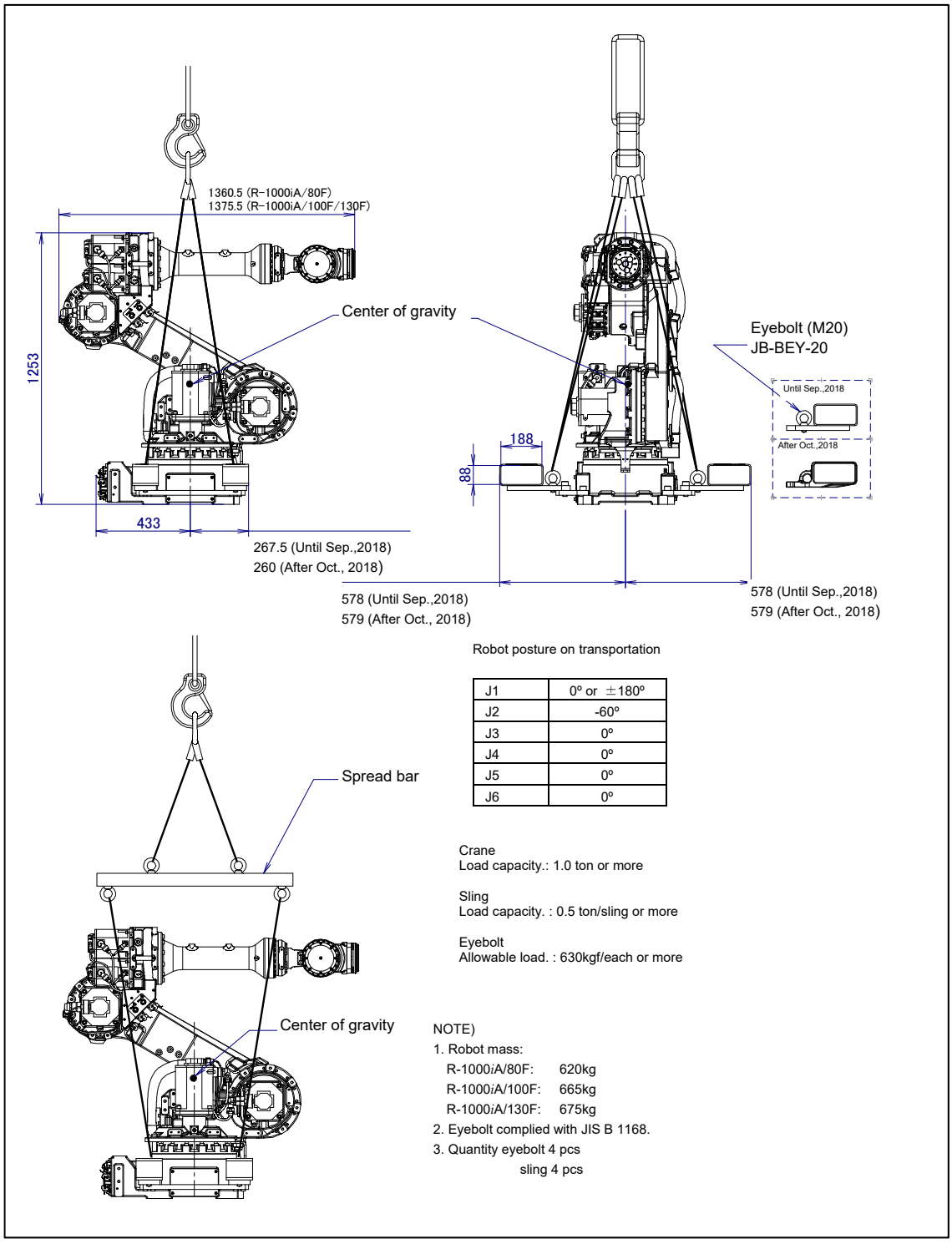
(1) Transportation using a crane (Fig. 1.1 (b) to (d))
Fasten the M20 eyebolts at the four points of special transport equipment and lift the robot by the four slings.

NOTE
When lifting the robot, notice so that the motor, connectors or cables of the robot are not damaged by slings.

(2) Transportation using a forklift (Fig. 1.1 (e) to (g))
Perform it by using special transport equipment.

⚠ WARNING
1 When hoisting or lowering the robot with a crane or forklift, move it slowly with great care. When placing the robot on the floor, exercise care to prevent the installation surface of the robot from striking the floor strongly.
2 Detach the end effectors and the floor plate before transporting the robot. If the robot need to be transported with the floor plate or end effectors attached, take the following precautions:
- The entire position of center of gravity is changed by installing the end effector and the floor plate. Please note the balance enough.
- The end effector swings by the vibration when transported, and there is a possibility that an excessive load acts on the robot. Secure the end effector firmly according to Subsection 1.1.1.
- When you lift robot with the floor plate installed, please lift up not the robot but the floor plate.

3 Use the forklift transport equipment only to transport the robot with a forklift. Do not use the forklift transport equipment to secure the robot.
Before moving the robot by using transport equipment, check the bolts on the transport equipment and tighten any loose bolts if any.
When J1/J2-axis motor covers (option) are installed, be sure to remove them before transporting robot with a crane.



Robot posture on transportation

J1	0º or ±180º
J2	-60º
J3	0º
J4	0º
J5	0º
J6	0º

Crane
Load capacity.: 1.0 ton or more

Sling
Load capacity. : 0.5 ton/sling or more

Eyebolt
Allowable load. : 630kgf/each or more

NOTE)
1. Robot mass:
R-1000*i*A/80F: 620kg
R-1000*i*A/100F: 665kg
R-1000*i*A/130F: 675kg
2. Eyebolt complied with JIS B 1168.
3. Quantity eyebolt 4 pcs
sling 4 pcs

Fig. 1.1 (b) Transportation using a crane (R-1000*i*A/80F/100F/130F)

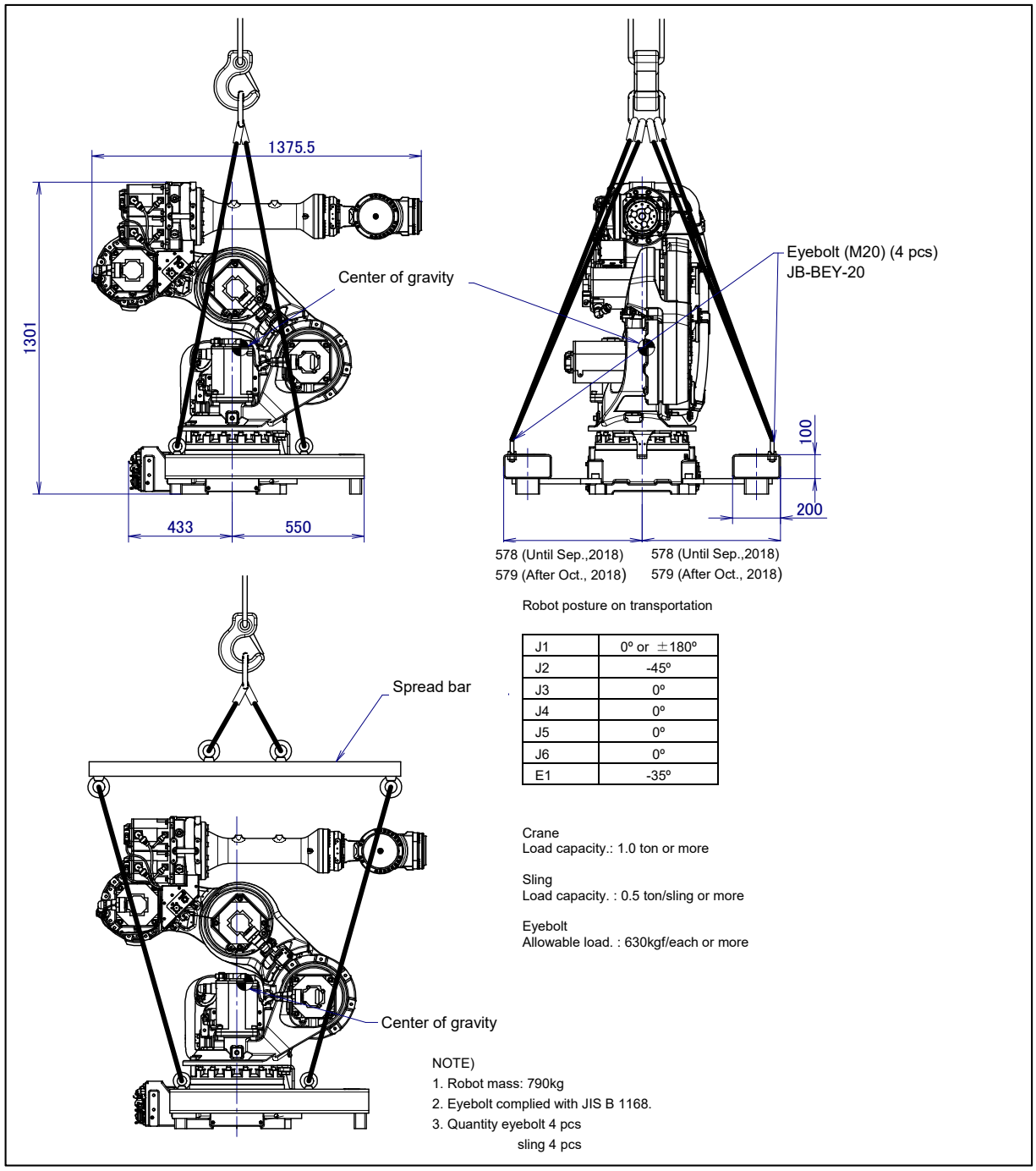
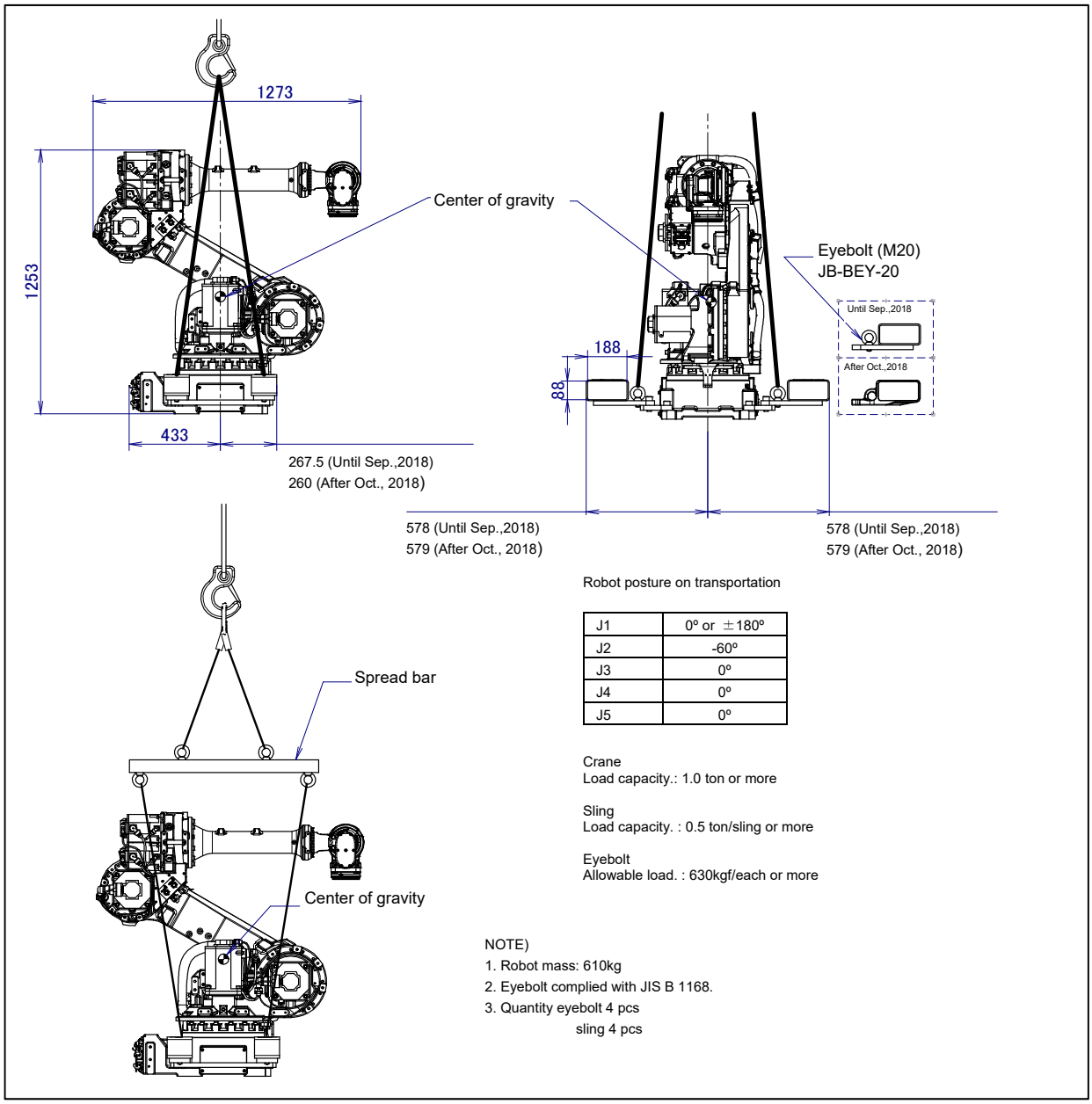


Fig. 1.1 (c) Transportation using a crane (R-1000*i*A/120F-7B)



Robot posture on transportation

J1	0º or ±180º
J2	-60º
J3	0º
J4	0º
J5	0º

Crane
Load capacity.: 1.0 ton or more

Sling
Load capacity. : 0.5 ton/sling or more

Eyebolt
Allowable load. : 630kgf/each or more

NOTE)
1. Robot mass: 610kg
2. Eyebolt complied with JIS B 1168.
3. Quantity eyebolt 4 pcs
sling 4 pcs

Fig. 1.1 (d) Transportation using a crane (R-1000*i*A/80H)

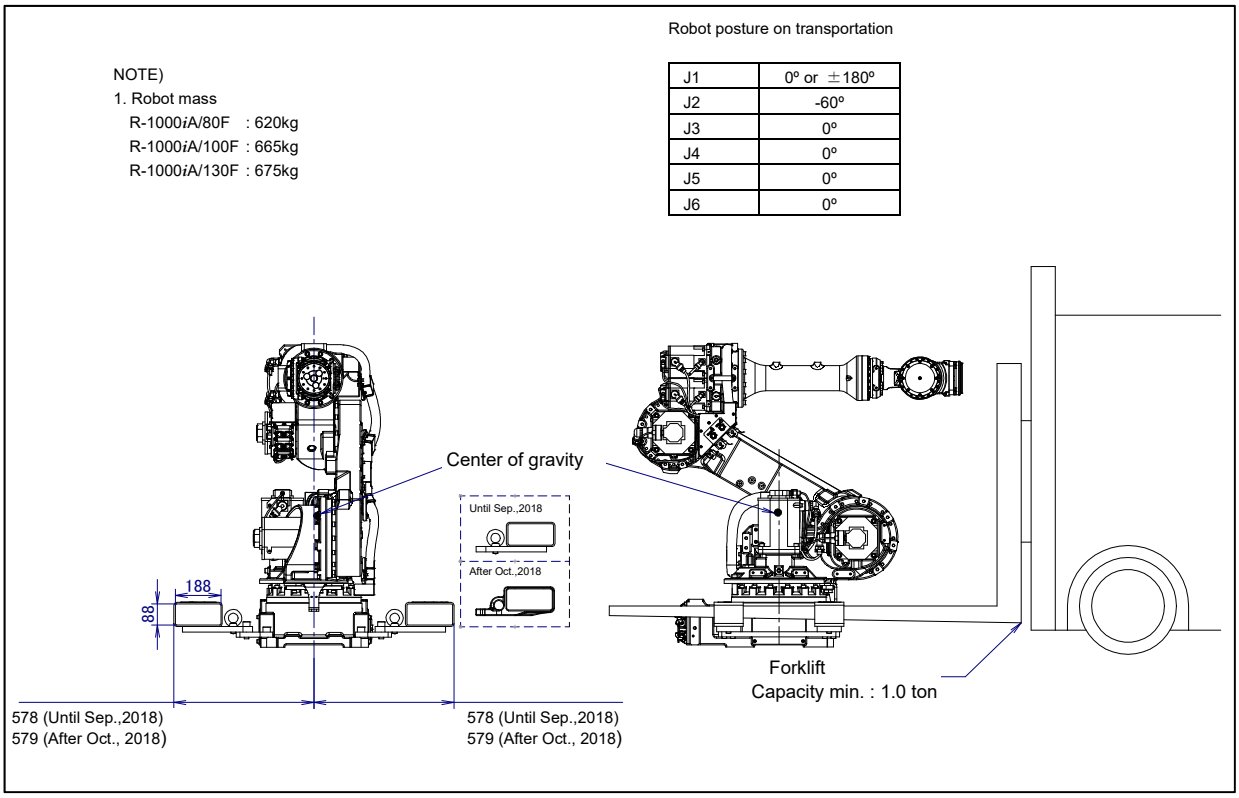


Fig. 1.1 (e) Transportation using a forklift (R-1000*i*A/80F/100F/130F)

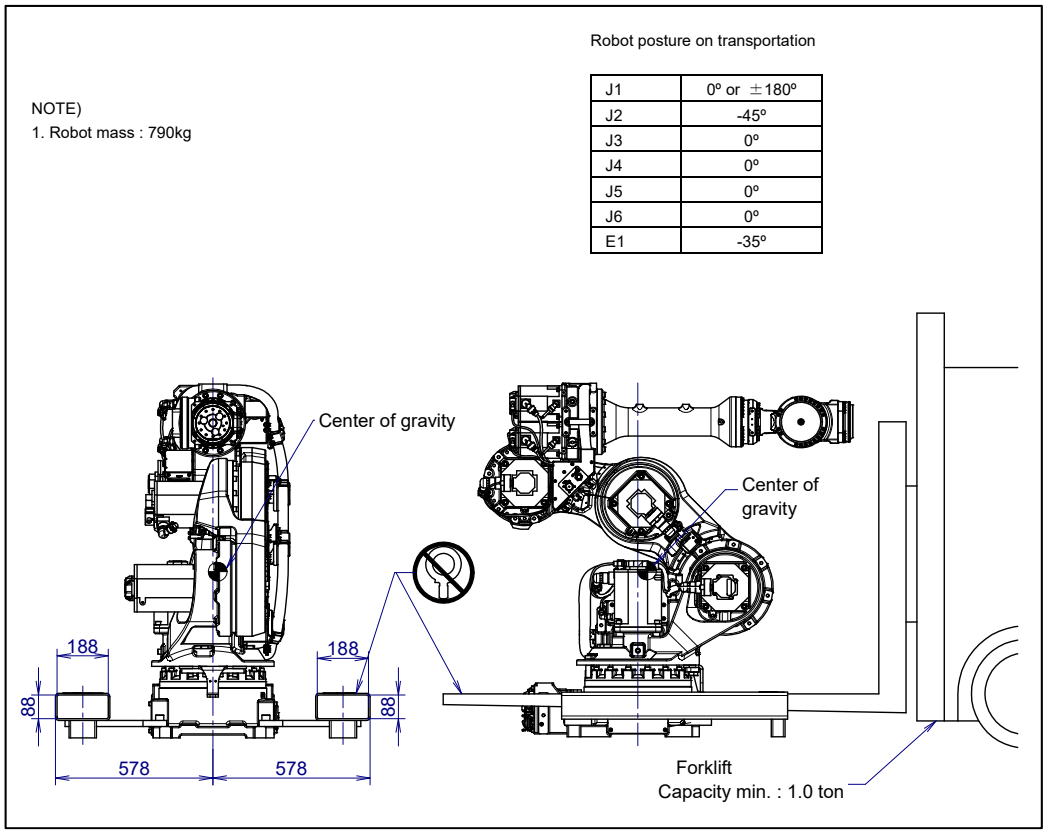


Fig. 1.1 (f) Transportation using a forklift (R-1000*i*A/120F-7B)

⚠ CAUTION
Be careful not to strike the transport equipment with the forklift forks.

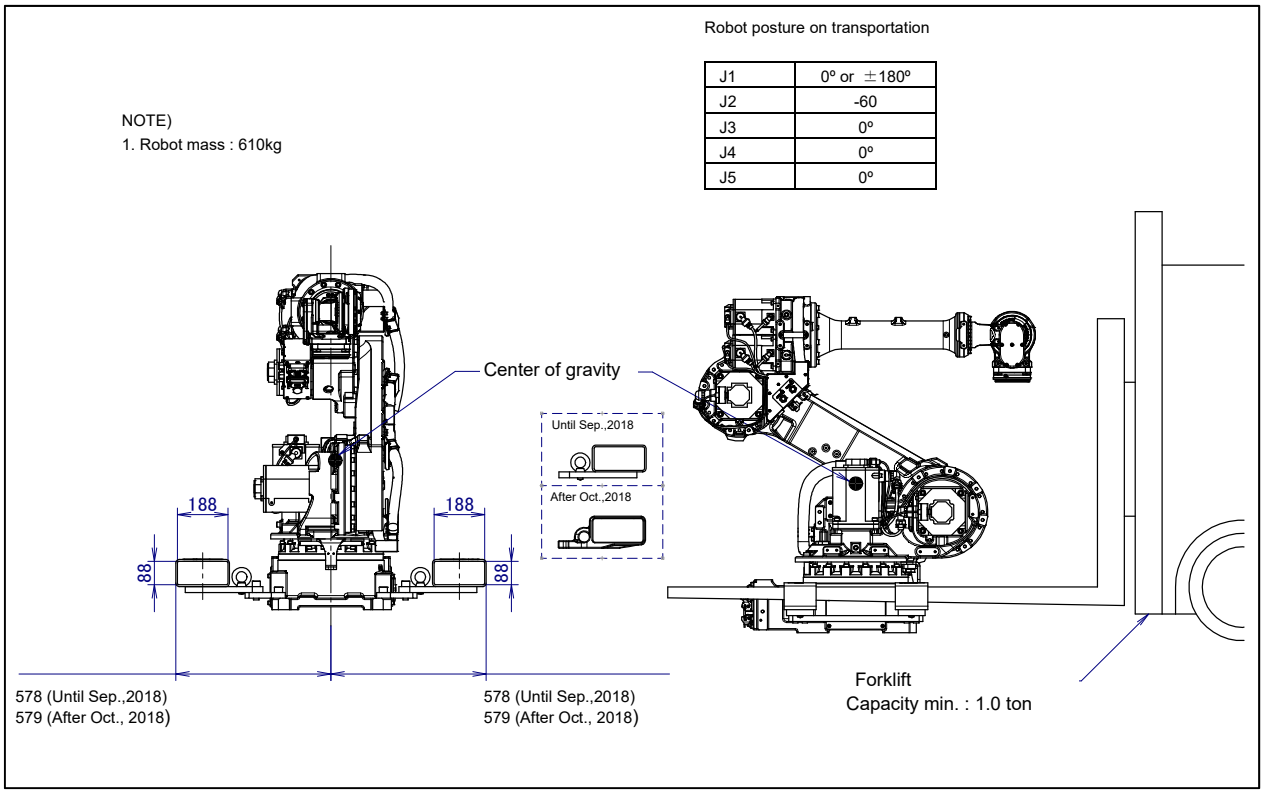


Fig.1.1 (g) Transportation using a forklift (R-1000*i*A/80H)

> **⚠ CAUTION**
> Be careful not to strike the transport equipment with the forklift forks.

1.1.1 Transportation with an End Effector Attached

When transporting a robot with an end effector such as a welding gun or hand attached, secure the arm with wood. If the arm is not secured, the end effector may oscillate for a cause such as vibration during transportation, as a result, a large impact load, imposes on the reducer of the robot, cause premature failure of the reducer.

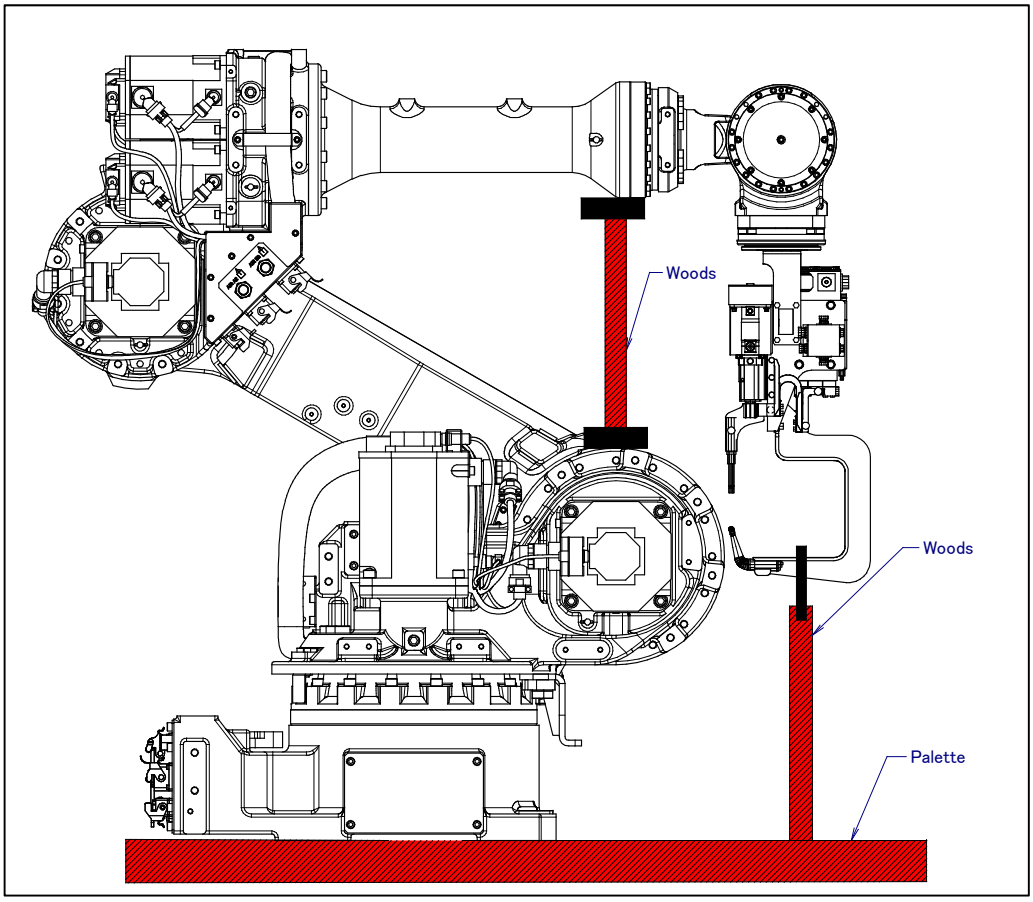


Fig. 1.1.1 (a) Example of securing the arm during transportation when an end effector is attached

1.2 INSTALLATION

Fig. 1.2 (a) shows the robot base dimensions. Avoid placing any object in front of the robot on the locating surface to facilitate the installation of the mastering fixture.

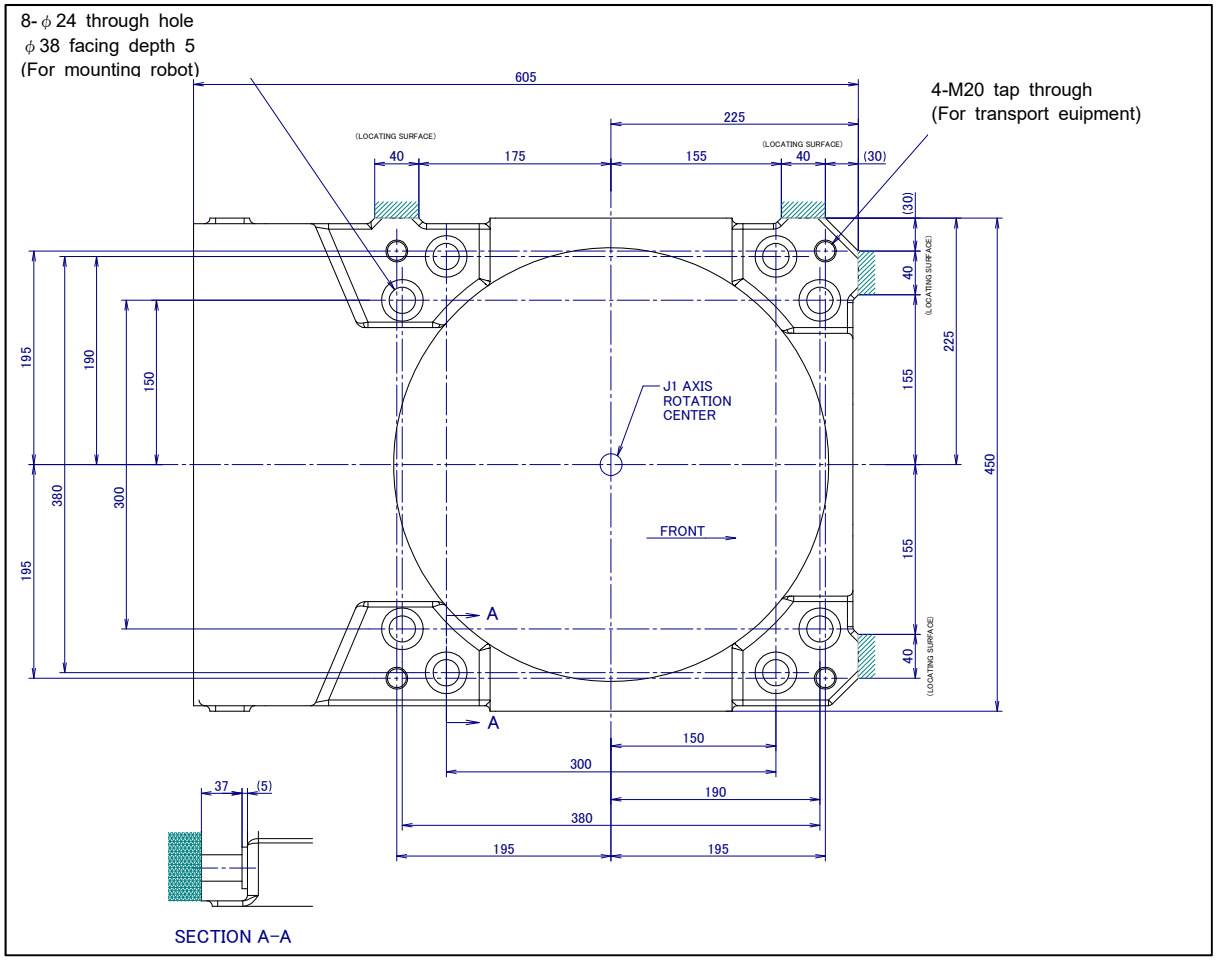


Fig. 1.2 (a) Dimension of robot base

Fig. 1.2 (b) and Table 1.2 (a) indicate the force and moment applied to the base plate at the time of Power-Off stop of the robot. Table 1.2 (b) to (d) indicate the stopping distance and time of the J1 to J3 axis until the robot stopping by Power-Off stop or by Controlled stop or by Smooth stop after input of the stop signal. Refer to the data when considering the strength of the installation face.

NOTE

Stopping times and distances in Table 1.2 (b) to (d) are reference values measured in accordance with ISO 10218-1. Please measure and check the actual values, since it varies depending on robot individual, load condition and operation program. Stopping times and distances in Table 1.2 (b) are affected by the robot's operating status and the number of Servo-Off stops. Please measure and check the actual values periodically.

Table 1.2 (a) Force and moment during Power-Off stop

Model	Vertical moment M_V [kNm (kgfm)]	Force in vertical direction F_V [kN (kgf)]	Horizontal moment M_H [kNm (kgfm)]	Force in horizontal direction F_H [kN (kgf)]
R-1000*i*A/80F	38.22 (3900)	21.56 (2200)	14.70 (1500)	21.56 (2200)
R-1000*i*A/100F	42.14 (4300)	22.54 (2300)	15.68 (1600)	20.58 (2100)
R-1000*i*A/130F	47.04 (4800)	25.48 (2600)	15.68 (1600)	22.54 (2300)
R-1000*i*A/120F-7B	49.00 (5000)	27.44 (2800)	15.68 (1600)	23.52 (2400)
R-1000*i*A/80H	36.26 (3700)	21.56 (2200)	11.76 (1200)	21.56 (2200)

Table 1.2 (b) Stopping time and distance until the robot stopping by Power-Off stop after input of stop signal

Model		J1-axis	J2-axis	J3-axis
R-1000*i*A/80F	Stopping time [ms]	366	238	174
	Stopping distance [deg] (rad)	28.4 (0.50)	15.1 (0.26)	13.8 (0.24)
R-1000*i*A/100F	Stopping time [ms]	375	260	205
	Stopping distance [deg] (rad)	26.7 (0.47)	15.0 (0.26)	13.4 (0.23)
R-1000*i*A/130F	Stopping time [ms]	381	347	195
	Stopping distance [deg] (rad)	26.2 (0.46)	17.3 (0.30)	11.3 (0.20)
R-1000*i*A/120F-7B	Stopping time [ms]	412	314	205
	Stopping distance [deg] (rad)	28.3 (0.49)	14.2 (0.25)	11.3 (0.20)
R-1000*i*A/80H	Stopping time [ms]	364	188	172
	Stopping distance [deg] (rad)	30.0 (0.52)	14.5 (0.25)	13.9 (0.24)

Table 1.2 (c) Stopping time and distance until the robot stopping by Controlled stop after input of stop signal

Model		J1-axis	J2-axis	J3-axis
R-1000*i*A/80F	Stopping time [ms]	734	766	686
	Stopping distance [deg] (rad)	64.2 (1.12)	49.6 (0.87)	60.6 (1.06)
R-1000*i*A/100F	Stopping time [ms]	780	900	780
	Stopping distance [deg] (rad)	55.7 (0.97)	48.0 (0.84)	53.1 (0.93)
R-1000*i*A/130F	Stopping time [ms]	904	900	894
	Stopping distance [deg] (rad)	62.8 (1.10)	52.0 (0.91)	56.2 (0.98)
R-1000*i*A/120F-7B	Stopping time [ms]	884	892	900
	Stopping distance [deg] (rad)	60.8 (1.06)	51.6 (0.90)	56.4 (0.98)
R-1000*i*A/80H	Stopping time [ms]	716	692	676
	Stopping distance [deg] (rad)	70.4 (1.23)	65.4 (1.14)	52.0 (0.91)

Table 1.2 (d) Stopping time and distance until the robot stopping by Smooth stop after input of stop signal

Model		J1-axis	J2-axis	J3-axis
R-1000*i*A/80F	Stopping time [ms]	682	728	484
	Stopping distance [deg] (rad)	57.4(1.00)	45.1(0.79)	36.1(0.63)
R-1000*i*A/100F	Stopping time [ms]	688	760	590
	Stopping distance [deg] (rad)	44.9(0.78)	38.8(0.68)	35.9(0.63)
R-1000*i*A/130F	Stopping time [ms]	728	726	706
	Stopping distance [deg] (rad)	48.1(0.84)	40.1(0.70)	39.9(0.70)
R-1000*i*A/120F-7B	Stopping time [ms]	756	764	762
	Stopping distance [deg] (rad)	47.9 (0.84)	40.6 (0.71)	41.5 (0.72)
R-1000*i*A/80H	Stopping time [ms]	636	668	320
	Stopping distance [deg] (rad)	58.2(1.02)	51.3(0.9)	26.1(0.46)

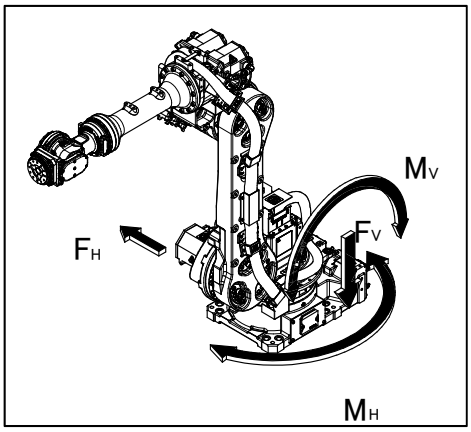


Fig. 1.2 (b) Force and moment that acts during Power-Off stop

1.2.1 Actual Installation Example

The following show three actual examples of the robot installation. Please choose either to the use environment of the customer.

The strength of the chemical anchor depends on the concrete strength. See the design guideline of the manufacturer for the execution of the chemical anchor and consider the safety ratio sufficiently before use.

- Installation example I Fig. 1.2.1 (a)
  The floor plate is imbedded in concrete and fastened with eight M20 (Tensile strength 400N/mm^2 or more) chemical anchors. Also fasten the base plate to the robot base using eight M20 x 65 bolts (Tensile strength 1200N/mm^2 or more). Next, position the robot, and weld the base plate to the floor plate. (Floor length is 10 to 15mm.) (The base plate is prepared as the option.)

- Installation example II Fig. 1.2.1 (b)
  The floor plate is not imbedded in concrete. The floor plate is fastened at the eight points with M20 chemical anchors (Tensile strength 400N/mm^2 or more) and the inclination of the floor plate is adjusted with the four fixing screws. The robot is positioned with the robot base pushed against the three ϕ20 parallel pins inserted into the base and the robot base is fastened on the floor plate with eight M20 x 65 bolts (Tensile strength 1200N/mm^2).

- Installation example III Fig. 1.2.1 (c)
  The installation method is generally the same as described above except that the parallel pins for pushing the robot base are not used.

  The following parts are required to install the robot.
  (○ : Parts needs to be prepared.)

Required parts	Remarks	Example I	Example II	Example III
Robot mounting bolts	M20 x 65 (Tensile strength 1200N/mm^2 or more) 8 pcs	○	○	○
Plain washers	For M20 (HRC 35 or more, thickness between 4 and 5 mm) 8 pcs	○	○	○
Chemical anchors	M20 (Tensile strength 400N/mm^2 or more) 8 pcs	○	○	○
Floor plate	Thickness 32t 1 pc	○	○	○
Base plates	Thickness 32t 4 pcs	○		
Fixing screws	M20 4 pcs		○	○
Nuts	M20 4 pcs		○	○
Parallel pins	φ20 3 pcs		○	

NOTE
- Customer must provide all necessary arrangements for the actual installation work (such as welding and anchoring).
- Flatness of robot installation surface must be less than or equal to 0.5mm. Inclination of robot installation surface must be less than or equal to 0.5º. If robot base is placed on uneven ground, it may result in the base breakage or low performance of the robot.

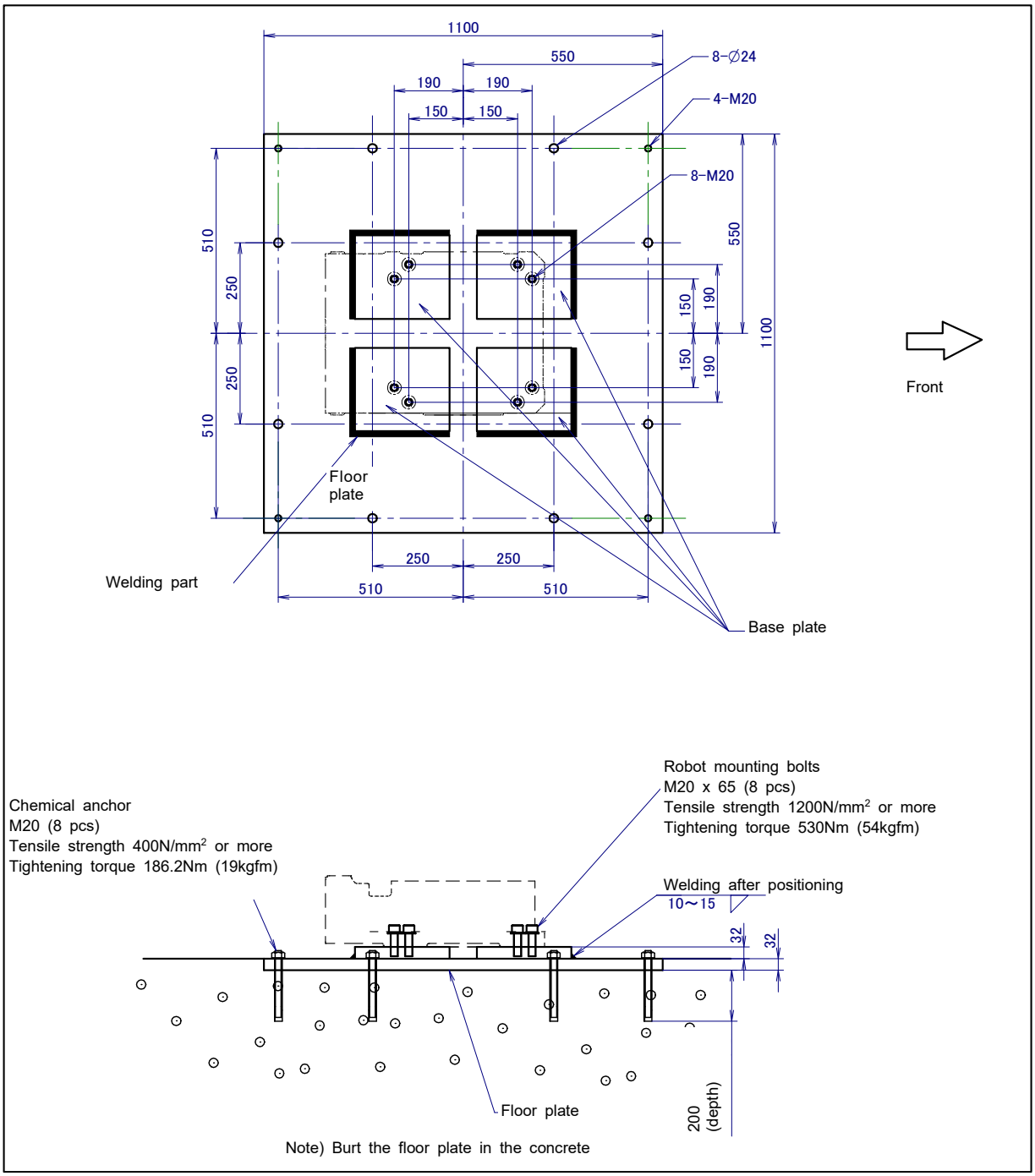


Fig. 1.2.1 (a) Actual installation example I

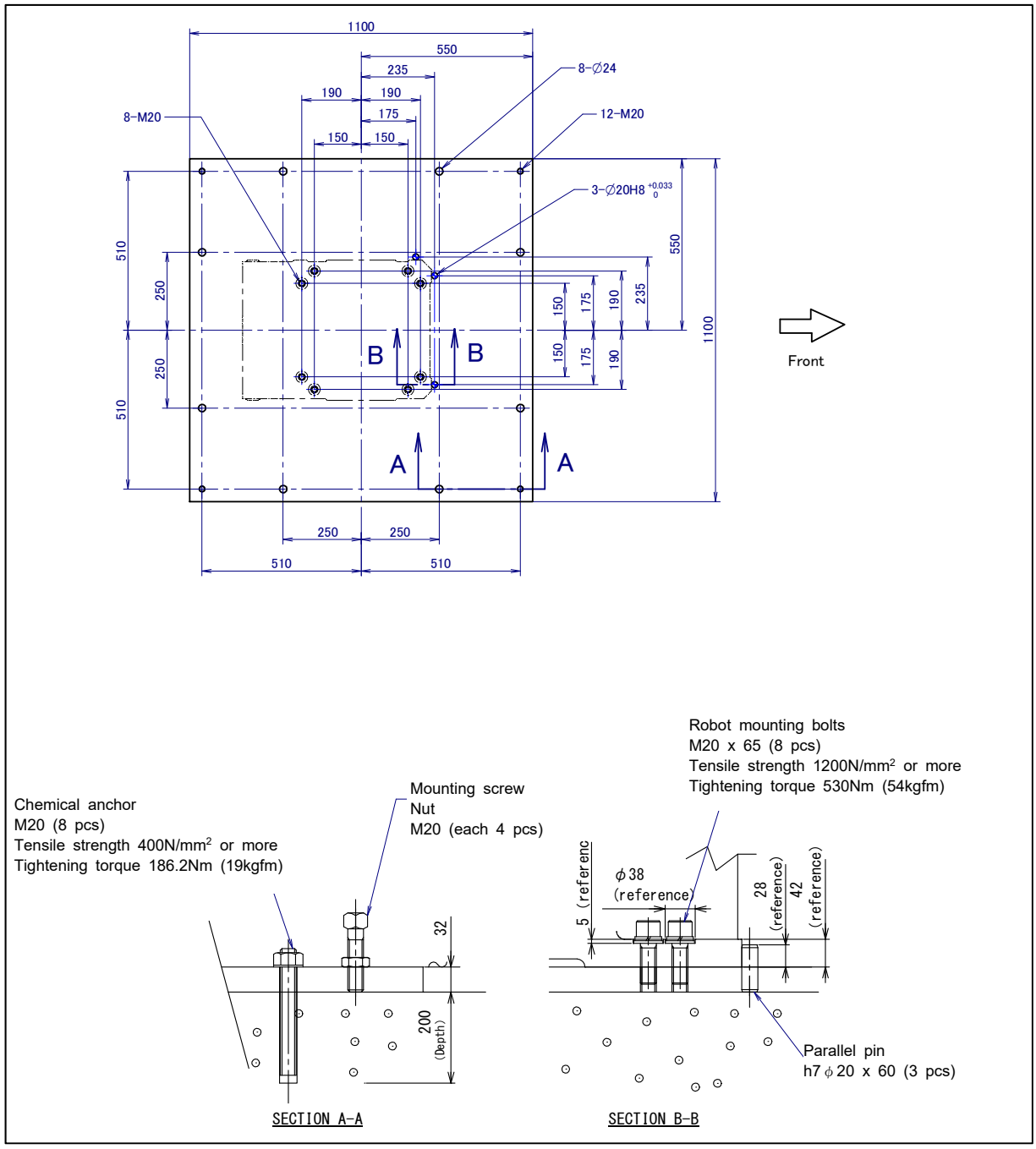


Fig.1.2.1 (b) Actual installation example Ⅱ

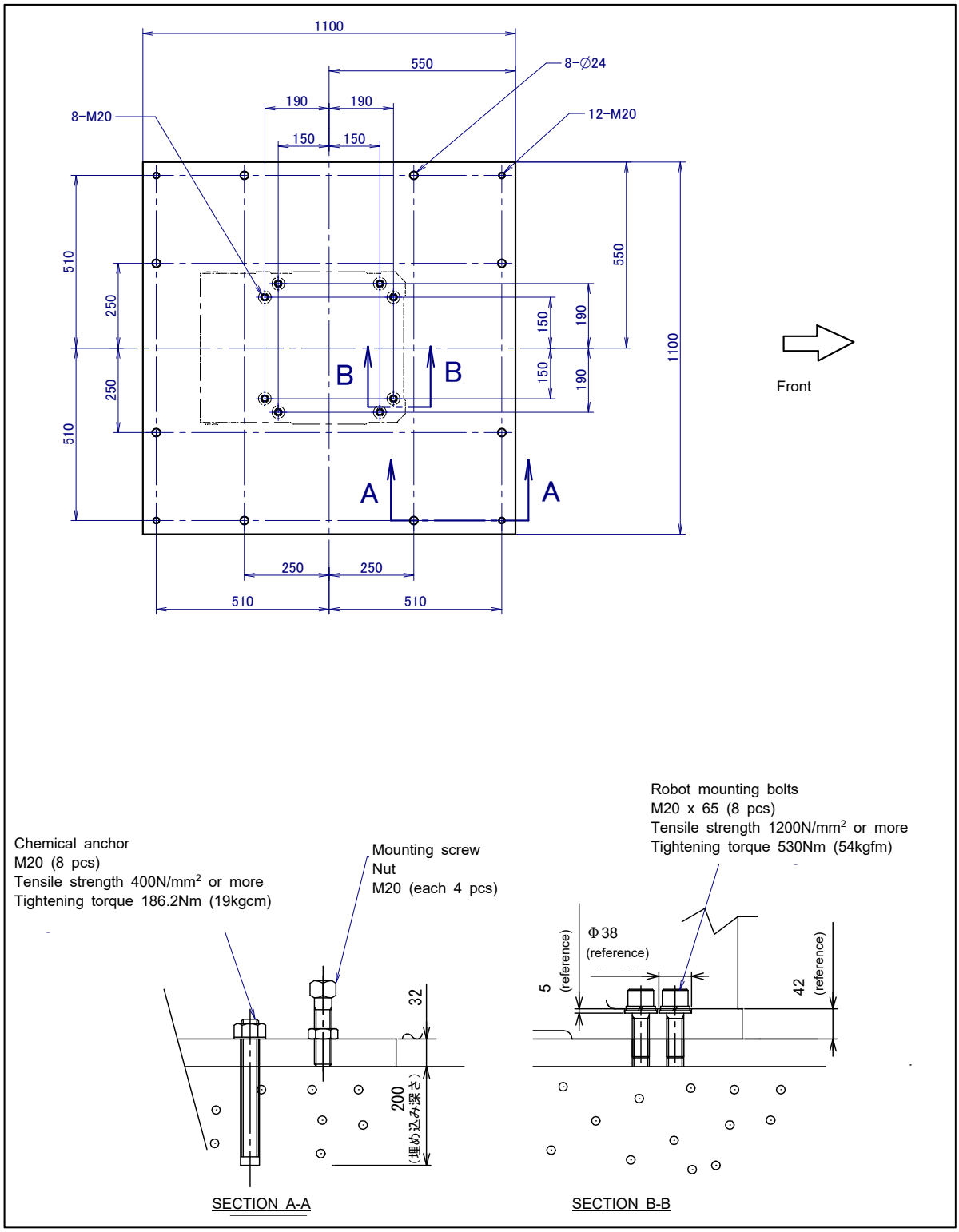
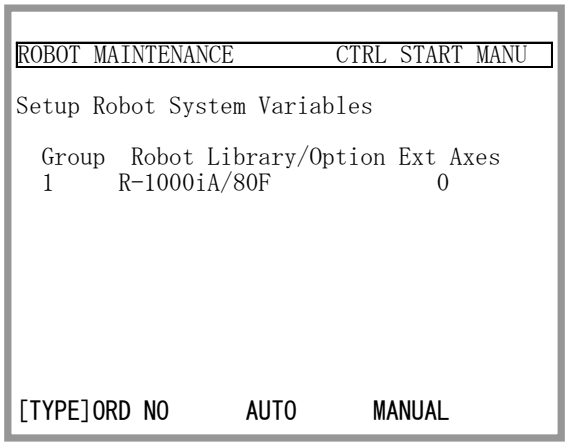


Fig. 1.2.1 (c) Actual installation example Ⅲ

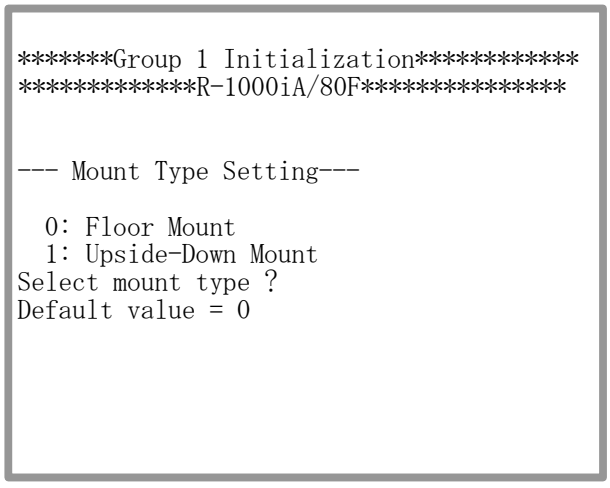
1.2.2 Angle of Mounting Surface Setting

If the robot is installed as upside-down mount, be sure to set the mounting angle referring to the procedure below.
Refer to specifications in Section 3.1 for installation type.

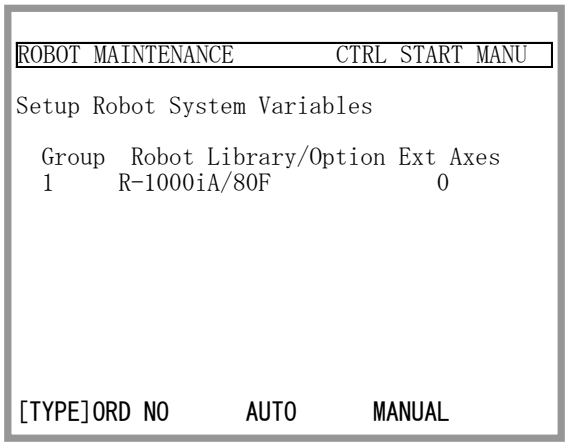
1 Turn on the controller with the [PREV] and the [NEXT] key pressed. Then select [3 Controlled start].
2 Press the [MENU] key and select “9 MAINTENANCE”.
3 Select the robot for which you want to set the mount angle and press the [ENTER] key.



4 Press the [F4] key.
5 Press the [ENTER] key until screen below is displayed.



6 To change to the upside-down mount, input “1”.
7 Press the [ENTER] key. Then the following screen will be displayed.



8 Press the [FCTN] key and select ”1 START (COLD)”.

* For J4-axis motion range change in case of R-1000*i*A/80H upside-down mount, refer to “3.3.1 Change Method of J4-axis Motion Range”.

1.3 MAINTENANCE AREA

Fig. 1.3 (a) shows the maintenance area of the mechanical unit. Dotted line area is necessary for fixture position mastering. Be sure to leave enough room for the robot to be mastered. Contact your local FANUC representative for fixture position mastering.

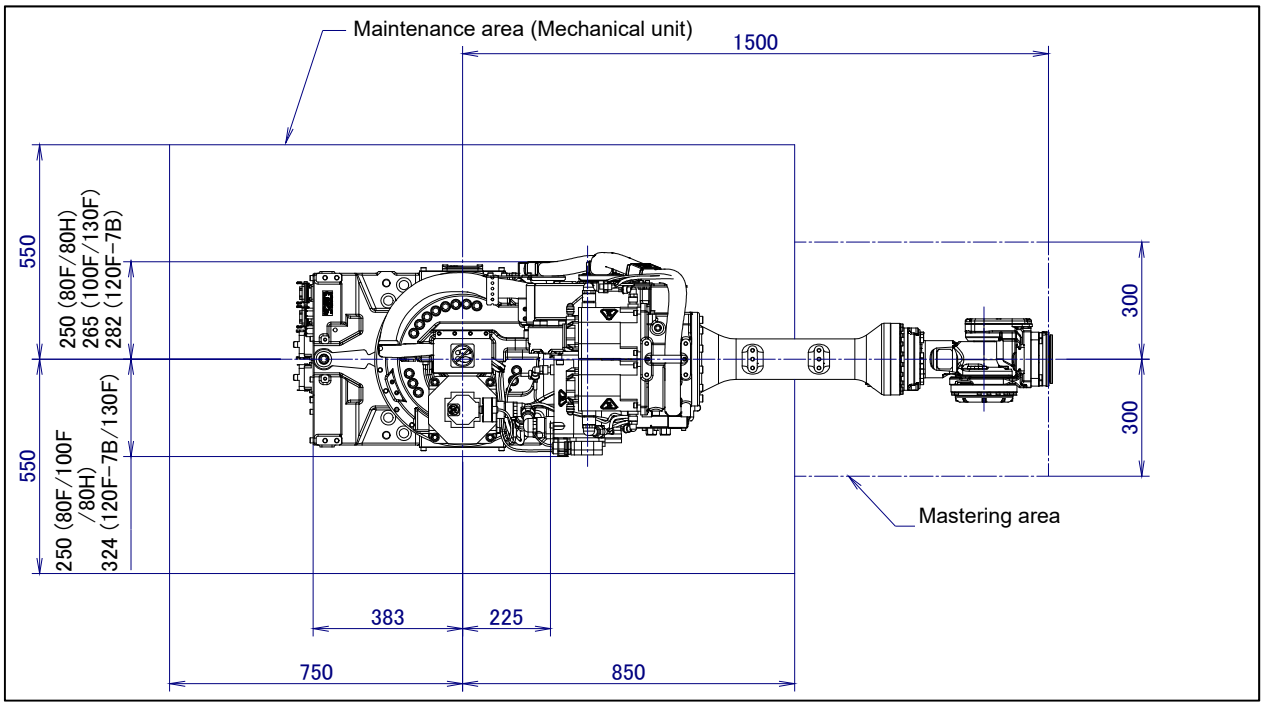


Fig. 1.3 (a) Maintenance area

1.4 INSTALLATION CONDITIONS

Refer to specification of Section 3.1 about installation conditions.

> ⚠ **CAUTION**
> Damage to the cable jacket can cause water intrusion. Take care not to damage the cable jacket when installing the robot. Replace the cable if it is damaged.

2 CONNECTION WITH THE CONTROLLER

The robot is connected with the controller via the power cable, the signal cable, and the earth cable. Connect these cables to the connectors on the back of the base.
For details on air and option cables, see Chapter 5.

> ⚠ **WARNING**
> Before turning on controller power, be sure to connect the robot and controller with the earth line (ground). Otherwise, there is the risk of electrical shock.

> ⚠ **CAUTION**
> 1 Before connecting the cables, be sure to turn off the controller power.
> 2 Do not use 10m or longer coiled cable without first untying it. The long coiled cable could heat up and become damaged.

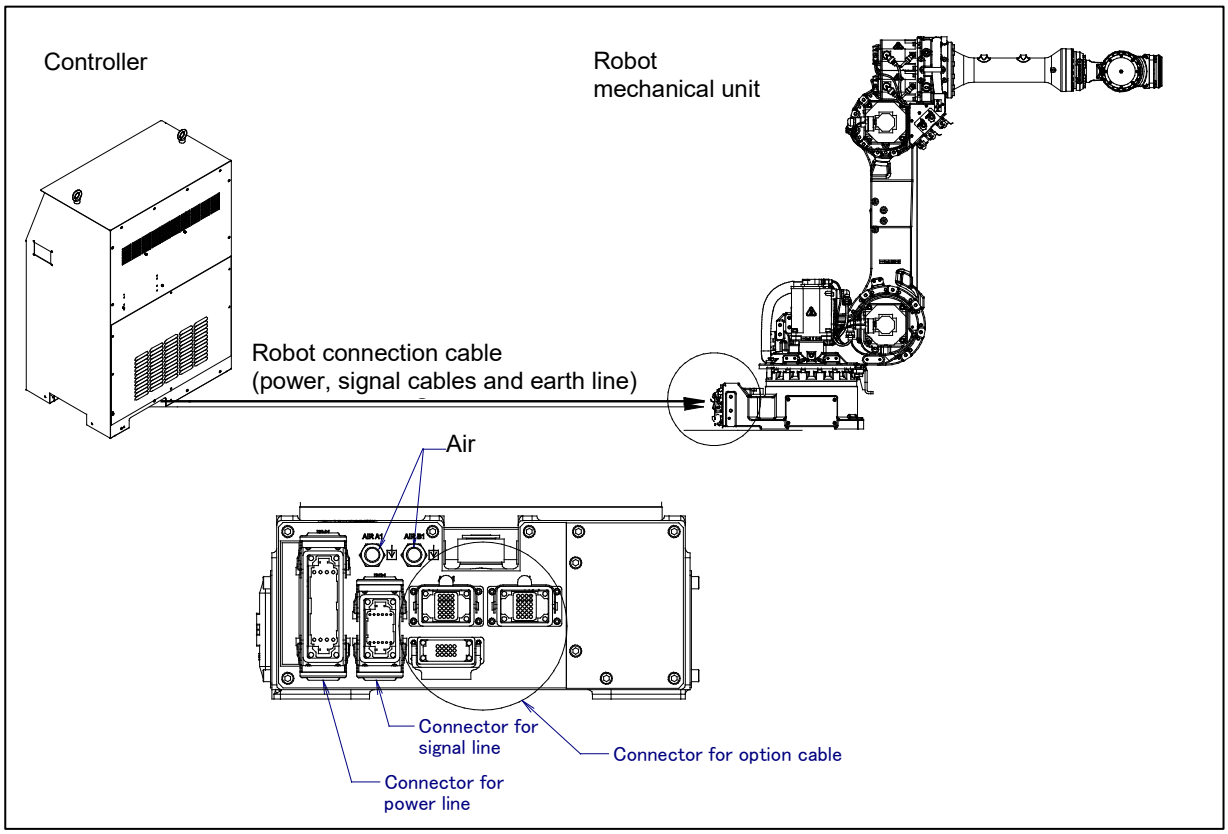


Fig. 2 (a) Cable connection

3 BASIC SPECIFICATIONS

3.1 ROBOT CONFIGURATION

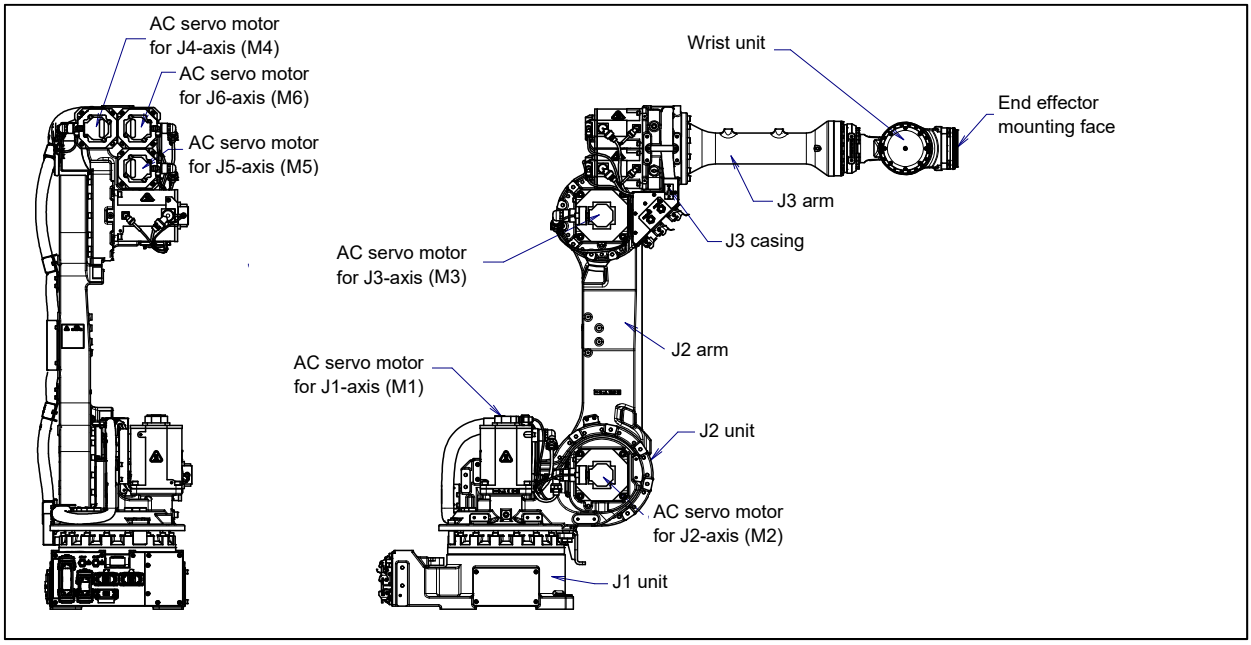


Fig. 3.1 (a) Mechanical unit configuration (R-1000*i*A/80F/100F/130F)

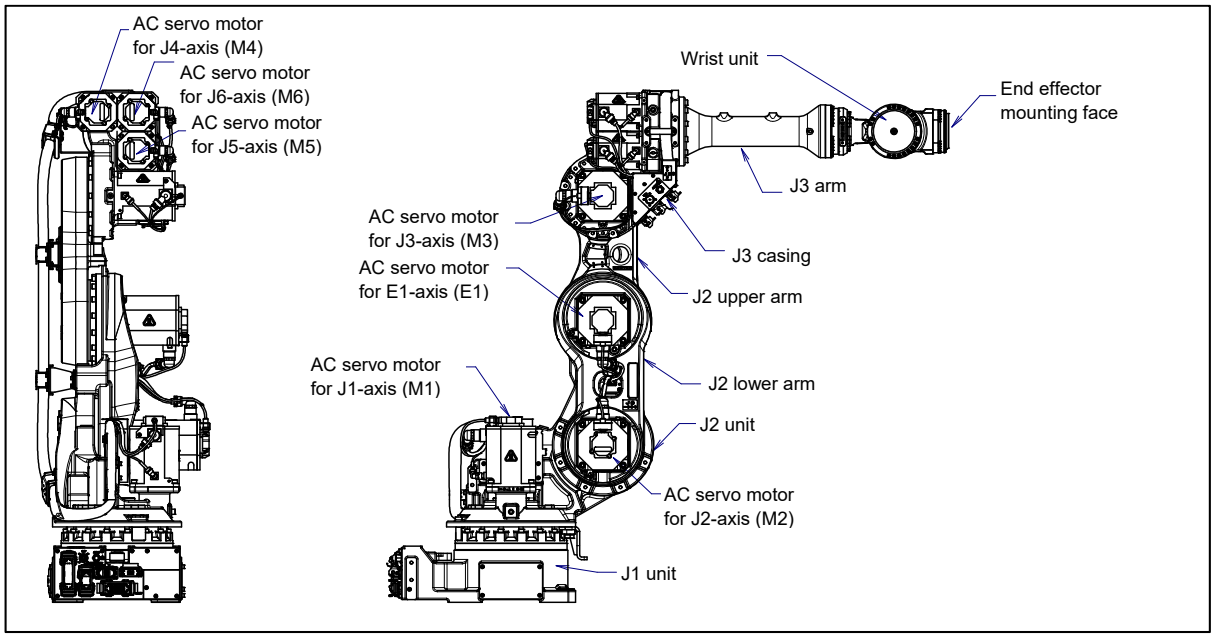


Fig. 3.1 (b) Mechanical unit configuration (R-1000*i*A/120F-7B)

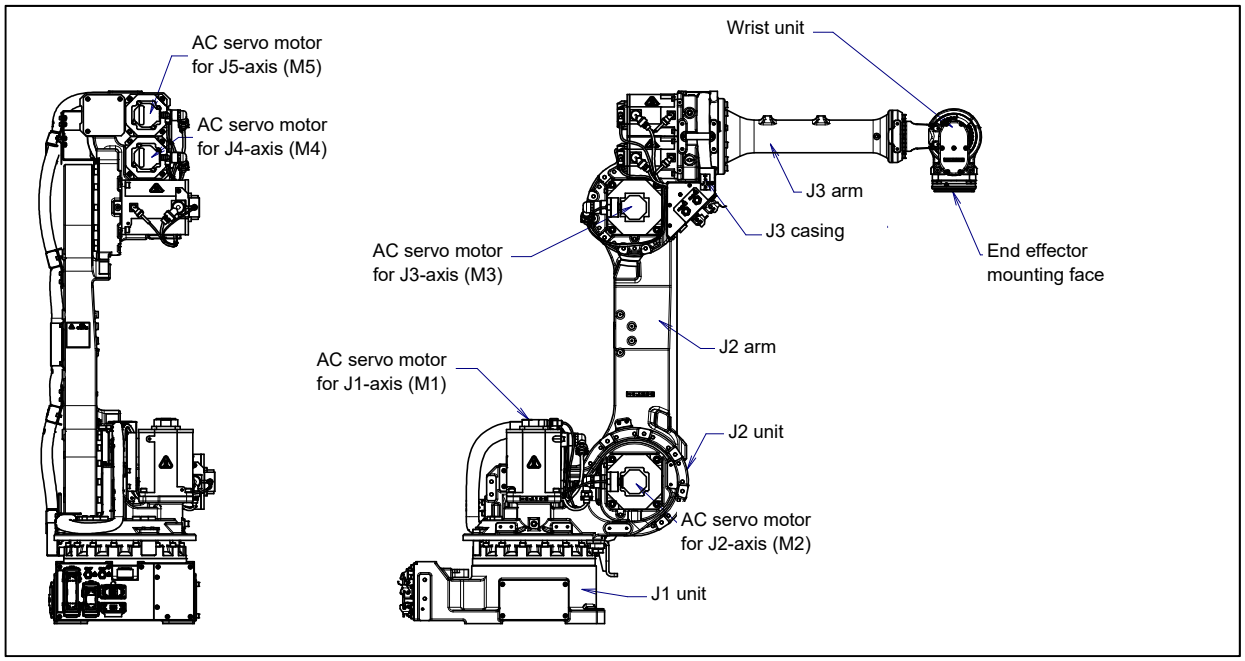


Fig. 3.1 (c) Mechanical unit configuration (R-1000*i*A/80H)

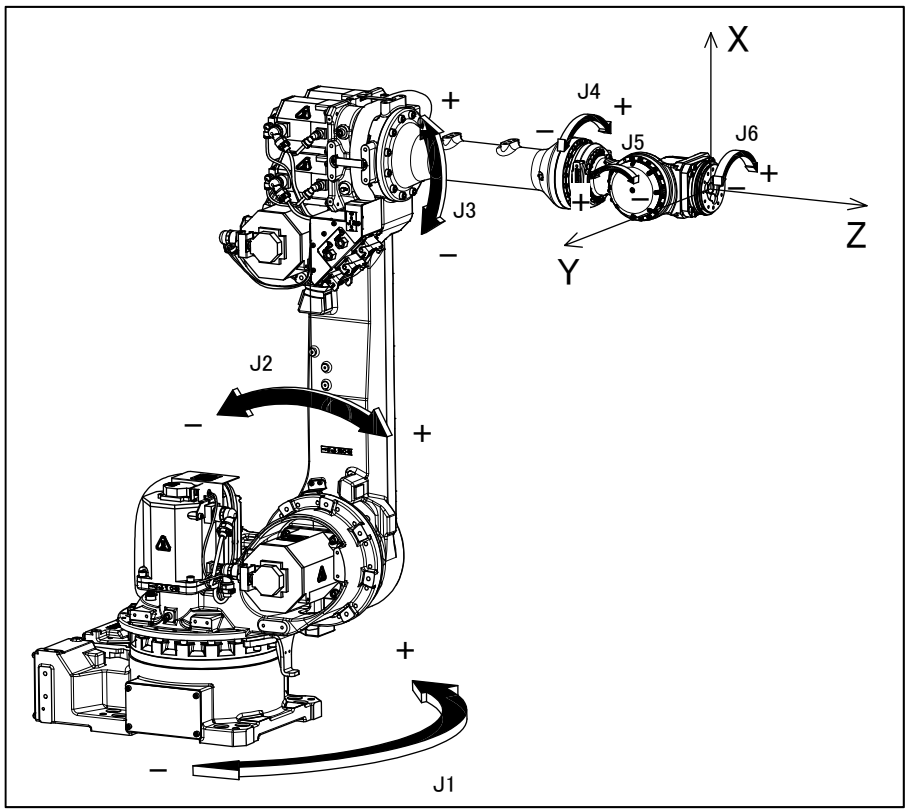


Fig. 3.1 (d) Each axes coordinates and mechanical interface coordinates (R-1000*i*A/80F/100F/130F)

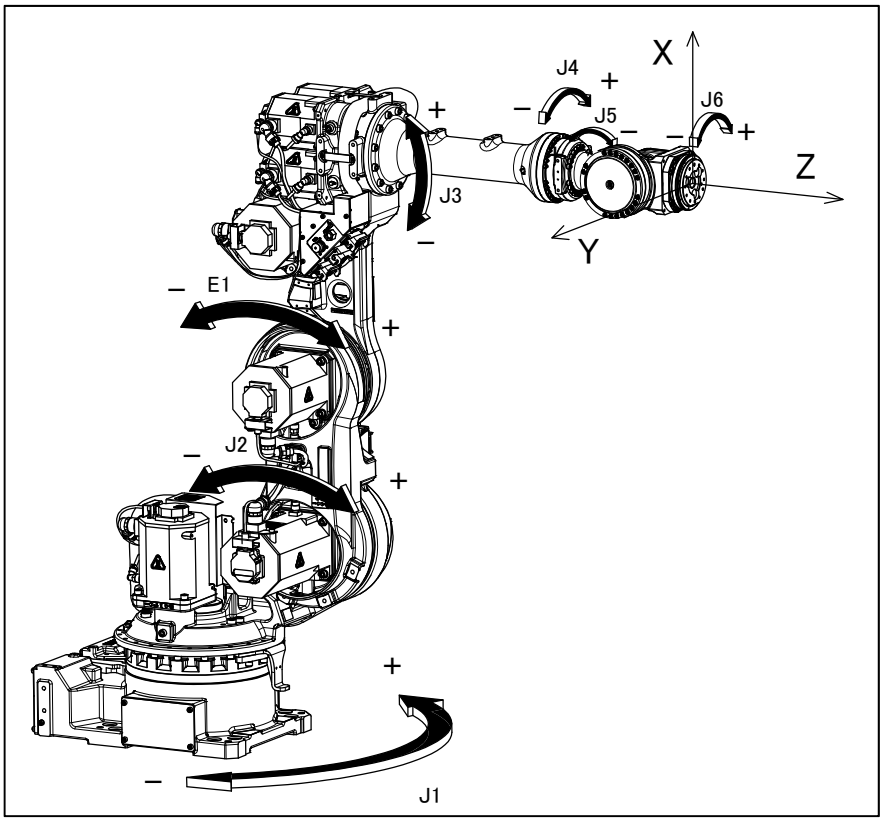


Fig. 3.1 (e) Each axes coordinates and mechanical interface coordinates (R-1000*i*A/120F-7B)

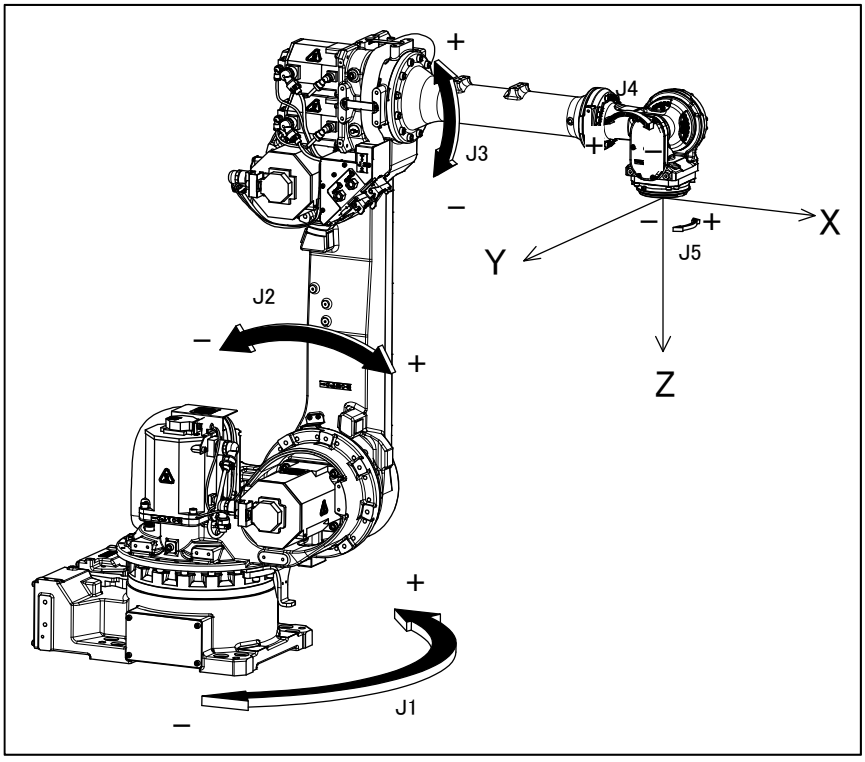


Fig. 3.1 (f) Each axes coordinates and mechanical interface coordinates (R-1000*i*A/80H)

NOTE
The end effector mounting face center is 0, 0, 0 of the mechanical interface coordinates.

Specifications (NOTE 1) (1/3)

Model		R-1000*i*A/80F		R-1000*i*A/100F		R-1000*i*A/130F
Type		Articulated type				
Controlled axes		6-axes (J1, J2, J3, J4, J5, J6)				
Installation		Floor mount, Upside down				
Motion range (Upper limit / Lower limit)	J1-axis	180° (3.14rad) / -180° (-3.14rad)				
	J2-axis	155° (2.71rad) / -90° (-1.57rad)				
	J3-axis	180° (3.14rad) / -180° (-3.14rad)				
	J4-axis	360° (6.28rad) / -360° (-6.28rad)				
	J5-axis	125° (2.18rad) / -125° (-2.18rad)				
	J6-axis	360° (6.28rad) / -360° (-6.28rad)				
Maximum speed (NOTE 2)	J1-axis	170°/s (2.97rad/s)		130°/s (2.27rad/s)		
	J2-axis	140°/s (2.44rad/s)		110°/s (1.92rad/s)		
	J3-axis	160°/s (2.79rad/s)		120°/s (2.09rad/s)		
	J4-axis	230°/s (4.01rad/s)		170°/s (2.97rad/s)		
	J5-axis	230°/s (4.01rad/s)		170°/s (2.97rad/s)		
	J6-axis	350°/s (6.11rad/s)		250°/s (4.36rad/s)		
Max. payload	At wrist	80kg (A)		100kg		130kg
	On J3 arm	—	(A) + (B) < 80kg	20kg (C)	(C) + (D) < 20kg	
	On J3 casing	15kg (B)		20kg (D)		
Allowable load moment at wrist	J4-axis	380N·m (38.8kgf·m)		690N·m (70.4kgf·m)		800N·m (81.6kgf·m)
	J5-axis	380N·m (38.8kgf·m)		690N·m (70.4kgf·m)		800N·m (81.6kgf·m)
	J6-axis	200N·m (20.4kgf·m)		260N·m (26.5kgf·m)		360N·m (36.7kgf·m)
Allowable load inertia at wrist	J4-axis	30kg·m^2 (306.1kgf·cm·s^2)		57kg·m^2 (581.6kgf·cm·s^2)		71kg·m^2 (724.5kgf·cm·s^2)
	J5-axis	30kg·m^2 (306.1kgf·cm·s^2)		57kg·m^2 (581.6kgf·cm·s^2)		71kg·m^2 (724.5kgf·cm·s^2)
	J6-axis	20kg·m^2 (204.1kgf·cm·s^2)		32kg·m^2 (326.5kgf·cm·s^2)		38kg·m^2 (387.8kgf·cm·s^2)
Drive method		Electric servo drive by AC servo motor				
Repeatability (NOTE 3)		±0.03mm				
Mass		620kg		665kg		675kg
Acoustic noise level		Less than 70dB (NOTE 4)				
Installation environment		Ambient temperature: 0 to 45℃ (NOTE 5) Ambient humidity: Normally 75%RH or less (No condensation allowed.) Short time (Within 1 month) 95%Rh or less (No condensation allowed.) Permissible altitude: Above the sea 1000m or less Vibration acceleration: 4.9m/s^2 (0.5G) or less Free of corrosive gases (NOTE 6)				

NOTE

1 Even if the robot is used according to the defined specifications, motion programs might shorten reducer life or cause the robot to overheat. Use ROBOGUIDE (system design support tool by FANUC) for further evaluation before running production.
2 During short distance motions, the axis speed may not reach the maximum value stated.
3 Compliant with ISO 9283.
4 This value is equivalent continuous A-weighted sound pressure level that applied with ISO11201 (EN31201). This value is measured with the following conditions.
  - Maximum load and speed
  - Operating mode is AUTO
5 When robot is used in low temperature environment that is near to 0ºC,or robot is not operated for a long time in the environment that is less than 0ºC in a holiday or the night, because viscous resistance of the drive train is so big that may cause occurrence of collision detect alarm (SRVO –050) etc. In this case, we recommend performing the warm up operation for several minutes.
6 Contact the service representative, if the robot is to be used in an environment or a place subjected to hot/cold temperatures, severe vibrations, heavy dust, cutting oil splash and or other foreign substances.

Specifications (NOTE 1) (2/3)

Model		R-1000*i*A/120F-7B	
Type		Articulated type	
Controlled axes		7-axes (J1, J2, J3, J4, J5, J6, E1)	
Installation		Floor mount, Upside down	
Motion range (Upper limit / Lower limit)	J1-axis	180° (3.14rad) / -180° (-3.14rad)	
	J2-axis	155° (2.71rad) / -45° (-0.79rad)	
	J3-axis	180° (3.14rad) / -205° (-3.58rad)	
	J4-axis	360° (6.28rad) / -360° (-6.28rad)	
	J5-axis	125° (2.18rad) / -125° (-2.18rad)	
	J6-axis	360° (6.28rad) / -360° (-6.28rad)	
	E1-axis	115° (2.01rad) / -110° (-1.92rad)	
Maximum speed (NOTE 2)	J1-axis	130°/s (2.27rad/s)	
	J2-axis	110°/s (1.92rad/s)	
	J3-axis	120°/s (2.09rad/s)	
	J4-axis	170°/s (2.97rad/s)	
	J5-axis	170°/s (2.97rad/s)	
	J6-axis	250°/s (4.36rad/s)	
	E1-axis	130°/s (2.27rad/s)	
Max. payload	At wrist	120kg	
	On J3 arm	20kg (C)	(C) + (D) < 20kg
	On J3 casing	20kg (D)	
Allowable load moment at wrist	J4-axis	800N·m (81.6kgf·m)	
	J5-axis	800N·m (81.6kgf·m)	
	J6-axis	360N·m (36.7kgf·m)	
Allowable load inertia at wrist	J4-axis	71kg·m^2 (724.5kgf·cm·s^2)	
	J5-axis	71kg·m^2 (724.5kgf·cm·s^2)	
	J6-axis	38kg·m^2 (387.8kgf·cm·s^2)	
Drive method		Electric servo drive by AC servo motor	
Repeatability (NOTE 3)		±0.03mm	
Mass		790kg	
Acoustic noise level		Less than 70dB (NOTE 4)	
Installation environment		Ambient temperature: 0 to 45℃ (NOTE 5) Ambient humidity: Normally 75%RH or less (No condensation allowed.) Short time (Within 1 month) 95%Rh or less (No condensation allowed.) Permissible altitude: Above the sea 1000m or less Vibration acceleration: 4.9m/s^2 (0.5G) or less Free of corrosive gases (NOTE 6)	

NOTE

1 Even if the robot is used according to the defined specifications, motion programs might shorten reducer life or cause the robot to overheat. Use ROBOGUIDE (system design support tool by FANUC) for further evaluation before running production.
2 During short distance motions, the axis speed may not reach the maximum value stated.
3 Compliant with ISO 9283.
4 This value is equivalent continuous A-weighted sound pressure level that applied with ISO11201 (EN31201). This value is measured with the following conditions.
- Maximum load and speed
- Operating mode is AUTO

5 When robot is used in low temperature environment that is near to 0ºC,or robot is not operated for a long time in the environment that is less than 0ºC in a holiday or the night, because viscous resistance of the drive train is so big that may cause occurrence of collision detect alarm (SRVO –050) etc. In this case, we recommend performing the warm up operation for several minutes.
6 Contact the service representative, if the robot is to be used in an environment or a place subjected to hot/cold temperatures, severe vibrations, heavy dust, water, water vapor, cutting oil, cleaning fluid splash and or other foreign materials.

Specifications (NOTE 1) (3/3)

Model		R-1000*i*A/80H	
Type		Articulated type	
Controlled axes		5-axes (J1, J2, J3, J4, J5)	
Installation		Floor mount, Upside down	
Motion range (Upper limit / Lower limit)	J1-axis	180° (3.14rad) / -180° (-3.14rad)	
	J2-axis	155° (2.71rad) / -90° (-1.57rad)	
	J3-axis	35° (0.61rad) / -180° (-3.14rad) (Floor mount) 180° (3.14rad) / -180° (-3.14rad) (Upside down mount)	
	J4-axis (NOTE 2)	10° (0.31rad) / -10° (-0.31rad) (NOTE 3) 190° (3.31rad) / 170° (2.97rad) (NOTE 3)	
	J5-axis	360° (6.28rad) / -360° (-6.28rad)	
Maximum speed (NOTE 4)	J1-axis	185° /s (3.23rad/s)	
	J2-axis	180° /s (3.14rad/s)	
	J3-axis	180° /s (3.14rad/s)	
	J4-axis	180° /s (3.14rad/s)	
	J5-axis	500° /s (8.73rad/s)	
Max. payload	At wrist	80kg (A)	
	On J3 arm	-	(A) + (B) < 80kg
	On J3 casing	15kg (B)	
Allowable load moment at wrist	J4-axis	(NOTE 5)	
	J5-axis		
Allowable load inertia at wrist	J4-axis	48kg·m^2 (489.8kgf·cm·s^2)	
	J5-axis	25kg·m^2 (255.1kgf·cm·s^2)	
Drive method		Electric servo drive by AC servo motor	
Repeatability (NOTE 6)		±0.03mm	
Mass		610kg	
Acoustic noise level		Less than 70dB (NOTE 7)	
Installation environment		Ambient temperature: 0 to 45°C (NOTE 8) Ambient humidity: Normally 75%RH or less (No condensation allowed.) Short time (Within 1 month) 95%Rh or less (No condensation allowed.) Permissible altitude: Above the sea 1000m or less Vibration acceleration: 4.9m/s^2 (0.5G) or less Free of corrosive gases (NOTE 9)	

NOTE

1 Even if the robot is used according to the defined specifications, motion programs might shorten reducer life or cause the robot to overheat. Use ROBOGUIDE (system design support tool by FANUC) for further evaluation before running production.
2 The wrist interface is always controlled downward. It can be made fine adjustment from -10 to 10 degrees or 170 to 190 degrees
3 R-1000*i*A/80H provides 2 different types of J4-axis motion range. Refer to Section 3.3.1 about changing method
4 During short distance motions, the axis speed may not reach the maximum value stated.
5 Distance from the center of gravity of the load to the wrist flange center is limited by the wrist load and load inertia. In case of the wrist load and load inertia is maximum, center of gravity of the load can be offset up to 254mm in the horizontal direction and up to 400mm in the vertical direction from the wrist flange center.
6 Compliant with ISO 9283.
7 This value is equivalent continuous A-weighted sound pressure level that applied with ISO11201 (EN31201). This value is measured with the following conditions.
   - Maximum load and speed
   - Operating mode is AUTO
8 When robot is used in low temperature environment that is near to 0ºC,or robot is not operated for a long time in the environment that is less than 0ºC in a holiday or the night, because viscous resistance of the drive train is so big that may cause occurrence of collision detect alarm (SRVO –050) etc. In this case, we recommend performing the warm up operation for several minutes.
9 Contact the service representative, if the robot is to be used in an environment or a place subjected to hot/cold temperatures, severe vibrations, heavy dust, water, water vapor, cutting oil, cleaning fluid splash and or other foreign materials.

The following table lists the IEC60529-based Severe dust/liquid protection characteristics of the R-1000*i*A. Refer to Chapter 10 about severe dust/liquid protection package (option).

	Standard	Severe dust/liquid protection package (option)
J3 arm and wrist section	IP67	IP67
Drive unit of the main body	IP66	IP66
Main body	IP54 (*)	IP56

(*) Except some connectors

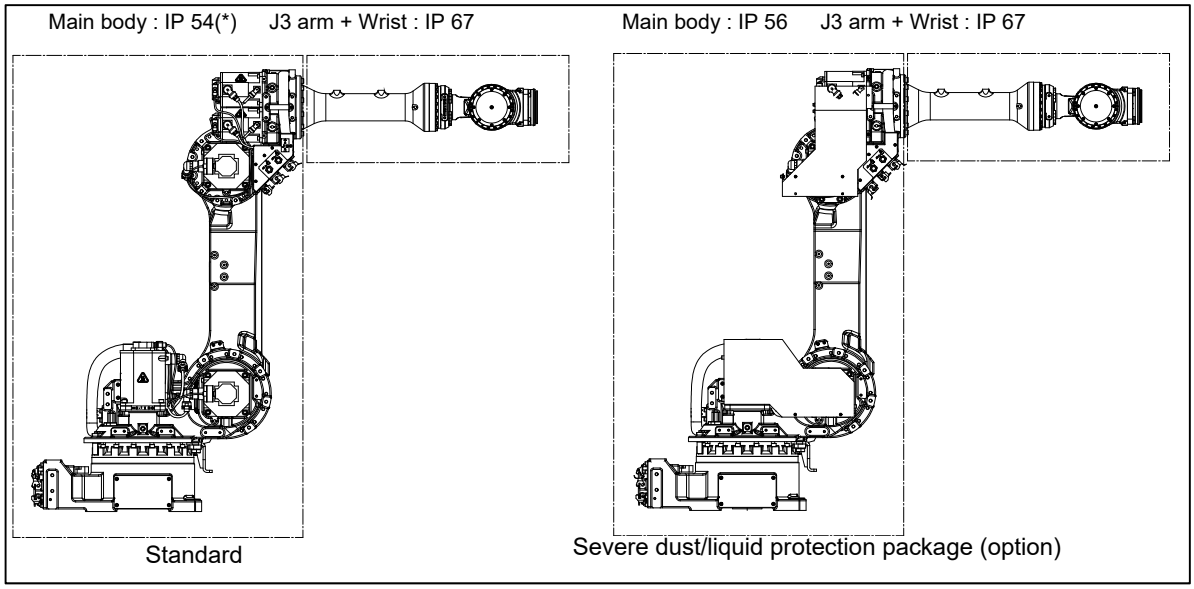


Fig. 3.1 (g) Severe dust/liquid protection characteristics of R-1000*i*A

NOTE

Definition of IP code

Definition of IP 67

6= Dust-tight: Complete protection against contact

7= Protection from water immersion: Ingress of water in harmful quantity shall not be possible when the enclosure is immersed in water under defined conditions of pressure and time.

Definition of IP 66

6= Dust-tight: Complete protection against contact

6= Protection from powerful water jets: Water projected in powerful jets against the enclosure from any direction shall have no harmful effects.

Definition of IP 54

5= Dust-tight: Ingress of dust is not entirely prevented, but it must not enter in sufficient quantity to interfere with the satisfactory of the equipment.

4= Protection from water immersion : Water splashing against the enclosure from any direction shall have no harmful effect.

Definition of IP 56

5= Dust-tight: Ingress of dust is not entirely prevented, but it must not enter in sufficient quantity to interfere with the satisfactory of the equipment.

6= Protection from powerful water jets: Water projected in powerful jets against the enclosure from any direction shall have no harmful effects.

Performance of resistant chemicals and resistant solvents

(1) The robot (including severe dust/liquid protection model) cannot be used with the following liquids. Potentially these liquids will cause irreversible damage to the rubber parts (such as: gaskets, oil seals, O-rings etc.). (As exception to this only liquids tested and approved by FANUC can be used with the robot.)
   (a) Organic solvents
   (b) Cutting fluid or detergent including chlorine / gasoline
   (c) Amine type cutting fluid or detergent
   (d) Acid, alkali and liquid causing rust
   (e) Other liquids or solutions, that will harm NBR or CR rubber
(2) When the robots work in the environment, using water or liquid, complete draining of J1 base must be done. Incomplete draining of J1 base will make the robot break down.
(3) Do not use unconfirmed liquid.
(4) Do not use the robot immersed in water, neither temporary nor permanent. Robot must not be wet permanently. *Example: in case motor surface is exposed to water for a long time, liquid may invade inside the motor and cause failure.

3.2 MECHANICAL UNIT EXTERNAL DIMENSIONS AND OPERATING SPACE

Fig. 3.2 (a) to (d) show the robot operating space. When installing peripheral devices, be careful not to interfere with the robot and its operating space.

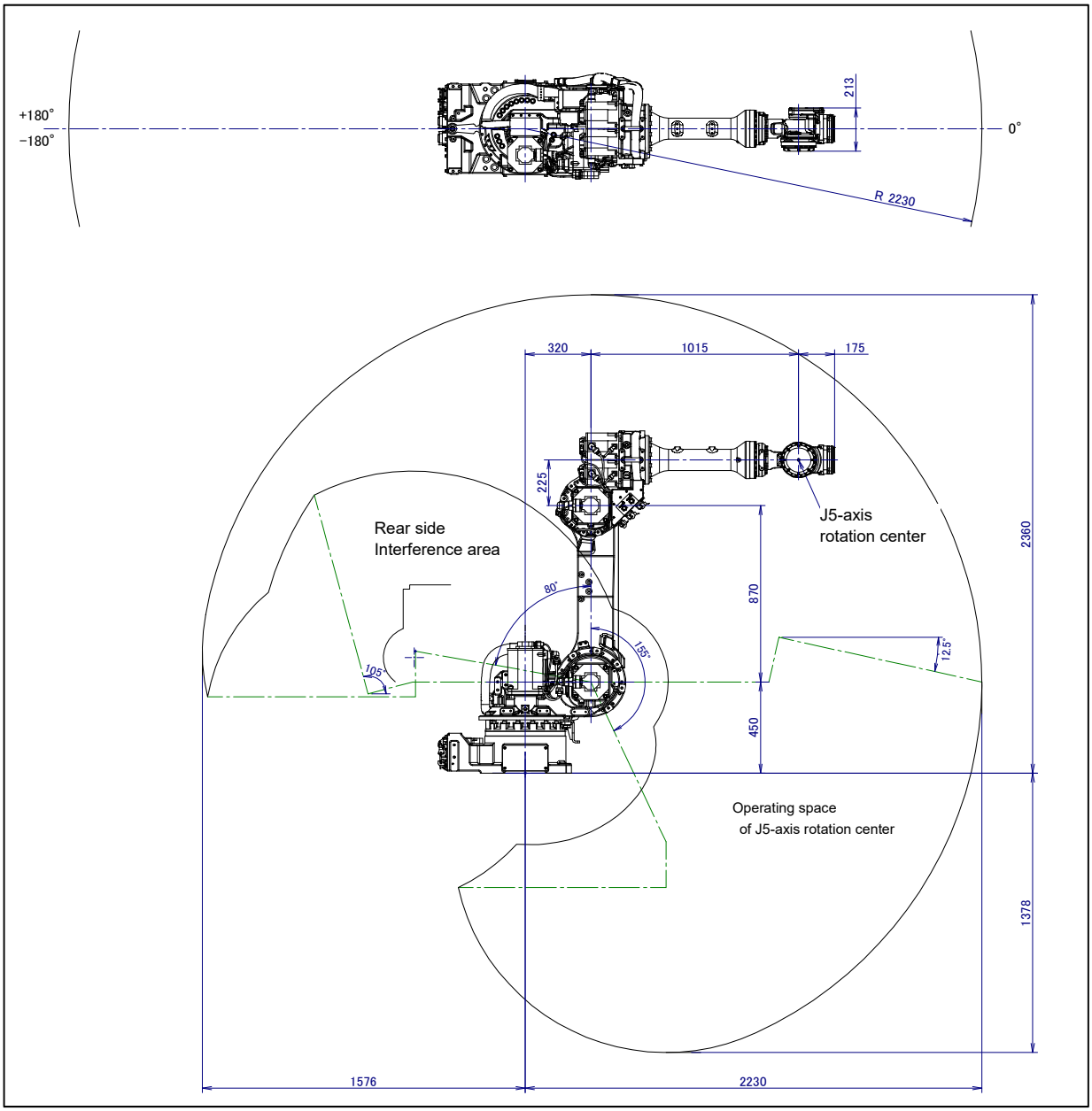


Fig. 3.2 (a) Operating space (R-1000*i*A/80F)

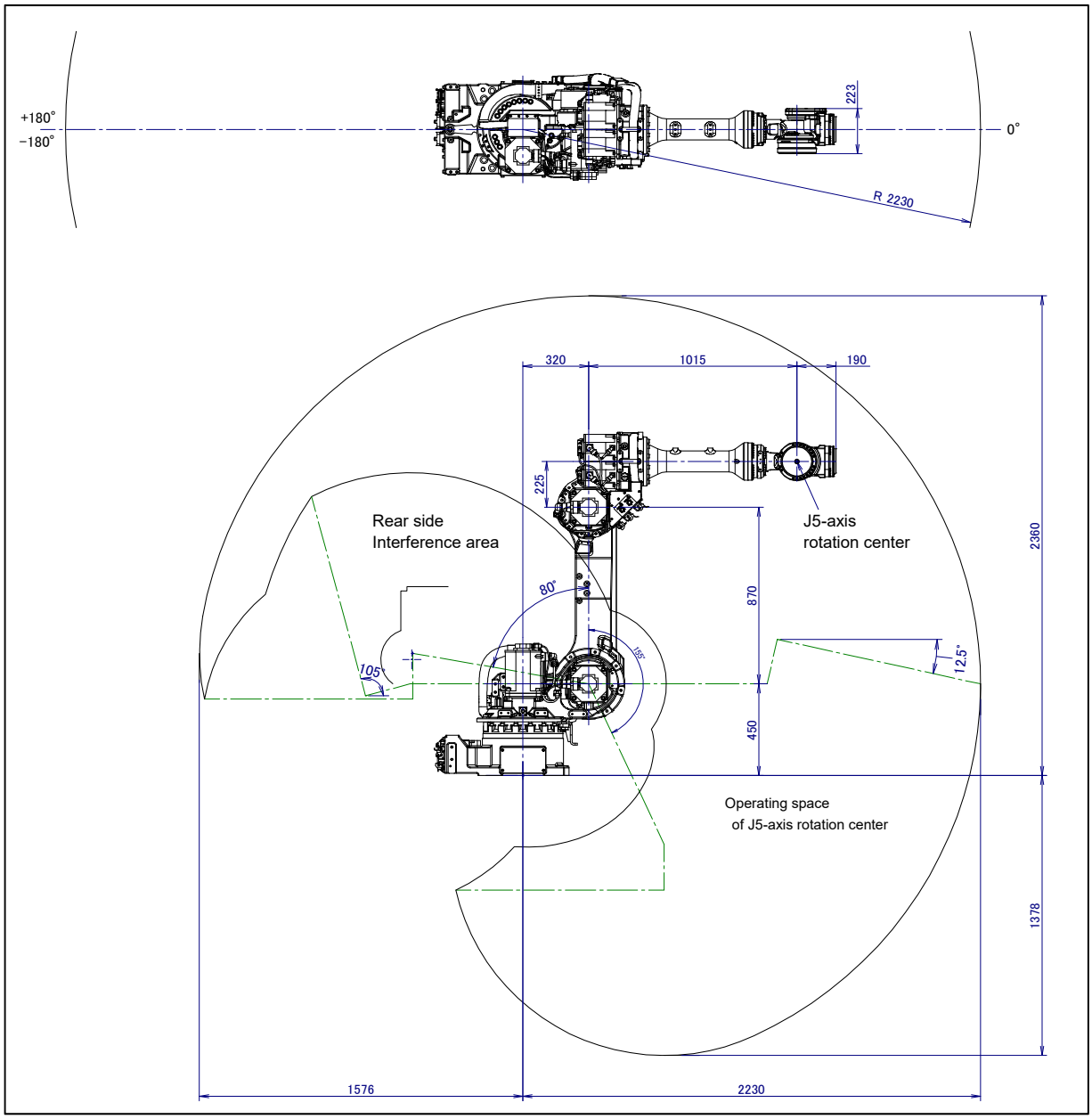


Fig. 3.2 (b) Operating space (R-1000*i*A/100F/130F)

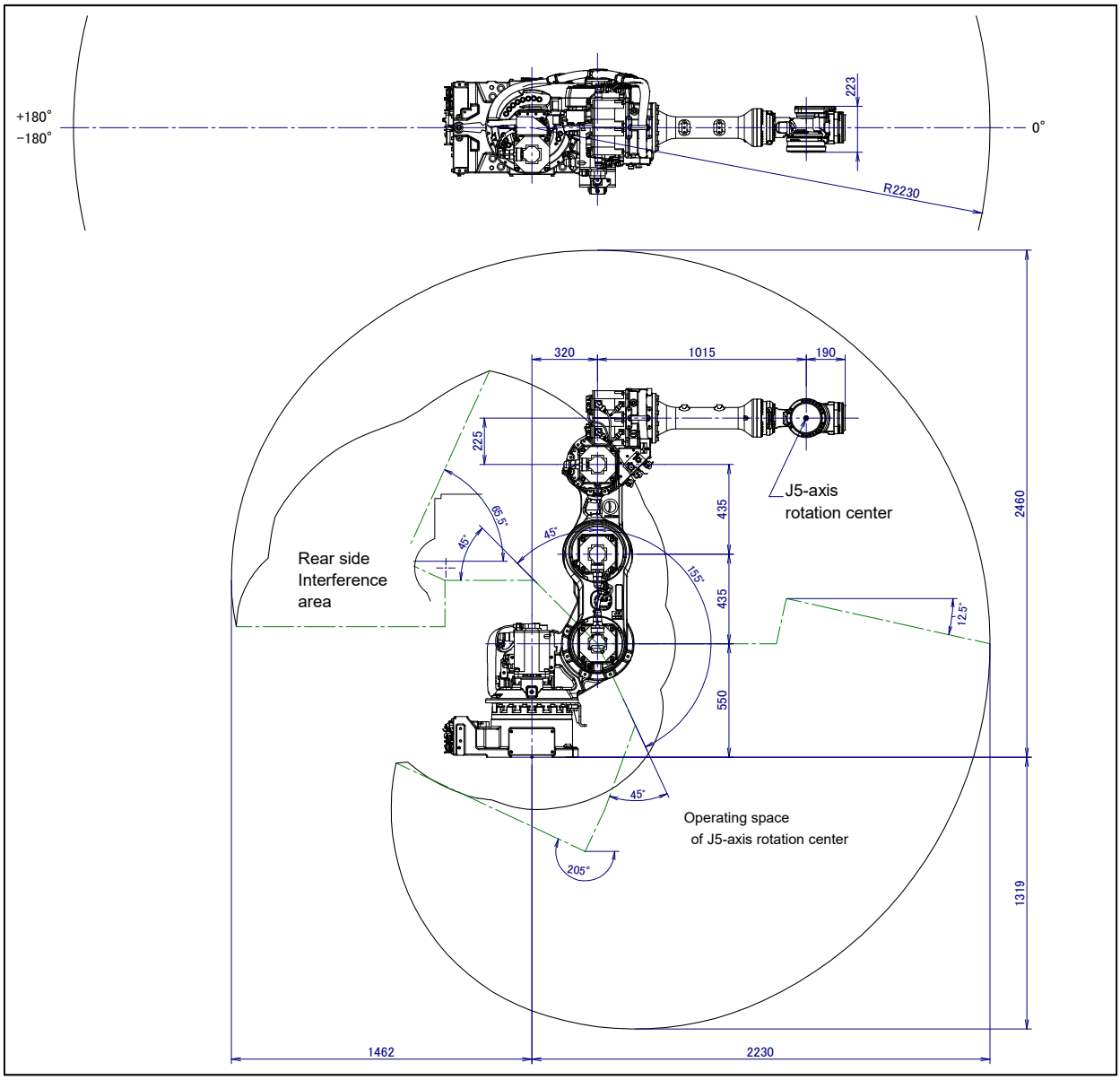


Fig. 3.2 (c) Operating space (R-1000*i*A/120F-7B)

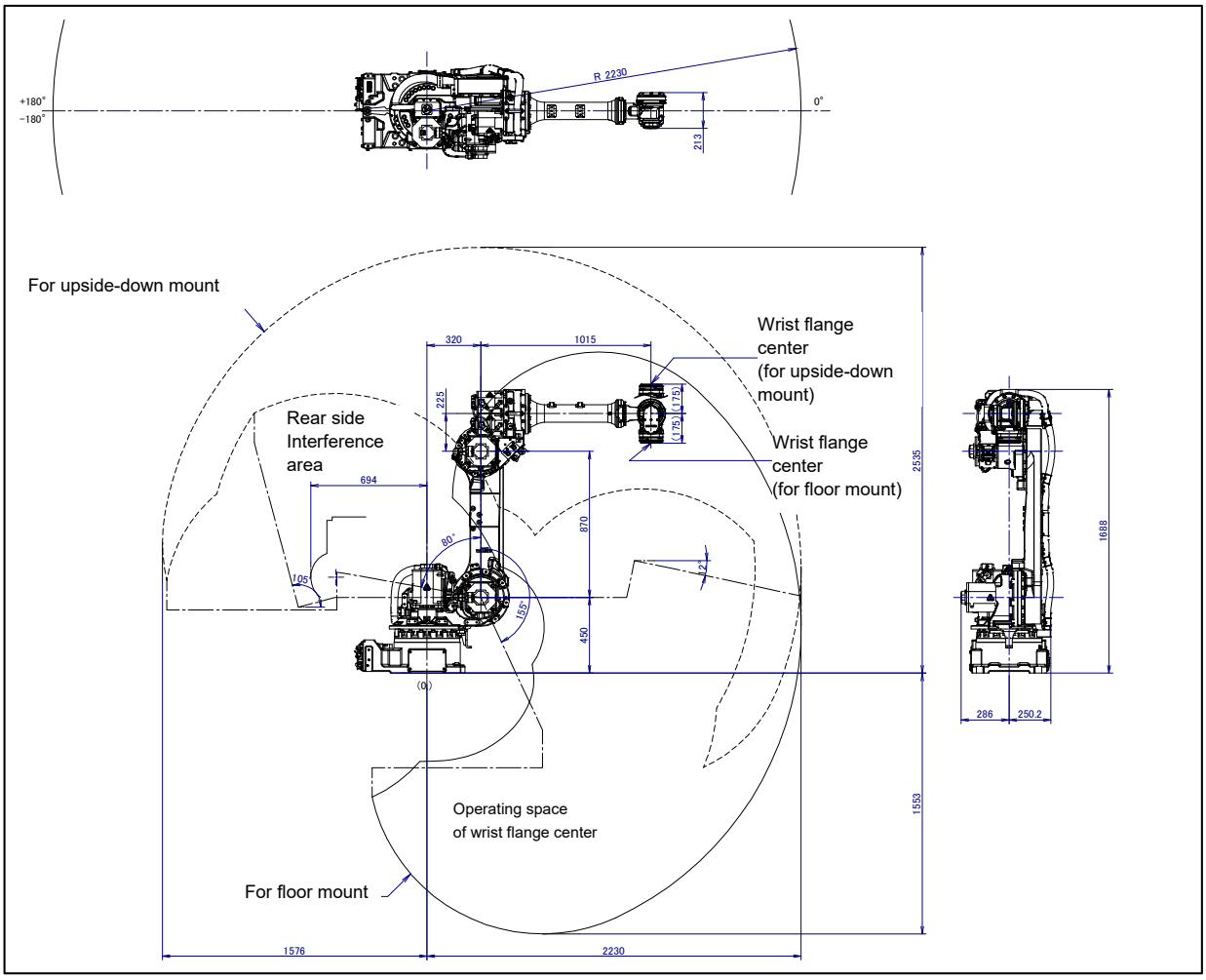


Fig. 3.2 (d) Operating space (R-1000*i*A/80H)

3.3 ZERO POINT POSITION AND MOTION LIMIT

Zero point and motion range are provided for each controlled axis. Exceeding the software motion limit of a controlled axis is called overtravel (OT). Overtravel is detected at both ends of the motion limit for each axis. The robot cannot exceed the motion range unless there is a loss of zero point position due to abnormalities in servo system or system error. In addition, the motion range limit by a mechanical stopper is also prepared to improve safety.

Fig. 3.3 (a) shows the position of mechanical stopper. Only in case of J1-axis, robot stops by transforming mechanical stopper. Be sure to exchange transformed stopper to new one. Tight the bolts according to Appendix B. Replace mechanical stopper of J1-axis referring to Fig.3.3 (b) and Fig.6.2.1 (a). Don't reconstruct the mechanical stopper. There is a possibility that the robot doesn't stop normally.

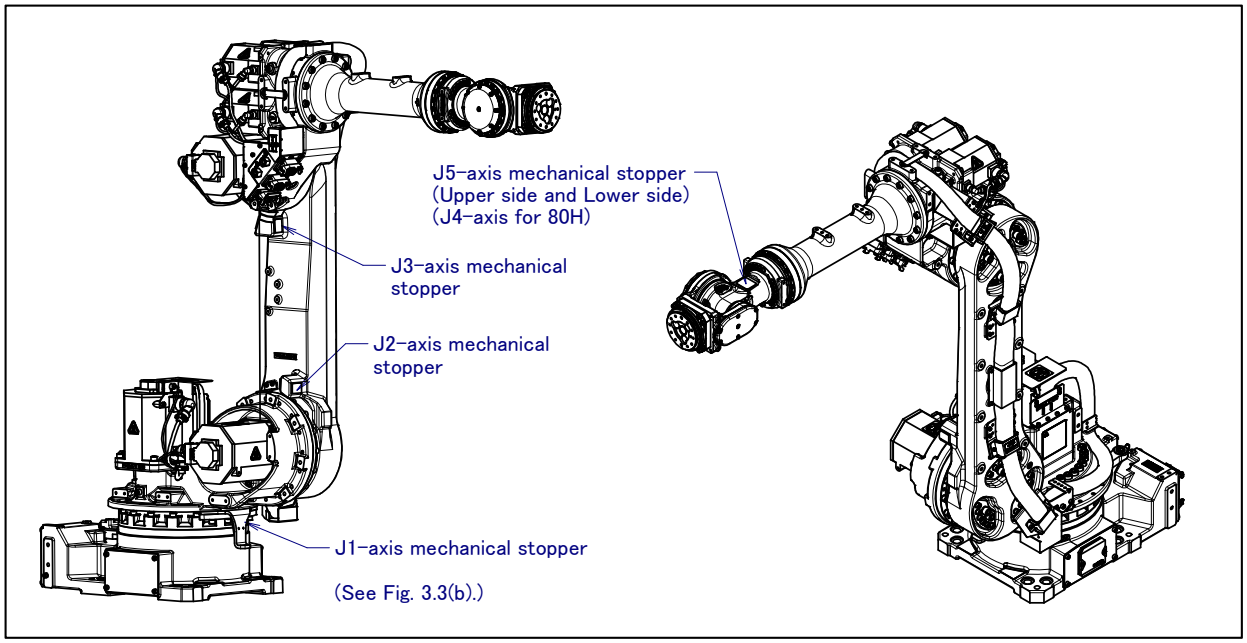


Fig. 3.3 (a) position of mechanical stopper

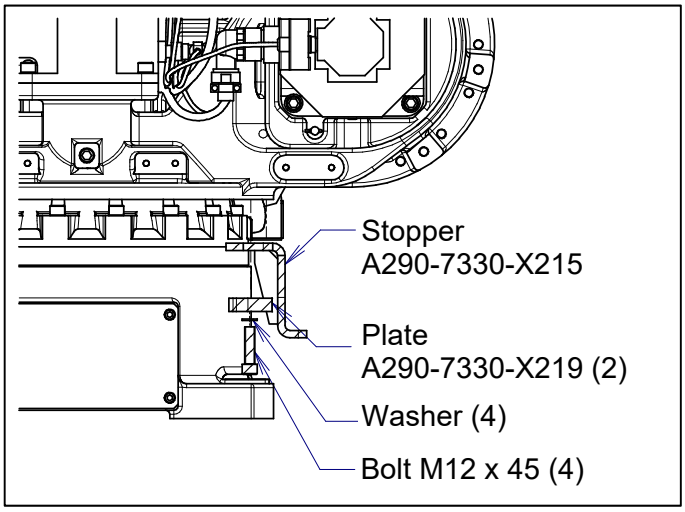


Fig. 3.3 (b) Replacing J1-axis mechanical stopper

Fig.3.3 (c) to (l) show the zero point, motion limit (stroke end), limit switch detection position, and maximum stopping distance (stopping distance in condition of max.speed and max. load) of each axis.

* The motion range can be changed. For information on how to change the motion range, see Chapter 6, “AXIS LIMIT SETUP”.

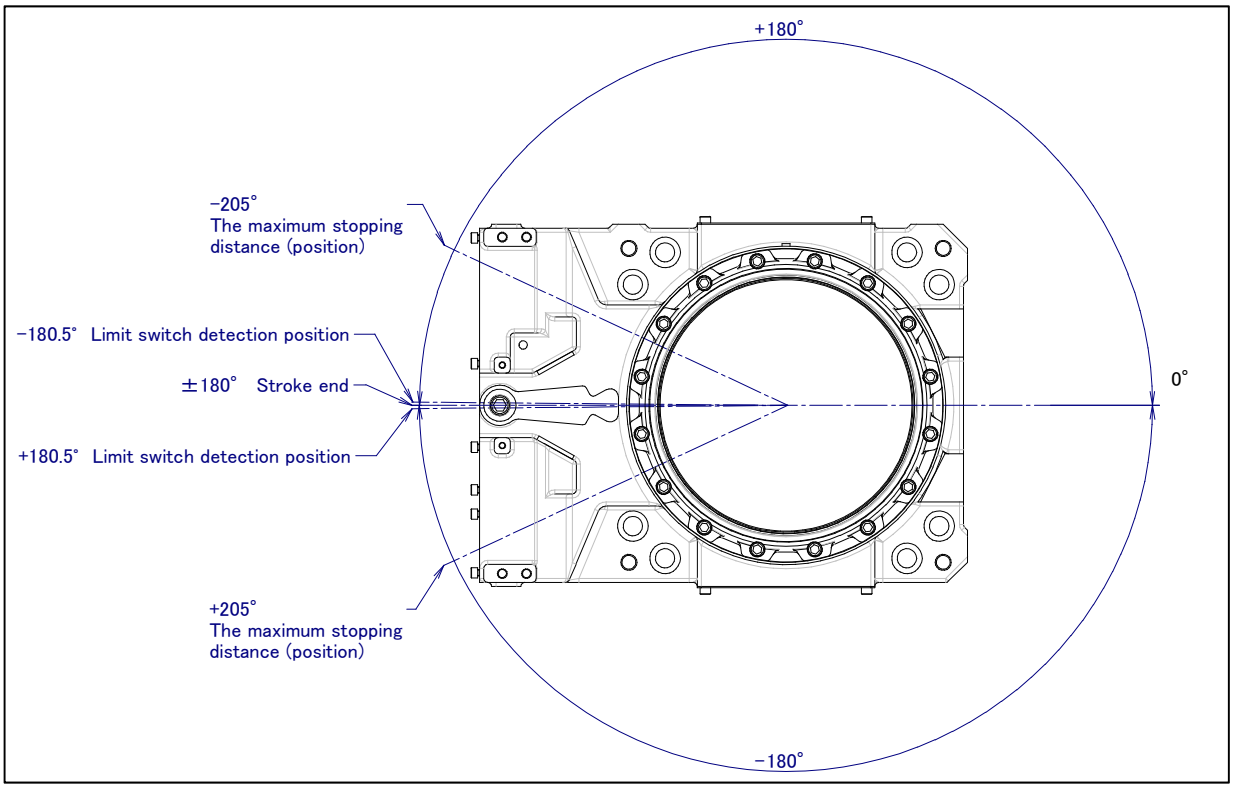


Fig. 3.3 (c) J1-axis motion limit

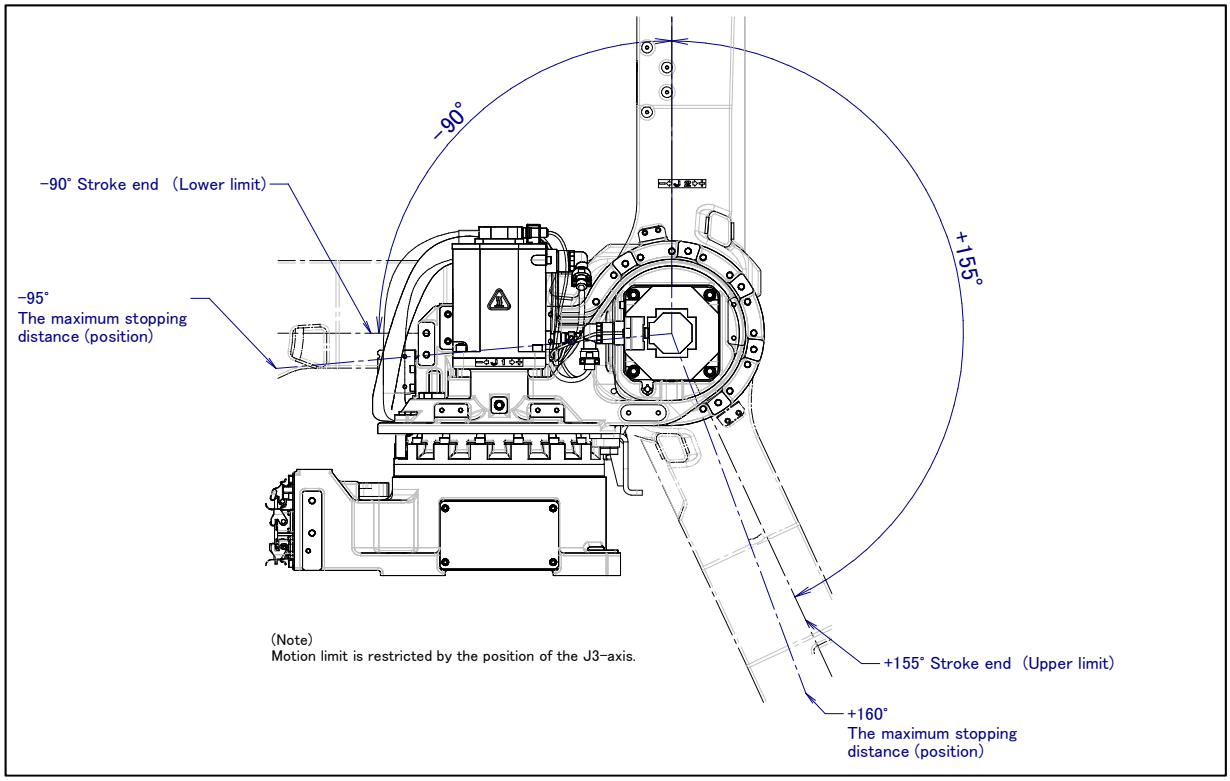


Fig. 3.3 (d) J2-axis motion limit (R-1000*i*A/80F/100F/130F/80H)

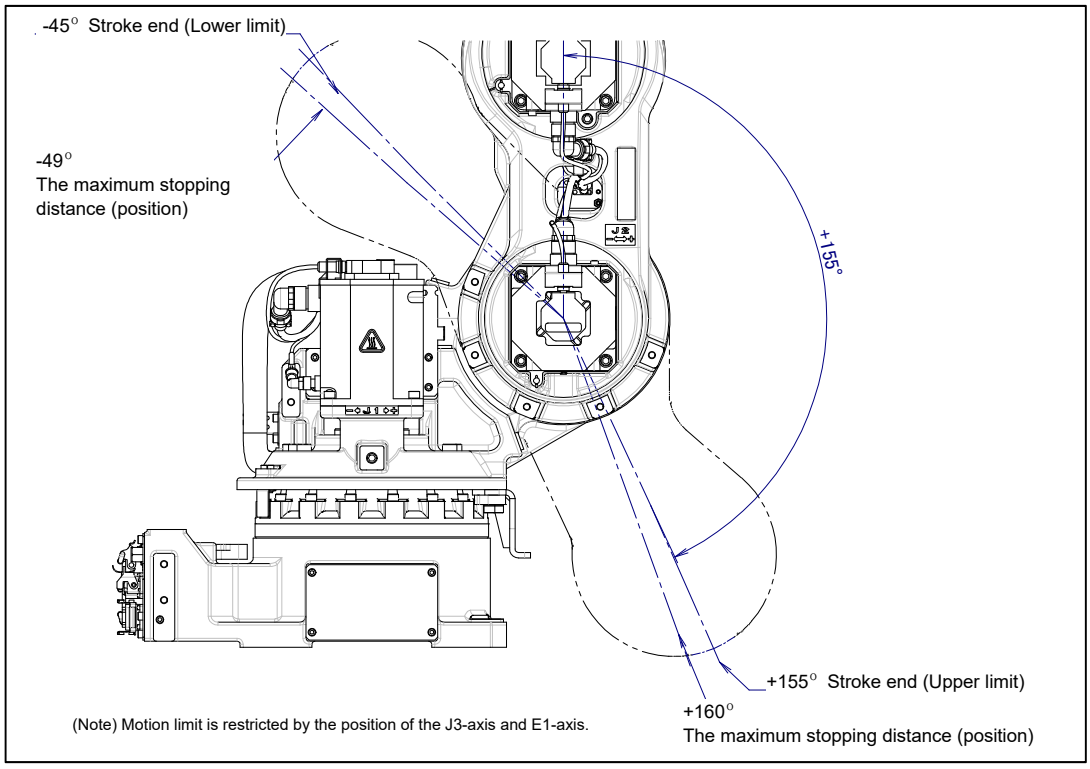


Fig. 3.3 (e) J2-axis motion limit (R-1000*i*A/120F-7B)

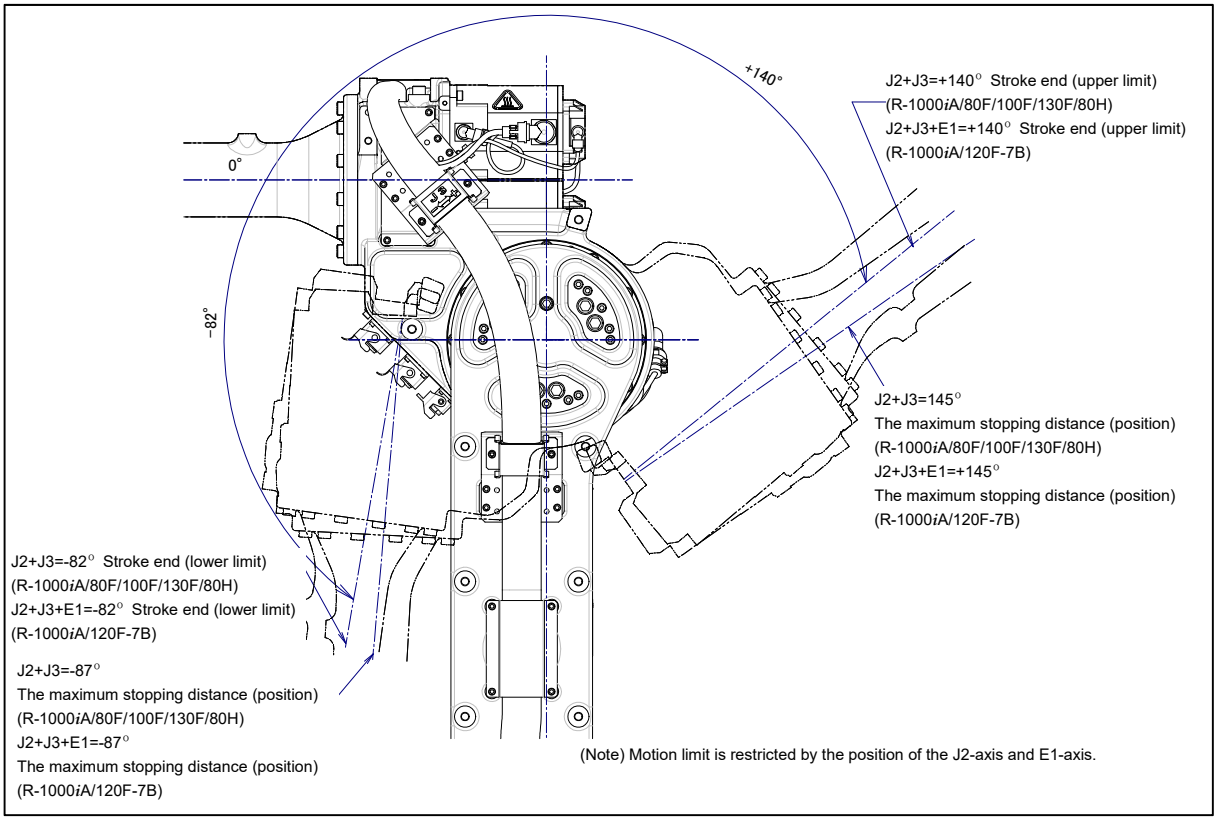


Fig. 3.3 (f) J3-axis motion limit

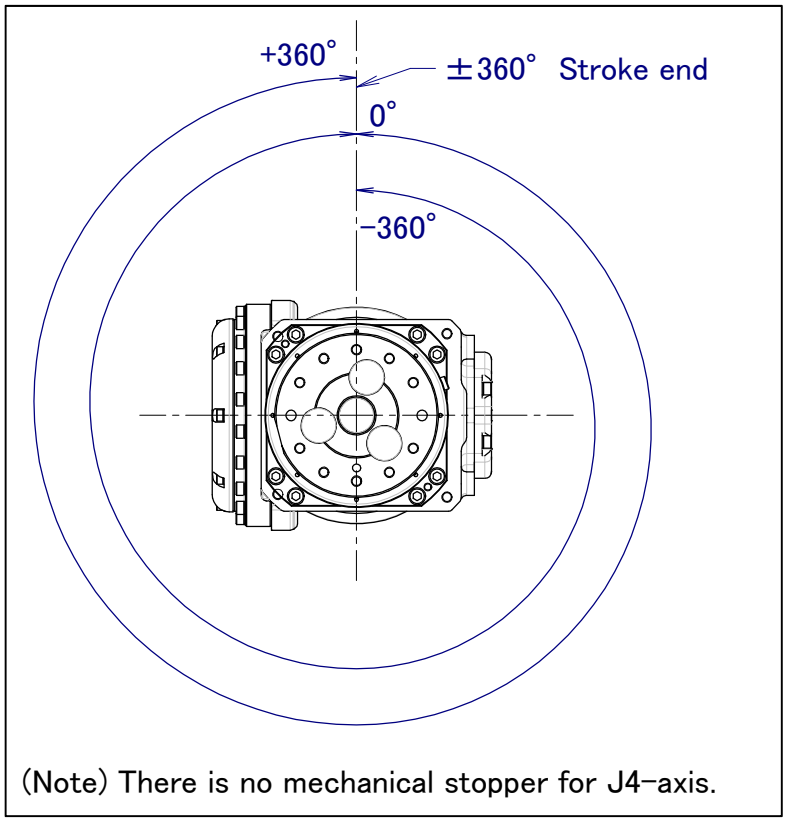


Fig. 3.3 (g) J4-axis motion limit
(R-1000*i*A/80F/100F/130F/120F-7B)

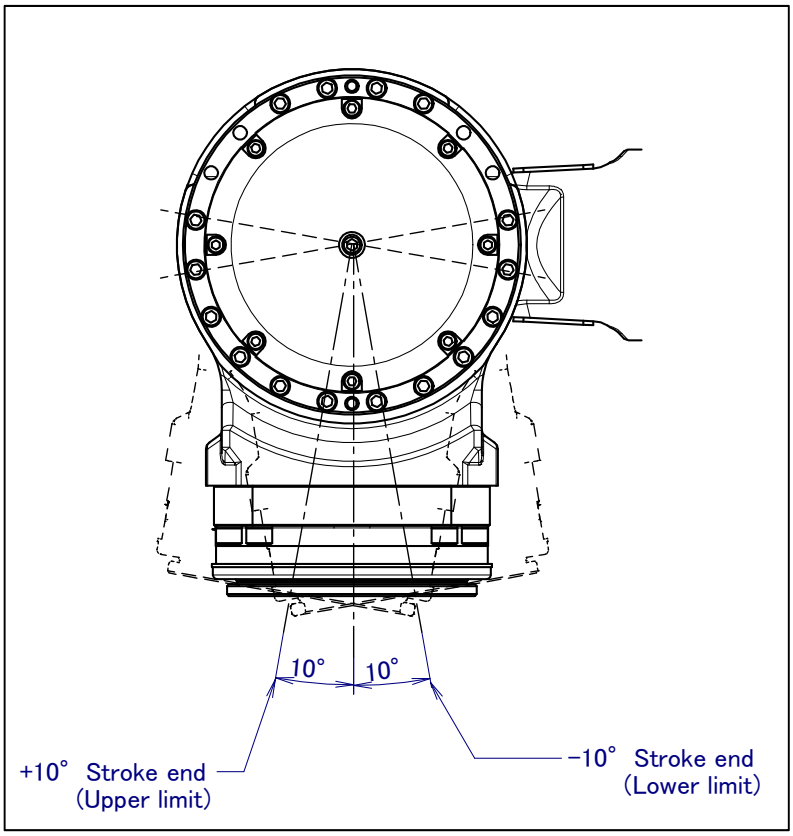


Fig. 3.3 (h) J4-axis motion limit (1)
(R-1000*i*A/80H)

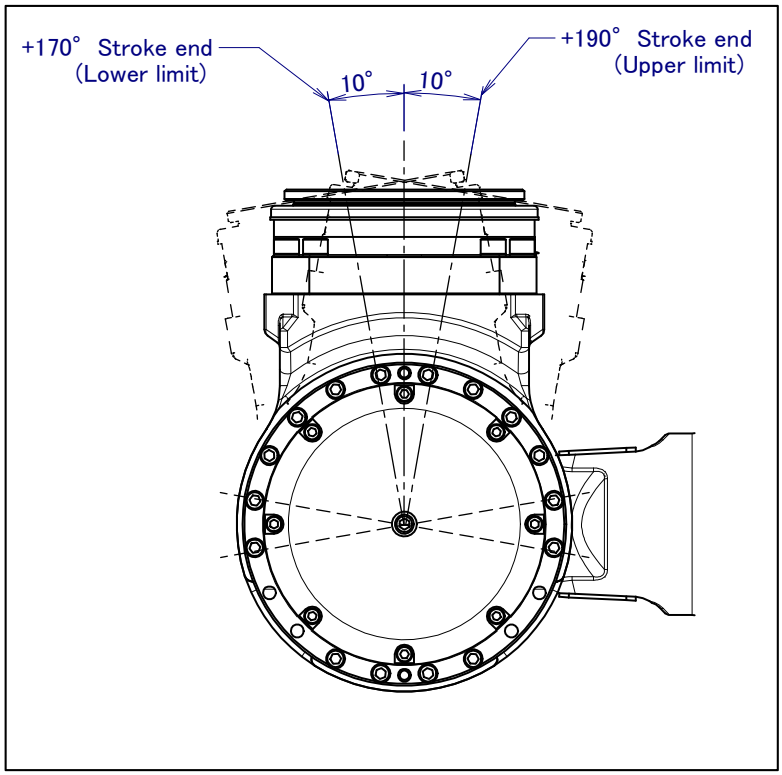


Fig. 3.3 (i) J4-axis motion limit (2)
(R-1000*i*A/80H)

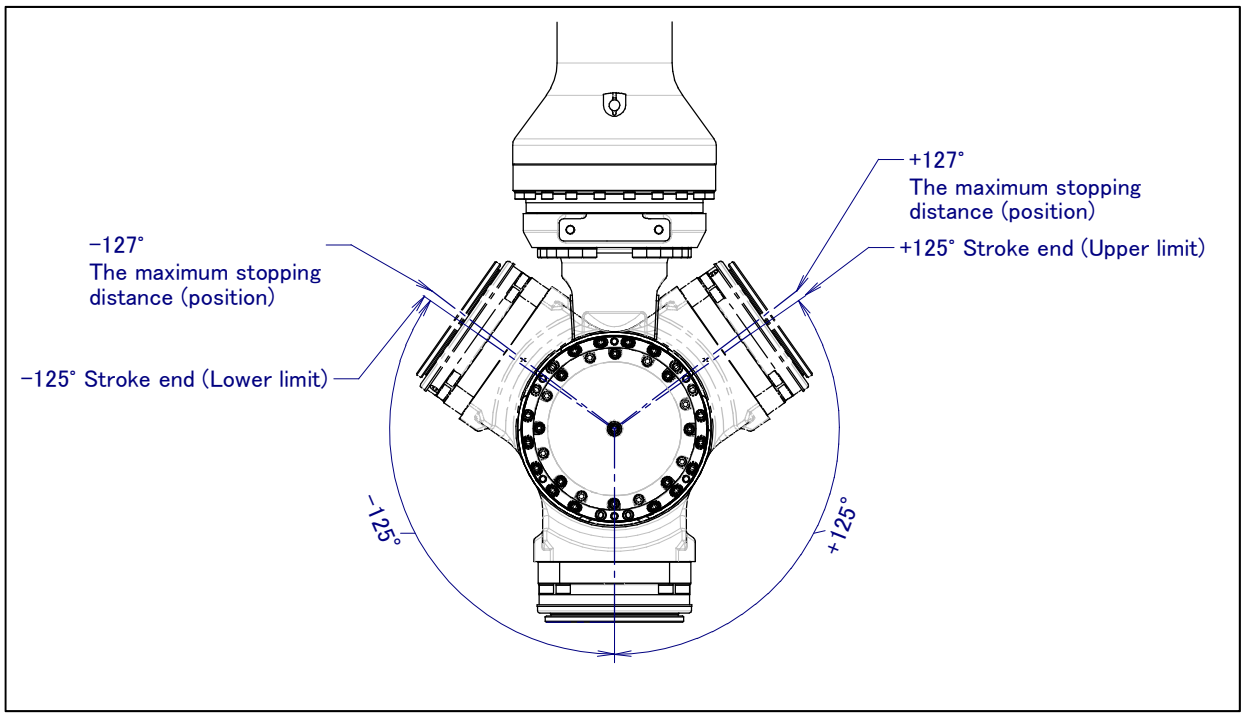


Fig. 3.3 (j) J5-axis motion limit (R-1000*i*A/80F/100F/130F/120F-7B)

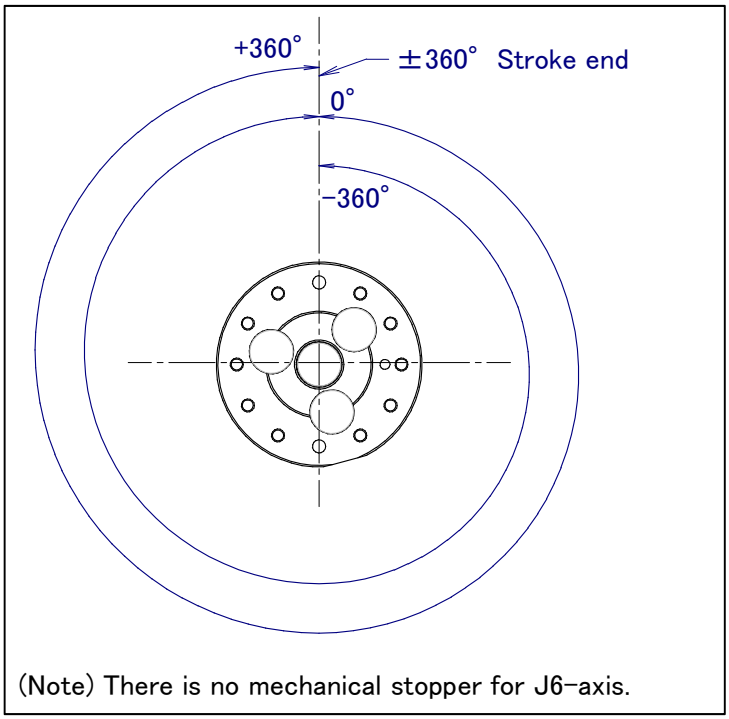


Fig. 3.3 (k) J6-axis motion limit (R-1000*i*A/80F/100F/130F/120F-7B)
J5-axis motion limit (R-1000*i*A/80H)

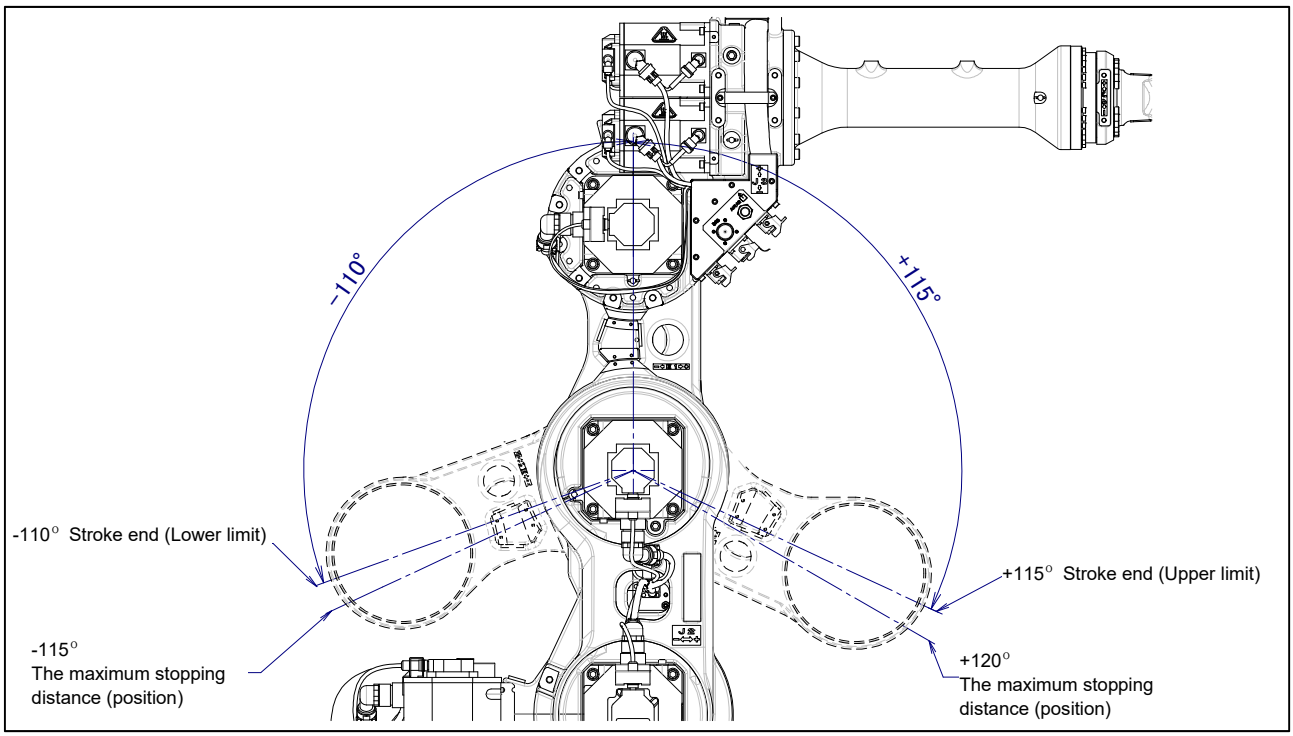


Fig. 3.3 (l) E1-axis motion limit (R-1000*i*A/120F-7B)

3.3.1 Change Method of J4-axis Motion Range (R-1000*i*A/80H)

R-1000*i*A/80H provides 2 different types of J4-axis motion range. Please refer to Fig. 3.3 (h) and (i).
All robots shipped from factory will have their J4-axis motion range set according to Fig. 3.3 (h).
Please perform following procedure in order to change the selected motion range type :

1 Press the [MENU] key, then press NEXT and select “SYSTEM”.
2 Press F1, [TYPE]. Select [Variables]. The system variable screen appears.
3 Select $MOR_GRP[n].$CAL_DONE, and change it from TRUE to FALSE.
4 Jog the J4-axis into the motion range of Fig. 3.3 (h), or of Fig. 3.3 (i).
CAUTION : at this time the robot does not check the interference of each axis. Therefore jog robot slowly and watch out for possible interference.
5 Select $MOR_GRP[n].$CAL_DONE, and change it back from FALSE to TRUE.

3.4 WRIST LOAD CONDITIONS

Fig. 3.4 (a) to (i) are diagrams to limit loads applied to the wrist.

- Apply a load within the region indicated in the graph.
- Apply the conditions of the allowable load moment and the allowable load inertia. See Section 3.1 about the allowable load moment and the allowable load inertia.
- See Section 4.1 about mounting of end effector.

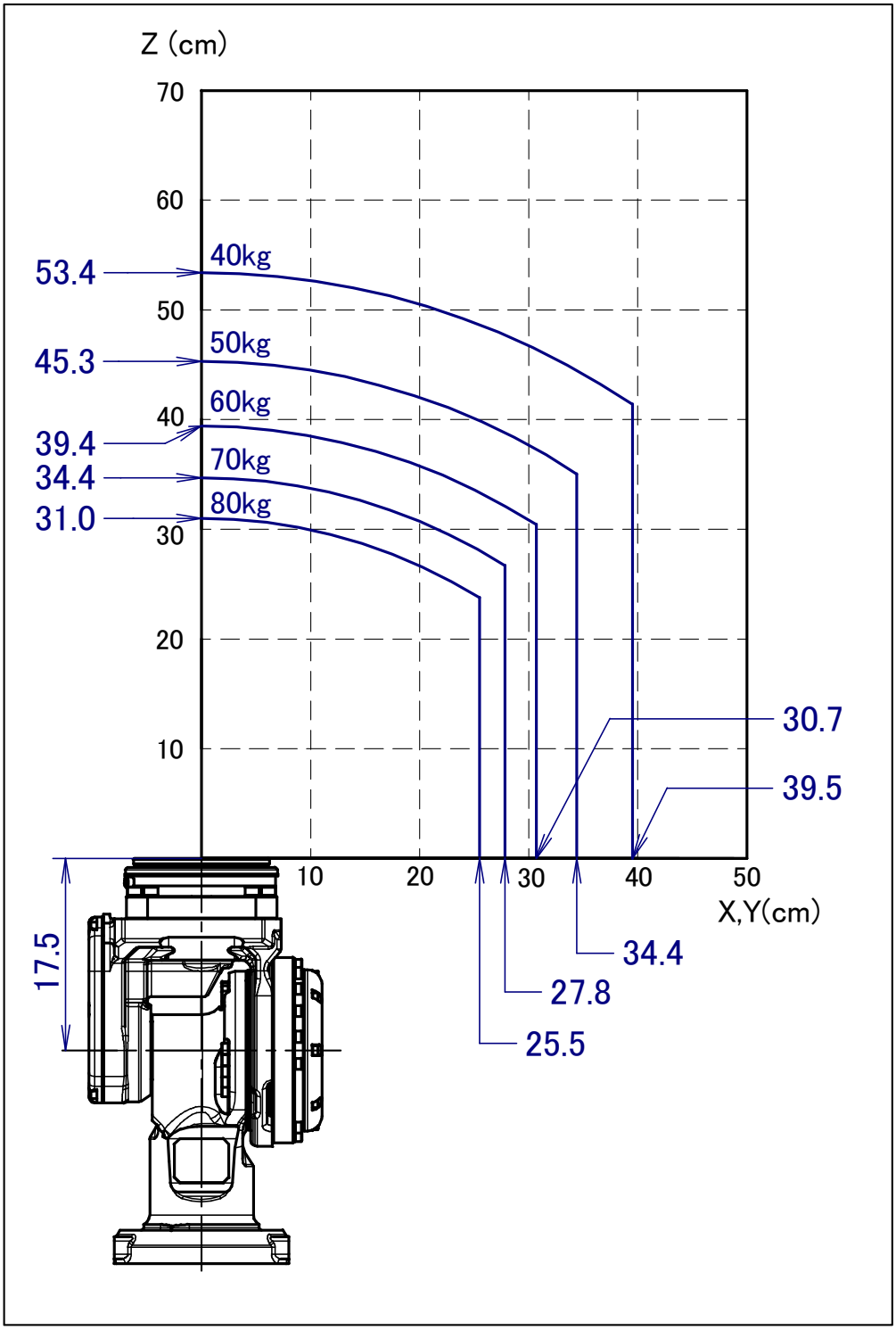


Fig. 3.4 (a) Wrist load diagram (ISO flange)
(R-1000*i*A/80F)

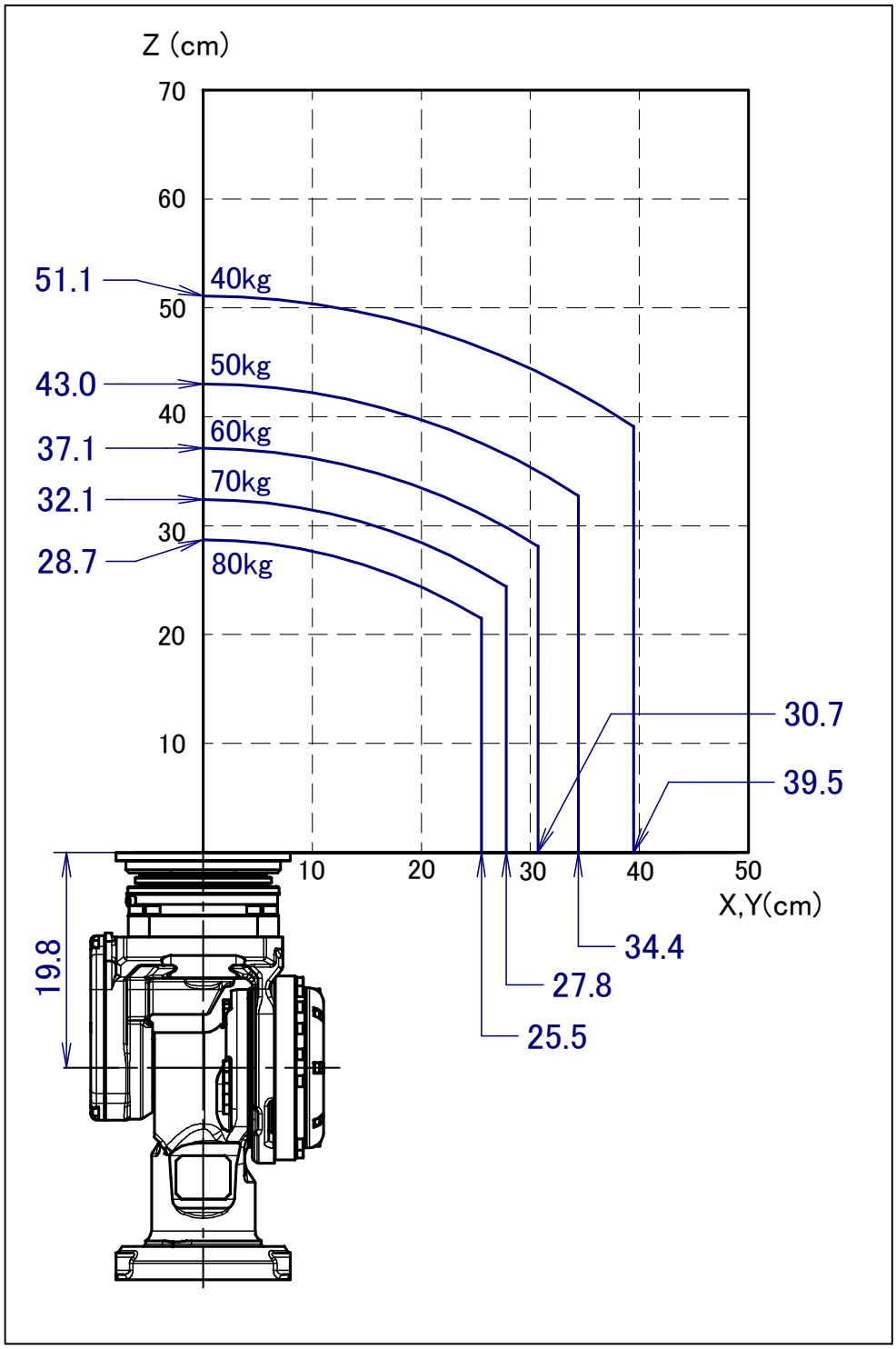


Fig. 3.4 (b) Wrist load diagram (Insulated ISO flange)
(R-1000*i*A/80F)

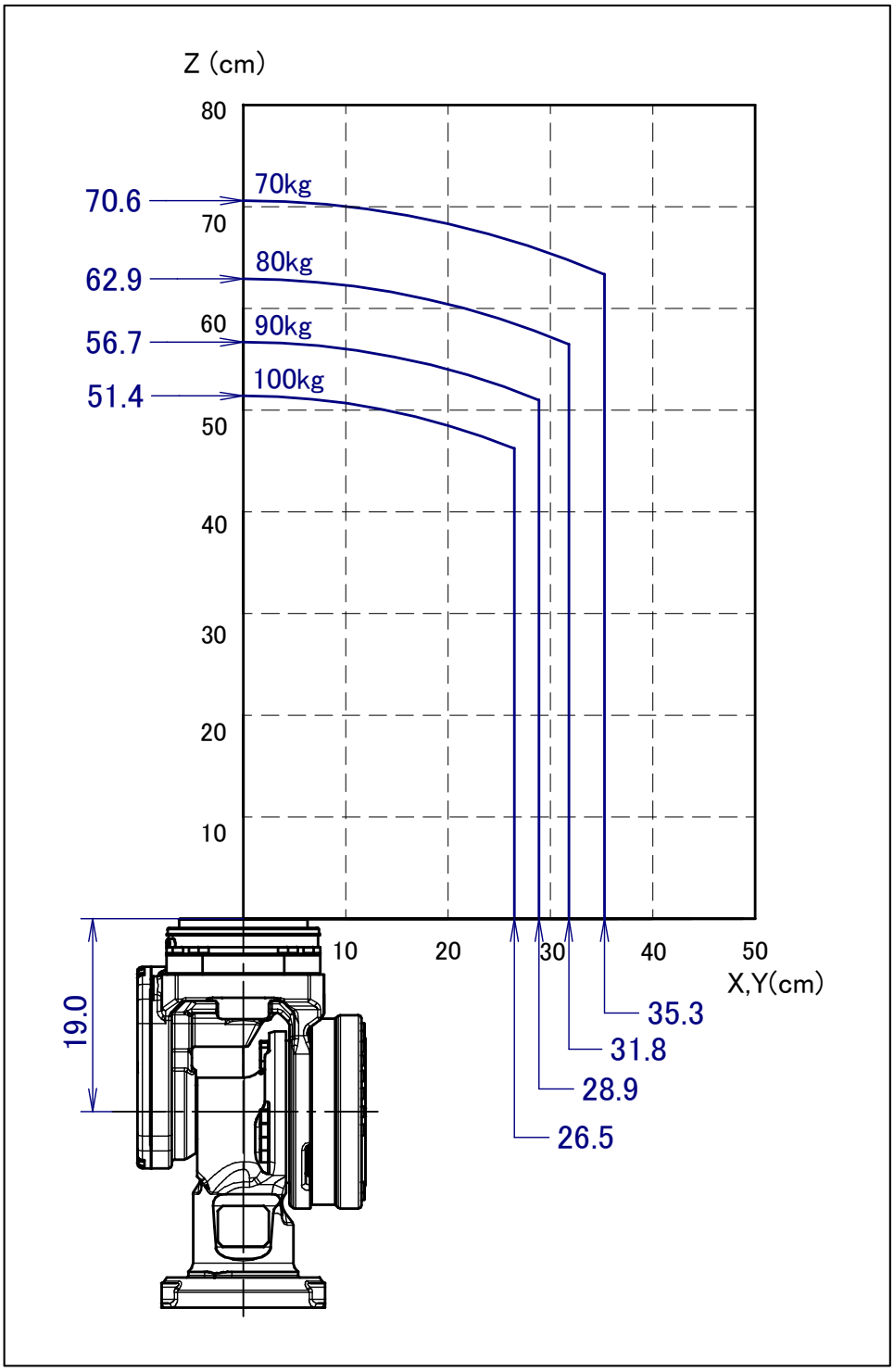


Fig. 3.4 (c) Wrist load diagram (ISO flange)
(R-1000*i*A/100F)

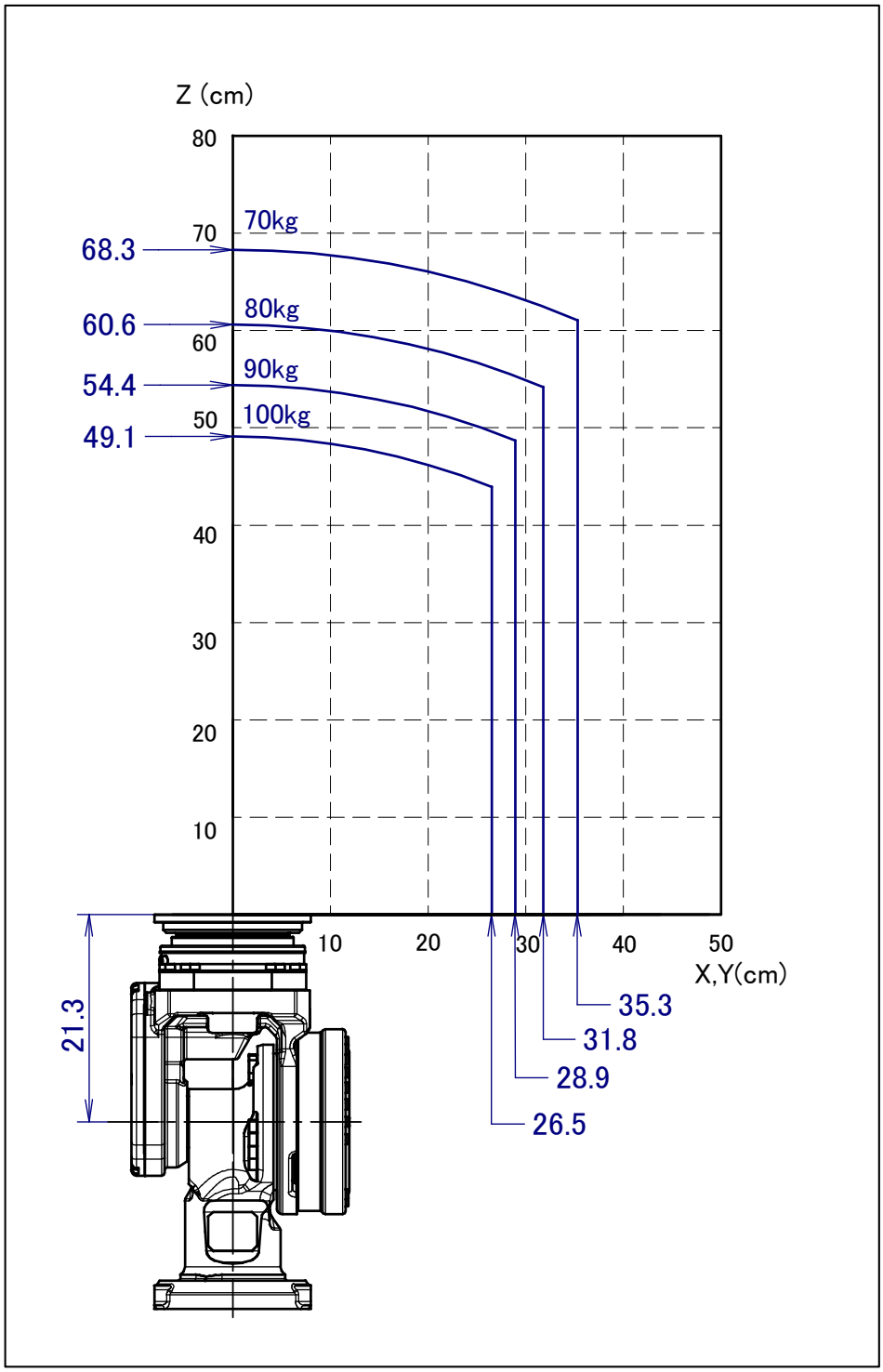


Fig. 3.4 (d) Wrist load diagram (Insulated ISO flange)
(R-1000*i*A/100F)

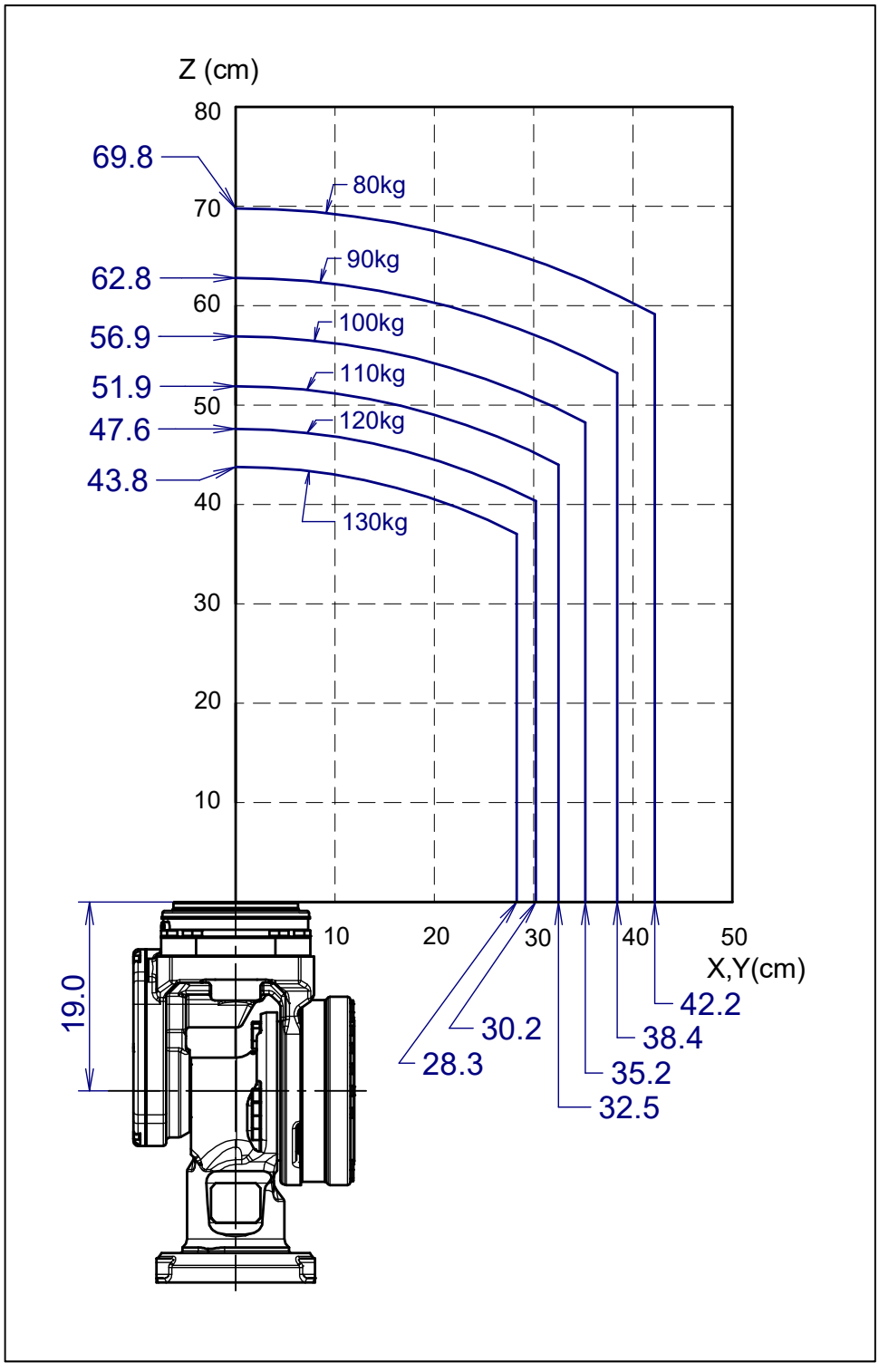


Fig. 3.4 (e) Wrist load diagram (ISO flange)
(R-1000*i*A/130F)

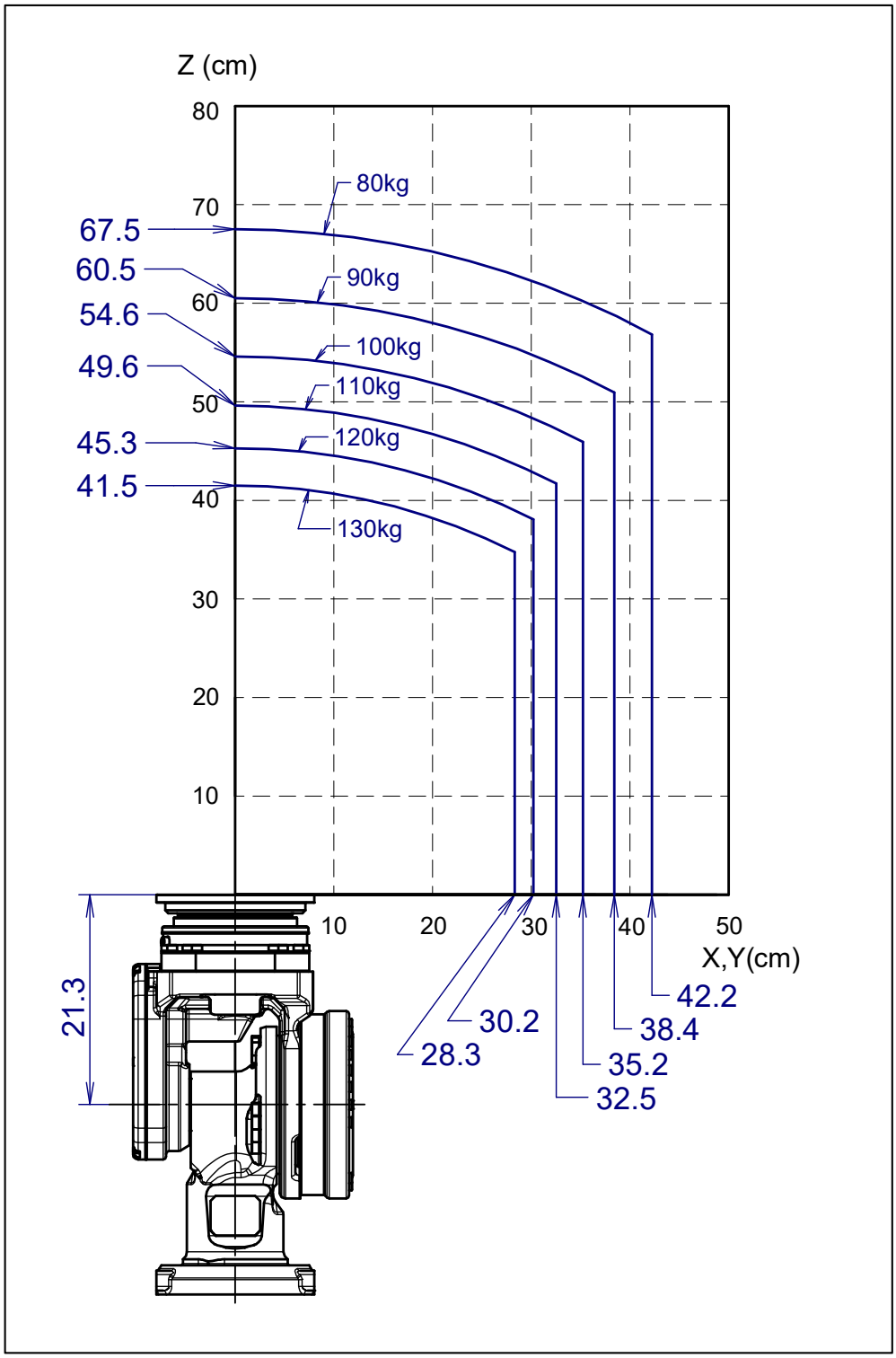


Fig. 3.4 (f) Wrist load diagram (Insulated ISO flange)
(R-1000*i*A/130F)

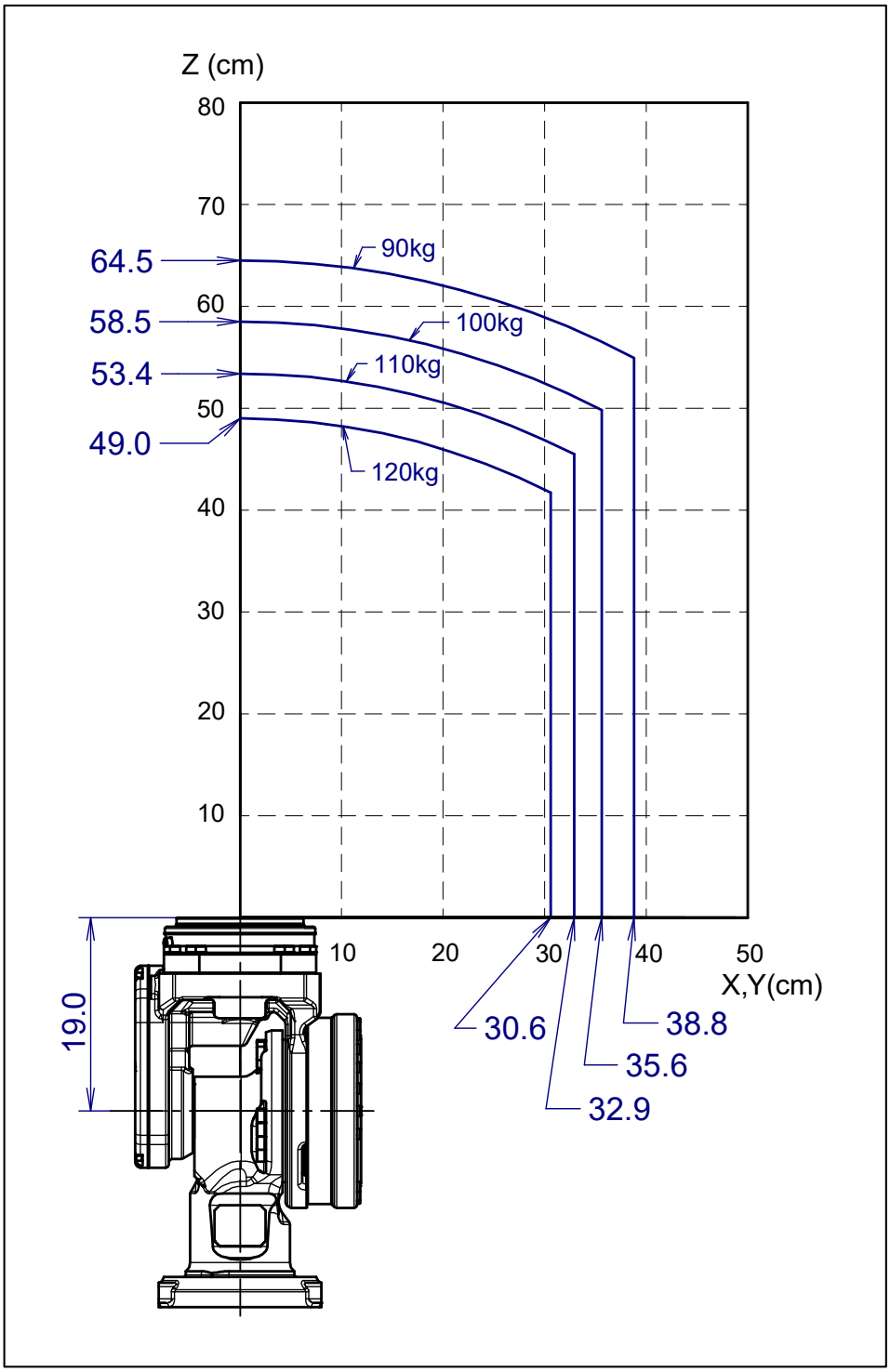


Fig. 3.4 (g) Wrist load diagram (ISO flange)
(R-1000*i*A/120F-7B)

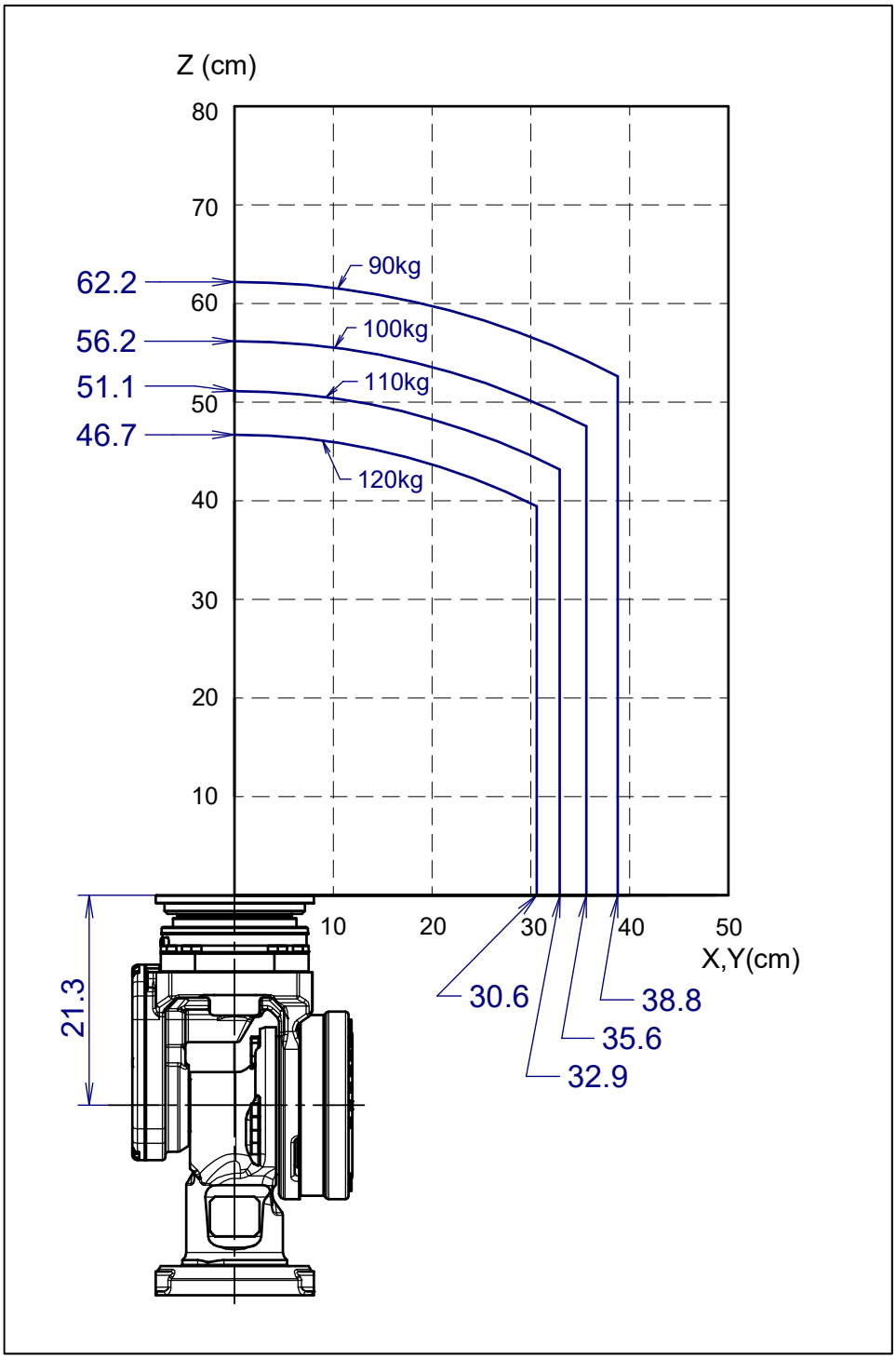


Fig. 3.4 (h) Wrist load diagram (Insulated ISO flange)
(R-1000*i*A/120F-7B)

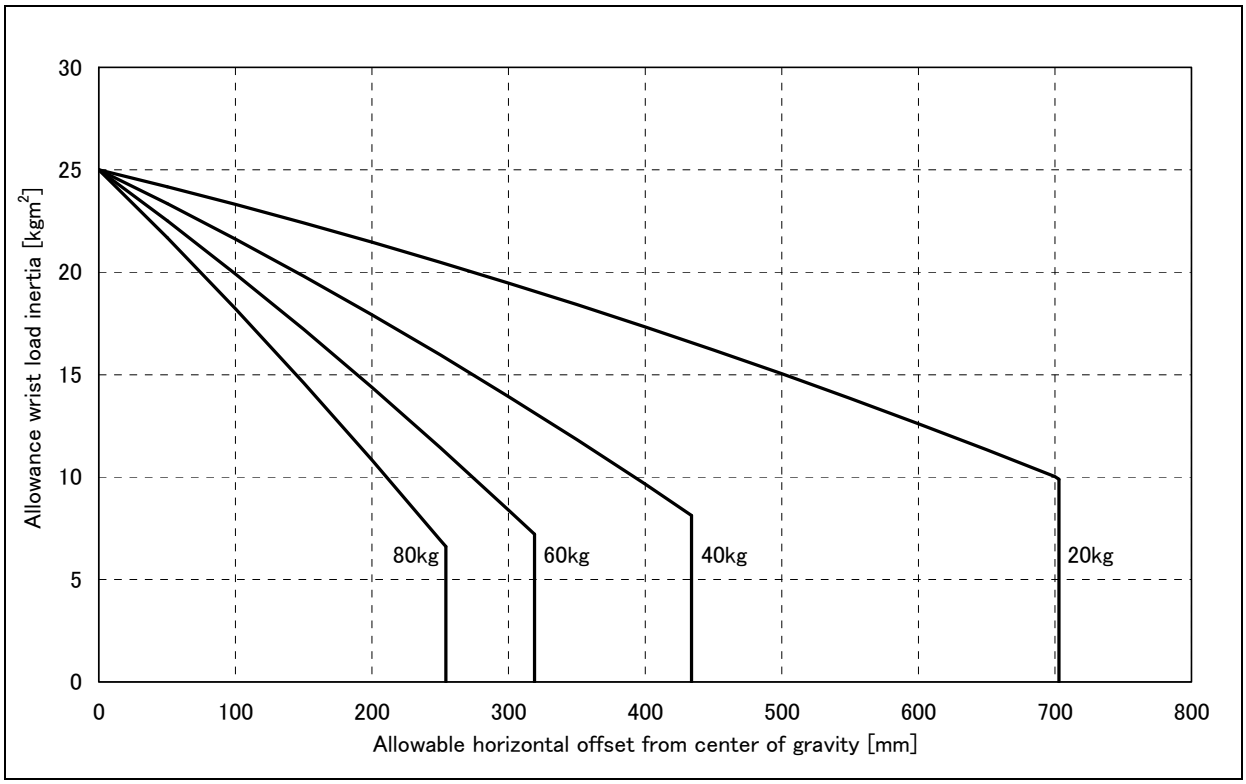


Fig. 3.4 (i) Wrist load diagram (R-1000*i*A/80H)

NOTE
Allowable vertical offset from the wrist flange is 400mm.

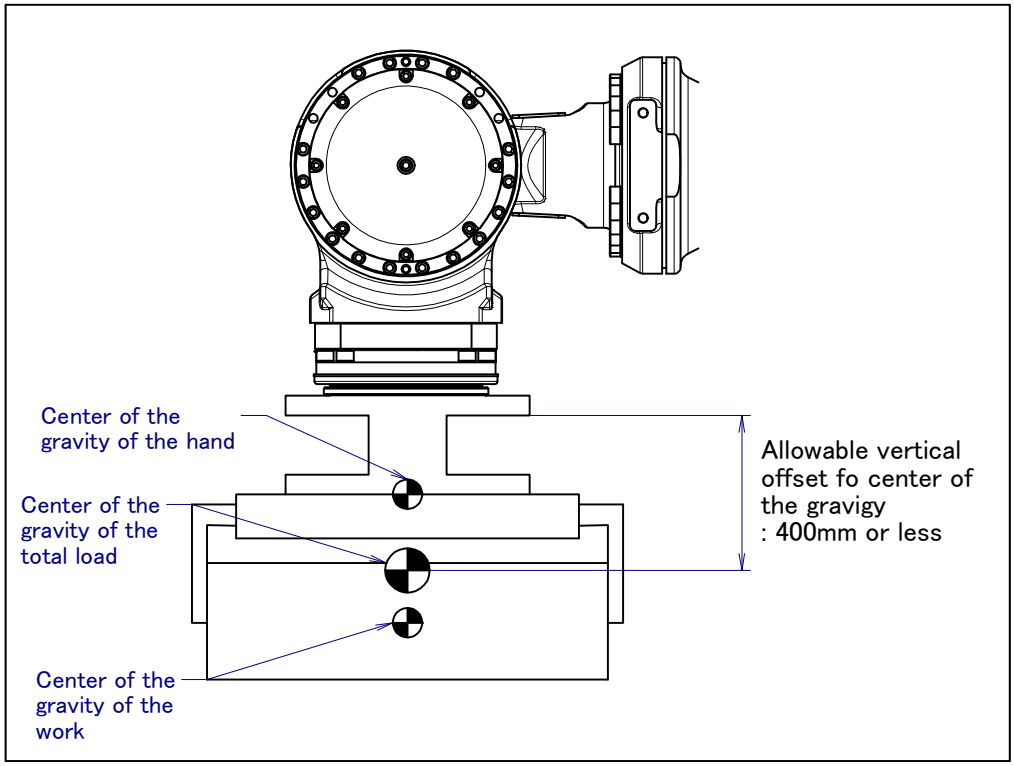


Fig. 3.4 (j) Allowable wrist load condition (R-1000*i*A/80H)

3.5 LOAD CONDITIONS

Fig. 3.5 (a) to (c) show J3 casing/J3 arm load condition.

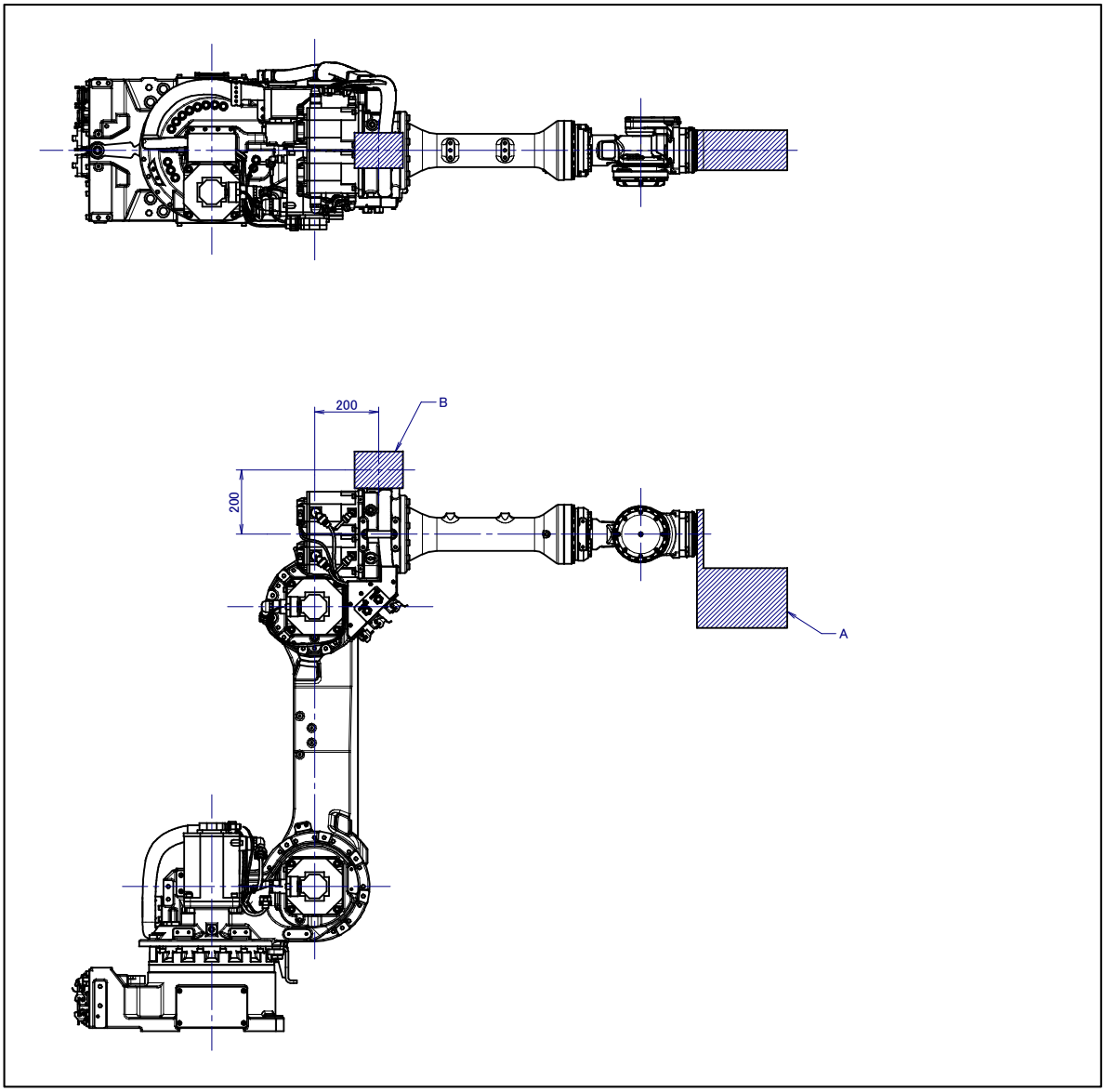


Fig. 3.5 (a) J3 casing load condition (R-1000*i*A/80F/80H)

Table 3.5 (a) J3 casing load condition (R-1000*i*A/80F/80H)

Wrist load weight A	J3 casing load weight B
80kg or less	15kg or less
A+B≦80kg	

⚠ CAUTION
You cannot bet load on J2 base and J3 arm.

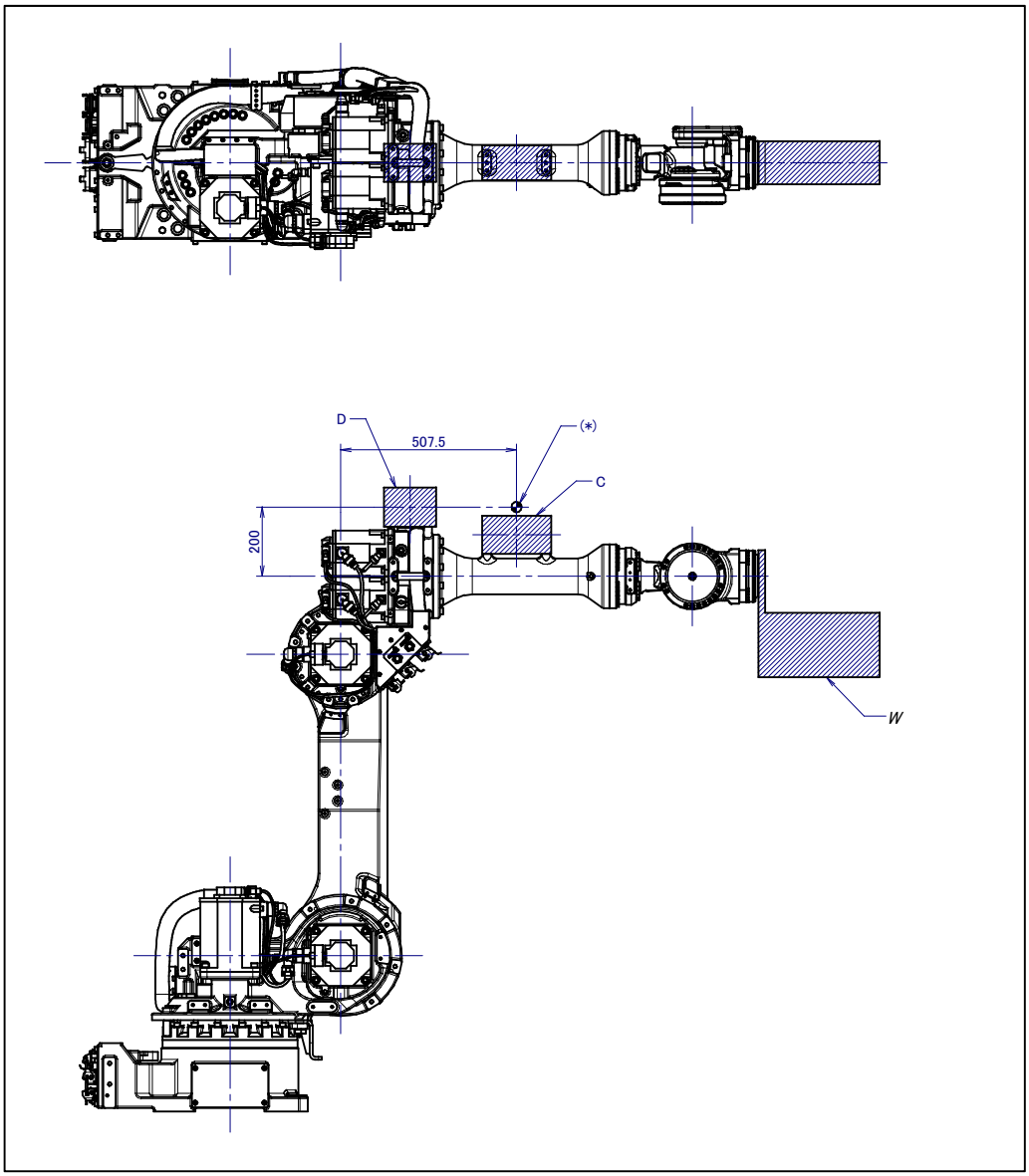


Fig. 3.5 (b) J3 casing/J3 arm load condition (R-1000*i*A/100F/130F)

Table 3.5 (b) J3 casing/J3 arm load condition (R-1000*i*A/100F)

Wrist load weight W	J3 arm load weight C + J3 casing load weight D
100kg or less	20kg or less

Table 3.5 (c) J3 casing/J3 arm load condition (R-1000*i*A/130F)

Wrist load weight W	J3 arm load weight C + J3 casing load weight D
130kg or less	20kg or less

(*) Center of gravity of total of load on J3 arm and load on J3 casing

⚠ CAUTION
You cannot bet load on J2 base.

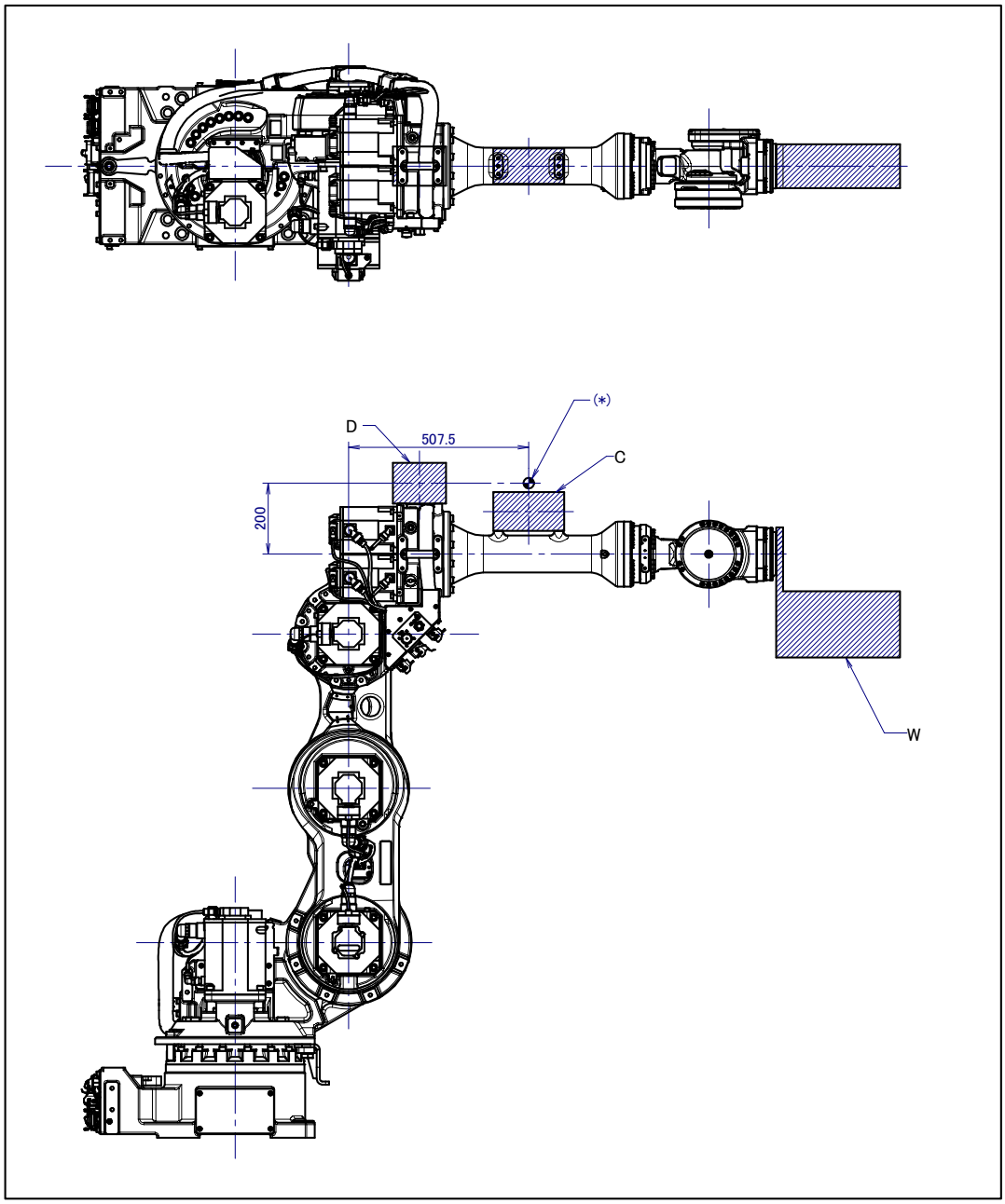


Fig. 3.5 (c) J3 casing/J3 arm load condition (R-1000*i*A/120F-7B)

Table 3.5 (d) J3 casing/J3 arm load condition (R-1000*i*A/120F-7B)

Wrist load weight W	J3 arm load weight C + J3 casing load weight D
120kg or less	20kg or less

(*) Center of gravity of total of load on J3 arm and load on J3 casing

> ⚠ **CAUTION**
> You cannot bet load on J2 base.

4 EQUIPMENT INSTALLATION TO THE ROBOT

4.1 END EFFECTOR INSTALLATION TO WRIST

Fig. 4.1 (a) to (c) show the figures for installing end effectors on the wrist. Select screws and positioning pins of a length that matches the depth of the tapped holes and pin holes.
Then Use 10 M8 bolts or 6 M10 bolts for end effector and tighten them with the torque below.

M8: 37.2±1.86Nm (380±19kgfcm)
M10: 73.5±3.4Nm (750±35kgfcm)

> ⚠ **CAUTION**
> Notice the tooling coupling depth to wrist flange should be shorter than the flange coupling length.

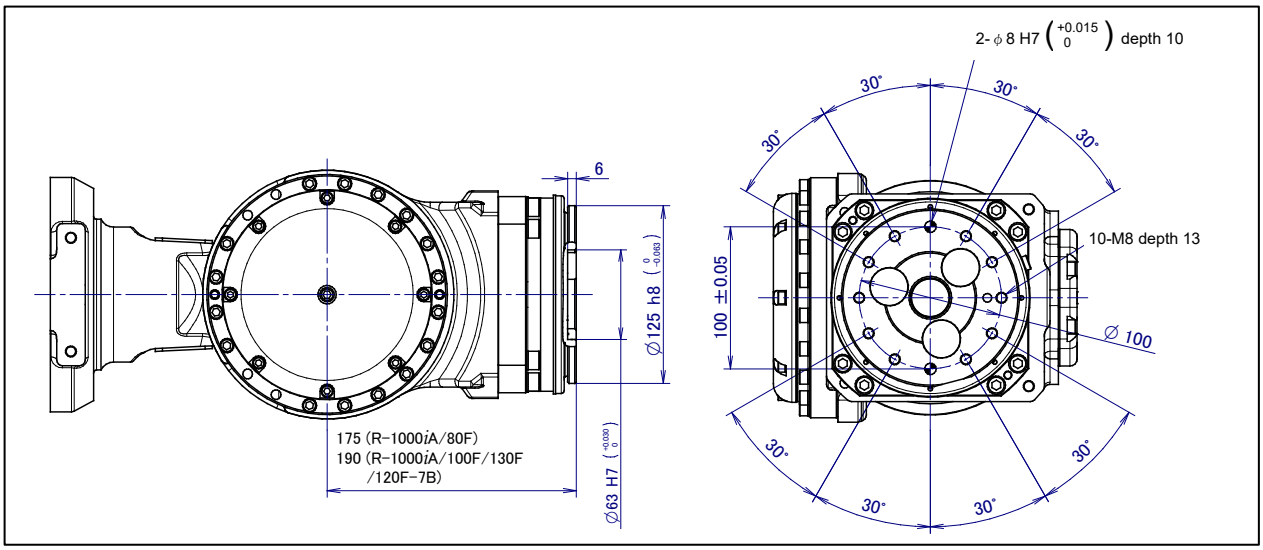


Fig. 4.1 (a) End effector interface (ISO flange) (R-1000*i*A/80F/100F/130F/120F-7B)

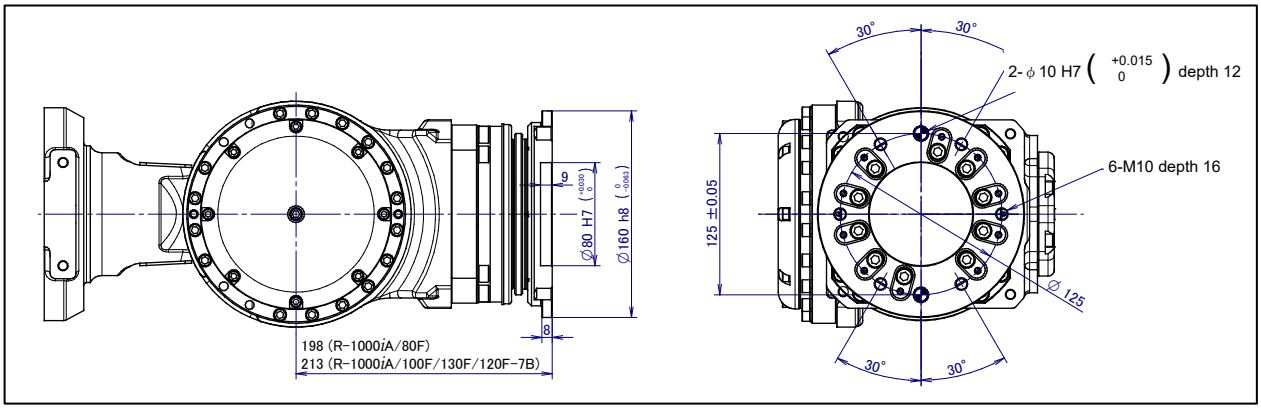


Fig. 4.1 (b) End effector interface (Insulated ISO flange) (R-1000*i*A/80F/100F/130F/120F-7B)

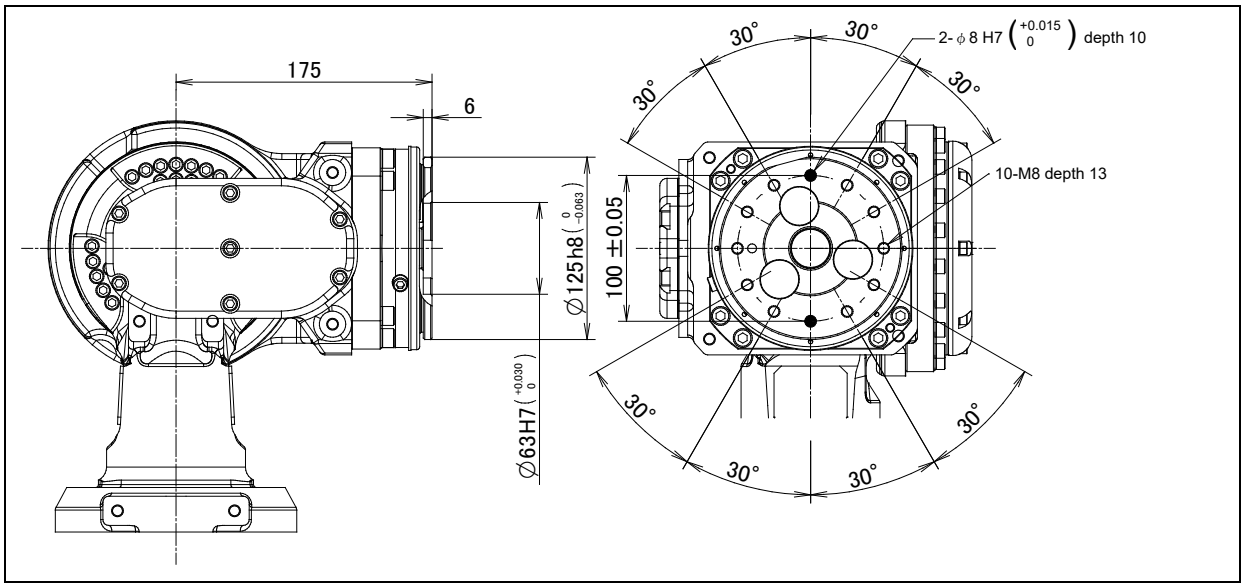


Fig. 4.1 (c) End effector interface (R-1000*i*A/80H)

4.2 EQUIPMENT MOUNTING FACE

As shown in Fig. 4.2 (a), (b), tapped holes are provided to install equipment to the robot.

> ⚠ **CAUTION**
> 1 Never perform additional machining operations such as drilling or tapping on the robot body. This can seriously affect the safety and functions of the robot.
> 2 Note that the use of a tapped hole not shown in the following figure is not assured. Please do not tighten both with the tightening bolts used for mechanical unit.
> 3 Equipment should be installed so that mechanical unit cable does not interfere. If equipment interfere, the mechanical unit cable might be disconnected, and unexpected troubles might occur.

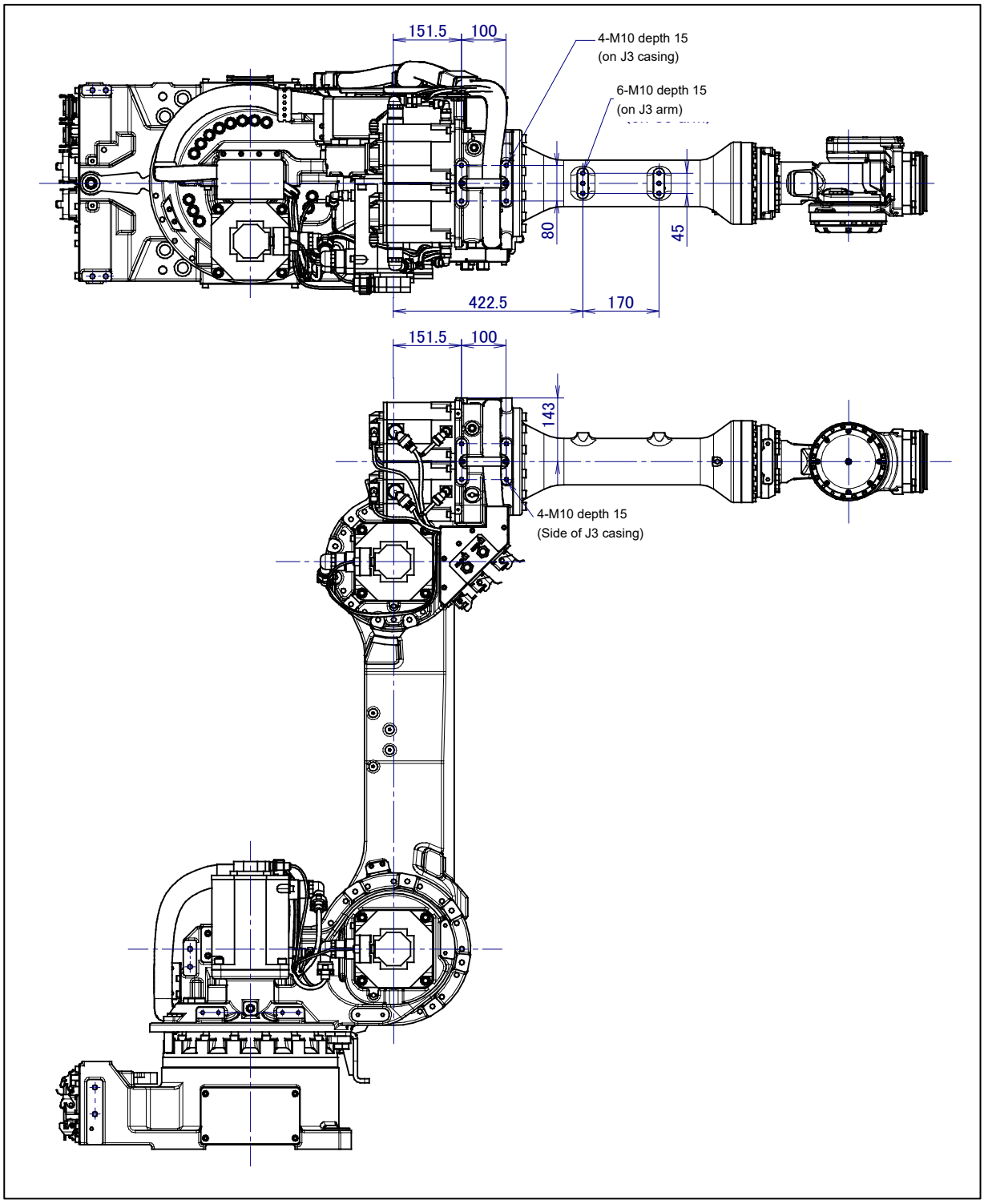


Fig. 4.2 (a) Equipment mounting faces (R-1000*i*A/80F/100F/130F/80H)

> ⚠ **CAUTION**
> In case of R-1000*i*A/80F/80H, when it is necessary to hang the J3 arm with a sling, you can use tap on J3 arm for mounting of eyebolts.

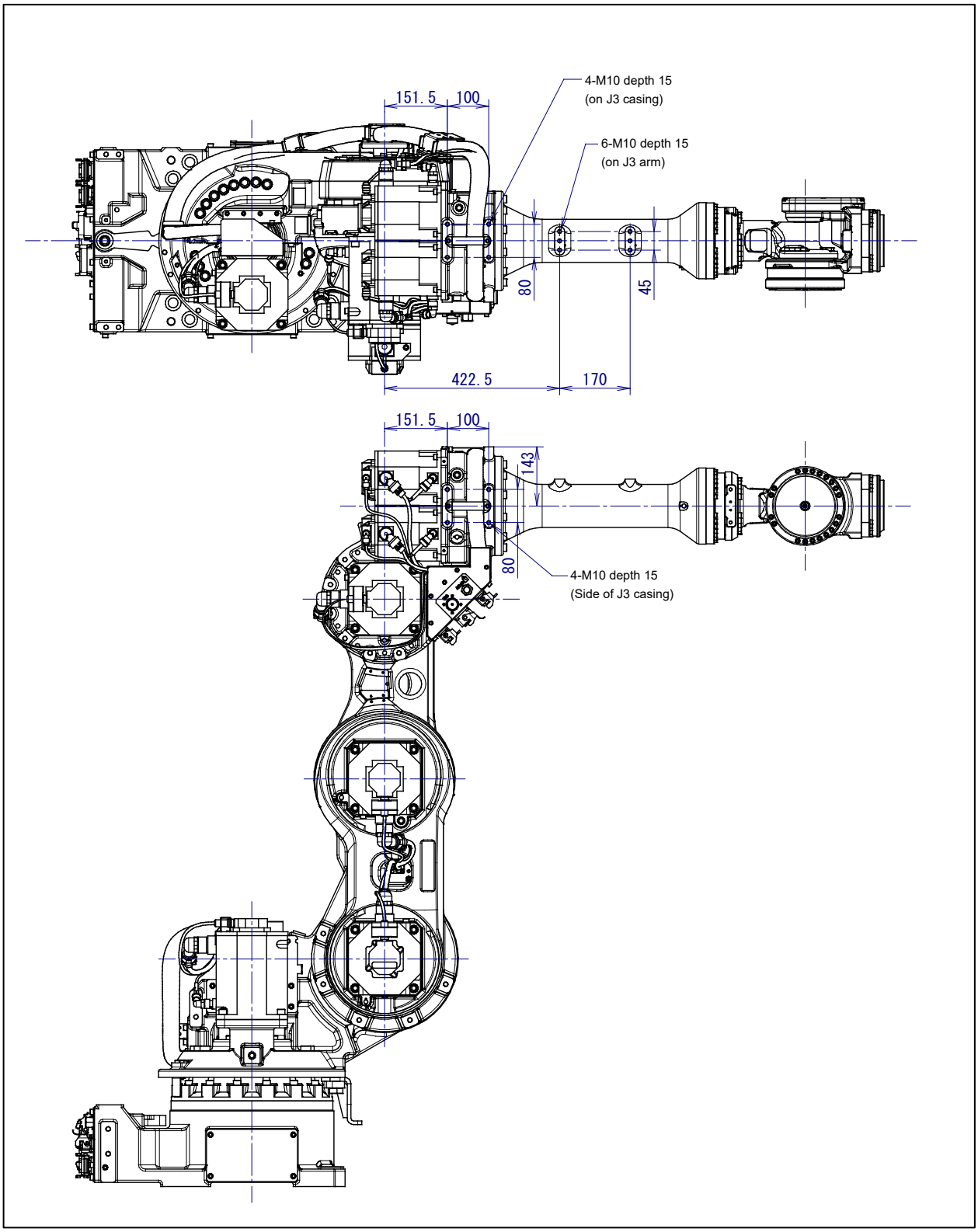


Fig. 4.2 (b) Equipment mounting faces (R-1000*i*A/120F-7B)

4.3 LOAD SETTING

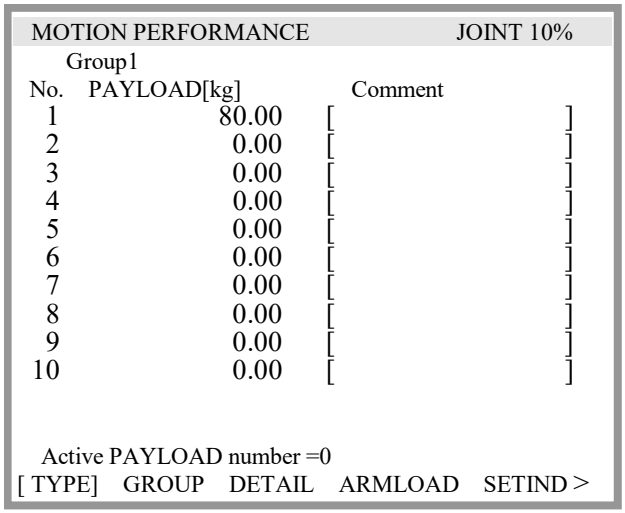
⚠ CAUTION

1 Set the correct load condition parameter before the robot runs. Do not operate the robot in over when its payload is exceeded or incorrect. Do not exceed the allowable payload including connection cables. Operation in with the robot over payload may result in troubles such as reducer life reduction.

2 WHEN PERFORMING LOAD ESTIMATION AFTER PARTS REPLACEMENT
If wrist axis motors (J5/J6-axis) or reducers are replaced, payload estimation accuracy may decrease. Perform calibration of load estimation without the load such as hand before performing load estimation.
(R-1000*i*A/80H does not support load estimation option.)
Section 9.15 “LOAD ESTIMATION” in R-30*i*A Controller
Spot tool+ OPERATOR’S MANUAL (B-83124EN-1).
Section 9.15 “LOAD ESTIMATION” in R-30*i*A Controller
Handling tool OPERATOR’S MANUAL (B-83124EN-2).
Section 9.15 “LOAD ESTIMATION” in R-30*i*A Controller
Dispense tool OPERATOR’S MANUAL (B-83124EN-3).
Chapter 9 “LOAD ESTIMATION” in R-30*i*B/R-30*i*B Mate/R-30*i*B Plus /R-30*i*B Mate Plus/R-30*i*B Compact Plus/R-30*i*B Mini Plus Controller Optional Function OPERATOR’S MANUAL (B-83284EN-2).

The operation motion performance screens include the MOTION PERFORMANCE screen, MOTION PAYLOAD SET screen, and payload information and equipment information on the robot.

1 Press the [MENU] key to display the screen menu.
2 Select [6 SYSTEM] on the next page.
3 Press the F1 ([TYPE]) to bring up the screen menu.
4 Select “Motion” The MOTION PERFORMANCE screen will be displayed.



5 Ten different pieces of payload information can be set using condition No.1 to No.10 on this screen. Place the cursor on one of the numbers, and press F3 (DETAIL). The MOTION PAYLOAD SET screen will be displayed.

```
MOTION PAYLOAD SET          JOINT   100%

   Group 1
 1 Schedule No[         1]:[Comment          ]
 2 PAYLOAD                 [kg]          80.00
 3 PAYLOAD CENTER  X [cm]                -23.33
 4 PAYLOAD CENTER  Y [cm]                 0.00
 5 PAYLOAD CENTER  Z [cm]                23.70
 6 PAYLOAD INERTIA X [kgfcms^2]          56.84
 7 PAYLOAD INERTIA Y [kgfcms^2]          59.39
 8 PAYLOAD INERTIA Z [kgfcms^2]          15.10

 [TYPE] GROUP NUMBER    DEFAULT    HELP
```

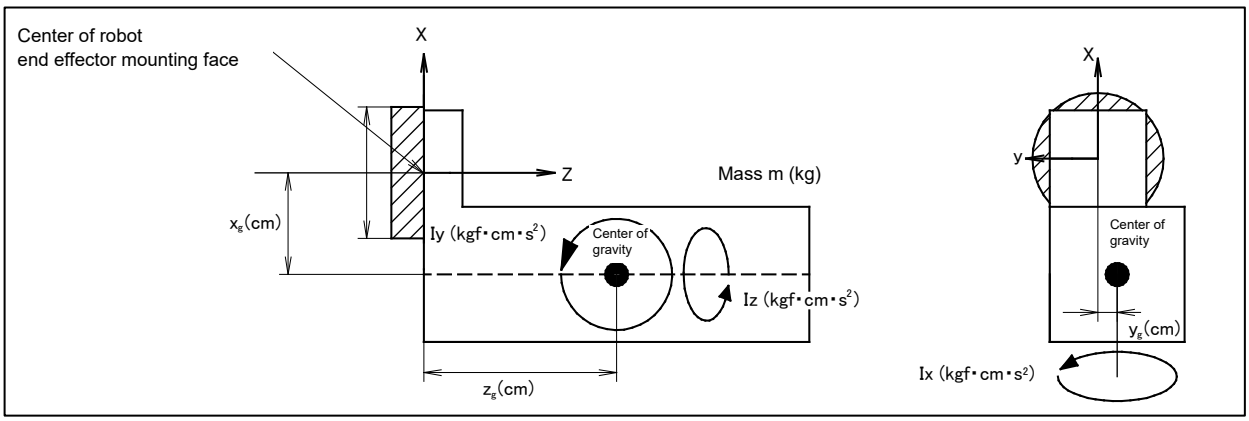


Fig. 4.3 (a) Standard tool coordinate

6 Set the payload, gravity center position, and inertia around the gravity center on the MOTION PAYLOAD SET screen. The X, Y, and Z directions displayed on this screen correspond to the respective standard tool coordinates (with no tool coordinate system set up). When values are entered, the following message appears: “Path and Cycle time will change. Set it?” Respond to the message with F4 ([YES]) or F5 ([NO]).

7 Press F3 ([NUMBER]) will bring you to the MOTION PAYLOAD SET screen for another condition number. For a multigroup system, pressing F2 ([GROUP]) will bring you to the MOTION PAYLOAD SET screen for another group

8 Press the [PREV] key to return to the MOTION PERFORMANCE screen. Press F5 ([SETIND]), and enter the desired payload setting condition number.

9 On the list screen, pressing F4 ARMLOAD brings you to the device-setting screen.

```
MOTION ARMLOAD SET          JOINT   100%

   Group 1
 1 ARM LOAD AXIS #1 [kg]                 0.00
 2 ARM LOAD AXIS #3 [kg]                15.00

[  TYPE  ]     GROUP          DEFAULT   HELP
```

10 Specify the weight of the load on the J2 base and J3 arm/J3 casing as follows:
ARMLOAD AXIS #1[kg]: Weight of the load on the J2 base (No armload #1 is allowed for the R-1000***i***A.)
ARMLOAD AXIS #3[kg]: Weight of the load on the J3 casing/J3 arm (No armload is allowed for the J3 arm of R-1000***i***A/80F/80H.)
The following message appears: “Path and Cycletime will change. Set it?” Select F4 ([YES]) or F5 ([NO]). Once the arm payload is set up, the settings are completed by switching the power off and on again.

5 PIPING AND WIRING TO THE END EFFECTOR

⚠ WARNING

- Only use appropriately-specified mechanical unit cables.
- Do not add user cables or hoses inside of the mechanical unit.
- Please do not obstruct the movement of the mechanical unit when cables are added to outside of mechanical unit.
- Please do not perform remodeling (adding a protective cover, or secure an additional outside cable) that obstructs the behavior of the outcrop of the cable.
- When external equipment is installed in the robot, make sure that it does not interfere with other parts of the robot.
- Cut and discard any unnecessary length of wire strand of the end effector (hand) cable. Insulate the cable with seal tape. (See Fig. 5 (a))
- If you have end effector wiring and a process that develops static electricity, keep the end effector wiring as far away from the process as possible. If the end effector and process must remain close, be sure to insulate the cable.
- Be sure to seal the connectors of the user cable and terminal parts of all cables to prevent water from entering the mechanical unit. Also, attach the cover to the unused connector.
- Frequently check that connectors are tight and cable jackets are not damaged.
- When precautions are not followed, damage to cables might occur. Cable failure may result in incorrect function of end effector, robot faults, or damage to robot electrical hardware. In addition, electric shock could occur when touching the power cables.

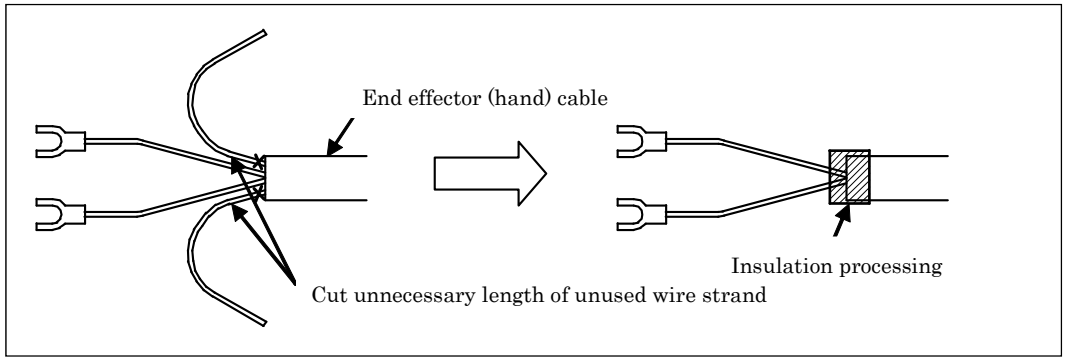


Fig. 5 (a) Treatment method of end effector (hand) cable

5.1 AIR SUPPLY (OPTION)

Robot has air inlet and air outlet openings on the back of the J1 base and the side of the J3 casing used to supply air pressure to the end effector. The connector is an Rc1/2 female (ISO). Because coupling is not supplied, it will be necessary to prepare couplings, which suit to the hose size.

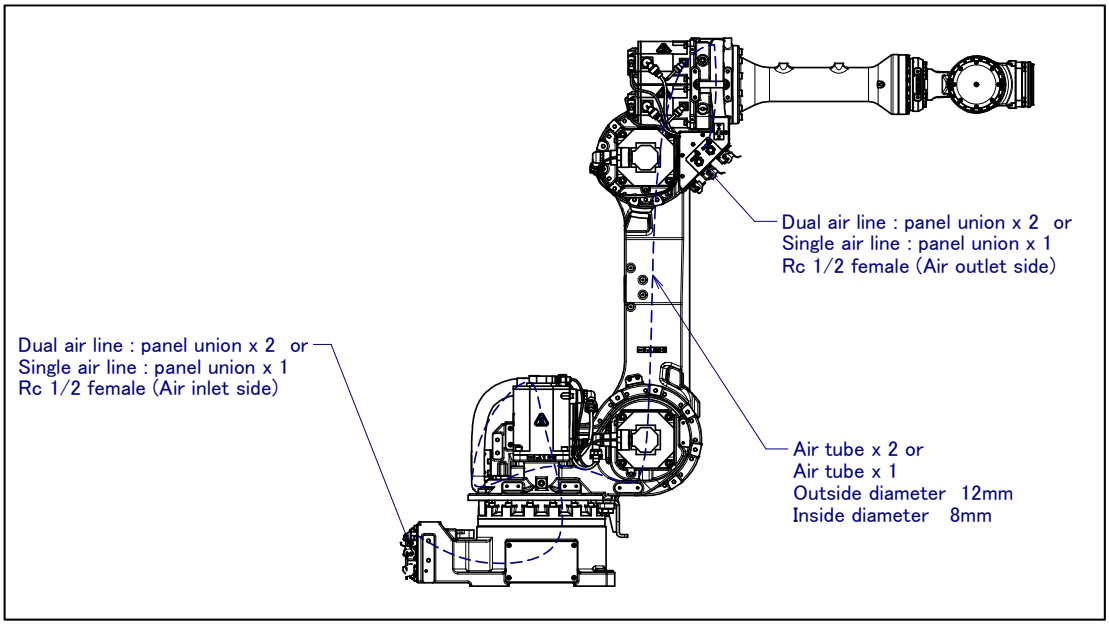


Fig. 5.1 (a) Air supply (option)

5.2 AIR PIPING (OPTION)

Fig. 5.2 (a) shows how to connect air hose to the robot. If the air control set is specified as an option, the air hose between the mechanical unit and the air control set is provided. A tap holes shown in Fig.5.2 (b) are necessary for the installation of three points of air sets. This is outside FANUC delivery scope.

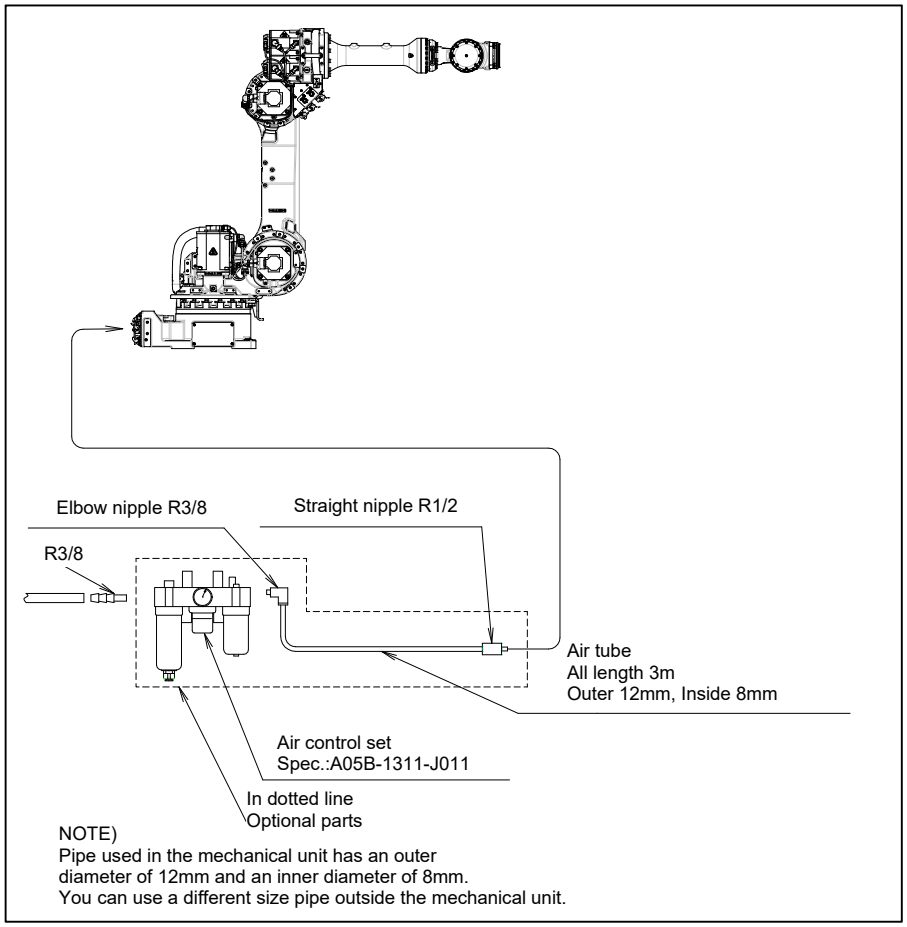


Fig. 5.2 (a) Air piping (option)

Air control set

Fill the lubricator having air control set to the specified level with turbine oil #90 to # 140. The machine tool builder is required to prepare mounting bolts. This is outside FANUC delivery scope.

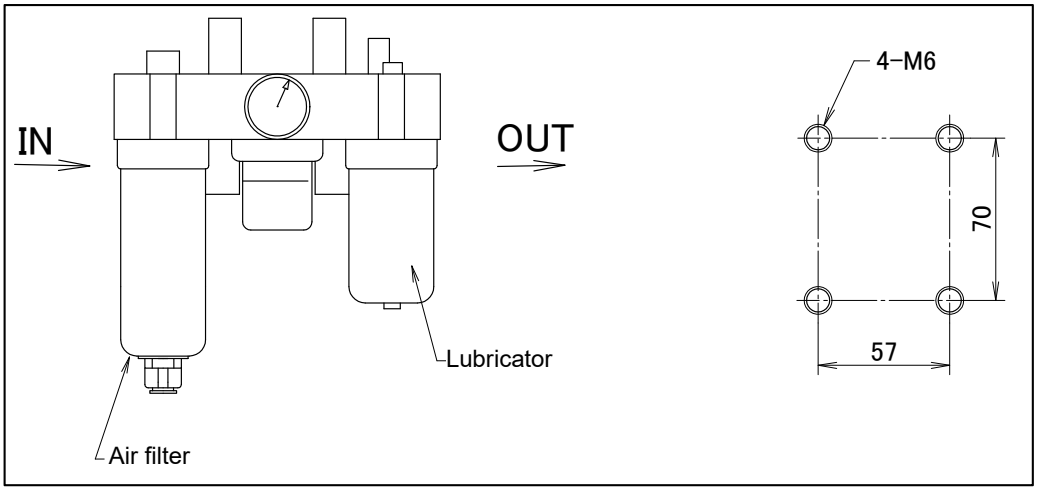


Fig. 5.2 (b) Air control set option (option)

NOTE
The capacity of the air control set is as follows.
These values must not be exceeded.

Air pressure	Supply air pressure	0.49 to 0.69MPa(5 to 7kgf/cm^2) Setting: 0.49MPa(5kgf/cm^2)
	Amount of consumption	Maximum instantaneous amount 150Nl/min (0.15Nm^3/min)

5.3 INTERFACE FOR OPTION CABLE (OPTION)

Fig. 5.3 (a) shows the position of the option cable interface. Fig 5.3 (b) to (j) show the option cable interface. EE interface (RI/RO), user cable (signal, signal usable to force sensor and 3D Laser Vision sensor, signal usable to force sensor and power line), camera cable , 3D Laser Vision sensor cable, DeviceNet cable (signal line and power line) , additional axis motor cable (Pulsecoder) and Ethernet cable (signal/power) as options.

NOTE

Each option cable is written as shown below on the connector panel.

EE(RI/RO) interface	: EE
User cable (signal)	: AS
User cable (power)	: AP
User cable (signal usable to force sensor and 3D Laser Vision sensor)	: ASi
User cable (signal usable to force sensor)	: ASH
Camera cable	: CAM
3D Laser Vision sensor cable	: SEN
DeviceNet cable (signal)	: DS
DeviceNet cable (power)	: DP
Additional axis motor cable (Pulsecoder)	: ARP
Additional axis motor cable (power, brake)	: ARM
Ethernet cable (signal)	: ES
Ethernet cable (power)	: EP

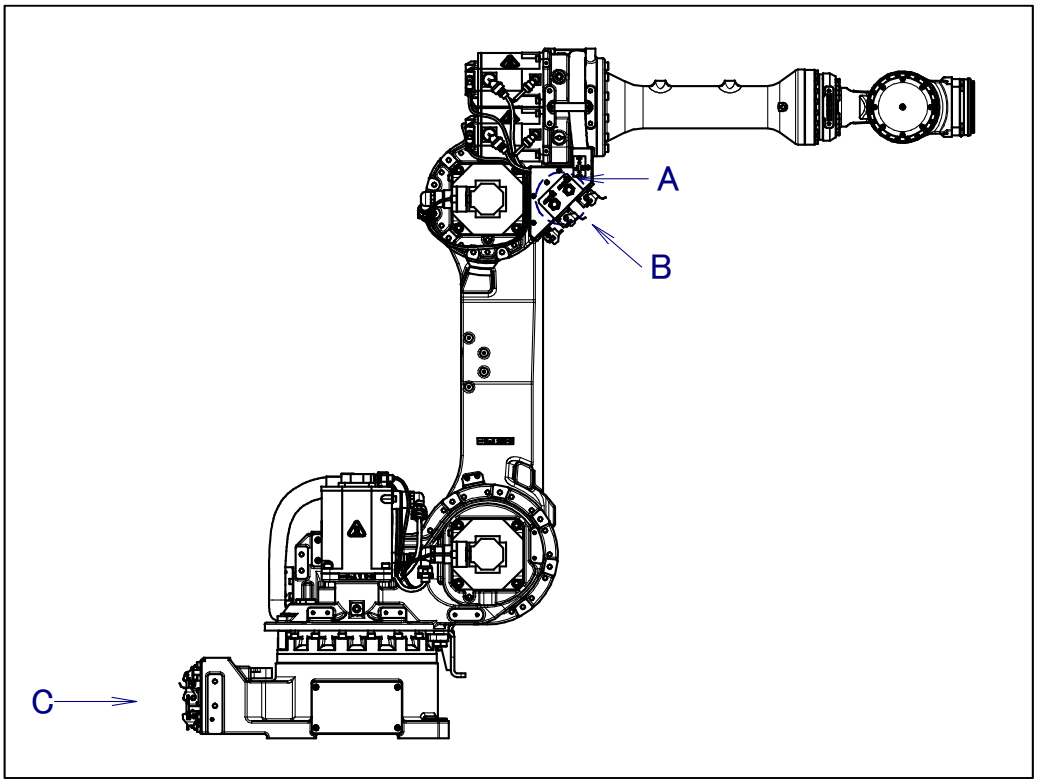
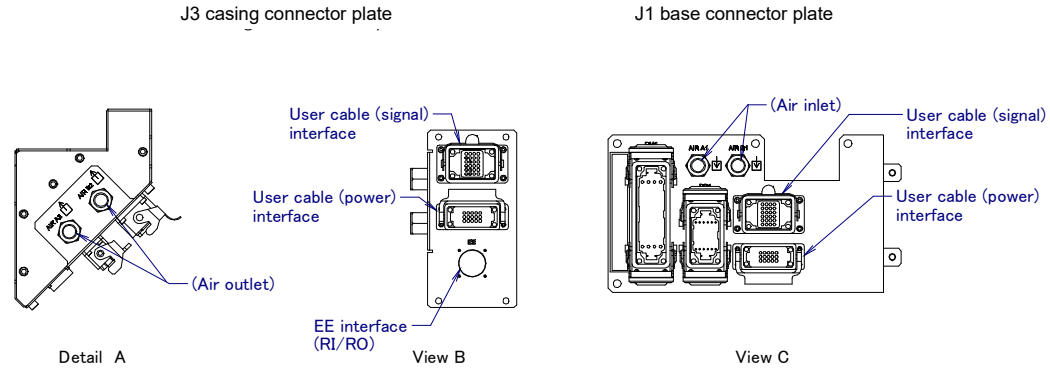
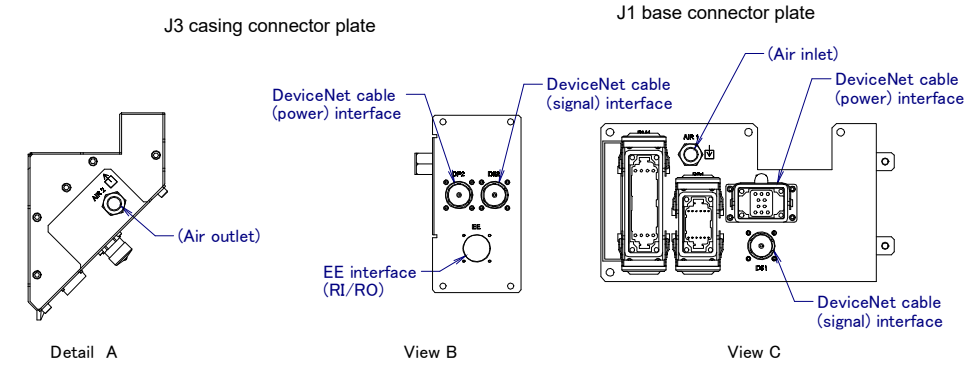


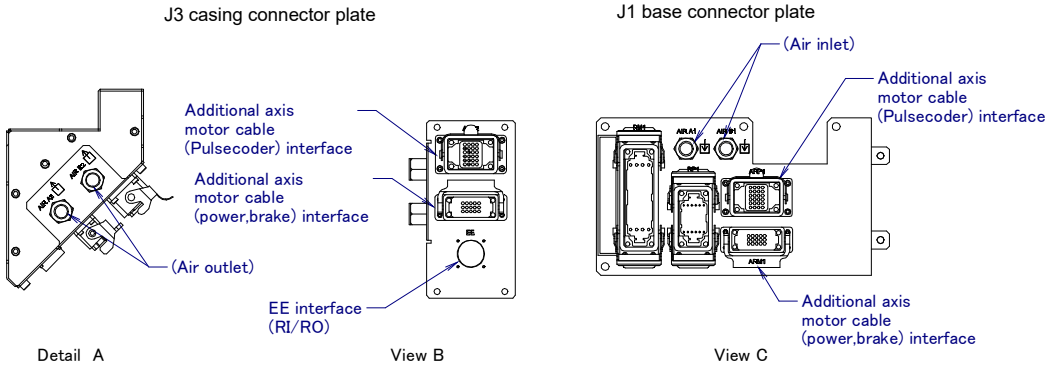
Fig. 5.3 (a) Position of interface for optional cable (option)



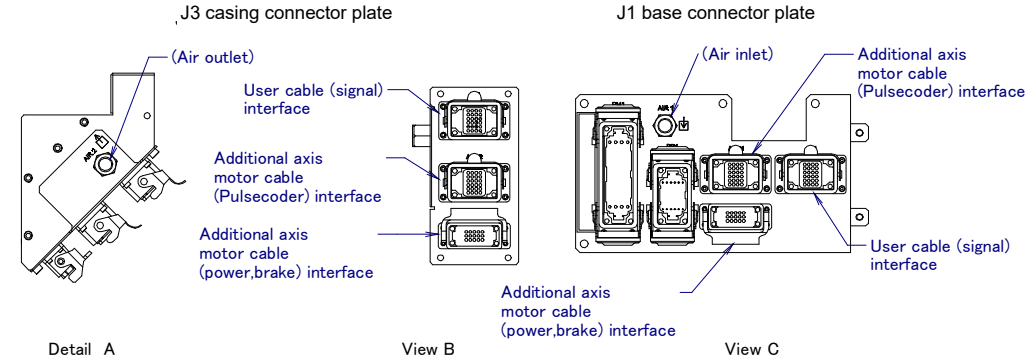
With user cable (signal /power), AIR x 2
Spec. of mechanical unit cable : A05B-1330-H201, H401, H501, H701,



With DeviceNet cable (signal /power), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H202, H502

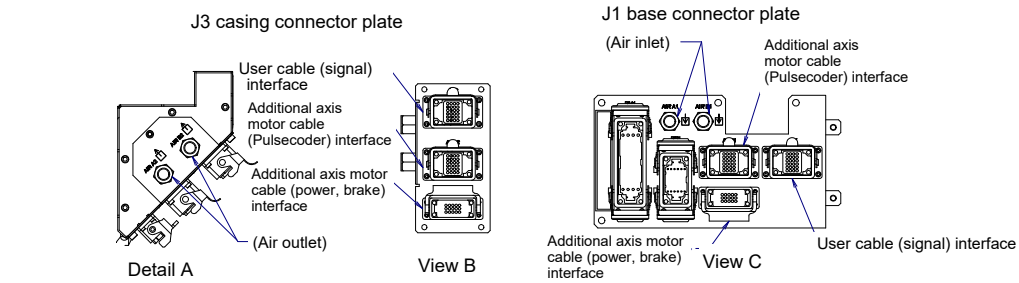


With additional axis motor cable (Pulsecoder, power, brake), AIR x 2
Spec. of mechanical unit cable : A05B-1330-H204,H504

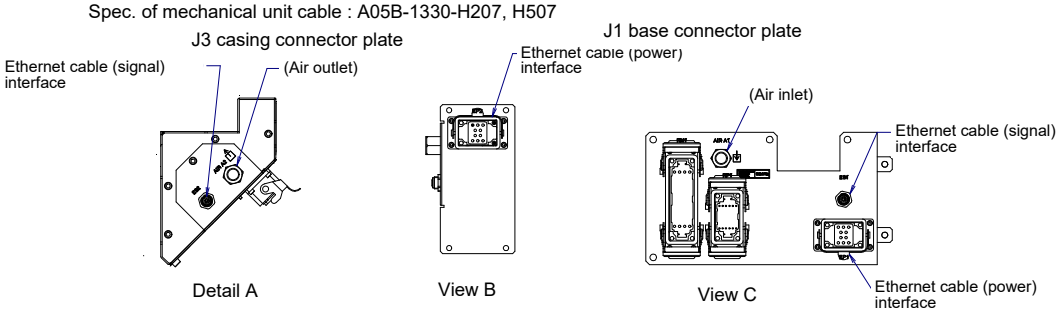


With additional axis motor cable (Pulsecoder, power, brake), user cable (signal), AIR x 1,without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H205, H505

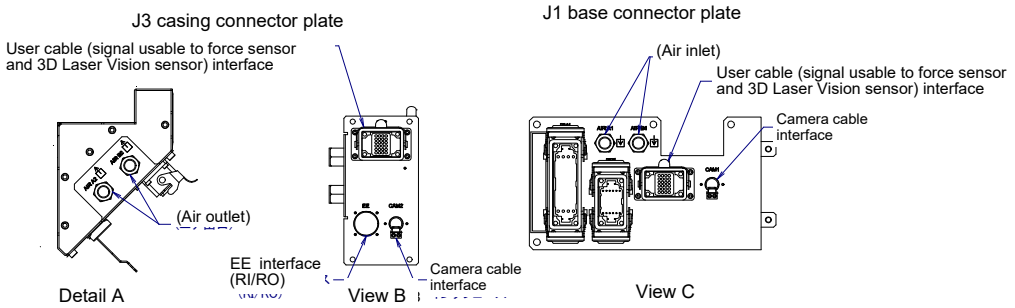
Fig. 5.3 (b) option cable interface (1/9)



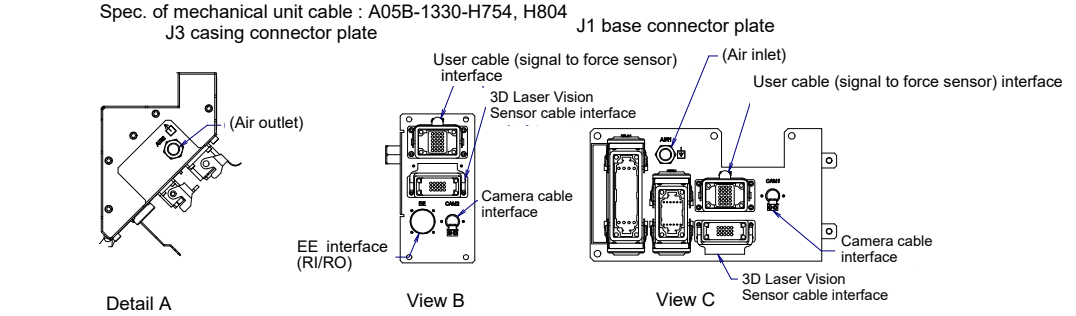
With additional axis motor cable (Pulsecoder, power, brake), user cable (signal), AIR x 2, without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H207, H507



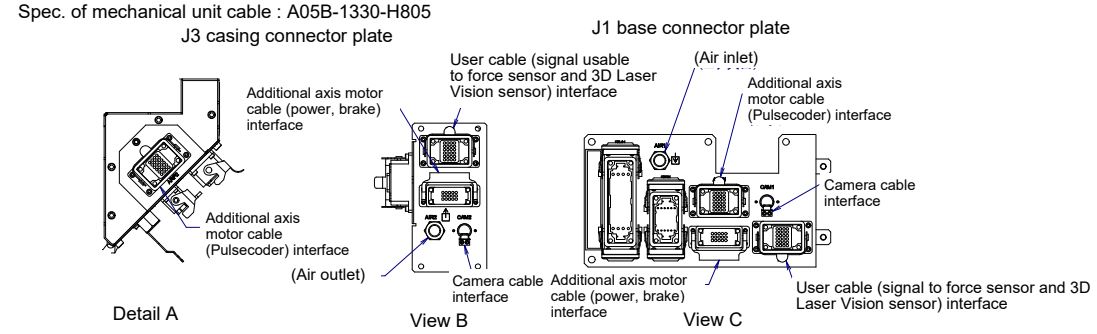
With Ethernet cable (signal/power), AIR x 2, without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H510



With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, AIR x 2
Spec. of mechanical unit cable : A05B-1330-H754, H804

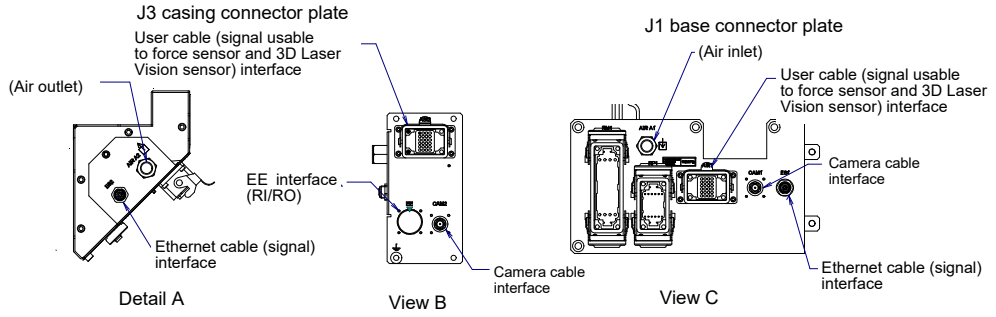


With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, 3D Laser Vision Sensor cable, AIR x 1
Spec. of mechanical unit cable : A05B-1330-H805

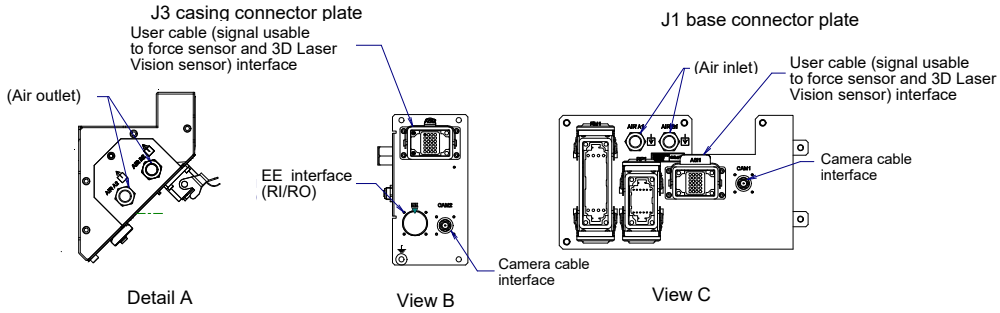


With user cable (signal usable to force sensor and 3D Laser Vision sensor), additional axis motor cable (Pulsecoder/power, brake), AIR x 1
Without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H806

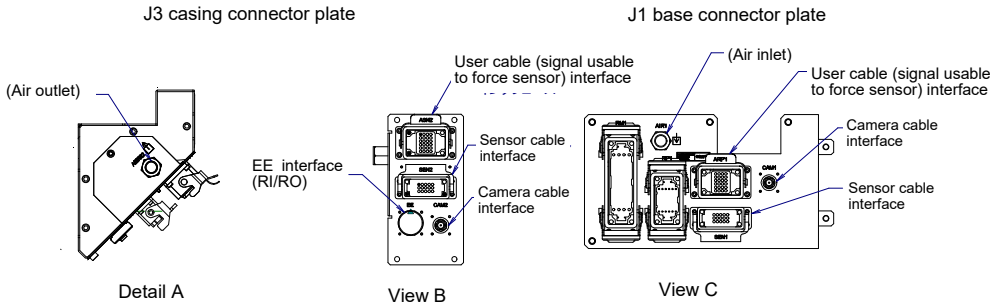
Fig. 5.3 (c) option cable interface (2/9)



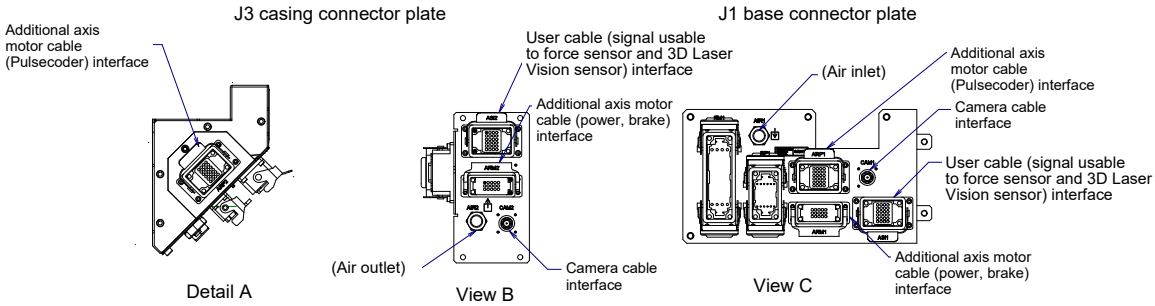
With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, Ethernet cable (signal), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H751, H807



With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, AIR x 2
Spec. of mechanical unit cable : A05B-1330-H808



With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, sensor cable AIR x 2
Spec. of mechanical unit cable : A05B-1330-H809



With additional axis motor cable (Pulsecoder, power, brake), user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable AIR x 1, without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H810

Fig. 5.3 (d) option cable interface (3/9)

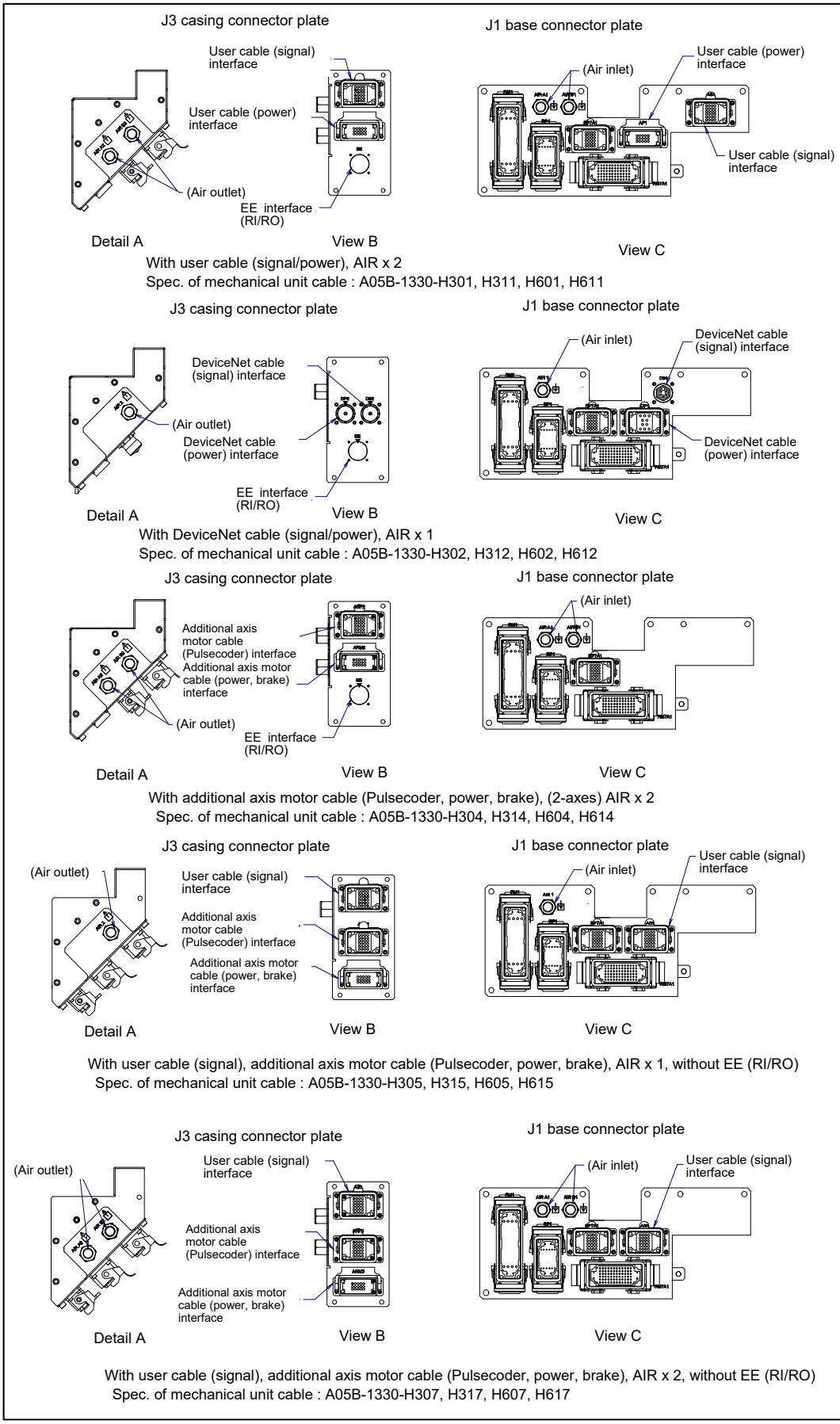
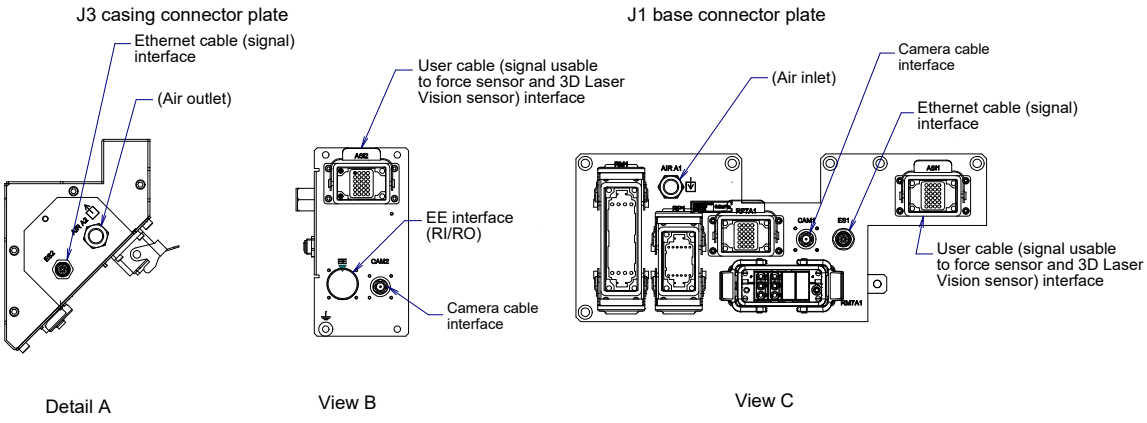
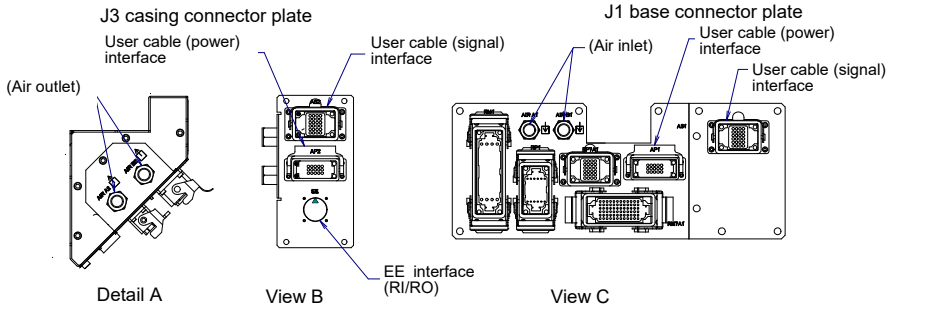


Fig. 5.3 (e) option cable interface (4/9)

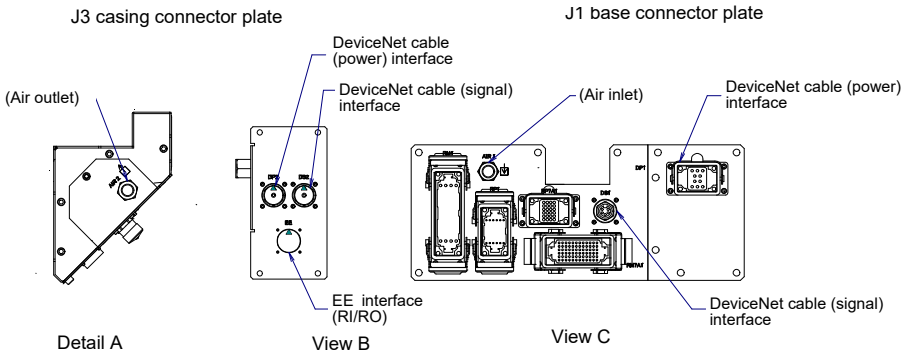


With user cable (signal usable to force sensor and 3D Laser Vision sensor), camera cable, Ethernet cable (signal), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H618

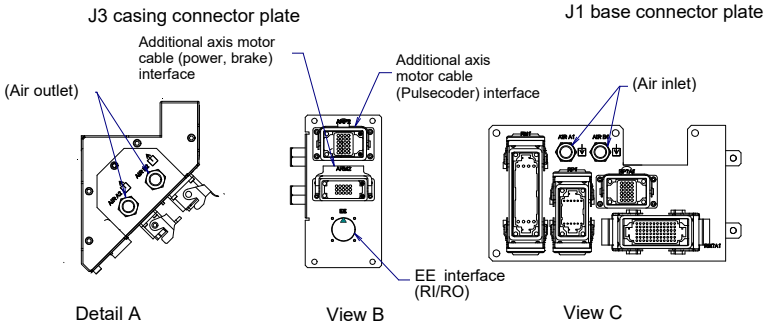
Fig. 5.3 (f) option cable interface (5/9)



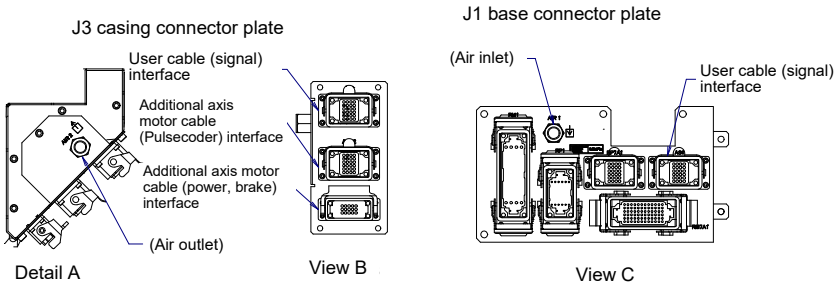
With user cable (signal/power), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H351, H651



With DeviceNet cable (signal/power), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H352, H652,



With additional axis motor cable (Pulsecoder, power, brake), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H354, H654



With additional axis motor cable (Pulsecoder, power, brake), user cable (signal),AIR x 1, without EE(RI/RO)
Spec. of mechanical unit cable : A05B-1330-H355, H655

Fig. 5.3 (g) option cable interface (6/9)

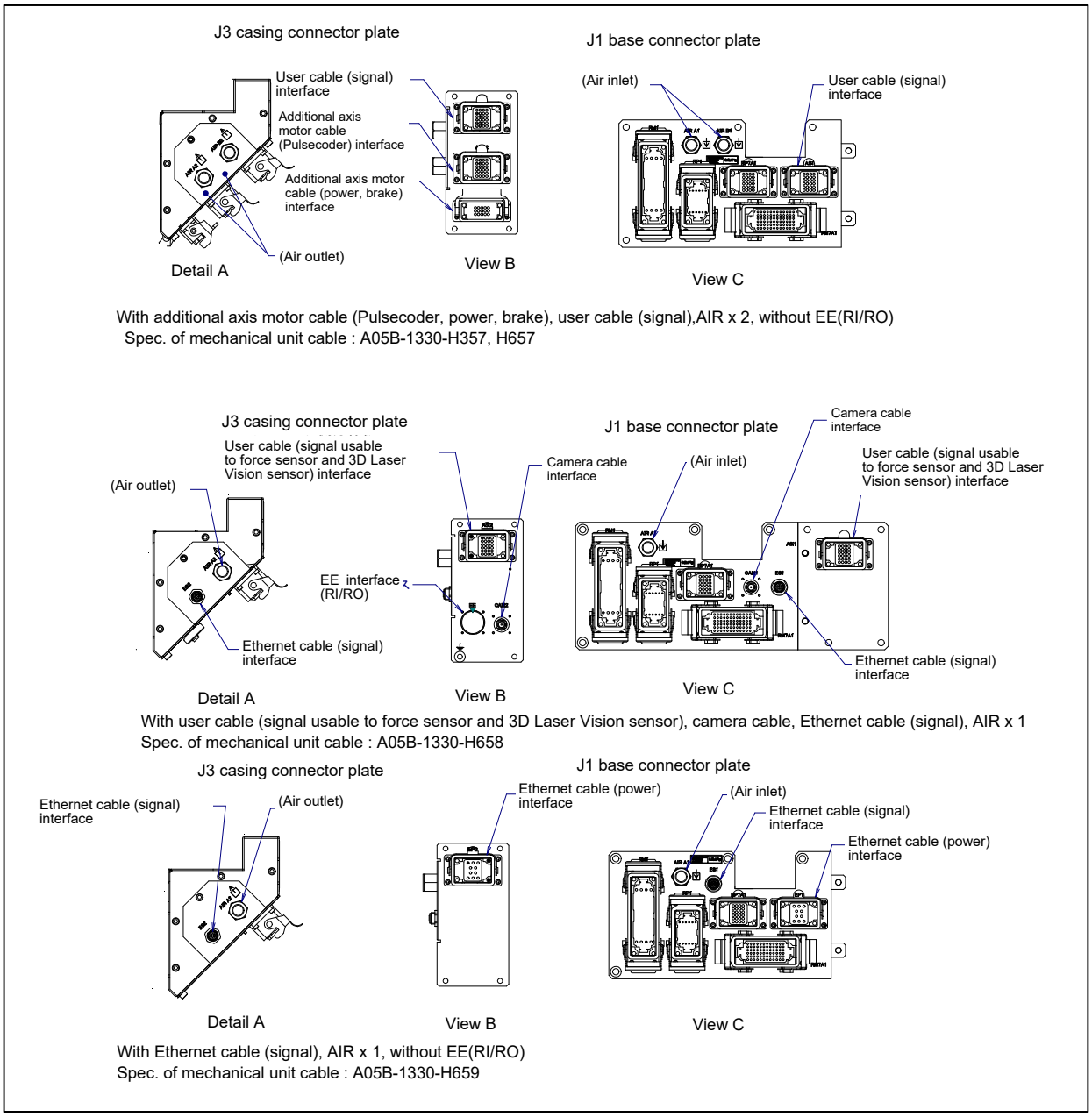


Fig. 5.3 (h) option cable interface (7/9)

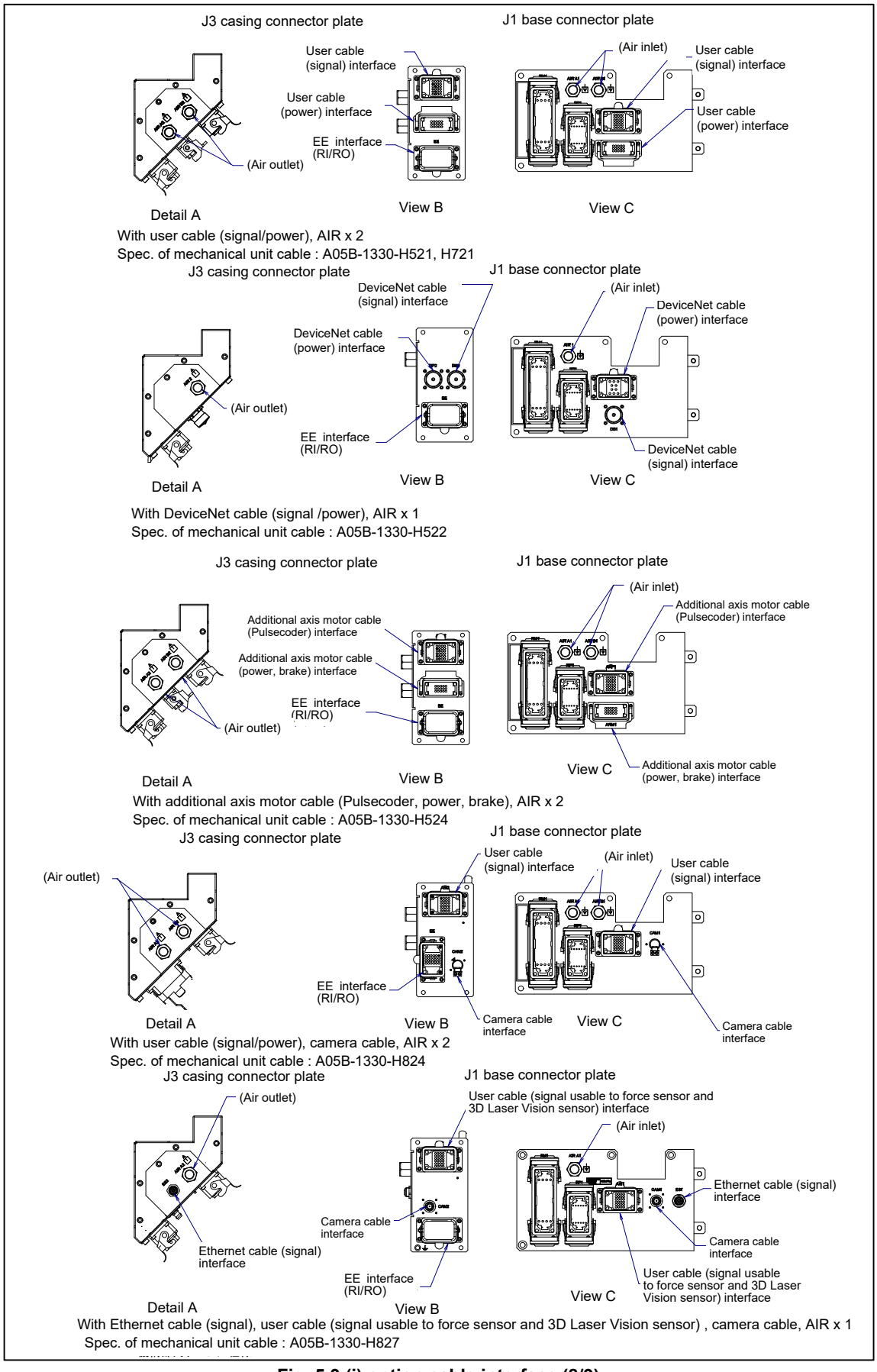
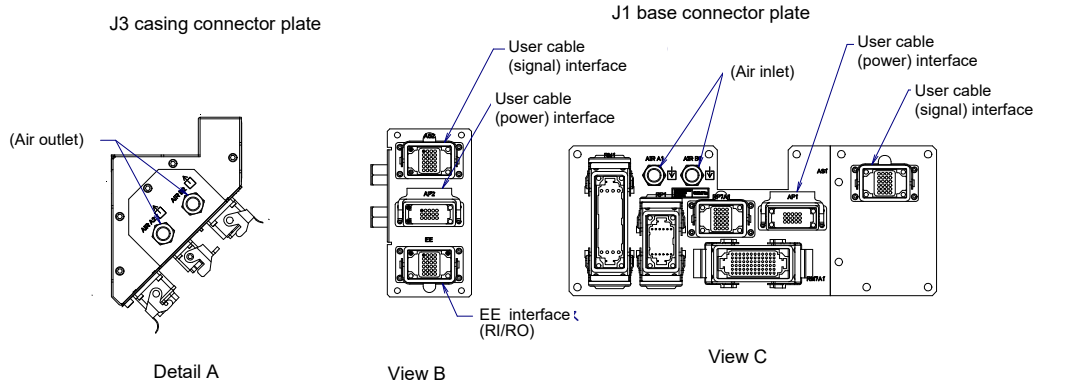
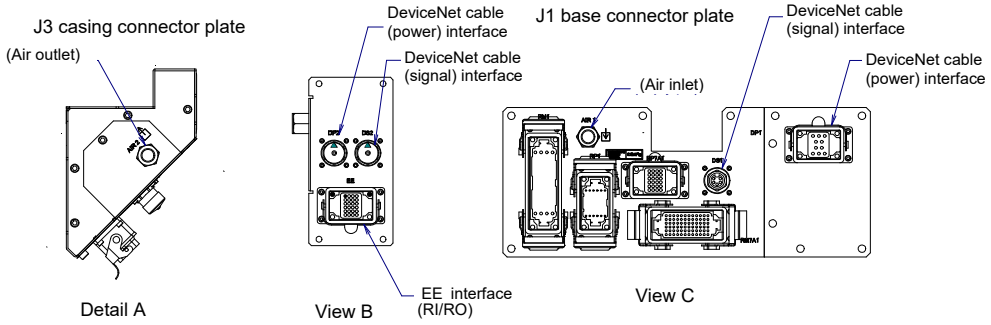


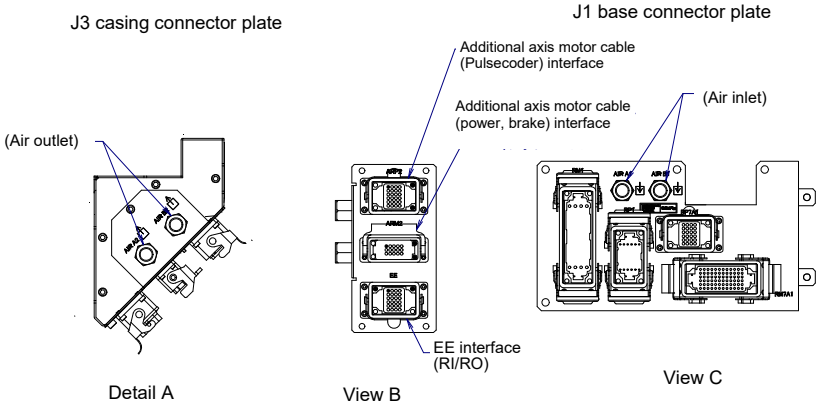
Fig. 5.3 (i) option cable interface (8/9)
(Severe dust/liquid protection package is specified)



With user cable (signal/power), AIR x 2
Spec. of mechanical unit cable : A05B-1330-H661



With DeviceNet cable (signal /power), AIR x 1
Spec. of mechanical unit cable : A05B-1330-H662



With additional axis motor cable (Pulsecoder, power, brake), AIR x 2
Spec. of mechanical unit cable : A05B-1330-H664

Fig. 5.3 (j) option cable interface (9/9)
(Severe dust/liquid protection package is specified)

1 EE interface (RI/RO) (option)

Fig. 5.3 (k) and (l) show pin layout for EE interface (RI/RO). When severe dust/liquid protection package is specified, the connector has guide pins and bushes for preventing improper insertion. For cables prepared by the user, use these guide pins and bushes.

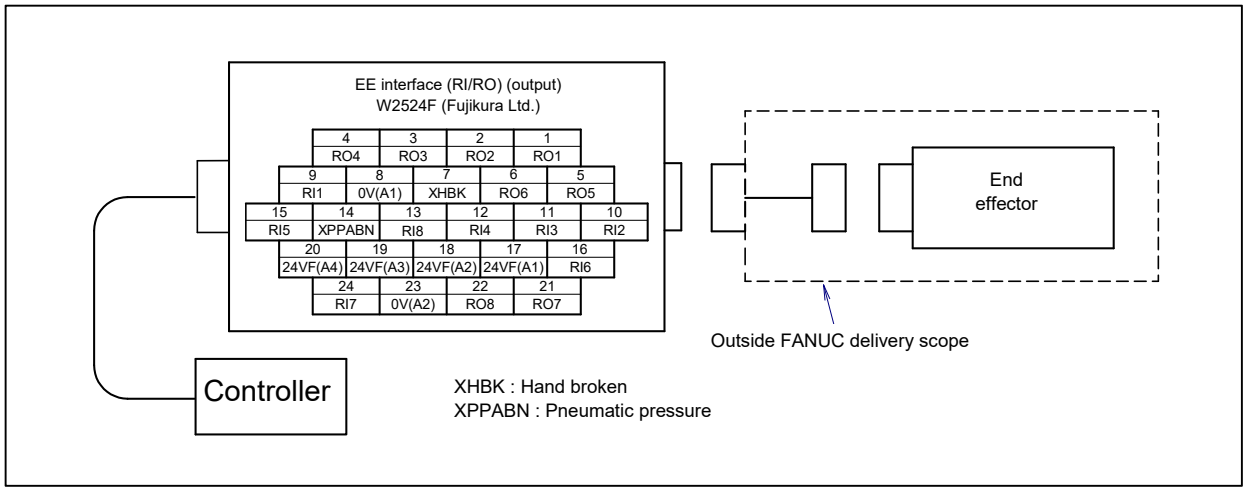


Fig. 5.3 (k) Pin layout for EE interface (RI/RO) (option)

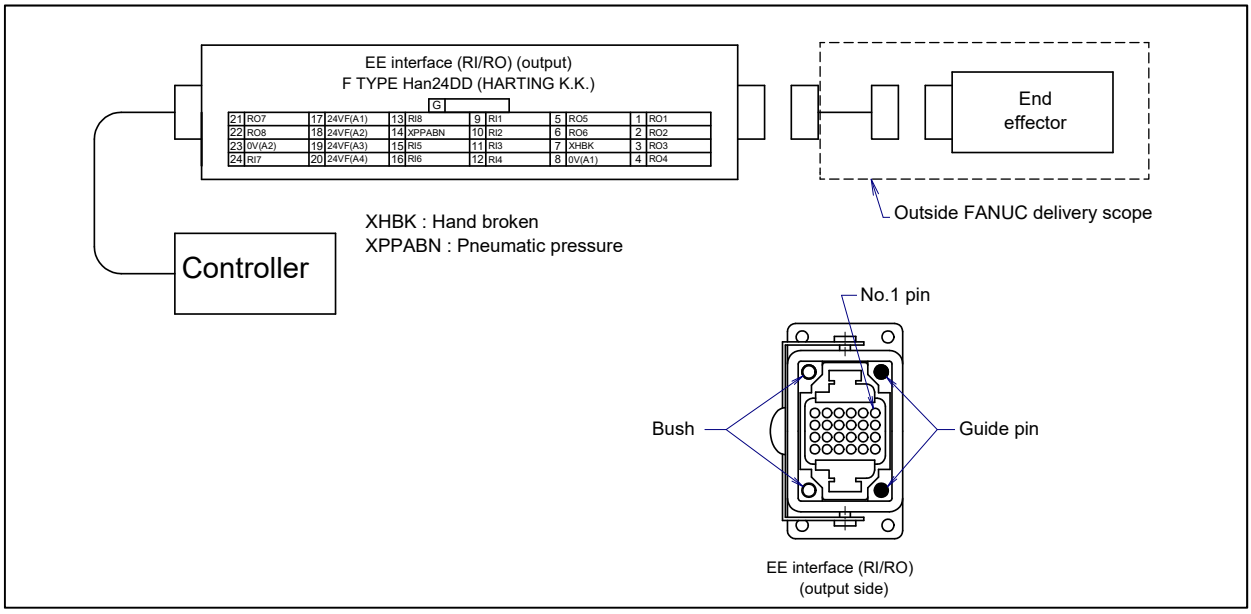


Fig. 5.3 (l) Pin layout for EE interface (RI/RO)(Severe dust/liquid protection package) (option)

2 User cable (signal) (AS) Interface (option)

Fig. 5.3 (m) shows pin layout for user cable (signal) interface. The connector has a code pin for preventing improper insertion. For cables prepared by the user, use this code pin.

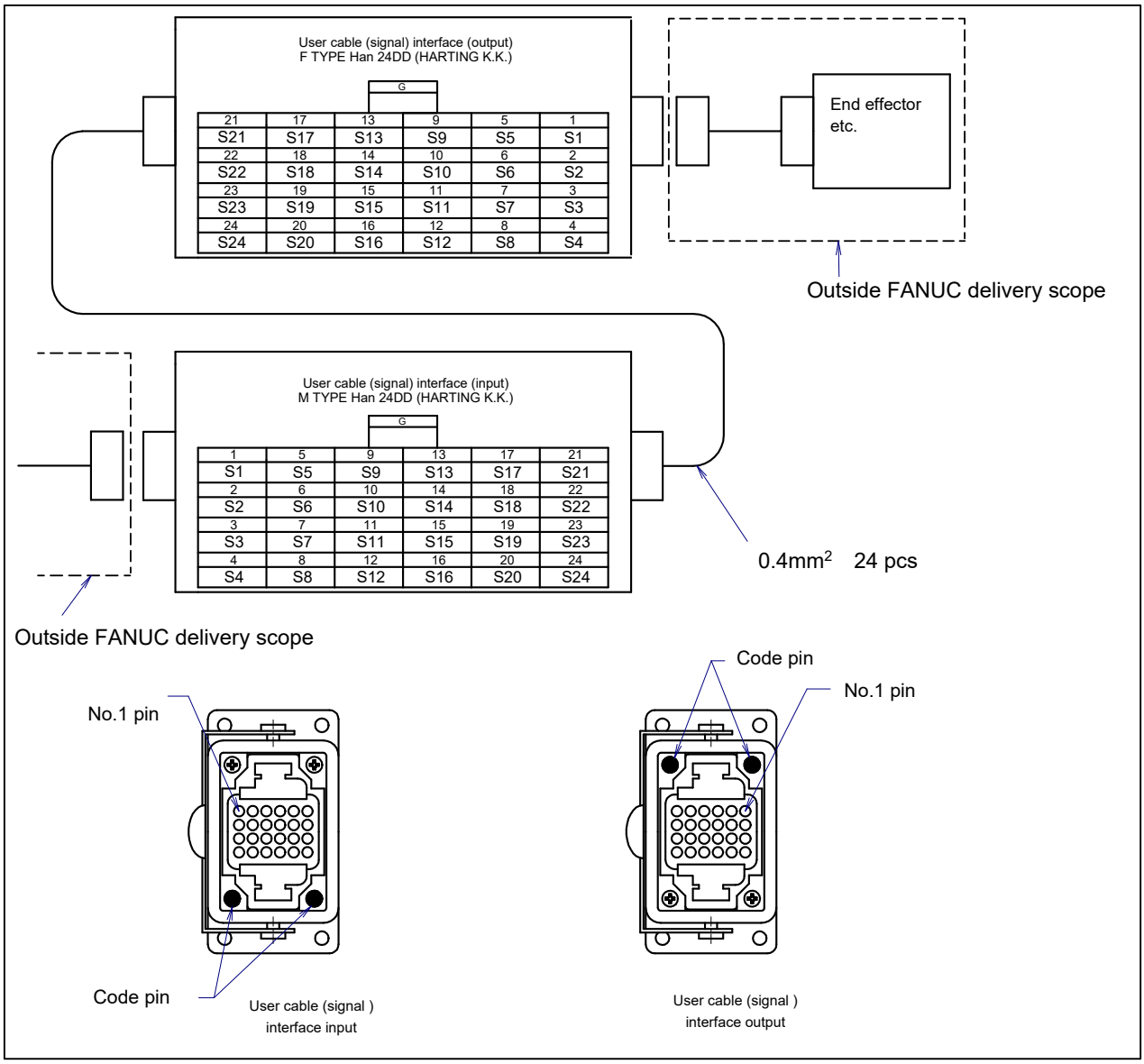


Fig. 5.3 (m) Pin layout for user cable (signal) (AS) interface and code pin layout (option)

3 User cable (signal usable to force sensor and 3D Laser Vision sensor) (ASi) (signal usable to force sensor) (ASH) Interface (option)

Fig. 5.3 (n) shows the pin layout for the user cable (signal usable to force sensor and 3D Laser Vision sensor)/(signal usable to force sensor) (ASH) interface.

The connector has a code pin for preventing improper insertion. The code pin is required for the cable which is prepared by the user.

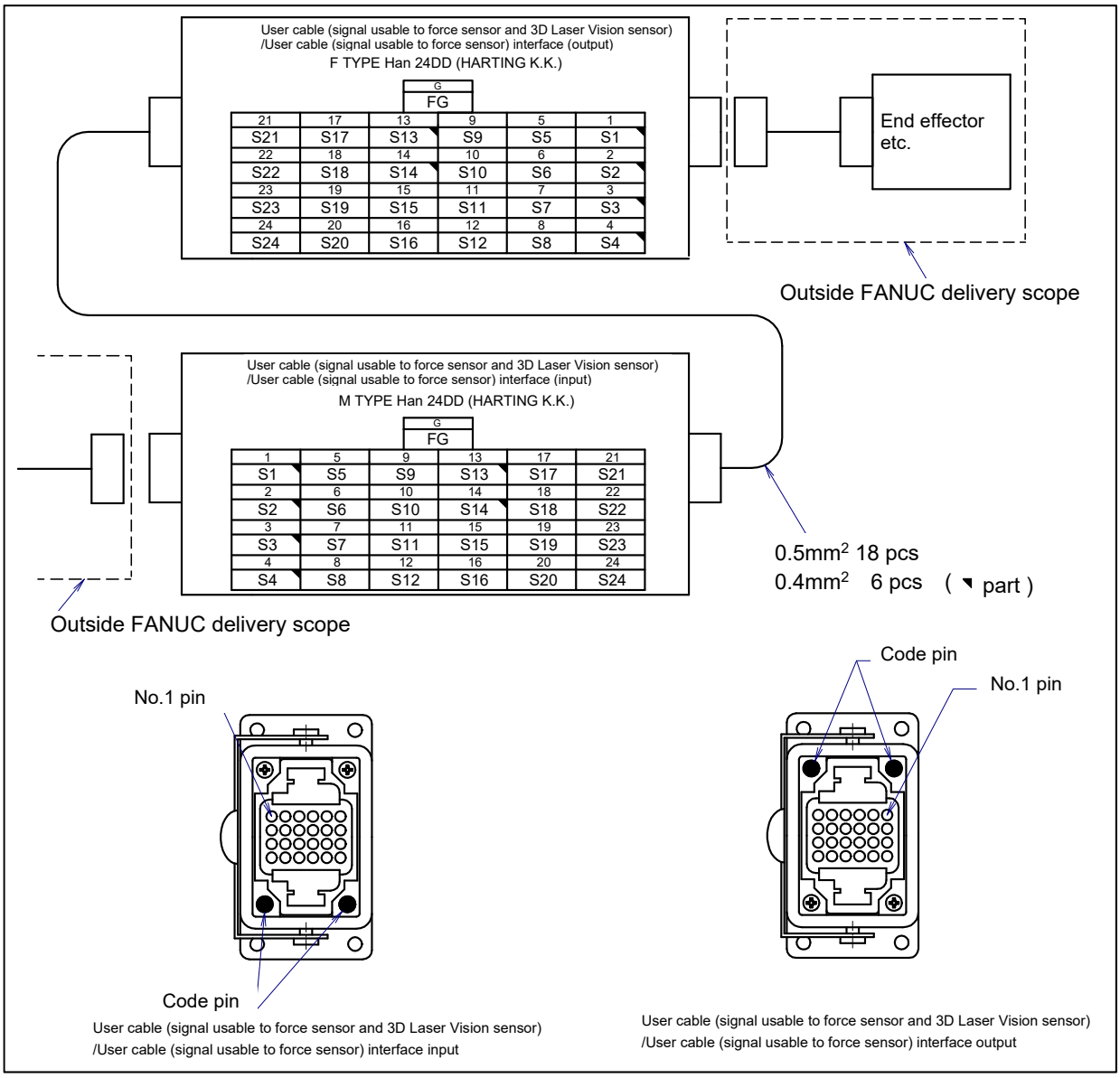


Fig. 5.3 (n) Pin layout for user cable (signal usable to force sensor and 3D Laser Vision sensor) (ASi) (signal usable to force sensor) (ASH)/interface and code pin layout (option)

4 User cable (power) (AP) Interface (option)
Fig. 5.3 (o) shows pin layout for user cable (power) interface.
The connector has a code pin for preventing improper insertion. For cables prepared by the user, use this code pin.

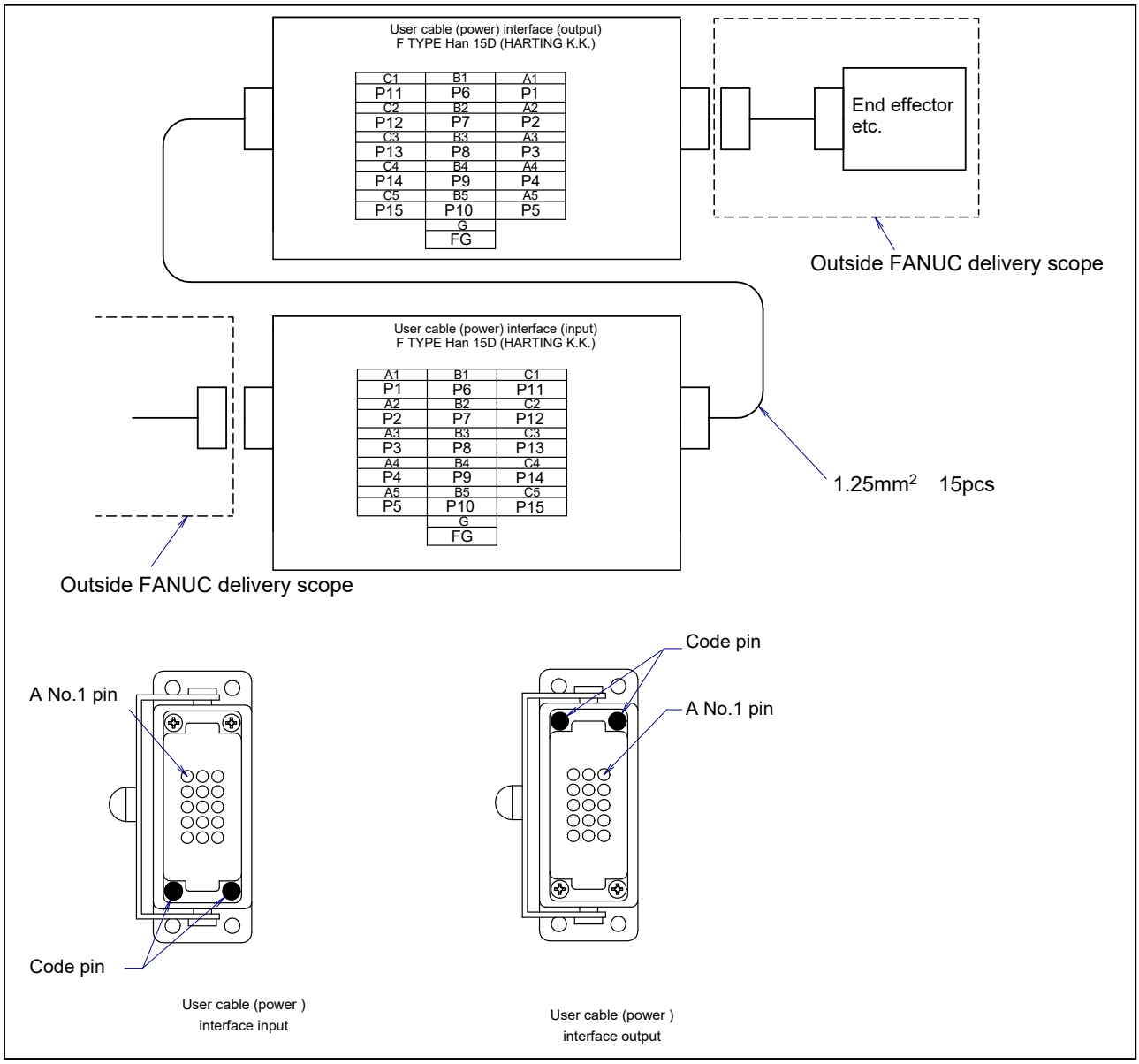


Fig. 5.3 (o) Pin layout for user cable (power) (AP) interface and code pin layout (option)

5 DeviceNet cable (signal) (DS) Interface (option)
Fig. 5.3 (p) shows pin layout for DeviceNet cable (signal) interface.

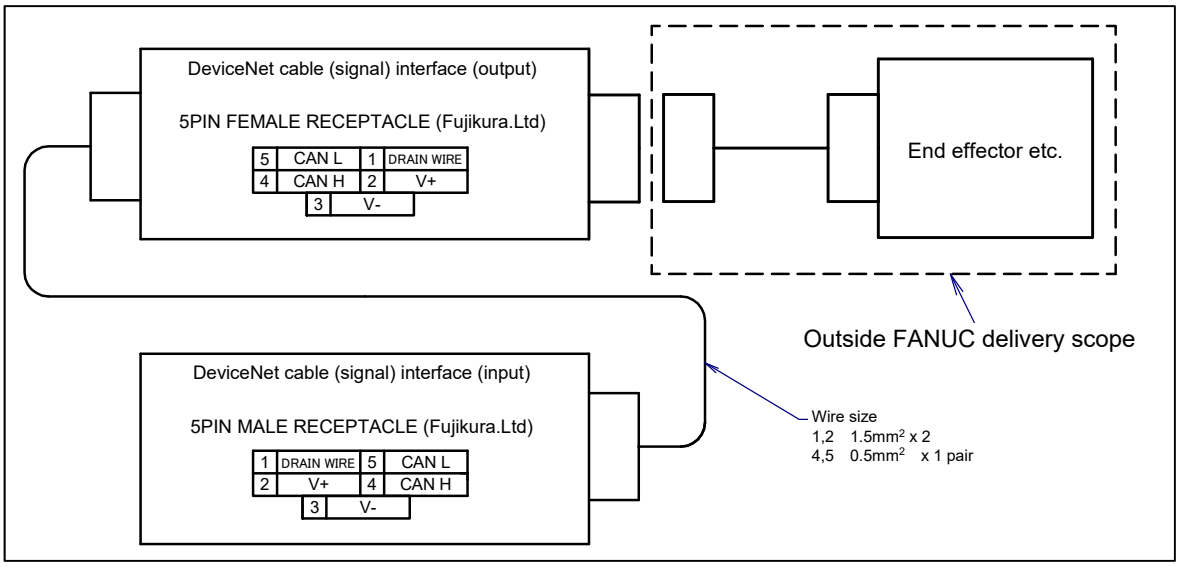


Fig. 5.3 (p) Pin layout for DeviceNet cable (signal) (DS) interface (option)

6 DeviceNet cable (power) (DP) Interface (option)
Fig. 5.3 (q) shows pin layout for DeviceNet cable (power) interface.

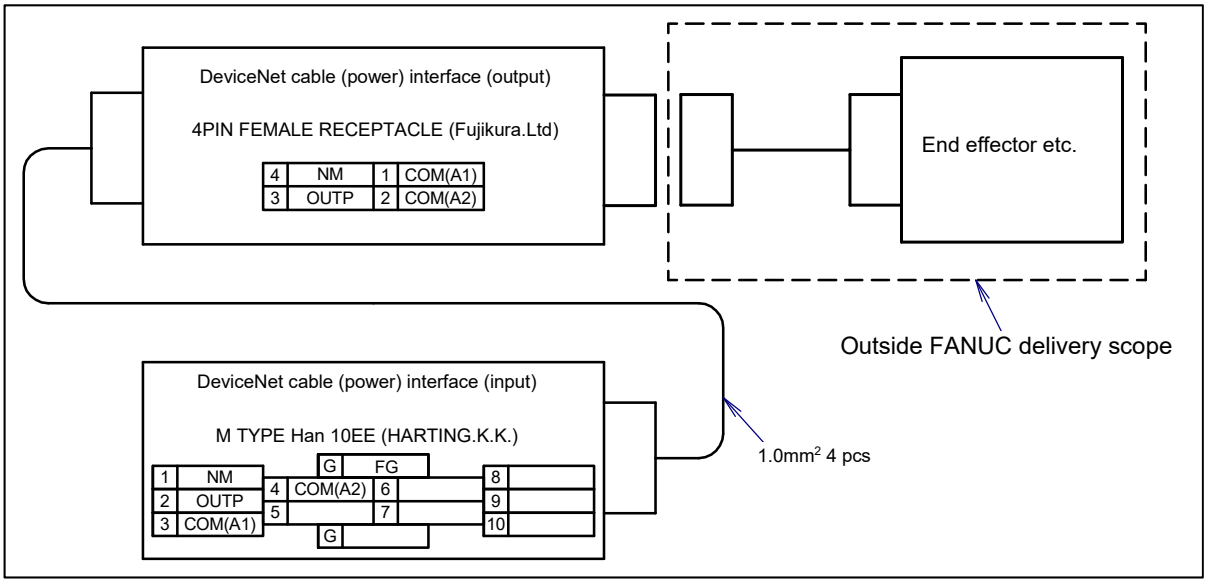


Fig. 5.3 (q) Pin layout for DeviceNet cable (power) (DP) interface (option)

7 Additional axis motor cable (Pulsecoder cable) (ARP) interface (option)
Fig. 5.3 (r) shows the pin layout of the additional axis motor cable (Pulsecoder cable) interface.
The connector has a code pin for preventing improper insertion.

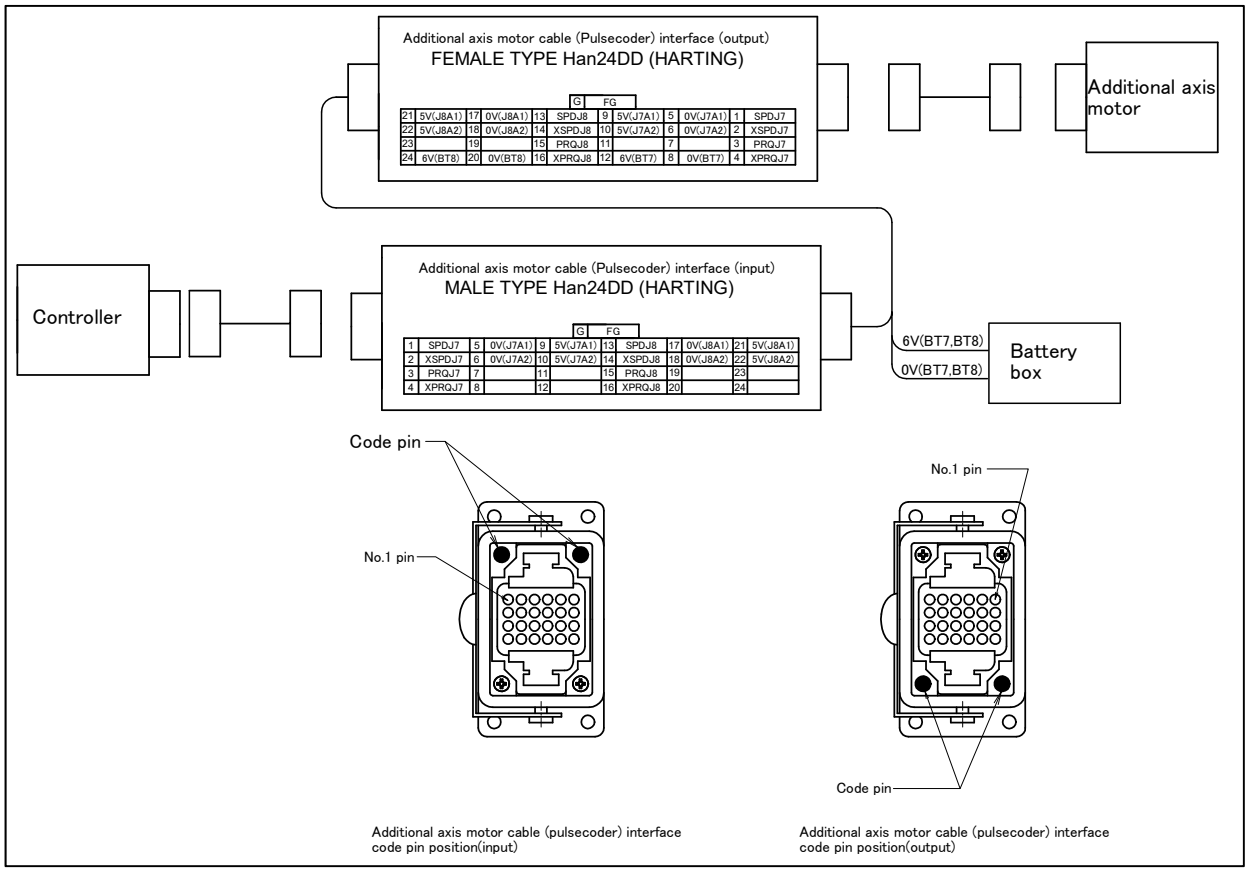


Fig. 5.3 (r) Pin layout and code pin position of the additional axis motor cable (Pulsecoder cable) (ARP) interface and layout position of the code pin (option)

Table 5.3 (a) Comparative table of signal name according to the motor

ARP	α motor, β motor	α*i* motor, β*i* motor
SPD	SD	-
XSPD	*SD	-
PRQ	REQ	RD
XPRQ	*REQ	*RD

8 Additional axis motor cable (power and brake cables) (ARM) interface (option)
Fig. 5.3 (s) shows the pin layout of the additional axis motor cable (power and brake cables) interface. The connector has a code pin for preventing improper insertion.

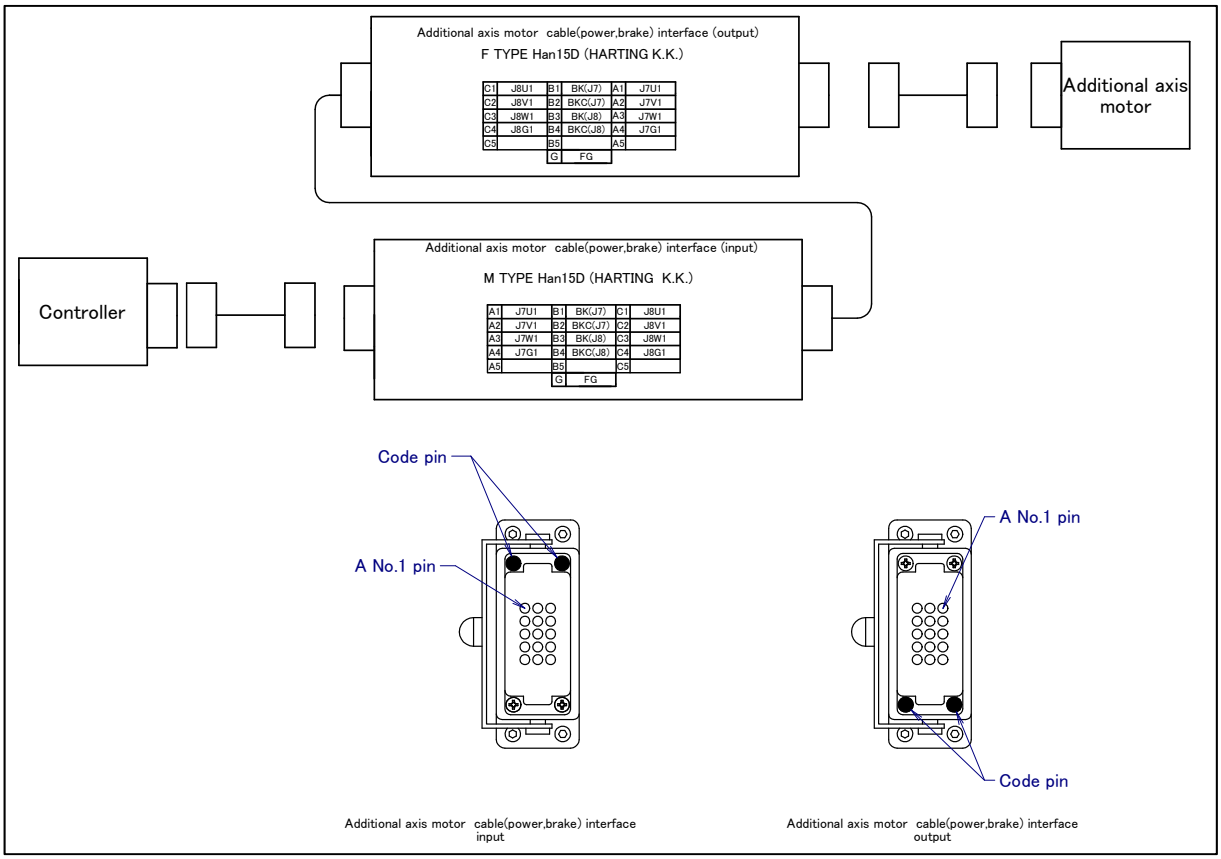


Fig. 5.3 (s) Pin layout and code pin position of the additional axis motor cable (power and brake cables) (ARM) interface and layout position of the code pin (option)

9 Ethernet cable (signal) (ES) interface (option)
Fig. 5.3 (t) shows the pin layout of the Ethernet cable (signal) (ES) interface.

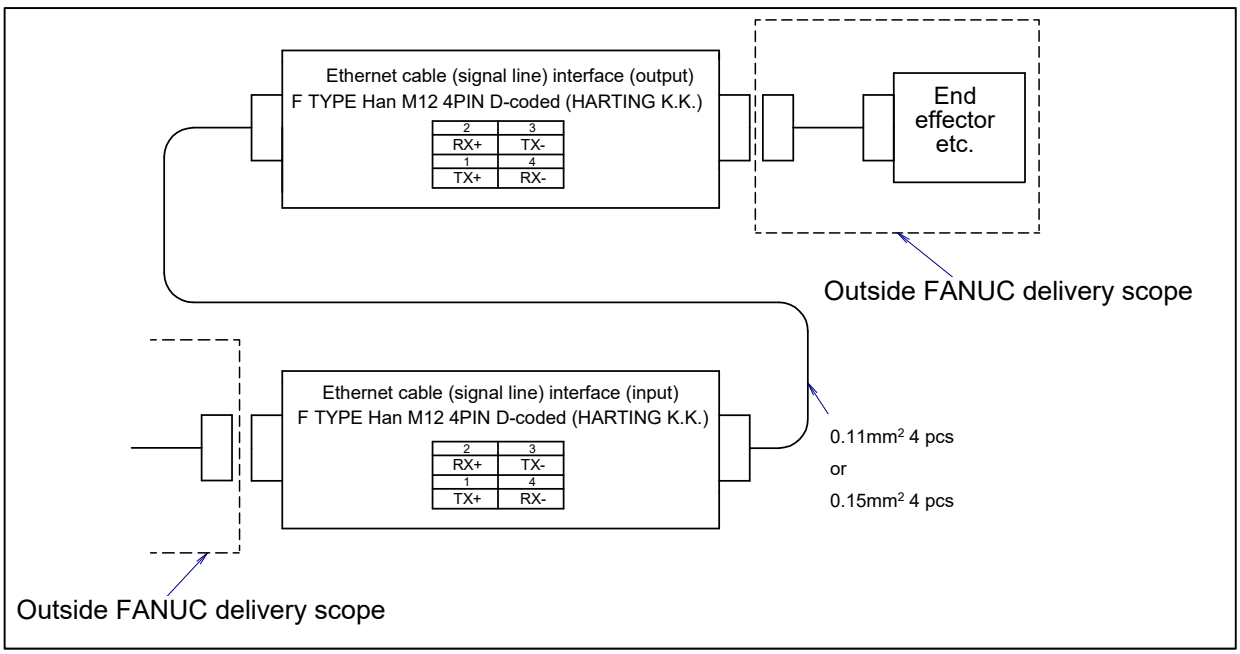


Fig. 5.3 (t) Pin layout for Ethernet cable (signal line) (ES) interface (option)

10 Ethernet cable (power line) (EP) interface (option)
Fig. 5.3 (u) shows the pin layout of the Ethernet cable (power line) (EP) interface. The connector has a code pin for preventing improper insertion.

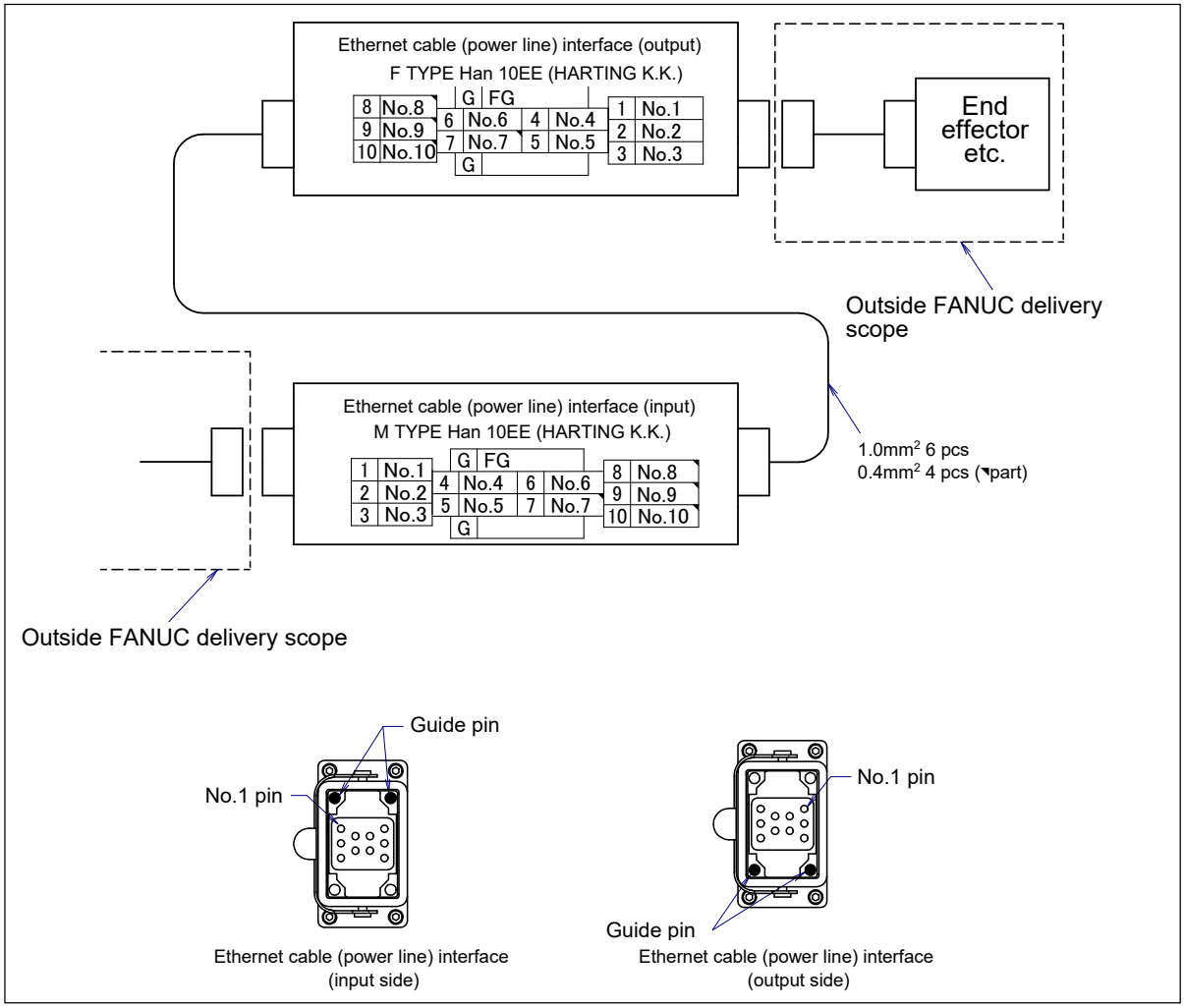


Fig. 5.3 (u) Pin layout for Ethernet cable (power line) (EP) interface (option)

Connector specifications

Table 5.3 (b) Connector specifications (Mechanical unit side)

Cable	Input side (J1 base)		Output side (J3 casing)		Maker /dealer
EE (RI/RO)	———		JMWR2524F		Fujikura Ltd.
AS ASi ASH	Housing Insert Contact Code pin	09 30 006 0301 09 16 024 3001 09 15 000 6103 09 30 000 9901	Housing Insert Contact Code pin	09 30 006 0301 09 16 024 3101 09 15 000 6203 09 30 000 9901	HARTING K.K.
AP	Housing Insert Contact Code pin	09 20 010 0301 09 21 015 3001 09 15 000 6101 09 30 000 9901	Housing Insert Contact Code pin	09 20 010 0301 09 21 015 3101 09 15 000 6201 09 30 000 9901	
ARP	Housing Insert Contact Contact Code pin	09 30 006 0301 09 16 024 3001 09 15 000 6103 09 15 000 6104 09 30 000 9901	Housing Insert Contact Contact Code pin	09 30 006 0301 09 16 024 3101 09 15 000 6203 09 15 000 6204 09 30 000 9901	
ARM	Housing Insert Contact Contact Code pin	09 20 010 0301 09 21 015 3001 09 15 000 6101 09 15 000 6106 09 30 000 9901	Housing Insert Contact Contact Code pin	09 20 010 0301 09 21 015 3101 09 15 000 6201 09 15 000 6206 09 30 000 9901	
EE (RI/RO) (When severe dust/liquid protection package is specified)	———		Housing Insert Contact Guide pin Bush	09 30 006 0301 09 16 024 3101 09 15 000 6204 09 33 000 9908 09 33 000 9909	
ES	Connector Contact	21 03 881 2425 09 67 000 7476	Connector Contact	21 03 881 2425 09 67 000 7476	
EP	Housing Insert Contact Contact Guide pin Bush	09 30 006 0301 09 32 010 3001 09 33 000 6105 09 33 000 6121 09 33 000 9908 09 33 000 9909	Housing Insert Contact Contact Guide pin Bush	09 30 006 0301 09 32 010 3101 09 33 000 6205 09 33 000 6220 09 33 000 9908 09 33 000 9909	

Table 5.3 (c) Connector specifications (User side)

Cable	Input side (J1 base)		Output side (J3 casing)		Maker /Dealer
EE (RI/RO)	_____		JMSP2524M (*1) Straight JMLP2524M Angle		Fujikura .Ltd
AS ASi ASH	Hood (NOTE 2)	09 30 006 1540 Side entry 1541 ↓ 0542 0543 1440 Top entry 1441 ↓ 0442 0443	Hood	← Same as left	HARTING K.K.
	Insert	09 16 024 3101	Insert	09 16 024 3001	
	Contact (NOTE 2)	09 15 000 6204 AWG 26-22 6203 AWG 20 6205 AWG 18 6202 AWG 18 6201 AWG 16 6206 AWG 14	Contact	09 15 000 6104 AWG 26-22 6103 AWG 20 6105 AWG 18 6102 AWG 18 6101 AWG 16 6106 AWG 14	
	Clamp (NOTE 2)	09 00 000 5083 5086 5090 5094 etc.	Clamp	← Same as left	

Table 5.3 (d) Connector specifications (User side)

Cable	Input side (J1 base)		Output side (J3 casing)		Maker /Dealer
AP	Hood (NOTE 2)	09 20 010 1541 Side entry 0540 ↓ 0541 1440 Top entry 0440 ↓ 0441	Hood	← Same as left	HARTING K.K.
	Insert	09 21 015 3101	Insert	09 21 015 3001	
	Contact (NOTE 2)	09 15 000 6204 AWG 26-22 6203 AWG 20 6205 AWG 18 6202 AWG 18 6201 AWG 16 6206 AWG 14	Contact	09 15 000 6104 AWG 26-22 6103 AWG 20 6105 AWG 18 6102 AWG 18 6101 AWG 16 6106 AWG 14	
	Clamp (NOTE 2)	09 00 000 5083 5086 5090 5094 etc.	Clamp	← Same as left	
EE (RI/RO) (When severe dust/liquid protection package is specified)	———		Hood (NOTE 2)	09 30 006 1540 Side entry 1541 ↓ 0542 0543 1440(*2) Top entry 1441 ↓ 0442 0443	
			Insert	09 16 024 3001 (*3)	
			Contact (24 pcs)	09 15 000 6104 (*4) AWG 26-22 6103 AWG 20 6105 AWG 18 6102 AWG 18 6101 AWG 16 6106 AWG 14	
			Clamp (NOTE 2)	09 00 000 5085 (*5) 5086 5090 5094 Many other types are available	
			Guide pin (2 pcs)	09 33 000 9908 (*6)	
			Bush (2 pcs)	09 33 000 9909 (*7)	
ES	Connector	21 03 881 1405	Connector	← Same as left	
	Contact (NOTE 2)	09 67 000 7576 AWG 28-24 5576 AWG 26-22 8576 AWG 24-20 3576 AWG 22-18	Contact	← Same as left	

Cable	Input side (J1 base)		Output side (J3 casing)		Maker /Dealer
EP	Hood (NOTE 2)	09 20 010 1540 Side entry 1541 0542 0543 ↓ 1440 Top entry 1441 ↓ 0442 0443	Hood	←The same	
	Insert	09 32 010 3101	Insert	09 32 010 3001	
	Contact (NOTE 2)	09 33 000 6220 AWG 20 6214 AWG 18 6205 AWG 18 6204 AWG 16 6202 AWG 14 6207 AWG 12	Contact (NOTE 2)	09 33 000 6121 AWG 20 6114 AWG 18 6105 AWG 18 6104 AWG 16 6102 AWG 14 6107 AWG 12	HARTING K.K.
	Clamp (NOTE 2)	09 00 000 5083 5086 5090 5094 Many other types are available.	Clamp	←The same	
	Guide pin	09 33 000 9908	Guide pin	←The same	
	Bush	09 33 000 9909	Bush	←The same	

NOTE 1

Underlined parts are attached. Below shows spec. to order in our company.

(*1) A63L-0001-0234#S2524M
(*2) A63L-0001-0453#06B1440
(*3) A63L-0001-0453#24DDM
(*4) A63L-0001-0453#CA6104
(*5) A63L-0001-0453#A-152D
(*6) A63L-0001-0453#A-9908
(*7) A63L-0001-0453#A-9909

Table 5.3 (e) Connector specifications (DeviceNet cable, Mechanical unit side)

Cable	Input side (J1 base)		Maker /dealer	Output side (J3 casing)	Maker /dealer
DS	CM03A-R5P-S-2		Fujikura Ltd.	CM03A-PR5S-S-2	Fujikura Ltd.
DP	Housing Insert Contact	09 30 006 0301 09 32 010 3001 09 33 000 6105	HARTING K.K.	CM03A-PR4S-S-2	Fujikura Ltd.

Table 5.3 (f) Connector specifications (DeviceNet cable, User side)

Cable	Input side (J1 base)	Maker /dealer	Output side (J3 casing)	Maker /dealer
DS	MINI connector for use on the device net 5-pin, FEMALE CM03-P5S	Fujikura Ltd.	MINI connector for use on the device net 5-pin, MALE CM03-J5P	Fujikura Ltd.

Cable	Input side (J1 base)			Maker /dealer	Output side (J3 casing)	Maker /dealer
DP	Hood (NOTE 2)	09 30 006 1540 1541 0542 0543 1440 1441 0442 0443	Side entry ↓ ↓ Top entry ↓ ↓	HARTING K.K.	MINI connector for use on the device net4-pin, MALE CM03-J4P	Fujikura Ltd.
	Insert	09 32 010 3101				
	Contact (NOTE 2)	09 33 000 6220 6214 6205 6204 6202 6207	AWG 20 AWG 18 AWG 18 AWG 16 AWG 14 AWG 12			
	Clamp (NOTE 2)	09 00 000 5083 5086 5090 5094 Many other types are available.				

NOTE 2
For details, such as the dimensions, of the parts listed above, refer to the related catalogs offered by the respective manufactures, or contact your local FANUC representative.

6 AXIS LIMITS SETUP

By setting the motion range of each axis, you can change the robot's motion range from the standard values.
Changing the motion range of the robot is effective under the following circumstances:

- Used motion range of the robot is limited.
- There is an area where tool and peripheral devices interfere with the robot.
- The length of cables and hoses attached for application is limited.

There are three methods used to prevent the robot from going beyond the necessary motion range.

- Limit axis motion range by DCS (All axes (option))
- Limit axis motion range adjustable mechanical stopper (J1/J2/J3-axes (option))
- Limit axis motion range by adjustable mechanical stopper and switches (J1-axis (option))

⚠ WARNING

1 Changing the motion range of any axis affects the operating range of the robot. To avoid trouble, carefully consider any possible effect of the change to the movable range of each axis in advance. Otherwise, it is likely that an unexpected condition will occur; for example, an alarm may occur in a previously taught position.
2 When limiting the motion range, for J1-axis, use adjustable mechanical stoppers, for J2/J3-axis, use the adjustable mechanical stoppers or DCS function so that damage to peripheral equipment and injuries to human bodies can be avoided.
3 Mechanical stoppers are physical obstacles. For J1 to J3-axis, it is possible to re-position the adjustable mechanical stoppers. But the robot cannot move beyond them. For J5 and E1-axis, the mechanical stoppers are fixed. For the J4 and J6-axes, only DCS-specified limits are available.
4 For changing J2 andJ3-axes interference angles, only adjustable mechanical stoppers are available; DCS specified movable range cannot be changed.
5 Adjustable mechanical stoppers (J1, J2, and J3-axes) are deformed in a collision to stop the robot. Once a stopper is subject to a collision, it can no longer assure its original strength and, therefore, may not stop the robot. When this happens, replace it with a new one.

6.1 CHANGE AXIS LIMIT BY DCS (OPTION)

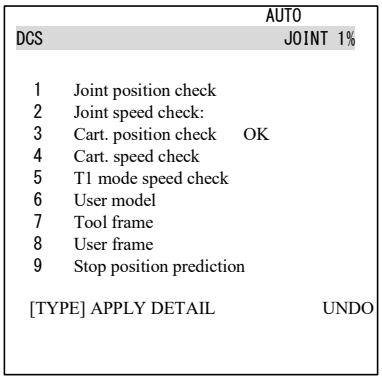
The robot motion can be restricted with DCS (Dual check safety) function by using the following software. For J2/J3-axis, the same effect as adjustable mechanical stopper described in Section 6.2 can be obtained. The robot motion can be restricted at any angle and position if it is in robot motion area. DCS functions are certified to meet the requirements of International Standard ISO13849-1 and IEC61508 approved by notified body. If only the operating space is set using Joint Position Check, the robot stops after it goes beyond the workspace. When the motor power is shut down, the robot's momentum causes it to move some distance before it completely stops. The actual "Robot Stop Position" will be beyond the workspace. To stop the robot within the robot workspace, use the DCS Stop Position Prediction function. The stop position prediction is disabled by default.

- DCS position/speed check function (J567)

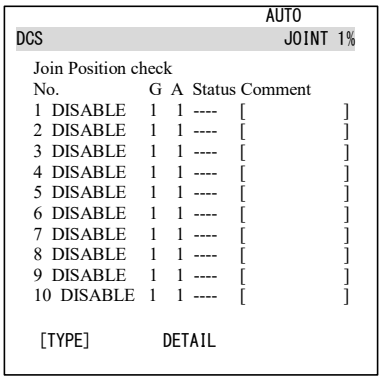
As an example, we shows the procedure to set ±30° for J2-axis in here. Refer to R-30*i*B/R-30*i*B Mate /R-30*i*B Plus Controller Dual check safety function Operator's Manual (B-83184EN) or R-30*i*A/R-30*i*A Mate Controller Dual check safety function Operator's Manual (B-83104EN) for details of other setting, function and DCS stop position prediction.

Setting procedure

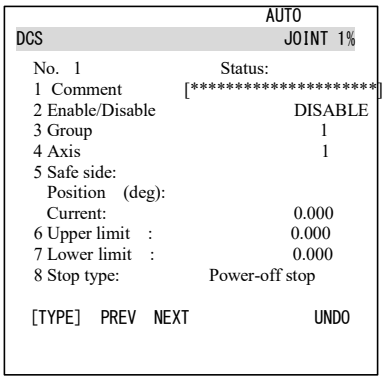
1 Press the [MENU] key to display the screen menu.
2 Press [0 NEXT] and press [6 SYSTEM].
3 Press the F1 ([TYPE]).
4 Select [DCS]. The following screen will be displayed.



5 Move the cursor to [1 Joint position check], then press the [DETAIL].

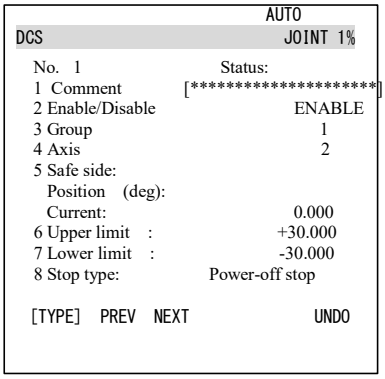


6 Move the cursor to [1], then press the [DETAIL].

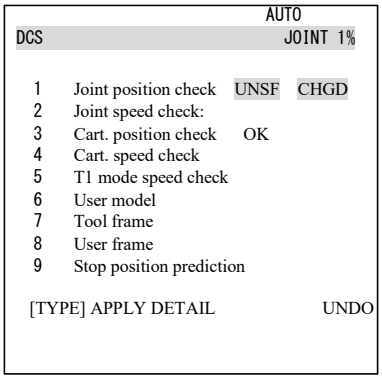


7 Move the cursor to [DISABLE], then press [CHOICE], set the status to [ENABLE].
8 Move the cursor to [Group], then input the robot group number, then press the [ENTER] key.
9 Move the cursor to [Axis], then input “2”, then press the [ENTER] key.
10 Move the cursor to [Upper limit] right side, then input “30”, then press the [ENTER] key.
11 Move the cursor to [Lower limit] right side, then input “-30”, then press the [ENTER] key.

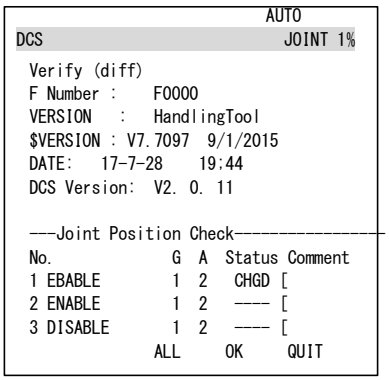
> ⚠ **WARNING**
> If only the operating space is set using Joint Position Check, the robot stops after it goes beyond the workspace. When the motor power is shut down, the robot’s momentum causes it to move some distance before it completely stops. The actual "Robot Stop Position" will be beyond the workspace. To stop the robot within the robot workspace, use the DCS Stop Position Prediction function. The stop position prediction is disabled by default.



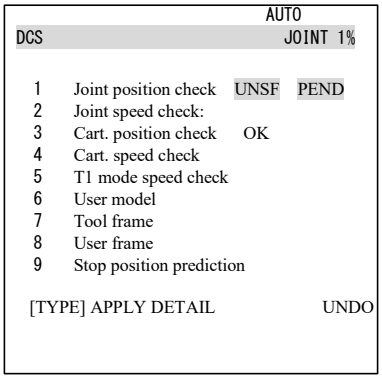
12 Press the [PREV] key two times, back to the first screen.



13 Press the [APPLY].
14 Input 4-digit password, then press the [ENTER] key. (Password default setting is “1111”.)
15 The following screen will be displayed, then press the [OK].



[CHGD] on the right side of [1 Joint position check] will change to [PEND].



16 Cycle the power of the controller in the cold start mode so the new settings are enabled.

> ⚠ **WARNING**
> You must cycle the power of the controller to enable the new setting. If you fail to do so, the robot does not work normally and it may injure personnel or damage the equipment.

6.2 ADJUSTABLE MECHANICAL STOPPER AND LIMIT SWITCH SETTING (OPTION)

For the J1, J2, and J3-axes, adjustable mechanical stopper (option) can be installed. It is possible to re-position adjustable mechanical stoppers. Change the position of the adjustable mechanical stoppers according to the desired movable range. For the J1-axis, the limit switch-based movable range can be used together. Refer to Section 6.3 and 6.4 for details.

Table 6.2 (a) motion range that can be set by the adjustable mechanical stopper and space between the upper and lower limits

Item		Settable motion range
J1-axis mechanical stopper, limit switch	Upper limit	Settable in steps of 7.5° in a range of -112.5° to +180°
	Lower limit	Settable in steps of 7.5° in a range of -180° to +112.5°
	Space between the upper and lower limits	A space of 67.5° or more is required.
J2-axis mechanical stopper (R-1000*i*A/80F/100F/130F /80H)	Upper limit	Settable in steps of 15° in a range of -75° to +90° A mechanical stopper is also provided at the upper limit +155° of the standard movable range.
	Lower limit	Settable in steps of 15° in a range of -60° to +105° A mechanical stopper is also provided at the lower limit -90°of the standard movable range.
	Space between the upper and lower limits	A space of 30° or more is required.
J2-axis mechanical stopper (R-1000*i*A/120F-7B)	Upper limit	Settable in steps of 15° in a range of -30° to +90° A mechanical stopper is also provided at the upper limit +155° of the standard movable range.
	Lower limit	Settable in steps of 15° in a range of -15° to +150° A mechanical stopper is also provided at the lower limit -45°of the standard movable range.
	Space between the upper and lower limits	A space of 30° or more is required.
J3-axis mechanical stopper	Upper limit	Settable in steps of 15° in a range of -15° to +105°. A mechanical stopper is also provided at the upper limit +140° of the standard movable range.
	Lower limit	Settable in steps of 15° in a range of 0° to +120° A mechanical stopper is also provided at the lower limit -82°of the standard movable range.
	Space between the upper and lower limits	A space of 30° or more is required.

NOTE
1 If the newly set operation range does not include 0°, you must change it zero degree mastering so that 0° is included.
2 When adjustable mechanical stopper (option) is ordered, mounting bolt is attached.
3 When motion range is changed by adjustable mechanical stopper, be sure to set the motion range of soft same refer to Subsection 6.2.2.

6.2.1 Installing adjustable mechanical stopper option

Attach adjustable mechanical stoppers referring to Fig. 6.2.1 (a) to (j).

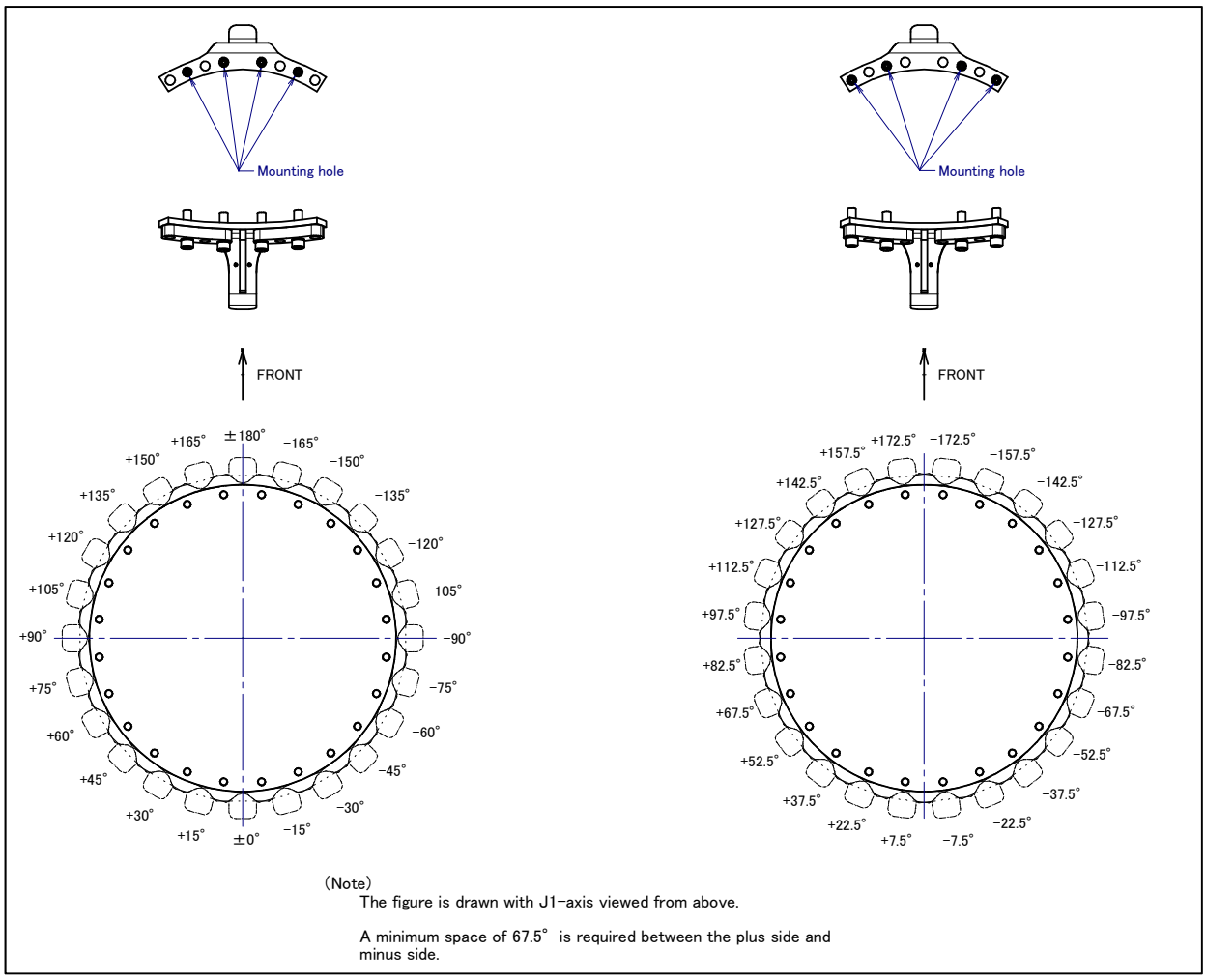


Fig. 6.2.1 (a) Mounting the J1-axis mechanical adjustable Stopper (Option)

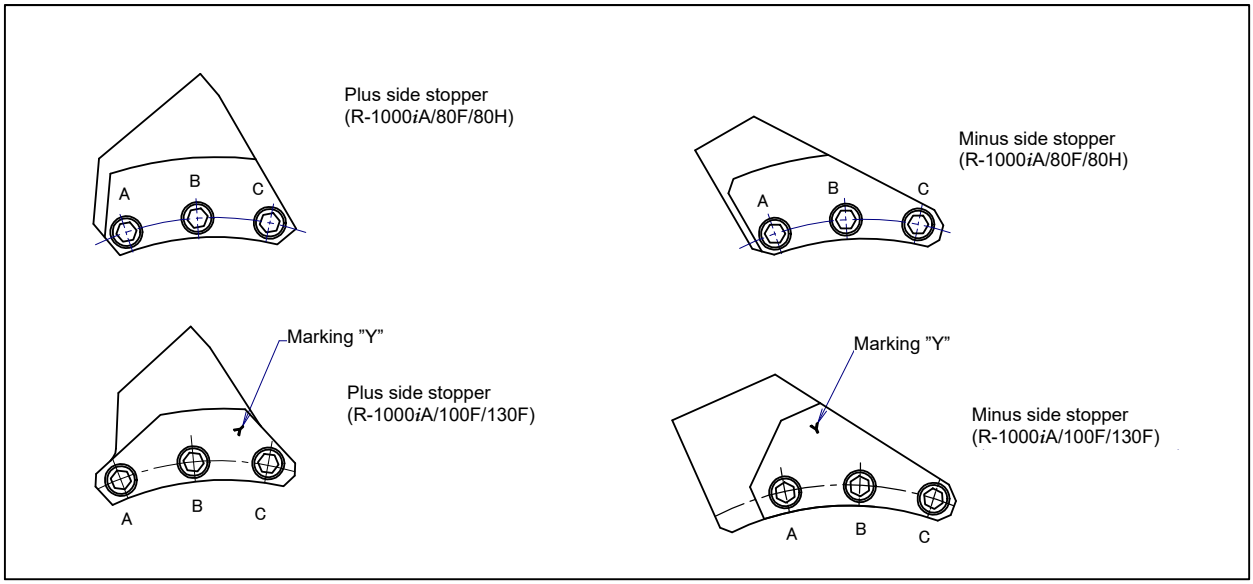


Fig. 6.2.1 (b) J2-axis adjustable mechanical stopper (R-1000*i*A/80F/100F/130F/80H)

Table 6.2.1 (a) Plus side stopper installation position and used bolt (R-1000*i*A/80F/100F/130F/80H)

Plus side stopper (deg)	Position		
	A	B	C
-75, -30, +15, +60	M12 x 45	M12 x 65	M12 x 45
-60, -15, +30, +75	M12 x 65	M12 x 45	M12 x 45
-45, 0, +45, +90	M12 x 45	M12 x 45	M12 x 65

Table 6.2.1 (b) Minus side stopper installation position and used bolt (R-1000*i*A/80F/100F/130F/80H)

Minus side stopper (deg)	Position		
	A	B	C
-60, -15, +30, +75	M12 x 45	M12 x 65	M12 x 45
-45, 0, +45, +90	M12 x 65	M12 x 45	M12 x 45
-30, +15, +60, +105	M12 x 45	M12 x 45	M12 x 65

Note) When you use the M12 x 65 bolt, assemble the stopper into the J2 base with the stopper base

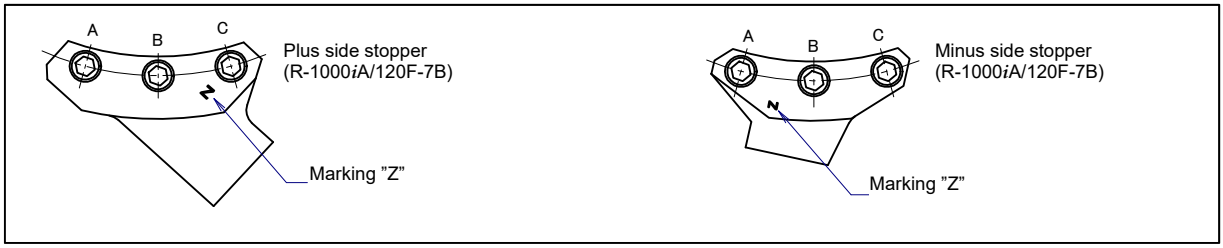


Fig. 6.2.1 (c) J2-axis adjustable mechanical stopper (R-1000*i*A/120F-7B)

Table 6.2.1 (c) Plus side stopper installation position and used bolt (R-1000*i*A/120F-7B)

Plus side stopper (deg)	Position		
	A	B	C
0, +45, +90	M12 x 45	M12 x 65	M12 x 45
-30, +15, +60	M12 x 65	M12 x 45	M12 x 45
-15, +30, +75	M12 x 45	M12 x 45	M12 x 65

Table 6.2.1 (d) Minus side stopper installation position and used bolt (R-1000*i*A/120F-7B)

Minus side stopper (deg)	Position		
	A	B	C
+15, +60, +105, +150	M12 x 45	M12 x 65	M12 x 45
-15, +30, +75, +120	M12 x 65	M12 x 45	M12 x 45
0, +45, +90, +135	M12 x 45	M12 x 45	M12 x 65

Note) When you use the M12 x 65 bolt, assemble the stopper into the J2 base with the stopper base

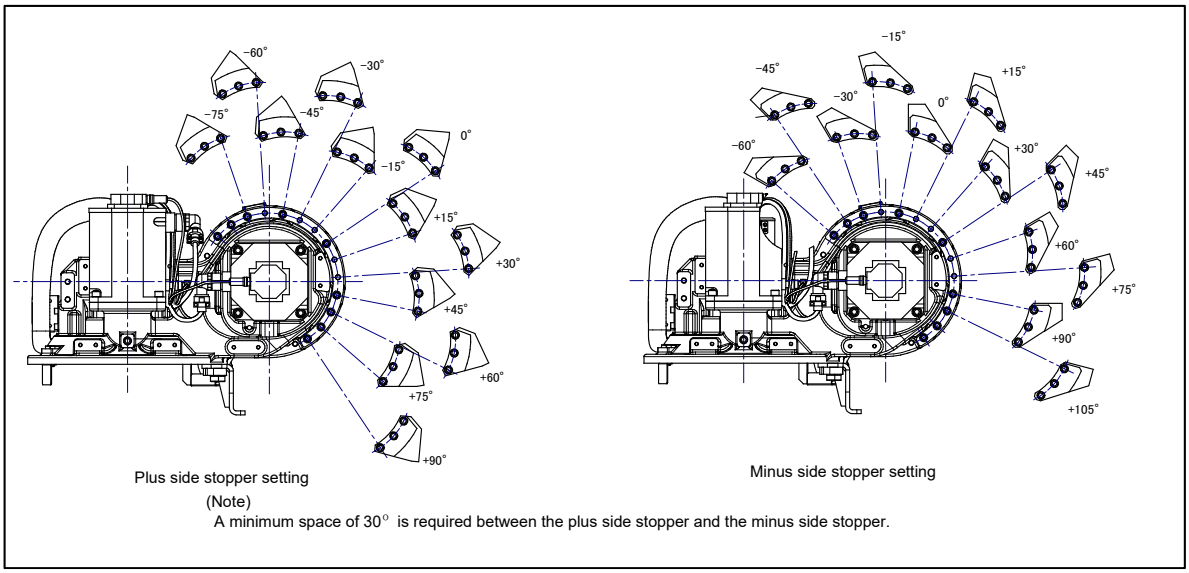


Fig. 6.2.1 (d) Mounting the J2-axis mechanical adjustable Stopper (Option)
(R-1000*i*A/80F/100F/130F/80H)

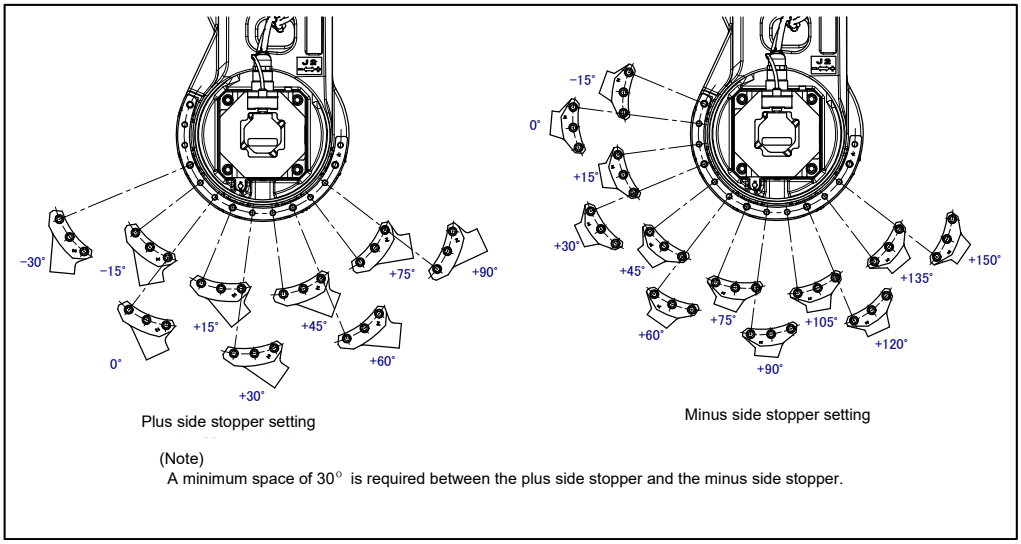


Fig. 6.2.1 (e) Mounting the J2-axis mechanical adjustable Stopper (Option)
(R-1000*i*A/120F-7B)

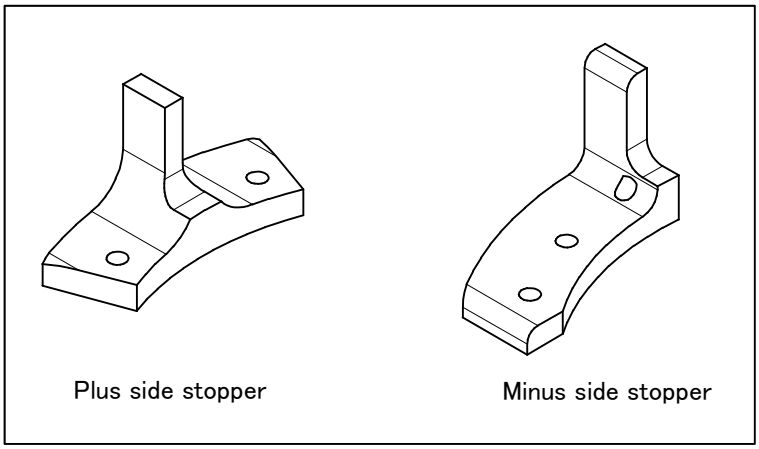


Fig. 6.2.1 (f) J3-axis adjustable mechanical stopper

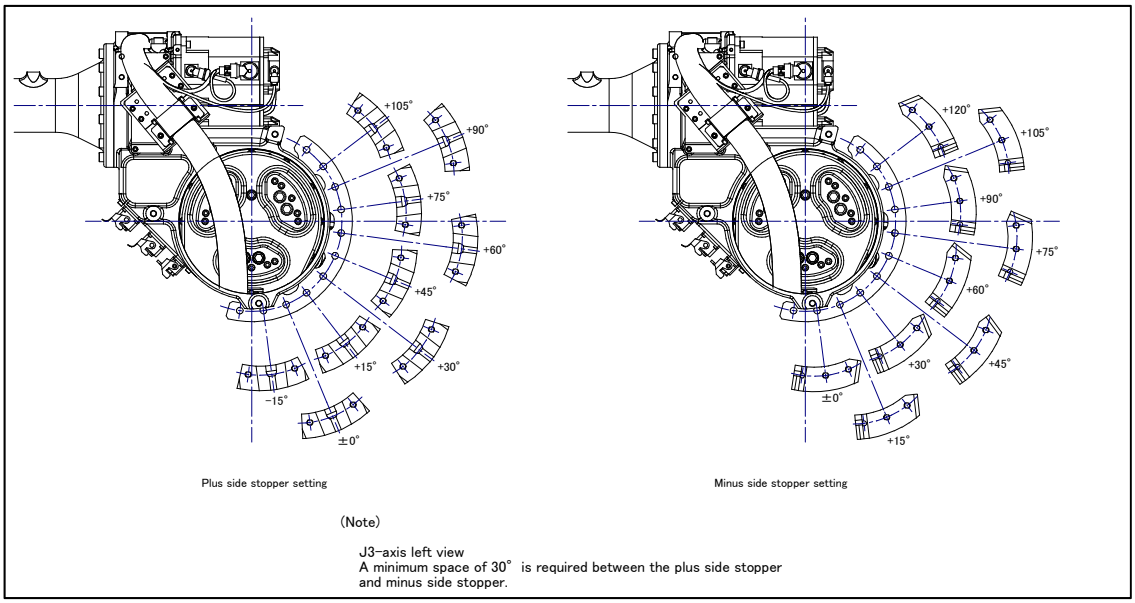


Fig. 6.2.1 (g) Mounting the J3-axis mechanical adjustable Stopper (Option)

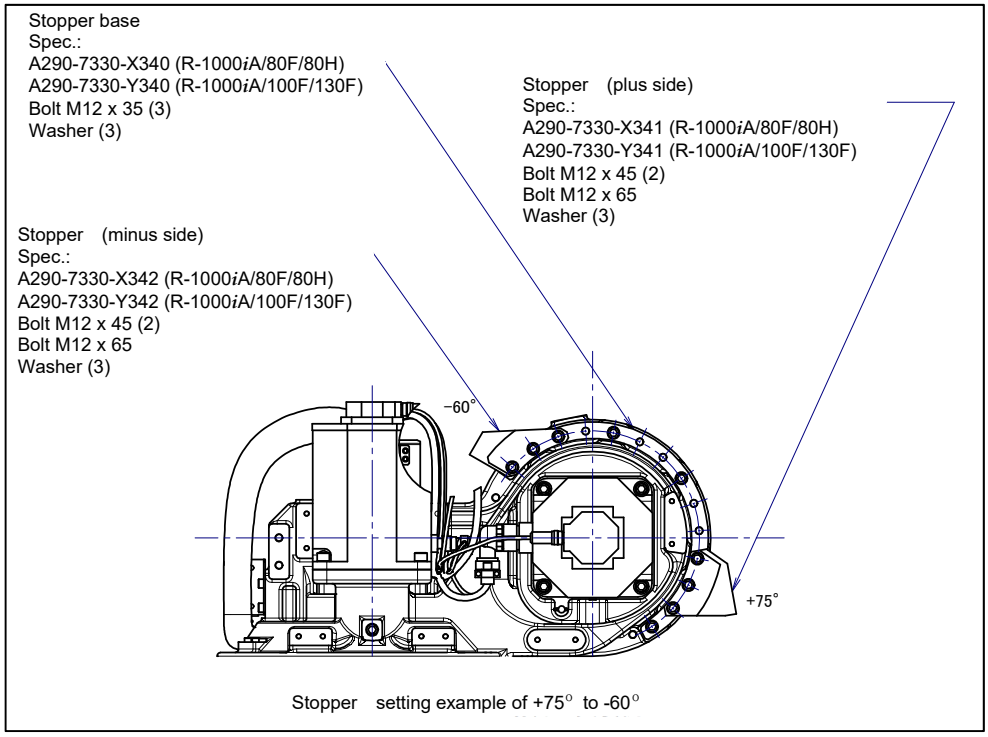


Fig. 6.2.1 (h) Setting example of J2-axis adjustable mechanical stopper (R-1000*i*A/80F/100F/130F/80H)

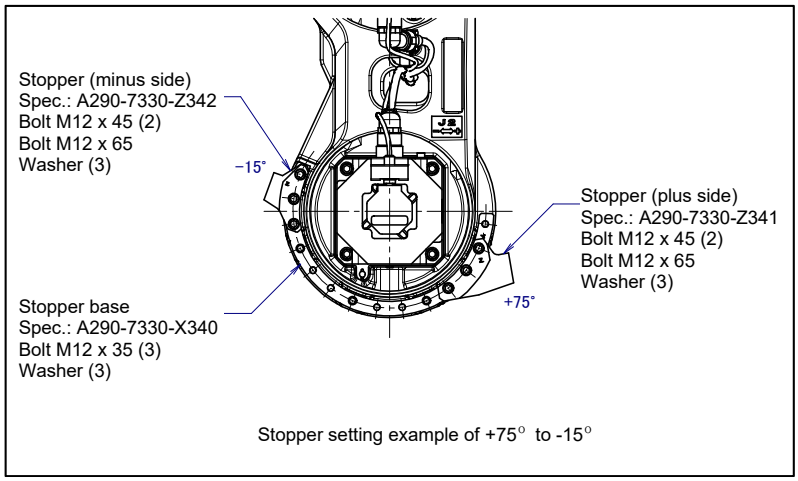


Fig. 6.2.1 (i) Setting example of J2-axis adjustable mechanical stopper (R-1000*i*A/120F-7B)

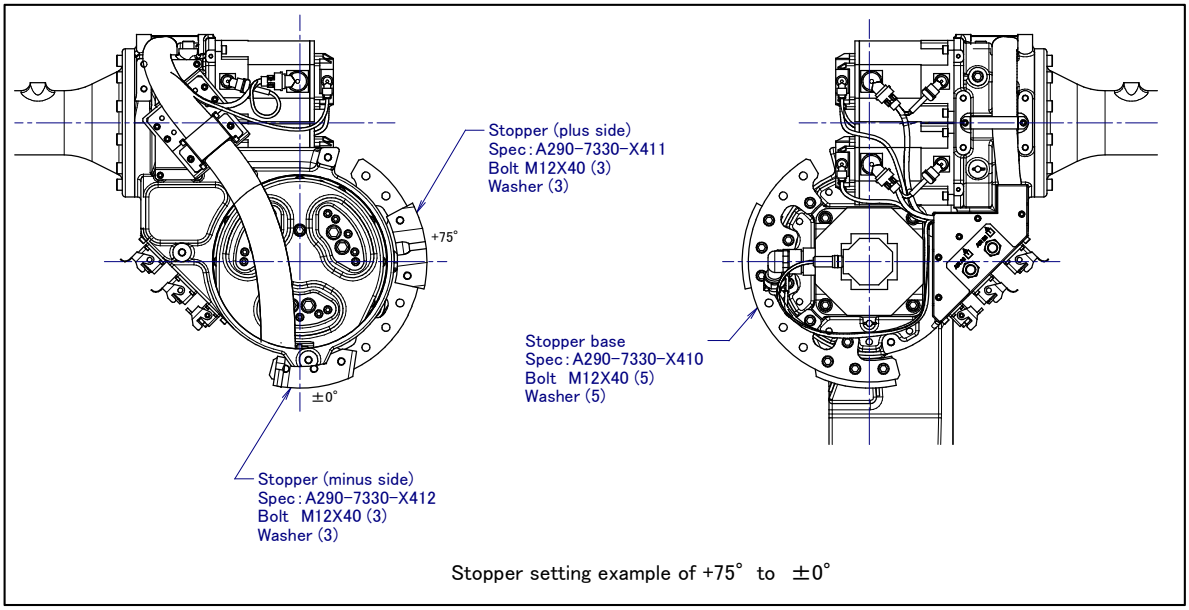


Fig. 6.2.1 (j) Setting example of J3-axis adjustable mechanical stopper

6.2.2 Changing the parameter setting

Setting procedure

1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE].
4 Select [Axis Limits]. The following screen will be displayed.

System Axis Limits JOINT 100%
Group1 1/16

AXIS	GROUP	LOWER	UPPER	
1	1	-180.00	180.00	deg
2	1	-90.00	155.00	deg
3	1	-180.00	180.00	deg
4	1	-360.00	360.00	deg
5	1	-125.00	125.00	deg
6	1	-360.00	360.00	deg
7	1	0.00	0.00	mm
8	1	0.00	0.00	mm
9	1	0.00	0.00	mm

[TYPE]

NOTE
0.00 indicates the robot does not have these axes.

5 Move the cursor to the axis limit to be set. Type the new value using the numeric keys on the teach pendant. In this time, set the axial upper limit and the lower limit at the position same as adjustable mechanical stoppers are attached.

System Axis Limits 2/16

AXIS	GROUP	LOWER	UPPER	
2	1	-90.00	155.00	deg

[TYPE]

6 Turn off the controller and then turn it back on again in the cold start mode so the new information can be used.

⚠ WARNING
1 You must turn off the controller and then turn it back on to use the new information; otherwise, the old settings remain valid and could cause personnel injury or equipment damage.
2 After changing system variables, be sure to run the robot at a low speed and make sure that the robot stops at the ends of the stroke.
3 If a collision should occur, the adjustable mechanical stopper becomes deformed to absorb energy, so that the robot can stop safely. If the stopper is deformed by mistake, replace it.
4 Do not depend on parameter settings to control the motion range of your robot.

6.2.3 The maximum stopping distance (position) of adjustable mechanical stopper

The adjustable mechanical stopper is a mechanism that can be adjusted in its position. The robot can work safely inside the adjusted motion range, up to the maximum range as shown in Table 6.2.3 (a) and Fig. 6.2.3 (a) to (d). A robot attempting to travel beyond this set range of motion, will be stopped by these stoppers, by collision; and therefore the robot will remain contained within the setup range.
Stopping the robot will cause the mechanical stopper to be “transformed” (means : permanently damaged). Be sure to replace the deformed stopper before using the robot again.

Table 6.2.3 (a) The maximum stopping distance (position) of adjustable mechanical stopper

	Plus side	Minus side
J1-axis	+25°	-25°
J2-axis	+20°	-22°
J3-axis	+10°	-20°

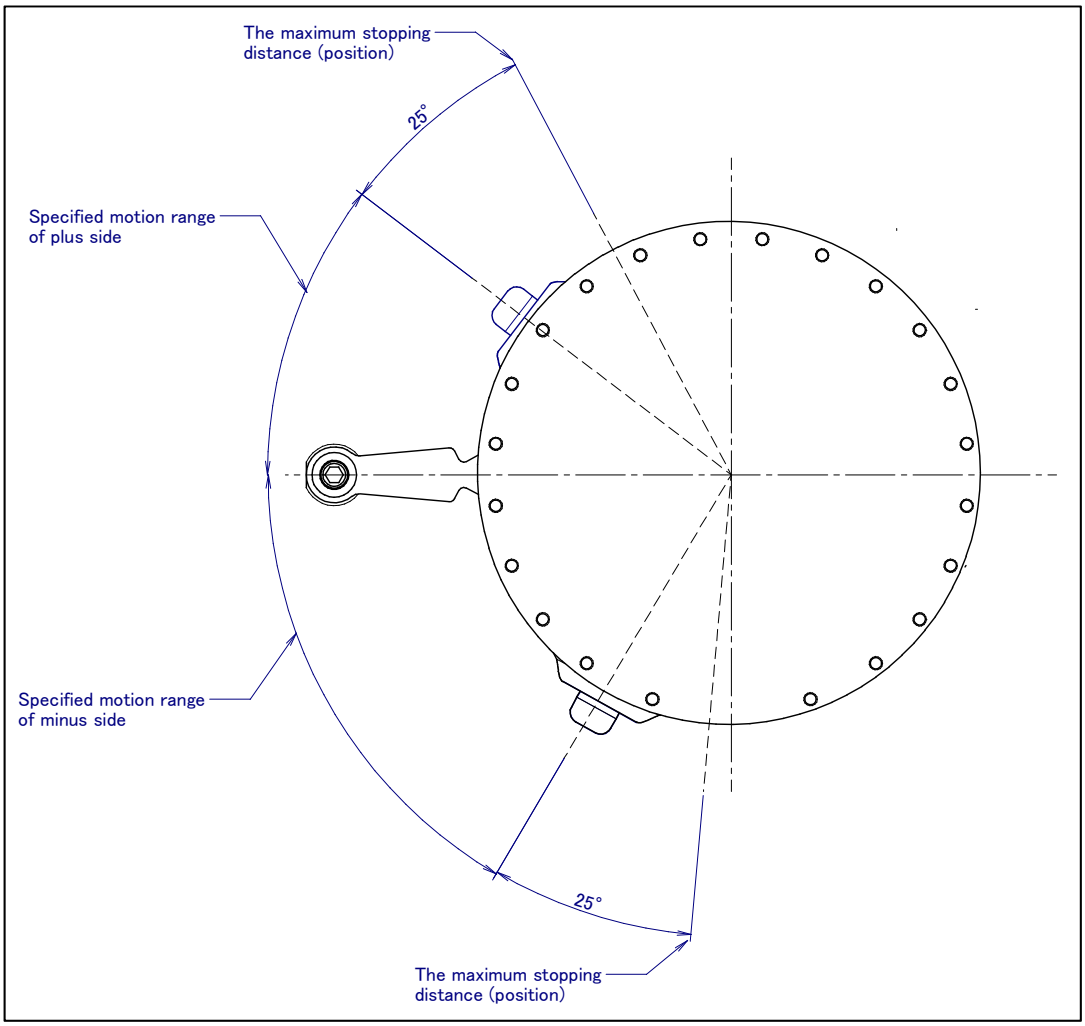


Fig. 6.2.3 (a) The maximum stopping distance (position) of adjustable mechanical stopper of J1-axis

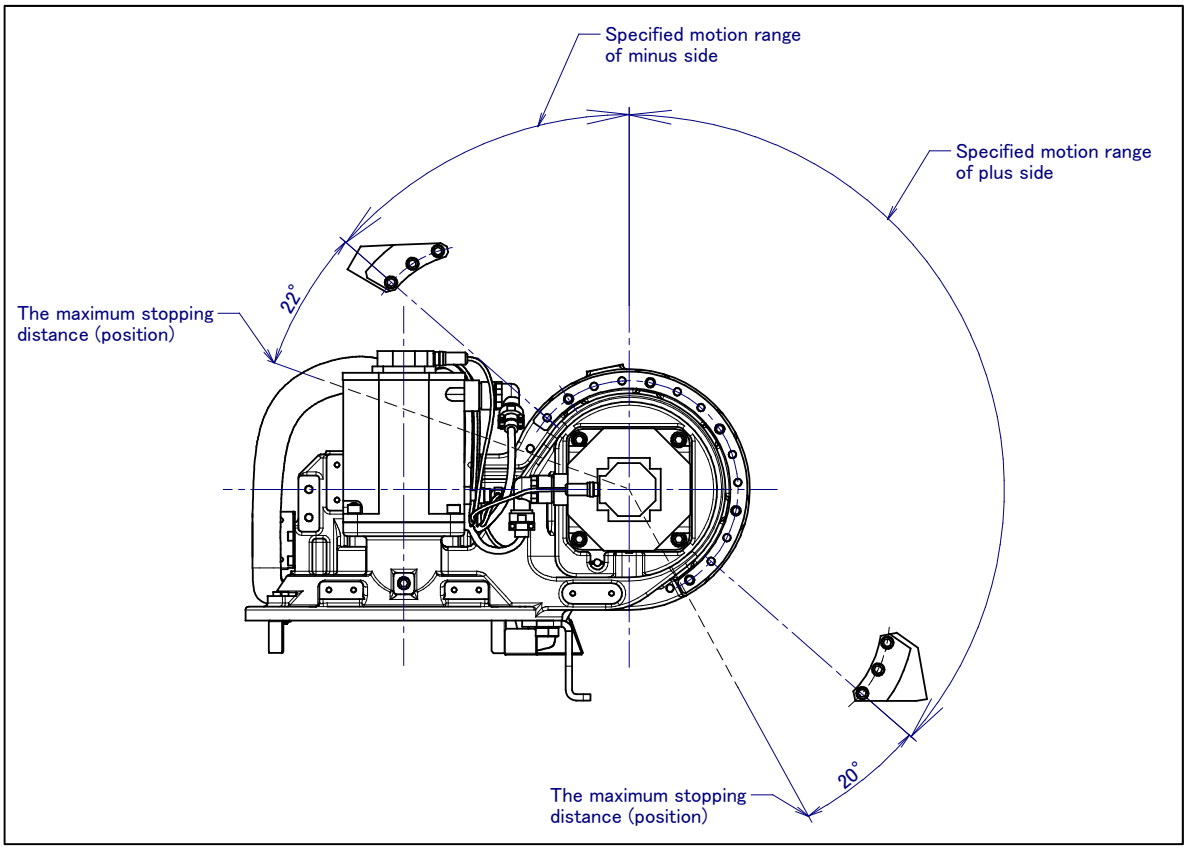


Fig. 6.2.3 (b) The maximum stopping distance (position) of adjustable mechanical stopper of J2-axis (R-1000*i*A/80F/100F/130F/80H)

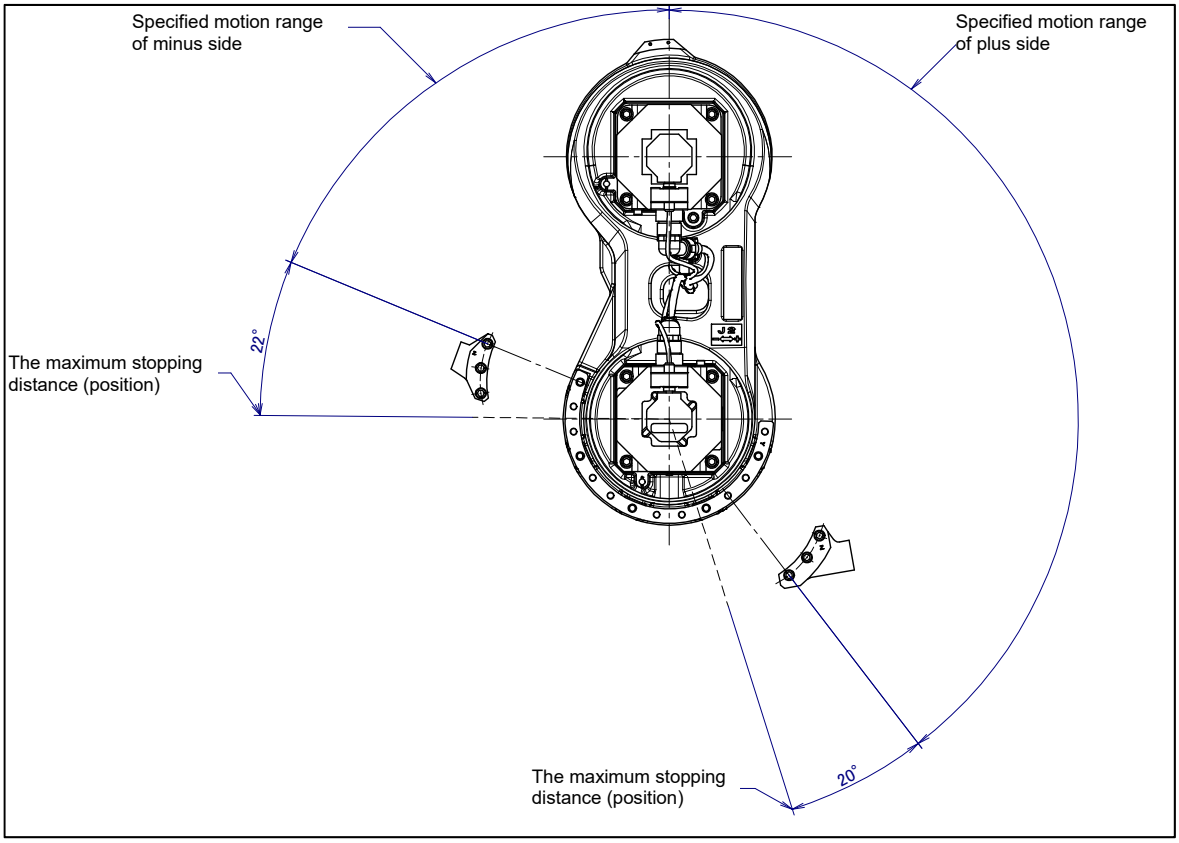


Fig. 6.2.3 (c) The maximum stopping distance (position) of adjustable mechanical stopper of J2-axis (R-1000*i*A/120F-7B)

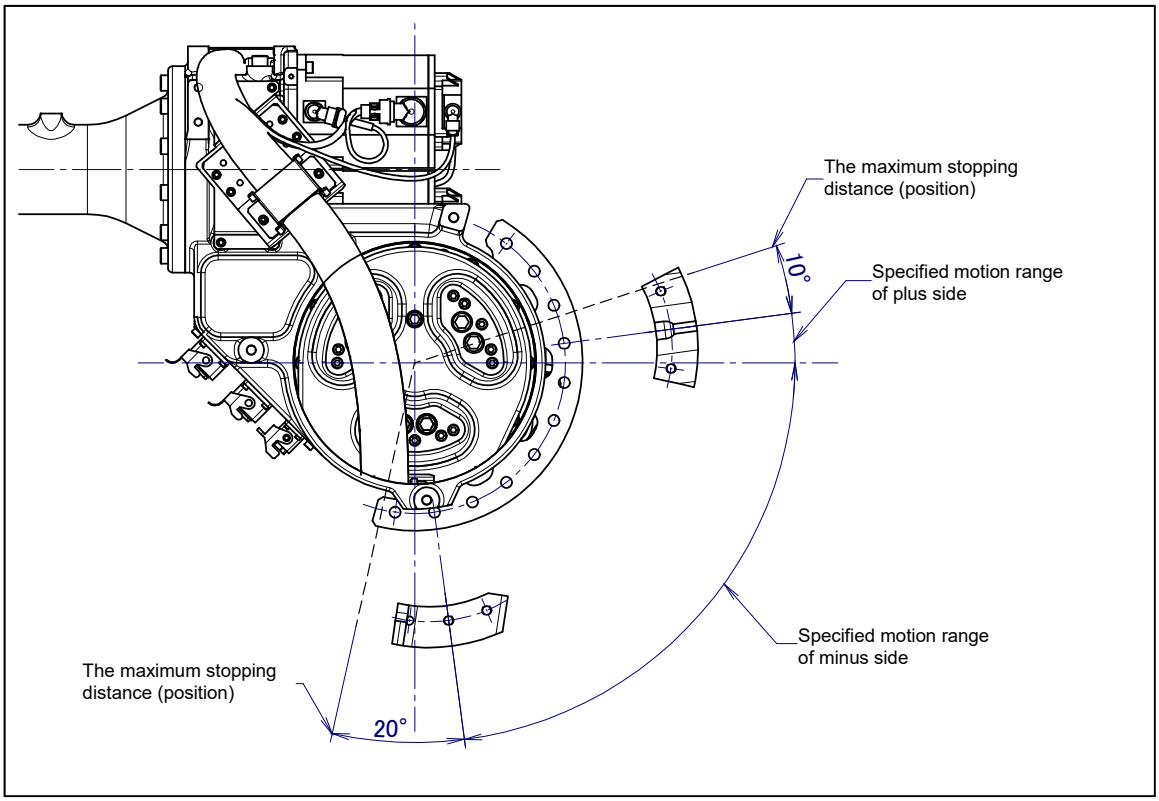


Fig. 6.2.3 (d) The maximum stopping distance (position) of adjustable mechanical stopper of J3-axis

6.3 CHANGING THE MOTION RANGE BY THE LIMIT SWITCH (OPTION)

The limit switch is an over travel switch, which interrupts power to the servo motor and stops the robot when turned on. The limit switch is optionally provided for the J1-axis.
To change the motion range by the limit switch, move the dog. The following figure shows the relationship between the dog position and the motion range.
The dog of the J1-axis is placed in the same position as with the mechanical stopper.

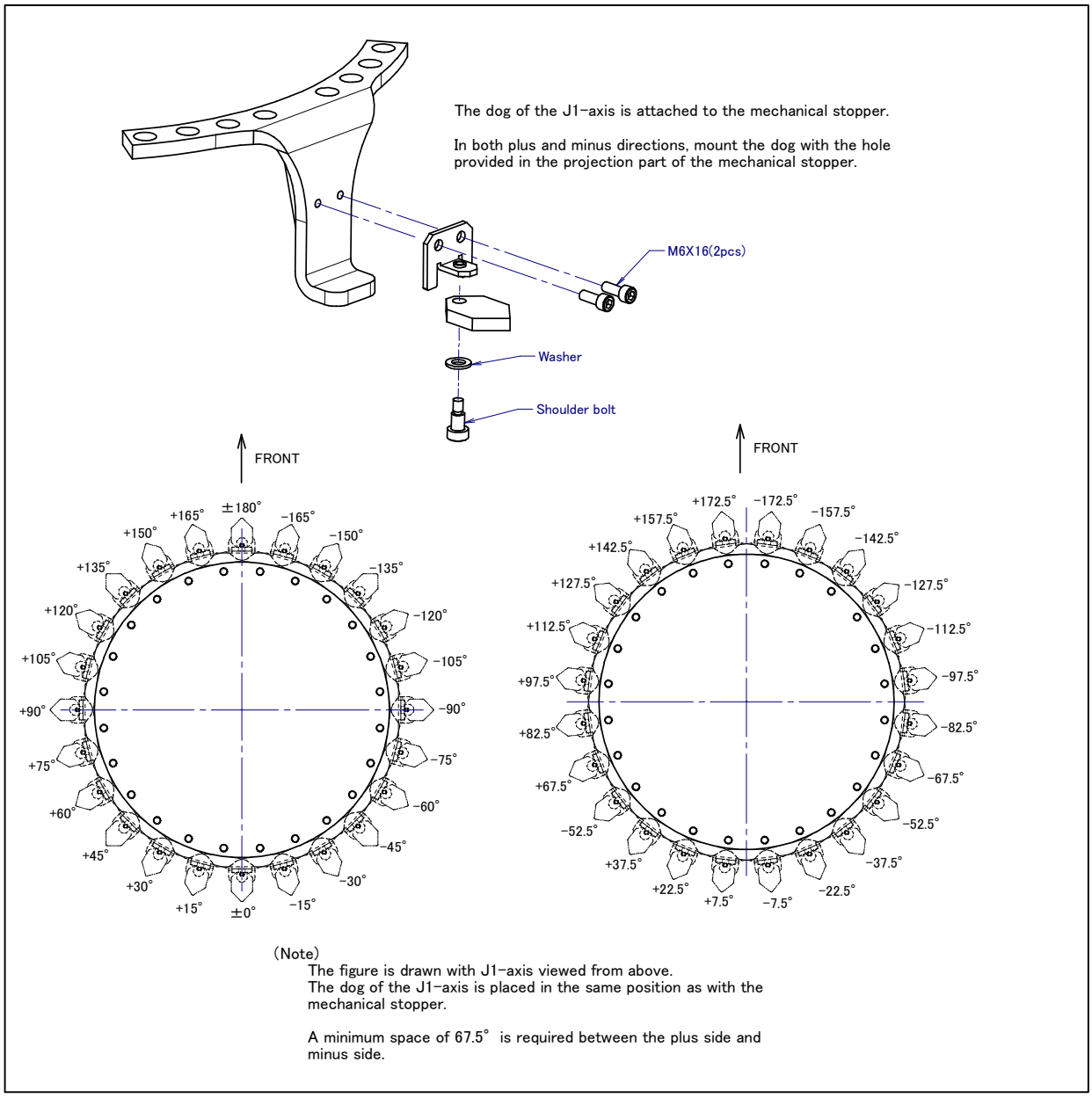


Fig. 6.3 (a) Dog position and motion range of J1-axis (Option)

6.4 ADJUSTING LIMIT SWITCH (OPTION)

After the motion range is changed by the adjustable mechanical stopper and limit switch, be sure to make adjustment.

ADJUSTING PROCEDURE

1 Set the $MOR_GRP.$CAL_DONE system parameter to FALSE. This disables the motion limit specified by the software. As a result, the operator can rotate the robot by a jog feed which goes beyond the motion limit.
2 Loosen the following bolts that hold the limit switch.
J1-axis : M8 x 12 2 pcs M4 x 25 2 pcs
3 Move the limit switch so that the robot activates it at about 0.5° before the stroke end. Step on the dog, and position the limit switch in such a place that only one of the step-on allowance indication lines at the tip of the switch is hidden.
4 When the limit switch operates and detects overtravel (OT), the robot stops, and an error message, "OVERTRAVEL", is displayed. To restart the robot, hold on the [SHIFT] key and press the [RESET] key. Then, while holding on the SHIFT key, move the adjusting axis off the OT limit switch by jogging in joint mode.
5 Check that the robot also activates the limit switch when the robot is approx. 0.5° from the opposite stroke end in the same way as above. If the limit switch does not operate at the position, adjust the position of the switch again.
6 Set the $MOR_GRP.$CAL_DONE system parameter to TRUE.
7 Turn off the power, then turn it on again to restart the controller.

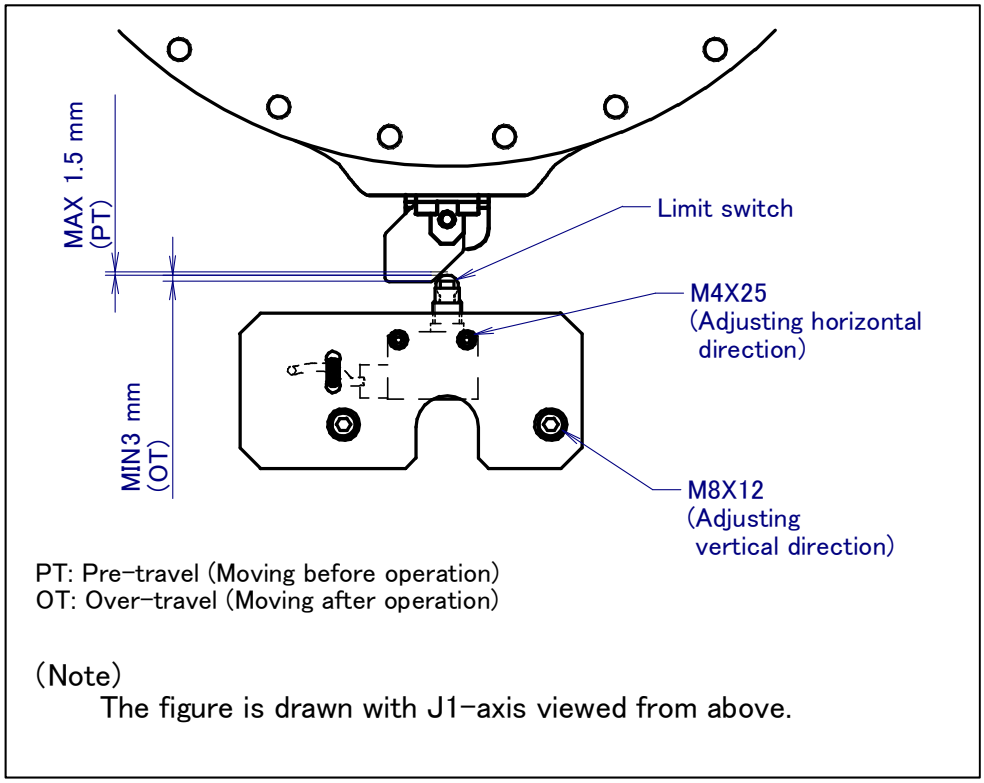


Fig. 6.4 (a) Adjusting J1-axis limit switch (Option)

7 CHECKS AND MAINTENANCE

Optimum performance of the robot can be maintained by performing the checks and maintenance procedures presented in this chapter. (See the APPENDIX A PERIODIC MAINTENANCE TABLE.)

NOTE
The periodic maintenance procedures described in this chapter assume that the FANUC robot is used for up to 3840 hours a year. In cases where robot use exceeds 3840 hours/year, adjust the given maintenance frequencies accordingly. The ratio of actual operation time/year vs. the 3840 hours/year should be used to calculate the new (higher) frequencies. For example, when using the robot 7680 hours a year with a recommended maintenance interval of 3 years or 11520 hours, use the following calculation to determine the maintenance frequency: 3 years / 2 = perform maintenance every 1.5 years.

7.1 CHECKS AND MAINTENANCE

7.1.1 Daily Checks

Check the following items when necessary before daily system operation.

Check items	Check points and management
Oil seepage	Check to see if there is oil on the sealed part of each joint. If there is an oil seepage, clean it. **⇒"7.2.1 Confirmation of Oil Seepage"**
Air control set	(When air control set is used) **⇒"7.2.2 Confirmation of the Air Control Set"**
Vibration, abnormal noises	Check whether vibration or abnormal noises occur. When vibration or abnormal noises occur, perform measures referring to the following section: **⇒"9.1 TROUBLESHOOTING"(symptom : Vibration, Noise)**
Positioning accuracy	Check that the taught positions of the robot have not deviated from the previously taught positions. If displacement occurs, perform the measures as described in the following section: **⇒"9.1 TROUBLESHOOTING"(symptom : Displacement)**
Peripheral equipment for proper operation	Check whether the peripheral equipment operate properly according to commands from the robot and the peripheral equipment.
Brakes for each axis	Check that the end effector drops 0.2 mm or less when the servo power is turned off. If the end effector (hand) drops more than the prescribed amount, perform the measures as described in the following section: **⇒"9.1 TROUBLESHOOTING"(symptom : Dropping axis)**
Warnings	Check whether unexpected warnings occur in the alarm screen on the teach pendant. If unexpected warnings occur, perform the measures as described in the following manual: **⇒"R-30*i*B/R-30*i*B Mate/R-30*i*B Plus/R-30*i*B Mate Plus/R-30*i*B Compact Plus /R-30*i*B Mini Plus CONTROLLER OPERATOR'S MANUAL (Alarm Code List)(B-83284EN-1) or R-30*i*A/R-30*i*A Mate CONTROLLER OPERATOR'S MANUAL (Alarm Code List)(B-83124EN-6)"**

7.1.2 Periodic Checks and Maintenance

Check the following items at the intervals recommended below based on the period the accumulated operating time, whichever comes first. (○ : Item needs to be performed.)

Check and maintenance intervals (Period, Accumulated operating time)						Check and maintenance items	Check points, management and maintenance methods	Periodic maintenance table No.
1 month 320h	3 months 960h	1 year 3840h	1.5 years 5760h	3 years 11520h	4 years 15360h			
○ Only 1st check	○					Cleaning the controller ventilation system	Confirm the controller ventilation system is not dusty. If dust has accumulated, remove it.	22
	○					Check the external damage or peeling paint	Check whether the robot has external damage or peeling paint due to the interference with the peripheral devices. If an interference occurs, eliminate the cause. Also, if the external damage is serious, and causes a problem in which the robot will not operate, replace the damaged parts.	1
	○					Check the damages of the cable protective sleeve	Check whether the mechanical unit cable protective sleeves for holes or tears. If damage is found, replace the cable protective sleeve. If the cable protective sleeve is damaged due to the interference with peripheral devices, eliminate the cause. **⇒"7.2.3 Check the Mechanical Unit Cables and Connectors"**	2
	○					Check the wear debris of the J1-axis swing stopper	Check whether wear debris is generated on the J1-axis swing stopper rotation part. If serious wear occurs on the part that generated the wear debris, replace the part.	3
	○					Check for water	Check whether the robot is subjected to water or cutting oils. If liquid was found, remove the cause, and wipe the liquid off.	4
	○ Only 1st check	○				Check for damages to the teach pendant cable, the operation box connection cable or the robot connection cable	Check whether the cable connected to the teach pendant, operation box and robot are unevenly twisted or damaged. If damage is found, replace the damaged cables.	21
	○ Only 1st check	○				Check for damage to the mechanical unit cable (movable part)	Observe the movable part of the mechanical unit cable, and check for damage. Also, check whether the cables are excessively bent or unevenly twisted. **⇒"7.2.3 Check the Mechanical Unit Cables and Connectors"**	5
	○ Only 1st Check	○				Check for damage to the end effector (hand) cable	Check whether the end effector cables are unevenly twisted or damaged. If damage is found, replace the damaged cables.	6
	○ Only 1st check	○				Check the connection of each axis motor and other exposed connectors	Check the connection of each axis motor and other exposed connectors. **⇒"7.2.3 Check the Mechanical Unit Cables and Connectors"**	7

Check and maintenance intervals (Period, Accumulated operating time)						Check and maintenance items	Check points, management and maintenance methods	Periodic maintenance table No.
1 month 320h	3 months 960h	1 year 3840h	1.5 years 5760h	3 years 11520h	4 years 15360h			
	○ Only 1st check	○				Retightening the end effector mounting bolts	Retighten the end effector mounting bolts. Refer to the following section for tightening torque information: **⇒"4.1 END EFFECTOR INSTALLATION TO WRIST"**	8
	○ Only 1st check	○				Retightening the external main bolts	Retighten the bolts which were installed, removed, or exposed during inspection. Refer to the recommended bolt tightening torque guidelines at the end of the manual. Some bolts are attached with adhesive. If the bolts are tightened with greater than the recommended torque, the adhesive might be removed. Therefore, follow the recommended bolt tightening torque guidelines when retightening the bolts.	9
	○ Only 1st check	○				Check the fixed mechanical stopper and the adjustable mechanical stopper	Check that there is no evidence of a collision on the fixed mechanical stopper, the adjustable mechanical stopper, and check that the stopper mounting bolts are not loose. Check that the J1-axis swing stopper rotates smoothly. **⇒"7.2.4 Check of Fixed Mechanical Stopper and Adjustable Mechanical Stopper"**	10
	○ Only 1st check	○				Clean spatters, sawdust and dust	Check that spatters, sawdust, or dust does not exist on the robot main body. If dust has accumulated, remove it. Especially, clean the robot movable parts well (each joint, and the cable protective sleeve).	11
	○ Only 1st check	○				Check the operation of the cooling fan	(When cooling fans are installed on the each axis motor) Check whether the cooling fans are operating correctly. If the cooling fans do not operate, replace them.	12
			○			Replacing the mechanical unit batteries	Replace the mechanical unit batteries. Regardless of operating time, replace batteries at 1.5 years. **⇒"7.3.1 Replacing the Batteries"**	13
				○		Replacing the grease of drive mechanism	Replace the grease of each axis reducer and gearbox **⇒"7.3.2 Replacing the Grease of the Drive Mechanism"**	14 to 19
					○	Replacing the mechanical unit cable	Replace the mechanical unit cable Contact your local FANUC representative for information regarding replacing the cable.	20
					○	Replacing the controller batteries	Replace the controller batteries. Regardless of operating time, replace batteries at 4 years. **⇒Chapter 7 Replacing batteries of R-30*i*B/R-30*i*B Plus CONTROLLER MAINTENANCE MANUAL(B-83195EN) or R-30*i*B Mate CONTROLLER MAINTENANCE MANUAL (B-83525EN) or R-30*i*A CONTROLLER MAINTENANCE MANUAL (B-82595EN) or R-30*i*A CONTROLLER MAINTENANCE MANUAL(For Europe) (B-82595EN-1) or R-30*i*A CONTROLLER MAINTENANCE MANUAL(For RIA) (B-82595EN-2)"**	23

7.2 CHECK POINTS

7.2.1 Confirmation of Oil Seepage

Check items

Confirm whether there is oil seepage on the rotating parts of each joint axis.

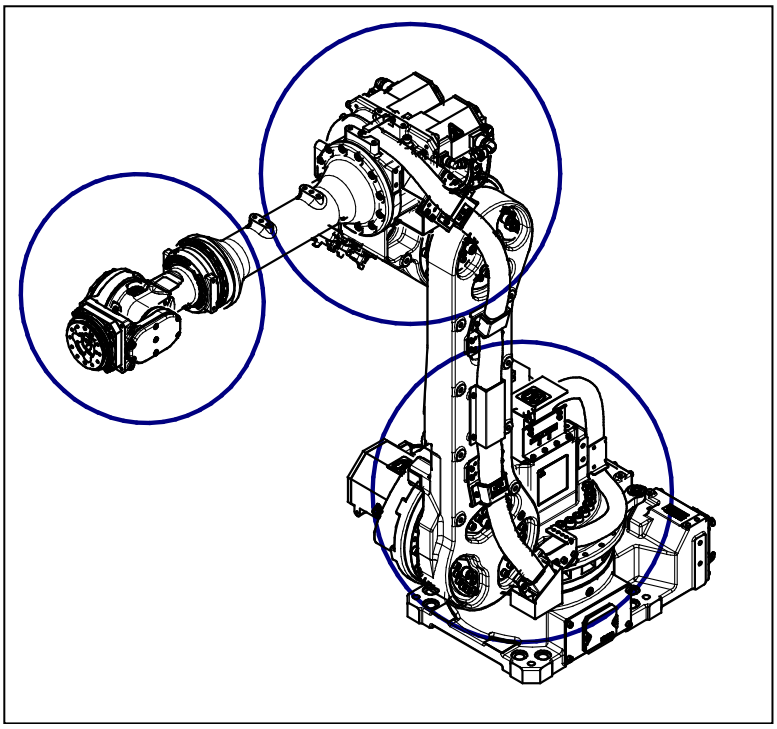


Fig. 7.2.1 (a) Check parts of oil seepage

Management

- Oil might accumulate on the outside of the seal lip depending on the movement condition or environment of the axis. If the oil viscosity changes, the oil might drip depending on the axis movement. To prevent oil spots, be sure to wipe away any accumulated oil under the axis components in Fig. 7.2.1 (a) before you operate the robot.
- Also, drive mechanisms might become hot and the internal pressure of the grease bath might rise by frequent repetitive movement and use in high temperature environments. In these cases, normal internal pressure can be achieved by venting the grease outlet. (When opening the grease outlet, refer to Subsection 7.3.3 and ensure that grease is not expelled onto the machine or tooling.)

> ⚠ **WARNING**
> Hot grease might eject suddenly when you open the grease outlet. Attach bags for collecting grease, and use appropriate protective equipment such as heat-resistant gloves, protective glasses, a face shield, or a body suit if necessary.

- If you must wipe oil frequently, and opening the grease outlet does not stop the seepage, perform the measures below.
  ⇒”9.1 TROUBLESHOOTING” (symptom：Grease leakage)

7.2.2 Confirmation of the Air Control Set (option)

When adopting an air control set, check the items below.

Item	Check items	Check points
1	Air pressure	Check the air pressure using the pressure gauge on the air control set as shown in Fig. 7.2.2 (a). If it does not meet the specified pressure of 0.49 to 0.69 MPa (5-7 kgf/cm^2), adjust it using the regulator pressure-setting handle.
2	Lubricator oil mist quantity	Check the number of oil drops during operation. If it does not meet the specified value (1 drop/10-20 sec), adjust it using the handle for lubricator adjustment. The lubricator becomes empty in about 10 to 20 days under normal operation.
3	Lubricator oil level	Check to see that the air control set oil level is within the specified level.
4	Leakage from hose	Check the joints, tubes, etc. for leaks. Retighten the joints or replace parts, as required.
5	Drain	Check the drain and release it. If the quantity of the drained liquid is significant, examine the setting of the air dryer on the air supply side.

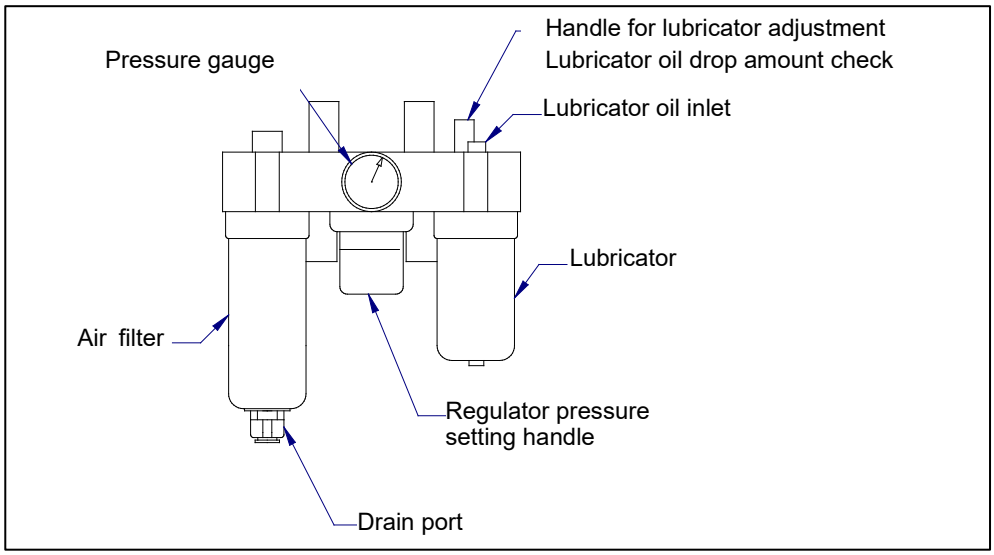


Fig. 7.2.2 (a) Air control set (option)

7.2.3 Check the Mechanical Unit Cables and Connectors

Check points of the mechanical unit cables

J1, J2, and J3 movable parts and fixed part cables can interfere with the peripheral equipment

* For the J1-axis, inspect the cables from above the J2 base and from the side by removing the metal plate on the side of the J1 base.

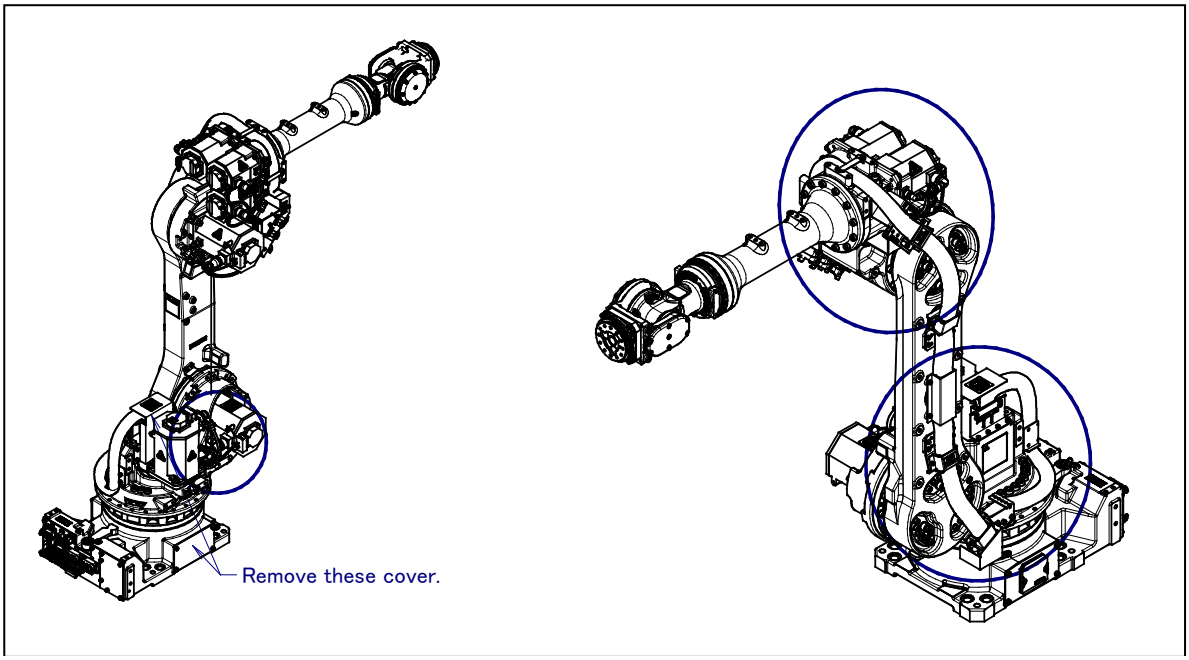


Fig. 7.2.3 (a) Inspection points of the mechanical unit cables

Check items

＜Cable protective sleeve＞

- Check that no holes or tears exist on the cable protective sleeves.
- If there is damage as shown in Fig. 7.2.3 (b), replace the cable protective sleeves.

Fig. 7.2.3 (b) Damage on the cable protective sleeve

＜Cables＞
- Check that there is no wear or damage on the cable jacket.
- If the inside wire strands are exposed due to wear or damage, replace the cables.

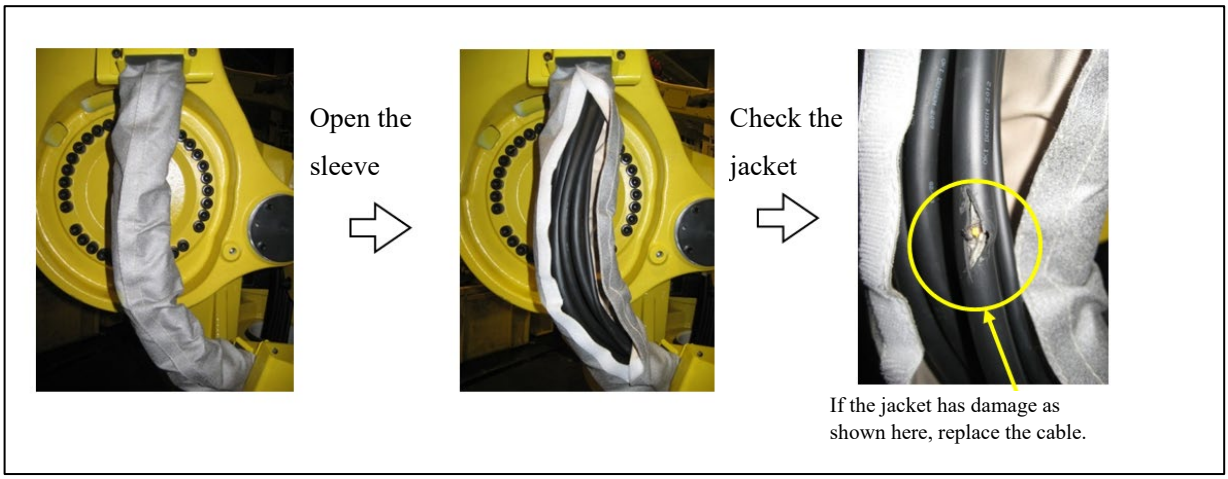


Fig. 7.2.3 (c) Cable check method

Inspection points of the connectors
- Power/brake connectors of the motor exposed externally
- Robot connection cables, earth terminal and user cables

Check items
- Circular connector: Check the connector for tightness by turning it by hand.
- Square connector: Check the connector for engagement of its lever.
- Earth terminal: Check the terminal for tightness.

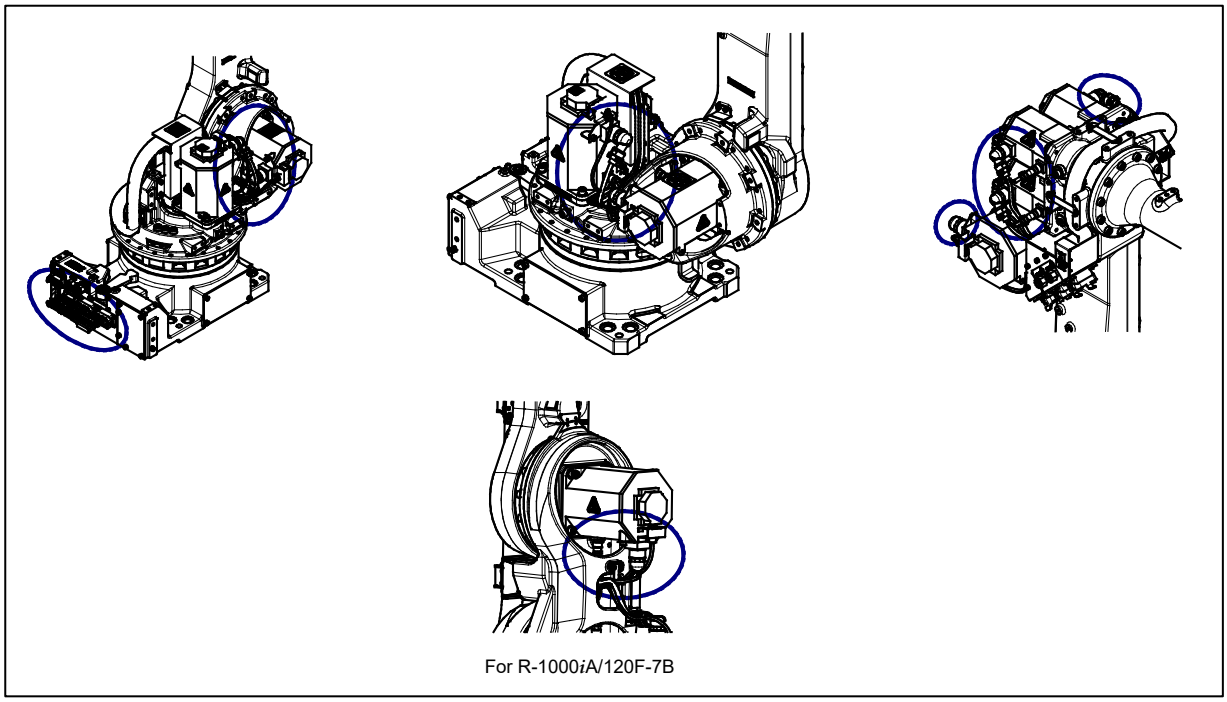


Fig. 7.2.3 (d) Connector Inspection points

7.2.4 Check of Fixed Mechanical Stopper and Adjustable Mechanical Stopper

- Check that there is no evidence of a collision on the mechanical stopper and the adjustable mechanical stopper. If there is evidence of a collision on the stopper, replace the parts.
- Check the tightness of the stopper mounting bolts. If they are loose, retighten them. Be sure to check the tightness of the mounting bolts of the J1-axis swing stopper.
- Check that J1-axis swing stopper rotates smoothly.
- Refer to Section 6.2 of the operator's manual for details regarding the adjustable mechanical stopper.

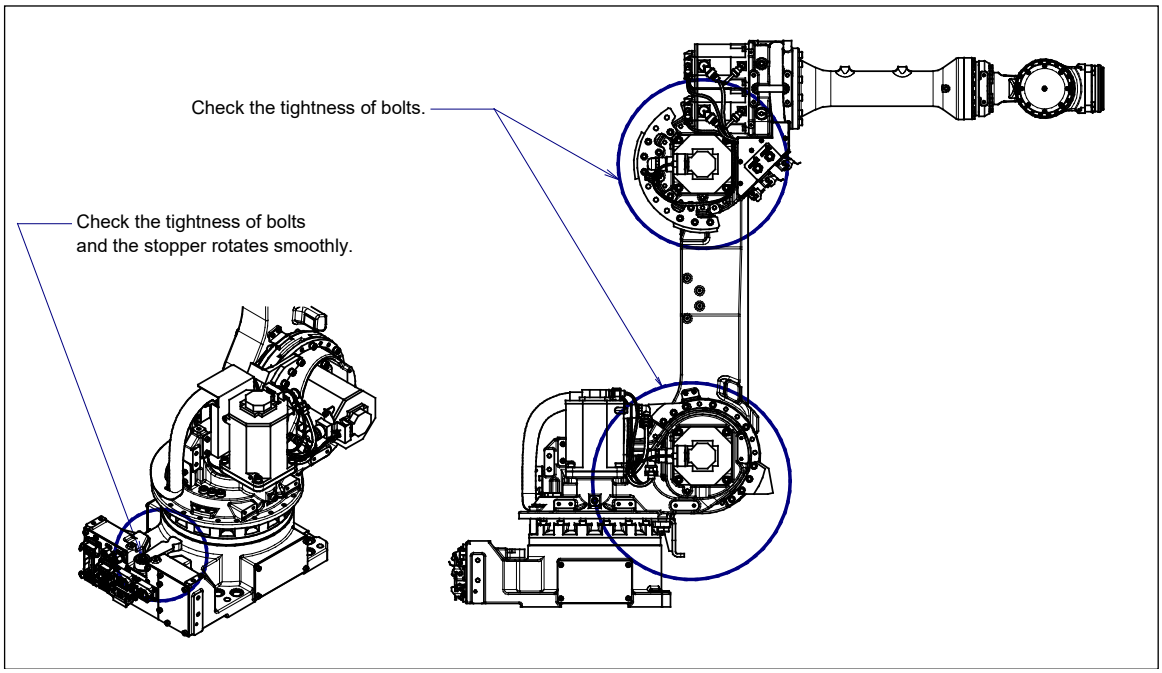


Fig. 7.2.4 (a) Check of fixed mechanical stopper and adjustable mechanical stopper

7.3 MAINTENANCE

7.3.1 Replacing the Batteries (1.5 year check (5760 hours) Periodic Maintenance)

The position data of each axis is preserved by the backup batteries. The batteries need to be replaced every 1.5 year. Also use the following procedure to replace when the backup battery voltage drop alarm occurs.

Procedure of replacing the battery

1 Press the EMERGENCY STOP button to stop the robot motion.

> **⚠ CAUTION**
> Be sure to keep the power turning on. Replacing the batteries with the power turned off causes all current position data to be lost. Therefore, mastering will be required again.

2 Remove the battery case cap. (Fig. 7.3.1 (a))
3 Take out the old batteries from the battery case.
4 Insert new batteries into the battery case while observing their correct orientation.
5 Close the battery case cap.

> **⚠ CAUTION**
> When using a robot with the severe dust/liquid protection option, remove the cover from the battery case as shown in Fig. 7.3.1 (b) to replace the battery. After replacing the battery, reinstall the cover. At this time, please be sure to replace gasket with new one for severe dust/liquid protection.

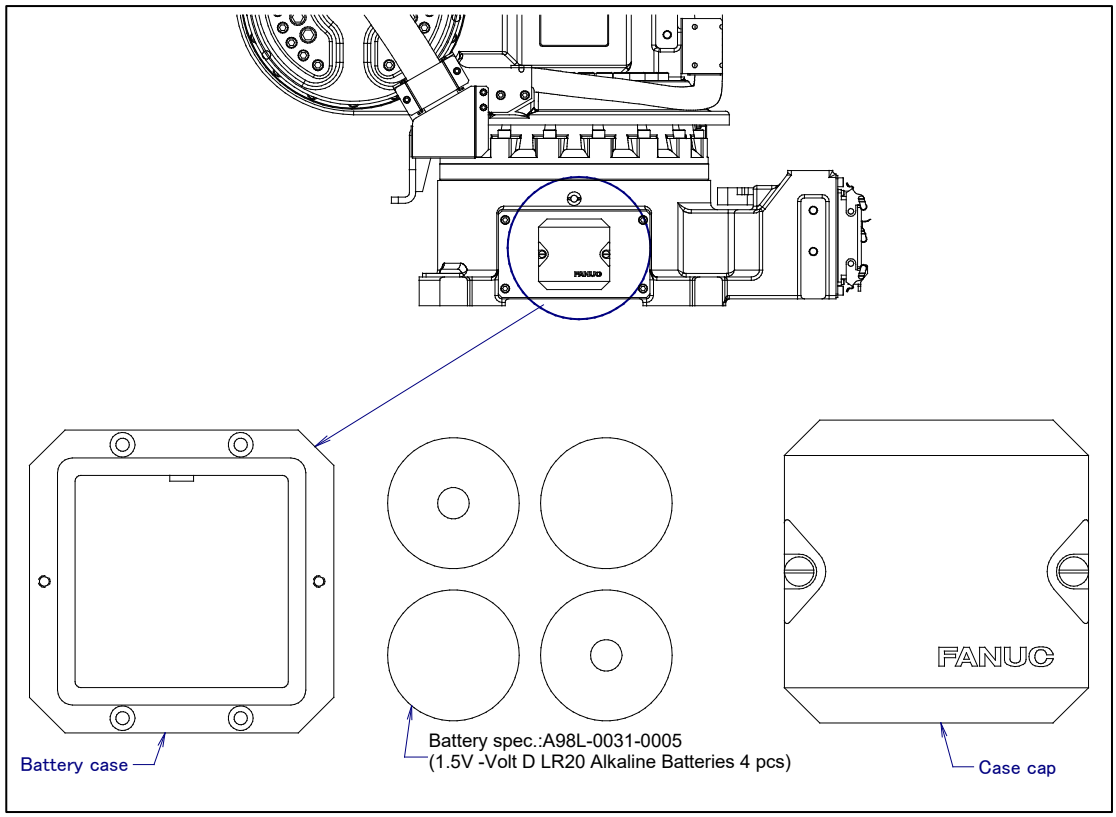


Fig. 7.3.1 (a) Replacing Batteries

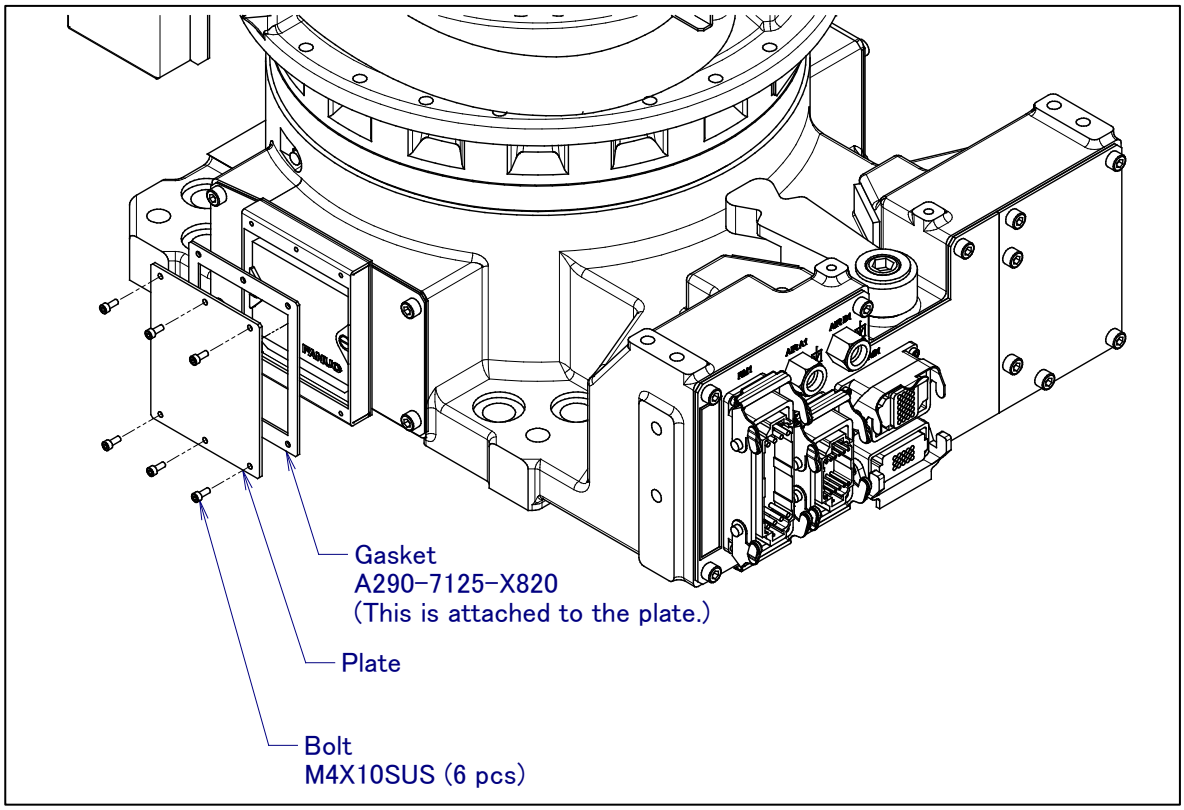


Fig. 7.3.1 (b) Removing the battery cover plate (When severe dust/liquid protection is specified)

7.3.2 Replacing the Grease of the Drive Mechanism (3 years check (11520 hours) Periodic Maintenance)

According to below, replace the grease of the reducers of J1/J2/J3/E1, the J4 gearbox and the wrist at the intervals based on every 3 years or 11520 hours, whichever comes first. See table 7.3.2 (a) for the grease name and the quantity.

Table 7.3.2 (a) Grease for 3-year (11520 hours) periodical replacement

Models	Grease supplying position	Quantity	Gun tip pressure	Grease name
R-1000*i*A/80F	J1-axis reducer	3210g (3570ml)	0.15MPa or less (NOTE)	Spec : A98L-0040-0174
	J2-axis reducer	1500g (1670ml)		
	J3-axis reducer	950g (1060ml)		
	J4-axis gearbox	1880g (2090ml)		
	Wrist 1	1070g (1190ml)		
	Wrist 2	310g (350ml)		
R-1000*i*A/100F/130F	J1-axis reducer	3210g (3570ml)		
	J2-axis reducer	1320g (1470ml)		
	J3-axis reducer	950g (1060ml)		
	J4-axis gearbox	1880g (2090ml)		
	Wrist 1	1170g (1300ml)		
	Wrist 2	430g (480ml)		
R-1000*i*A/120F-7B	J1-axis reducer	3210g (3570ml)		
	J2-axis reducer	1320g (1470ml)		
	J3-axis reducer	950g (1060ml)		
	J4-axis gearbox	1880g (2090ml)		
	Wrist 1	1170g (1300ml)		
	Wrist 2	430g (480ml)		
	E1-axis reducer	1500g (1670ml)		
R-1000*i*A/80H	J1-axis reducer	3210g (3570ml)		
	J2-axis reducer	1500g (1670ml)		
	J3-axis reducer	950g (1060ml)		
	J4-axis gearbox	1880g (2090ml)		
	Wrist 1	910g (1010ml)		
	Wrist 2	360g (400ml)		

NOTE
When a manual pump is used for greasing, the standard rate is two pumping cycles per three seconds.

⚠ WARNING
Hot grease might eject suddenly when you open the grease outlet. Attach bags for collecting grease, and use appropriate protective equipment such as heat-resistant gloves, protective glasses, a face shield, or a body suit if necessary.

For grease replacement or replenishment, use the postures indicated below.

Table 7.3.2 (b) Postures for greasing (R-1000*i*A/80F/100F/130F/80H)

Supply position	Posture					
	J1	J2	J3	J4	J5	J6
J1-axis reducer	Arbitrary	Arbitrary	Arbitrary	Arbitrary	Arbitrary	Arbitrary
J2-axis reducer		0°				
J3-axis reducer		0°	0°			
J4-axis gearbox		Arbitrary	0°			
Wrist			0°	0°	0°	0°

Table 7.3.2 (c) Postures for greasing (R-1000*i*A/120F-7B)

Supply position	Posture						
	J1	J2	J3	J4	J5	J6	E1
J1-axis reducer	Arbitrary	Arbitrary	Arbitrary	Arbitrary	Arbitrary	Arbitrary	Arbitrary
J2-axis reducer		0°					
J3-axis reducer		0°	0°	Arbitrary	Arbitrary	Arbitrary	0°
J4-axis gearbox		Arbitrary	0°	Arbitrary	Arbitrary	Arbitrary	Arbitrary
Wrist			0°	0°	0°	0°	
E1-axis reducer		0°	Arbitrary	Arbitrary	Arbitrary	Arbitrary	0°

⚠ CAUTION

1 Failure to follow proper greasing procedures may cause a sudden increase of the grease bath internal pressure and damage to the seal. This, could lead to grease leakage and abnormal operation. When greasing, observe the following precautions.
   (1) Before starting to grease, remove the seal bolt or the taper plug to allow the grease to come out.
   (2) Supply grease slowly without applying excessive force, using a manual pump.
   (3) Whenever possible, avoid using a compressed-air pump, powered by the factory air supply. Even when using a compressed-air pump unavoidably, set the gun tip pressure (see Table 7.3.2 (a).) during application of grease.
   (4) Use specified grease. Use of non-approved grease may damage the reducer or lead to other problems.
   (5) After applying grease, release the remaining pressure within the grease bath as described in the procedure in Subsection 7.3.3.
   (6) To prevent an accident such as a fall or fire, remove all the excess grease from the floor and robot.
2 There is no J6-axis for R-1000*i*A/80H.

Grease replacement procedure for the J1-axis, J2-axis, J3-axis, E1-axis reducers and J4-axis gearbox

1 Move the robot to the greasing posture described in Table 7.3.2 (b), (c).
2 Turn off the controller power.
3 Remove the seal bolt of grease outlet and ventilator hole. (See Fig. 7.3.2 (a) to (d))
4 Supply new grease until new grease is output from the grease outlet.
5 After applying grease, release the remaining pressure within the grease bath as described in the procedure in Section 7.3.3.

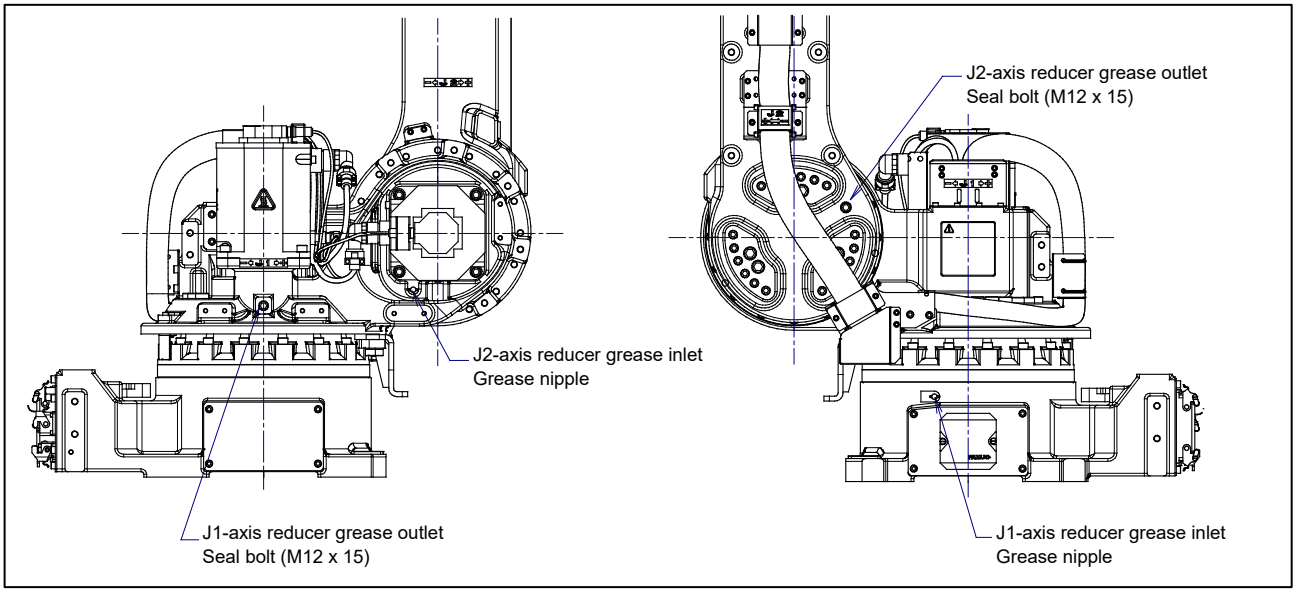


Fig. 7.3.2 (a) Replacing grease of J1/J2-axis reducer

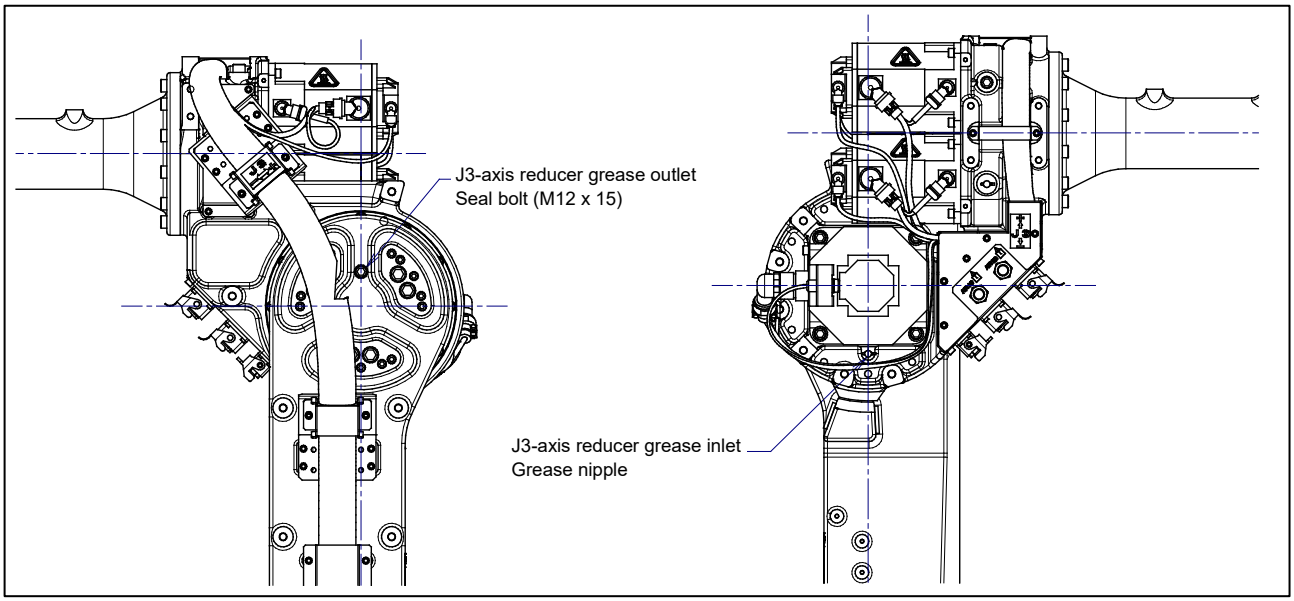


Fig. 7.3.2 (b) Replacing grease of J3-axis reducer

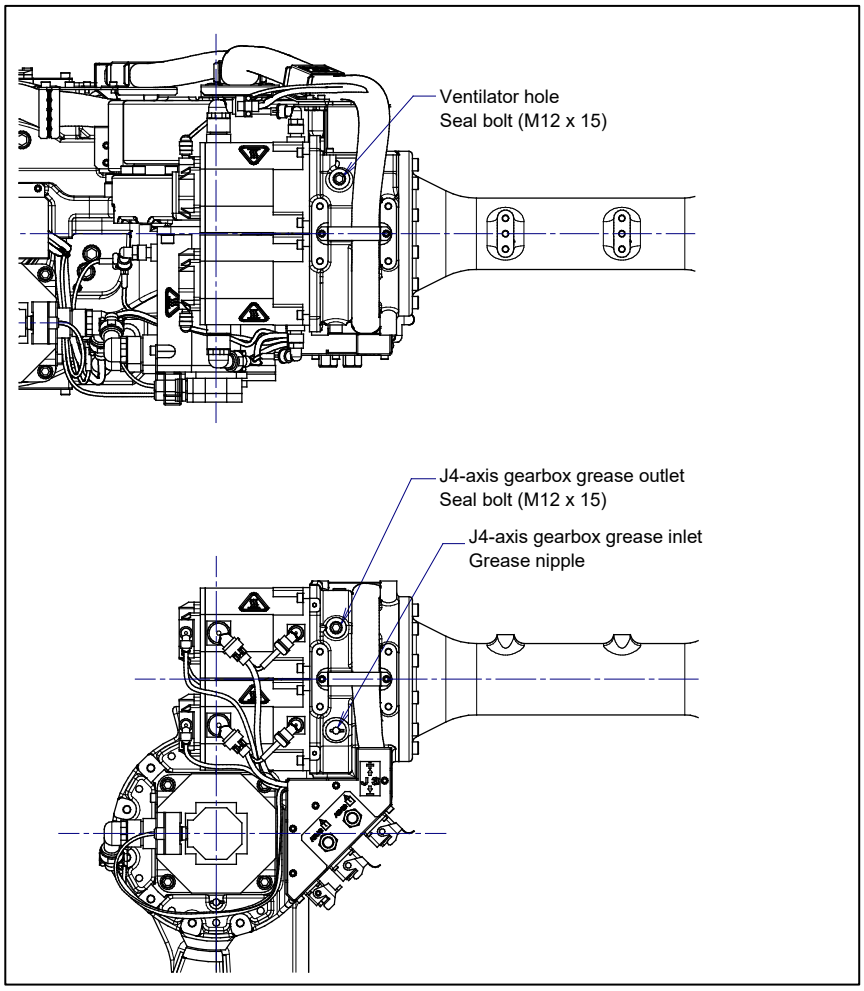


Fig. 7.3.2 (c) Replacing grease of J4-axis gearbox

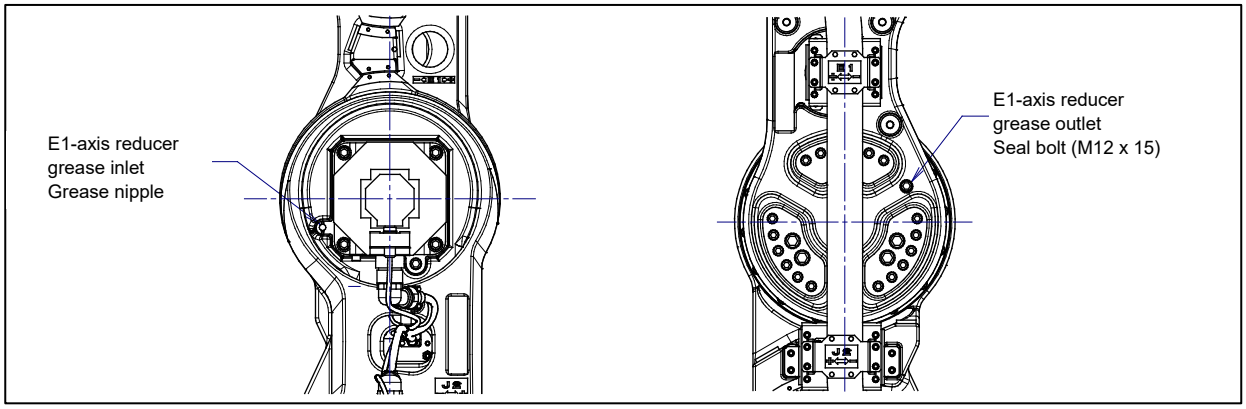


Fig. 7.3.2 (d) Replacing grease of E1-axis reducer

Grease replacement procedure for the wrist

1 Move the robot to the greasing posture described in table 7.3.2 (b), (c).
2 Turn off controller power.
3 Remove the taper plug of wrist grease outlet 1 (Figs. 7.3.2 (e), (f)).
4 Supply grease to the wrist grease inlet until new grease outputs from wrist grease outlet 1.
5 Attach the taper plug to wrist grease outlet 1.
6 Next, remove the seal bolt of wrist grease outlet 2.
7 Supply new grease through the wrist grease inlet until new grease is output from wrist grease outlet 2
8 Release remaining pressure using the procedure given in Section 7.3.3.

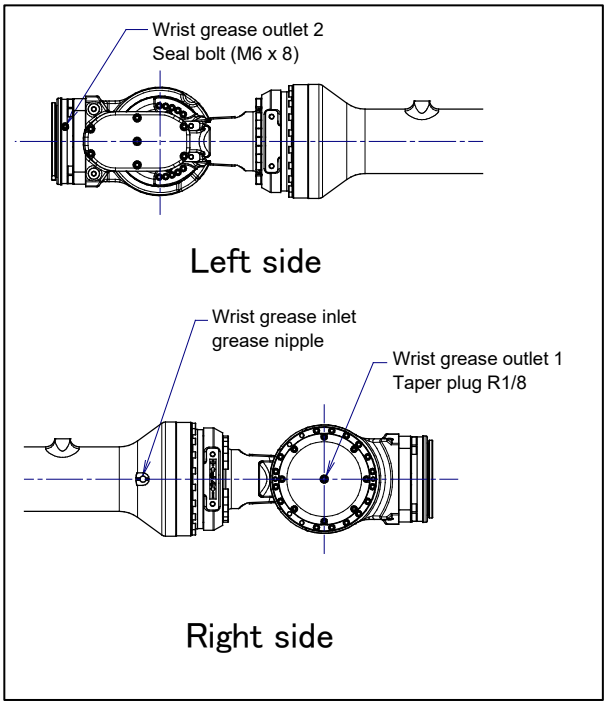


Fig. 7.3.2 (e) Replacing grease of wrist (R-1000*i*A/80F/100F/130F/120F-7B)

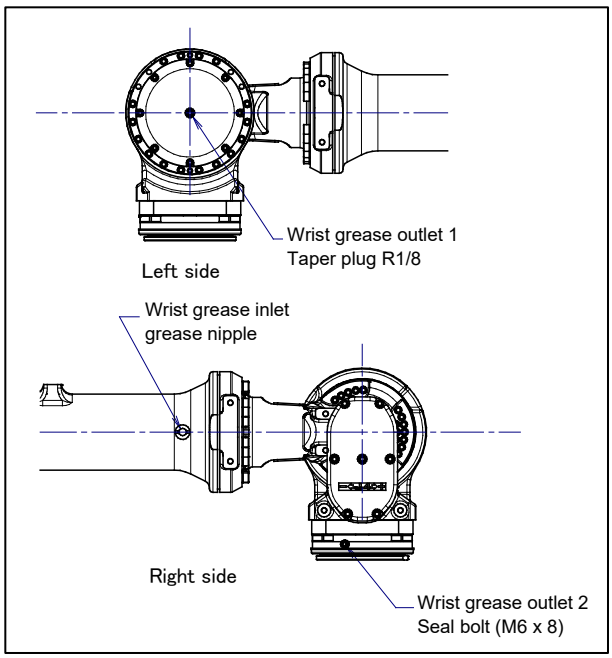


Fig. 7.3.2 (f) Replacing grease of wrist (R-1000*i*A/80H)

Table 7.3.2 (d) Spec of the seal bolts, taper plugs and the grease nipple

Parts name	Specifications
Seal bolt (M6)	A97L-0218-0417#060808
Seal bolt (M12)	A97L-0218-0417#121515
Taper plug (R1/8)	A97L-0001-0436#2-1D
Grease nipple	A97L-0218-0013#A610

7.3.3 Procedure for Releasing Remaining Pressure from the Grease Bath

Release remaining pressure as described below.
Under the grease inlets and outlets, attach bags for collecting grease so that grease does not spatter when it comes out of the inlets or outlets.

Grease replacement position	Motion angle	OVR	Operating time	Open point
J1-axis reducer	80° or more	50%	20 minutes	A
J2-axis reducer	90° or more	50%	20 minutes	A
J3-axis reducer	70° or more	50%	20 minutes	A
J4-axis gearbox (R-1000*i*A/80F/100F/130F/120F-7B)	J4: 60° or more J5: 120° or more J6: 60° or more	100%	20 minutes	B
J4-axis gearbox (R-1000*i*A/80H)	J3: 60° or more J5: 180° or more	50%	20 minutes	B
Wrist (R-1000*i*A/80F/100F/130F/120F-7B)	J4: 60° or more J5: 120° or more J6: 60° or more	100%	10 minutes	C
Wrist (R-1000*i*A/80H)	J4: 20° J5: 180° or more	50%	40 minutes	C
E1-axis reducer (R-1000*i*A/120F-7B)	90° or more	50%	20 minutes	A

In the case of A
Open the grease inlets and outlets and perform continuous operation.

In the case of B
Open the grease inlet, outlets and ventilator hole and perform continuous operation.

In the case of C
Open all of the grease inlets and outlets referring to Fig. 7.3.3 (a), (b) and perform continuous operation.

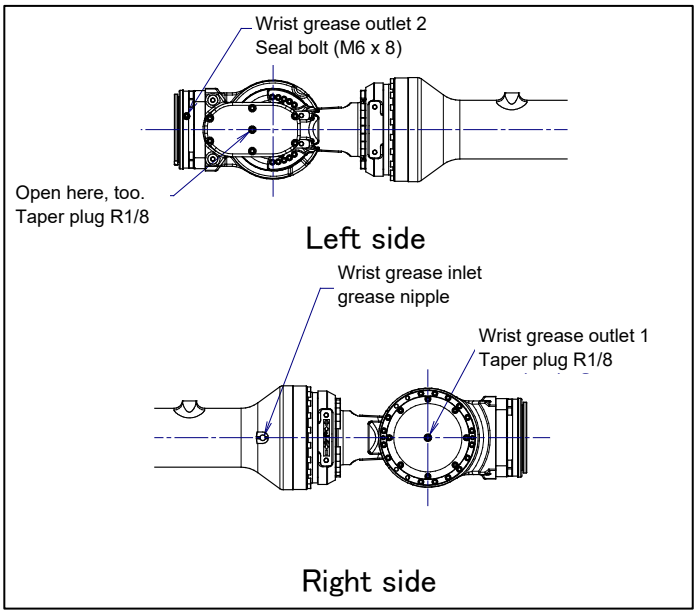


Fig. 7.3.3 (a) Open points for releasing remaining pressure from the wrist (R-1000*i*A/80F/100F/130F/120F-7B)

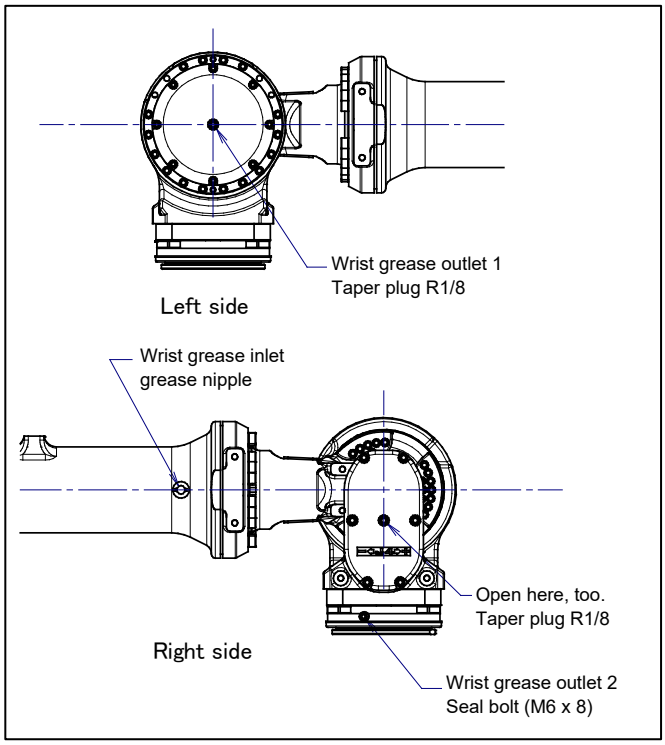


Fig. 7.3.3 (b) Open points for releasing remaining pressure from the wrist (R-1000*i*A/80H)

If the above operation cannot be performed due to the environment, adjust the operating time according to the operating angle. (If only half of the predetermined motion angle can be set, perform an operation for a time twice as long as the specified time.) If you grease multiple axes, you can exercise multiple axes at the same time. After completion of the operation, attach the seal bolts and grease nipples to the grease inlets and outlets immediately. When reusing the seal bolts and grease nipples, be sure to seal them with seal tape.

7.4 STORAGE

When storing the robot, place it on a level surface with the same posture for transportation. (See Section 1.1.)

8 MASTERING

Mastering associates the angle of each robot axis with the pulse count value supplied from the absolute Pulsecoder connected to the corresponding axis motor. To be specific, mastering is an operation for obtaining the pulse count value; corresponding to the zero position.

> ⚠ **CAUTION**
> In case of performing mastering with gravity compensation (option) is enabled, if load setting (See Section 4.3) is not correct, it will influence the precision of the mastering.

8.1 OVERVIEW

The current position of the robot is determined according to the pulse count value supplied from the Pulsecoder on each axis.
Mastering is factory-performed. It is unnecessary to perform mastering in daily operations. However, mastering becomes necessary after:

- Motor replacement.
- Pulsecoder replacement
- Reducer replacement
- Cable replacement
- Batteries for pulse count backup in the mechanical unit have gone dead

> ⚠ **CAUTION**
> Robot data (including mastering data) and Pulsecoder data are backed up by their respective backup batteries. Data will be lost if the batteries die. Replace the batteries in the controller and mechanical units periodically. An alarm will alert you when battery voltage is low.

Types of Mastering

Table 8.1 (a) describes the following mastering methods. If 7DC2 (V8.20P) or former software is installed, "Quick Mastering for Single Axis" has not been supported.

Table 8.1 (a) Type of mastering

Fixture position mastering	This is performed using a mastering fixture before the machine is shipped from the factory.
Zero-position mastering (witness mark mastering)	This is performed with all axes set at the 0-degree position. A zero-position mark (witness mark) is attached to each robot axis. This mastering is performed with all axes aligned to their respective witness marks.
Quick mastering	This is performed at a user-specified position. The corresponding count value is obtained from the rotation count of the Pulsecoder connected to the relevant motor and the rotation angle within one rotation. Quick mastering uses the fact that the absolute value of a rotation angle within one rotation will not be lost. (All axes at the same time)
Quick mastering for single axis	This is performed at a user-specified position for one axis. The corresponding count value is obtained from the rotation count of the Pulsecoder connected to the relevant motor and the rotation angle within one rotation. Quick mastering uses the fact that the absolute value of a rotation angle within one rotation will not be lost.
Single-axis mastering	This is performed for one axis at a time. The mastering position for each axis can be specified by the user. This is useful in performing mastering on a specific axis.
Mastering data entry	Mastering data is entered directly.

Once mastering is performed, you must carry out positioning, or calibration. Positioning is an operation in which the controller reads the current pulse count value to sense the current position of the robot.

This section describes zero-position mastering, quick mastering, quick mastering for single axis, single-axis mastering, and mastering data entry. For more detailed mastering (fixture position mastering), contact your local FANUC representative.

> ⚠ **CAUTION**
> 1 If mastering is performed incorrectly, the robot may behave unexpectedly. This is very dangerous. For this reason, the Master/Cal screen is designed to appear only when the $MASTER_ENB system variable is 1 or 2. After performing positioning, press F5, ([DONE]) on the Master/Cal screen. The $MASTER_ENB system variable is then reset to 0 automatically, and the Master/Cal screen will disappear.
> 2 Before performing mastering, it is recommended that you back up the current mastering data.

8.2 RESETTING ALARMS AND PREPARING FOR MASTERING

Before performing mastering because a motor is replaced, you must release the relevant alarm and display the positioning menu.

Alarm displayed

"SRVO-062 BZAL" or "SRVO-075 Pulse not established"

Procedure

1 Display the positioning menu by following the steps 1 to 6.
   1 Press the [MENU] key.
   2 Press [0 NEXT] and select [6 SYSTEM].
   3 Press the F1 ([TYPE]), and select [Variable] from the menu.
   4 Place the cursor on $MASTER_ENB, then key in "1" and press the [ENTER] key.
   5 Press the F1 ([TYPE]), and select [Master/Cal] from the menu.
   6 Select the desired mastering type from the [Master/Cal] menu.

2 To reset the "SRVO-062 BZAL" alarm, follow steps 1 to 5.
   1 Press the [MENU] key.
   2 Press [0 NEXT] and select [6 SYSTEM].
   3 Press the F1 ([TYPE]), and select [Master/Cal] from the menu.
   4 Place the cursor on the F3 ([RES_PCA]), then press the F4 ([YES]).
   5 Cycle power of the controller.

3 To reset the "SRVO-075 Pulse not established" alarm, follow the steps 1 to 2.
   1 After cycling controller power, the message "SRVO- 075 Pulse not established" appears again.
   2 Move the axis for which the message mentioned above has appeared in either direction till the alarm disappears when you press the [RESET] key.

If "SRVO-062 BZAL" alarm or "SRVO-068 DTERR" alarm occurred, and you cannot release the alarm, Please check there is no faulty wiring or disconnected part.

8.3 ZERO POSITION MASTERING

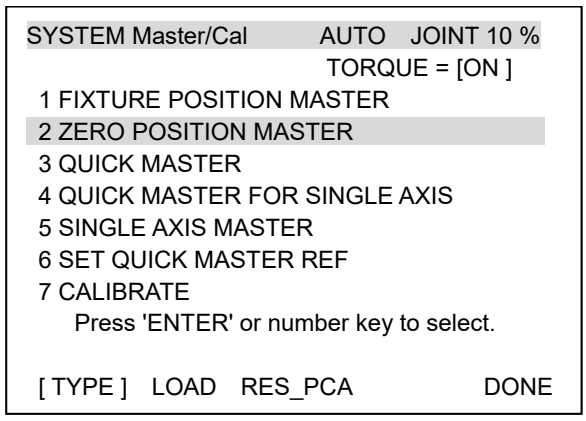
Zero-position mastering (witness mark mastering) is performed with all axes set at the 0-degree position. A zero-position mark (witness mark) is attached to each robot axis. (Fig. 8.3 (a) to (d)) This mastering is performed with all axes set at the 0-degree position using their respective witness marks.
Zero-position mastering involves a visual check, and might not be highly accurate. It should be used only as a quick-fix method.

Zero-position Mastering Procedure

1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

NOTE
Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
$PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
Brake control can be released by setting the system variables as follows:
$PARAM_GROUP.SV_OFF_ALL : FALSE
$PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
After changing the system variables, cycle power of the controller.
(Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

5 Press the [MENU] key to display the screen menu.
6 Select [0 NEXT] and press [6 SYSTEM].
7 Press F1 [TYPE], display the screen change menu.
8 Select [Master/Cal]. The positioning screen appears.



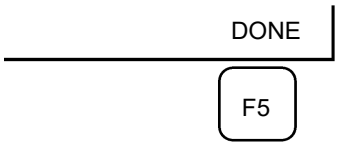
9 Jog the robot into a posture for mastering.
10 Select [2 Zero Position Master]. Press F4 [YES].

```
SYSTEM Master/Cal          AUTO   JOINT 10 %
                                  TORQUE = [ON ]
 1 FIXTURE POSITION MASTER
 2 ZERO POSITION MASTER
 3 QUICK MASTER
 4 QUICK MASTER FOR SINGLE AXIS
 5 SINGLE AXIS MASTER
 6 SET QUICK MASTER REF
 7 CALIBRATE
 Robot Mastered! Mastering Data:
    <0> <11808249> <38767856>
    <9873638> <12200039> <2000319>
 [ TYPE ]   LOAD   RES_PCA                DONE
```

11 Select [7 CALIBRATE] and press F4 [YES]. Mastering will be performed automatically. Alternatively, turn off the controller power and on again.

```
SYSTEM Master/Cal          AUTO   JOINT 10 %
                                  TORQUE = [ON ]
 1 FIXTURE POSITION MASTER
 2 ZERO POSITION MASTER
 3 QUICK MASTER
 4 QUICK MASTER FOR SINGLE AXIS
 5 SINGLE AXIS MASTER
 6 SET QUICK MASTER REF
 7 CALIBRATE
 Robot Calibrated! Cur Jnt Ang(deg):
    <    0.0000> <    0.0000> <    0.0000>
    <    0.0000> <    0.0000> <    0.0000>
```

12 After positioning is completed, press F5 [DONE].



13 Return the setting of the gravity compensation.
14 Return brake control to original setting, and cycle power of the controller.

Table 8.3 (a) Posture with position marks (witness mark) aligned

Axis	Position
J1-axis	0 deg
J2-axis	0 deg
J3-axis	0 deg (NOTE) When J2-axis is 0 deg or J2-axis + E1-axis is 0 deg.
J4-axis	0 deg
J5-axis	0 deg
J6-axis	0 deg
E1-axis	0 deg

⚠ CAUTION
There is no J6-axis for R-1000*i*A/80H.
There is no E1-axis for R-1000*i*A/80F/100F/130F/80H.

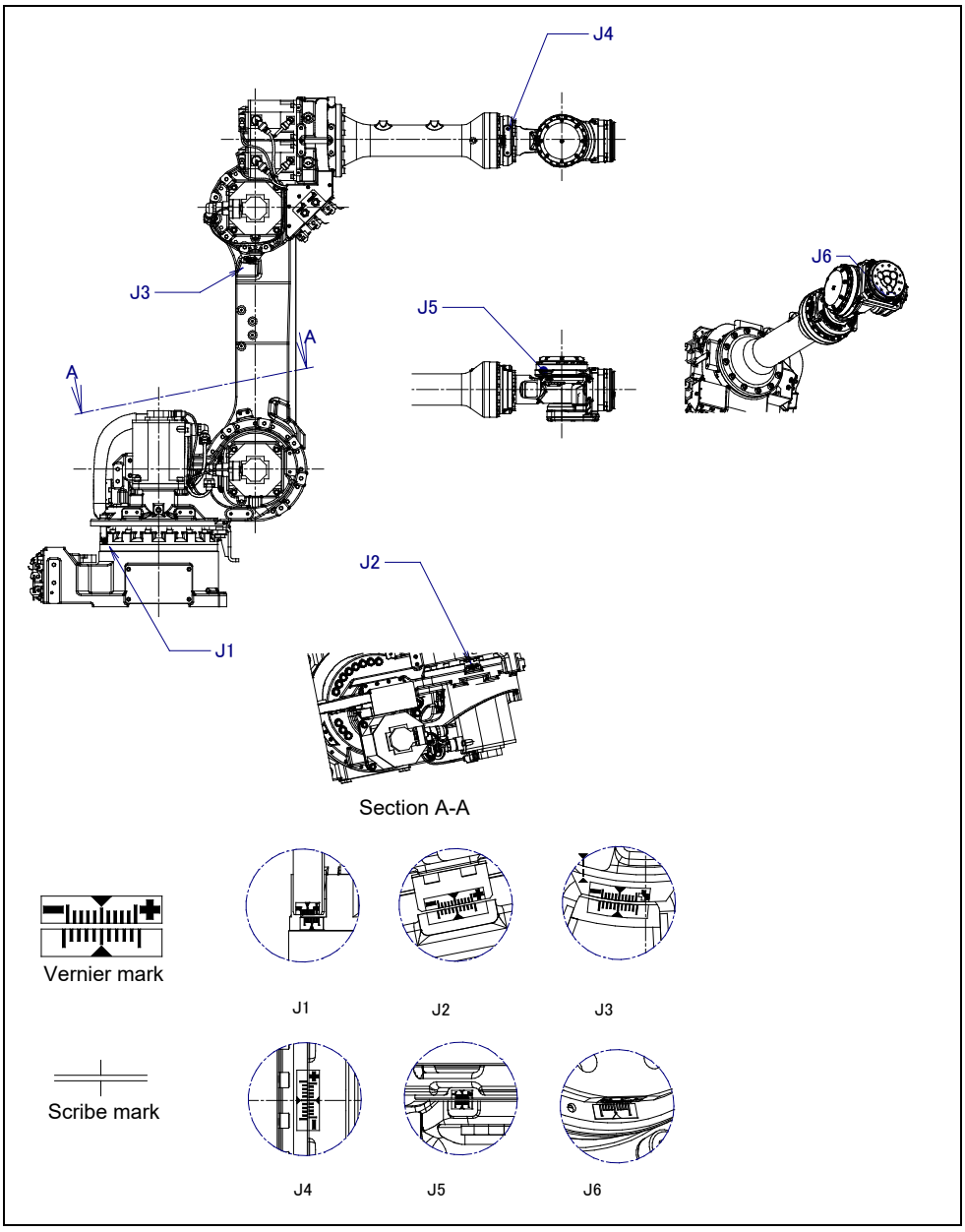


Fig. 8.3 (a) Zero-position mark (witness mark) for each axis (R-1000*i*A/80F)

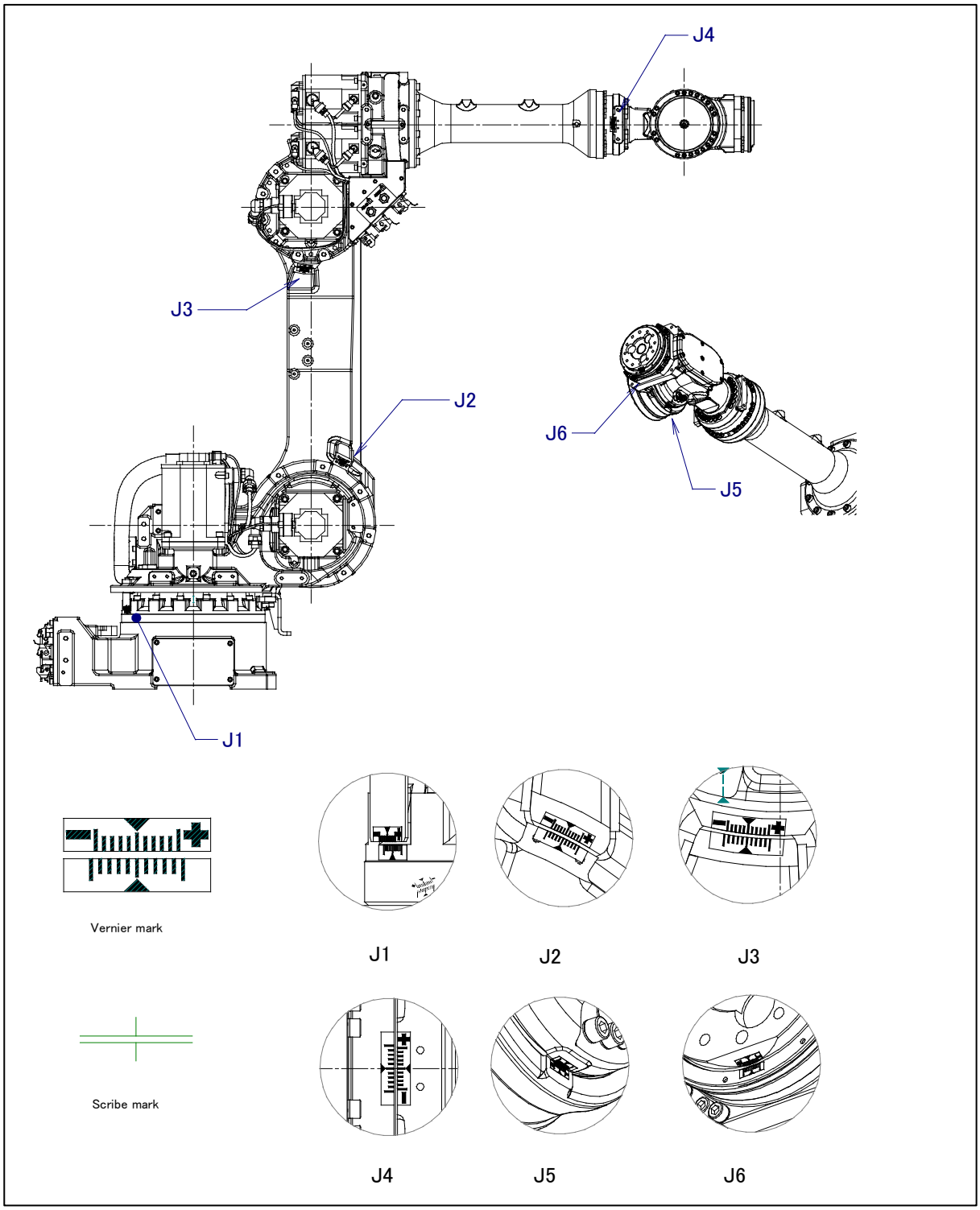


Fig. 8.3 (b) Zero-position mark (witness mark) for each axis (R-1000*i*A/100F/130F)

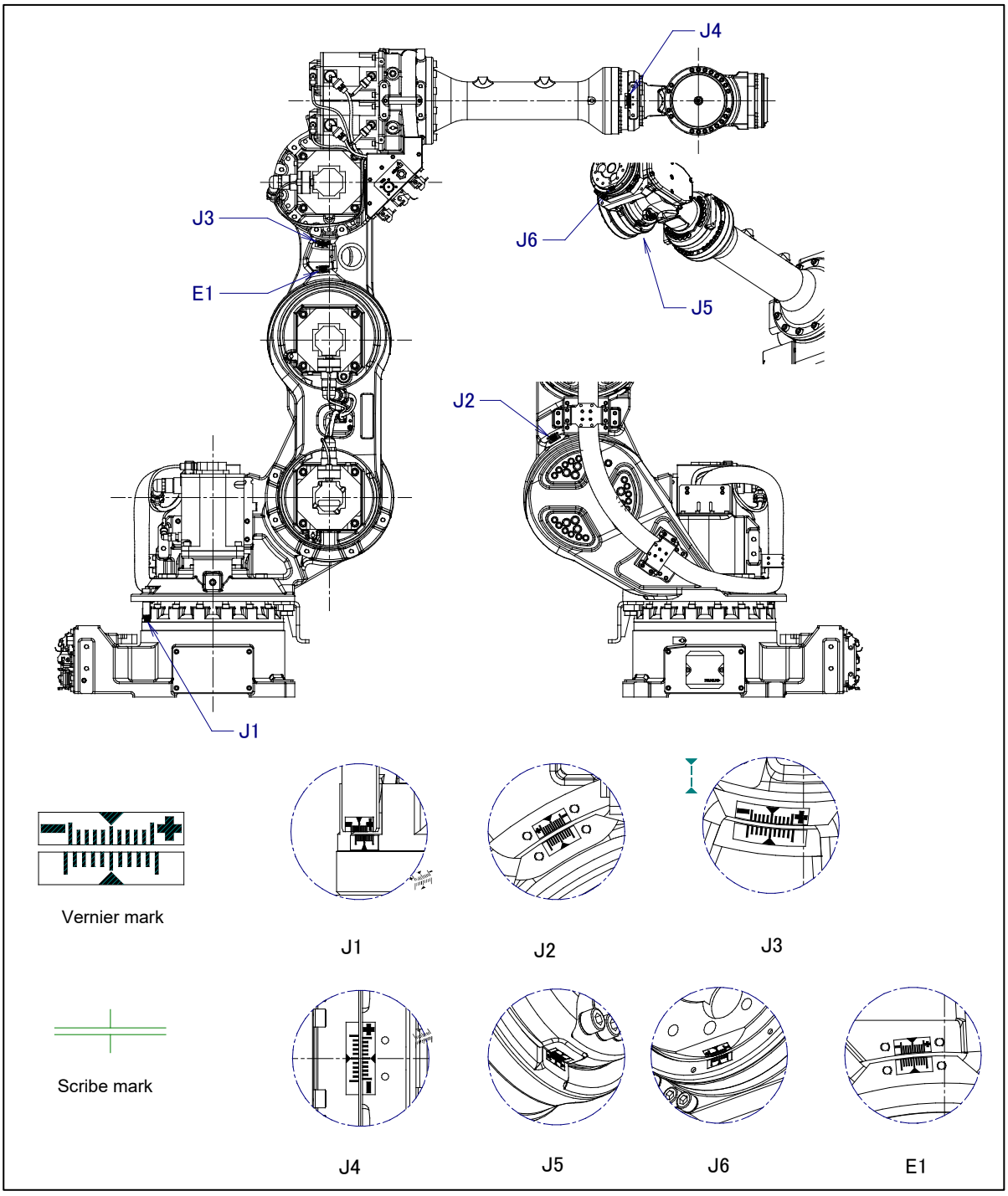


Fig. 8.3 (c) Zero-position mark (witness mark) for each axis (R-1000*i*A/120F-7B)

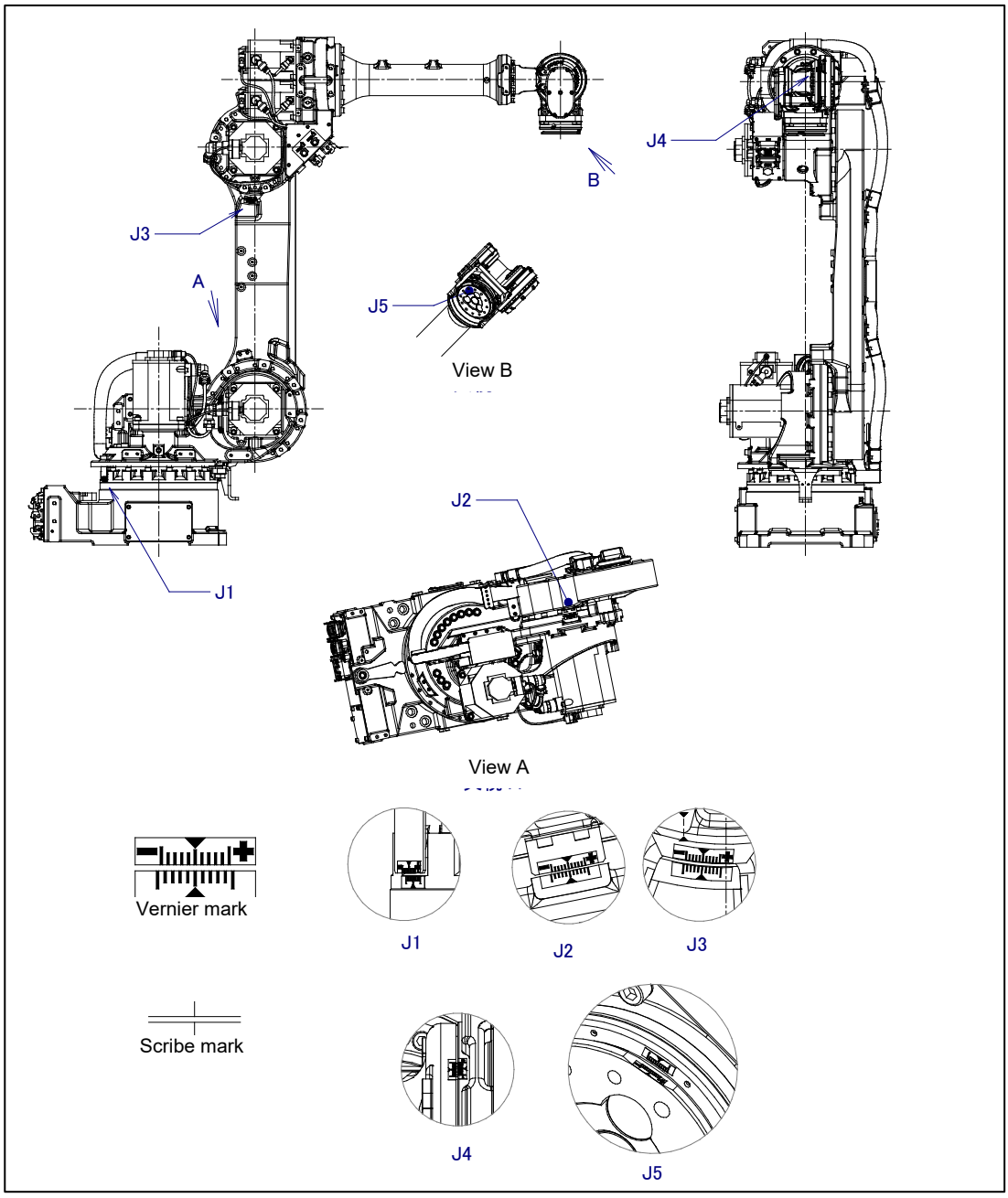


Fig. 8.3 (d) Zero-position mark (witness mark) for each axis (R-1000*i*A/80H)

8.4 QUICK MASTERING

Quick mastering is performed at a user-specified position. The pulse count value is obtained from the rotation times of the Pulsecoder connected to the relevant motor and the rotation angle within one rotation. Quick mastering uses the character that the absolute value of a rotation angle within one rotation will not be lost.

Quick mastering is factory-performed at the position indicated in Table 8.3 (a). If possible, do not change the setting.

If setting the robot at the position mentioned above is impossible, you must re-set the quick mastering reference position using the following method. (It would be convenient to set up a marker that can work in place of the witness mark.)

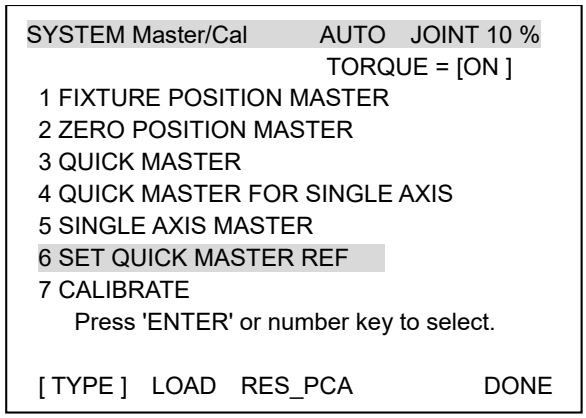
⚠ CAUTION
1 Quick mastering can be used, if the pulse count value is lost, for example, because a low voltage has been detected on the backup battery for the pulse counter.
2 Quick mastering cannot be used, after the Pulsecoder is replaced or after the mastering data is lost from the robot controller.

Procedure Recording the Quick Mastering Reference Position

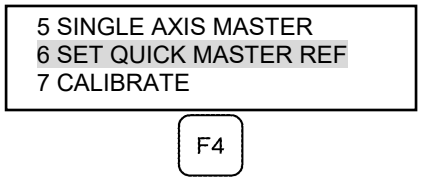
1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

NOTE
Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
$PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
Brake control can be released by setting the system variables as follows:
$PARAM_GROUP.SV_OFF_ALL : FALSE
$PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
After changing the system variables, cycle power of the controller.
(Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

5 Select [6 SYSTEM].
6 Select [Master/Cal]. The positioning screen will be displayed.



7 Jog the robot to the quick mastering reference position.
8 Select [6 SET QUICK MASTER REF] and press F4 [YES]. Quick mastering reference position is saved.



9 Return the setting of the gravity compensation.
10 Return brake control to original setting, and cycle power of the controller.

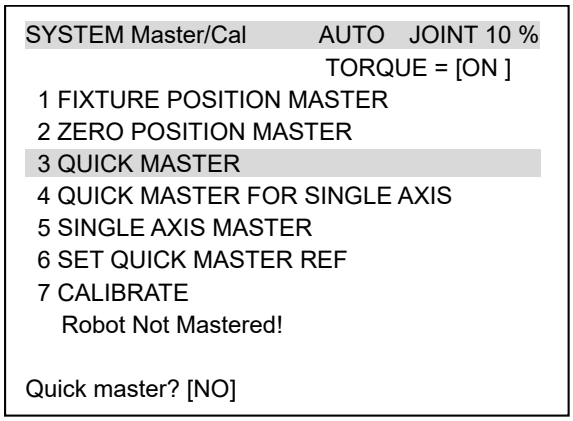
> **⚠ CAUTION**
> If the robot has lost mastering data due to mechanical disassembly or repair, you cannot perform this procedure. In this case, perform Fixture position mastering or Zero position mastering to restore mastering data.

Procedure of Quick Mastering

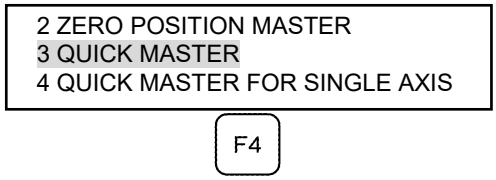
1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

> **NOTE**
> Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
> $PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
> Brake control can be released by setting the system variables as follows:
> $PARAM_GROUP.SV_OFF_ALL : FALSE
> $PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
> After changing the system variables, cycle power of the controller.
> (Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

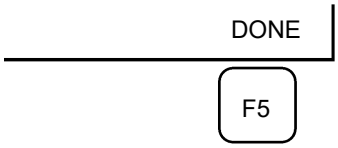
5 Display the Master/Cal screen.



6 Jog the robot to the quick mastering reference position.
7 Move the cursor to [3 QUICK MASTER] and press [ENTER]. Press F4 [YES]. Quick mastering data is saved.



8 Select [7 CALIBRATE] and press the [ENTER] key. Calibration is executed. Calibration is executed by cycling power.
9 After completing the calibration, press F5 Done.



10 Return the setting of the gravity compensation.
11 Return brake control to original setting, and cycle power of the controller.

8.5 QUICK MASTERING FOR SINGLE AXIS

Quick mastering is performed at a user-specified position for one axis. The pulse count value is obtained from the rotation times of the Pulsecoder connected to the relevant motor and the rotation angle within one rotation. Quick mastering uses the character that the absolute value of a rotation angle within one rotation will not be lost.

Quick mastering is factory-performed at the position indicated in Table 8.3 (a). If possible, do not change the setting.

If setting the robot at the position mentioned above is impossible, you must re-set the quick mastering reference position using the following method. (It would be convenient to set up a marker that can work in place of the witness mark.)

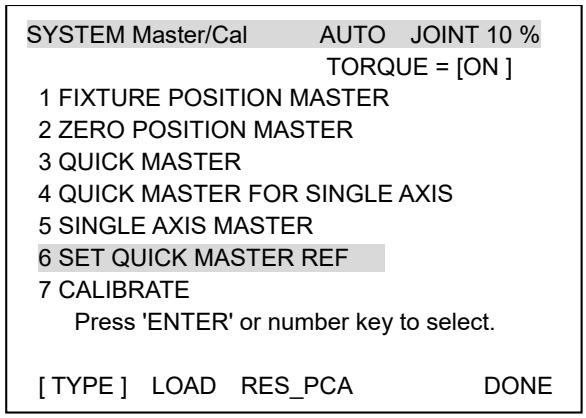
⚠ CAUTION
1 Quick mastering can be used, if the pulse count value is lost, for example, because a low voltage has been detected on the backup battery for the pulse counter.
2 Quick mastering cannot be used, after the Pulsecoder is replaced or after the mastering data is lost from the robot controller.

Procedure Recording the Quick Mastering Reference Position

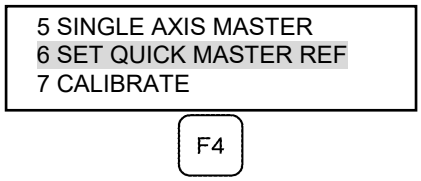
1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

NOTE
Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
$PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
Brake control can be released by setting the system variables as follows:
$PARAM_GROUP.SV_OFF_ALL : FALSE
$PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
After changing the system variables, cycle power of the controller.
(Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

5 Select [6 SYSTEM].
6 Select [Master/Cal]. The positioning screen appears.



7 Release brake control, and jog the robot to the quick mastering reference position.
8 Select [6 SET QUICK MASTER REF] and press F4 [YES]. Quick mastering reference position is saved.



9 Return the setting of the gravity compensation.
10 Return brake control to original setting, and cycle power of the controller.

> ⚠ **CAUTION**
> If the robot has lost mastering data due to mechanical disassembly or repair, you cannot perform this procedure. In this case, perform Fixture position mastering or Zero position mastering to restore mastering data.

Procedure of Quick Mastering for single axis

1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

> **NOTE**
> Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
> $PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
> Brake control can be released by setting the system variables as follows:
> $PARAM_GROUP.SV_OFF_ALL : FALSE
> $PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
> After changing the system variables, cycle power of the controller.
> (Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

5 Display the Master/Cal screen.

```
SYSTEM Master/Cal          AUTO   JOINT 10 %
                                  TORQUE = [ON ]
 1 FIXTURE POSITION MASTER
 2 ZERO POSITION MASTER
 3 QUICK MASTER
 4 QUICK MASTER FOR SINGLE AXIS
 5 SINGLE AXIS MASTER
 6 SET QUICK MASTER REF
 7 CALIBRATE
   Robot Not Mastered!

Quick master? [NO]
```

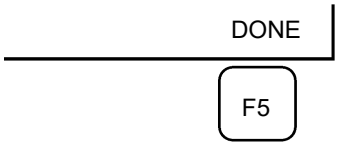
6 Select [4 QUICK MASTER FOR SINGLE AXIS]. You will see the quick master for single axis screen.

```
SINGLE AXIS MASTER              AUTO   JOINT 10%
                                                1/9
    ACTUAL   POS    (MSTR POS)      (SEL)   [ST]
J1          0.000   (      0.000)   (0)     [2]
J2          0.000   (      0.000)   (0)     [2]
J3          0.000   (      0.000)   (0)     [2]
J4          0.000   (      0.000)   (0)     [2]
J5          0.000   (      0.000)   (0)     [2]
J6          0.000   (      0.000)   (0)     [0]
E1          0.000   (      0.000)   (0)     [0]
E2          0.000   (      0.000)   (0)     [0]
E3          0.000   (      0.000)   (0)     [0]

                                                EXEC
```

7 Move the cursor to the [SEL] column for the unmastered axis and press the numeric key [1]. Setting of [SEL] is available for one or more axes.

```
SINGLE AXIS MASTER              AUTO   JOINT 10%
                                                1/9
    ACTUAL   POS    (MSTR POS)      (SEL)   [ST]
J5          0.000   (      0.000)   (1)     [2]
J6          0.000   (      0.000)   (1)     [2]

                                              EXEC
```

8 Jog the robot to the quick mastering reference position.
9 Press F5 [EXEC]. Mastering is performed. So, [SEL] is reset to 0, and [ST] is re-set to 2.
10 Select [7 CALIBRATE] and press [ENTER] key. Calibration is executed. Calibration is executed by cycling power.
11 After completing the calibration, press F5 Done.



12 If gravity compensation is disabled, set it to enabled.
13 Return brake control to original setting, and cycle power of the controller.

8.6 SINGLE AXIS MASTERING

Single axis mastering is performed for one axis at a time. The mastering position for each axis can be specified by the user.
Single axis mastering can be used, if mastering data for a specific axis is lost, for example, because a low voltage has been detected on the pulse counter backup battery or because the Pulsecoder has been replaced.

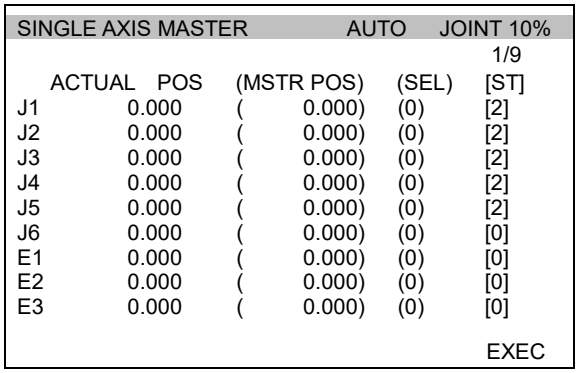


Table 8.6 (a) Items set in single axis mastering

Item	Description
Current position (ACTUAL AXIS)	The current position of the robot is displayed for each axis in degree units.
Mastering position (MSTR POS)	A mastering position is specified for an axis to be subjected to single axis mastering. It would be convenient to set to it to the 0_ position.
SEL	This item is set to 1 for an axis to be subjected to single axis mastering. Usually, it is 0.
ST	This item indicates whether single axis mastering has been completed for the corresponding axis. It cannot be changed directly by the user. The value of the item is reflected in $EACHMST_DON (1 to 9). 0 :Mastering data has been lost. Single axis mastering is necessary. 1 :Mastering data has been lost. (Mastering has been performed only for the other interactive axes.) Single axis mastering is necessary. 2 :Mastering has been completed.

Single axis mastering for interaction axis

When single axis mastering is done in interaction axis, the axis of the interaction pair is also influenced. Therefore, mastering of these interaction axes must be done at the same time. Interaction axis depends on the robot model. Following table shows the relation between robot model and interaction axis. For example, J4 motor is replaced, mastering of J5 and J6 should be done at the same time with J4. (Provided that if 7DC2 (V8.20P)/14 or later software version is installed, axis numbers which should be selected to do single axis mastering at the same time are displayed if these are not selected. In this case, it is unnecessary to refer to a following table.)

Table 8.6 (b) Relation between robot model and interaction axis

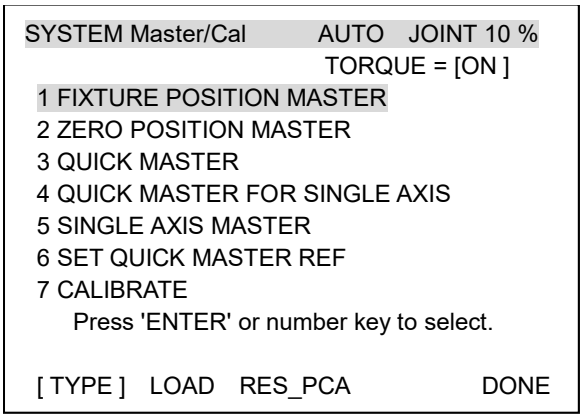
Robot model		Interaction axis
R-1000*i*A	/80F/100F/130F	・ J2/J3 ・ J4/J5/J6
	/80H	・ J2/J3/J4/J5
	/120F-7B	・ J2/J3/E1 ・ J4/J5/J6

Procedure of Single axis mastering

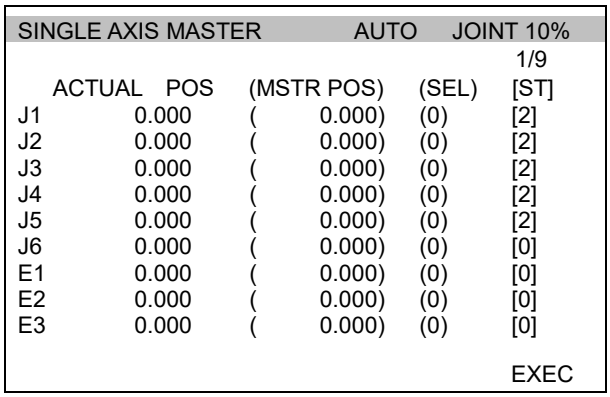
1 Press the [MENU] key to display the screen menu.
2 Select [0 NEXT] and press [6 SYSTEM].
3 Press F1 [TYPE]. Then select [Variables] from the menu.
4 If $DMR_GRP[group].$GRAV_MAST=1, set the gravity compensation to enabled, if it is 0, set the gravity compensation to disabled. In addition release the brake control.

NOTE
Gravity compensation can be set to enabled/disabled by setting the system variables as follows:
$PARAM_GROUP[group].$SV_DMY_LNK[8] : FALSE(disabled) or TRUE (enabled)
Brake control can be released by setting the system variables as follows:
$PARAM_GROUP.SV_OFF_ALL : FALSE
$PARAM_GROUP.SV_OFF_ENB[*] : FALSE (for all axes)
After changing the system variables, cycle power of the controller.
(Mastering can be performed without setting of gravity compensation. However, it will affect precision.)

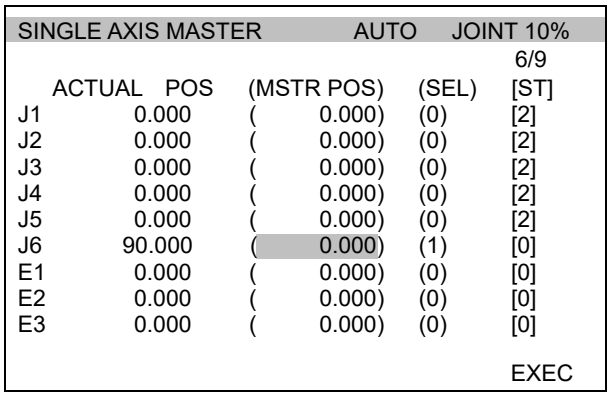
5 Select [6 SYSTEM].
6 Select [Master/Cal]. The positioning screen will be displayed.



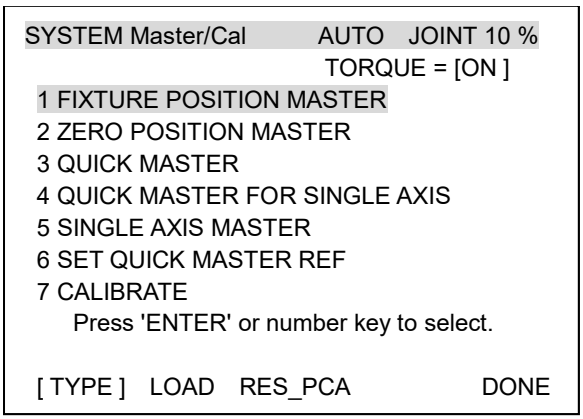
7 Select [5 SINGLE AXIS MASTER]. The following screen will be displayed.



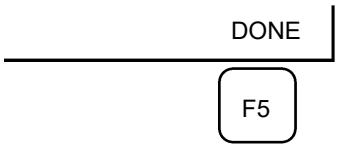
8 Move the cursor to the [SEL] column for the unmastered axis and press the numeric key [1]. Setting of [SEL] is available for one or more axes.
9 Jog the robot to the mastering position.
10 Enter axis data for the mastering position.
11 Press F5 [EXEC]. Mastering is performed. So, [SEL] is reset to 0, and [ST] is re-set to 2 or 1.



12 When single axis mastering is completed, press the [PREV] key to resume the previous screen.



13 Select [7 CALIBRATE], then press F4 [YES]. Positioning is performed. Alternatively, turn off the controller power and on again. Positioning is performed.
14 After positioning is completed, press F5 [DONE].



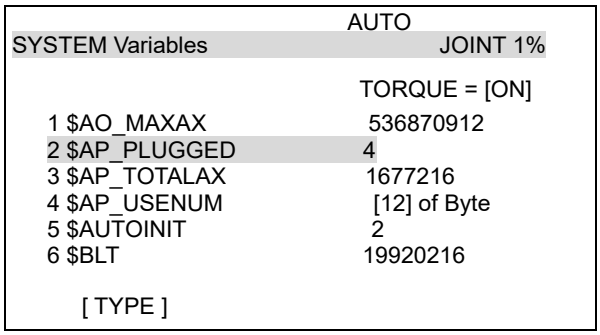
15 Return the setting of the gravity compensation.
16 Return brake control to original setting, and cycle power of the controller.

8.7 MASTERING DATA ENTRY

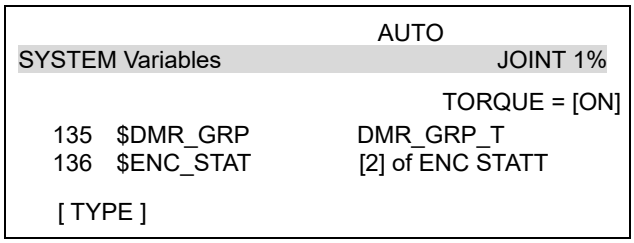
This function enables mastering data values to be assigned directly to a system variable. It can be used if mastering data has been lost but the pulse count is preserved.

Mastering data entry method

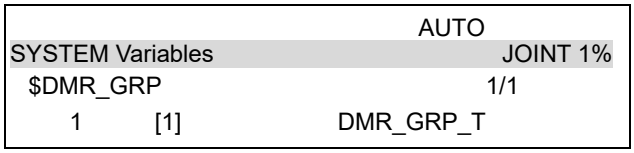
1 Press the [MENU] key, then press [0 NEXT] and select [6 SYSTEM].
2 Press F1 [TYPE]. Select [Variables]. The system variable screen appears.

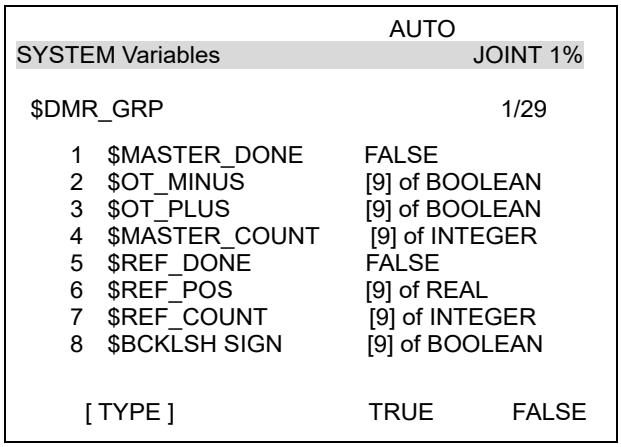


3 Change the mastering data.
The mastering data is saved to the $DMR_GRP.$MASTER_COUN system variable.

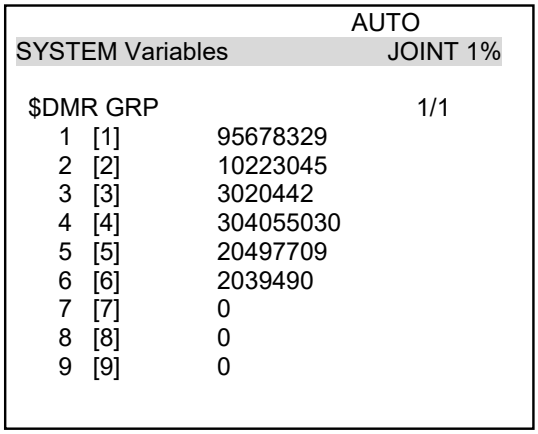


4 Select $DMR_GRP.



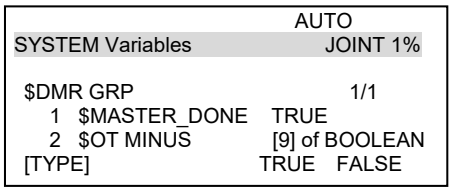


5 Select $MASTER_COUN, and enter the mastering data you have recorded.

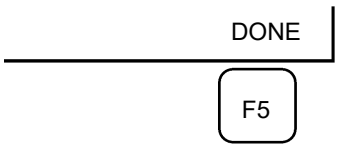


NOTE
E1-axis of R-1000*i*A/120F-7B is “7”.

6 Press the [PREV] key.
7 Set $MASTER_DONE to TRUE.



8 Display the positioning screen, and select [7 CALIBRATE], then press F4 [YES].
9 After completing positioning, press F5 [DONE].



8.8 VERIFYING MASTERING

1 How to verify that the robot is mastered properly:
Usually, positioning is performed automatically when the power is turned on. To check whether mastering has been performed correctly, examine if the current displayed position matches the actual robot position by using one or more of the procedures described below:
(1) Reproduce a particular point in a program. Check whether the point agrees with the specified position.
(2) Set all axes of the robot to their 0-degree (0 rad) positions. Check that the zero-degree position marks indicated in Section 8.3 of the OPERATOR'S MANUAL are aligned. There is no need to use a visual aid.
If the displayed and actual positions do not match, the counter value for a Pulsecoder may have been invalidated as a result of an alarm described in 2. Alternatively, the mastering data in system variable $DMR_GRP.$MASTER_COUN may have been overwritten as a result of an operation error or some other reason.
Compare the data with the values indicated on the supplied data sheet. This system variable is overwritten whenever mastering is performed. Whenever mastering is performed, record the value of the system variable on the data sheet.

2 Alarm types displayed during mastering and their solution method:
(1) BZAL alarm
This alarm is displayed if the Pulsecoder's backup battery voltage decreases to 0 V while the power to the controller is disconnected. Furthermore, if the Pulsecoder connector is removed for cable replacement, etc. this alarm is displayed as the voltage decreases to 0. Check to see if the alarm will disappear by performing a pulse reset (See Section 8.2.). Then, cycle controller power and check if the alarm disappears or not.
The battery may be drained if the alarm is still displayed. Perform a pulse reset, and turn off and on the controller power after replacing the battery. Note that, if this alarm is displayed, all the original data held by the Pulsecoder will be lost. Mastering is required.
(2) BLAL alarm
This alarm is displayed if the voltage of the Pulsecoder's backup battery has fallen to a level where backup is no longer possible. If this alarm is displayed, replace the battery with a new one immediately while keeping the power turned on. Check whether the current position data is valid, using the procedure described in 1.
(3) Alarm notification like CKAL, RCAL, PHAL, CSAL, DTERR, CRCERR, STBERR, and SPHAL may have trouble with Pulsecoder, contact your local FANUC representative.

9 TROUBLESHOOTING

The source of mechanical unit problems may be difficult to locate because of overlapping causes. Problems may become further complicated, if they are not corrected properly. Therefore, you must keep an accurate record of problems and take proper corrective actions.

9.1 TROUBLESHOOTING

Table 9.1 (a) shows the major troubleshooting items that may occur in the mechanical unit and their probable causes. If you cannot pinpoint a failure cause or which measures to take, contact your local FANUC representative. For troubleshooting except the mechanical unit, refer to "CONTROLLER MAINTENANCE MANUAL (B-83195EN etc.)" and Alarm Code List (B-83284EN-1).

Table 9.1 (a) Troubleshooting

Symptom	Description	Cause	Measure
Vibration Noise	- As the robot operates, its base plate lifts off the floor plate. - There is a gap between the base plate and the floor plate. - There is a crack in the weld that fastens the base plate to the floor plate.	[Base plate and floor plate fastening] - It is likely that the base plate is not securely fastened to the floor plate because of poor welding. - If the base plate is not securely fastened to the floor plate, it lifts as the robot operates, allowing the base and floor plates to strike each other which, in turn, leads to vibration.	- Re-weld the base plate to the floor plate. - If the weld is not strong enough, increase its width and length.
	- The J1 base lifts off the base plate as the robot operates. - There is a gap between the J1 base and base plate. - A J1 base retaining bolt is loose.	[J1 base fastening] - It is likely that the robot J1 base is not securely fastened to the base plate. - Probable cause is a loose bolt, an insufficient degree of surface flatness, or contamination caught between the base plate and floor plate. - If the robot is not securely fastened to the base plate, the J1 base lifts the base plate as the robot operates, allowing the base and floor plates to strike each other which, in turn, leads to vibration.	- If a bolt is loose, apply LOCTITE and tighten it with the appropriate torque. - Adjust the base plate surface flatness to within the specified tolerance. - If there is any contamination, remove it. - Apply adhesive between the J1 base and base plate.
	- The rack or floor plate vibrates during operation of the robot.	[Rack or floor] - It is likely that the rack or floor is not rigid enough. - If they are not rigid enough, counterforce deforms the rack or floor, and responsible for the vibration.	- Reinforce the rack or floor to make it more rigid. - If reinforcing the rack or floor is impossible, modify the robot control program; doing so will reduce the vibration.

Symptom	Description	Cause	Measure
Vibration Noise (Continued)	- Vibration becomes more serious when the robot adopts a specific posture. - If the operating speed of the robot is reduced, vibration stops. - Vibration is most noticeable when the robot is accelerating. - Vibration occurs when two or more axes operate at the same time.	[Overload] - It is likely that the load on the robot is greater than the maximum rating. - It is likely that the robot control program is too demanding for the robot hardware. - It is likely that the ACCELERATION value is excessive.	- Check the maximum load that the robot can handle once more. If the robot is found to be overloaded, reduce the load, or modify the robot control program. - Vibration in a specific portion can be reduced by modifying the robot control program while slowing the robot and reducing its acceleration (to minimize the influence on the entire cycle time).
	- Vibration or noise was first noticed after the robot collided with an object or the robot was overloaded for a long period. - The grease of the vibrating or noise occurring axis has not been replaced for a long period. - Periodic vibration and noise occur.	[Gear, bearing, or reducer] - It is likely that the collision or overload applied an excessive force to the drive system, thus damaged the geartooth surface or rolling surface of a bearing, or reducer. - It is likely that prolonged use of the robot while overloaded caused fretting of the gear tooth surface or rolling surface of a bearing, or reducer due to resulting metal fatigue. - It is likely that contamination caught in a gear, bearing, or within a reducer caused damage on the gear tooth surface or rolling surface of the bearing, or reducer. - It is likely that contamination caught in a gear, bearing, or within a reducer caused vibration. - It is likely that, because the grease has not been replaced for a long period, fretting occurred on the gear tooth surface or rolling surface of a bearing, or reducer due to metal fatigue.	- Operate one axis at a time to determine which axis is vibrating. - Remove the motor, and replace the gear, the bearing, and the reducer. For the spec. of parts and the method of replacement, contact your local FANUC representative. - Using the robot within its maximum rating prevents problems with the drive mechanism. - Supplying the specified grease at the recommended interval will prevent problems.

Symptom	Description	Cause	Measure
Vibration Noise (Continued)	- The cause of problem cannot be identified from examination of the floor, rack, or mechanical unit.	[Controller, cable, and motor] - If a failure occurs in a controller circuit, preventing control commands from being supplied to the motor normally, or preventing motor information from being sent to the controller normally, vibration might occur. - Pulsecoder defect may be the cause of the vibration as the motor cannot propagate the accurate position to the controller. - If the motor becomes defective, vibration might occur because the motor cannot deliver its rated performance. - If a power line in a movable cable of the mechanical unit has an intermittent break, vibration might occur because the motor cannot accurately respond to commands. - If a Pulsecoder wire in a movable part of the mechanical unit has an intermittent break, vibration might occur because commands cannot be sent to the motor accurately. - If a connection cable between the mechanical unit and the controller has an intermittent break, vibration might occur. - If the power supply cable is about to be snapped, vibration might occur. - If the power source voltage drops below the rating, vibration might occur. - It may vibrate when the invalid value parameter was set.	- Refer to the Controller Maintenance Manual for troubleshooting related to the controller and amplifier. - Replace the motor of the axis that is vibrating, and check whether vibration still occurs. For the method of replacement, contact your local FANUC representative. - If vibration occurs only when the robot assumes a specific posture, it is likely that a cable in the mechanical unit is broken. - Shake the movable part cable while the robot is at rest, and check whether an alarm occurs. If an alarm or any other abnormal condition occurs, replace the mechanical unit cable. - Check whether the cable jacket connecting the mechanical unit and controller is damaged. If so, replace the connection cable, and check whether vibration still occurs. - Check whether the power cable jacket is damaged. If so, replace the power cable, and check whether vibration still occurs. - Check that the robot is supplied with the rated voltage. - Check that the robot control parameter is set to a valid value. If it is set to an invalid value, correct them. Contact FANUC for further information if necessary.

Symptom	Description	Cause	Measure
Vibration Noise (Continued)	- There is some relationship between the vibration of the robot and the operation of a machine near the robot.	[Noise from a nearby machine] - If the robot is not grounded properly, electrical noise is induced on the grounding wire, preventing commands from being transferred accurately, thus leading to vibration. - If the robot is grounded at an unsuitable point, its grounding potential becomes unstable, and noise is likely to be induced on the grounding line, thus leading to vibration.	- Connect the grounding wire firmly to ensure a reliable ground potential and prevent extraneous electrical noise.
	- There is an unusual sound after replacement of grease. - There is an unusual sound after a long period. - There is an unusual sound during operation at low speed.	- There may be an unusual sound when using other than the specified grease. - Even for the specified grease, there may be an unusual sound during operation at low speed immediately after replacement or after a long period.	- Use the specified grease. - When there is an abnormal noise even when using the specified grease, operate for one or two days as an experiment. Generally, any abnormal noise will disappear.
Rattling	- While the robot is not supplied with power, pushing it with the hand causes part of the mechanical unit to wobble. - There is a gap on the mounting surface of the mechanical unit.	[Mechanical section coupling bolt] - It is likely that overloading or a collision has loosened a mounting bolt in the robot mechanical section.	- Check that the following bolts for each axis are tight. If any of these bolts is loose, apply LOCTITE and tighten it to the appropriate torque. - Motor retaining bolt - Reducer retaining bolt - Reducer shaft retaining bolt - Base retaining bolt - Arm retaining bolt - Casting retaining bolt - End effector retaining bolt

Symptom	Description	Cause	Measure
Motor overheating	- The motor overheated due to the temperature in the installation area rose. - After a cover was attached to the motor, the motor overheated. - After changing the Robot control program or the load, the motor overheat.	[Ambient temperature] - It is likely that the motor overheated along with the ambient temperature rose, and could not release heat. [Operating condition] - It is likely that the overcurrent above the specified permissive average current.	- Reducing the ambient temperature is the most effective means of preventing overheat. - Having the surroundings of the motor well ventilated enables the motor to release heat efficiently, thus preventing overheat. - If there is a source of heat near, it is advisable to install shielding to protect the motor from heat radiation. - Relaxing the robot control program and load condition is effective to reduce the average current. Thus, prevent overheat. - The teach pendant can monitor the average current. Check the average current when the robot control program launched.
	- After a robot control parameter (load setting etc.) was changed, the motor overheated.	[Parameter] - If data input for a workpiece is invalid, the robot cannot be accelerated or decelerated normally, so the average current increases, leading to overheat.	- As for load setting, Input an appropriate parameter referring to Section 4.3 of the operator's manual.
	- Symptom other than stated above	[Mechanical section problems] - It is likely that problems occurred in the mechanical unit drive mechanism, thus placing an excessive load on the motor. [Motor problems] - It is likely that a failure of the motor brake resulted in the motor running with the brake applied, thus placing an excessive load on the motor. - It is likely that a failure of the motor prevented it from delivering its rated performance, thus causing an excessive current to flow through the motor. - It is likely that fan is broken.	- Repair the mechanical unit while referring to the above descriptions of vibration, noise, and rattling. - Check that, when the servo system is energized, the brake is released. If the brake remains applied to the motor all the time, replace the motor. - If the average current falls after the motor is replaced, it indicates that the first motor was faulty. - If the fan is broken, replace it by new one.

Symptom	Description	Cause	Measure

Grease leakage	- Grease is leaking from the mechanical unit.	[Poor sealing]
		- Probable causes are a crack in the casting, a broken O-ring, a damaged oil seal, or a loose seal bolt.
		- A crack in a casting can occur due to excessive force that might be caused in collision.
		- An O-ring can be damaged if it is trapped or cut during disassembling or re-assembling.
		- An oil seal might be damaged if extraneous dust scratches the lip of the oil seal.
		- A loose seal bolt might allow grease to leak along the threads.
		- Problems with the grease nipple or threads.
			- If a crack develops in the casting, sealant can be used as a quick-fix to prevent further grease leakage. However, the component should be replaced as soon as possible, because the crack might extend.
			- O-rings are used in the locations listed below.
			  - Motor coupling section
			  - Reducer (case and shaft) coupling section
			  - Wrist coupling section
			  - J3 arm coupling section
			  - Inside the wrist
			- Oil seals are used in the locations stated below.
			  - J1 cable pipe
			  - Inside the reducer
			  - Inside the wrist
			- Seal bolts are used in the locations stated below.
			  - Grease drain outlet
			  - J2-axis motor mounting part
			- Replace the grease nipple.

Dropping axis	- An axis drops because the brake does not function.
	- An axis drops gradually when it should be at rest.
		[Brake drive relay and motor]
		- It is likely that brake drive relays are stuck to each other and keep the brakes current flowing, thus preventing the brake from operating when the motor is reenergized.
		- It is likely that the brake shoe has worn out or the brake main body is damaged, preventing the brake from operating efficiently.
		- It is likely that oil or grease soak through the motor, causing the brake to slip.
			- Check whether the brake drive relays stuck each other or not. If they are found to be stuck, replace the relay.
			- Replace the motor confirmed following symptoms.
			  - Brake shoe is worn out
			  - Brake main body is damaged
			  - Oil soak through the motor

Symptom	Description	Cause	Measure
Displace-ment	- The robot moves to a point other than the taught position. - The repeatability is not within the tolerance.	[Mechanical section problems] - If the repeatability is unstable, probable causes are a failure in the drive mechanism or a loose bolt. - If the repeatability becomes stable, it is likely that a collision imposed an excessive load, leading to slipping on the base surface or the mating surface of an arm or reducer. - It is likely that the Pulsecoder is faulty.	- If the repeatability is unstable, repair the mechanical section by referring to the above descriptions of vibration, noise, and rattling. - If the repeatability is stable, correct the taught program. The problem will not occur unless another collision occurs. - If the Pulsecoder is faulty, replace the motor.
	- Displacement occurs only in specific peripheral equipment.	[Peripheral equipment displacement] - It is likely that an external force was applied to the peripheral equipment, thus shifting its position relative to the robot.	- Correct the setting of the peripheral equipment position. - Correct the taught program.
	- Displacement occurred after a parameter was changed.	[Parameter] - It is likely that the mastering data was rewritten in such a way that the robot origin was shifted.	- Re-enter the previous mastering data, which is known to be correct. - If correct mastering data is unavailable, perform mastering again.
CLALM alarm occurred. Move error excess alarm occurred.	- CLALM alarm is displayed on the teach pendant screen, because ambient temperature of the robot installation location is low, - “Move error excess” alarm is displayed on the teach pendant screen, because ambient temperature of the robot installation position is low	[Peripheral temperature] - When the robot is used in a low temperature environment that is near to 0ºC, or the robot is not operated for a long time in an environment that is less than 0ºC, there will be a large viscous resistance of the drive train immediately after starting which will cause the alarm.	- Perform a warm up operation or a low speed operation for several minutes.

Symptom	Description	Cause	Measure
CLALM alarm occurred. Move error excess alarm occurred.	- After changing the motion program or the load condition, the CLALM alarm is displayed. - After changing the motion program or the load condition, the “Move error excess” alarm is displayed.	- It is likely that a robot collision occurred.	- If a robot collision has occurred, press the [RESET] key while pressing the [SHIFT] key. Then, jog the robot in the opposite direction while pressing the [SHIFT] key. - Check the motion program.
		[Overload] - It is likely that load exceeded the permissible value. - It is likely that the motion program is too severe for the robot. ・ Excessive motion due to a large “ACC (value)”. ・ Tight motion such as reverse motion using “CNT”. ・ Linear motion occurs near singularity point where axes revolve in high speed.	- Check the permissible value of the robot payload. If the load exceeds the permissible value, reduce the load or change the motion program. - Consider minimizing the cycle time by reducing the speed or acceleration, and changing the motion program. - Check that the load setting is performed correctly.
	- None of the symptoms stated above are the problem.	- It is likely the vibration occurred.	- Refer to the Symptoms: Vibration, Noise section of this troubleshooting for more information.
		- If the power source voltage drops below the rating, a vibration might occur.	- Check that the robot is supplied with the proper rated voltage.
		- Angle of robot mounting surface is not set correctly.	- According to “Angle of Mounting Surface Setting”, set the angle of robot mounting surface correctly.
BZAL alarm occurred.	- BZAL is displayed on the teach pendant screen.	- It is likely that the voltage of the memory backup battery is low. - It is likely that the Pulsecoder cable is defective.	- Replace the battery. - Replace the cable.

10 SEVERE DUST/LIQUID PROTECTION PACKAGE

10.1 SEVERE DUST/LIQUID PROTECTION PACKAGE(OPTION)

The package is intended to improve the Severe dust/Liquid protection characteristics of the robot so that it can be used in a severe environment. Refer to Section 3.1 about dustproof and waterproof characteristics of the Severe dust/Liquid protection.

NOTE
Contact your FANUC representative for confirmation that the Severe Dust/liquid protection package is suitable for your environment.

Model	Severe dust/liquid protection specification
R-1000*i*A/80F	A05B-1330-J801 (*1)
	A05B-1330-J802 (*2)
R-1000*i*A/100F	A05B-1330-J803 (*1)
	A05B-1330-J804 (*2)
R-1000*i*A/80H	A05B-1330-J805 (*1)
	A05B-1330-J806 (*2)

(*1) J3-axis adjustable stopper is not selected
(*2) J3-axis adjustable stopper is selected

10.2 CONFIGURATION OF THE SEVERE DUST/LIQUID PROTECTION PACKAGE

The following table lists the major differences between the R-1000*i*A standard specification and severe dust/liquid protection package.

	Standard specifications	Severe dust/liquid protection option	
	Entire mechanical unit	Main unit	J3 arm and wrist
Bolts	Black oxide finish steel bolt Black oxide finish washer	FR coating bolt Black chromate washer Stainless bolt Black oxide finish steel bolt	FR coating bolt Stainless bolt Black chromate washer
Covers		J1/J2-axes motor cover J3/J4/J5/J6-axes motor cover Battery box cover Cable cover in mechanical unit (for all exposed cables)	
J3 connector panel EE(RI/RO), I/O connectors	Non-waterproof connector	Waterproof connector	

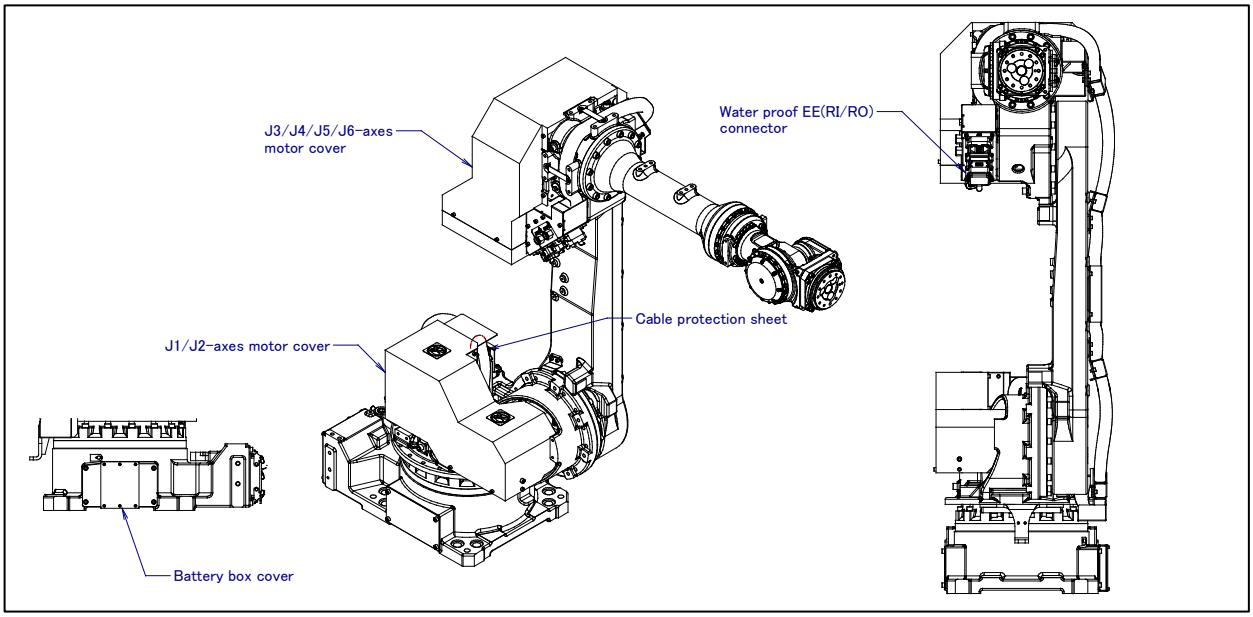


Fig. 10.2 (a) Configuration of the severe dust/liquid protection package

APPENDIX

A PERIODIC MAINTENANCE TABLE

FANUC Robot R-1000*i*A **Periodic Maintenance Table**

Items		Accumulated operating time (H)	Check time	Grease amount	First check 320	3 months 960	6 months 1920	9 months 2880	1 year 3840	4800	5760	6720	2 years 7680	8640	9600	10560
Mechanical unit	1	Check for external damage or peeling paint	0.1H	—		○	○	○	○	○	○	○	○	○	○	○
	2	Check damages of the cable protective sleeves	0.1H	—		○	○	○	○	○	○	○	○	○	○	○
	3	Check wear debris of the J1-axis swing stopper	0.1H	—		○	○	○	○	○	○	○	○	○	○	○
	4	Check for water	0.1H	—		○	○	○	○	○	○	○	○	○	○	○
	5	Check the mechanical cable. (damaged or twisted)	0.1H	—		○			○				○			
	6	Check the end effector (hand) cable	0.1H	—		○			○				○			
	7	Check the motor connector. (loosening)	0.1H	—		○			○				○			
	8	Tighten the end effector bolt	0.1H	—		○			○				○			
	9	Tighten main bolts.	1.0H	—		○			○				○			
	10	Check the mechanical stopper and adjustable mechanical stopper	0.1H	—		○			○				○			
	11	Clean spatters, sawdust and dust	0.1H	—		○			○				○			
	12	Check the operation of the cooling fan	0.1H	—		○			○				○			
	13	Replacing battery *3	0.1H	—							●					
	14	Replacing grease of J1-axis reducer	0.7H	3570ml												
	15	Replacing grease of J2-axis reducer (R-1000*i*A/80F/80H)	0.5H	1670ml												
		Replacing grease of J2-axis reducer (R-1000*i*A/100F/130F /120F-7B)	0.5H	1470ml												
	16	Replacing grease of J3-axis reducer	0.5H	1060ml												
	17	Replacing grease of J4-axis gearbox	0.5H	2090ml												
	18	Replacing grease of the wrist axis (J4/J5/J6) (R-1000*i*A/80F)	0.5H	1540ml												
		Replacing grease of the wrist axis (J4/J5/J6) (R-1000*i*A/100F /130F/120F-7B)	0.5H	1780ml												
		Replacing grease of the wrist axis (J4/J5) (R-1000*i*A/80H)	0.5H	1410ml												
	19	Replacing grease of E1-axis reducer(R-1000*i*A/120F-7B)	0.5H	1670ml												
	20	Replacing cable of mechanical unit	4.0H	—												
Controller	21	Check the robot cable, teach pendant cable and robot connecting cable	0.2H	—		○			○				○			
	22	Cleaning the ventilator	0.2H	—	○	○	○	○	○	○	○	○	○	○	○	○
	23	Replacing battery *1 *3	0.1H	—												

*1 Refer to “REPLACING UNITS Chapter of MAINTENANCE ” of the following manuals.
R-30*i*A CONTROLLER MAINTENANCE MANUAL (Standard) (B-82595EN),
R-30*i*A CONTROLLER MAINTENANCE MANUAL (For Europe) (B-82595EN-1),
R-30*i*A CONTROLLER MAINTENANCE MANUAL (For RIA) (B-82595EN-2),
R-30*i*B/R-30*i*B Plus CONTROLLER MAINTENANCE MANUAL (B-83195EN),
R-30*i*B Mate/R-30*i*B Mate Plus CONTROLLER MAINTENANCE MANUAL (B-83525EN)

*2 ●: requires order of parts
○: does not require order of parts

*3 Regardless of the operating time, replace the mechanical unit batteries at 1.5 year, replace controller batteries at 4 years.

3 years 11520	12480	13440	14400	4 years 15360	16320	17280	18240	5 years 19200	20160	21120	22080	6 years 23040	24000	24960	25920	7 years 26880	27840	28800	29760	8 years 30720	Item
○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○		1
○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○		2
○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○		3
○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○		4
○				○				○				○				○					5
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				●																	23

Overhaul

B STRENGTH OF BOLT AND BOLT TORQUE LIST

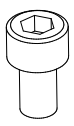
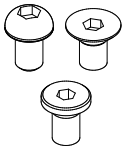
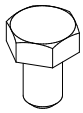
NOTE
When applying LOCTITE to a part, spread the LOCTITE on the entire length of the engaging part of the female thread. If applied to the male threads, poor adhesion can occur potentially loosening the bolt. Clean the bolts and the threaded holes and wipe off the oil on the engaging section. Make sure that there is no solvent left in the threaded holes. In this case, remove all the excess LOCTITE when you are finished screwing the bolts into the threaded holes.

Use the following strength bolts. Comply with any bolt specification instructions as specified.

Hexagon socket head bolt made of steel:
Size M22 or less: Tensile strength 1200N/mm^2 or more
Size M24 or more: Tensile strength 1000N/mm^2 or more
All size plating bolt: Tensile strength 1000N/mm^2 or more
Hexagon bolt, stainless bolt, special shape bolt (button bolt, low-head bolt, flush bolt .etc.)
Tensile strength 400N/mm^2 or more

Refer to the following tables if the bolts tightening torque are not specified.

Recommended bolt tightening torques **Unit: Nm**

Nominal diameter	Hexagon socket head bolt (steel)		Hexagon socket head bolt (stainless steel)		Hexagon socket head button bolt Hexagon socket head flush bolt Low-head bolt (steel)		Hexagon bolt (steel)	
	Tightening torque		Tightening torque		Tightening torque		Tightening torque	
	Upper limit	Lower limit	Upper limit	Lower limit	Upper limit	Lower limit	Upper limit	Lower limit
M3	1.8	1.3	0.76	0.53	———	———	———	———
M4	4.0	2.8	1.8	1.3	1.8	1.3	1.7	1.2
M5	7.9	5.6	3.4	2.5	4.0	2.8	3.2	2.3
M6	14	9.6	5.8	4.1	7.9	5.6	5.5	3.8
M8	32	23	14	9.8	14	9.6	13	9.3
M10	66	46	27	19	32	23	26	19
M12	110	78	48	33	———	———	45	31
(M14)	180	130	76	53	———	———	73	51
M16	270	190	120	82	———	———	98	69
(M18)	380	260	160	110	———	———	140	96
M20	530	370	230	160	———	———	190	130
(M22)	730	510	———	———	———	———	———	———
M24	930	650	———	———	———	———	———	———
(M27)	1400	960	———	———	———	———	———	———
M30	1800	1300	———	———	———	———	———	———
M36	3200	2300	———	———	———	———	———	———
								

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REVISION RECORD

Edition	Date	Contents
11	Sep.,2022	• Addition of angle of mounting surface setting • Addition of mechanical unit cables • Correction of errors
10	Oct.,2021	• Change of the grease amount • Correction of errors
09	Sep.,2020	• Change of the transport equipment • Correction of errors
08	Aug.,2018	• Addition of R-1000*i*A/120F-7B (A05B-1330-B226) • Correction of errors
07	Nov.,2016	• Addition of R-1000*i*A/130F • Correction of errors
06	Jul.,2016	• Addition of R-1000*i*A/120F-7B • Addition of quick mastering for single axis • Correction of errors
05	Dec.,2013	• Addition of R-30*i*B Mate • Addition of R-1000*i*A/80H • Correction of errors
04	Apr.,2012	• Addition of R-30*i*B • Addition of note for low temperature • Addition of mechanical unit cables • Addition of check of oil leak • Correction of errors
03	Mar.,2011	• Addition of R-1000*i*A/100F • Addition of Severe dust/liquid protection package • Addition of stop type of robot • Addition of stopping time and distance when controlled stop is executed • Correction of errors
02	Jun., 2009	• Change of J1-axis mechanical stopper • Addition of J2, J3-axis adjustable mechanical stopper • Addition of check of stopper • Correction of errors
01	Jan., 2009	

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