

**Kawasaki Robot
BA Series**

**Installation and
Connection Manual**

-Arc Welding-

Robot

Kawasaki Heavy Industries, Ltd.

Preface

This manual describes installation and operation procedures required for applying the robot arm BA series which is controlled by Kawasaki Robot E01 or F60 controller to arc welding.

Read and understand the contents of this and “Safety Manual” thoroughly and strictly observe all rules for safety before proceeding with any operation. Installation and connection methods in this manual apply only to arc welding equipment. Read this manual together with the following manuals: “Installation and Connection Manual” for Robot Arm, and “Installation and Connection Manual” for Controller.

This manual is applicable to the following robots.

BA006N/006L E01
BA006N/006L F60

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1. This manual does not constitute a guarantee of the systems in which the robot is utilized. Accordingly, Kawasaki is not responsible for any accidents, damages, and/or problems relating to industrial property rights as a result of using the system.
 2. It is recommended that all personnel assigned for activation of operation, teaching, maintenance or inspection of the robot attend the necessary education/training course(s) prepared by Kawasaki, before assuming their responsibilities.
 3. Kawasaki reserves the right to change, revise, or update this manual without prior notice.
 4. This manual may not, in whole or in part, be reprinted or copied without the prior written consent of Kawasaki.
 5. Store this manual with care and keep it available for use at any time. If the robot is reinstalled or moved to a different site or sold off to a different user, attach this manual to the robot without fail. In the event the manual is lost or damaged severely, contact Kawasaki.
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Symbols

The items that require special attention in this manual are designated with the following symbols.

Ensure proper and safe operation of the robot and prevent physical injury or property damages by complying with the safety matters given in the boxes with these symbols.

 **DANGER**

Failure to comply with indicated matters can result in imminent injury or death.

 **WARNING**


Failure to comply with indicated matters may possibly lead to injury or death.

 **CAUTION**

Failure to comply with indicated matters may lead to physical injury and/or mechanical damage.

[NOTE]

Denotes precautions regarding robot specification, operation, and maintenance.

 **WARNING**

- 1. The accuracy and effectiveness of the diagrams, procedures, and detail explanations given in this manual cannot be confirmed with absolute certainty. Accordingly, it is necessary to give one's fullest attention when using this manual to perform any work. Should any unexplained questions or problems arise, please contact Kawasaki.**
- 2. Safety related contents described in this manual apply to each individual work and not to all robot work. In order to perform every work in safety, read and fully understand the "Safety Manual", all pertinent laws, regulations and related materials as well as all the safety explanations described in each chapter, and prepare safety measures suitable for actual work.**

Safety

When installing and connecting the Arc Welding Robot, carefully read the following precautions together with the safety precautions in the “Installation and Connection Manual” for Robot Arm and Controller.

Installation Environment of Robot Arm

1. Install the safety fence in consideration of not only the motion range of the robot arm but also the distance that protects operators/personnel from any possible exposure to arc spatter.
2. Provide light shield in order to protect operators/personnel from arc burning and eye injury caused by direct viewing of arc beam.
3. Do not put any flammable/combustible materials around the Arc Welding Robot.

Installation of the Robot Arm

1. Be sure to isolate the robot arm from the torch and welding wires.

Installation and Connection of Controller

1. Provide an external power switch exclusively for the robot. Do not share the switch with the welder and other equipment.
2. Use the dedicated ground (100 Ω or less). Never share the ground with welder, etc. for grounding wire or grounding electrode.
3. Never wire the motor cable and the signal cable through under the welder.
4. To avoid influence by electromagnetic noises generated from welding arc, install precision equipment, etc. away from welding arc and supply input power separately.



CAUTION

When there is equipment which generates high levels of noise, such as electromagnetic contactors, brakes, solenoids and induction motors, around the installation site, attach an appropriate surge killer to them to prevent from generating the noise.

Harness Connection

Strictly observe the following precautions when connecting the robot arm with the robot controller.



WARNING

In order to prevent accidents caused by electric shock, do not connect the external power until connections between the robot arm and robot control equipment are complete.



CAUTION

- 1. Be careful when connecting the harnesses. Be sure to use the correct harnesses. Using an incorrect harness, or forcing or misconnecting the harness may damage connectors or cause a break in the electrical system.**
- 2. Prevent people or equipment (forklift etc.) from stepping on or riding over the harnesses and connection cables between transformer unit and controller. Otherwise, the harness may become damaged or the electrical system may break.**
- 3. Separate the harnesses from any nearby high voltage lines (minimum 1 m apart). Do not bundle or run the harnesses in parallel with other power lines. Otherwise, the noise generated from power lines will cause malfunctions.**
- 4. Even when the harnesses are long, do not bundle them winded or bended. Bundling the harness causes the heat to build up in the harness, resulting in over-heat and furthermore may cause fire.**

External Power Connection

Strictly observe the following precautions when connecting the external power.



DANGER

Before beginning the connection work, confirm that the external power supply for the control equipment is cut off at the source. To prevent external power from being turned ON accidentally, tag the breaker and indicate clearly that work is in progress. Or, assign a supervisor in front of the breaker until all the connections are complete. Connecting work while power is supplied is extremely dangerous and may cause electric shock.



WARNING

- 1. Confirm that the connected supplying power to the controller meets specifications shown on the rating plate. In addition, when using the transformer unit, confirm the connected supply power meets specifications shown on the label attached on the side of the transformer unit and connect the voltage switching tap connector (X601) in accordance with the voltage specifications. Supplying out-of-specification power will damage electric components in the controller.**
- 2. Ground the controller to prevent against electrical noise and shock.**
- 3. Use dedicated ground wire (100 Ω or less), which is equal to or larger than the recommended power cable size (3.5 to 8.0 mm²).**
- 4. Never share a ground line with workpiece to be welded or another machine (weld machine, etc.).**
- 5. In arc welding applications, connect the minus pole of the weld power supply to a jig or directly to workpiece to be welded. Insulate the robot body and controller so that they do not share a common ground line.**
- 6. Without fail, before turning ON the external power to control equipment, make sure the power supply wiring is complete and all the covers reattached properly. Failure to do so may cause electric shock.**



CAUTION

1. Prepare external power that meets the specifications of the control equipment in terms of momentary power interruption, voltage fluctuation, power capacity, etc. If the power is interrupted or the voltage goes out of the control equipment's specified range (above/below ratings), then the power monitoring circuit activates cutting off the power, and an error is returned.
2. If the external power emits a lot of electrical noise, set up a noise filter to reduce the interference.
3. PWM noise from robot motor lines may cause malfunction of low noise-resistant devices* via external power line. Confirm that there are no such devices in the vicinity.
4. Install a separate external power switch (breaker) for the robot, independent and unconnected to the weld machine.
5. To prevent shorting or accidental leakage on the external power switch, install a ground leakage breaker. (Use a time delay type with sensitivity of 100 mA or more.) Also, use a time-delay-type ground leakage breaker with sensitivity of 100 mA or more when using a transformer unit.
6. If there is a possibility that surge voltage such as lightning surge might be applied from external power line, decrease the surge voltage level by mounting a surge absorber.

NOTE* Proximity switch directly connected with power line etc. may suffer from the influence.

Connection with Welding Equipment

1. Check if the welding cable has no damages before connections. Use only the welding cable with no damages.
2. Use and handle the gas cylinders with caution.
3. Firmly fix the gas cylinders so as not to fall over.
4. Check if the gas hose and water-cooling torch hose have no damages on them. Use only hoses with no damages.
5. Conduct gas and water piping without gas or water leakage.
6. When using a gas flowmeter, check if it is for gas cylinders or for the factory piping, and use the appropriate flow meter.

Arc Welding Work

1. Enclose the source of arc ray with welding screen/plate. Arc rays can injure eyes and burn skin. Never look at the arc ray directly.
2. All operators and supervisors must wear welding glasses or masks with sufficient protection grade to protect their eyes from arc ray, spatter and slag or filler wires.
3. Use suitable welding curtain to protect the eyes of nearby persons from the arc rays.
4. Always wear welding glasses in a welding area.
5. Wear appropriate protective clothing such as leather gloves, long-sleeve shirts, leggings, leather apron, etc. in order to avoid burns caused by hot workpieces after welding and by spatter and slag.
6. Do not use flammable materials such as paint, grease, etc. near the welding area.
7. Remove flammables and combustibles well away from the welding area.
8. Always have someone watch for fire.
9. Use enough ventilation to keep hazardous fumes and gases away from the breathing zone.
10. When welding, keep your head as far away as possible from the fume to minimize the amount of fume inhaled.
11. To prevent intoxication or to eliminate possible oxygen deficiency, supply adequate ventilation by an exhaust system located as close to the work area as possible or by respiratory protection per pertinent laws and regulations, such as Industrial Safety and Health Law, Ordinance on Prevention of Hazards due to Dust.
12. Properly insulate and ground each of the required devices according to instructions for each device.
13. Electric arc welding produces electromagnetic field which may have bad influences on the pacemaker. Therefore, persons with pacemakers should not go near welding operations until they have consulted their doctor.

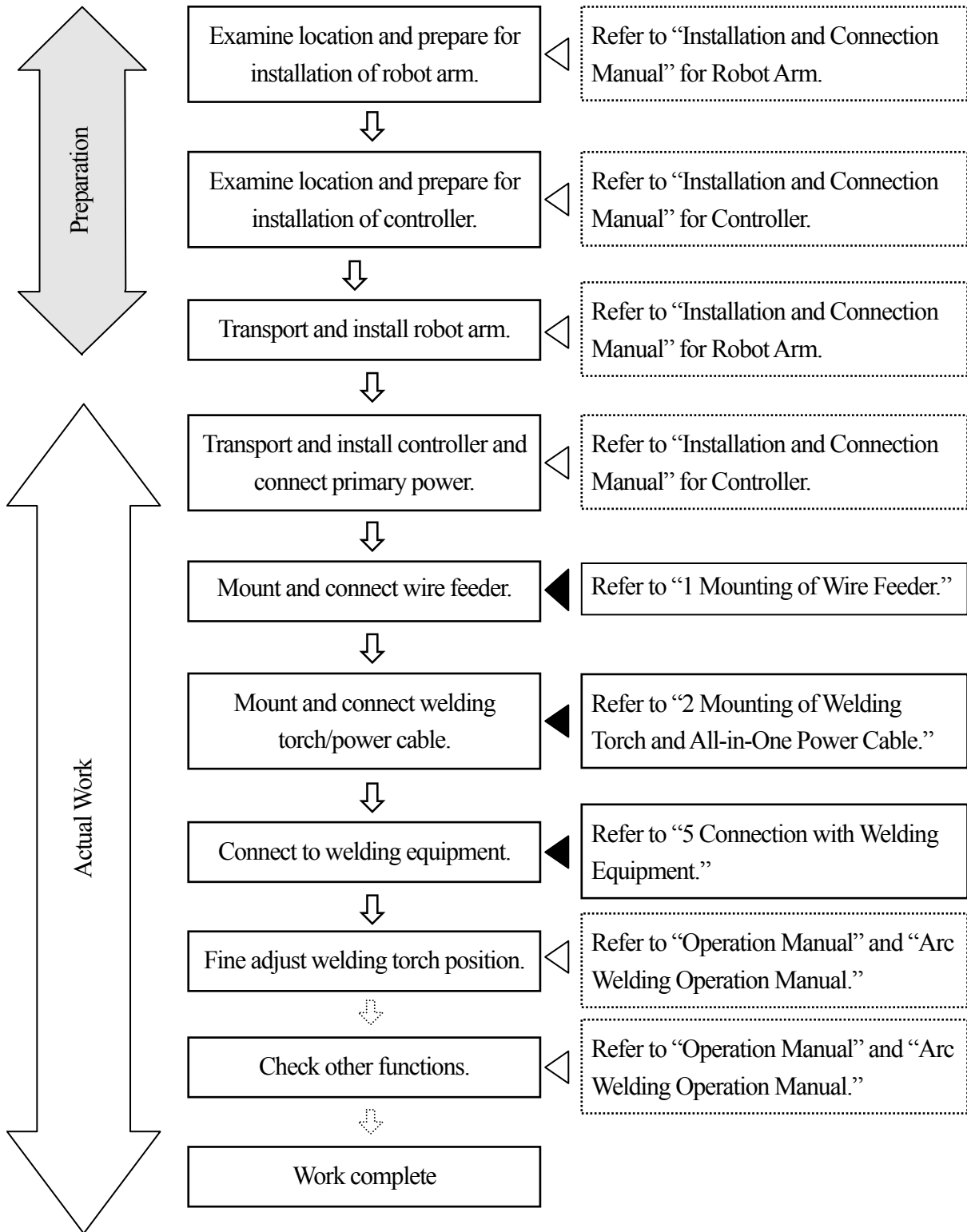
14. The electromagnetic noise produced in arc welding may cause malfunction of peripheral devices without noise protection.
15. Use the laser devices in accordance with the instructions from the manufacturer when using laser welder, laser sensor and so on.
16. Incorrect usage of laser devices may result in severe injuries. Especially, take proper “eye safety” precautions, since there is a risk for blindness. Laser beams may also burn skin, clothing or ignite surrounding volatile substances such as alcohol.

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Work Flow at Installation and Connection of Arc Welding Robot



1 Mounting of Wire Feeder

This manual describes wire feeders CMRE-741 and CMRE-742 manufactured by Daihen (OTC). For other wire feeders, please consider by yourself or contact Kawasaki.



WARNING

1. **Before starting mounting of wire feeder, move the robot arm to a place where the work can be done easily and turn OFF the “motor power” and the “controller power.”**
2. **Keep isolation between the wire feeder and the robot arm by bakelite board etc. without fail. Otherwise welding current might short to the robot arm due to the isolation failure.**

1.1 Floor-standing Installation

Follow the procedures below to mount wire feeder onto the posterior part of JT3 of the upper arm. The fixing brackets are separately required for mounting.

1. Referring to Figure 1.1, mount the fixing bracket onto the posterior part of JT3 of arm using four hexagon socket head bolts (M4×10).
2. Referring to Figure 1.2, mount the wire feeder to the fixing bracket. Fix it temporarily using the hexagon head bolts and washers and nuts. (The bracket is fixed temporarily in order to adjust the tension of all-in-one power cable.)
3. Figure 1.3 shows the state after the wire feeder is mounted.

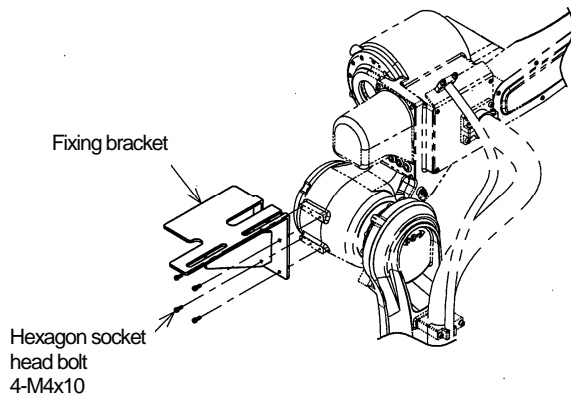


Figure 1.1 Mounting of fixing bracket
(Procedure 1)

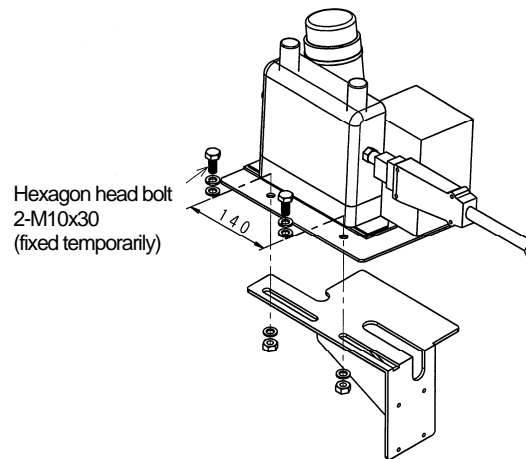


Figure 1.2 Mounting of wire feeder
(Procedure 2)

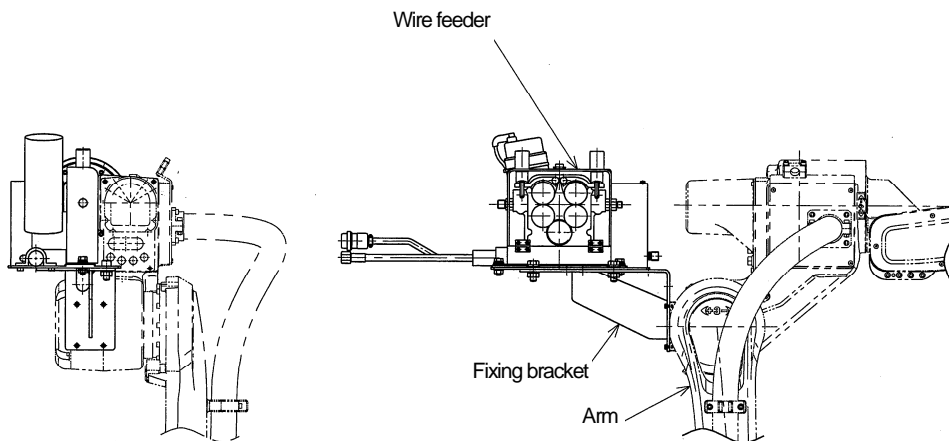


Figure 1.3 Outline view of mounting wire feeder (Procedure 3)

1.2 Ceiling Installation

Installation place will vary depending on the conditions at your production facility. Carry out an appropriate installation procedure in consideration of the workpiece and other obstacles.

1.3 Wiring and Piping of the Wire Feeder

1. Referring to Figure 1.4, unscrew four hexagon socket head bolts (M4×10) and open the cover of optional BOX on the upper arm.
2. Referring to Figure 1.5, connect the connectors (XMSA1, XMSA2) with the cable provided inside the optional BOX and the control cable (relay) (option). In addition, take out the gas hose inside the optional BOX, attach the reducing nipple (option) and one touch coupling (option), and connect them with the gas hose of the wire feeder.
3. Connect the shock sensor harness of the all-in-one power cable to the connector (XLS). (Refer to the “Mounting of All-in-One Power Cable” mentioned below for the connection of the shock sensor harness.)
4. Remount the cover of the optional BOX after the connection as it was.

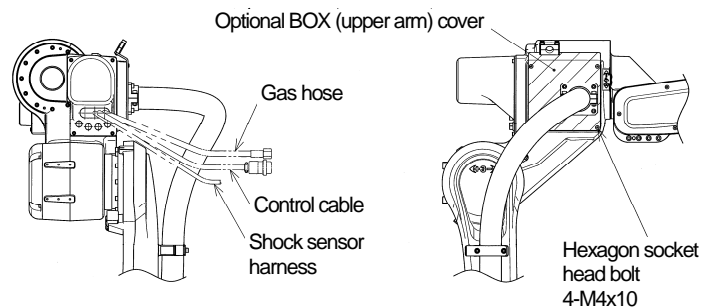


Figure 1.4 Outline of optional BOX (upper arm)

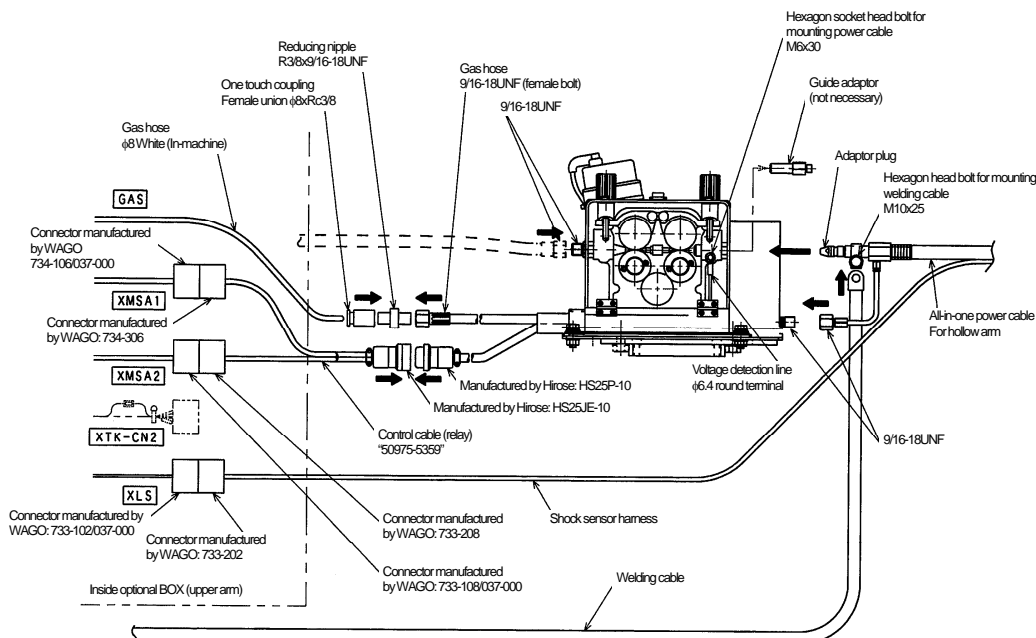


Figure 1.5 Connection of control cable and gas hose

[NOTE]

Shock sensor and control cable connectors are attached on the connector connected to the harness inside the optional BOX.

2 Mounting of Welding Torch and All-in-One Power Cable

The torches mentioned in this manual are as follows.

- Torch manufactured by TOKIN (N-type: torch gauge non-support type)
- Torch manufactured by TOKIN (G-type)
- Torch manufactured by ABICOR BINZEL

When mounting the all-in-one power cable for BA006L, pass the all-in-one power cable through the guide cable as shown in Figure 2.1, and then mount the all-in-one power cable.

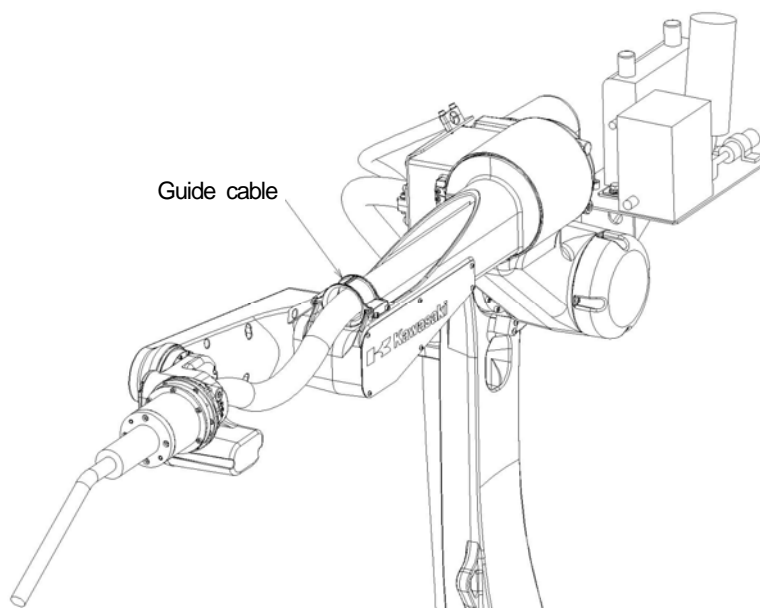


Figure 2.1 Guide cable for BA006L



WARNING

Before mounting the welding torch, move the robot arm to a place where work can be done easily and turn OFF the “motor power” and the “controller power” of the robot controller. When replacing/mounting a welding torch that is connected to the welder, turn OFF the power to the welder before starting the work without fail.

2.1 Mounting Non-Kawasaki Shock Sensor on Wrist Flange

1. Mount a torch holder and welding torch whose total weight is within the load capacity of the robot, specified in separate manual “Installation and Connection Manual” for Robot Arm.
2. Keep isolation between wrist flange and welding torch without fail.

2.2 Mounting of Torch, Shock Sensor and Power Cable Manufactured by TOKIN Corporation (N-type)

2.2.1 Mounting of All-in-One Power Cable Manufactured by TOKIN Corporation (N-type)

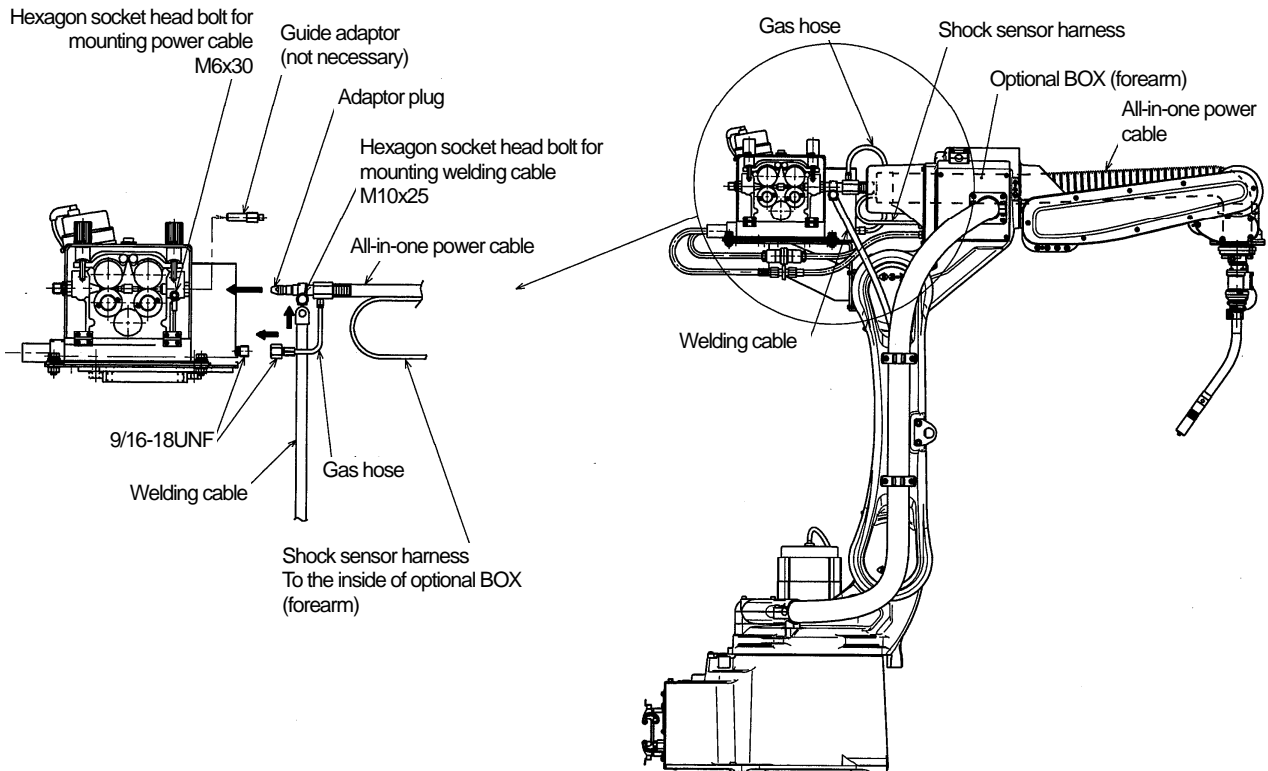


Figure 2.2 Mounting of all-in-one power cable manufactured by TOKIN (N-type)

Refer to “1.3 Wiring and Piping of the Wire Feeder” for the connection between the all-in-one power cable and wire feeder/robot.

1. Put the all-in-one power cable through the hollow section (inside wrist, upper arm) of the robot arm. Unscrew hexagon socket head bolt (M6×30) for mounting power cable of the wire feeder and remove the guide adaptor. Then, insert the adaptor plug of the all-in-one power cable and screw the hexagon socket head bolt for mounting power cable as it was. (Do not use the removed guide adaptor.)
2. Connect the welding cable using the hexagon head bolt (M10×25) of the all-in-one power cable.
3. Mount the gas hose of the all-in-one power cable to the wire feeder.
4. Connect the shock sensor harness of the all-in-one power cable to the connector inside the optional BOX of the upper arm.

2.2.2 Mounting of Torch and Shock Sensor Manufactured by TOKIN Corporation (N-type)

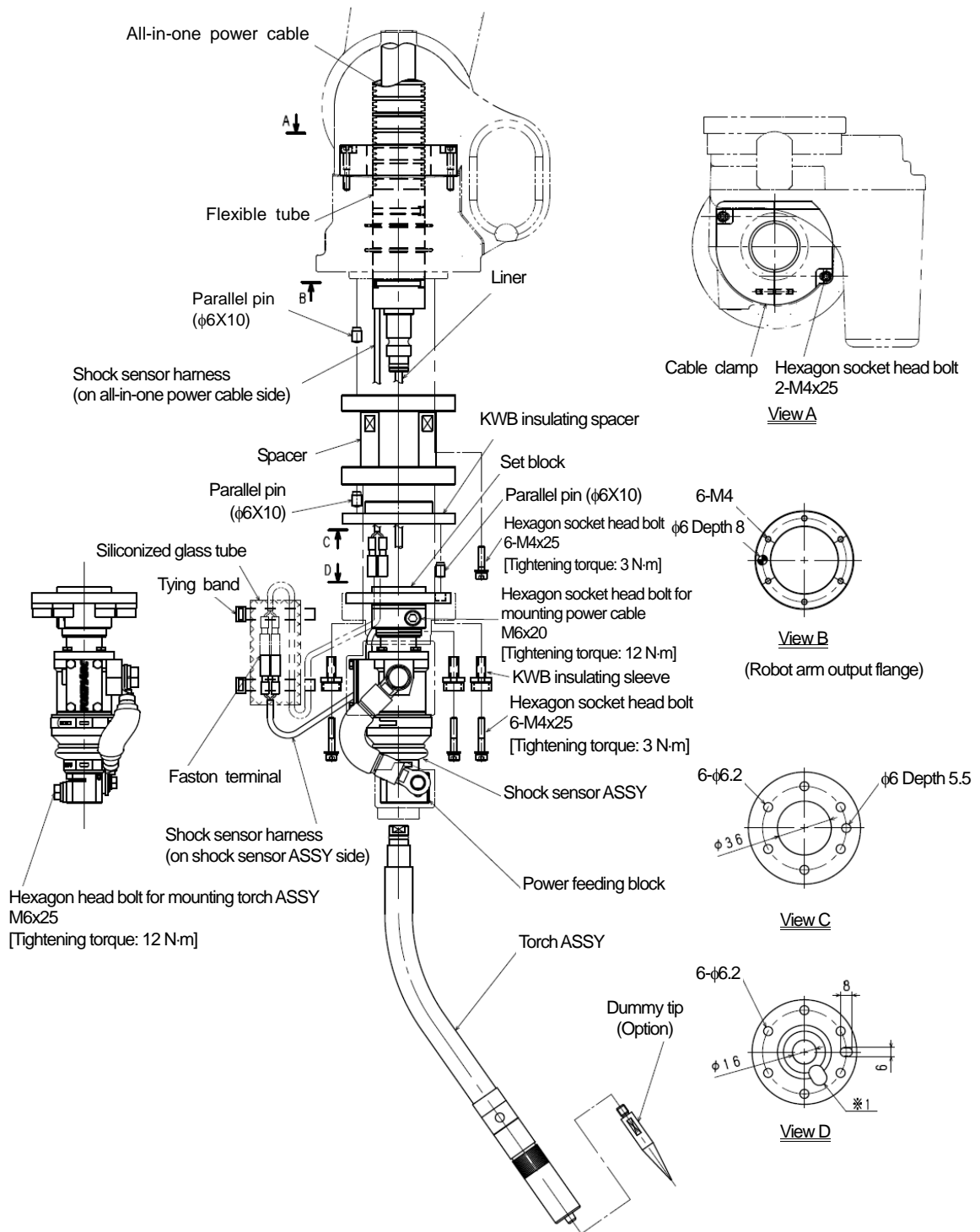
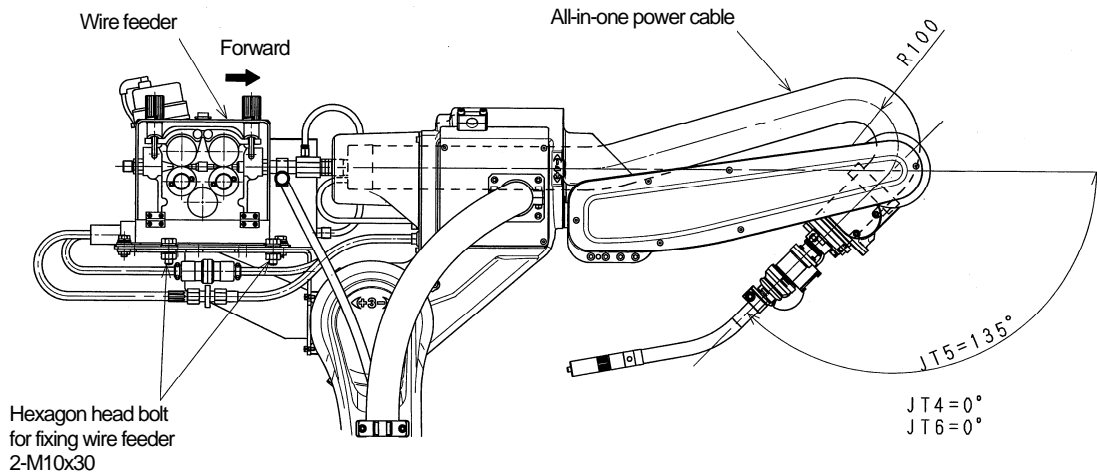


Figure 2.3 Mounting of torch and shock sensor manufactured by TOKIN (N-type)

1. Insert the parallel pins ($\phi 6 \times 10$) into the output flange of the robot arm, and screw six hexagon socket head bolts (M4 \times 15) to install the spacer.
2. Insert the parallel pins ($\phi 6 \times 10$) into the output flange of the spacer, and push the KWB insulating spacer into the flange.
3. Unscrew the hexagon socket head bolt (M6 \times 20) for mounting power cable of the all-in-one power cable, fit the all-in-one power cable liner into the set block securely while inserting it into the shock sensor ASSY, screw the hexagon socket head bolt (M6 \times 20) for mounting power cable and tighten it to the specified torque so that the cable does not come off.
4. Insert the parallel pins ($\phi 6 \times 10$) into the shock sensor, insert six hexagon socket head bolts (M4 \times 25) into six KWB insulating sleeves while putting the shock sensor harness of all-in-one power cable through the hole of the shock sensor ASSY (view D *1), then put them through the KWB insulating spacer and mount the shock sensor to the output flange of the robot arm by tightening the bolts to the specified torque.
5. Fit the torch ASSY into the power feeding block of the shock sensor ASSY, and fix it by tightening the hexagon head bolt (M6 \times 25) to the specified torque.
6. Clamp the flexible tube of the all-in-one power cable with cable clamp, and mount it on the wrist of the robot using two hexagon socket head bolts (M4 \times 25).
7. Connect the Faston terminal of the shock sensor, protect it with the attached siliconized glass tube and bundle it with tying bands.

2.2.3 Method of Adjusting Tension of All-in-One Power Cable Manufactured by TOKIN Corporation (N-type)



NOTE* The outline view of the robot arm may differ depending on the model.

Figure 2.4 Robot posture when adjusting tension

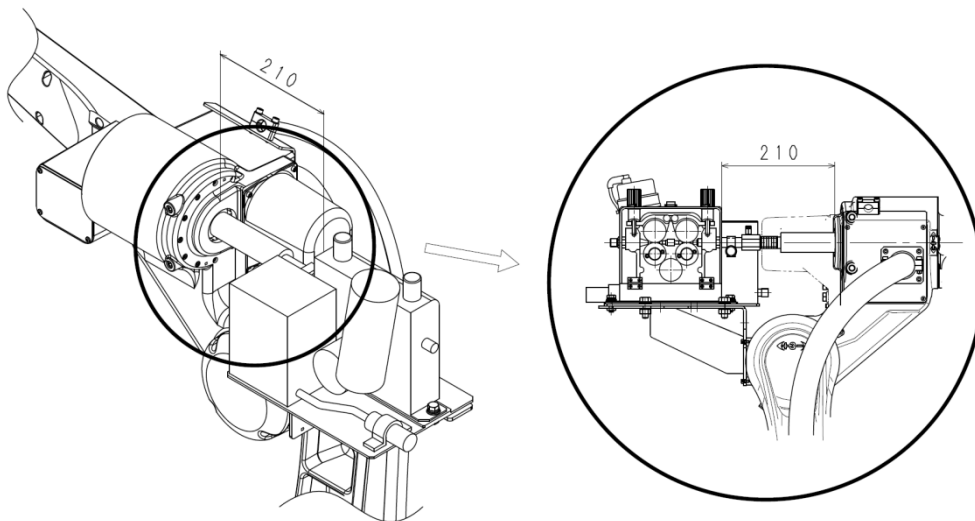


Figure 2.5 Fixing position of wire feeder (manufactured by TOKIN N-type)

1. Confirm that the shock sensor and the all-in-one power cable are mounted on the robot.
2. Move the wire feeder toward the front of the fixing bracket as much as possible.
3. Move the robot to the posture shown in the Figure 2.4.
4. Moving the wire feeder backward, pull the all-in-one power cable so that it does not have slack, arrange it in the position shown in the Figure 2.5, and fix it using two hexagon head bolts (M10×30).

[NOTE]

The tension must be adjusted, because the torch cable may be disconnected or its lifetime may shorten if not. In addition, when the bending radius of the all-in-one power cable is 100 mm or less or when slack is observed, adjust the tension by moving the wire feeder forward/backward.

2.3 Mounting of Torch, Shock Sensor and Power Cable Manufactured by TOKIN Corporation (G-type)

2.3.1 Mounting of All-in-One Power Cable Manufactured by TOKIN Corporation (G-type)

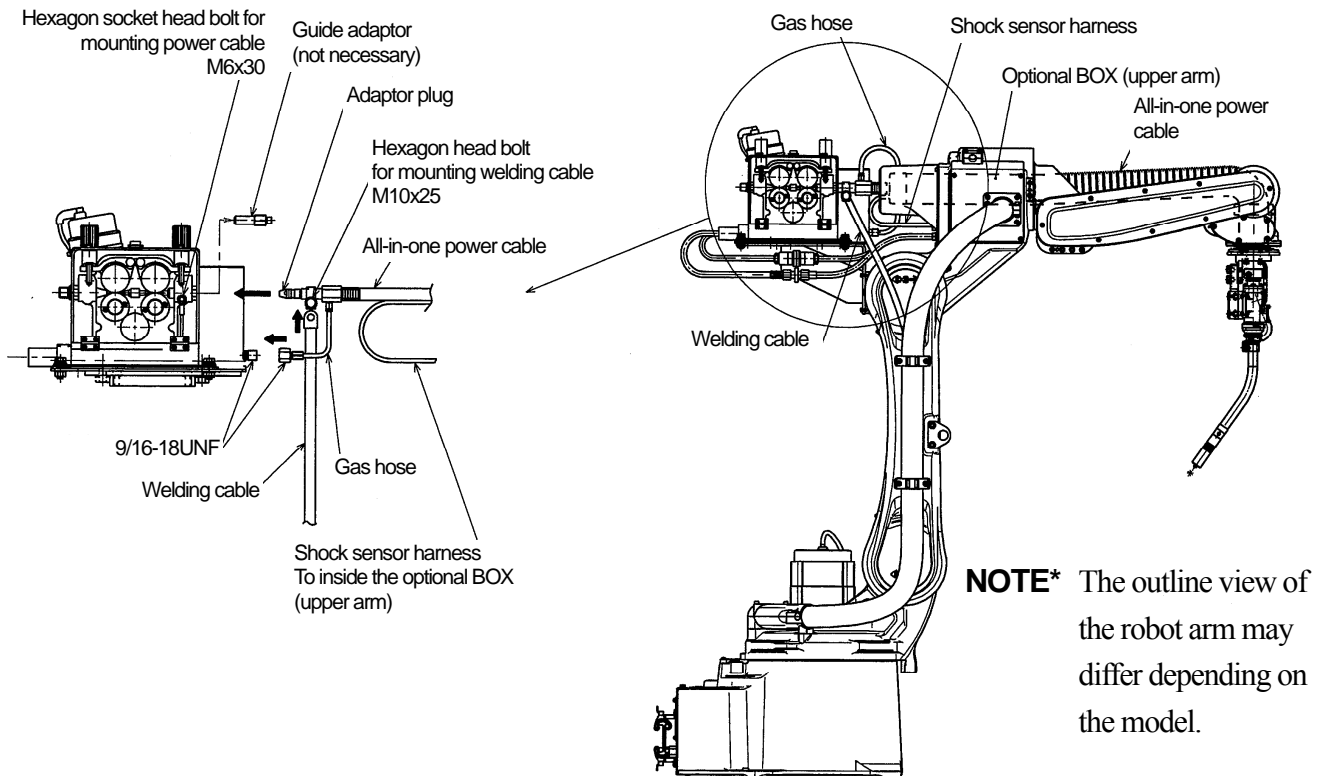


Figure 2.6 Mounting of all-in-one power cable manufactured by TOKIN (G-type)

Refer to “1.3 Wiring and Piping of the Wire Feeder” for the connection between the all-in-one power cable and wire feeder/robot.

1. Put the all-in-one power cable through the hollow section (inside wrist, upper arm) of the robot arm. Unscrew hexagon socket head bolt for mounting power cable (M6×30) of the wire feeder and remove the guide adapter. Then, insert the adapter plug of the all-in-one power cable and screw the hexagon socket head bolt for mounting power cable as it was. (Do not use the removed guide adapter.)
2. Connect the welding cable using the hexagon head bolt (M10×25) of the all-in-one power cable.
3. Mount the gas hose of the all-in-one power cable to the wire feeder.
4. Connect the shock sensor harness of the all-in-one power cable to the connector inside the optional BOX of the upper arm.

2.3.2 Mounting of Torch and Shock Sensor Manufactured by TOKIN Corporation (G-type)

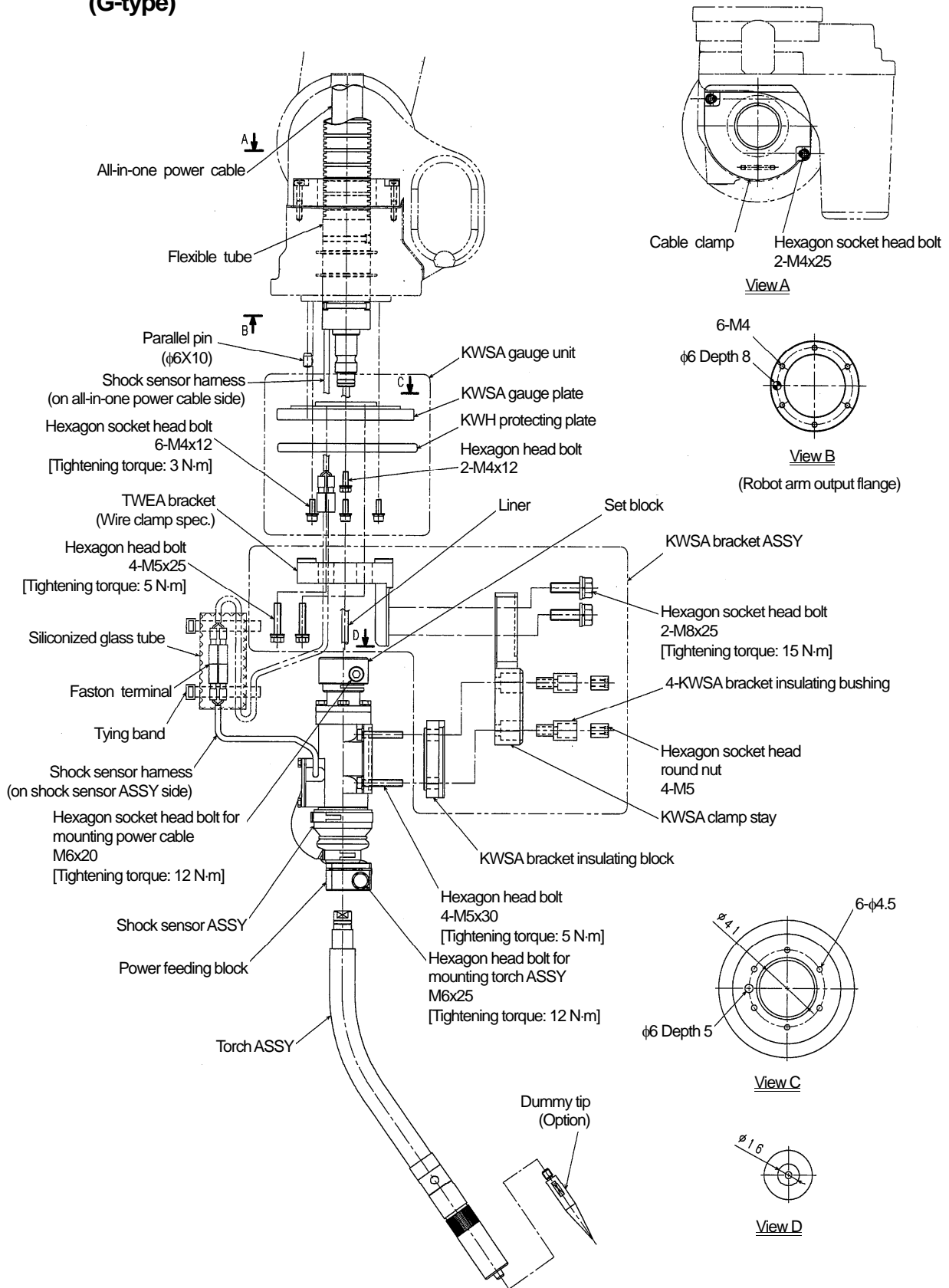


Figure 2.7 Mounting of torch and shock sensor manufactured by TOKIN (G-type)

1. For mounting of KWSA gauge plate, insert the parallel pin ($\phi 6 \times 10$) into the output flange of the robot arm and fix it by tightening six hexagon socket head bolts (M4 \times 12) to the specified torque.
2. Mount TWEA bracket on KWSA gauge plate by tightening four hexagon socket head bolts (M5 \times 25) to the specified torque.
3. Mount KWSA clamp stay on TWEA bracket by tightening two hexagon socket head bolts (M8 \times 25) to the specified torque.
4. Unscrew the hexagon socket head bolt for mounting power cable of the all-in-one power cable (M6 \times 20), fit the liner into the set block securely while inserting it into the shock sensor ASSY, rescrew the hexagon socket head bolt (M6 \times 20) for mounting power cable and tighten it to the specified torque so that the cable does not come off.
5. Insert KWSA bracket insulating bushing and hexagon socket head cylinder nut (M5) into KWSA clamp stay, and tighten four hexagon head bolts (M5 \times 30) to the specified torque while putting the KWSA bracket insulating block between the shock sensor ASSY and the clamp stay.
6. Fit the torch ASSY into the power feeding block of the shock sensor ASSY, and fix it by tightening the hexagon head bolt (M6 \times 25) to the specified torque.
7. Clamp the flexible tube of the all-in-one power cable with cable clamp, and mount it on the wrist of the robot using two hexagon socket head bolts (M4 \times 25).
8. Protect the Faston terminal of the shock sensor cable with the attached siliconized glass tube and bundle it with tying bands.
9. Mount KWH protecting plate using two hexagon head bolts (M4 \times 12).

2.3.3 Mounting of Torch Gauge Manufactured by TOKIN Corporation (G-type) (Option)

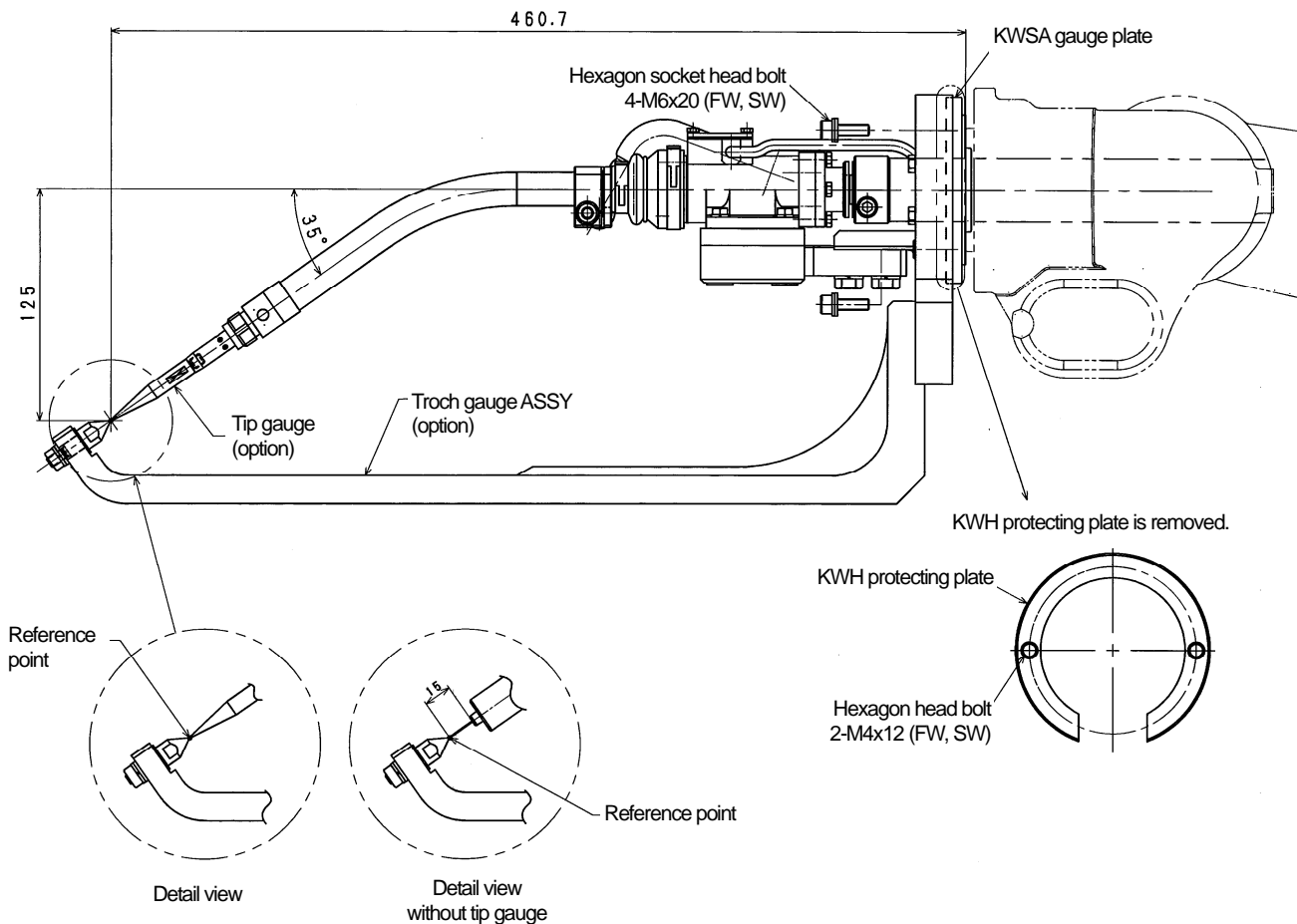


Figure 2.8 Mounting of torch gauge manufactured by TOKIN (G-type) (option)

1. Remove the nozzle and the contact tip from the torch.
2. Mount the tip gauge (option) to the torch firmly.
3. Referring to Figure 2.8, loosen two hexagon head bolts (M4×12) attached on the KWSA plate, and remove the KWH protecting plate.
4. Referring to Figure 2.8, mount the torch gauge ASSY (option) using four hexagon head bolts (M6×20) to the KWSA gauge plate.
5. Make sure that the reference point of the torch gauge coincides with the tip gauge (option) end. If not, adjust the end position of the tip gauge so that its end coincides with the reference point of the torch gauge. (Refer to “2.3.4 Method of Adjusting the Torch Manufactured by TOKIN Corporation (G-type)”).

[NOTE]

When the tip gauge (option) is not used, adjust the torch by cutting wire to a specified length, etc.

2.3.4 Method of Adjusting the Torch Manufactured by TOKIN Corporation (G-type)

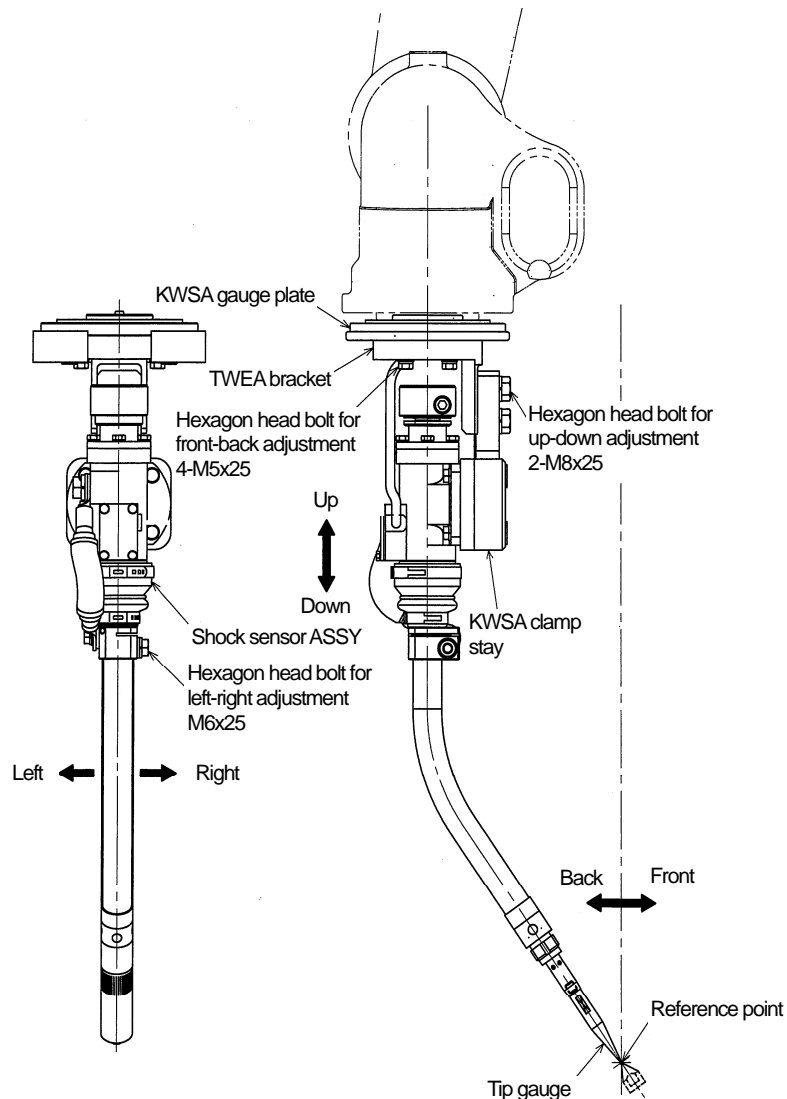


Figure 2.9 Adjustment method of torch manufactured by TOKIN (G-type)

1. If the torch end deviates in up-down direction, loosen two hexagon head bolts for up and down adjustment (M8×25) that fix the KWSA clamp stay. Correct the position, moving the torch end in the direction that the torch end deviates (upward or downward), and then fix it firmly by tightening the hexagon head bolts.
2. If the torch end deviates in front-rear direction, loosen four hexagon head bolts for front-back adjustment (M5×25) that fix the TWEA bracket. Correct the position, moving the torch end in the direction in which the torch end deviates (backward or forward), and then fix it firmly by tightening the hexagon head bolts.
3. If the torch end deviates in left-right direction, loosen the hexagon head bolt for right and left adjustment (M6×25) that fix the torch. Correct the position, rotating to the direction (left or right) in which the torch end deviates, and then fix it firmly by tightening the hexagon head bolt.

2.3.5 Method of Adjusting Tension of All-in-One Power Cable Manufactured by TOKIN Corporation (G-type)

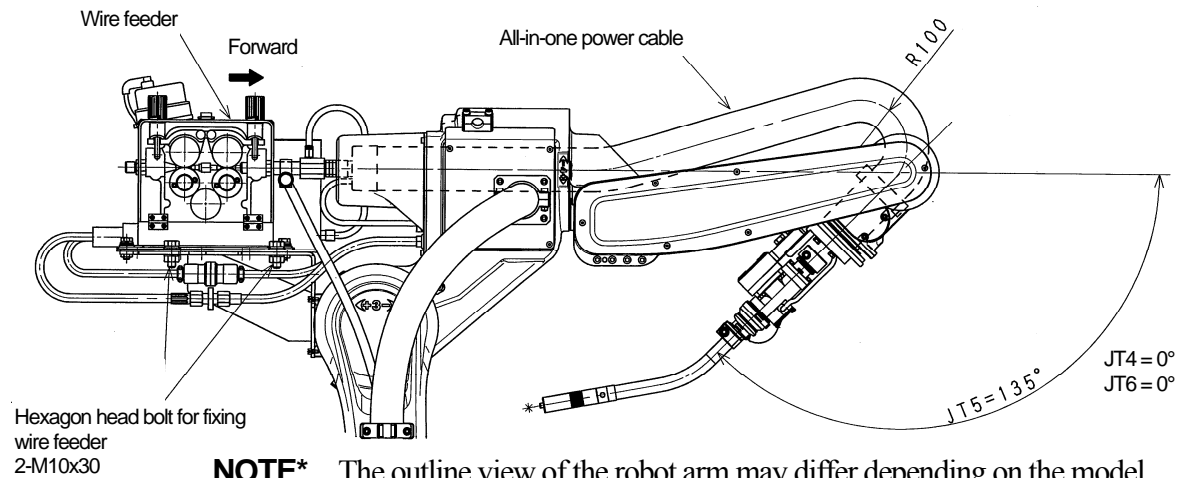


Figure 2.10 Robot posture when adjusting tension

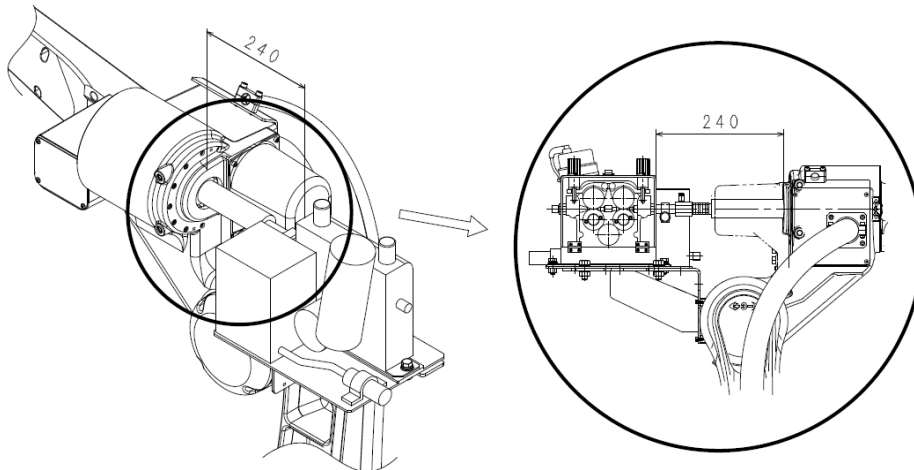


Figure 2.11 Fixing position of wire feeder (manufactured by TOKIN G-type)

1. Confirm that the shock sensor and the all-in-one power cable are mounted on the robot.
2. Move the wire feeder toward the front of the fixing bracket as much as possible.
3. Move the robot to the posture shown in the Figure 2.10.
4. Moving the wire feeder backward, pull the all-in-one power cable so that it does not have slack, arrange it in the position shown in the Figure 2.11, and fix it by tightening two hexagon head bolts (M10×30).

[NOTE]

The tension must be adjusted, because the torch cable may be disconnected or its lifetime may shorten if not. In addition, when the bending radius of the all-in-one power cable is 100 mm or less or when slack is observed, adjust the tension by moving the wire feeder forward/backward.

2.4 Liner Clamp Structure of Torch Manufactured by TOKIN Corporation

A liner clamp mechanism is equipped with the tip body of the torch manufactured by TOKIN.

During welding, weld wire may become floppy and it causes unstable wire feeding depending on clearance between the sensor and the liner in the all-in-one power cable. This problem will result in faulty weld arc start or fluctuations in the protrusion length of weld wire.

The liner clamp mechanism has the effect of reducing the irregular feed of weld wire by constraining the liner.

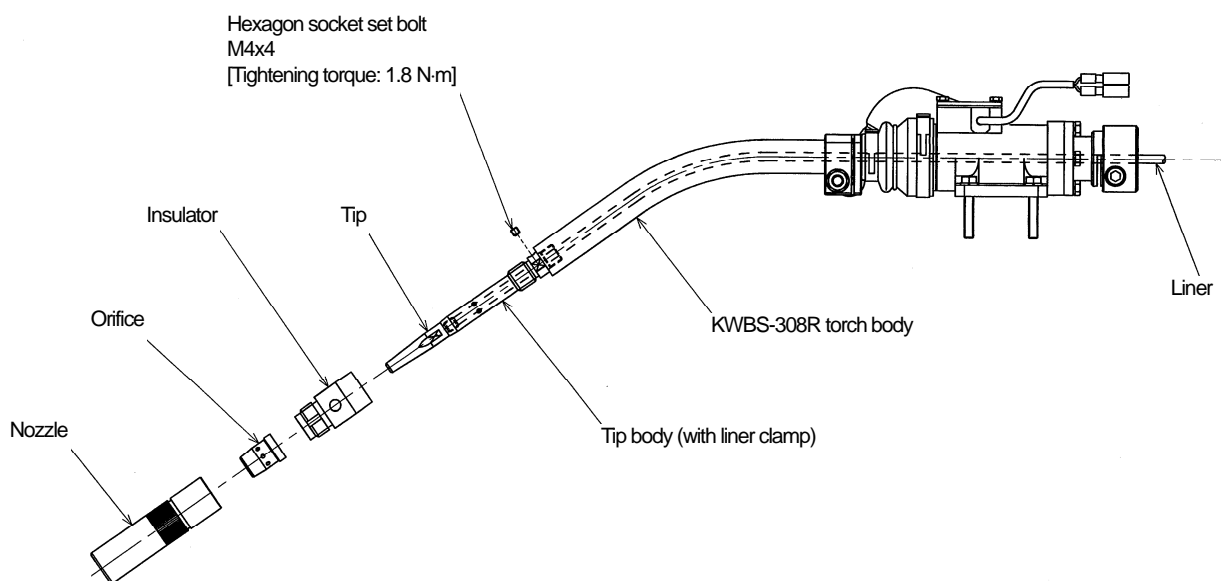


Figure 2.12 Liner clamp mechanism

1. Referring to the Figure 2.12, remove nozzle, orifice and insulator of the torch.
2. Insert the liner into the all-in-one power cable.
3. Gradually turn the hexagon socket set bolt (M4×4), and tighten it to the specified torque.
4. Mount the nozzle, orifice and insulator of the torch.

[NOTE]

1. Turning the hexagon socket set bolt excessively will damage the liner and disables weld wire feeding.
2. To remove the all-in-one power cable or the liner, unclamp the liner clamp first.

2.5 Mounting of Torch, Shock Sensor and Power Cable Manufactured by ABICOR BINZEL

2.5.1 Mounting of All-in-One Power Cable Manufactured by ABICOR BINZEL

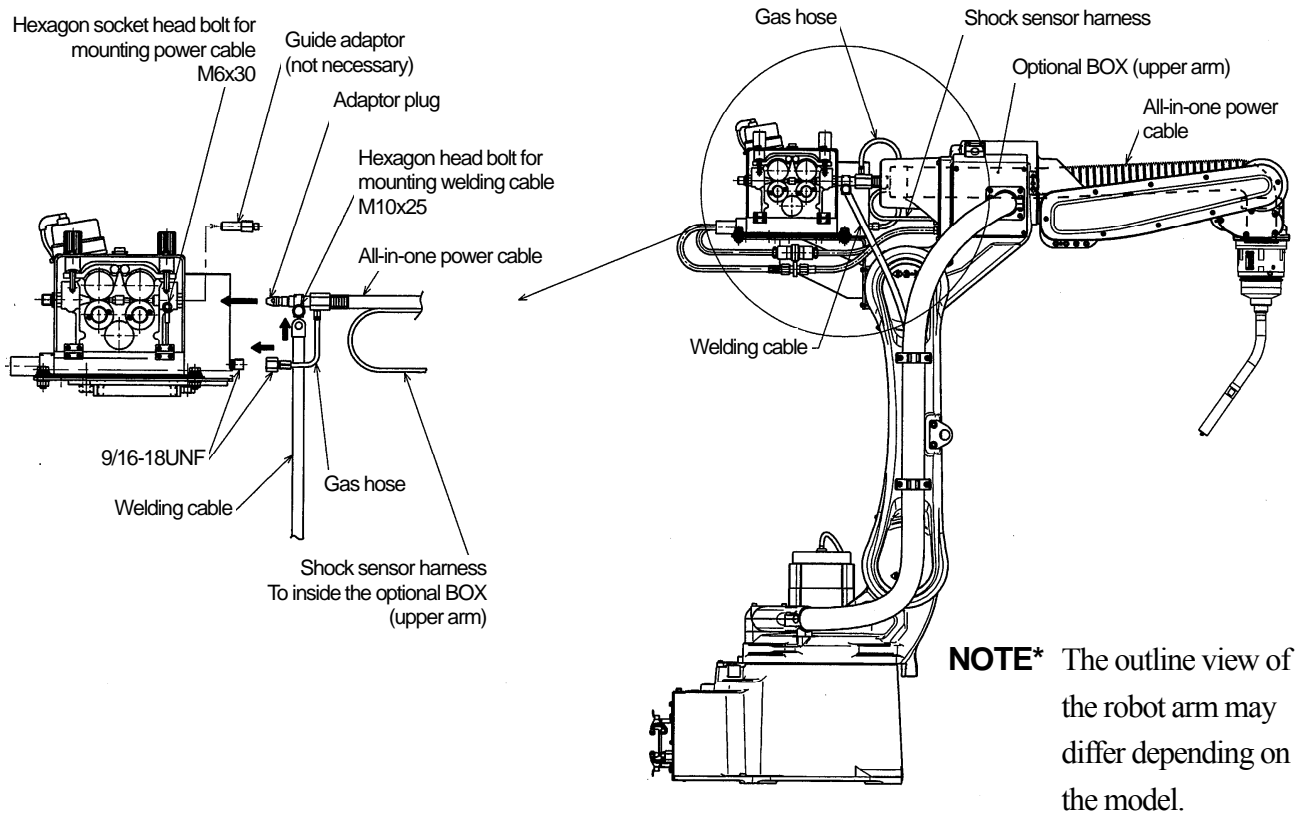


Figure 2.13 Mounting of all-in-one power cable manufactured by ABICOR BINZEL

Refer to “1.3 Wiring and Piping of the Wire Feeder” for the connection between the all-in-one power cable and wire feeder/robot.

1. Put the all-in-one power cable through the hollow section (inside upper arm) of the robot arm. Unscrew hexagon socket head bolts for mounting power cable (M6×30) of the wire feeder and remove the guide adaptor. Then, insert the adapter plug of the all-in-one power cable and screw the hexagon socket head bolts for mounting power cable as it was. (Do not use the removed guide adapter.)
2. Connect the welding cable using the hexagon head bolt (M10×25) of the all-in-one power cable.
3. Mount the gas hose of the all-in-one power cable on the wire feeder.
4. Connect the shock sensor harness of the all-in-one power cable to the connector inside the optional BOX of the upper arm.

2.5.2 Mounting of Torch and Shock Sensor Manufactured by ABICOR BINZEL

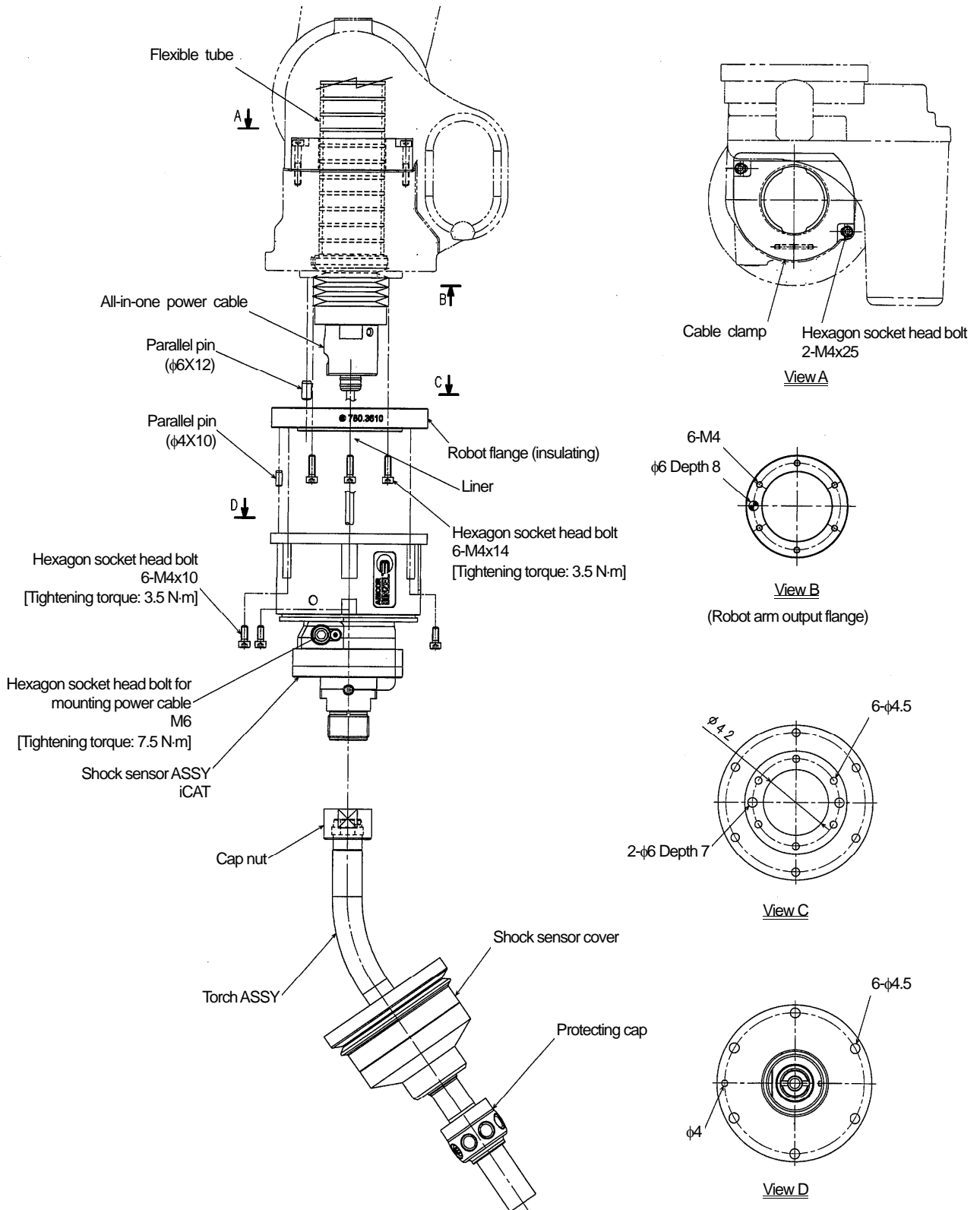


Figure 2.14 Mounting of torch and shock sensor manufactured by ABICOR BINZEL

1. Insert the parallel pin ($\phi 6 \times 12$) into the robot flange (insulating), and attach six hexagon socket head bolts (M4 \times 14) on the output flange of the arm to the specified torque.
2. Insert the parallel pin ($\phi 4 \times 10$) into the shock sensor ASSY (iCAT), and mount it to the robot flange (insulating) by tightening six hexagon socket head bolts (M4 \times 10) to the specified torque.
3. Remove the protecting cap, and remove the shock sensor cover by rotating it. Insert the cap nut, the shock sensor cover and the protecting cap in this order from the front of the torch ASSY, put the torch ASSY into the shock sensor ASSY (iCAT), and mount it by screwing the cap nut.
4. Mount the shock sensor cover on the shock sensor ASSY while rotating it, and insert the protecting cap into the cap nut.
5. Put the all-in-one power cable into the hollow section of the robot arm (wrist), and fit the all-in-one power cable liner into the shock sensor ASSY (iCAT) securely. Then, tighten the special hexagon socket head bolt (M6) for mounting power cable to the specified torque to prevent it from coming off.
6. Clamp the flexible tube of the all-in-one power cable with cable clamp, and mount it on the wrist of the robot using two hexagon socket head bolts (M4 \times 25).

2.5.3 Mounting and Adjustment of Torch Gauge Manufactured by ABICOR BINZEL (Option)

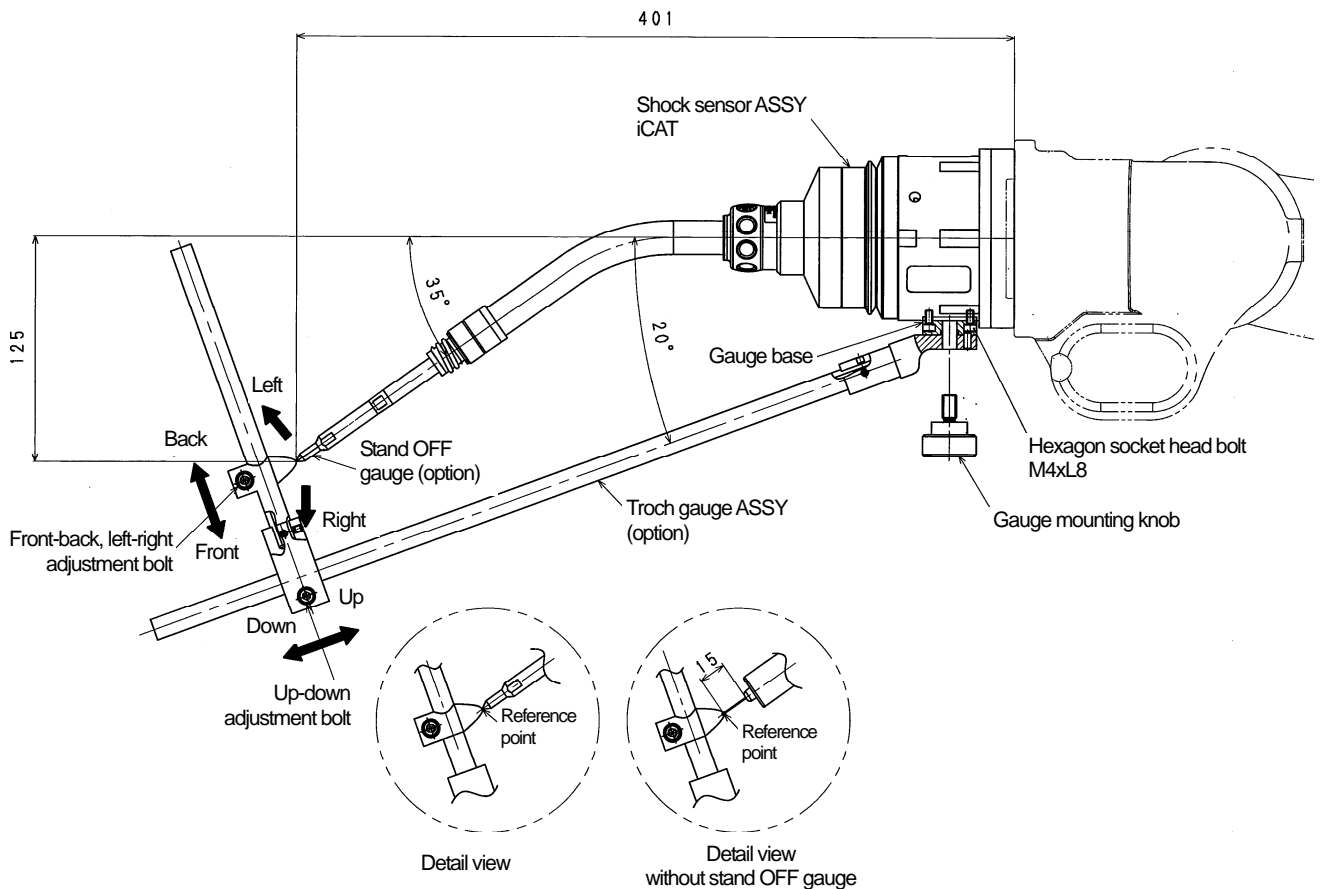


Figure 2.15 Mounting and adjustment of torch gauge manufactured by ABICOR BINZEL (option)

1. Remove the nozzle and the contact tip from the torch.
2. Mount the stand OFF gauge (option) to the torch firmly.
3. Mount the gauge base on the shock sensor ASSY (iCAT) using four hexagon socket head bolts (M4×8) attached with the torch gauge ASSY (option).
4. Mount the torch gauge ASSY (option) on the gauge base using the gauge mounting knob.
5. Make sure that the reference point of the torch gauge ASSY coincides with the stand OFF gauge (option) end. If not, loosen up-down adjustment bolt and front-back, left-right adjustment bolt and adjust the end position of the torch gauge ASSY so that its end coincides with the reference point of the stand OFF gauge.

[NOTE]

When the stand OFF gauge is not used, adjust the torch by cutting wire to a specified length, etc.

2.5.4 Method of Adjusting Tension of All-in-One Power Cable Manufactured by ABICOR BINZEL

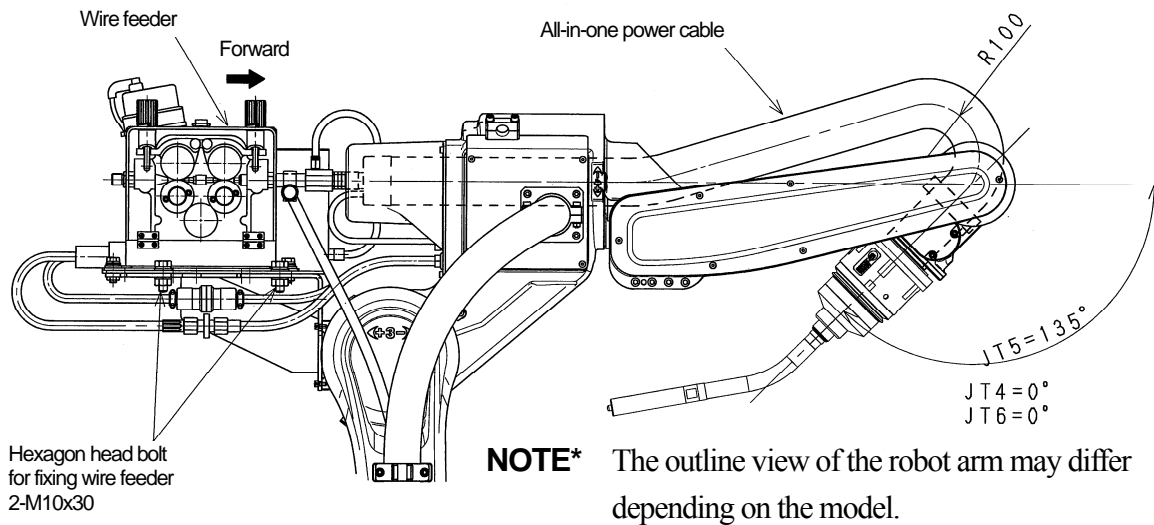


Figure 2.16 Robot posture when adjusting tension

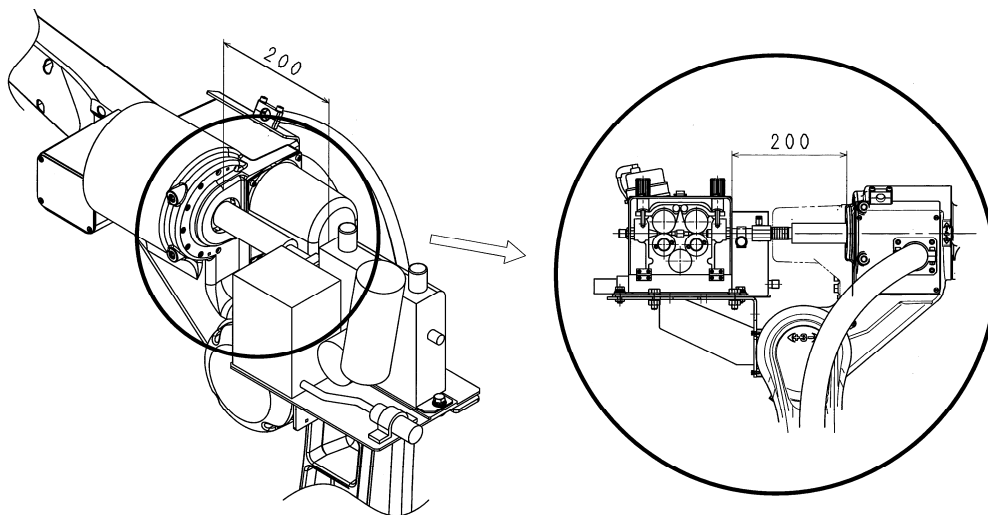


Figure 2.17 Fixing position of wire feeder (manufactured by ABCOL BINZEL)

1. Confirm that the shock sensor and the all-in-one power cable are mounted on the robot.
2. Move the wire feeder toward the front of the fixing bracket as much as possible.
3. Move the robot to the posture shown in the Figure 2.16.
4. Move the wire feeder backward, pull the all-in-one power cable so that it does not have slack, arrange it in the position shown in the Figure 2.17, and fix it using two hexagon head bolts (M10×30).

[NOTE]

The tension must be adjusted, because the torch cable may be disconnected or its lifetime may shorten if not. In addition, when the bending radius of the all-in-one power cable is 100 mm or less or when slack is observed, adjust the tension by moving the wire feeder forward/backward.

3 Mounting of Wire Reel Stand for JT1 (Option)

Unscrew two hanging bolts as shown in Figure 3.1 and mount the wire reel stand for JT1 using two hexagon head bolts (M8×40).

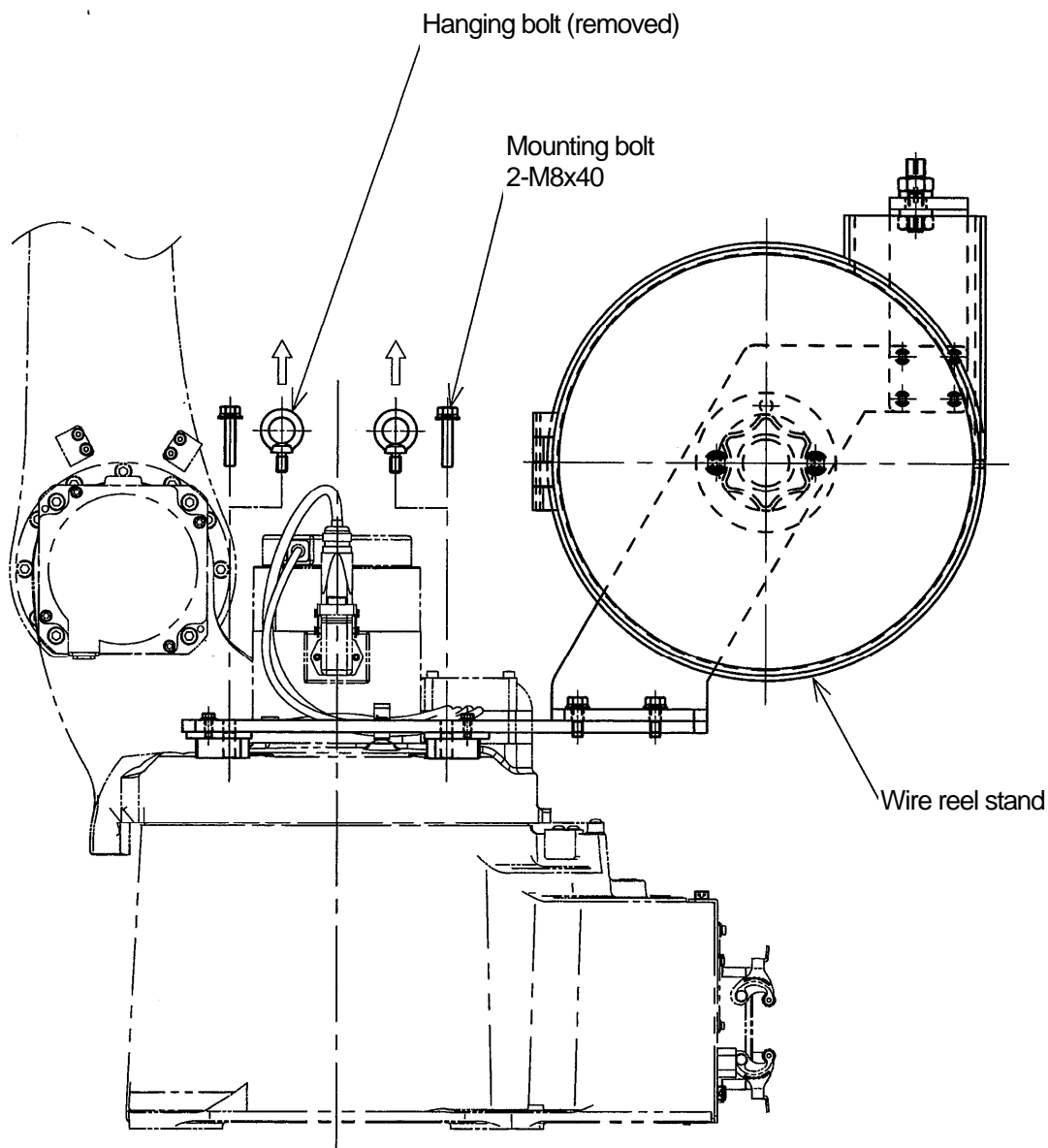


Figure 3.1 Mounting of wire reel stand for JT1

4 Grounding Method



WARNING

1. Never share the ground among the robot controller, robot arm, welder, other equipment and etc.
2. For the controller and robot arm, use a dedicated ground (100 Ω or less) as the ground line shown below.
3. If grounding and insulation of the controller and the robot arm are insufficient, malfunction caused by noise from ground lines, breakage or electrical shock may occur. Accordingly, strictly observe below. In addition, make sure that the controller and the robot are connected with dedicated ground lines and check that they are isolated from other equipment and devices via a circuit tester, etc.

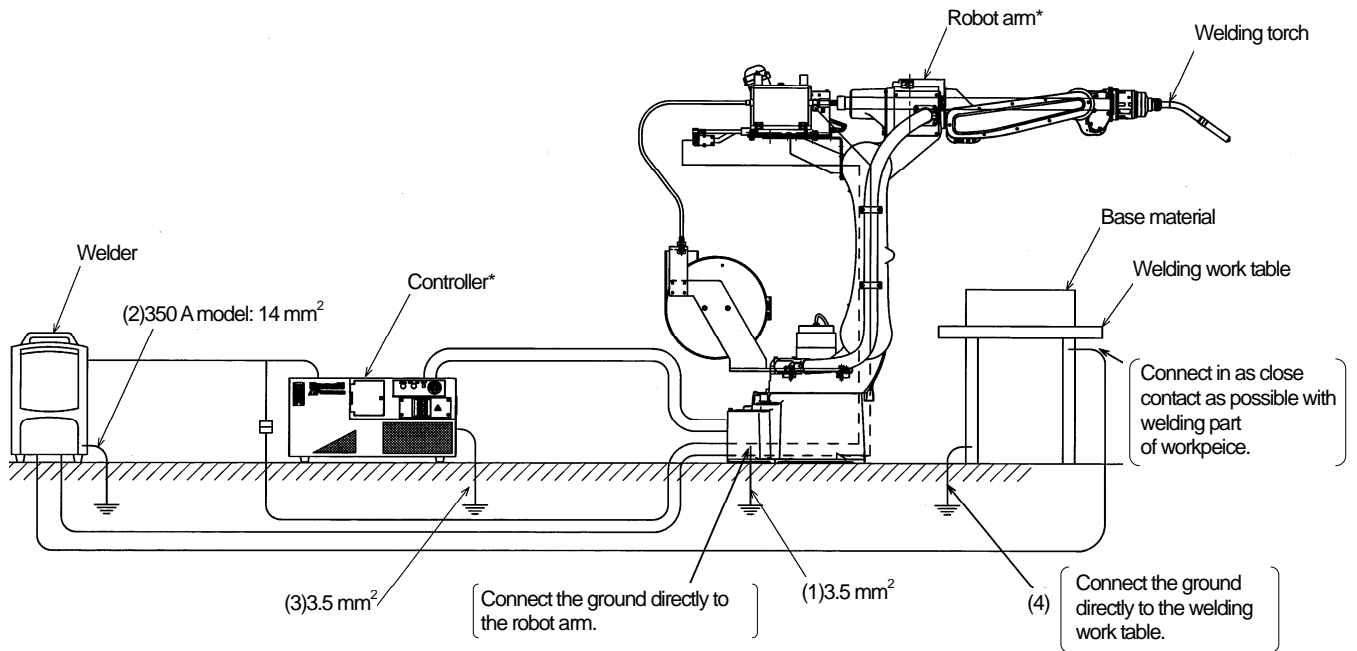
Robot controller : 3.5 mm² (AWG #12)

Robot arm : 3.5 mm² (AWG #12)

For the multi axes robot, use a ground line whose size is larger than that of the power supply line.

Isolate the wire feeder and welding torch from the robot arm using Bakelite etc. (Refer to “Safety.”)

Grounding is extremely important to prevent noise and electrical shock, etc. Connect the grounding wire by the following method.



For each ground ((1),(2),(3),(4)), connect them independently and separately with D class grounding (100 Ω or less).

NOTE* The outline view of the robot arm and controller may differ depending on the model.

Figure 4.1 Grounding method

5 Connection with Welding Equipment



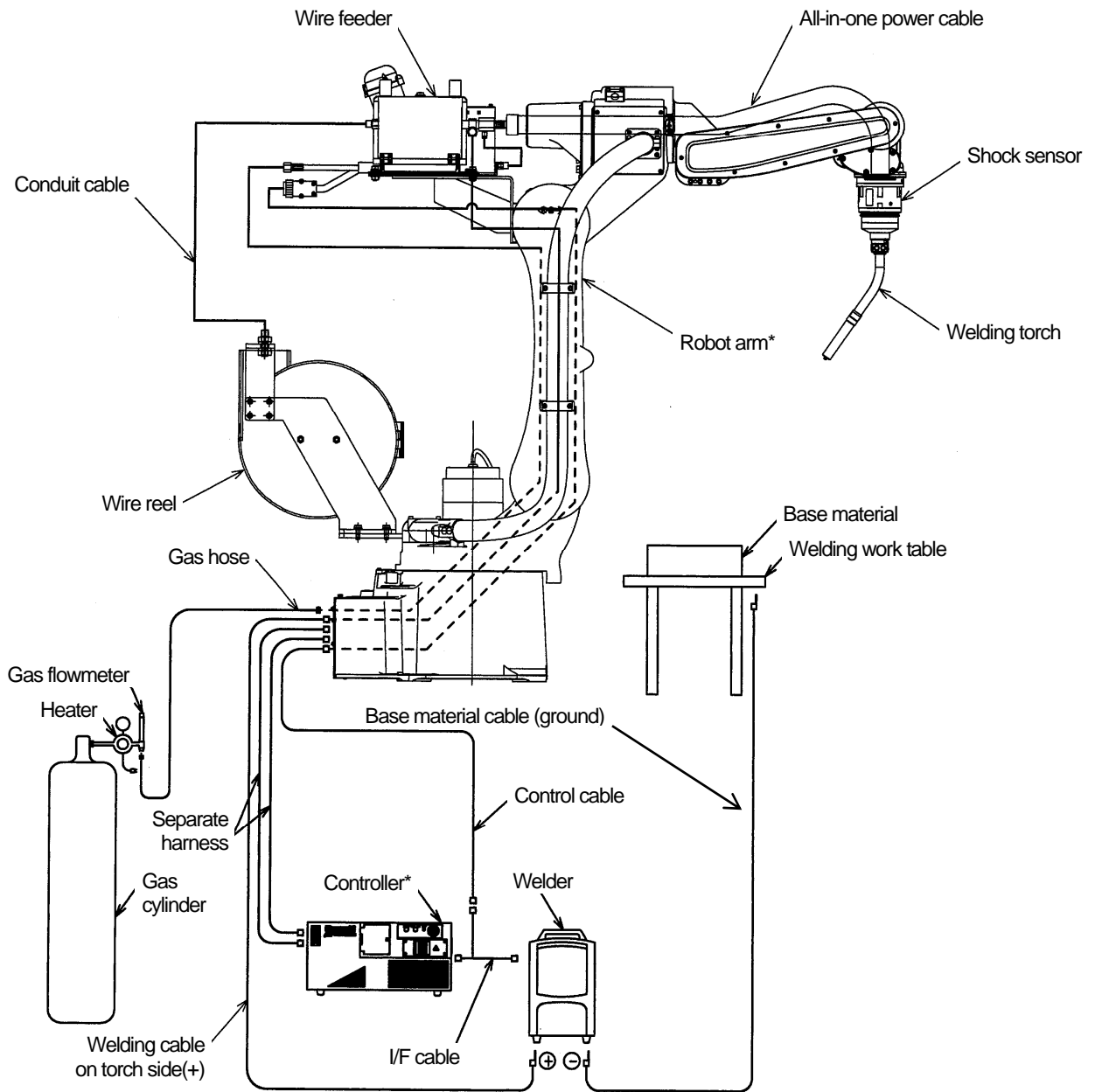
WARNING

- 1. Before connecting the robot arm with welding equipment, move the robot arm to a place where the work can be done easily. Then turn OFF the “motor power” and the “controller power.”**
- 2. Before connecting the robot arm with welding equipment, turn OFF the welder power supply without fail.**

Referring to Figure 5.1 on the next page, connect an arc welder, etc. with welding equipment. For details of handling and connection of power cables, etc. to the welder, refer to its instruction manual.

1. Connect the welder interface board in the controller (Refer to “Appendix 2 Welder Interface Board.”) to the welder via the I/F cable.
2. For CO₂ welding, a heater and gas flowmeter are normally connected to the gas cylinder. Non-heater type gas cylinder is also available. If a factory piping is used instead of cylinders, connect a flowmeter designed for factory piping.
3. Connect welding cable (ground) with the welding work table.
4. For the wire feeder, a reel type machine is shown in the figure. However, when a pack is used, connect the wire feeder with the pail pack.
5. Wire/pipe control cable, welding cable and gas hose to the robot’s rear arm, referring to Figure 5.2.
6. For the specifications of control cable and weld cable, see “Appendix 4 Machine Control Cable and Welding Cable Specifications.”

When DAIHEN welding power source (DM-350) is used



NOTE* The outline view of the robot arm and controller may differ depending on the model.

Figure 5.1 Connection with welder

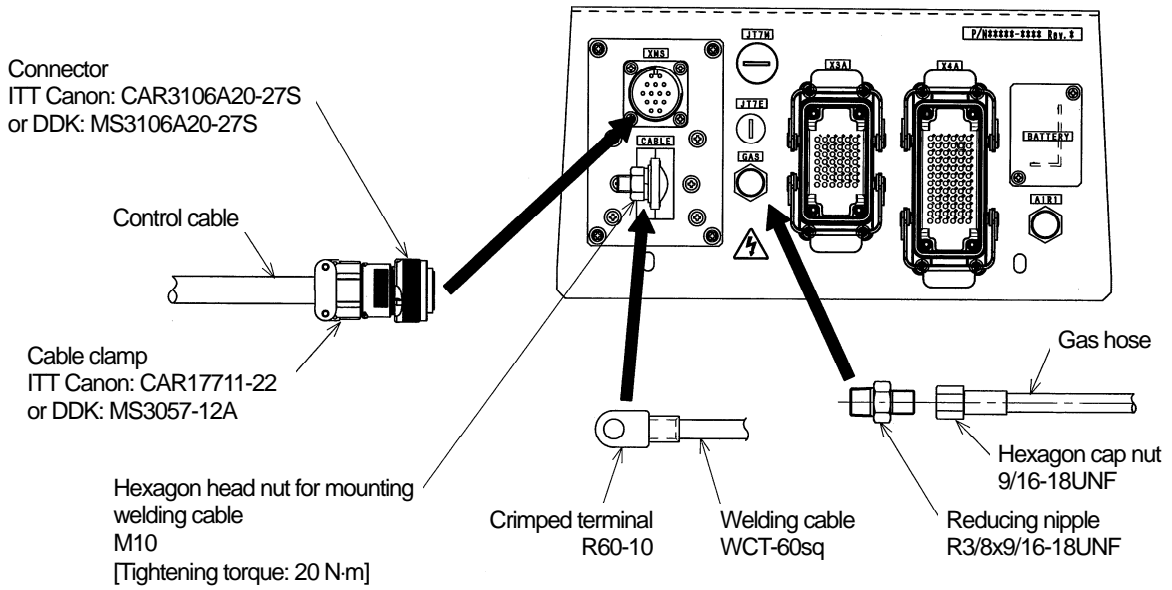


Figure 5.2 Wiring and piping to rear arm

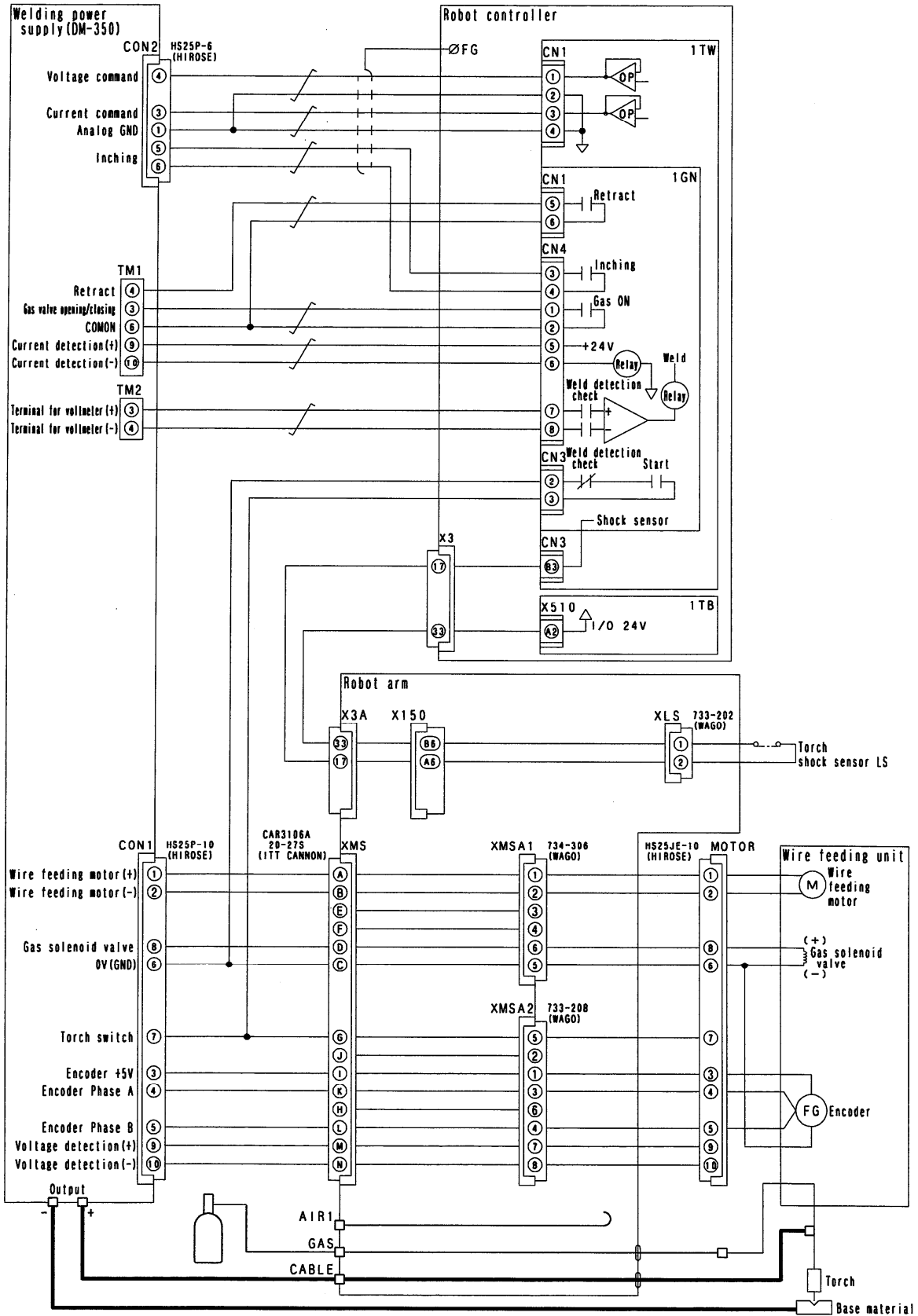
⚠ WARNING

A cover is not provided for the terminal to which the weld cable is connected. Use an optional cover if there is a possibility of electric shock.

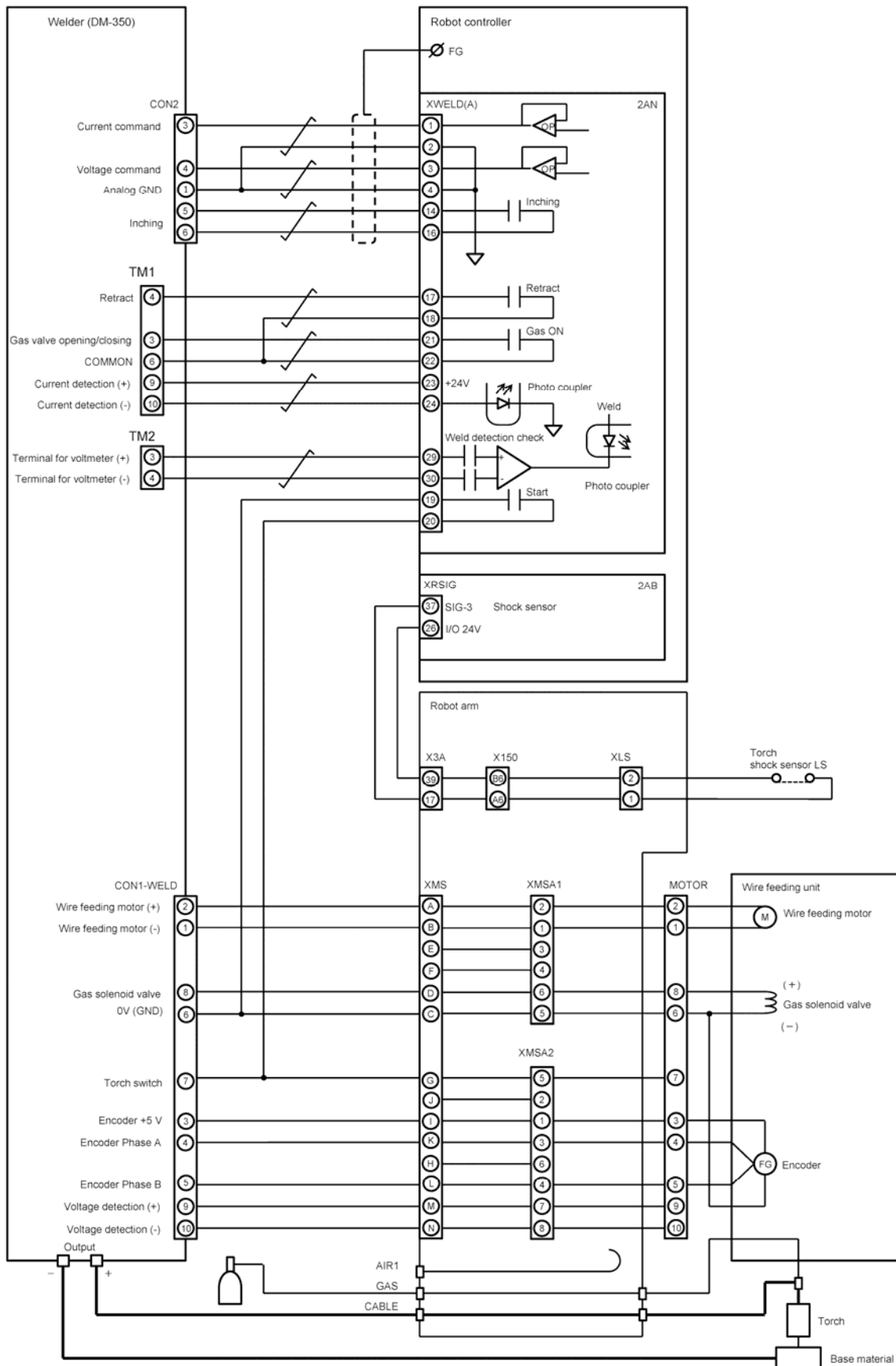
Part No. of optional cover: 60339-0184

Appendix 1 Connection Diagram with Welder (DM-350)

1. E01 Controller



2. F60 Controller



Appendix 2 Welder Interface Board

1. E01 Controller

1-1. Connector specifications

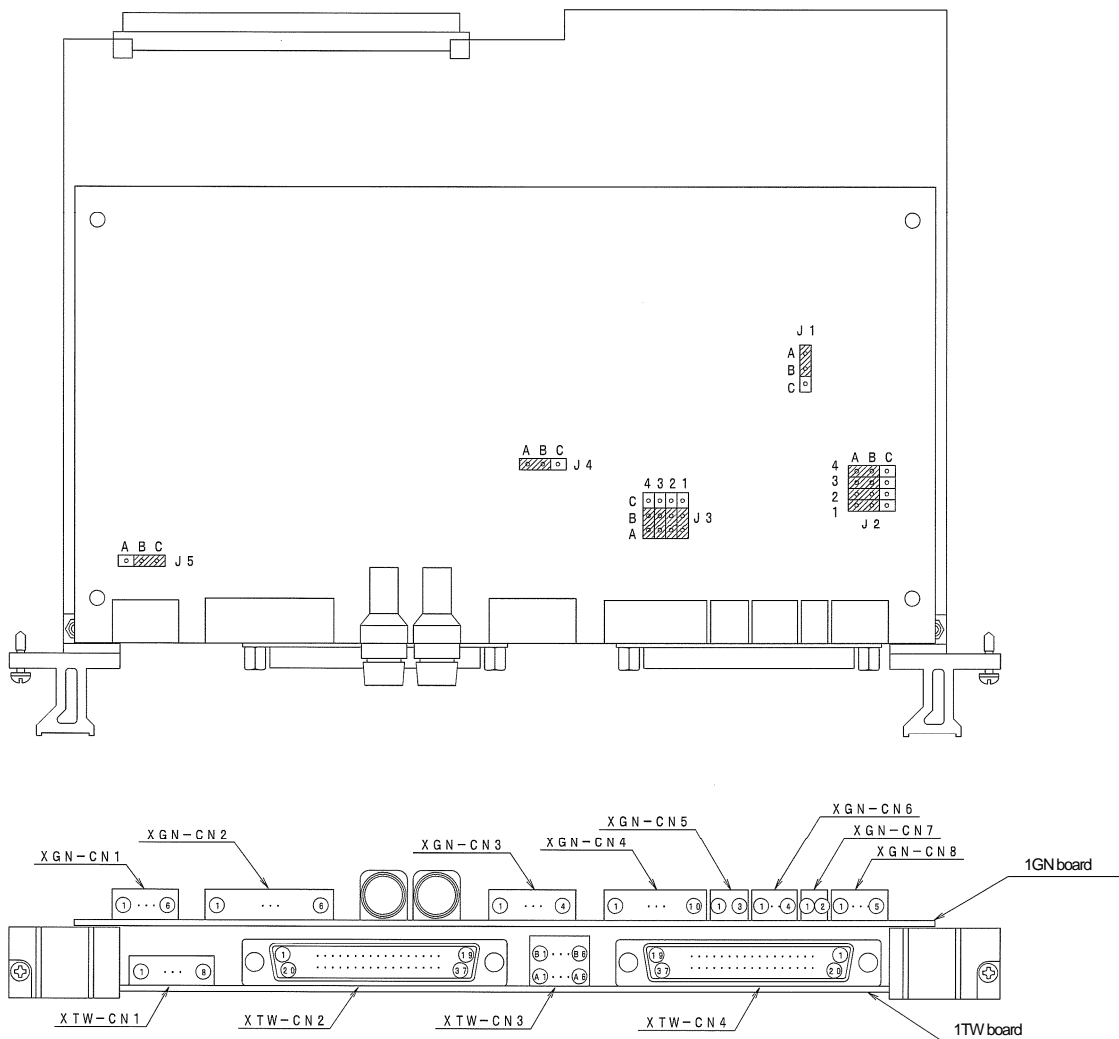
| Board | Connector No. | Pin No. | Signal Name | Function | Connector |
|-------|---------------|-------------|--|---|------------------------|
| ITW | CN1 | 1 | V_COMMAND | Voltage Command (0 to 15 V) | 733-108/KM (WAGO) |
| | | 2 | A15G | GND for Voltage Command D | |
| | | 3 | I_COMMAND | Current Command (0 to 15 V) | |
| | | 4 | A15G | GND for Current Command | |
| | | 5 | P_RATIO | Polarity Ratio (0 to 15 V) | |
| | | 6 | A15G | GND for Polarity Ratio | |
| IGN | CN1 | 1 | WELD_ON_A | Welding in progress Contact Close (Output) | 733-106 (WAGO) |
| | | 2 | WELD_ON_B | | |
| | | 3 | INCHING_C | Inching in progress Contact Close (Output) | |
| | | 4 | INCHING_D | | |
| | | 5 | WIRE_RETRACT_A | Wire Retract in progress Contact Close (Output) | |
| | | 6 | WIRE_RETRACT_B | | |
| | CN2 | 1 | I/O 24V | 24 V Power Supply for I/O | 231-306/037-000 (WAGO) |
| | | 2 | WIRE_HOLD | | |
| | | 3 | GAS_SOL | Gas Valve Power Supply + (Valve side) | |
| | | 4 | COM | Gas Valve Power Supply - (Valve side) | |
| | | 5 | MOTOR_A | Wire Feeder Motor Power Supply + (Motor side) | |
| | | 6 | MOTOR_COM | Wire Feeder Motor Power Supply - (Motor side) | |
| | CN3 | 1 | MOTOR | Wire Feeder Motor Power Supply (Welder side) | 231-304/037-000 (WAGO) |
| | | 2 | COM | Common for Motor and Start Valve | |
| | | 3 | WELD_ON | Welding in progress Contact Close (Output) | |
| | | 4 | GAS_SOL | Gas Valve Power Supply (Welder side) | |
| | CN4 | 1 | GAS_ON_A | Gas Supply in progress Contact Close (Output) | 733-110 (WAGO) |
| | | 2 | GAS_ON_B | | |
| | | 3 | INCHING_A | Inching in progress Contact Close (Output) | |
| | | 4 | INCHING_B | | |
| | | 5 | B24V | 24 V Power Supply for Welder Interface | |
| | | 6 | ARC_DETECT | Arc Generation in prog. Contact Close (Input) | |
| | | 7 | WIRE_STICK+ | Wire Stuck Detection 1.5 V Supply | |
| | | 8 | WIRE_STICK- | GND for 1.5 V Wire Stuck Detection | |
| 9 | | B24V | | | |
| 10 | | TORCH_SHORT | | | |
| CN6 | 1 | TOUCH_SENCE | Touch Sensing in progress Contact Close (Output) | 733-104 and 733-100 (WAGO) | |
| | 2 | I/O 24V | 24 V Power Supply for I/O | | |
| | 3 | I/O 24G | 24 V GND for I/O | | |
| | 4 | WIRE_TOUCH | Wire Touch in progress Contact Close (Output) | | |
| CN7 | 1 | B24V | Shock Sensor + | 733-102(WAGO) | |
| | 2 | TORCH_LS | Shock Sensor - | | |
| CN8 | 1 | I/O 24V | 24 V Power Supply for I/O | 733-105 (WAGO) Reserved | |
| | 2 | I/O 24G | 24 V GND for I/O | | |
| | 3 | WELDER_ERR1 | Welder error 1 | | |
| | 4 | WELDER_ERR2 | Welder error 2 | | |
| | 5 | WELDER_ERR3 | Welder error 3 | | |

[NOTE]

A15G, I/O24G and B24G are insulated respectively.

1-2. Appearance

- Part number: 50999-2141, 50999-0513

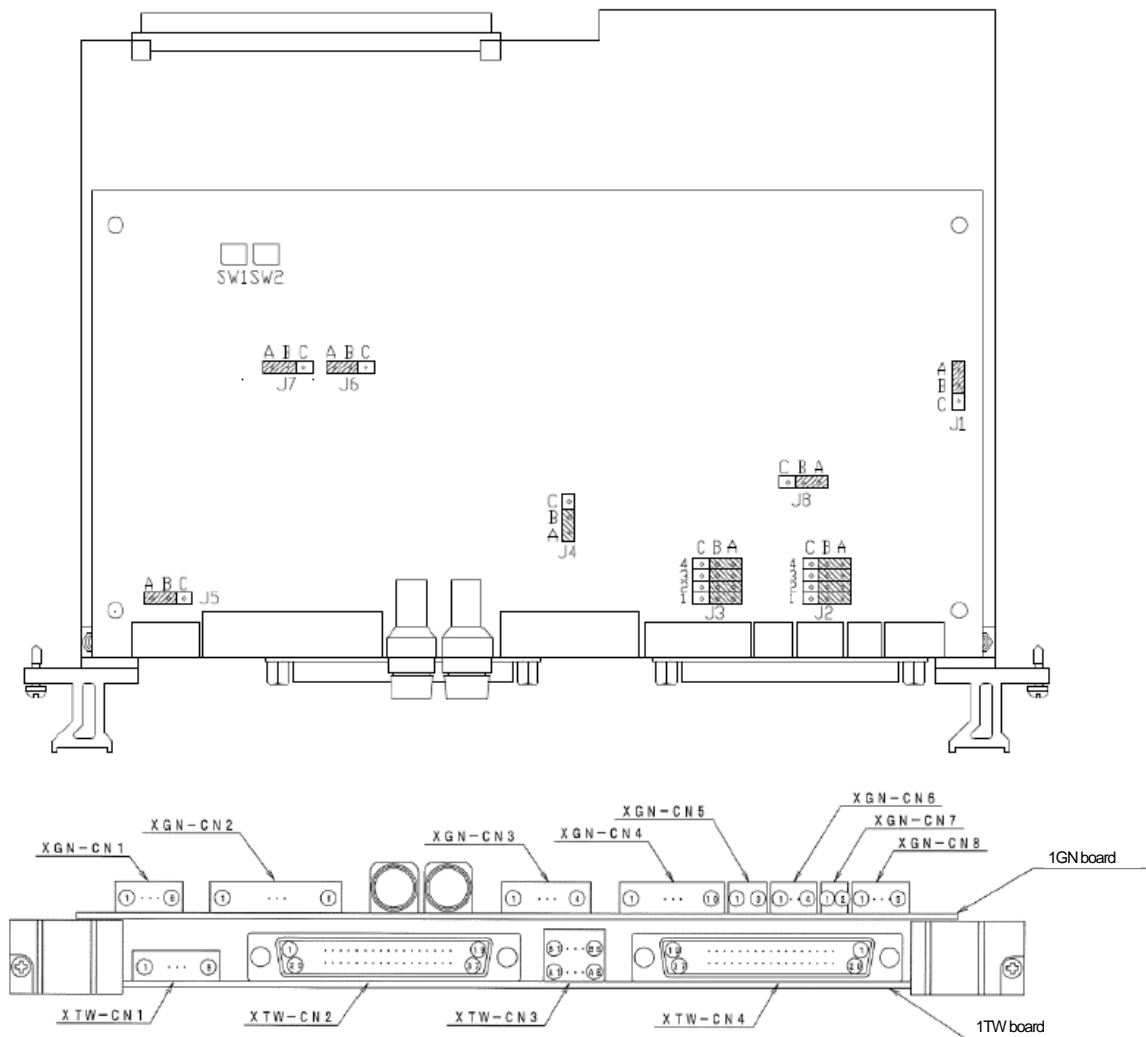


Appearance of 1GN + 1TW Boards

Jumper setting

| No. | Content | Setting |
|-----|---|---|
| J1 | Common switching for NO_GAS, NO_WATER and NO_WIRE signals | A-B jumper: I/O24 V for input common, SOURCE/PNP specifications (standard) B-C jumper: I/O24 G for input common, SINK/NPN specifications |
| J2 | Exclusive for system | A-B jumper (cannot change) |
| J3 | Exclusive for system | A-B jumper (cannot change) |
| J4 | Exclusive for system | A-B jumper (cannot change) |
| J5 | Retract interlock switching (effective only for CN1) | A-B jumper: The inching command and the retract command are turned ON at the same time for retracting. B-C jumper: Only the retract command is turned ON at for retracting (standard). |

- Part number: 50999-0676



Appearance of 1GN + 1TW Boards

Jumper setting

| No. | Content | Setting |
|-----|--|---|
| JP1 | Common switching for NO_GAS, NO_WATER, NO_WIRE signals | A-B jumper: I/O24 V for input common, SOURCE/PNP specifications (standard) B-C jumper: I/O24 G for input common, SINK/NPN specifications |
| JP2 | Exclusive for system | A-B jumper (cannot change) |
| JP3 | Exclusive for system | A-B jumper (cannot change) |
| JP4 | Exclusive for system | A-B jumper (cannot change) |
| JP5 | Retract relay switching (effective only for CN1) | A-B jumper: The inching command and the retract command are turned ON at the same time for retracting B-C jumper: Only the retract command is turned ON at for retracting (standard) |
| JP6 | Retract delay switching | A-B jumper: Delay (standard) B-C jumper: No delay |
| JP7 | Exclusive for system | A-B jumper (cannot change) |
| JP8 | Switching between E controller and D controller | A-B jumper: E controller B-C jumper: D controller |

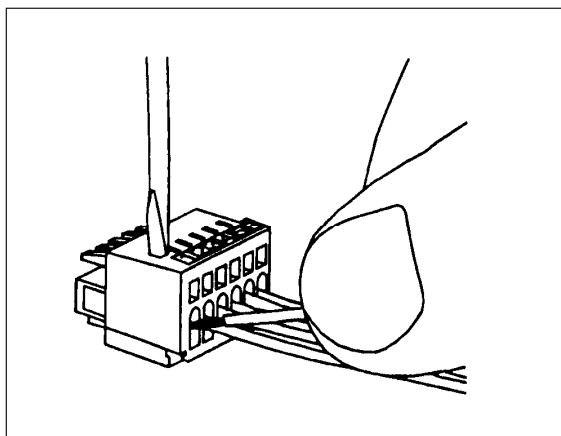
Switch setting

| No. | Content | Setting |
|-----|----------------------|-------------------------|
| SW1 | Exclusive for system | All OFF (cannot change) |
| SW2 | Exclusive for system | All OFF (cannot change) |

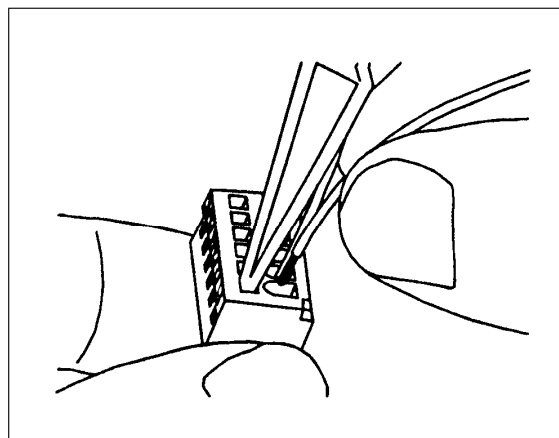
1-3. Connection of Gauge Clamp

| Board | Connector No. | Cross section | | Stripped length |
|-------|--------------------|---------------|-----------------------------|-----------------|
| 1TW | CN1 | AWG28-20 | 0.08 to 0.5 mm ² | 5 to 6 mm |
| 1GN | CN1, 4, 5, 6, 7, 8 | AWG28-20 | 0.08 to 0.5 mm ² | 5 to 6 mm |
| | CN2, 3 | AWG28-12 | 0.08 to 2.5 mm ² | 8 to 9 mm |

Connect wire leads as shown in figures below.



Connecting conductive wire from the side
 - via screwdriver (2.5×0.4) mm



Connecting conductive wire from the top
 - via tool WAGO 233-332 for WAGO Series 733
 - via screwdriver (2.5×0.4) mm for WAGO Series 231

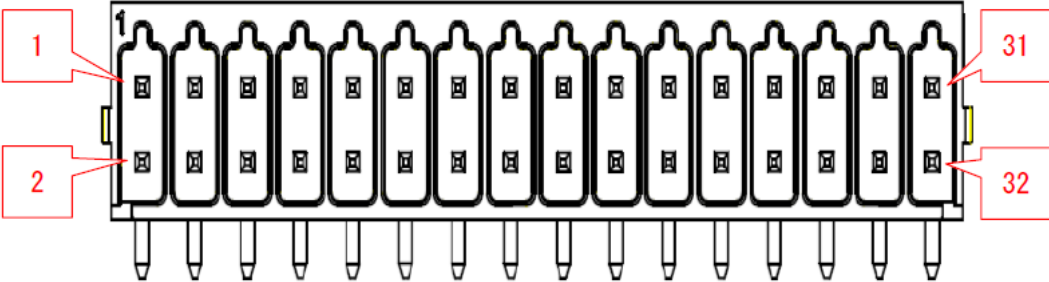
2. F60 Controller

2-1. Connector specifications

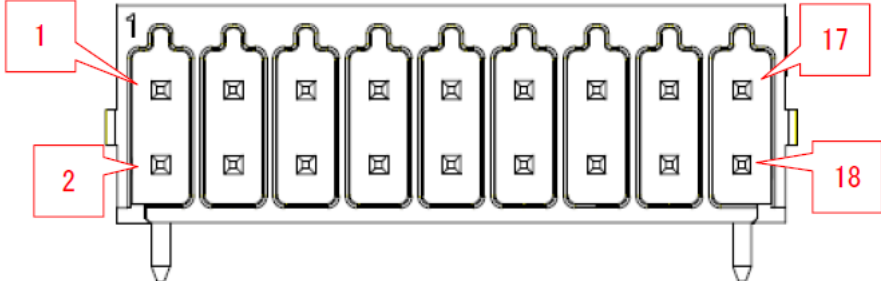
Set each output load capacity to 3 μF or less.

| Board | Connector No. | Pin No. | Signal Name | Function | |
|-----------|--------------------------------|-------------------------------|--|--|--|
| 2AN board | XWELD(A) DMC.0.5/16-G1-2.54 | 1 | A1_COMMAND | Analog voltage output for setting parameters (normally, for welding current) (Setting range: -15 V to +15 V) | |
| | | 2 | A1_COM_GND | GND for A1_COMMAND | |
| | | 3 | A2_COMMAND | Analog voltage output for setting parameters (normally, for welding current) (Setting range: -15 V to +15 V) | |
| | | 4 | A2_COM_GND | GND for A2_COMMAND | |
| | | 5 | A3_COMMAND | Analog voltage output for setting parameters (normally, for welding current) (Setting range: -15 V to +15 V) | |
| | | 6 | A3_COM_GND | GND for A3_COMMAND | |
| | | 7 | A4_COMMAND | Analog voltage output for setting parameters (normally, for welding current) (Setting range: -15 V to +15 V) | |
| | | 8 | A4_COM_GND | A4_COMMAND | |
| | | 9 | ROBOT_READY_A | Contact closed when welding is ready (Output) | |
| | | 10 | ROBOT_READY_B | | |
| | | 11 | WELDER_ERR_24V | +24 V power source for welder error detection signal | |
| | | 12 | WELDER_ERR_GND | GND for welder error detection signal | |
| | | 13 | WELDER_ERR | Welder error detection signal (Input) | |
| | | 14 | FEED_ON_A | Contact closed while the wire feeder motor is running (Output) | |
| | | 15 | WIRE_FWD_A | Contact closed while wire is being fed in the forward direction (Output) | |
| | | 16 | WIRE_FWD_B | FEED_ON_A common | |
| | | 17 | WIRE_REV_A | Contact closed while wire is being fed in the reverse direction (Output) | |
| | | 18 | WIRE_REV_B | | |
| | | 19 | WELD_ON_A | Contact closed when welding starts (Output) | |
| | | 20 | WELD_ON_B | | |
| | | 21 | GAS_ON_A | Contact closed when gas is supplied (Output) | |
| | | 22 | GAS_ON_B | | |
| | | 23 | ARC_DETECT_24V | +24 V power source for arc generation detection | |
| | | 24 | ARC_DETECT | +24 V input when arc generation is detected | |
| | | 25 | ARC_DETECT_EPS_A | +24 V input when arc generation is detected (external power supply type) | |
| | | 26 | ARC_DETECT_EPS_B | | |
| | | 27 | TORCH_SHORT_24V | +24 V power source for torch short circuit detection | |
| | | 28 | TORCH_SHORT | +24 V input when torch short circuit is detected | |
| | | 29 | WIRE_STICK_+ | +15 V output when deposition is detected | |
| | | 30 | WIRE_STICK_- | GND for WIRE_STICK_+ | |
| | 31 | WIRE_HOLD | +24 V output when the wire hold signal is turned ON (for driving the solenoid valve) | | |
| | 32 | WIRE_HOLD_GND | GND for WIRE_HOLD | | |
| | | XWELD(B) DMC.0.5/9-G1-2.54 | 1 | WELD_ON_C | Contact closed when welding starts (Output) |
| | | | 2 | WELD_ON_D | |
| | | | 3 | WIRE_FWD_C | Contact closed while wire is being fed in the forward direction (Output) |
| | | | 4 | WIRE_FWD_D | |
| | 5 | | WIRE_REV_C | Contact closed while wire is being fed in the reverse direction (Output) | |
| | 6 | | WIRE_REV_D | | |
| | 7 | | TOUCH_SENCE | +24 V output while touch sensing is being performed | |
| | 8 | | TOUCH_SENCE_24V | +24 V power source for TOUCH_SENCE | |
| | 9 | | TOUCH_SENCE_GND | GND for TOUCH_SENCE | |
| | 10 | | WIRE_TOUCH | +24 V input when wire touching is detected | |
| | 11 | | +16V | +16 V power source for current sensor | |
| | 12 | | -16V | -16 V power source for current sensor | |
| | 13 | | N.C. | | |
| | 14 | | N.C. | | |
| | 15 | | N.C. | | |
| | 16 | | N.C. | | |
| | 17 | | TORCH_LS_24V | +24 V power source for torch interference detection | |
| | 18 | | TORCH_LS | +24 V input when torch interference is detected | |

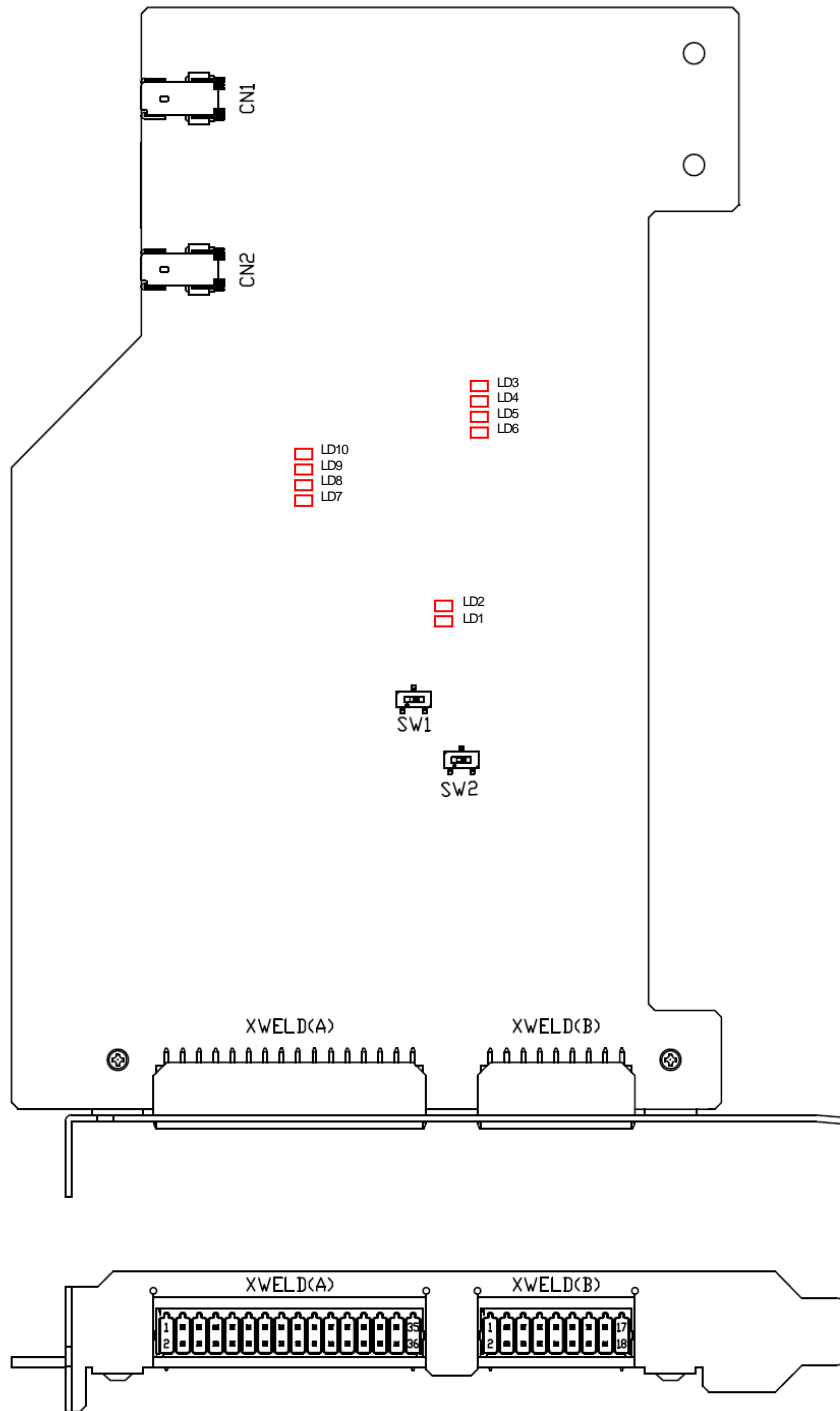
XWELD(A)



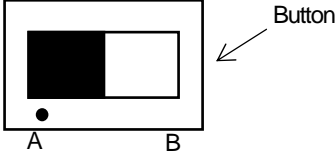
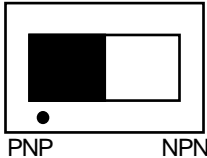
XWELD(B)



2-2. Appearance



| Connector | Content | Remarks (location) |
|-----------|--|-------------------------------|
| CN1 | Communication connector (to the servo board) | Side surface of circuit board |
| CN2 | Communication connector (to the extension I/O board) | Side surface of circuit board |
| XWELD (A) | I/O port 1 | Rear panel |
| XWELD (B) | I/O port 2 | Rear panel |

| Switch Name | Function |
|-------------|---|
| SW1 | <p>For the system</p>  |
| SW2 | <p>WELDER_ERR signal common switching</p> <ul style="list-style-type: none"> “PNP”: 24 V input common, SOURCE/PNP type (standard) “NPN”: GND input common, SINK/NPN type  |

| LED | Content | Color | Remarks |
|-----------------|--|--------|--------------------------|
| LD1 (#MON) | Extension I/O communication enabled | Green | Normal: ON Error: OFF |
| LD2 (DONA) | Extension I/O communication output enabled | Green | Normal: ON Error: OFF |
| LD7 (DONA) | Extension I/O communication output enabled (D/A) | Green | Normal: ON Error: OFF |
| LD8 (#MCARE) | Extension I/O communication error (2) | Red | Normal: OFF Error: ON |
| LD9 (#LCARE) | Extension I/O communication error (1) | Orange | Normal: OFF Error: ON |
| LD10 (#MON) | Extension I/O communication enabled (D/A) | Green | Normal: ON Error: OFF |

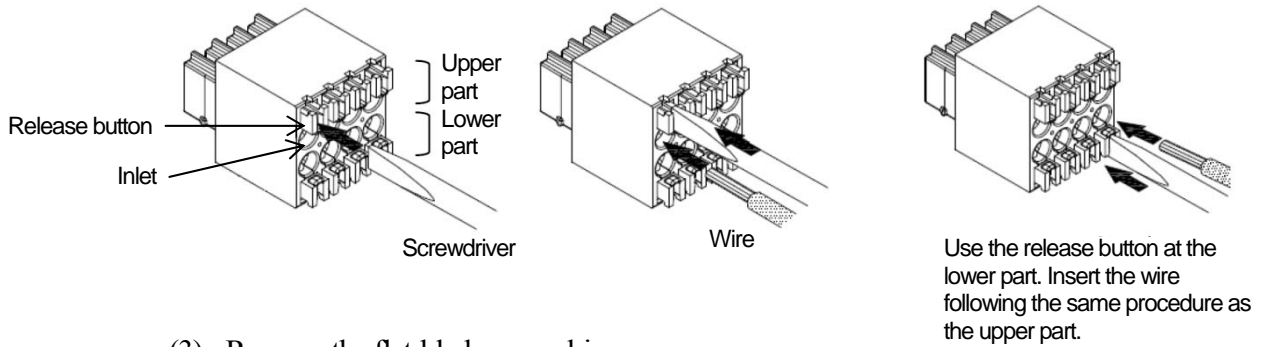
2-3. Gauge clamp connection

Connect the lead wires as shown below.

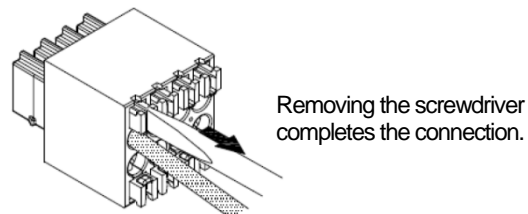
- (1) Use the wires specified in the table below. If the wire end needs to be terminated, fit a ferrule.

| Board | Connector No. | Cross section | | Stripped length |
|-------|---------------|---------------|-----------------------------|-----------------|
| 2AN | XWELD (A) | AWG26-20 | 0.14 to 0.5 mm ² | 6.5 to 7.5 mm |
| | XWELD (B) | AWG26-20 | 0.14 to 0.5 mm ² | 6.5 to 7.5 mm |

- (2) Push in the wire with a 1.5 to 2.0 mm flat-blade screwdriver while depressing the release button.



- (3) Remove the flat-blade screwdriver.



Appendix 3 Deformation of Welding Torch and Replacement

During welding by the robot, the welding torch may interfere with the workpiece due to an unexpected trouble, and this may result in bending or damage to the torch. In this case, repair or replace the torch and adjust it as described below.

Torch Adjusting Method Using a Fixed Teaching Point

After completing installation and adjustment of the robot and the jig, mark a point on a stationary section of the jig. Then teach the wire tip so as to face vertically with the wire extended to the length used when welding. It is recommended to give a name to the teaching program, which is distinguishable from other programs.

Appendix 4 Machine Control Cable and Welding Cable Specifications

1. Connector and cable specifications

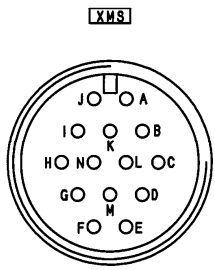
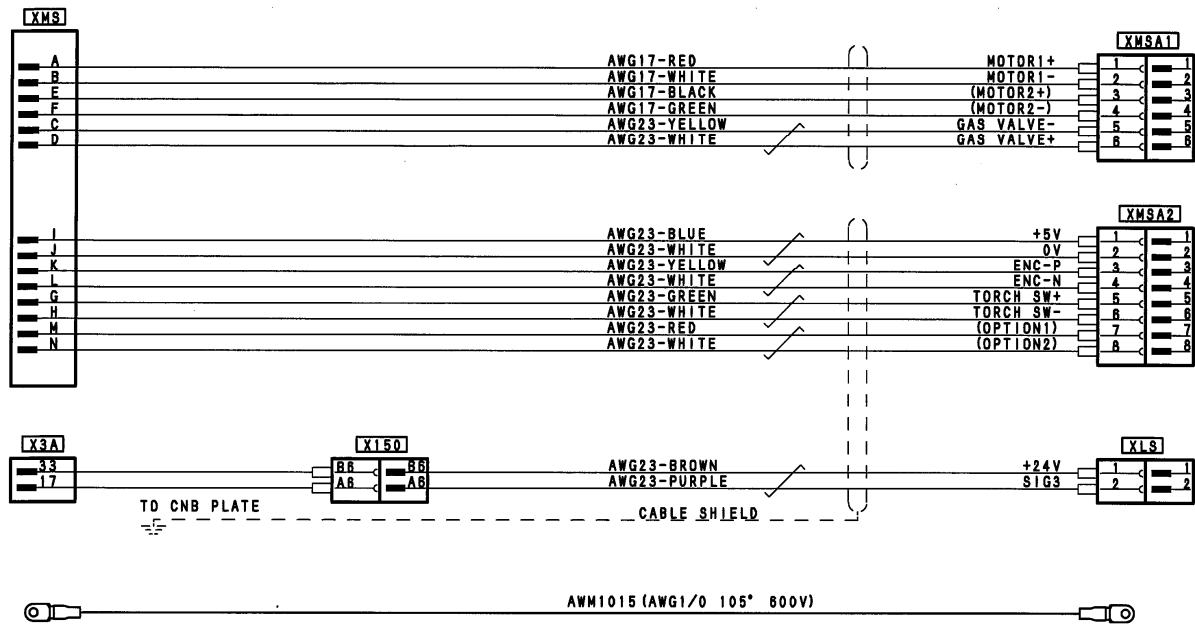
Prepare the control cable connected from the welder that is connected to the machine control cable to the robot base and the control cable from the optional BOX of upper arm to the feeder as needed.

- Mating connector (XMS) type on robot base
Connector/ITT CANON: CAR3106A20-27S
or DDK: D/MS3106A20-27S

Cable clamp/ITT CANON:CAR17711-22
or DDK: D/MS3057-12A

- Mating connector (XMSA1, XMSA2) type on upper arm
XMSA1/WAGO: 734-306 (attached to robot)
XMSA2/WAGO: 734-308 (attached to robot)

- Welding cable specifications
Welding cable is AWG1/0 (60sq or equivalent). Use it with the rated output current of 350 A (use rate 60%) or less. For other cases, use the welding cable of appropriate size by external wiring.



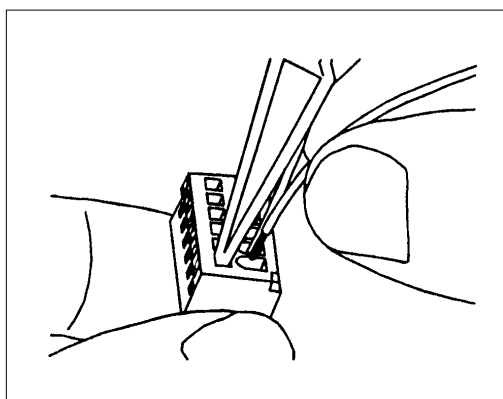
Connection with welder (DM-350)

| Connector | Number | Signal | Function | Number | Connector |
|--|--------|------------|-------------------------------------|--------|---------------------------------|
| XMS/(ITT) CAR3102A20-27P | A | MOTOR1+ | Wire Feeding Motor Power Supply (+) | 1 | XMSA1/(WAGO) 734-106/037-000 |
| | B | MOTOR1- | Wire Feeding Motor Power Supply (-) | 2 | |
| | E | (MOTOR2+) | Pull Motor Power Supply (+) | 3 | |
| | F | (MOTOR2-) | Pull Motor Power Supply (-) | 4 | |
| | C | GAS VALVE- | Gas Solenoid Valve Power Supply (-) | 5 | |
| | D | GAS VALVE+ | Gas Solenoid Valve Power Supply (+) | 6 | |
| | I | +5V | Encoder Power Supply (+5V) | 1 | XMSA2/(WAGO) 734-108/037-000 |
| | J | 0V | Encoder Power Supply (0V) | 2 | |
| | K | ENC-P | Encoder (phase A) | 3 | |
| | L | ENC-N | Encoder (phase B) | 4 | |
| | G | TORCH SW+ | Torch Switch + | 5 | |
| | H | TORCH SW- | Torch Switch - | 6 | |
| | M | (OPTION1) | Reserve | 7 | |
| | N | (OPTION2) | Reserve | 8 | |
| X3A/(WAIN) housing:H10B-BK-2L/CW terminal:HDD-042-NC | 33 | +24V | Shock Sensor (+24V) | 1 | XLS/(WAGO) 733-102/037-000 |
| | 17 | SIG3 | Shock Sensor (SIG3) | 2 | |

2. Connection of gauge clamp

| Connector No. | Cross section | | Stripped length |
|---------------|---------------|-----------------------------|-----------------|
| XMSA1 | AWG16-14 | 1.25 to 2.0 mm ² | 6 to 7 mm |
| XMSA2 | AWG22-14 | 0.5 to 2.0 mm ² | 6 to 7 mm |
| XLS | AWG22-20 | 0.5 mm ² | 5 to 6 mm |

Connect wire leads as shown in figures below.



- Connecting conductive wire from the top
- via tool WAGO 233-332 for WAGO Series 733
 - via tool WAGO 233-332 for WAGO Series 734



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