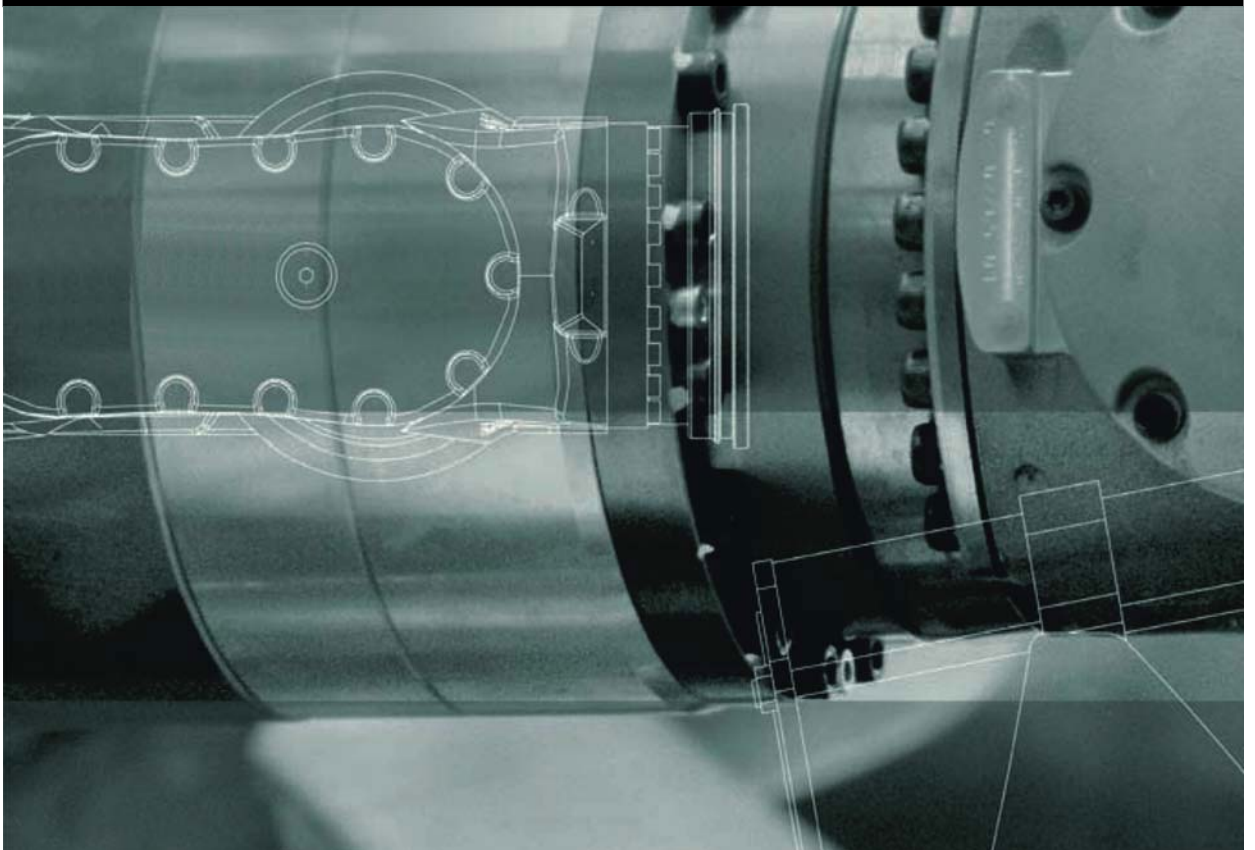


KR 360-3; KR 500-3

Specification



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Other functions not described in this documentation may be operable in the controller. The user has no claims to these functions, however, in the case of a replacement or service work.

We have checked the content of this documentation for conformity with the hardware and software described. Nevertheless, discrepancies cannot be precluded, for which reason we are not able to guarantee total conformity. The information in this documentation is checked on a regular basis, however, and necessary corrections will be incorporated in the subsequent edition.

Subject to technical alterations without an effect on the function.

Translation of the original documentation

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1 Introduction

1.1 Industrial robot documentation

The industrial robot documentation consists of the following parts:


- Documentation for the manipulator
- Documentation for the robot controller
- Operating and programming instructions for the KUKA System Software
- Documentation relating to options and accessories
- Parts catalog on storage medium


Each of these sets of instructions is a separate document.


1.2 Representation of warnings and notes


Safety


These warnings are relevant to safety and **must** be observed.

 **DANGER** These warnings mean that it is certain or highly probable that death or severe injuries **will** occur, if no precautions are taken.


 **WARNING** These warnings mean that death or severe injuries **may** occur, if no precautions are taken.

 **CAUTION** These warnings mean that minor injuries **may** occur, if no precautions are taken.

 **NOTICE** These warnings mean that damage to property **may** occur, if no precautions are taken.


 These warnings contain references to safety-relevant information or general safety measures.
These warnings do not refer to individual hazards or individual precautionary measures.

This warning draws attention to procedures which serve to prevent or remedy emergencies or malfunctions:

 **SAFETY INSTRUCTIONS** Procedures marked with this warning **must** be followed exactly.

Notes

These hints serve to make your work easier or contain references to further information.

 Tip to make your work easier or reference to further information.

1.3 Terms used

Term	Description
Stopping distance	Stopping distance = reaction distance + braking distance The stopping distance is part of the danger zone.
KCP	The KCP (KUKA Control Panel) teach pendant has all the operator control and display functions required for operating and programming the industrial robot. The KCP variant for the KR C4 is called KUKA smartPAD. The general term "KCP", however, is generally used in this documentation.
Manipulator	The robot arm and the associated electrical installations

2 Purpose

2.1 Target group

This documentation is aimed at users with the following knowledge and skills:

- Advanced knowledge of mechanical engineering
- Advanced knowledge of electrical and electronic systems
- Knowledge of the robot controller system



For optimal use of our products, we recommend that our customers take part in a course of training at KUKA College. Information about the training program can be found at www.kuka.com or can be obtained directly from our subsidiaries.

2.2 Intended use

Use The industrial robot is intended for handling tools and fixtures, or for processing or transferring components or products. Use is only permitted under the specified environmental conditions.

Misuse Any use or application deviating from the intended use is deemed to be impermissible misuse. This includes e.g.:

- Transportation of persons and animals
- Use as a climbing aid
- Operation outside the permissible operating parameters
- Use in potentially explosive environments
- Use in underground mining

NOTICE

Changing the structure of the manipulator, e.g. by drilling holes, etc., can result in damage to the components. This is considered improper use and leads to loss of guarantee and liability entitlements.



The robot system is an integral part of a complete system and may only be operated in a CE-compliant system.

3 Product description

3.1 Overview of the robot system

The robot system consists of the following components:

- Robot
- Robot controller
- smartPAD teach pendant
- Connecting cables
- Software
- Options, accessories

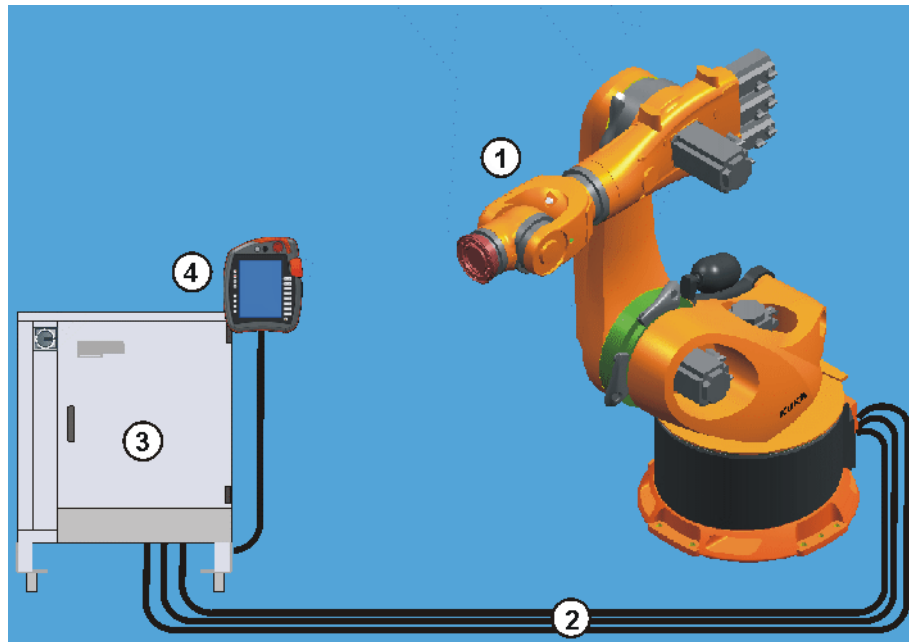


Fig. 3-1: Example of a robot system

- | | | | |
|---|-------------------|---|------------------------|
| 1 | Robot | 3 | Robot controller |
| 2 | Connecting cables | 4 | smartPAD teach pendant |

3.2 Description of the robot

Overview

The robot is designed as a 6-axis jointed-arm kinematic system. The structural components of the robot are made of light alloy and iron castings. The axes are driven by AC servomotors. A hydropneumatic counterbalancing system is used to equalize the load moment about axis 2.

The robot consists of the following principal components:

- In-line wrist
- Arm
- Link arm
- Rotating column
- Base frame
- Counterbalancing system
- Electrical installations

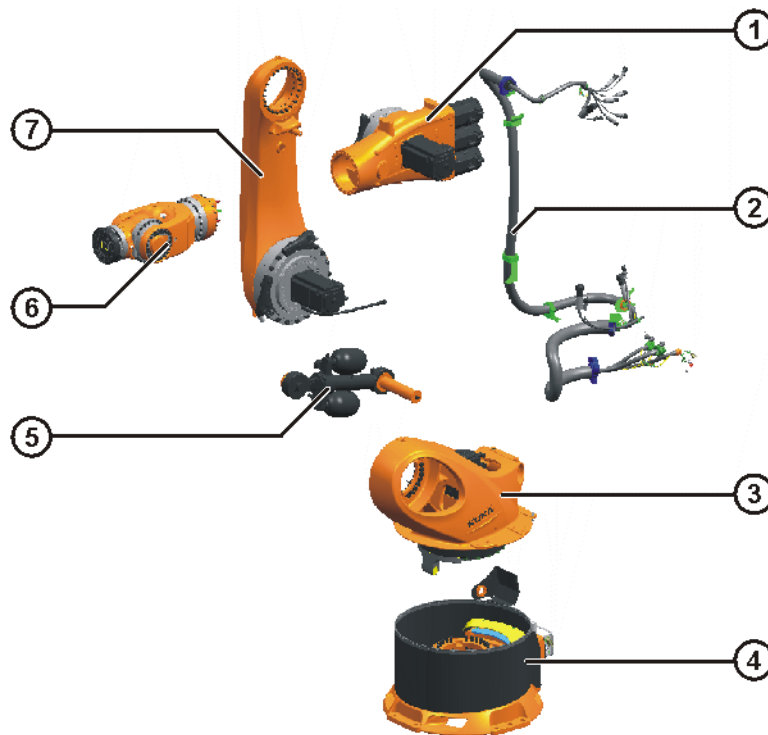


Fig. 3-2: Principal components

- | | |
|----------------------------|---------------------------|
| 1 Arm | 5 Counterbalancing system |
| 2 Electrical installations | 6 In-line wrist |
| 3 Rotating column | 7 Link arm |
| 4 Base frame | |

In-line wrist

The robot is fitted with a 3-axis in-line wrist for a rated payload of 500 kg. The in-line wrist comprises axes 4, 5 and 6. It is driven by three AC servomotors installed at the rear end of the arm via drive shafts. The motor unit consists of brushless AC servomotors with a permanent-magnet single-disk brake and hollow-shaft resolver, both integrated. The permanent-magnet single-disk brakes perform a holding function when the servomotor is at rest and contribute to the braking of the respective axis in the event of short-circuit braking (e.g. if one or more of the enabling switches is released while in Test mode). Short-circuit braking must not be used to stop the robot under normal circumstances. The gear units of the in-line wrist are supplied with oil from two separate oil chambers.

If the permissible turning range of a wrist axis is exceeded, the robot is switched off by means of software limit switches. The turning range of A5 is mechanically limited by end stops performing a buffer function.

The in-line wrist forms an exchangeable unit with a standardized mechanical interface to the arm.

The assembly also has a gauge mount with a gauge cartridge, through which the mechanical zero of the axis can be determined by means of an electronic probe (accessory) and transferred to the controller.

The in-line wrist variant "F" is available for operating conditions involving greater mechanical and thermal stress.

Arm

The arm is the link between the in-line wrist and the link arm. It houses the motors of the wrist axes A4, A5 and A6, as well as motor A3. The arm is driven by an AC servomotor via a gear unit that is installed between the arm and the link arm. The maximum permissible swivel range is limited by mechanical limit

stops with a buffer function in the positive and negative directions in addition to the software limit switches.

The arm variant “F” is available for operating conditions involving greater mechanical and thermal stress. The arms of the F variants are pressurized to prevent penetration of moisture and dust.

Link arm	The link arm is the assembly located between the arm and the rotating column. It is mounted on one side of the rotating column via a gear unit. The motor unit consists of a brushless AC servomotor with a permanent-magnet single-disk brake and hollow-shaft resolver, both integrated. The permanent-magnet single-disk brake performs a holding function when the servomotor is at rest and contributes to the braking of the respective axis in the event of short-circuit braking (e.g. if one or more of the enabling switches is released while in Test mode). Short-circuit braking must not be used to stop the robot under normal circumstances. During motion about axis 2, the link arm moves about the stationary rotating column. The usable software swivel range is limited by mechanical limit stops with a buffer function in the positive and negative directions in addition to the software limit switches.
Rotating column	The rotating column houses the motors of axes 1 and 2. The rotational motion of axis 1 is performed by the rotating column. It is screwed to the base frame via the gear unit of axis 1. Inside the rotating column is a brushless AC servomotor with a permanent-magnet single-disk brake and hollow-shaft resolver, both integrated, for driving axis 1. The permanent-magnet single-disk brake performs a holding function when the servomotor is at rest and contributes to the braking of the respective axis in the event of short-circuit braking (e.g. if one or more of the enabling switches is released while in Test mode). Short-circuit braking must not be used to stop the robot under normal circumstances. The counterbearing for the counterbalancing system is integrated into the rear of the rotating column housing.
Base frame	The base frame is the base of the robot. It is screwed to the mounting base. The interfaces for the electrical installations and the energy supply systems (accessory) are housed in the base frame. The base frame and rotating column are connected via the gear unit of axis 1. The flexible tube for the electrical installations and the energy supply system is accommodated in the base frame.
Counterbalancing system	The counterbalancing system is an assembly installed between the rotating column and the link arm. This assembly minimizes the torques generated about axis 2 when the robot is moving or stationary. A closed, hydropneumatic system is used. The system consists of two accumulators, a hydraulic cylinder with associated hoses, a pressure gauge and a bursting disc as a safety element to protect against overload. The accumulators correspond to category III, fluid group 2, of the Pressure Equipment Directive. Different variants of the counterbalancing system are used for floor and ceiling-mounted robots and for the F variants. The mode of operation is reversed for ceiling-mounted robots, i.e. the piston rod pushes against the link arm.
Electrical installations	The electrical installations are described in Chapter .
Options	The robot can be fitted and operated with various options, e.g. working range limitation. The options are described in separate documentation.

4 Technical data

4.1 Basic data

Basic data KR 360-3

Type	KR 360-3 KR 360-3 F KR 360 L240-3 KR 360 L240-3 F KR 360 L280-3 KR 360 L280-3 F
Number of axes	6
Volume of working envelope	KR 360-3: 68 m ³ KR 360-3 F: 68 m ³ KR 360 L240-3: 114.5 m ³ KR 360 L240-3 F: 114.5 m ³ KR 360 L280-3: 88 m ³ KR 360 L280-3 F: 88 m ³
Pose repeatability (ISO 9283)	±0.08 mm
Working envelope reference point	Intersection of axes 4 and 5
Weight	KR 360-3: 2,375 kg KR 360-3 F: 2,375 kg KR 360 L240-3: 2,411 kg KR 360 L240-3 F: 2,411 kg KR 360 L280-3: 2,405 kg KR 360 L280-3 F: 2,405 kg
Principal dynamic loads	See Loads acting on the foundation
Protection classification of the robot	IP 65 ready for operation, with connecting cables plugged in (according to EN 60529)
Protection classification of the in-line wrist	IP 65
Protection classification of the "F" in-line wrist	IP 67
Sound level	< 75 dB (A) outside the working envelope
Mounting position	Floor Permissible angle of inclination ≤ 10°
Surface finish, paint-work	Base (stationary): black (RAL 9005); moving parts: KUKA orange 2567

Basic data
KR 500-3

Type	KR 500-3 KR 500-3 F KR 500-3 C KR 500 L340-3 KR 500 L340-3 F KR 500 L420-3 KR 500 L420-3 F KR 500 L420-3 C
Number of axes	6
Volume of working envelope	KR 500-3: 68 m ³ KR 500-3 F: 68 m ³ KR 500-3 C: 68 m ³ KR 500 L340-3: 114.5 m ³ KR 500 L340-3 F: 114.5 m ³ KR 500 L420-3: 88 m ³ KR 500 L420-3 F: 88 m ³ KR 500 L420-3 C: 88 m ³
Pose repeatability (ISO 9283)	±0.08 mm
Work envelope reference point	Intersection of axes 4 and 5
Weight	KR 500-3: 2,375 kg KR 500-3 F: 2,375 kg KR 500-3 C: 2,375 kg KR 500 L340-3: 2,411 kg KR 500 L340-3 F: 2,411 kg KR 500 L420-3: 2,405 kg KR 500 L420-3 F: 2,405 kg KR 500 L420-3 C: 2,405 kg
Principal dynamic loads	See Loads acting on the foundation
Protection classification of the robot	IP 65 ready for operation, with connecting cables plugged in (according to EN 60529)
Protection classification of the in-line wrist	IP 65
Protection classification of the in-line wrist F	IP 67
Sound level	< 75 dB (A) outside the working envelope

Mounting position	Floor Permissible angle of inclination $\leq 10^\circ$ Ceiling No angle of inclination permissible
Surface finish, paint-work	Base (stationary): black (RAL 9005); moving parts: KUKA orange 2567

Foundry robots

Overpressure in the arm	0.01 MPa (0.1 bar)
Compressed air	Free of oil and water
Compressed air supply line	Air line in the cable set
Air consumption	0.1 m ³ /h
Air line connection	Quick Star push-in fitting for hose PUN-6x1, blue
Pressure regulator connection	R 1/8", internal thread
Input pressure	0.1 - 1.2 MPa (1 - 12 bar)
Pressure regulator	0.005 - 0.07 MPa (0.05 - 0.7 bar)
Manometer range	0.0 - 0.1 MPa (0.0 - 1.0 bar)
Filter gauge	25 - 30 μ m
Thermal loading	10 s/min at 353 K (180 °C)
Resistance	Increased resistance to dust, lubricants, coolants and water vapor.
Special paint finish on wrist	Heat-resistant and heat-reflecting silver paint finish on the in-line wrist.
Special paint finish on the robot	Special paint finish on the entire robot, and an additional protective clear coat.
Other ambient conditions	KUKA Roboter GmbH must be consulted if the robot is to be used under other ambient conditions.

Ambient temperature

Operation	+10 °C to +55 °C (283 K to 328 K)
Storage and transportation	-40 °C to +60 °C (233 K to 333 K)
Start-up	+10 °C to +15 °C (283 K to 288 K) At these temperatures the robot may have to be warmed up before normal operation.
Ambient conditions	DIN EN 60721-3-3 Class 3K3

Connecting cables

Cable designation	Connector designation	Interface with robot
Motor cable	X20.1 - X30.1	Harting connectors at both ends
Motor cable	X20.4 - X30.4	Harting connectors at both ends
Control cable	X21 - X31	HAN 3A EMC at both ends
Ground conductor / equipotential bonding 16 mm ² (optional)		M8 ring cable lug at both ends

Cable lengths	
Standard	7 m, 15 m, 25 m, 35 m, 50 m

For detailed specifications of the connecting cables, see .

4.2 Axis data

Axis data

KR 360-3

The following axis data are valid for the robots:

- KR 360-3
- KR 360-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	98 °/s
2	+20° to -130°	91 °/s
3	+144° to -100°	89 °/s
4	+/-350°	110 °/s
5	+/-120°	111 °/s
6	+/-350°	153 °/s

The following axis data are valid for the robots:

- KR 360 L240-3
- KR 360 L240-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	98 °/s
2	+20° to -130°	91 °/s
3	+144° to -100°	89 °/s
4	+/-350°	110 °/s
5	+/-120°	111 °/s
6	+/-350°	153 °/s

The following axis data are valid for the robots:

- KR 360 L280-3
- KR 360 L280-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	98 °/s
2	+20° to -130°	91 °/s
3	+144° to -100°	89 °/s
4	+/-350°	110 °/s
5	+/-120°	111 °/s
6	+/-350°	153 °/s

Axis data

KR 500-3

The following axis data are valid for the robots:

- KR 500-3
- KR 500-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	84 °/s
2	+20° to -130°	79 °/s

Axis	Range of motion, software-limited	Speed with rated payload
3	+144° to -100°	73 °/s
4	+/-350°	76 °/s
5	+/-120°	74 °/s
6	+/-350°	123 °/s

The following axis data are valid for the robot:

■ KR 500-3 C

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	84 °/s
2	+20° to -130°	79 °/s
3	+144° to -100°	73 °/s
4	+/-350°	76 °/s
5	+/-118°	74 °/s
6	+/-350°	123 °/s

The following axis data are valid for the robots:

■ KR 500 L340-3

■ KR 500 L340-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	84 °/s
2	+20° to -130°	79 °/s
3	+144° to -100°	73 °/s
4	+/-350°	76 °/s
5	+/-120°	74 °/s
6	+/-350°	123 °/s

The following axis data are valid for the robots:

■ KR 500 L420-3

■ KR 500 L420-3 F

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	84 °/s
2	+20° to -130°	79 °/s
3	+144° to -100°	73 °/s
4	+/-350°	76 °/s
5	+/-120°	74 °/s
6	+/-350°	123 °/s

The following axis data are valid for the robot:

■ KR 500 L420-3 C

Axis	Range of motion, software-limited	Speed with rated payload
1	+/-185°	84 °/s
2	+20° to -130°	79 °/s
3	+144° to -100°	73 °/s
4	+/-350°	76 °/s

Axis	Range of motion, software-limited	Speed with rated payload
5	+/-118°	74 °/s
6	+/-350°	123 °/s

The direction of motion and the arrangement of the individual axes may be noted from the diagram (>>> Fig. 4-1).

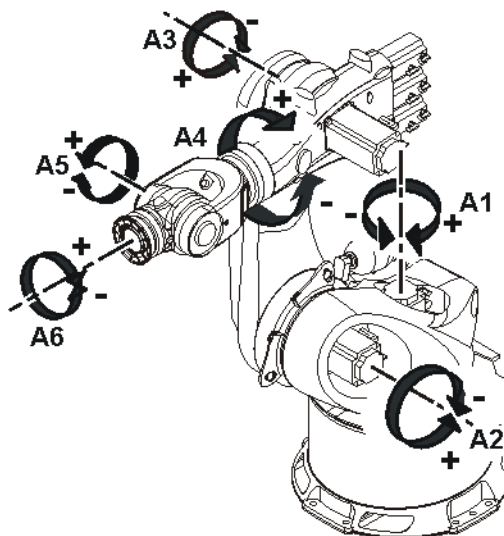


Fig. 4-1: Direction of rotation of robot axes

Working envelope

The diagram (>>> Fig. 4-2) shows the shape and size of the working envelope for the robots:

- KR 360-3
- KR 360-3 F
- KR 500-3
- KR 500-3 F

The reference point for the working envelope is the intersection of axis 4 with axis 5.

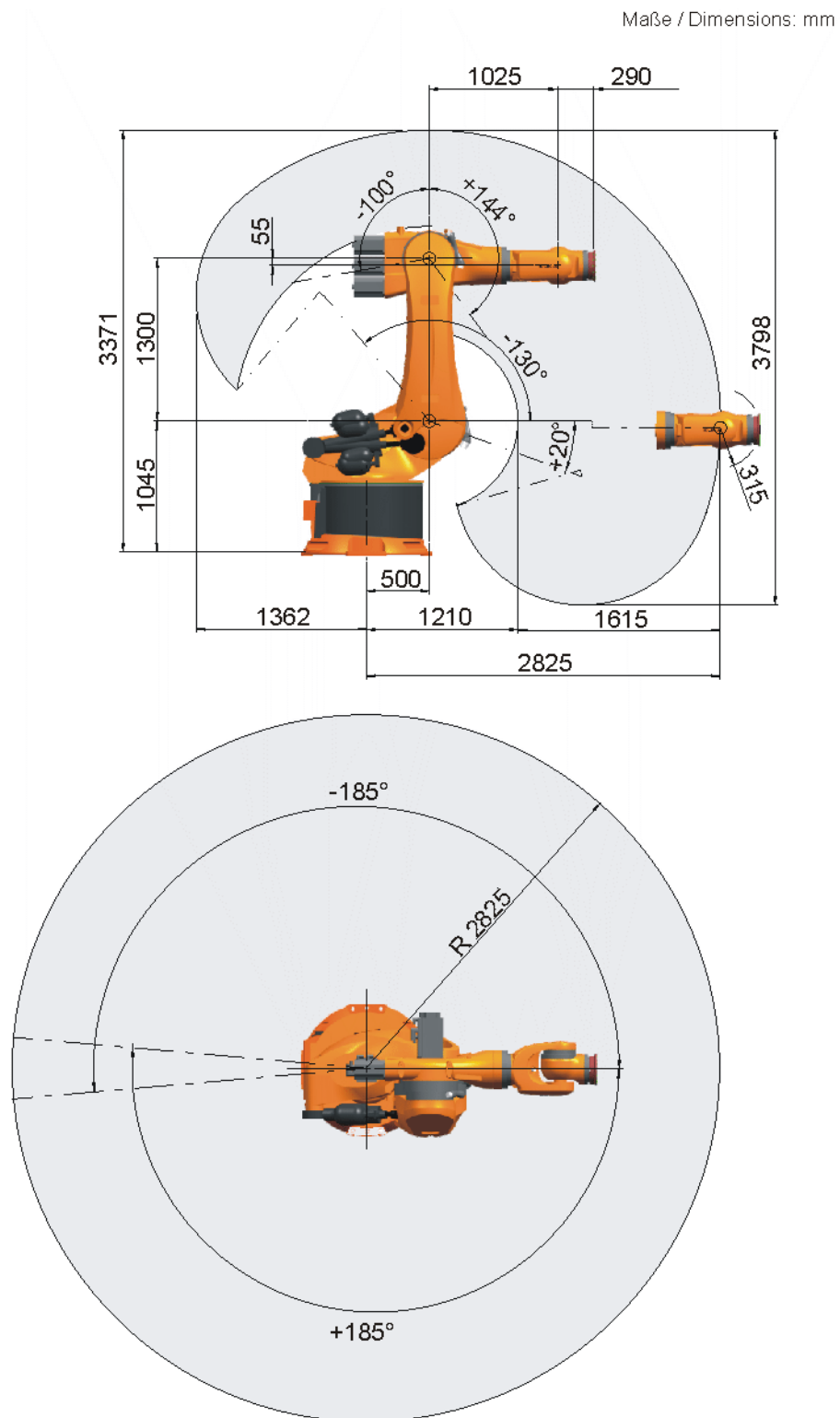


Fig. 4-2: Working envelope for KR 360-3, KR 500-3 (incl. F variant)

The diagram (>>> Fig. 4-3) shows the shape and size of the working envelope for the robot:

■ KR 500-3 C

The reference point for the working envelope is the intersection of axis 4 with axis 5.

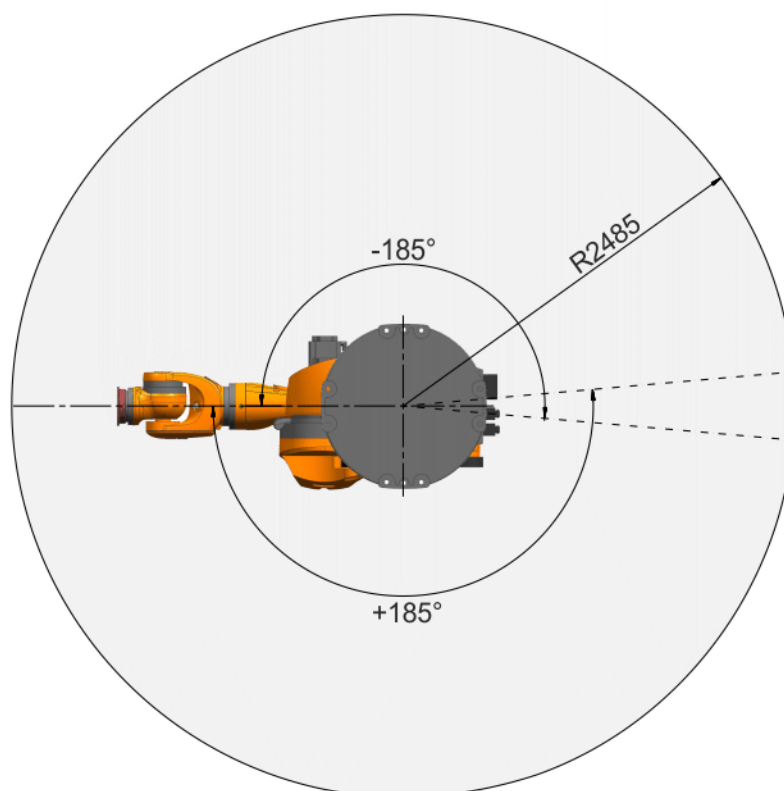
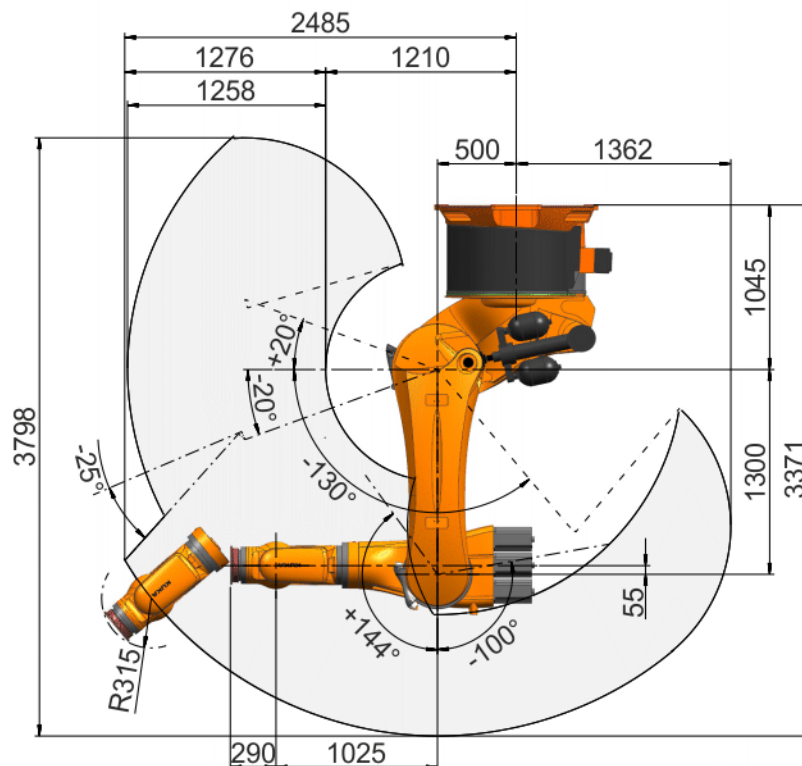


Fig. 4-3: Working envelope, KR 500-3 C

The diagram (>>> Fig. 4-4) shows the shape and size of the working envelope for the robots:

- KR 360 L240-3
- KR 360 L240-3 F
- KR 500 L340-3

■ KR 500 L340-3 F

The reference point for the working envelope is the intersection of axis 4 with axis 5.

Maße / Dimensions: mm

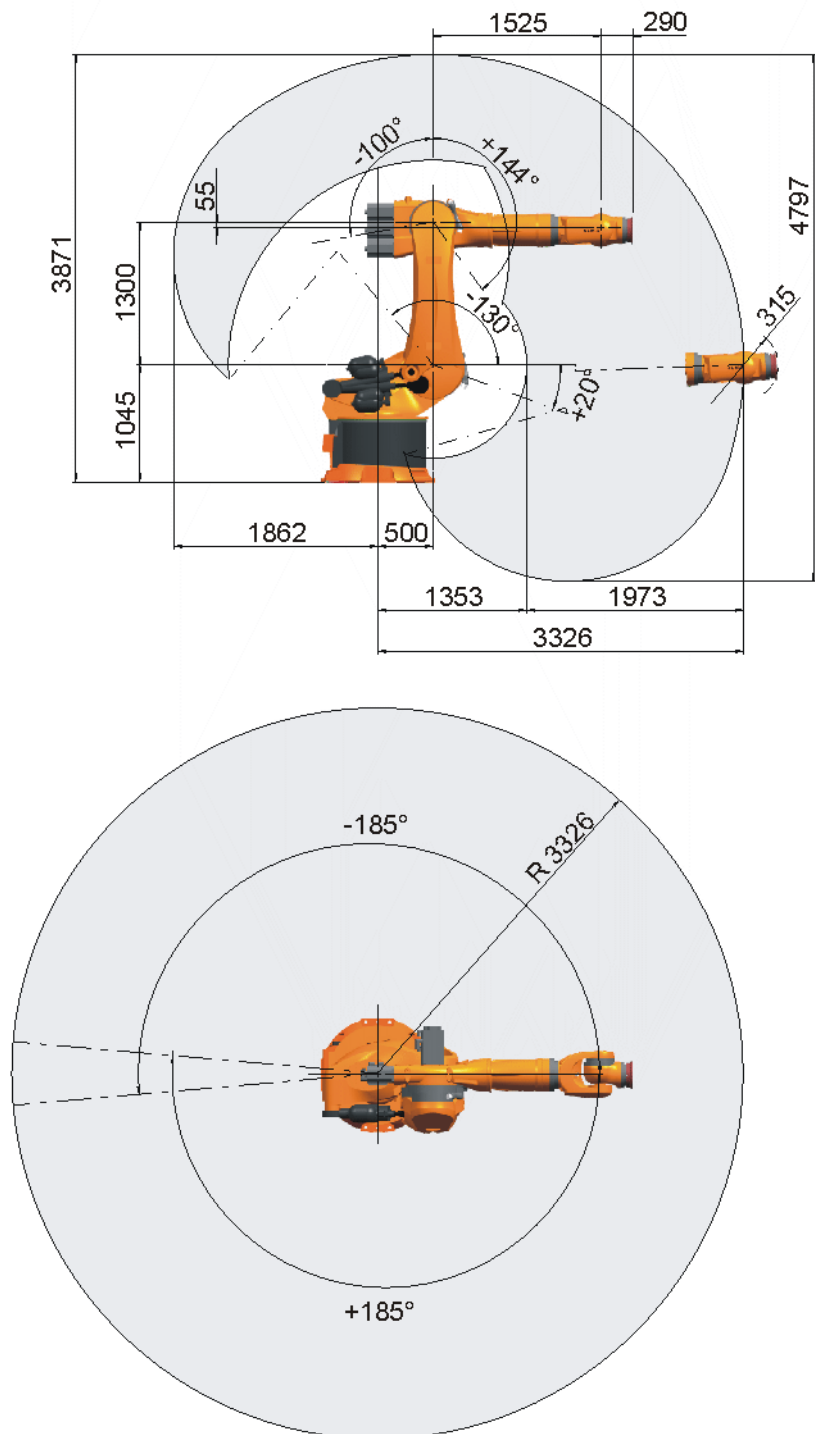


Fig. 4-4: Working envelope for KR 360 L240-3, KR 500 L340-3 (incl. F variant)

The diagram (>>> Fig. 4-5) shows the shape and size of the working envelope for the robots:

- KR 360 L280-3
- KR 360 L280-3 F
- KR 500 L420-3

■ KR 500 L420-3 F

The reference point for the working envelope is the intersection of axis 4 with axis 5.

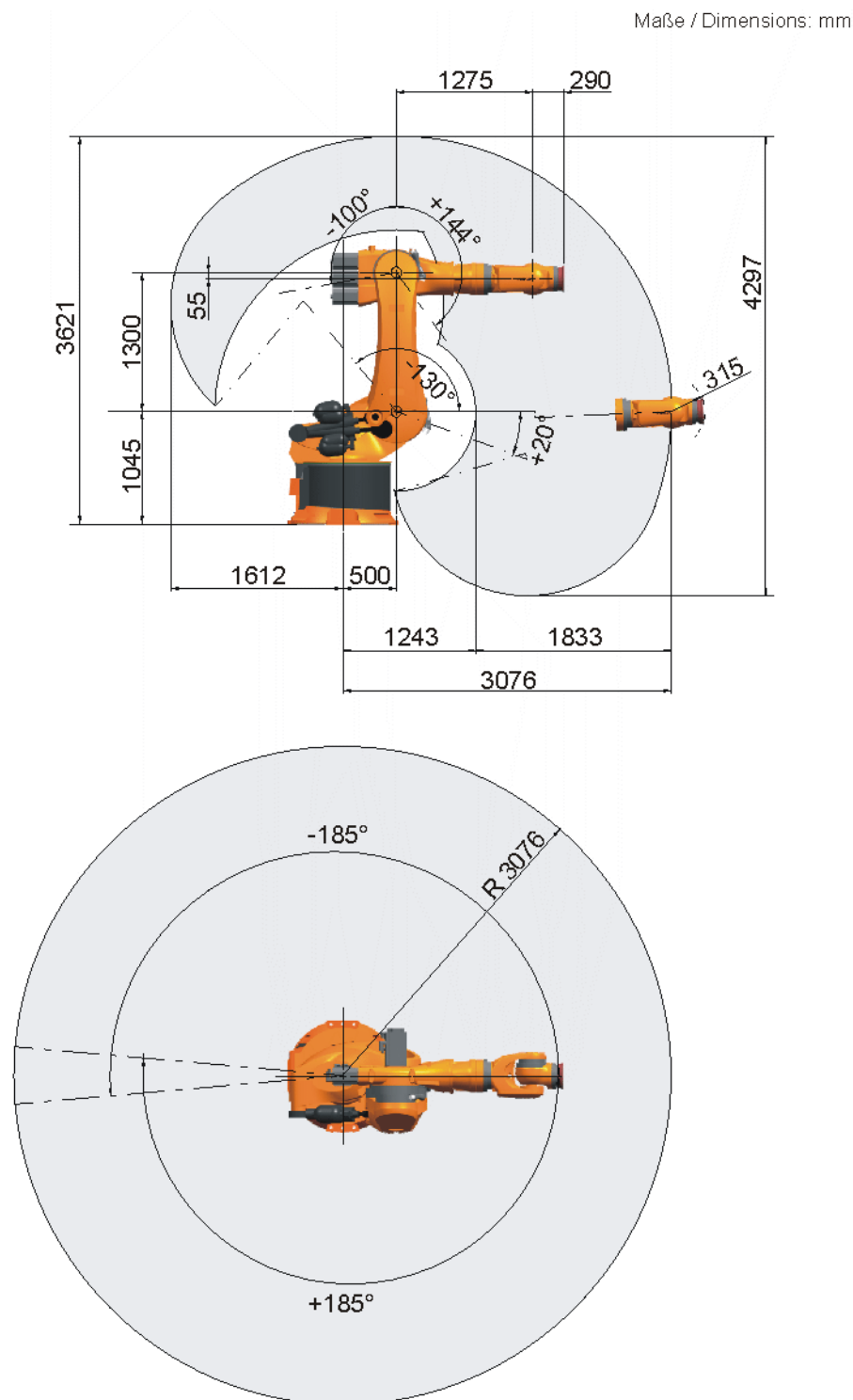


Fig. 4-5: Working envelope for KR 360 L280-3, KR 500 L420-3 (incl. F variant)

The diagram (>>> Fig. 4-6) shows the shape and size of the working envelope for the robot:

■ KR 500 L420-3 C

The reference point for the working envelope is the intersection of axis 4 with axis 5.

Maße / Dimensions: mm

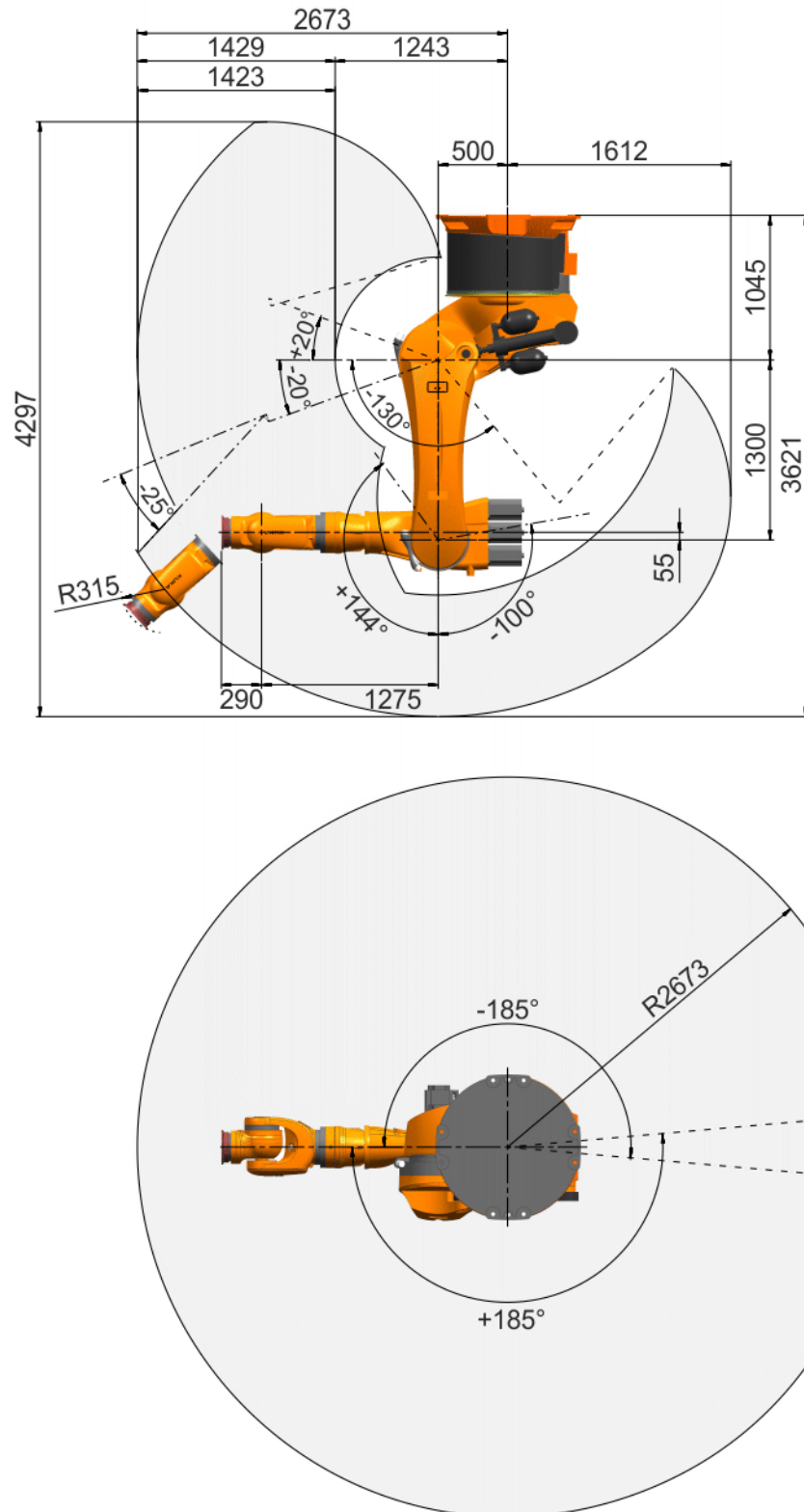


Fig. 4-6: Working envelope for KR 500 L420-3 C

4.3 Payloads

Payloads KR 360-3

The following payloads are valid for the robots:

- KR 360-3

- KR 360-3 F

Robot	KR 360-3
Wrist	IW 360-3
Rated payload	360 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	180 kgm ²
Max. total load	860 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	100 kg
Supplementary load, rotating column	400 kg

The following payloads are valid for the robots:

- KR 360 L240-3
- KR 360 L240-3 F

Robot	KR 360 L240-3
Wrist	IW 360-3
Rated payload	240 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	120 kgm ²
Max. total load	740 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	100 kg
Supplementary load, rotating column	400 kg

The following payloads are valid for the robots:

- KR 360 L280-3
- KR 360 L280-3 F

Robot	KR 360 L280-3
Wrist	IW 360-3
Rated payload	280 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	140 kgm ²
Max. total load	780 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	100 kg
Supplementary load, rotating column	400 kg

Payloads KR 500-3

The following payloads are valid for the robots:

- KR 500-3
- KR 500-3 F

Robot	KR 500-3
Wrist	IW 500-3
Rated payload	500 kg
Distance of the load center of gravity L_z	300 mm

Robot	KR 500-3
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	250 kgm ²
Max. total load	1000 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	100 kg
Supplementary load, rotating column	400 kg

The following payloads are valid for the robot:

■ KR 500-3 C

Robot	KR 500-3 C
Wrist	IW 500-3
Rated payload	500 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	250 kgm ²
Max. total load	1000 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	50 kg
Supplementary load, rotating column	50 kg

The following payloads are valid for the robots:

■ KR 500 L340-3

■ KR 500 L340-3 F

Robot	KR 500 L340-3
Wrist	IW 500-3
Rated payload	340 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	170 kgm ²
Max. total load	840 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	100 kg
Supplementary load, rotating column	400 kg

The following payloads are valid for the robots:

■ KR 500 L420-3

■ KR 500 L420-3 F

Robot	KR 500 L420-3
Wrist	IW 500-3
Rated payload	420 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	210 kgm ²
Max. total load	920 kg
Supplementary load, arm	50 kg

Robot	KR 500 L420-3
Supplementary load, link arm	100 kg
Supplementary load on rotating column	400 kg

The following payloads are valid for the robots:

■ KR 500 L420-3 C

Robot	KR 500 L420-3 C
Wrist	IW 500-3
Rated payload	420 kg
Distance of the load center of gravity L_z	300 mm
Distance of the load center of gravity L_{xy}	350 mm
Permissible moment of inertia	210 kgm ²
Max. total load	920 kg
Supplementary load, arm	50 kg
Supplementary load, link arm	50 kg
Supplementary load, rotating column	50 kg

Load center of gravity P

For all payloads, the load center of gravity refers to the distance from the face of the mounting flange on axis 6. Refer to the payload diagram for the nominal distance.

Payload diagram

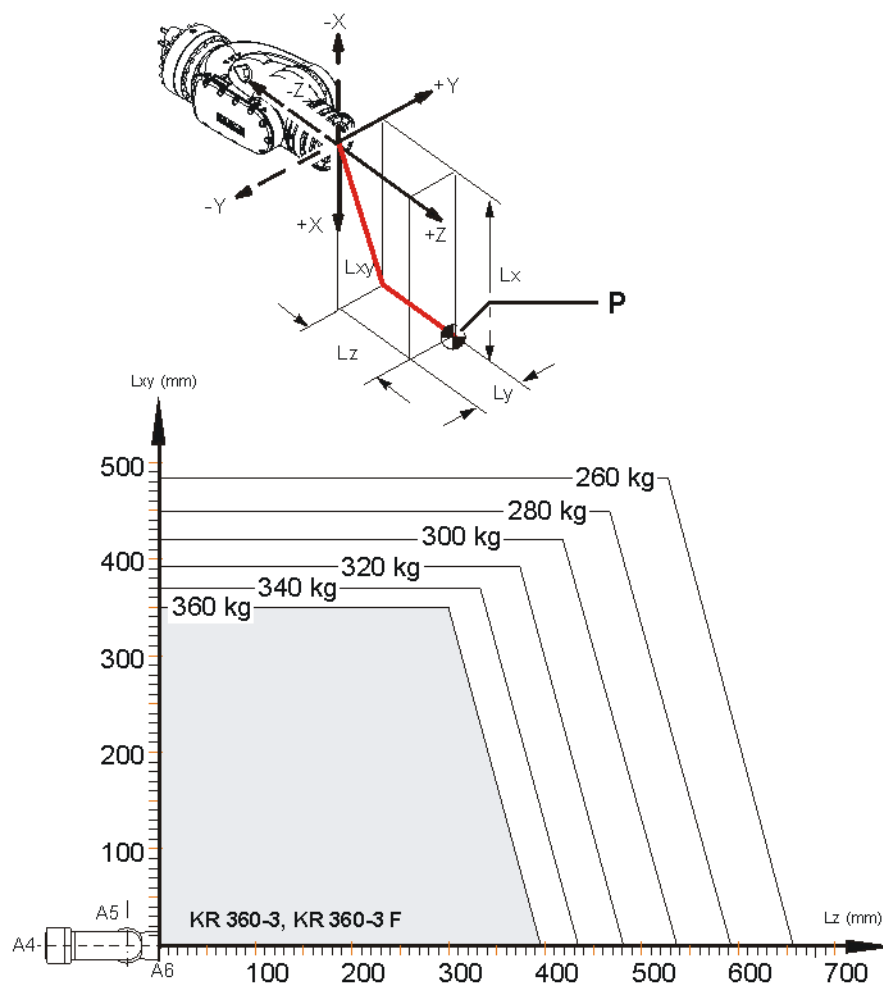


Fig. 4-7: Payload diagram for KR 360-3 (with F variant)

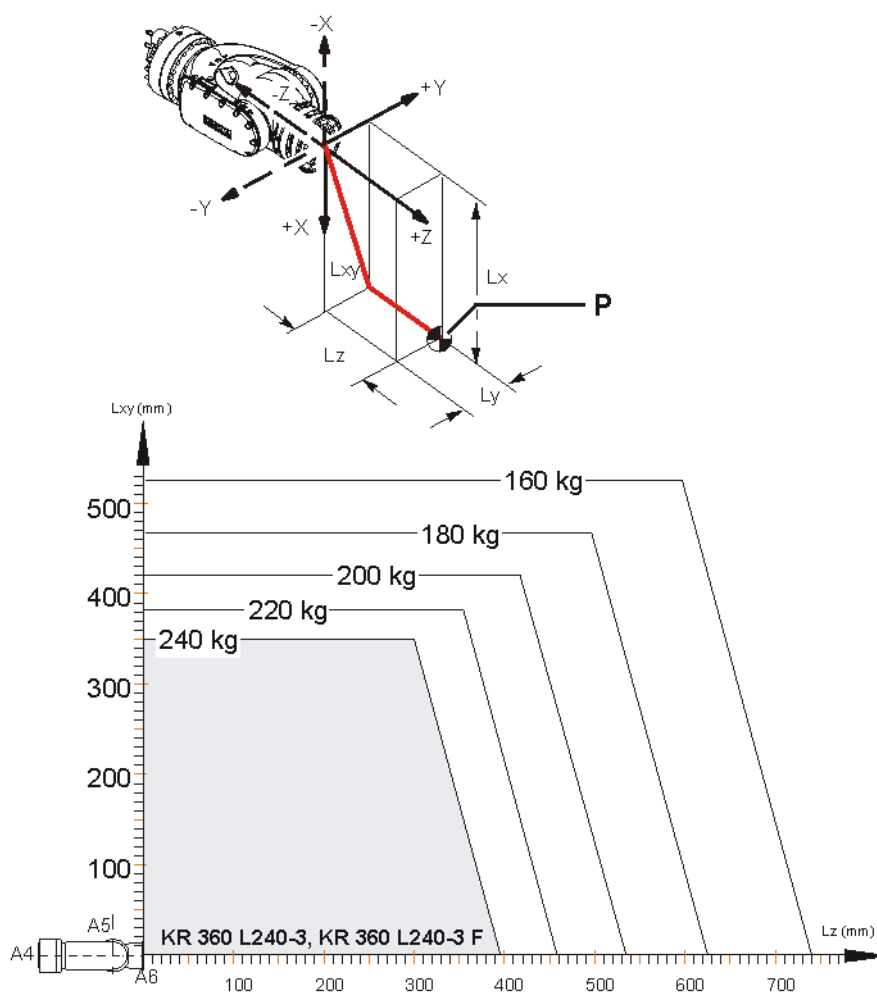


Fig. 4-8: Payload diagram for KR 360 L240-3 (with F variant)

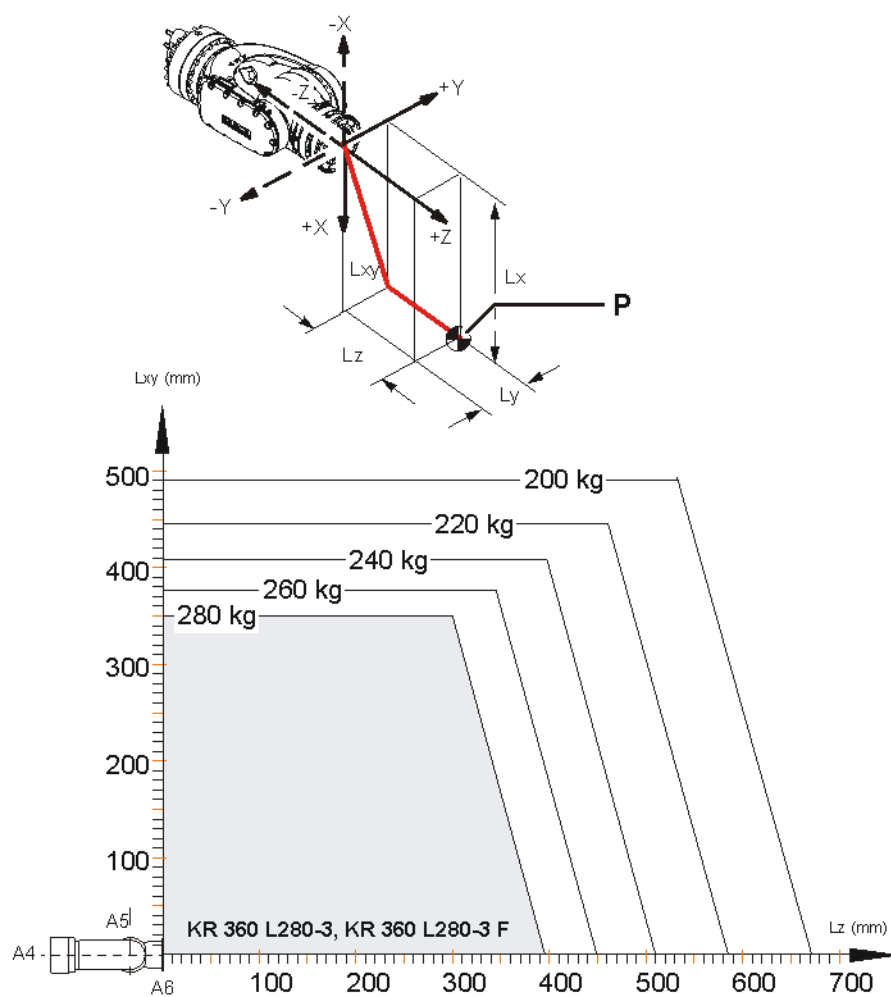


Fig. 4-9: Payload diagram for KR 360 L280-3 (with F variant)

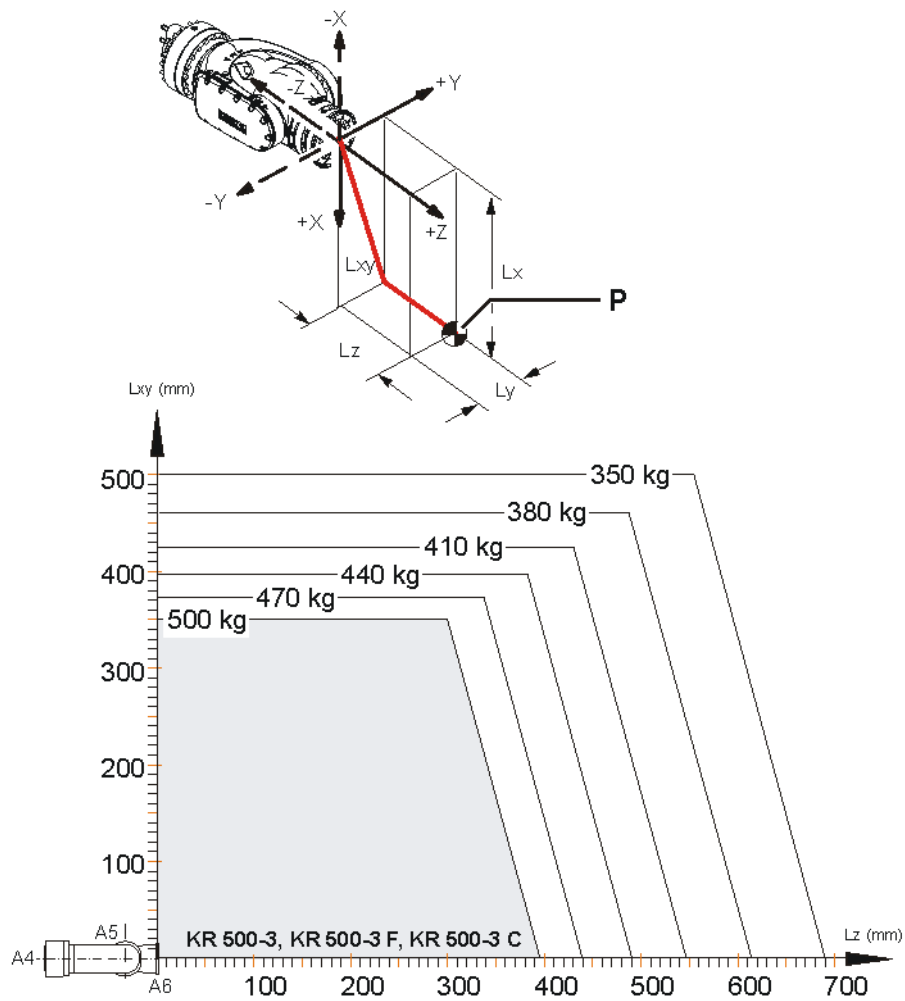


Fig. 4-10: Payload diagram for KR 500-3 MT (with F and C variant)

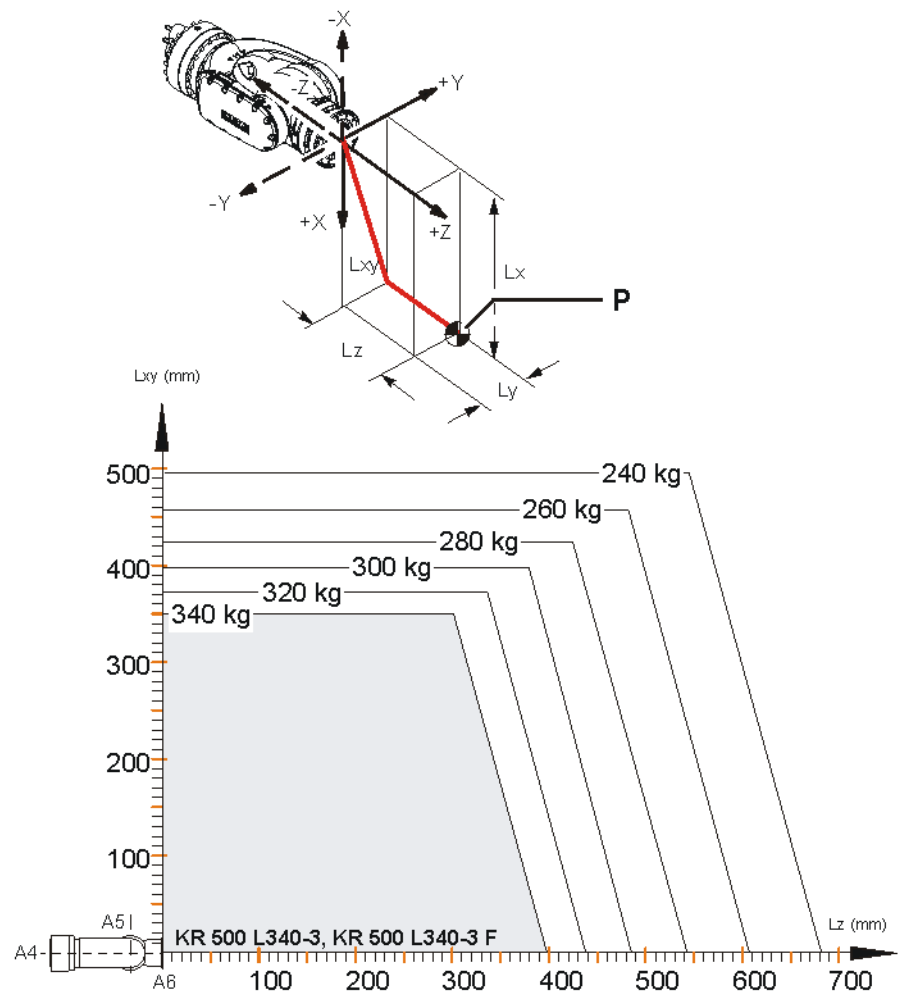


Fig. 4-11: Payload diagram for KR 500 L340-3 (with F variant)

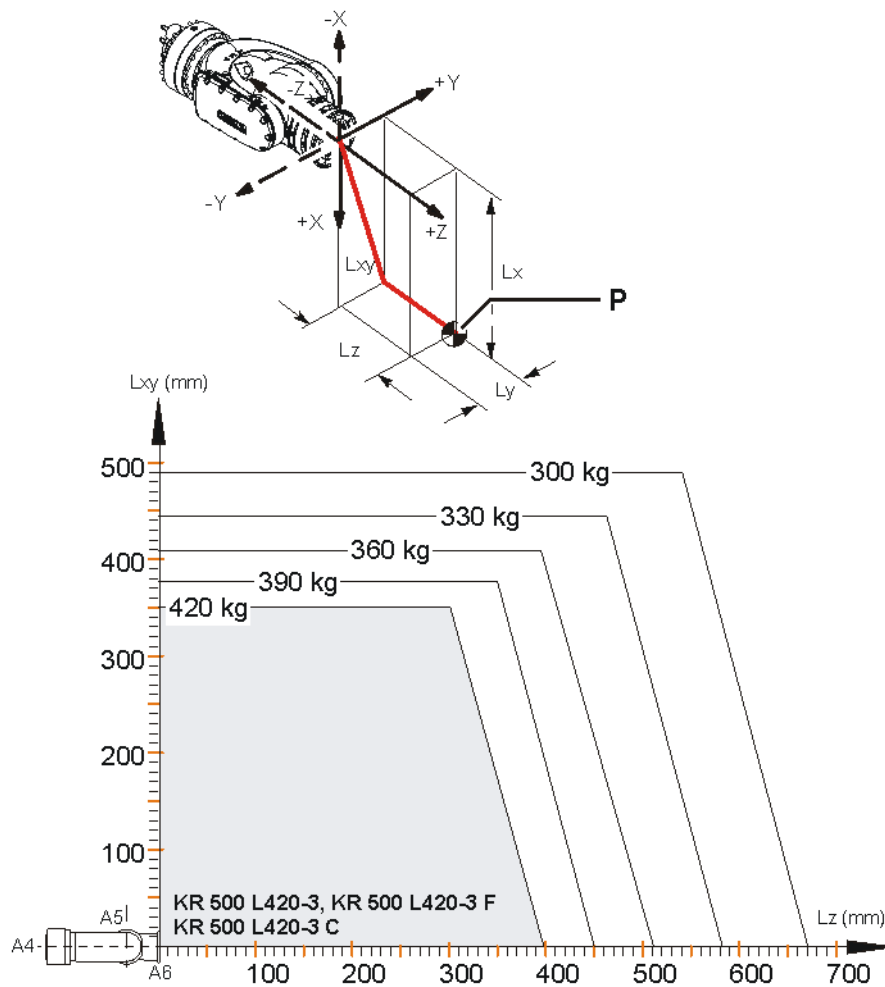


Fig. 4-12: Payload diagram for KR 500 L420-3 (with F and C variant)

NOTICE

This loading curve corresponds to the maximum load capacity. Both values (payload and mass moment of inertia) must be checked in all cases. Exceeding this capacity will reduce the service life of the robot and overload the motors and the gears; in any such case the KUKA Roboter GmbH must be consulted beforehand.

The values determined here are necessary for planning the robot application. For commissioning the robot, additional input data are required in accordance with operating and programming instructions of the KUKA System Software.

The mass inertia must be verified using KUKA.Load. It is imperative for the load data to be entered in the robot controller!

Mounting flange

Mounting flange	DIN/ISO 9409-1-A200
Screw grade	10.9
Screw size	M12
Grip length	1.5 x nominal diameter
Depth of engagement	min. 12 mm, max. 18 mm
Locating element	12 ^{H7}

The mounting flange is depicted (>>> Fig. 4-13) with axis 6 in the zero position. The symbol X_m indicates the position of the locating element (bushing) in the zero position.

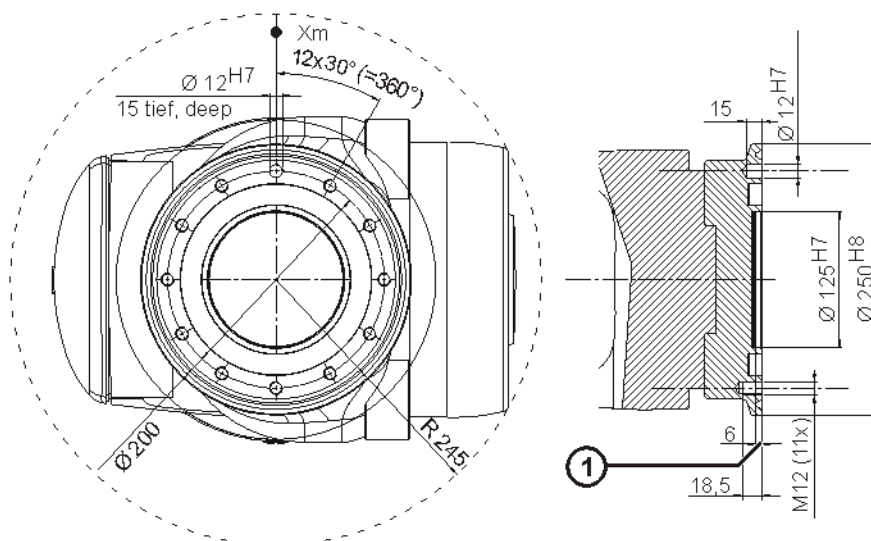


Fig. 4-13: Mounting flange

1 Fitting length

Supplementary load

The robot can carry supplementary loads on the arm, on the rotating column and on the link arm. When mounting the supplementary loads, be careful to observe the maximum permissible total load. The dimensions and positions of the installation options can be seen in the following diagram.

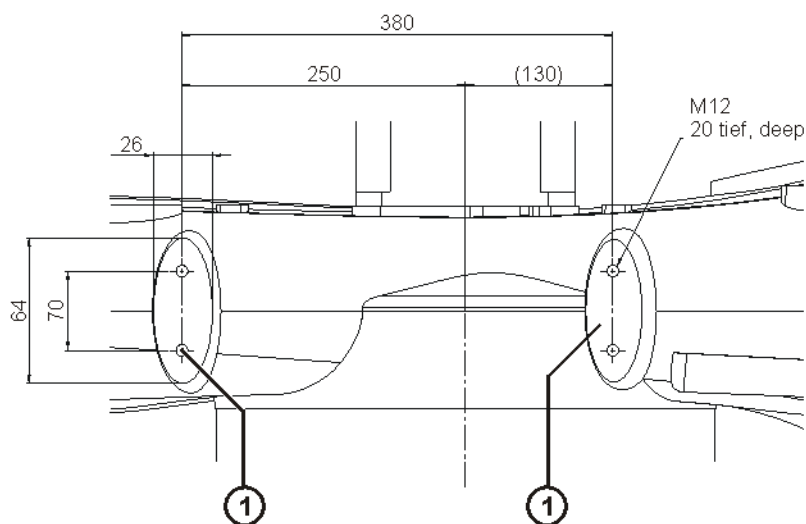


Fig. 4-14: Supplementary load on arm

1 Support bracket for supplementary load

Maße / Dimensions: mm

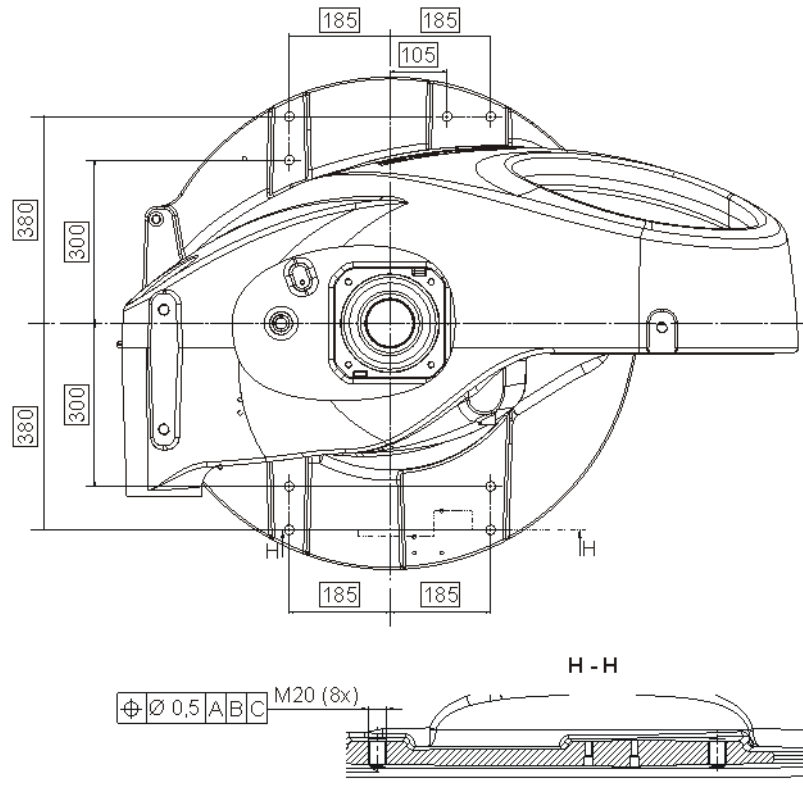


Fig. 4-15: Supplementary load on rotating column

Maße / Dimensions: mm

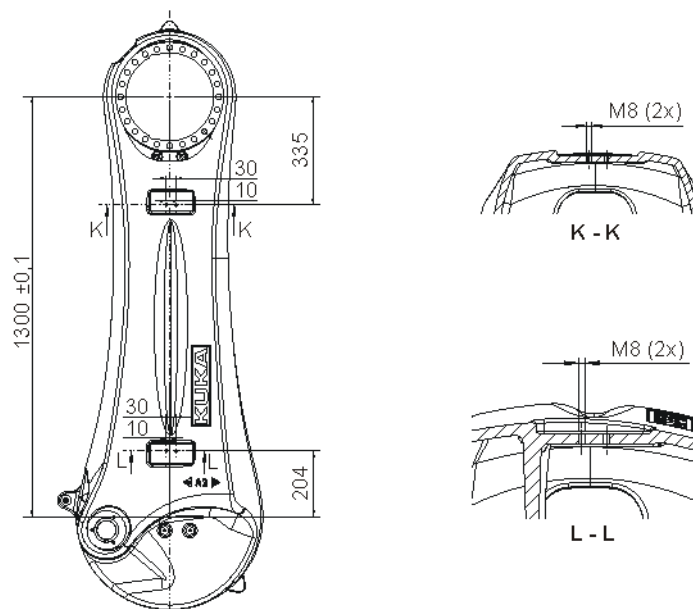


Fig. 4-16: Supplementary load, link arm

4.4 Foundation data

Foundation loads The specified forces and moments already include the payload and the inertia force (weight) of the robot.

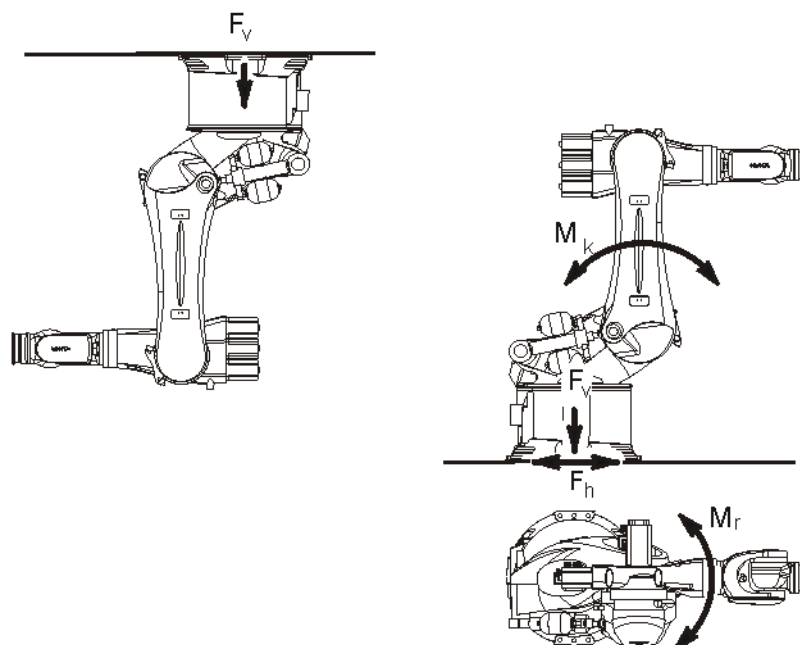


Fig. 4-17: Loads acting on the mounting base

**Foundation
loads, KR 360-3**

The following foundation loads are valid for the robots:

- KR 360-3 and KR 360-3 F
- KR 360 L240-3 and KR 360 L240-3 F
- KR 360 L280-3 and KR 360 L280-3 F

Type of load	Force/torque/mass
F_v = vertical force	$F_{vmax} = 40,500 \text{ N}$
F_h = horizontal force	$F_{hmax} = 23,500 \text{ N}$
M_k = tilting moment	$M_{kmax} = 84,500 \text{ Nm}$
M_r = torque	$M_{rmax} = 45,500 \text{ Nm}$
Total mass for load acting on the mounting base	KR 360-3: 3,235 kg KR 360-3 F: 3,235 kg KR 360 L240-3: 3,151 kg KR 360 L240-3 F: 3,151 kg KR 360 L280-3: 3,185 kg KR 360 L280-3 F: 3,185 kg

Type of load	Force/torque/mass
Robot	KR 360-3: 2,375 kg KR 360-3 F: 2,375 kg KR 360 L240-3: 2,411 kg KR 360 L240-3 F: 2,411 kg KR 360 L280-3: 2,405 kg KR 360 L280-3 F: 2,405 kg
Total load for foundation load	KR 360-3: 860 kg KR 360-3 F: 860 kg KR 360 L240-3: 740 kg KR 360 L240-3 F: 740 kg KR 360 L280-3: 780 kg KR 360 L280-3 F: 780 kg

Foundation loads, KR 500-3

The following foundation loads are valid for the robots:

- KR 500-3, KR 500-3 F and KR 500-3 C
- KR 500 L340-3 and KR 500 L340-3 F
- KR 500 L420-3, KR 500 L420-3 F and KR 500 L420-3 C

Type of load	Force/torque/mass
F_v = vertical force	$F_{vmax} = 40,500 \text{ N}$
F_h = horizontal force	$F_{hmax} = 23,500 \text{ N}$
M_k = tilting moment	$M_{kmax} = 84,500 \text{ Nm}$
M_r = torque	$M_{rmax} = 45,500 \text{ Nm}$
Total mass for load acting on the mounting base	KR 500-3: 3,375 kg KR 500-3 F: 3,375 kg KR 500-3 C: 3,375 kg KR 500 L340-3: 3,251 kg KR 500 L340-3 F: 3,251 kg KR 500 L420-3: 3,325 kg KR 500 L420-3 F: 3,325 kg KR 500 L420-3 C: 3,325 kg

Type of load	Force/torque/mass
Robot	KR 500-3: 2,375 kg KR 500-3 F: 2,375 kg KR 500-3 C: 2,375 kg KR 500 L340-3: 2,411 kg KR 500 L340-3 F: 2,411 kg KR 500 L420-3: 2,405 kg KR 500 L420-3 F: 2,405 kg KR 500 L420-3 C: 2,405 kg
Total load for foundation load	KR 500-3: 1,000 kg KR 500-3 F: 1,000 kg KR 500-3 C: 1,000 kg KR 500 L340-3: 840 kg KR 500 L340-3 F: 840 kg KR 500 L420-3: 920 kg KR 500 L420-3 F: 920 kg KR 500 L420-3 C: 920 kg

NOTICE

The mounting base loads specified in the table are the maximum loads that may occur. They must be referred to when dimensioning the mounting bases and must be adhered to for safety reasons.

The supplementary loads are not taken into consideration in the calculation of the foundation load. These supplementary loads must be taken into consideration for F_v .

Grade of concrete for foundations

When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. There must be no layers of insulation or screed between the bedplates and the concrete foundation. The quality of the concrete must meet the requirements of the following standard:

- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2008

4.5 Plates and labels**Plates and labels**

The following plates and labels are attached to the robot. They must not be removed or rendered illegible. Illegible plates and labels must be replaced.

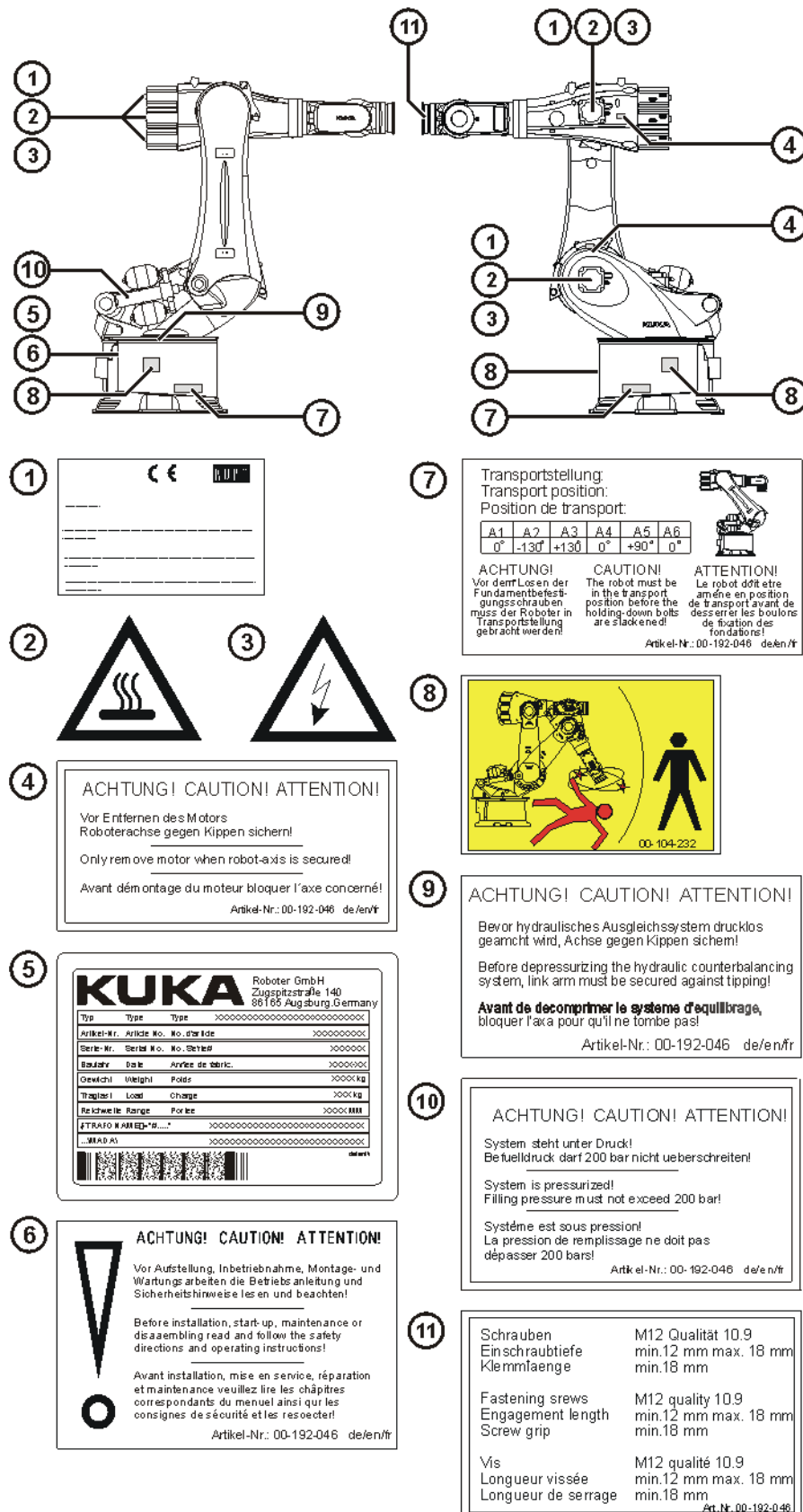


Fig. 4-18: Plates and labels

4.6 Stopping distances and times

4.6.1 General information

Information concerning the data:

- The stopping distance is the angle traveled by the robot from the moment the stop signal is triggered until the robot comes to a complete standstill.
- The stopping time is the time that elapses from the moment the stop signal is triggered until the robot comes to a complete standstill.
- The data are given for the main axes A1, A2 and A3. The main axes are the axes with the greatest deflection.
- Superposed axis motions can result in longer stopping distances.
- Stopping distances and stopping times in accordance with DIN EN ISO 10218-1, Annex B.
- Stop categories:
 - Stop category 0 » STOP 0
 - Stop category 1 » STOP 1
 according to IEC 60204-1
- The values specified for Stop 0 are guide values determined by means of tests and simulation. They are average values which conform to the requirements of DIN EN ISO 10218-1. The actual stopping distances and stopping times may differ due to internal and external influences on the braking torque. It is therefore advisable to determine the exact stopping distances and stopping times where necessary under the real conditions of the actual robot application.
- Measuring technique
The stopping distances were measured using the robot-internal measuring technique.
- The wear on the brakes varies depending on the operating mode, robot application and the number of STOP 0 triggered. It is therefore advisable to check the stopping distance at least once a year.

4.6.2 Terms used

Term	Description
m	Mass of the rated load and the supplementary load on the arm.
Phi	Angle of rotation (°) about the corresponding axis. This value can be entered in the controller via the KCP and is displayed on the KCP.
POV	Program override (%) = velocity of the robot motion. This value can be entered in the controller via the KCP and is displayed on the KCP.
Extension	Distance (l in %) (>>> Fig. 4-19) between axis 1 and the intersection of axes 4 and 5. With parallelogram robots, the distance between axis 1 and the intersection of axis 6 and the mounting flange.
KCP	The KCP teach pendant has all the operator control and display functions required for operating and programming the robot system.

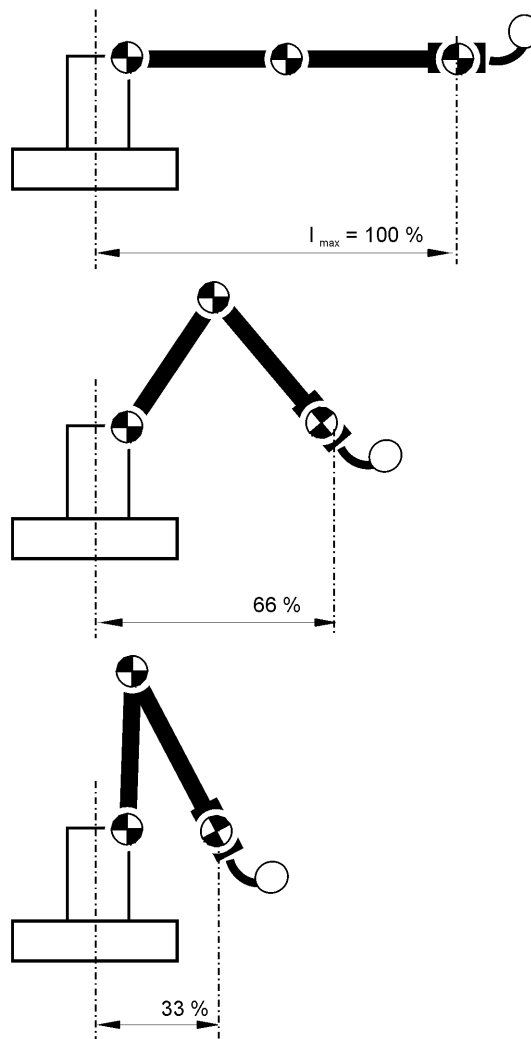


Fig. 4-19: Extension

4.6.3 Stopping distances and times, KR 360-3; KR 360-3 F

4.6.3.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension $l = 100\%$
- Program override POV = 100%
- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	57.64	1.03
Axis 2	44.11	0.789
Axis 3	24.57	0.379

4.6.3.2 Stopping distances and stopping times for STOP 1, axis 1

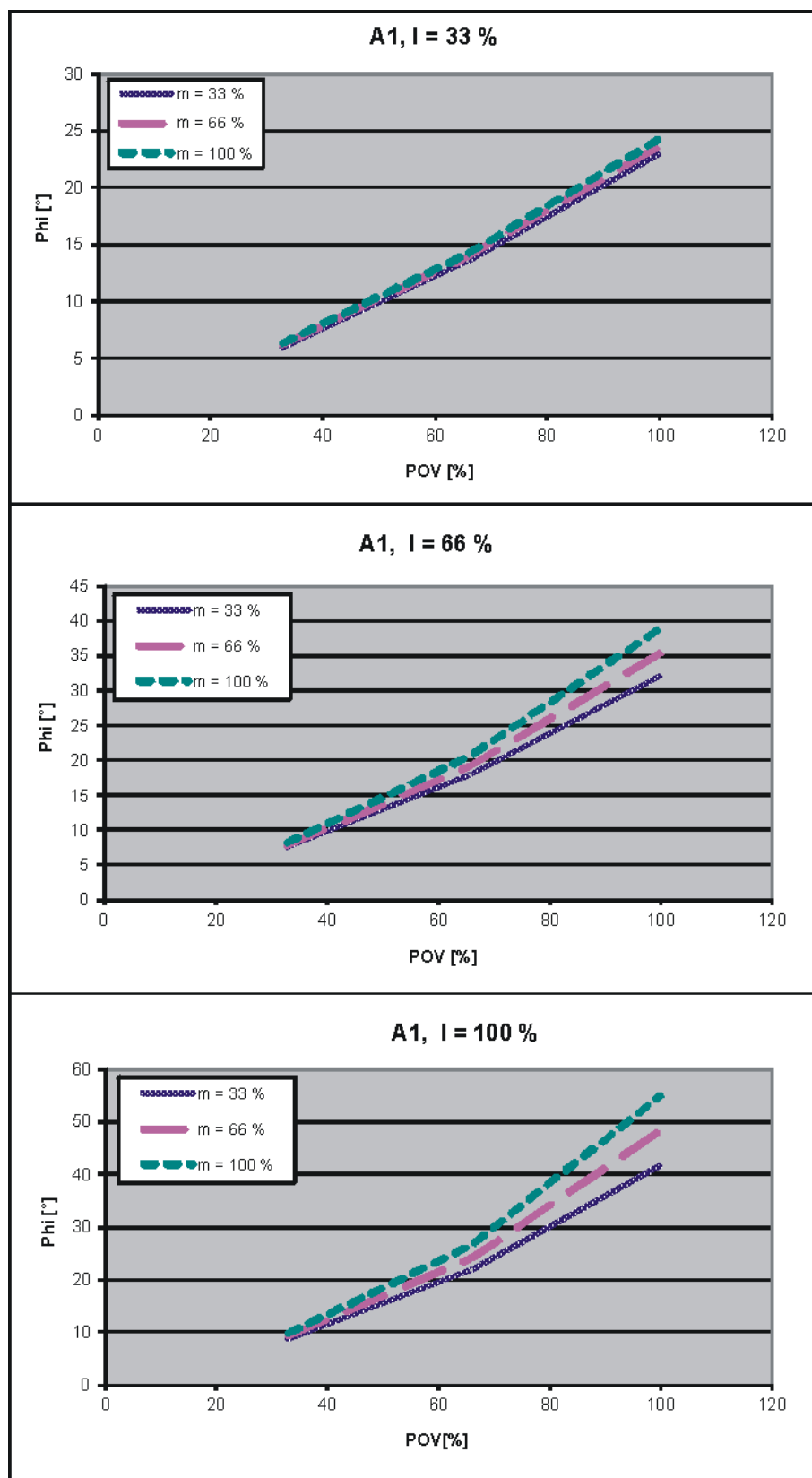


Fig. 4-20: Stopping distances for STOP 1, axis 1

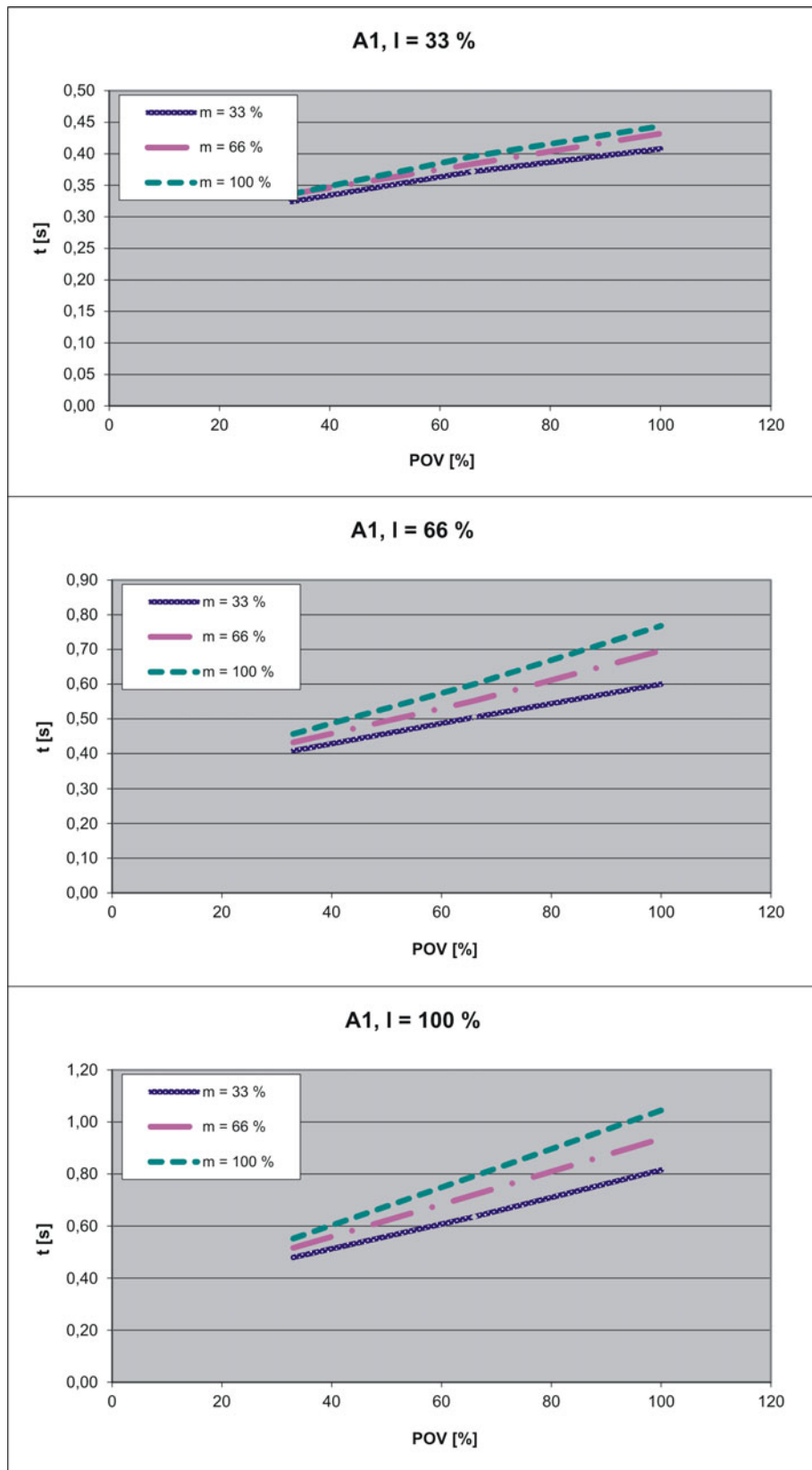


Fig. 4-21: Stopping times for STOP 1, axis 1

4.6.3.3 Stopping distances and stopping times for STOP 1, axis 2

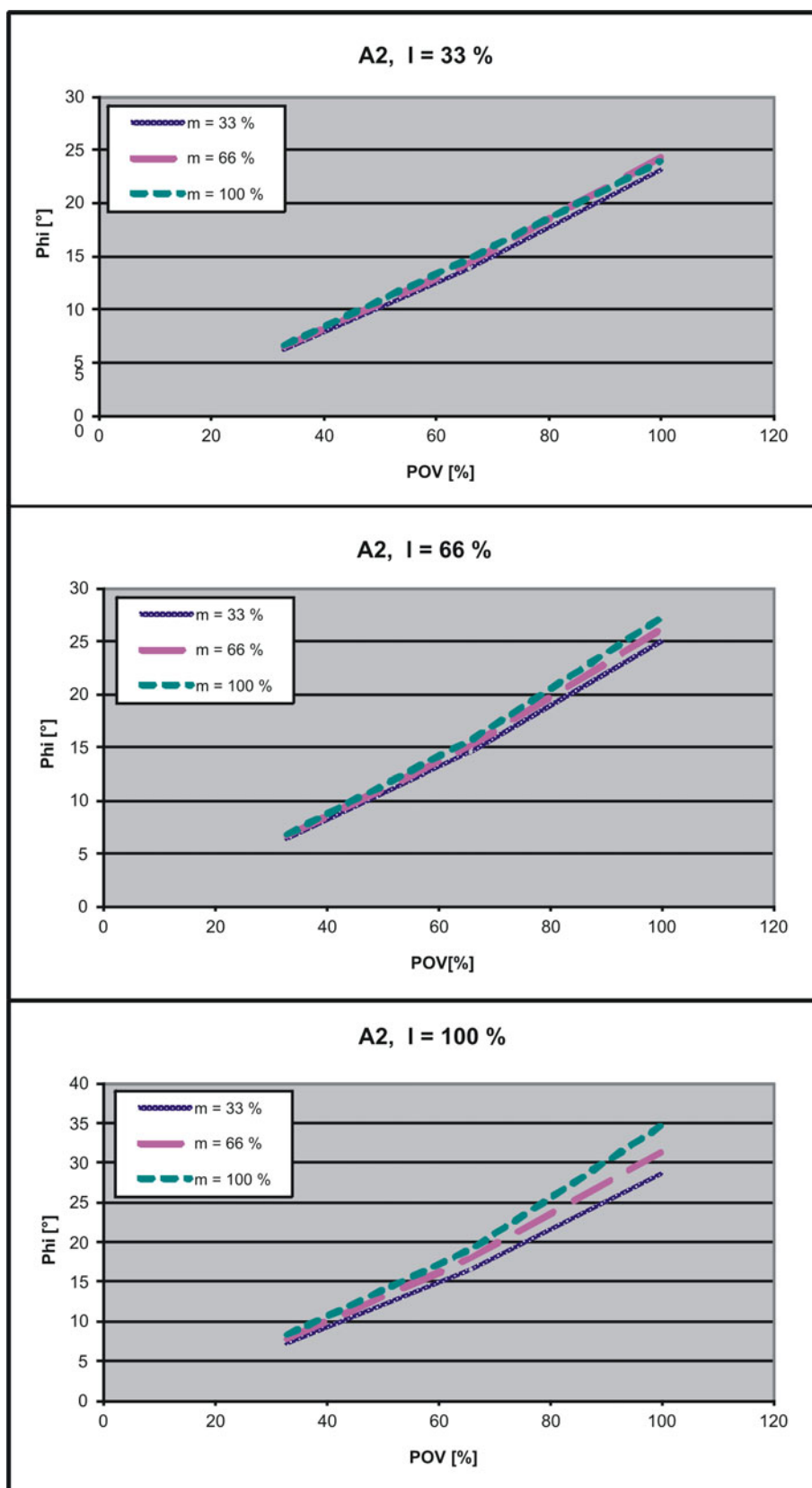


Fig. 4-22: Stopping distances for STOP 1, axis 2

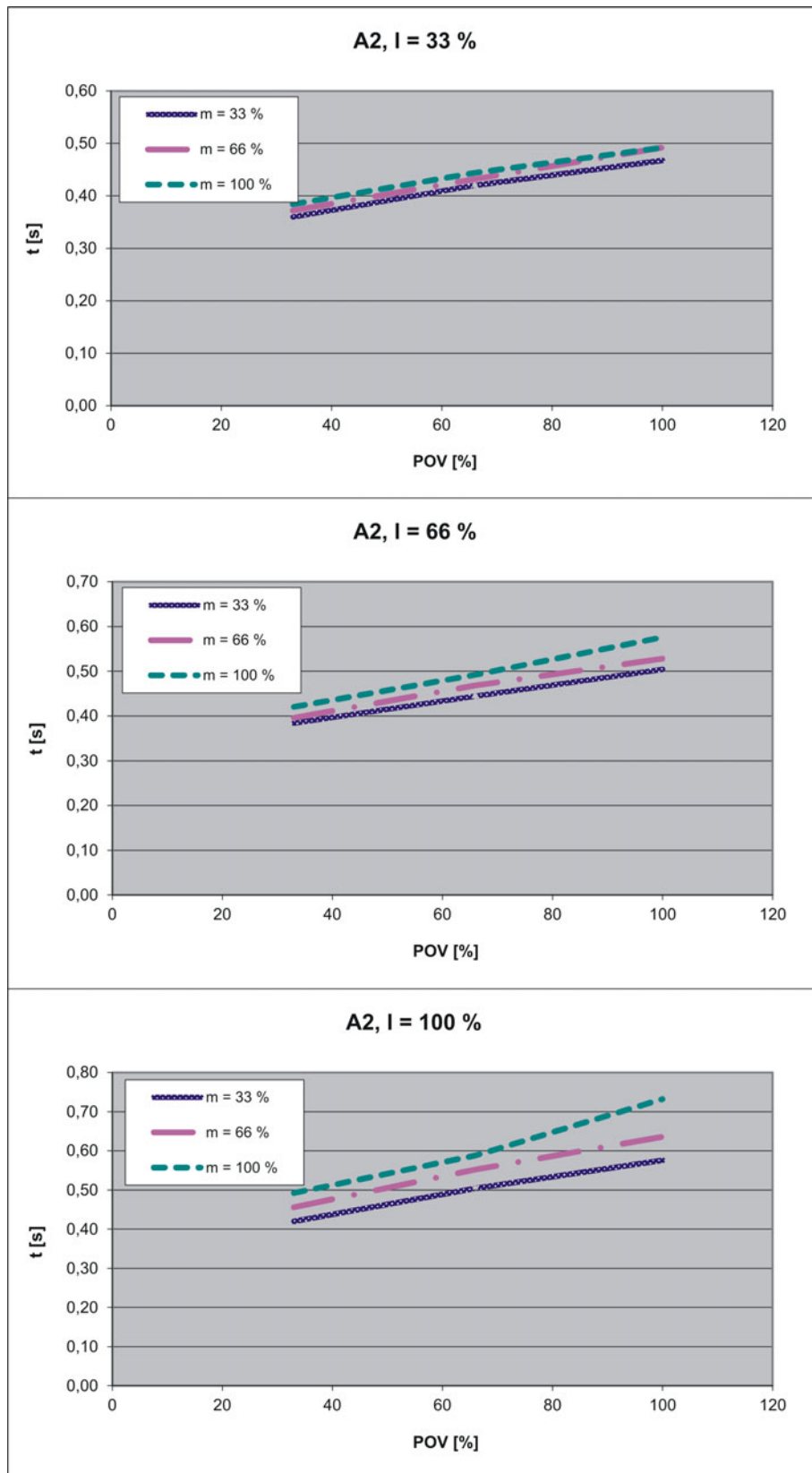


Fig. 4-23: Stopping times for STOP 1, axis 2

4.6.3.4 Stopping distances and stopping times for STOP 1, axis 3

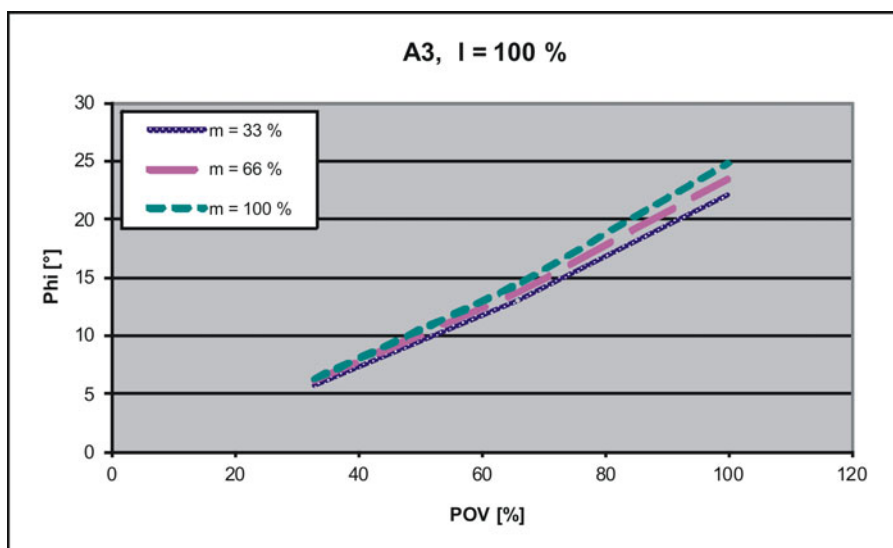


Fig. 4-24: Stopping distances for STOP 1, axis 3

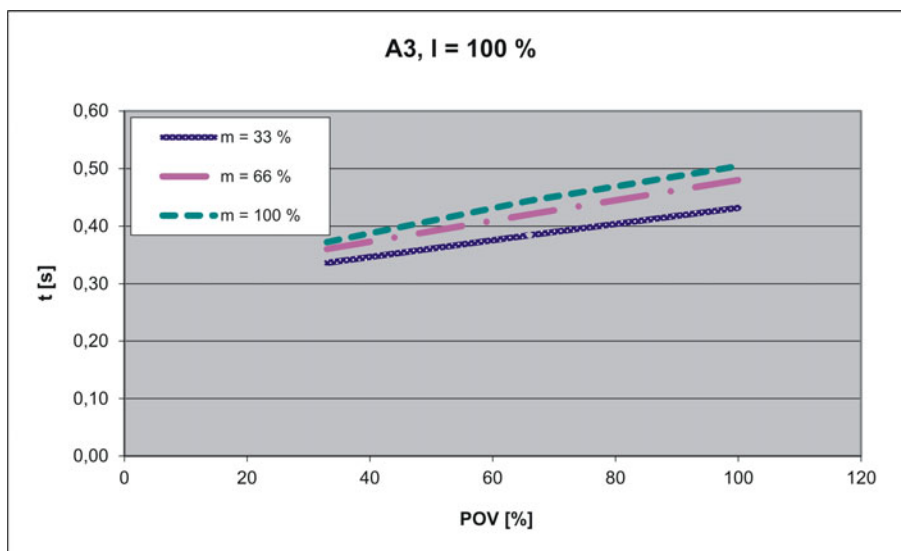


Fig. 4-25: Stopping times for STOP 1, axis 3

4.6.4 Stopping distances and times, KR 360 L240-3, KR 360 L240-3 F

4.6.4.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension I = 100%
- Program override POV = 100%
- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	58.81	1.056
Axis 2	43.91	0.799
Axis 3	26.73	0.425

4.6.4.2 Stopping distances and stopping times for STOP 1, axis 1

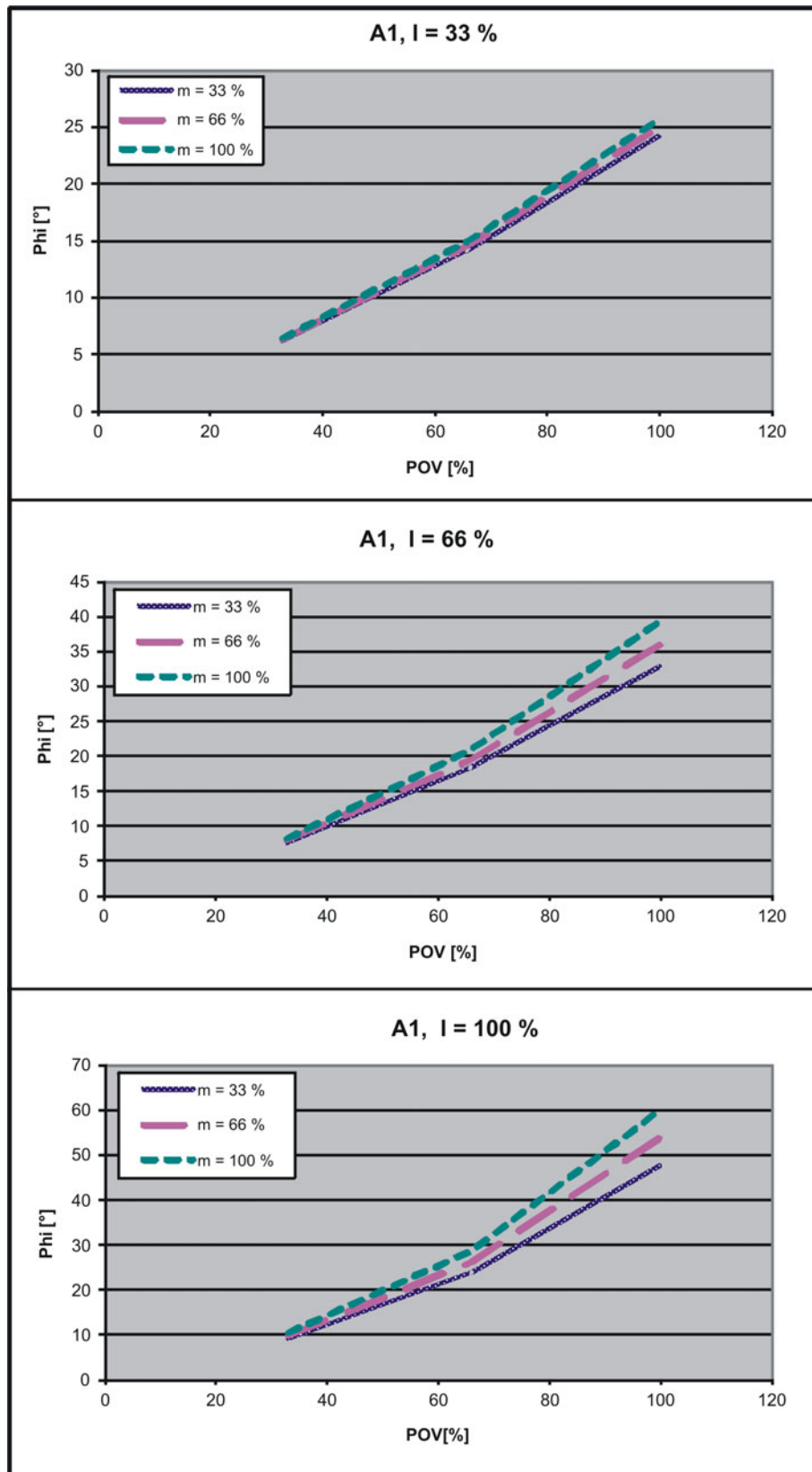


Fig. 4-26: Stopping distances for STOP 1, axis 1

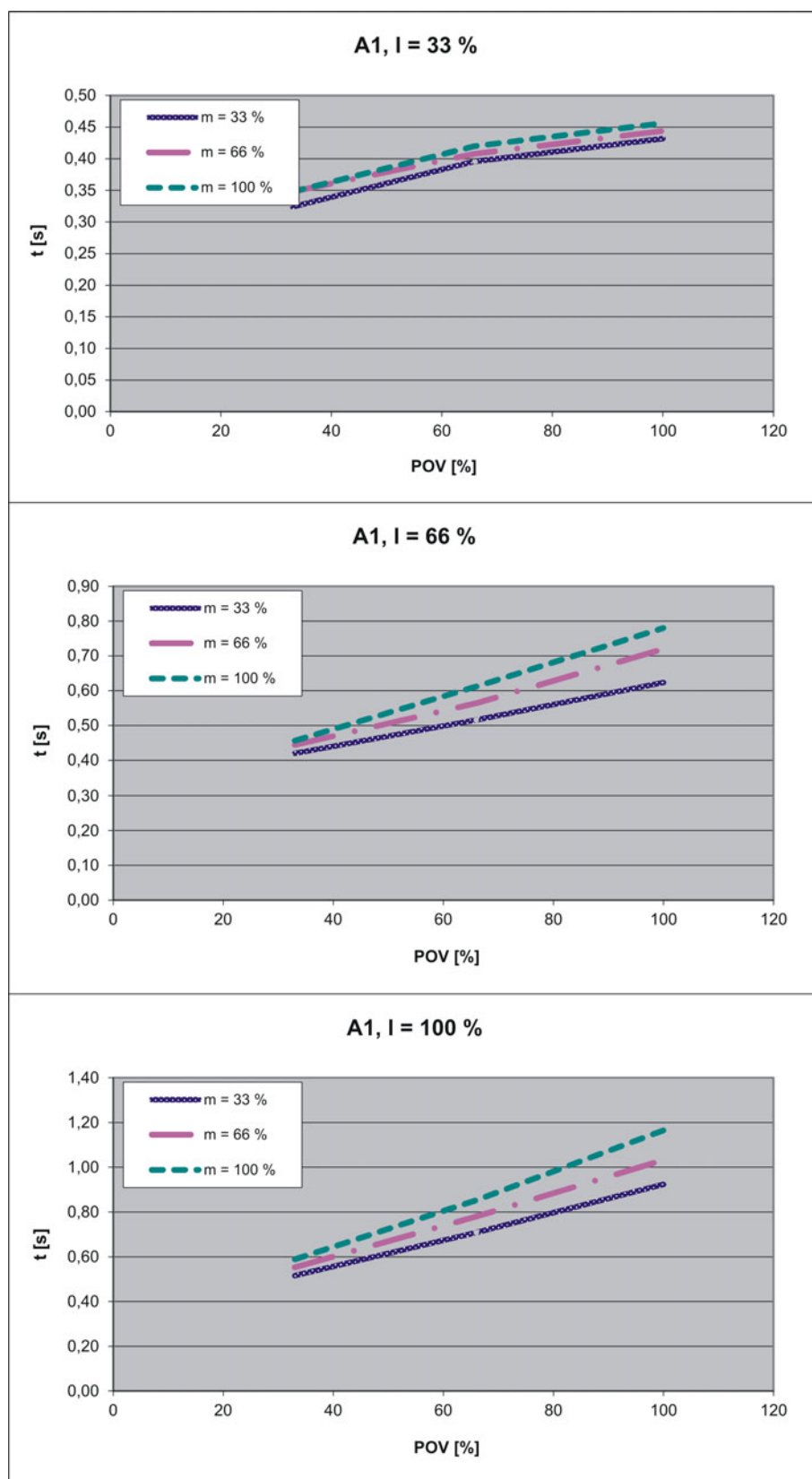


Fig. 4-27: Stopping times for STOP 1, axis 1

4.6.4.3 Stopping distances and stopping times for STOP 1, axis 2

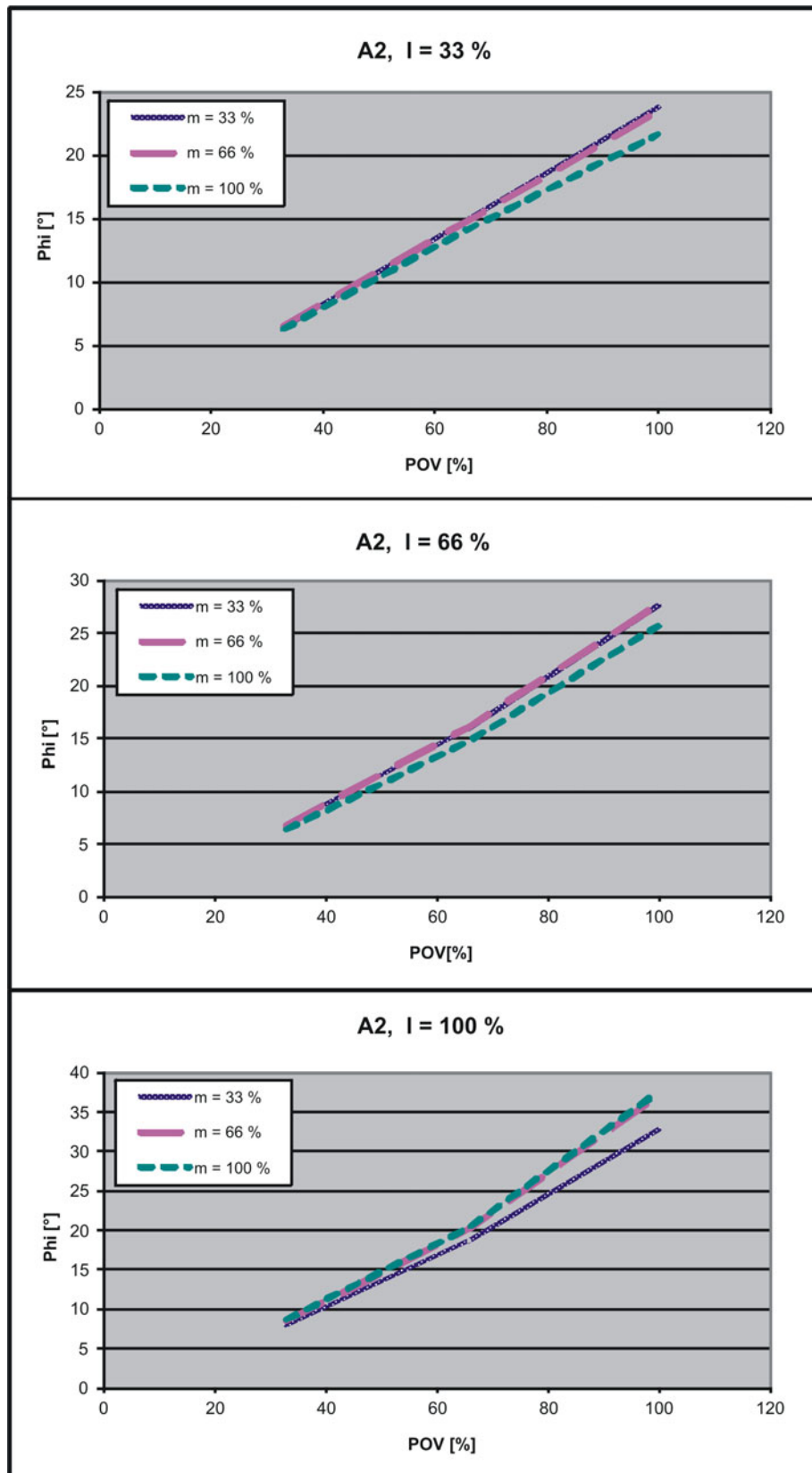


Fig. 4-28: Stopping distances for STOP 1, axis 2

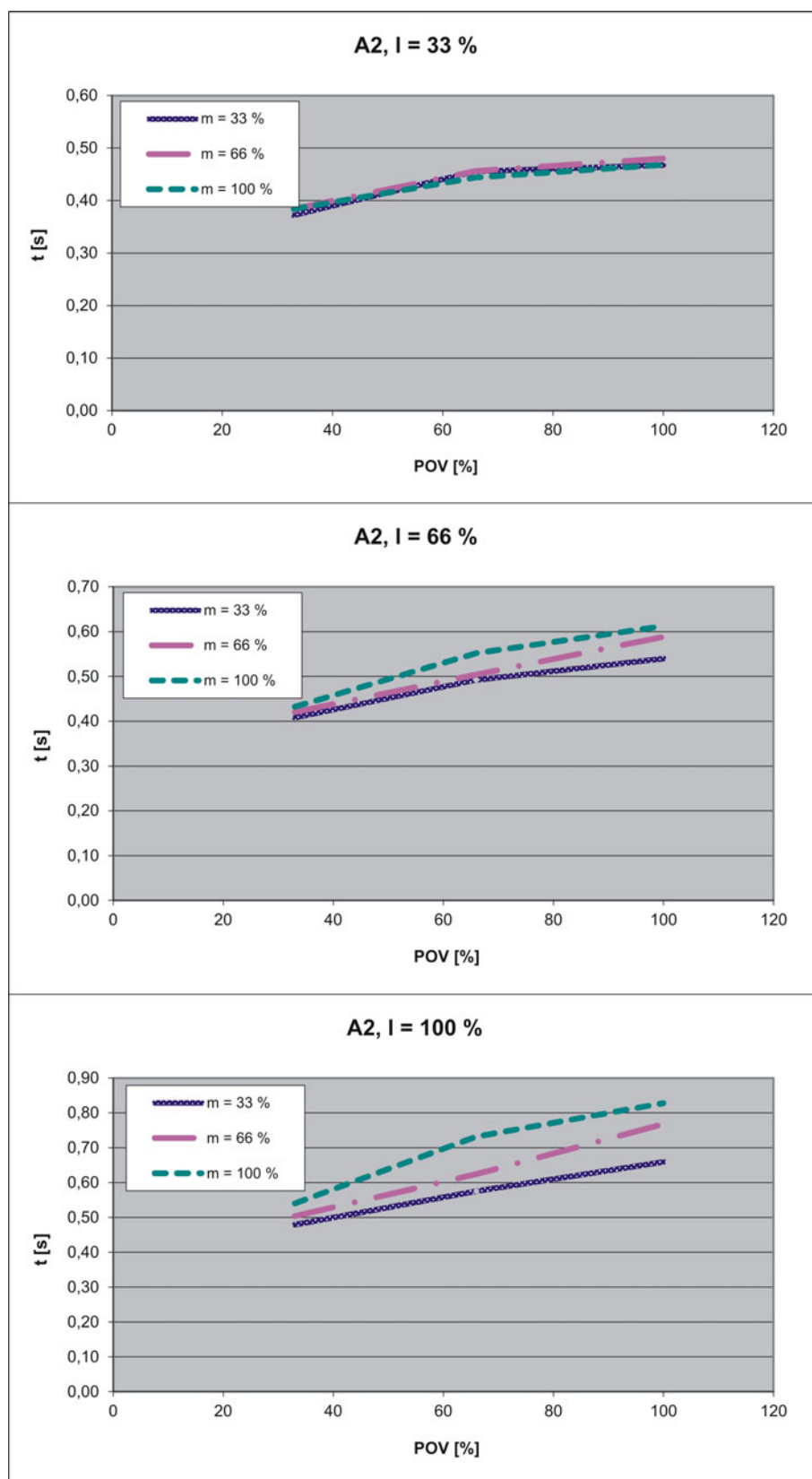


Fig. 4-29: Stopping times for STOP 1, axis 2

4.6.4.4 Stopping distances and stopping times for STOP 1, axis 3

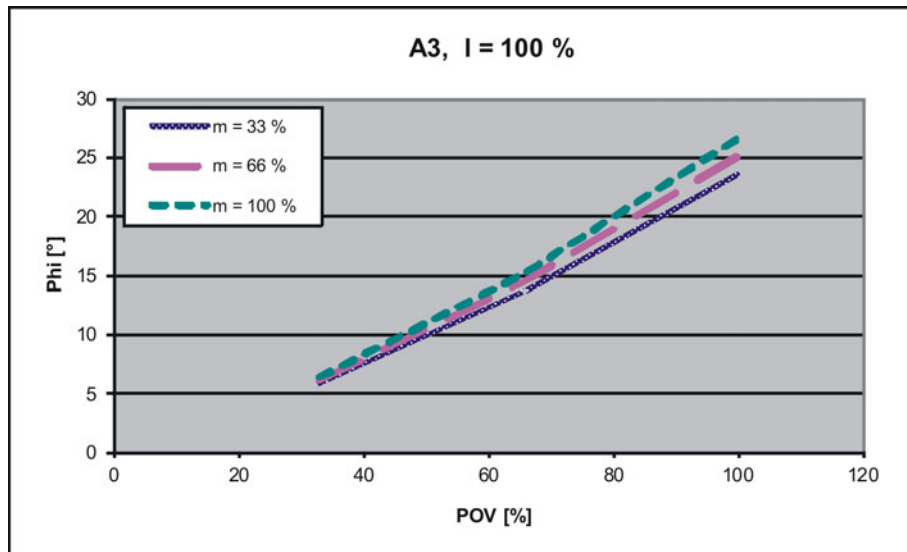


Fig. 4-30: Stopping distances for STOP 1, axis 3

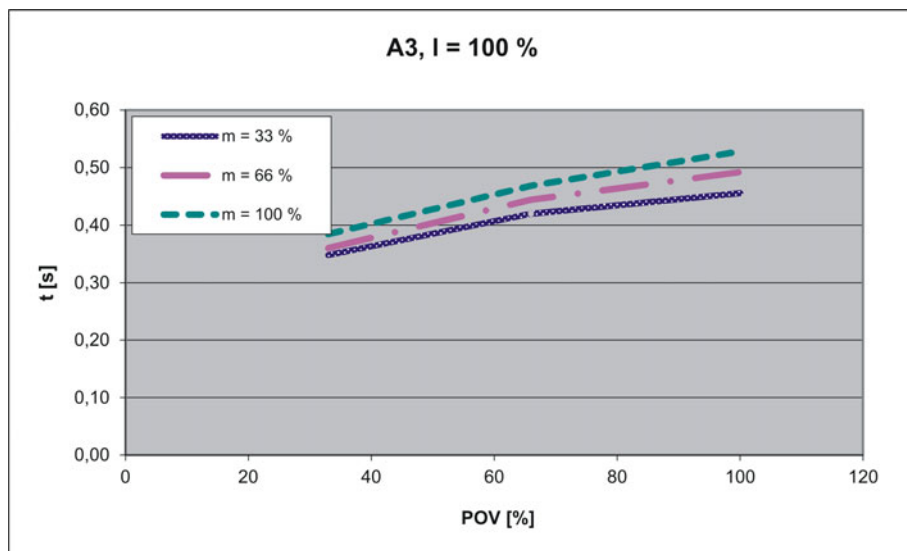


Fig. 4-31: Stopping times for STOP 1, axis 3

4.6.5 Stopping distances and times, KR 360 L280-3, KR 360 L280-3 F

4.6.5.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension $l = 100\%$
- Program override $POV = 100\%$
- Mass $m = \text{maximum load (rated load + supplementary load on arm)}$

	Stopping distance (°)	Stopping time (s)
Axis 1	57.73	1.032
Axis 2	43.06	0.777
Axis 3	25.50	0.398

4.6.5.2 Stopping distances and stopping times for STOP 1, axis 1

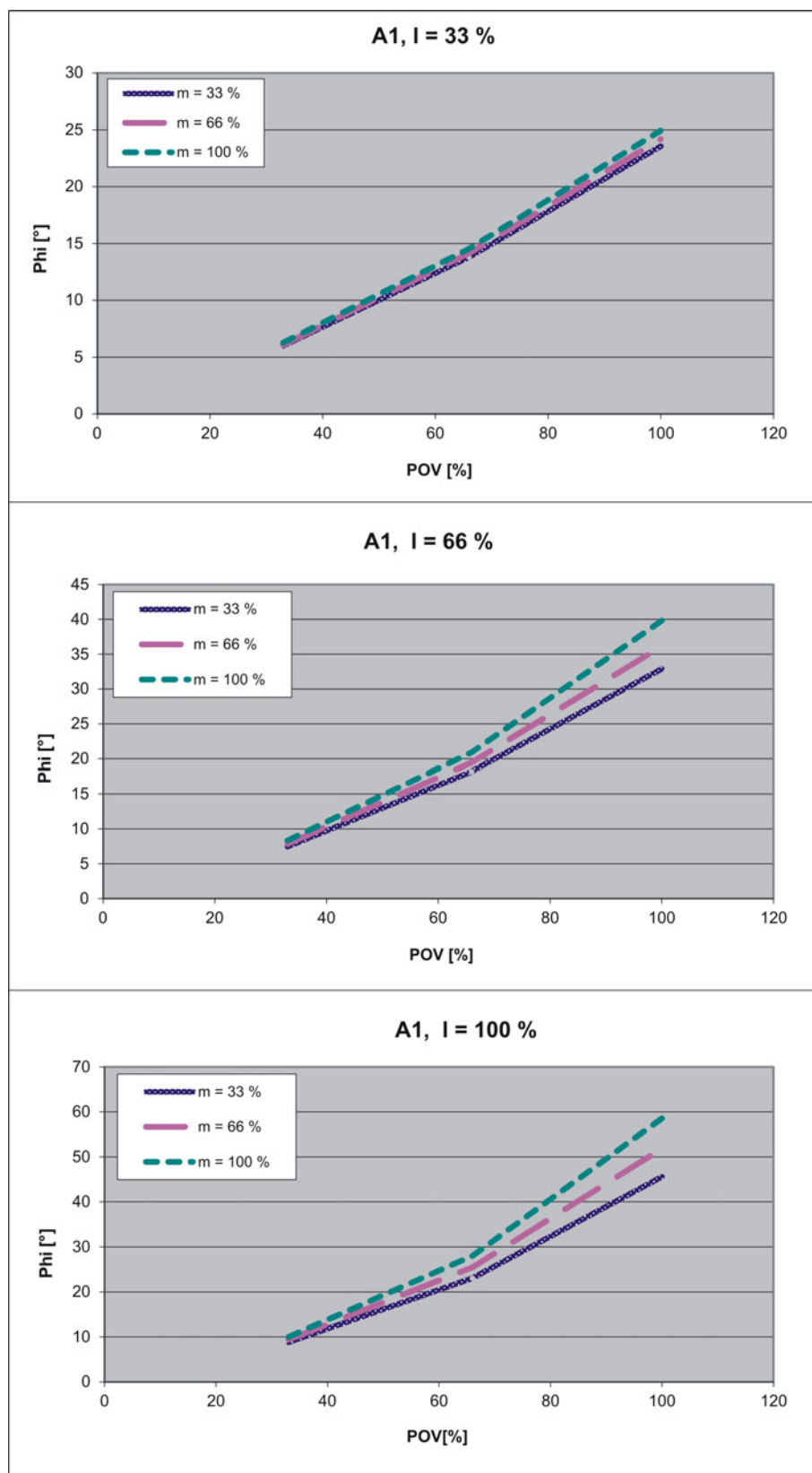


Fig. 4-32: Stopping distances for STOP 1, axis 1

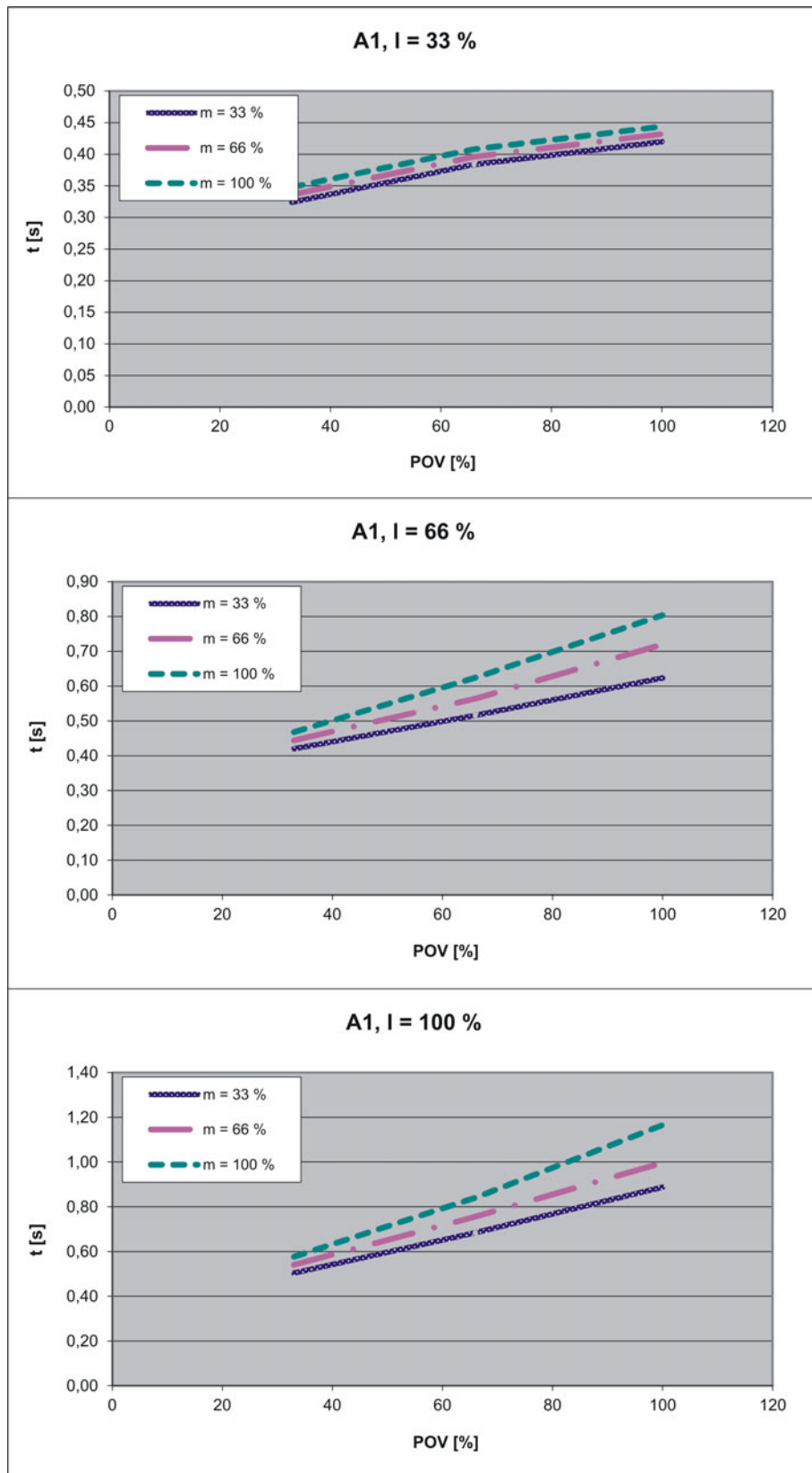


Fig. 4-33: Stopping times for STOP 1, axis 1

4.6.5.3 Stopping distances and stopping times for STOP 1, axis 2

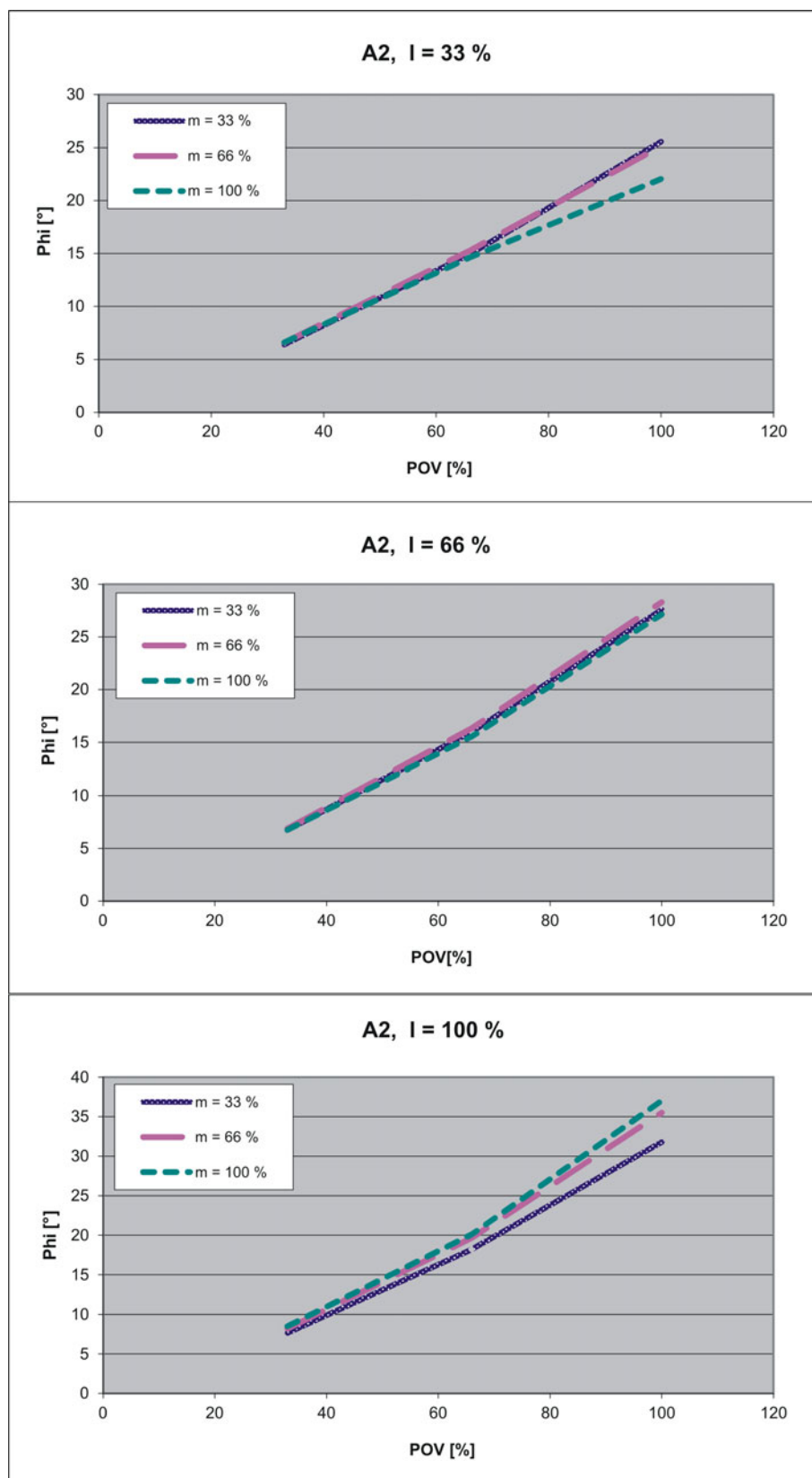


Fig. 4-34: Stopping distances for STOP 1, axis 2

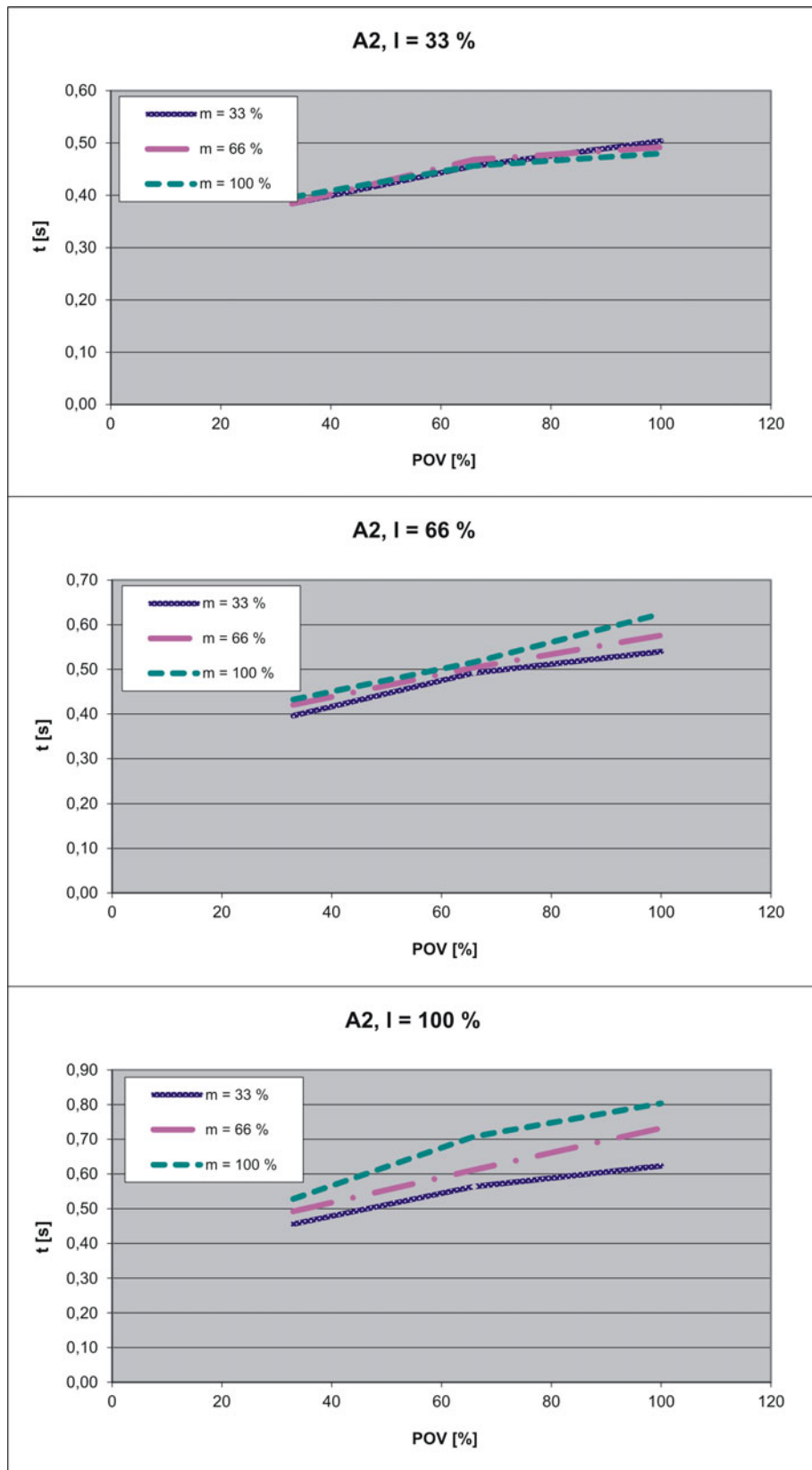


Fig. 4-35: Stopping times for STOP 1, axis 2

4.6.5.4 Stopping distances and stopping times for STOP 1, axis 3

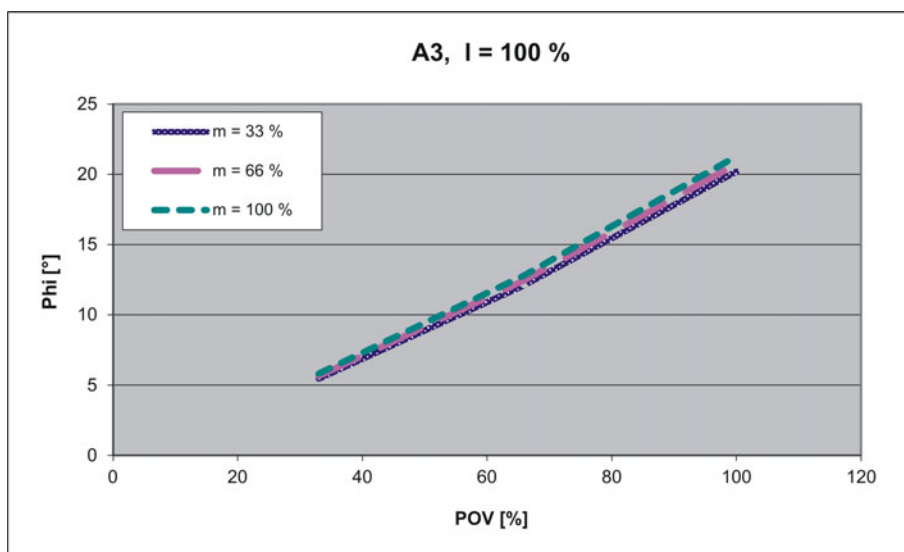


Fig. 4-36: Stopping distances for STOP 1, axis 3

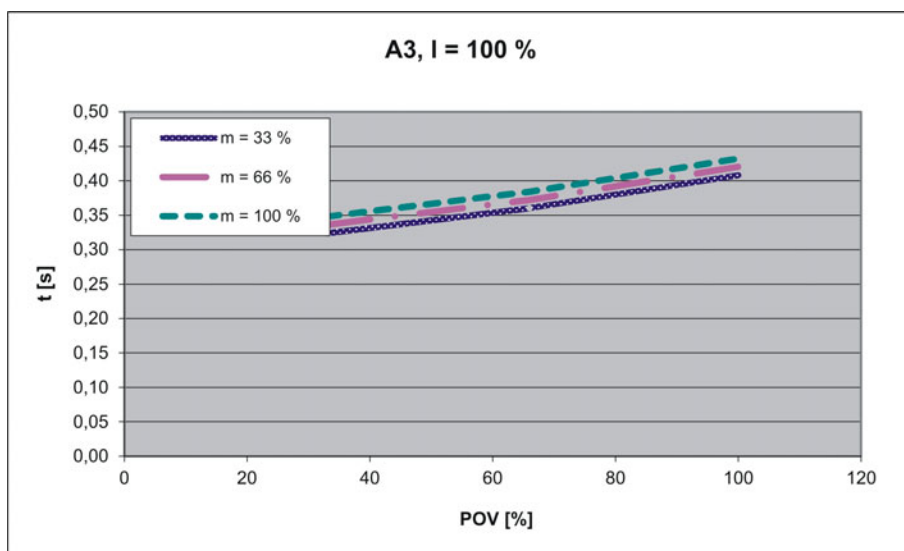


Fig. 4-37: Stopping times for STOP 1, axis 3

4.6.6 Stopping distances and times, KR 500-3, KR 500-3 F, KR 500-3 C

4.6.6.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension $I = 100\%$
- Program override $POV = 100\%$
- Mass $m =$ maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	23.79	0.692
Axis 2	30.94	0.666
Axis 3	19.40	0.362

4.6.6.2 Stopping distances and stopping times for STOP 1, axis 1

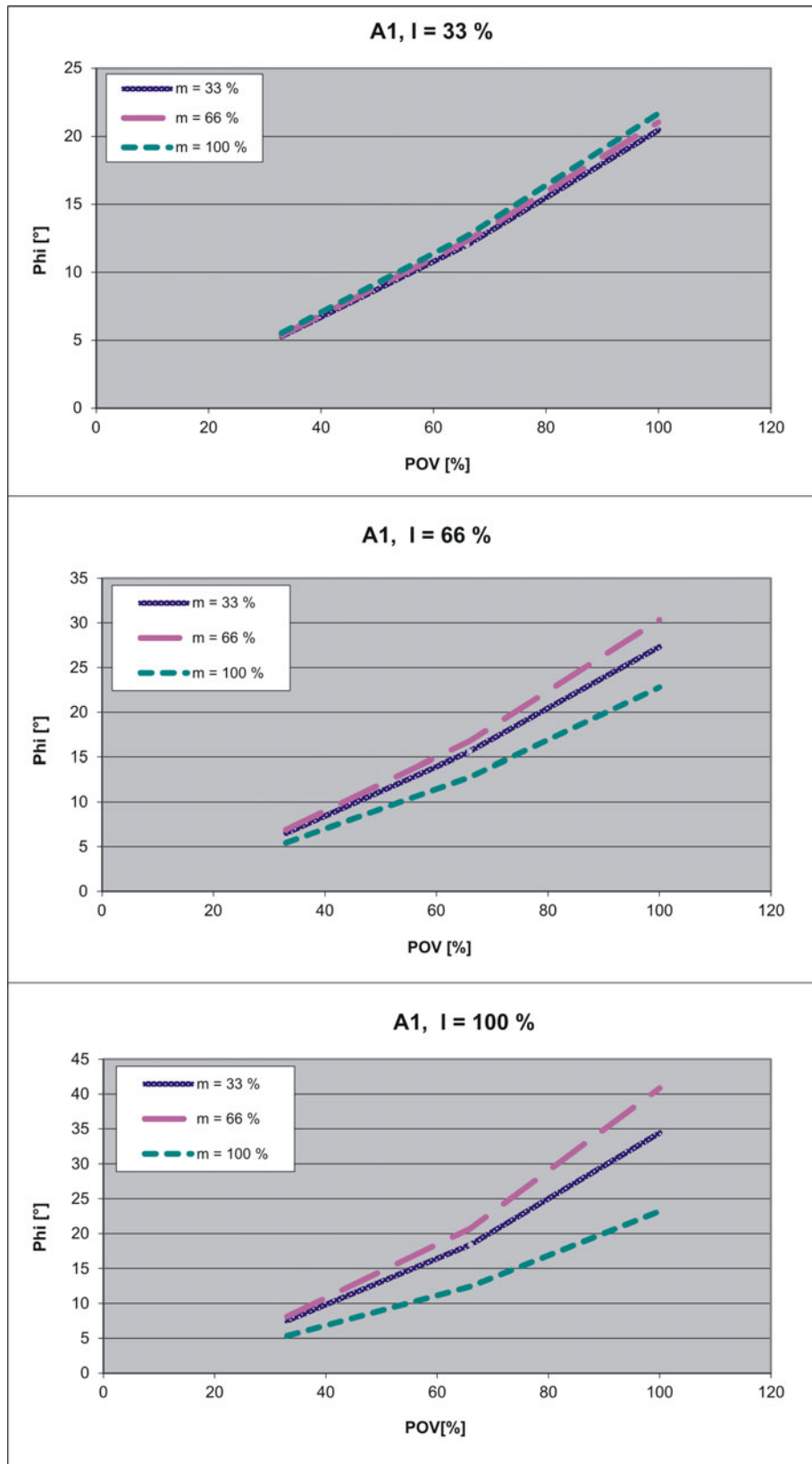


Fig. 4-38: Stopping distances for STOP 1, axis 1

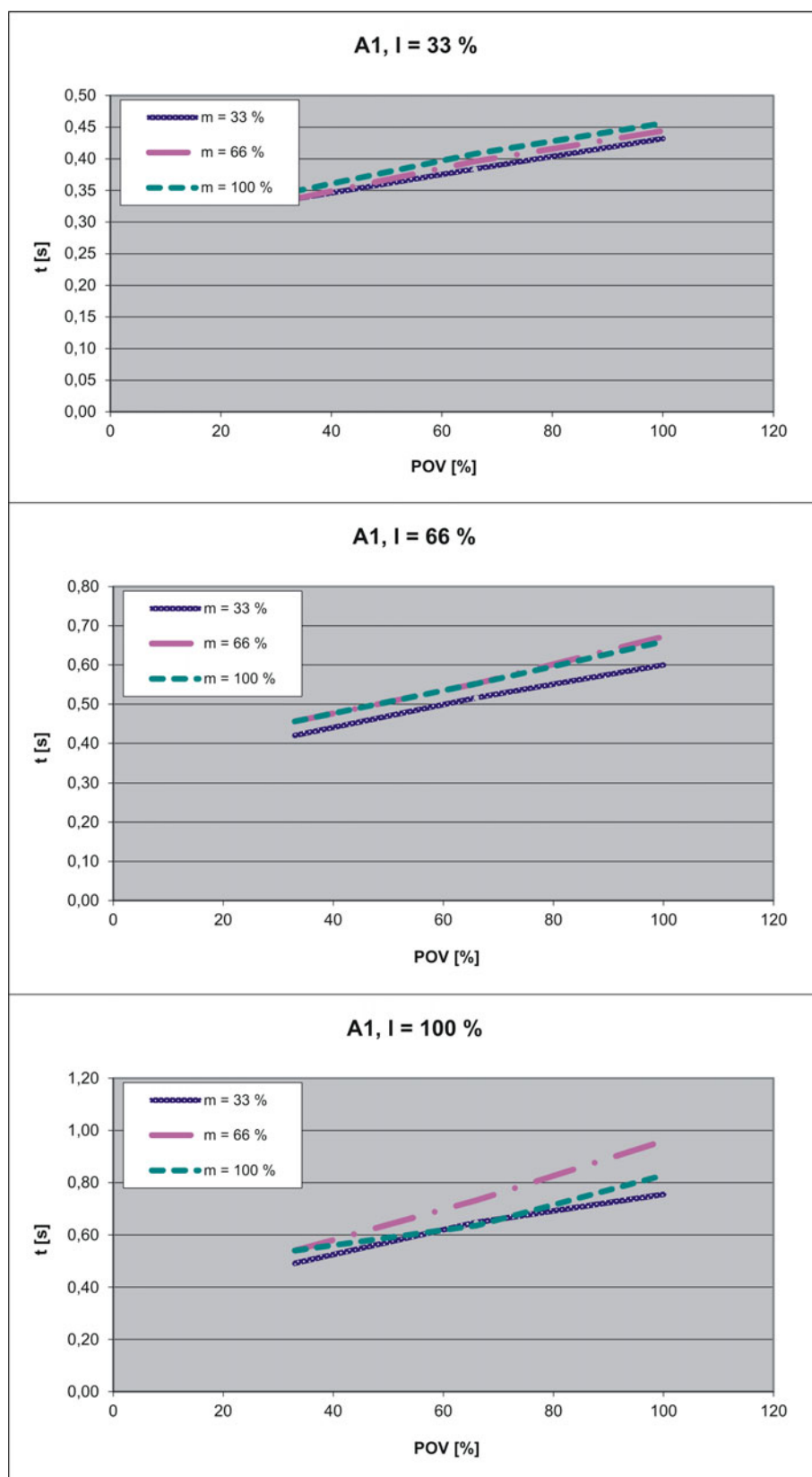


Fig. 4-39: Stopping times for STOP 1, axis 1

4.6.6.3 Stopping distances and stopping times for STOP 1, axis 2

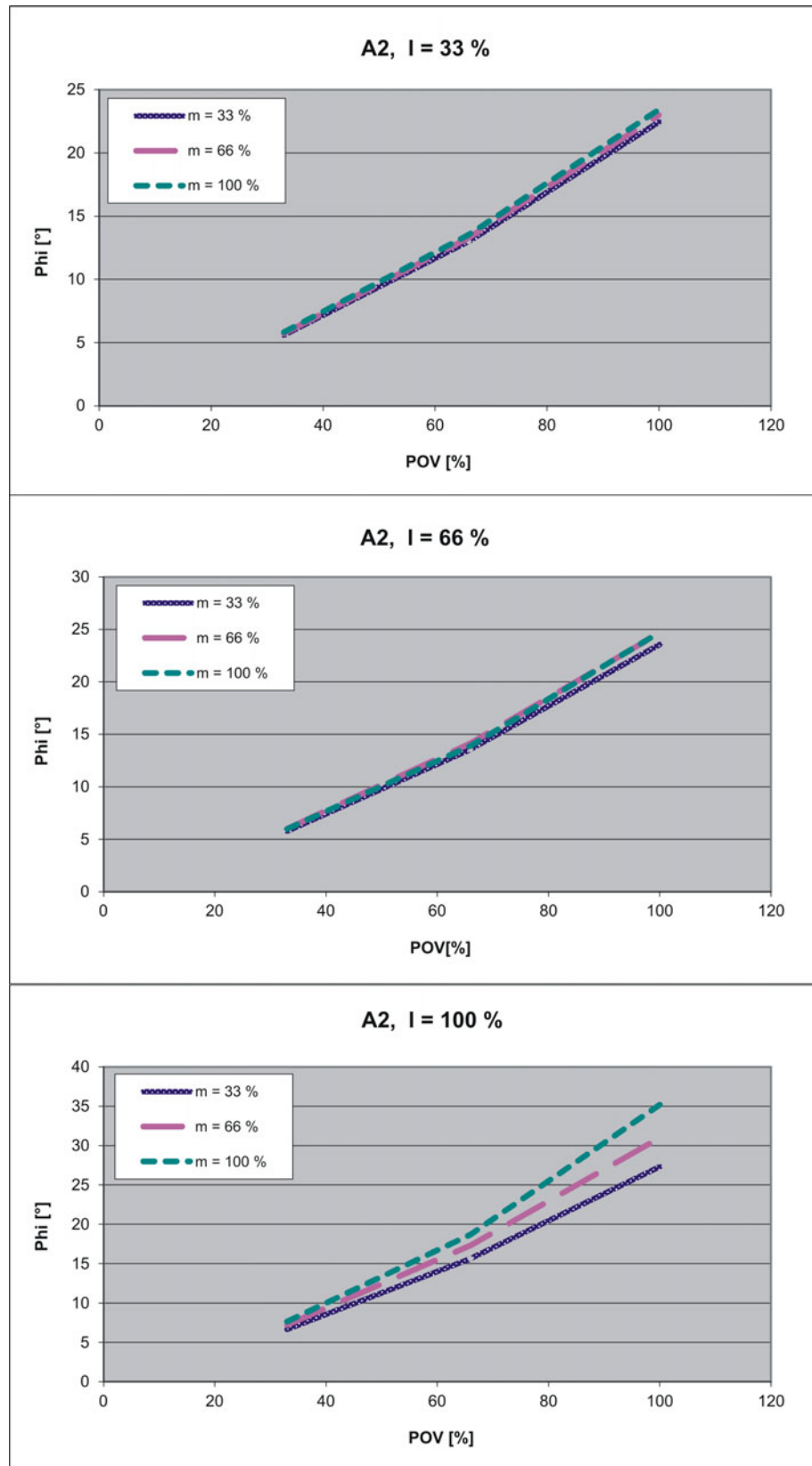


Fig. 4-40: Stopping distances for STOP 1, axis 2

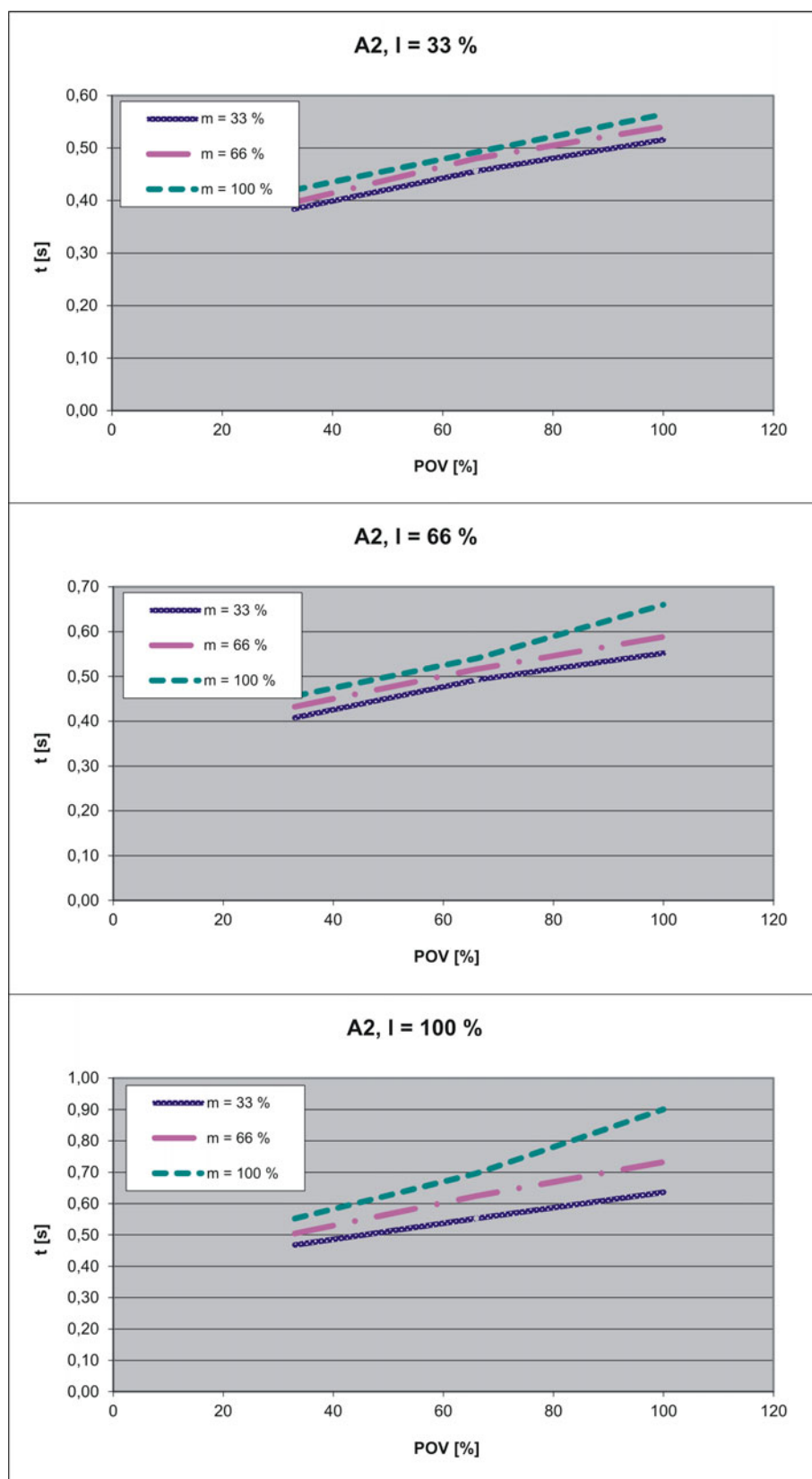


Fig. 4-41: Stopping times for STOP 1, axis 2

4.6.6.4 Stopping distances and stopping times for STOP 1, axis 3

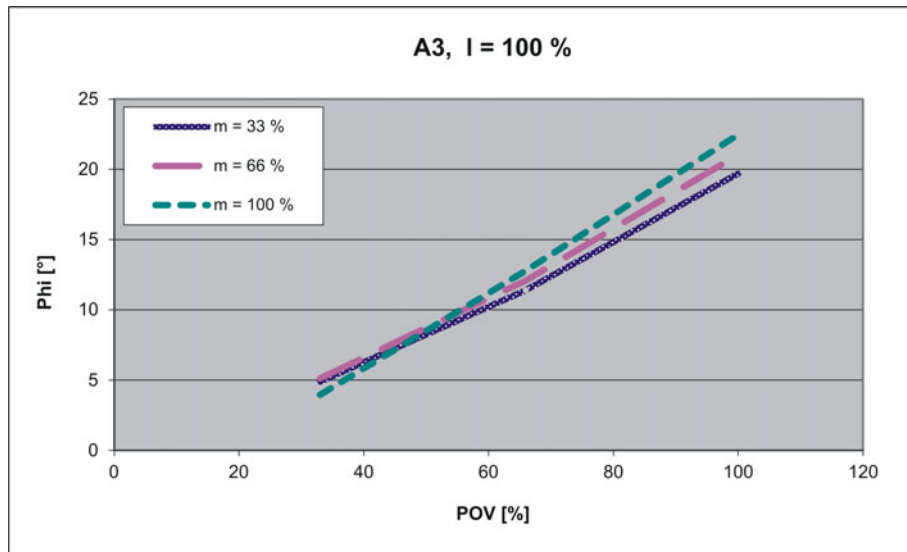


Fig. 4-42: Stopping distances for STOP 1, axis 3

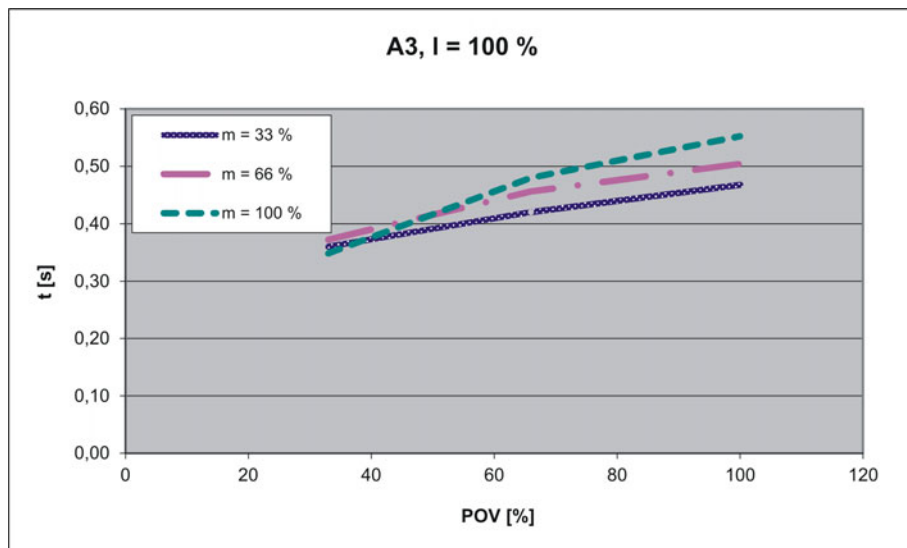


Fig. 4-43: Stopping times for STOP 1, axis 3

4.6.7 Stopping distances and times, KR 500 L340-3, KR 500 L340-3 F

4.6.7.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension I = 100%
- Program override POV = 100%
- Mass m = maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	47.67	0.97
Axis 2	36.34	0.785
Axis 3	20.98	0.401

4.6.7.2 Stopping distances and stopping times for STOP 1, axis 1

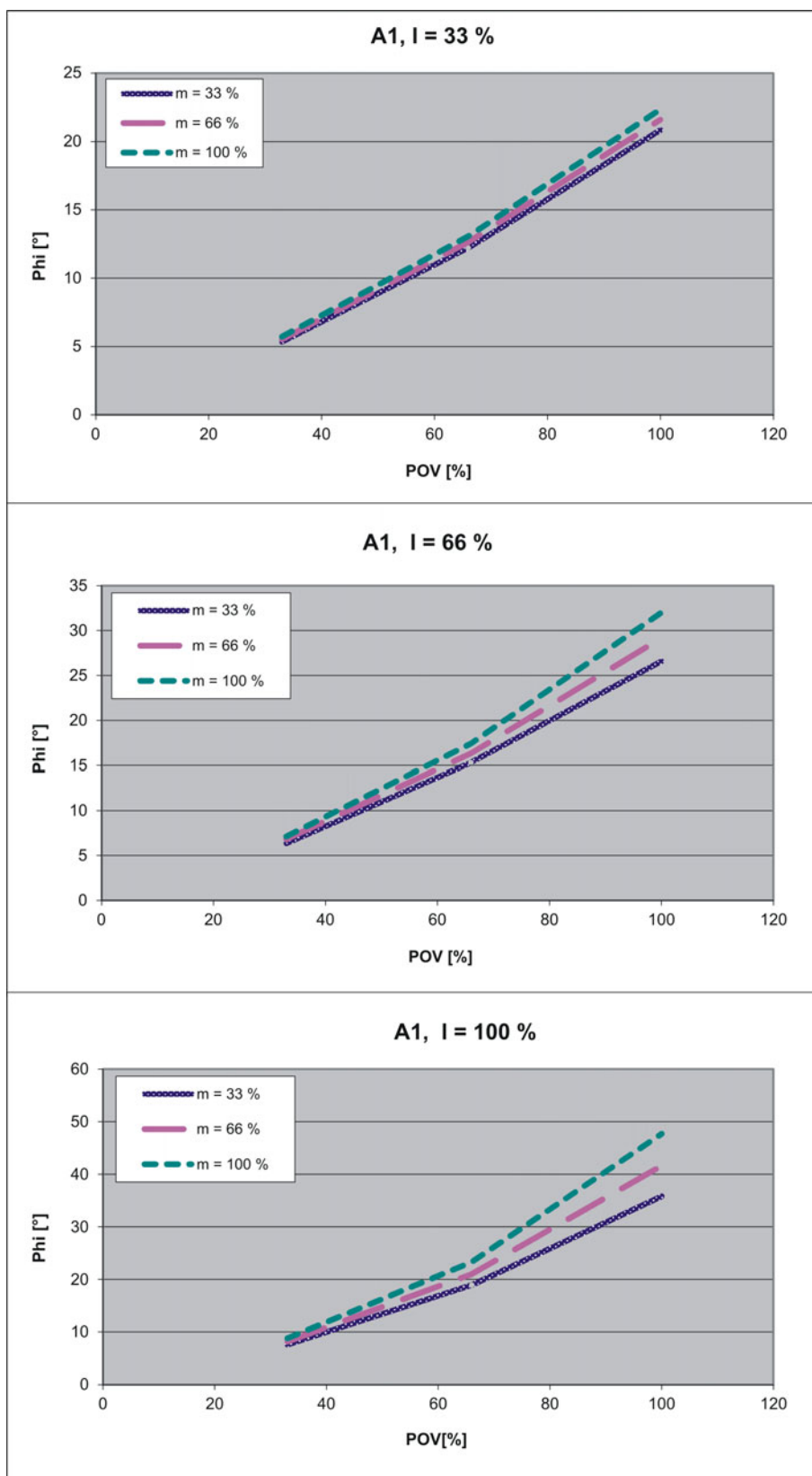


Fig. 4-44: Stopping distances for STOP 1, axis 1

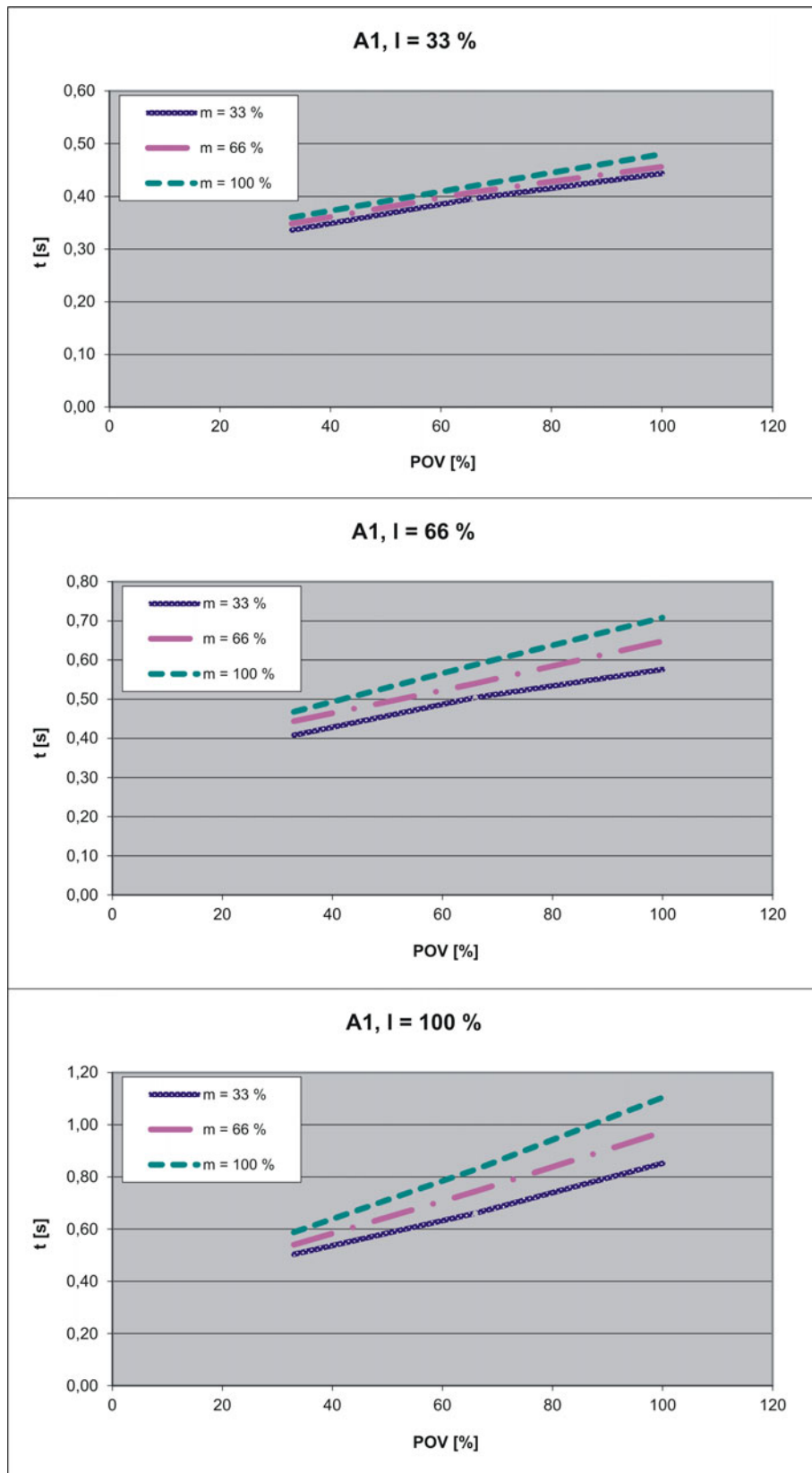


Fig. 4-45: Stopping times for STOP 1, axis 1

4.6.7.3 Stopping distances and stopping times for STOP 1, axis 2

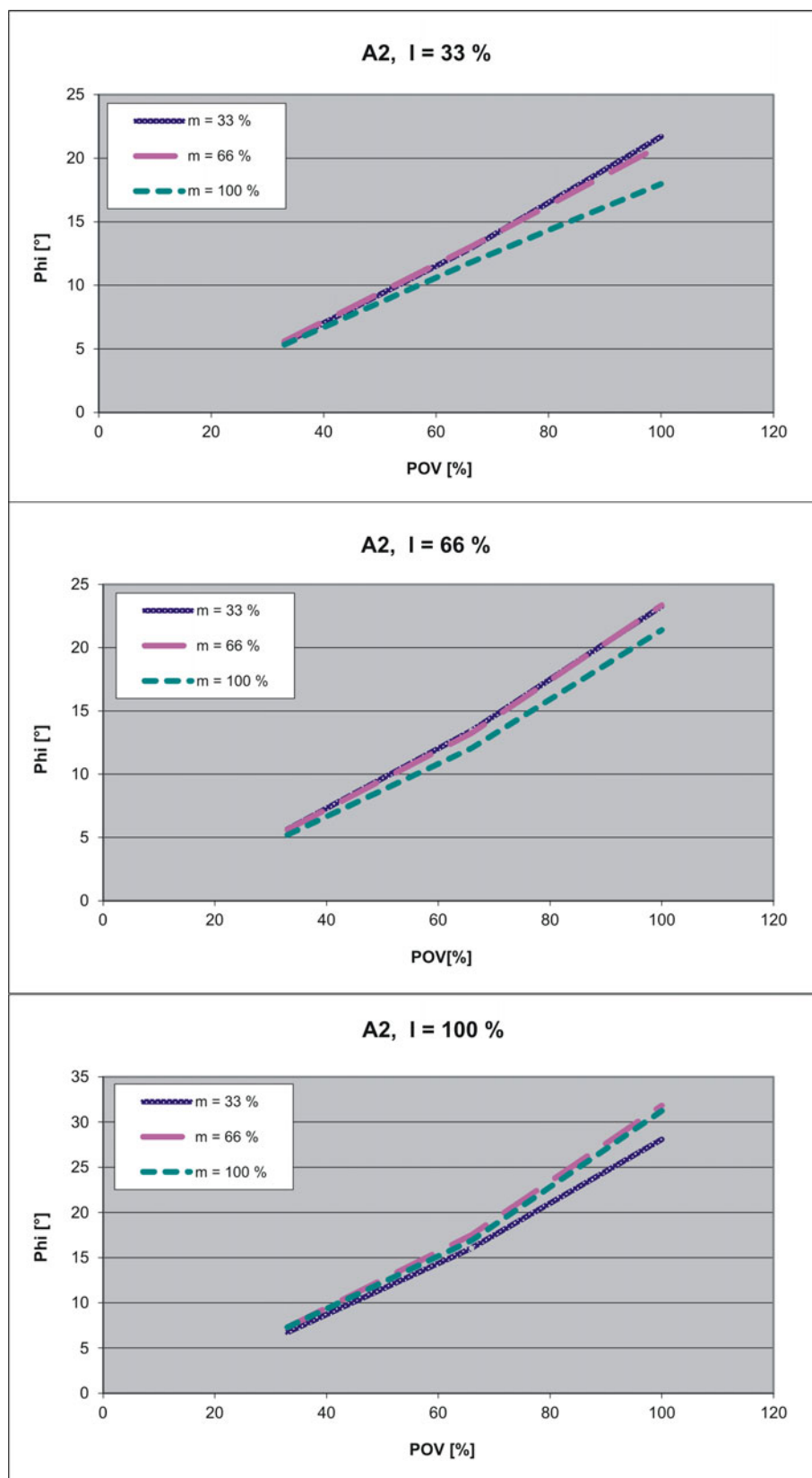


Fig. 4-46: Stopping distances for STOP 1, axis 2

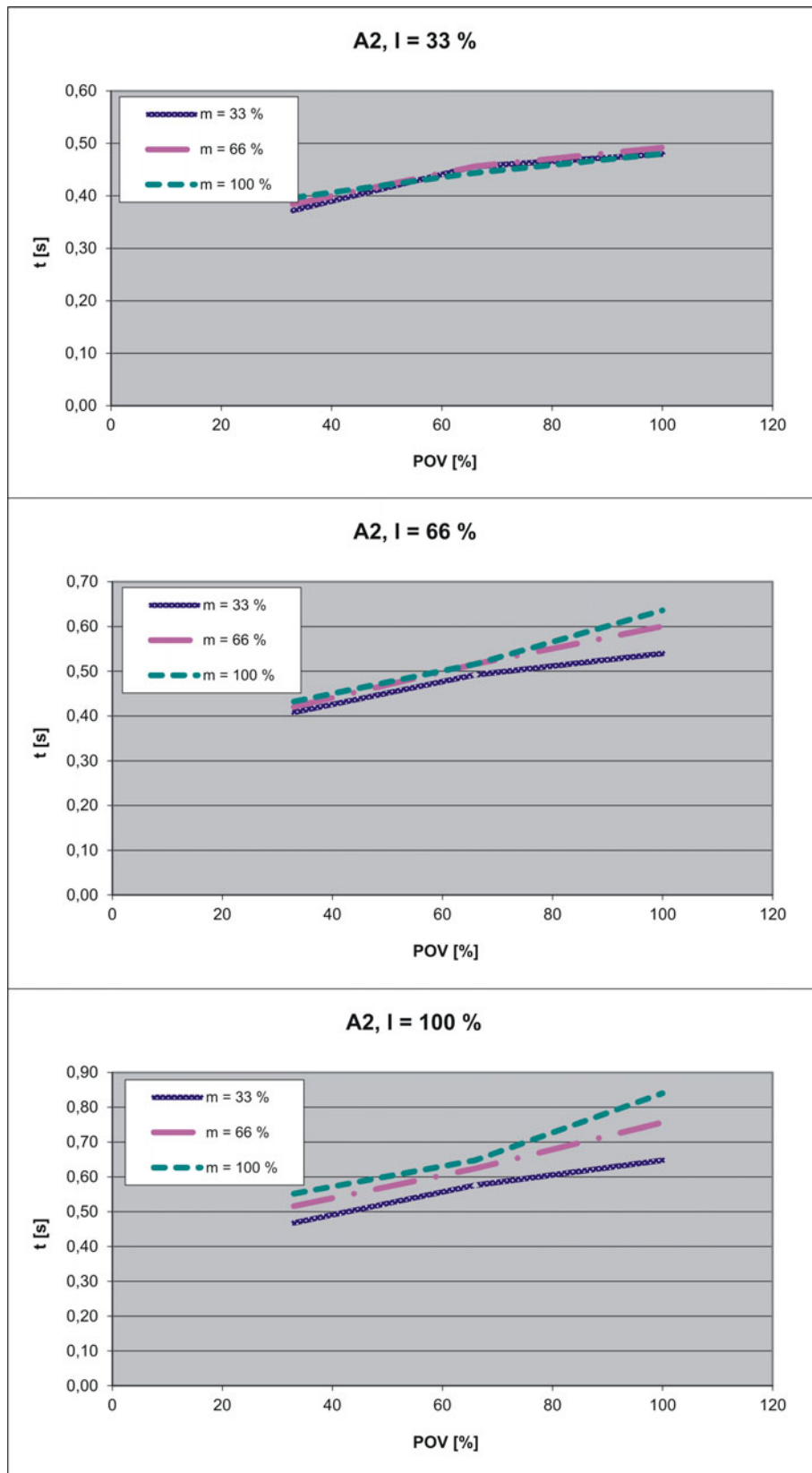


Fig. 4-47: Stopping times for STOP 1, axis 2

4.6.7.4 Stopping distances and stopping times for STOP 1, axis 3

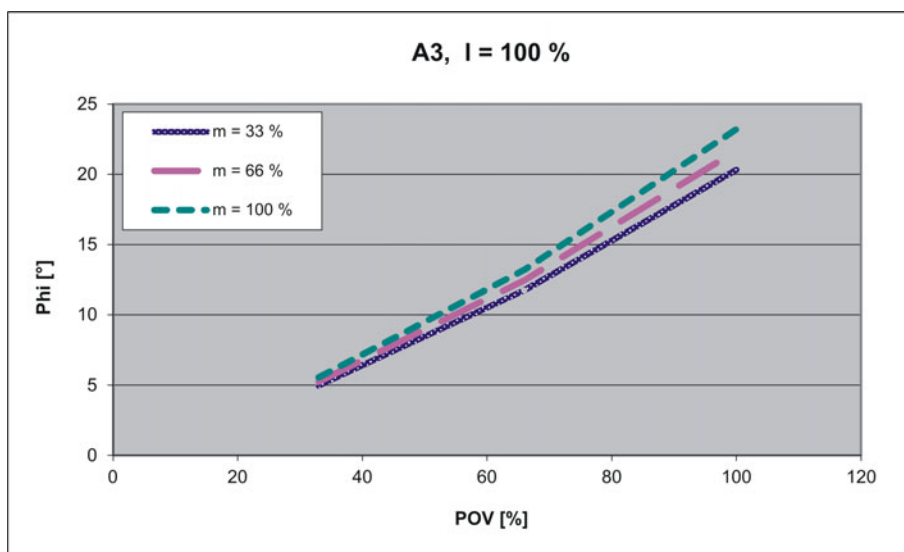


Fig. 4-48: Stopping distances for STOP 1, axis 3

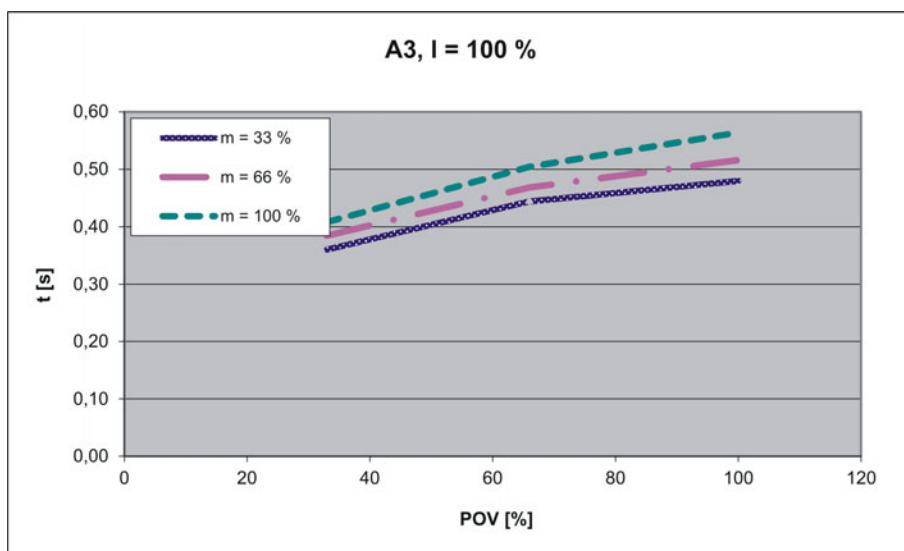


Fig. 4-49: Stopping times for STOP 1, axis 3

4.6.8 Stopping distances and times, KR 500 L420-3, KR 500 L420-3 F, KR 500 L420-3 C

4.6.8.1 Stopping distances and stopping times for STOP 0, axis 1 to axis 3

The table shows the stopping distances and stopping times after a STOP 0 (category 0 stop) is triggered. The values refer to the following configuration:

- Extension $I = 100\%$
- Program override $POV = 100\%$
- Mass $m =$ maximum load (rated load + supplementary load on arm)

	Stopping distance (°)	Stopping time (s)
Axis 1	48.17	0.982
Axis 2	35.96	0.778
Axis 3	20.41	0.387

4.6.8.2 Stopping distances and stopping times for STOP 1, axis 1

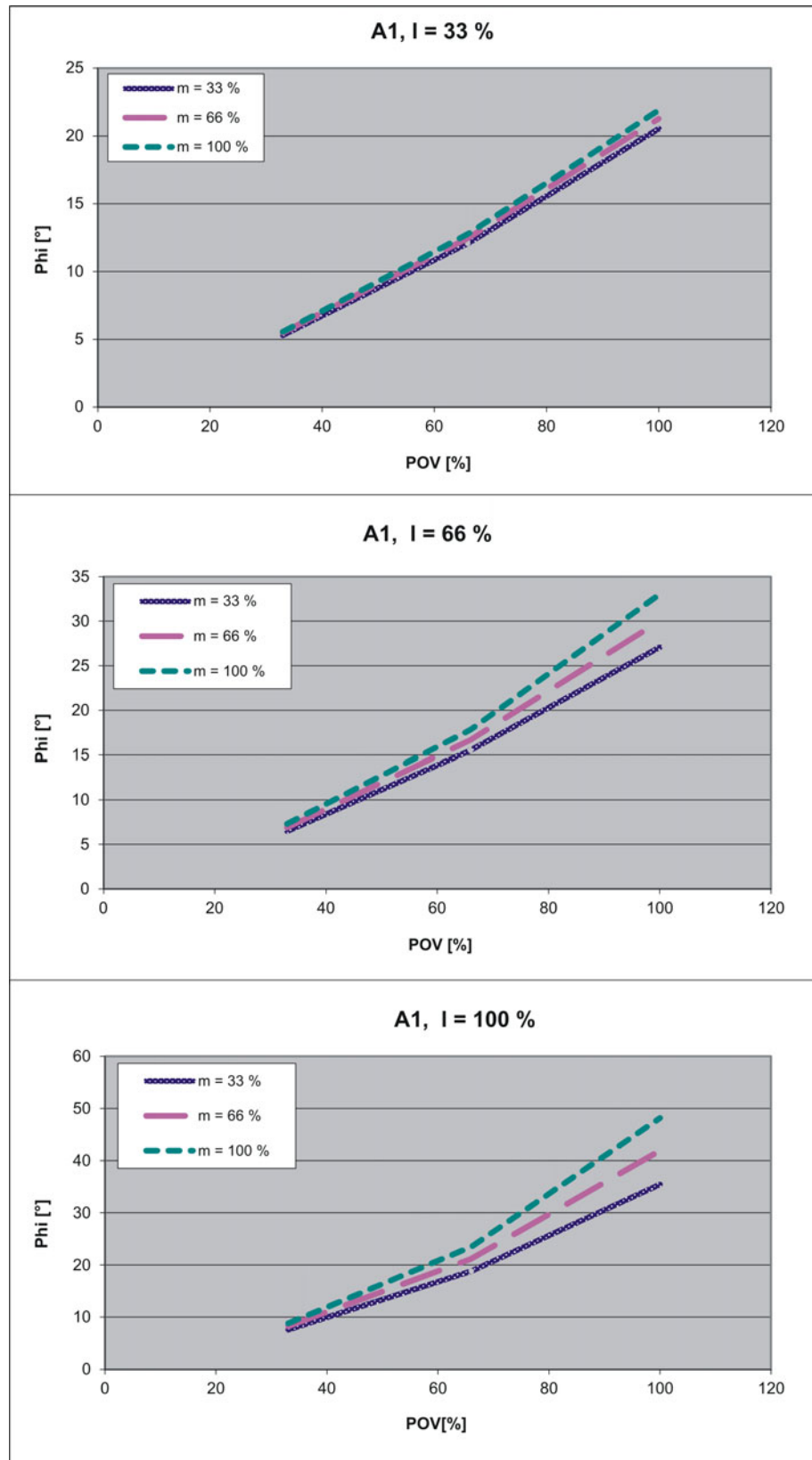


Fig. 4-50: Stopping distances for STOP 1, axis 1

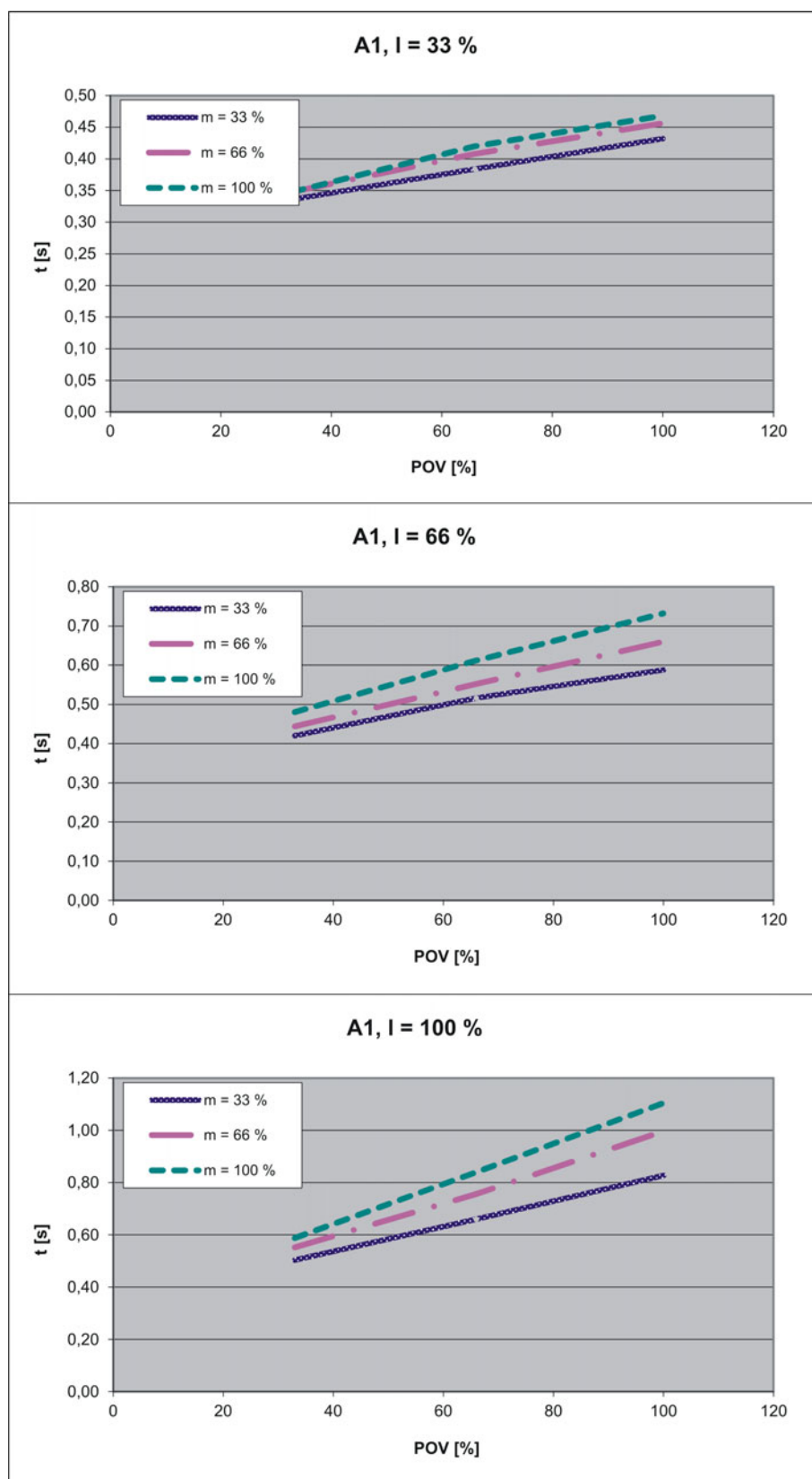


Fig. 4-51: Stopping times for STOP 1, axis 1

4.6.8.3 Stopping distances and stopping times for STOP 1, axis 2

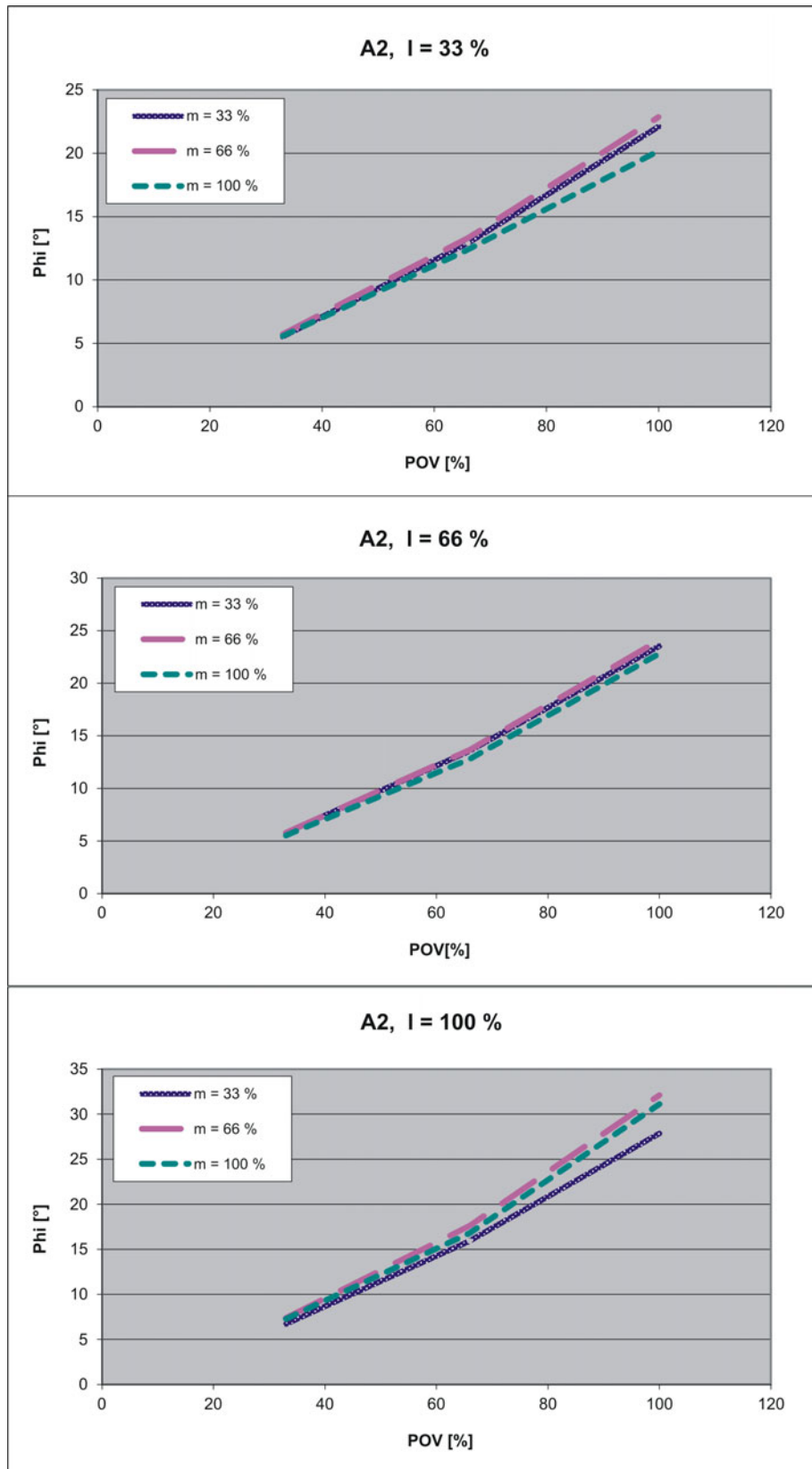


Fig. 4-52: Stopping distances for STOP 1, axis 2

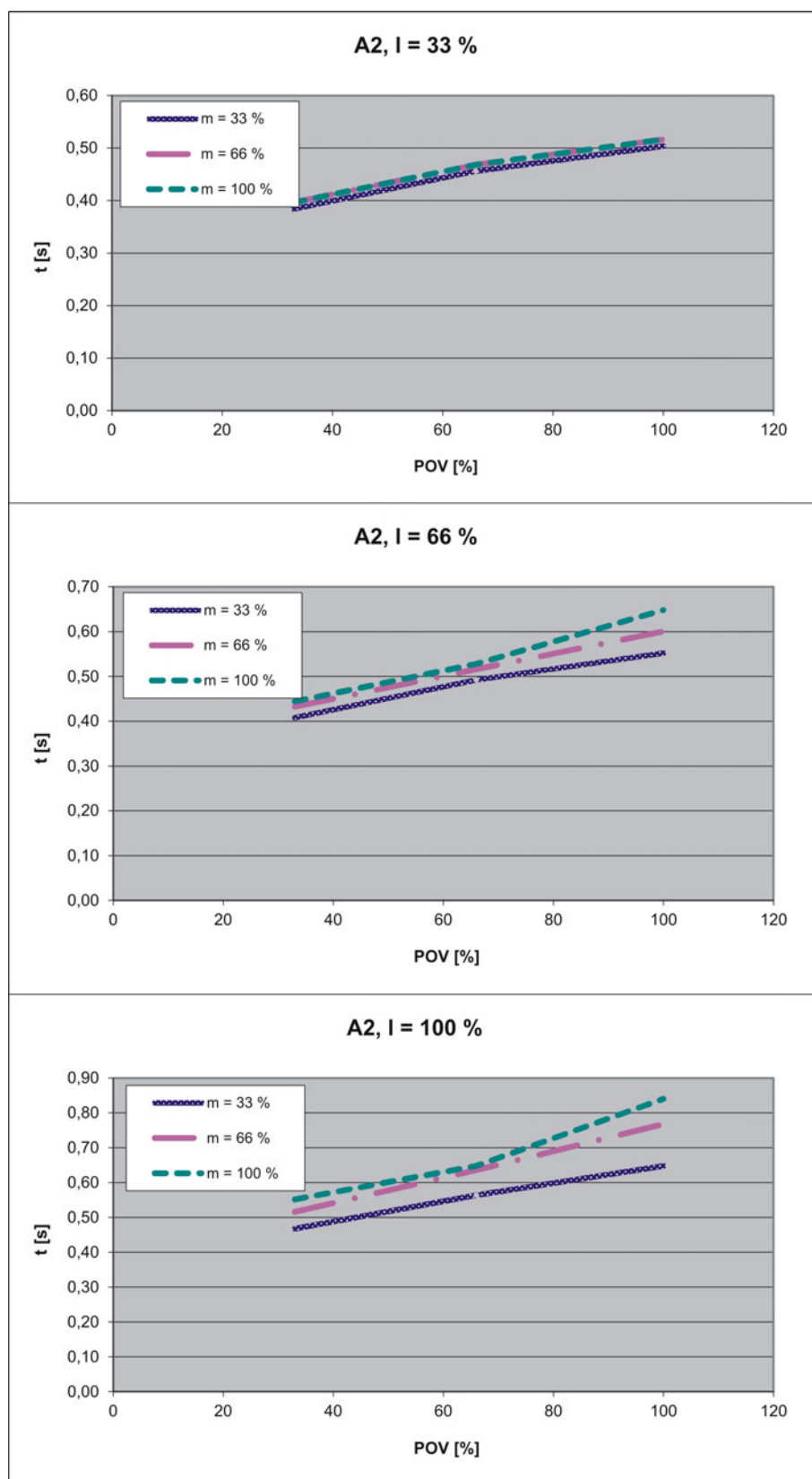


Fig. 4-53: Stopping times for STOP 1, axis 2

4.6.8.4 Stopping distances and stopping times for STOP 1, axis 3

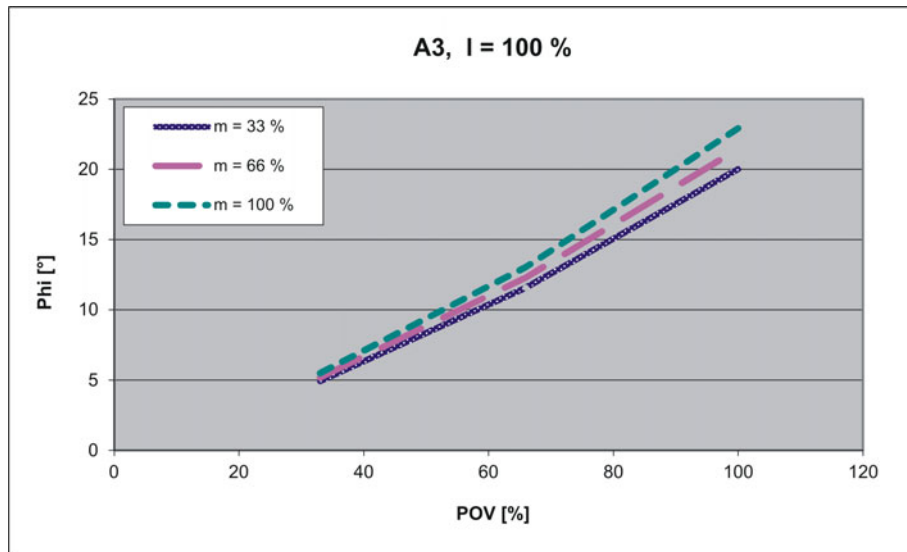


Fig. 4-54: Stopping distances for STOP 1, axis 3

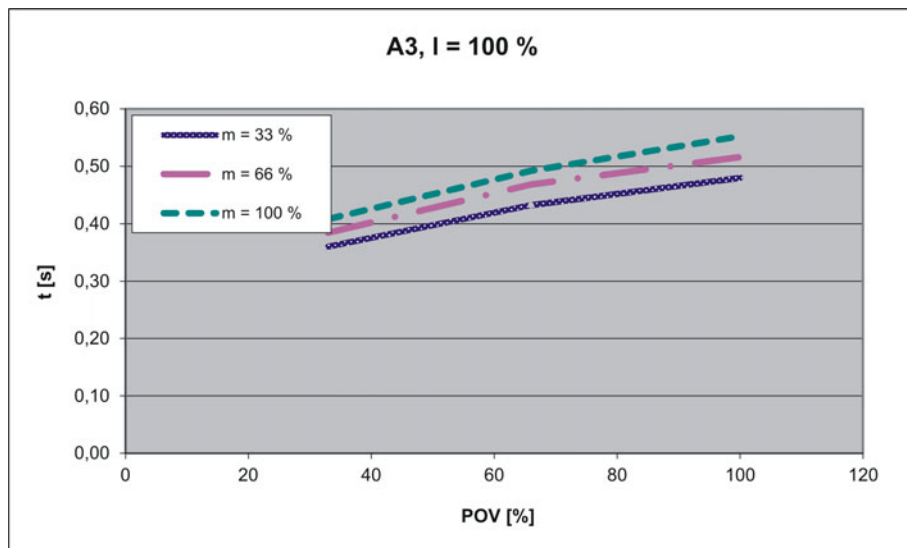


Fig. 4-55: Stopping times for STOP 1, axis 3

5 Safety

5.1 General



■ This “Safety” chapter refers to a mechanical component of an industrial robot.

■ If the mechanical component is used together with a KUKA robot controller, the “Safety” chapter of the operating instructions or assembly instructions of the robot controller must be used!

This contains all the information provided in this “Safety” chapter. It also contains additional safety information relating to the robot controller which must be observed.

■ Where this “Safety” chapter uses the term “industrial robot”, this also refers to the individual mechanical component if applicable.

5.1.1 Liability

The device described in this document is either an industrial robot or a component thereof.

Components of the industrial robot:

- Manipulator
- Robot controller
- Teach pendant
- Connecting cables
- External axes (optional)
e.g. linear unit, turn-tilt table, positioner
- Software
- Options, accessories

The industrial robot is built using state-of-the-art technology and in accordance with the recognized safety rules. Nevertheless, misuse of the industrial robot may constitute a risk to life and limb or cause damage to the industrial robot and to other material property.

The industrial robot may only be used in perfect technical condition in accordance with its designated use and only by safety-conscious persons who are fully aware of the risks involved in its operation. Use of the industrial robot is subject to compliance with this document and with the declaration of incorporation supplied together with the industrial robot. Any functional disorders affecting safety must be rectified immediately.

Safety information

Safety information cannot be held against KUKA Roboter GmbH. Even if all safety instructions are followed, this is not a guarantee that the industrial robot will not cause personal injuries or material damage.

No modifications may be carried out to the industrial robot without the authorization of KUKA Roboter GmbH. Additional components (tools, software, etc.), not supplied by KUKA Roboter GmbH, may be integrated into the industrial robot. The user is liable for any damage these components may cause to the industrial robot or to other material property.

In addition to the Safety chapter, this document contains further safety instructions. These must also be observed.

5.1.2 Intended use of the industrial robot

The industrial robot is intended exclusively for the use designated in the “Purpose” chapter of the operating instructions or assembly instructions.



Further information is contained in the “Purpose” chapter of the operating instructions or assembly instructions of the industrial robot.

Using the industrial robot for any other or additional purpose is considered impermissible misuse. The manufacturer cannot be held liable for any damage resulting from such use. The risk lies entirely with the user.

Operating the industrial robot and its options within the limits of its intended use also involves observance of the operating and assembly instructions for the individual components, with particular reference to the maintenance specifications.

Misuse

Any use or application deviating from the intended use is deemed to be impermissible misuse. This includes e.g.:

- Transportation of persons and animals
- Use as a climbing aid
- Operation outside the permissible operating parameters
- Use in potentially explosive environments
- Operation without additional safeguards
- Outdoor operation
- Underground operation

5.1.3 EC declaration of conformity and declaration of incorporation

This industrial robot constitutes partly completed machinery as defined by the EC Machinery Directive. The industrial robot may only be put into operation if the following preconditions are met:

- The industrial robot is integrated into a complete system.
Or: The industrial robot, together with other machinery, constitutes a complete system.
Or: All safety functions and safeguards required for operation in the complete machine as defined by the EC Machinery Directive have been added to the industrial robot.
- The complete system complies with the EC Machinery Directive. This has been confirmed by means of an assessment of conformity.

Declaration of conformity

The system integrator must issue a declaration of conformity for the complete system in accordance with the Machinery Directive. The declaration of conformity forms the basis for the CE mark for the system. The industrial robot must be operated in accordance with the applicable national laws, regulations and standards.

The robot controller is CE certified under the EMC Directive and the Low Voltage Directive.

Declaration of incorporation

The industrial robot as partly completed machinery is supplied with a declaration of incorporation in accordance with Annex II B of the EC Machinery Directive 2006/42/EC. The assembly instructions and a list of essential requirements complied with in accordance with Annex I are integral parts of this declaration of incorporation.

The declaration of incorporation declares that the start-up of the partly completed machinery remains impermissible until the partly completed machinery

has been incorporated into machinery, or has been assembled with other parts to form machinery, and this machinery complies with the terms of the EC Machinery Directive, and the EC declaration of conformity is present in accordance with Annex II A.

The declaration of incorporation, together with its annexes, remains with the system integrator as an integral part of the technical documentation of the complete machinery.

5.1.4 Terms used

Term	Description
Axis range	Range of each axis, in degrees or millimeters, within which it may move. The axis range must be defined for each axis.
Stopping distance	Stopping distance = reaction distance + braking distance The stopping distance is part of the danger zone.
Workspace	The manipulator is allowed to move within its workspace. The workspace is derived from the individual axis ranges.
Operator (User)	The user of the industrial robot can be the management, employer or delegated person responsible for use of the industrial robot.
Danger zone	The danger zone consists of the workspace and the stopping distances.
Service life	The service life of a safety-relevant component begins at the time of delivery of the component to the customer. The service life is not affected by whether the component is used in a robot controller or elsewhere or not, as safety-relevant components are also subject to ageing during storage.
KCP	KUKA Control Panel Teach pendant for the KR C2/KR C2 edition2005 The KCP has all the operator control and display functions required for operating and programming the industrial robot.
KUKA smartPAD	see "smartPAD"
Manipulator	The robot arm and the associated electrical installations
Safety zone	The safety zone is situated outside the danger zone.
smartPAD	Teach pendant for the KR C4 The smartPAD has all the operator control and display functions required for operating and programming the industrial robot.
Stop category 0	The drives are deactivated immediately and the brakes are applied. The manipulator and any external axes (optional) perform path-oriented braking. Note: This stop category is called STOP 0 in this document.
Stop category 1	The manipulator and any external axes (optional) perform path-maintaining braking. The drives are deactivated after 1 s and the brakes are applied. Note: This stop category is called STOP 1 in this document.
Stop category 2	The drives are not deactivated and the brakes are not applied. The manipulator and any external axes (optional) are braked with a normal braking ramp. Note: This stop category is called STOP 2 in this document.
System integrator (plant integrator)	System integrators are people who safely integrate the industrial robot into a complete system and commission it.
T1	Test mode, Manual Reduced Velocity (≤ 250 mm/s)

Term	Description
T2	Test mode, Manual High Velocity (> 250 mm/s permissible)
External axis	Motion axis which is not part of the manipulator but which is controlled using the robot controller, e.g. KUKA linear unit, turn-tilt table, Posiflex.

5.2 Personnel

The following persons or groups of persons are defined for the industrial robot:

- User
- Personnel



All persons working with the industrial robot must have read and understood the industrial robot documentation, including the safety chapter.

User

The user must observe the labor laws and regulations. This includes e.g.:

- The user must comply with his monitoring obligations.
- The user must carry out instructions at defined intervals.

Personnel

Personnel must be instructed, before any work is commenced, in the type of work involved and what exactly it entails as well as any hazards which may exist. Instruction must be carried out regularly. Instruction is also required after particular incidents or technical modifications.

Personnel includes:

- System integrator
- Operators, subdivided into:
 - Start-up, maintenance and service personnel
 - Operating personnel
 - Cleaning personnel



Installation, exchange, adjustment, operation, maintenance and repair must be performed only as specified in the operating or assembly instructions for the relevant component of the industrial robot and only by personnel specially trained for this purpose.

System integrator

The industrial robot is safely integrated into a complete system by the system integrator.

The system integrator is responsible for the following tasks:

- Installing the industrial robot
- Connecting the industrial robot
- Performing risk assessment
- Implementing the required safety functions and safeguards
- Issuing the declaration of conformity
- Attaching the CE mark
- Creating the operating instructions for the complete system

Operator

The operator must meet the following preconditions:

- The operator must be trained for the work to be carried out.
- Work on the industrial robot must only be carried out by qualified personnel. These are people who, due to their specialist training, knowledge and experience, and their familiarization with the relevant standards, are able to assess the work to be carried out and detect any potential hazards.

Example

The tasks can be distributed as shown in the following table.

Tasks	Operator	Programmer	System integrator
Switch robot controller on/off	x	x	x
Start program	x	x	x
Select program	x	x	x
Select operating mode	x	x	x
Calibration (tool, base)		x	x
Master the manipulator		x	x
Configuration		x	x
Programming		x	x
Start-up			x
Maintenance			x
Repair			x
Shutting down			x
Transportation			x



Work on the electrical and mechanical equipment of the industrial robot may only be carried out by specially trained personnel.

5.3 Workspace, safety zone and danger zone

Workspaces are to be restricted to the necessary minimum size. A workspace must be safeguarded using appropriate safeguards.

The safeguards (e.g. safety gate) must be situated inside the safety zone. In the case of a stop, the manipulator and external axes (optional) are braked and come to a stop within the danger zone.

The danger zone consists of the workspace and the stopping distances of the manipulator and external axes (optional). It must be safeguarded by means of physical safeguards to prevent danger to persons or the risk of material damage.

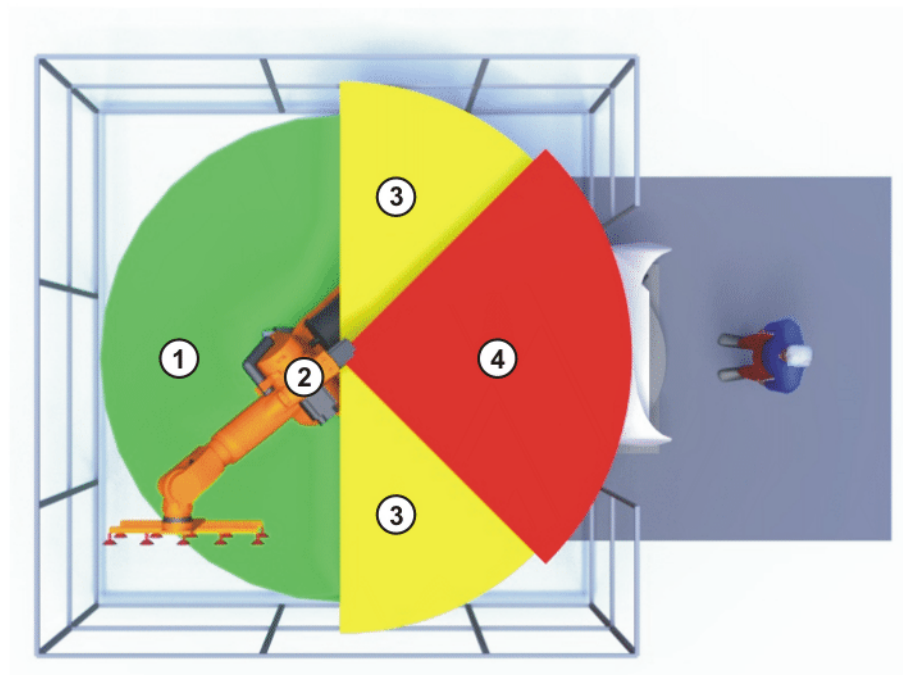


Fig. 5-1: Example of axis range A1

- | | | | |
|---|-------------|---|-------------------|
| 1 | Workspace | 3 | Stopping distance |
| 2 | Manipulator | 4 | Safety zone |

5.4 Overview of protective equipment

The protective equipment of the mechanical component may include:

- Mechanical end stops
- Mechanical axis range limitation (optional)
- Axis range monitoring (optional)
- Release device (optional)
- Labeling of danger areas

Not all equipment is relevant for every mechanical component.

5.4.1 Mechanical end stops

Depending on the robot variant, the axis ranges of the main and wrist axes of the manipulator are partially limited by mechanical end stops.

Additional mechanical end stops can be installed on the external axes.



WARNING If the manipulator or an external axis hits an obstruction or a mechanical end stop or axis range limitation, this can result in material damage to the industrial robot. The manipulator must be taken out of operation and KUKA Roboter GmbH must be consulted before it is put back into operation (>>> 8 "KUKA Service" Page 97).

5.4.2 Mechanical axis range limitation (optional)

Some manipulators can be fitted with mechanical axis range limitation in axes A1 to A3. The adjustable axis range limitation systems restrict the working range to the required minimum. This increases personal safety and protection of the system.

In the case of manipulators that are not designed to be fitted with mechanical axis range limitation, the workspace must be laid out in such a way that there is no danger to persons or material property, even in the absence of mechanical axis range limitation.

If this is not possible, the workspace must be limited by means of photoelectric barriers, photoelectric curtains or obstacles on the system side. There must be no shearing or crushing hazards at the loading and transfer areas.



This option is not available for all robot models. Information on specific robot models can be obtained from KUKA Roboter GmbH.

5.4.3 Axis range monitoring (optional)

Einige Manipulatoren können in den Grundachsen A1 bis A3 mit 2-kanaligen Achsbereichsüberwachungen ausgerüstet werden. Die Positionierachsen können mit weiteren Achsbereichsüberwachungen ausgerüstet sein. Mit einer Achsbereichsüberwachung kann für eine Achse der Schutzbereich eingestellt und überwacht werden. Damit wird der Personen- und Anlagenschutz erhöht.



This option is not available for the KR C4. This option is not available for all robot models. Information on specific robot models can be obtained from KUKA Roboter GmbH.

5.4.4 Options for moving the manipulator without drive energy



The system user is responsible for ensuring that the training of personnel with regard to the response to emergencies or exceptional situations also includes how the manipulator can be moved without drive energy.

Description

The following options are available for moving the manipulator without drive energy after an accident or malfunction:

- Release device (optional)
The release device can be used for the main axis drive motors and, depending on the robot variant, also for the wrist axis drive motors.
- Brake release device (option)
The brake release device is designed for robot variants whose motors are not freely accessible.
- Moving the wrist axes directly by hand
There is no release device available for the wrist axes of variants in the low payload category. This is not necessary because the wrist axes can be moved directly by hand.



Information about the options available for the various robot models and about how to use them can be found in the assembly and operating instructions for the robot or requested from KUKA Roboter GmbH.

NOTICE

Moving the manipulator without drive energy can damage the motor brakes of the axes concerned. The motor must be replaced if the brake has been damaged. The manipulator may therefore be moved without drive energy only in emergencies or exceptional situations, e.g. for rescuing persons.

5.4.5 Labeling on the industrial robot

All plates, labels, symbols and marks constitute safety-relevant parts of the industrial robot. They must not be modified or removed.

Labeling on the industrial robot consists of:

- Identification plates
- Warning labels
- Safety symbols
- Designation labels
- Cable markings
- Rating plates



Further information is contained in the technical data of the operating instructions or assembly instructions of the components of the industrial robot.

5.5 Safety measures

5.5.1 General safety measures

The industrial robot may only be used in perfect technical condition in accordance with its intended use and only by safety-conscious persons. Operator errors can result in personal injury and damage to property.

It is important to be prepared for possible movements of the industrial robot even after the robot controller has been switched off and locked out. Incorrect installation (e.g. overload) or mechanical defects (e.g. brake defect) can cause the manipulator or external axes to sag. If work is to be carried out on a switched-off industrial robot, the manipulator and external axes must first be moved into a position in which they are unable to move on their own, whether the payload is mounted or not. If this is not possible, the manipulator and external axes must be secured by appropriate means.



In the absence of operational safety functions and safeguards, the industrial robot can cause personal injury or material damage. If safety functions or safeguards are dismantled or deactivated, the industrial robot may not be operated.



Standing underneath the robot arm can cause death or serious injuries. For this reason, standing underneath the robot arm is prohibited!



The motors reach temperatures during operation which can cause burns to the skin. Contact must be avoided. Appropriate safety precautions must be taken, e.g. protective gloves must be worn.

KCP/smartPAD

The user must ensure that the industrial robot is only operated with the KCP/smartPAD by authorized persons.

If more than one KCP/smartPAD is used in the overall system, it must be ensured that each device is unambiguously assigned to the corresponding industrial robot. They must not be interchanged.

⚠ WARNING

The operator must ensure that decoupled KCPs/smart-PADs are immediately removed from the system and stored out of sight and reach of personnel working on the industrial robot. This serves to prevent operational and non-operational EMERGENCY STOP devices from becoming interchanged. Failure to observe this precaution may result in death, severe injuries or considerable damage to property.

External keyboard, external mouse

An external keyboard and/or external mouse may only be used if the following conditions are met:

- Start-up or maintenance work is being carried out.
- The drives are switched off.
- There are no persons in the danger zone.

The KCP/smartPAD must not be used as long as an external keyboard and/or external mouse are connected.

The external keyboard and/or external mouse must be removed as soon as the start-up or maintenance work is completed or the KCP/smartPAD is connected.

Modifications

After modifications to the industrial robot, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.

New or modified programs must always be tested first in Manual Reduced Velocity mode (T1).

After modifications to the industrial robot, existing programs must always be tested first in Manual Reduced Velocity mode (T1). This applies to all components of the industrial robot and includes modifications to the software and configuration settings.

Faults

The following tasks must be carried out in the case of faults in the industrial robot:

- Switch off the robot controller and secure it (e.g. with a padlock) to prevent unauthorized persons from switching it on again.
- Indicate the fault by means of a label with a corresponding warning (tag-out).
- Keep a record of the faults.
- Eliminate the fault and carry out a function test.

5.5.2 Transportation**Manipulator**

The prescribed transport position of the manipulator must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the robot.

Robot controller

The prescribed transport position of the robot controller must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the robot controller.

Avoid vibrations and impacts during transportation in order to prevent damage to the robot controller.

External axis (optional)

The prescribed transport position of the external axis (e.g. KUKA linear unit, turn-tilt table, positioner) must be observed. Transportation must be carried out in accordance with the operating instructions or assembly instructions of the external axis.

5.5.3 Start-up and recommissioning

Before starting up systems and devices for the first time, a check must be carried out to ensure that the systems and devices are complete and operational, that they can be operated safely and that any damage is detected.

The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety circuits must also be tested.



The passwords for logging onto the KUKA System Software as “Expert” and “Administrator” must be changed before start-up and must only be communicated to authorized personnel.



The robot controller is preconfigured for the specific industrial robot. If cables are interchanged, the manipulator and the external axes (optional) may receive incorrect data and can thus cause personal injury or material damage. If a system consists of more than one manipulator, always connect the connecting cables to the manipulators and their corresponding robot controllers.



If additional components (e.g. cables), which are not part of the scope of supply of KUKA Roboter GmbH, are integrated into the industrial robot, the user is responsible for ensuring that these components do not adversely affect or disable safety functions.

NOTICE

If the internal cabinet temperature of the robot controller differs greatly from the ambient temperature, condensation can form, which may cause damage to the electrical components. Do not put the robot controller into operation until the internal temperature of the cabinet has adjusted to the ambient temperature.

Function test

The following tests must be carried out before start-up and recommissioning:

It must be ensured that:

- The industrial robot is correctly installed and fastened in accordance with the specifications in the documentation.
- There are no foreign bodies or loose parts on the industrial robot.
- All required safety equipment is correctly installed and operational.
- The power supply ratings of the industrial robot correspond to the local supply voltage and mains type.
- The ground conductor and the equipotential bonding cable are sufficiently rated and correctly connected.
- The connecting cables are correctly connected and the connectors are locked.

Machine data

It must be ensured that the rating plate on the robot controller has the same machine data as those entered in the declaration of incorporation. The machine data on the rating plate of the manipulator and the external axes (optional) must be entered during start-up.



WARNING The industrial robot must not be moved if incorrect machine data are loaded. Death, severe injuries or considerable damage to property may otherwise result. The correct machine data must be loaded.

5.5.4 Manual mode

Manual mode is the mode for setup work. Setup work is all the tasks that have to be carried out on the industrial robot to enable automatic operation. Setup work includes:

- Jog mode
- Teach
- Programming
- Program verification

The following must be taken into consideration in manual mode:

- If the drives are not required, they must be switched off to prevent the manipulator or the external axes (optional) from being moved unintentionally. New or modified programs must always be tested first in Manual Reduced Velocity mode (T1).
- The manipulator, tooling or external axes (optional) must never touch or project beyond the safety fence.
- Workpieces, tooling and other objects must not become jammed as a result of the industrial robot motion, nor must they lead to short-circuits or be liable to fall off.
- All setup work must be carried out, where possible, from outside the safeguarded area.

If the setup work has to be carried out inside the safeguarded area, the following must be taken into consideration:

In Manual Reduced Velocity mode (T1):

- If it can be avoided, there must be no other persons inside the safeguarded area.
If it is necessary for there to be several persons inside the safeguarded area, the following must be observed:
 - Each person must have an enabling device.
 - All persons must have an unimpeded view of the industrial robot.
 - Eye-contact between all persons must be possible at all times.
- The operator must be so positioned that he can see into the danger area and get out of harm's way.

In Manual High Velocity mode (T2):

- This mode may only be used if the application requires a test at a velocity higher than Manual Reduced Velocity.
- Teaching and programming are not permissible in this operating mode.
- Before commencing the test, the operator must ensure that the enabling devices are operational.
- The operator must be positioned outside the danger zone.
- There must be no other persons inside the safeguarded area. It is the responsibility of the operator to ensure this.

5.5.5 Automatic mode

Automatic mode is only permissible in compliance with the following safety measures:

- All safety equipment and safeguards are present and operational.
- There are no persons in the system.
- The defined working procedures are adhered to.

If the manipulator or an external axis (optional) comes to a standstill for no apparent reason, the danger zone must not be entered until an EMERGENCY STOP has been triggered.

5.5.6 Maintenance and repair

After maintenance and repair work, checks must be carried out to ensure the required safety level. The valid national or regional work safety regulations must be observed for this check. The correct functioning of all safety functions must also be tested.

The purpose of maintenance and repair work is to ensure that the system is kept operational or, in the event of a fault, to return the system to an operational state. Repair work includes troubleshooting in addition to the actual repair itself.

The following safety measures must be carried out when working on the industrial robot:

- Carry out work outside the danger zone. If work inside the danger zone is necessary, the user must define additional safety measures to ensure the safe protection of personnel.
- Switch off the industrial robot and secure it (e.g. with a padlock) to prevent it from being switched on again. If it is necessary to carry out work with the robot controller switched on, the user must define additional safety measures to ensure the safe protection of personnel.
- If it is necessary to carry out work with the robot controller switched on, this may only be done in operating mode T1.
- Label the system with a sign indicating that work is in progress. This sign must remain in place, even during temporary interruptions to the work.
- The EMERGENCY STOP systems must remain active. If safety functions or safeguards are deactivated during maintenance or repair work, they must be reactivated immediately after the work is completed.



WARNING

Before work is commenced on live parts of the robot system, the main switch must be turned off and secured against being switched on again by unauthorized personnel. The incoming power cable must be deenergized. The robot controller and mains supply lead must then be checked to ensure that it is deenergized.

If the KR C4 or VKR C4 robot controller is used:

It is not sufficient, before commencing work on live parts, to execute an EMERGENCY STOP or a safety stop, or to switch off the drives, as this does not disconnect the robot system from the mains power supply in the case of the drives of the new generation. Parts remain energized. Death or severe injuries may result.

Faulty components must be replaced using new components with the same article numbers or equivalent components approved by KUKA Roboter GmbH for this purpose.

Cleaning and preventive maintenance work is to be carried out in accordance with the operating instructions.

Robot controller

Even when the robot controller is switched off, parts connected to peripheral devices may still carry voltage. The external power sources must therefore be switched off if work is to be carried out on the robot controller.

The ESD regulations must be adhered to when working on components in the robot controller.

Voltages in excess of 50 V (up to 600 V) can be present in various components for several minutes after the robot controller has been switched off! To prevent

life-threatening injuries, no work may be carried out on the industrial robot in this time.

Water and dust must be prevented from entering the robot controller.

Counterbalancing system

Some robot variants are equipped with a hydropneumatic, spring or gas cylinder counterbalancing system.

The hydropneumatic and gas cylinder counterbalancing systems are pressure equipment and, as such, are subject to obligatory equipment monitoring. Depending on the robot variant, the counterbalancing systems correspond to category 0, II or III, fluid group 2, of the Pressure Equipment Directive.

The user must comply with the applicable national laws, regulations and standards pertaining to pressure equipment.

Inspection intervals in Germany in accordance with Industrial Safety Order, Sections 14 and 15. Inspection by the user before commissioning at the installation site.

The following safety measures must be carried out when working on the counterbalancing system:

- The manipulator assemblies supported by the counterbalancing systems must be secured.
- Work on the counterbalancing systems must only be carried out by qualified personnel.

Hazardous substances

The following safety measures must be carried out when handling hazardous substances:

- Avoid prolonged and repeated intensive contact with the skin.
- Avoid breathing in oil spray or vapors.
- Clean skin and apply skin cream.



To ensure safe use of our products, we recommend that our customers regularly request up-to-date safety data sheets from the manufacturers of hazardous substances.

5.5.7 Decommissioning, storage and disposal

The industrial robot must be decommissioned, stored and disposed of in accordance with the applicable national laws, regulations and standards.

5.6 Applied norms and regulations

Name	Definition	Edition
2006/42/EC	Machinery Directive: Directive 2006/42/EC of the European Parliament and of the Council of 17 May 2006 on machinery, and amending Directive 95/16/EC (recast)	2006
2004/108/EC	EMC Directive: Directive 2004/108/EC of the European Parliament and of the Council of 15 December 2004 on the approximation of the laws of the Member States relating to electromagnetic compatibility and repealing Directive 89/336/EEC	2004

Name	Definition	Edition
97/23/EC	Pressure Equipment Directive: Directive 97/23/EC of the European Parliament and of the Council of 29 May 1997 on the approximation of the laws of the Member States concerning pressure equipment (Only applicable for robots with hydropneumatic counter-balancing system.)	1997
EN ISO 13850	Safety of machinery: Emergency stop - Principles for design	2008
EN ISO 13849-1	Safety of machinery: Safety-related parts of control systems - Part 1: General principles of design	2008
EN ISO 13849-2	Safety of machinery: Safety-related parts of control systems - Part 2: Validation	2008
EN ISO 12100	Safety of machinery: General principles of design, risk assessment and risk reduction	2010
EN ISO 10218-1	Industrial robots: Safety	2011
EN 614-1	Safety of machinery: Ergonomic design principles - Part 1: Terms and general principles	2006
EN 61000-6-2	Electromagnetic compatibility (EMC): Part 6-2: Generic standards; Immunity for industrial environments	2005
EN 61000-6-4	Electromagnetic compatibility (EMC): Part 6-4: Generic standards; Emission standard for industrial environments	2007
EN 60204-1	Safety of machinery: Electrical equipment of machines - Part 1: General requirements	2006

6 Planning

6.1 Mounting base 175 mm

Description

The mounting base with centering (>>> Fig. 6-1) is used when the robot is fastened to the floor, i.e. directly on a concrete foundation with a thickness of at least 175 mm.

The mounting base consists of:

- Bedplate
- Chemical anchors (resin-bonded anchors) with Dynamic Set
- Fasteners

This mounting variant requires a level and smooth surface on a concrete foundation with adequate load bearing capacity. The concrete foundation must be able to accommodate the forces occurring during operation. The minimum dimensions must be observed.

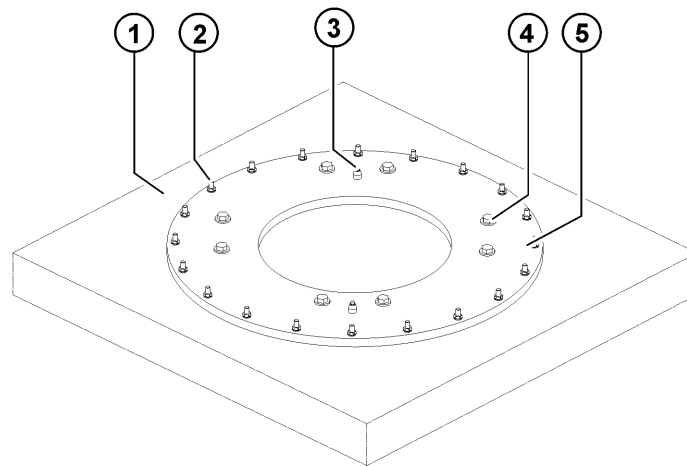


Fig. 6-1: Mounting base 175 mm

- | | | | |
|---|---------------------------------------|---|--------------|
| 1 | Concrete foundation | 4 | Hexagon bolt |
| 2 | Chemical anchor (resin-bonded anchor) | 5 | Bedplate |
| 3 | Pin | | |

Grade of concrete for foundations

When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. There must be no layers of insulation or screed between the bedplates and the concrete foundation. The quality of the concrete must meet the requirements of the following standard:

- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2008

Dimensioned drawing

The following illustration provides all the necessary information on the mounting base, together with the required foundation data.

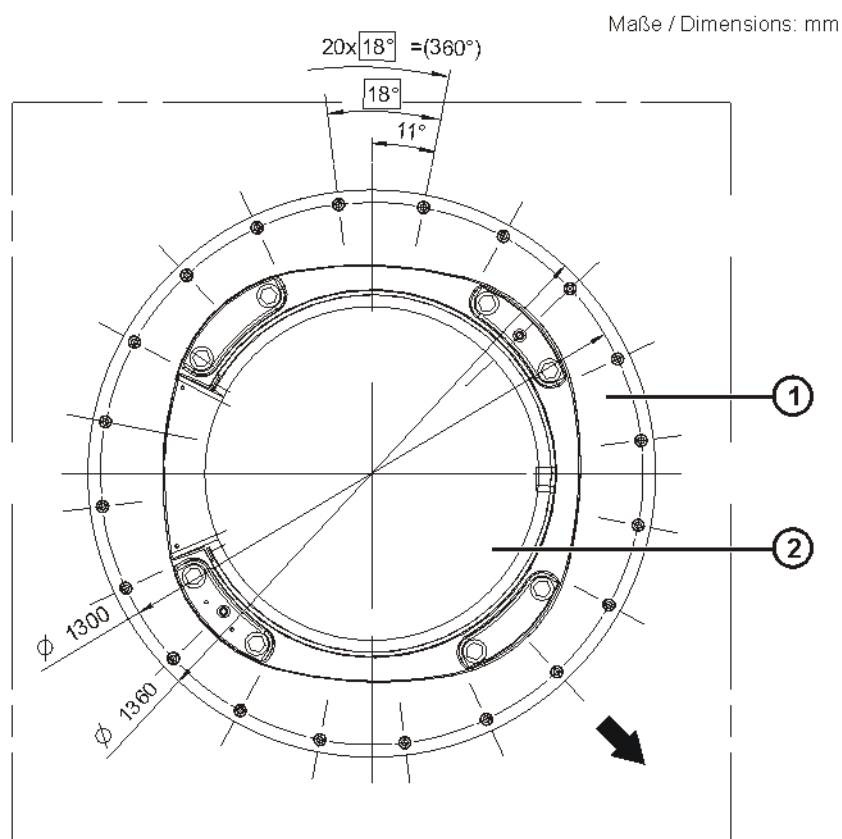


Fig. 6-2: Mounting base 175 mm, dimensioned drawing

1 Robot

2 Bedplate

To ensure that the anchor forces are safely transmitted to the foundation, observe the dimensions for concrete foundations specified in the following illustration (>>> Fig. 6-3).

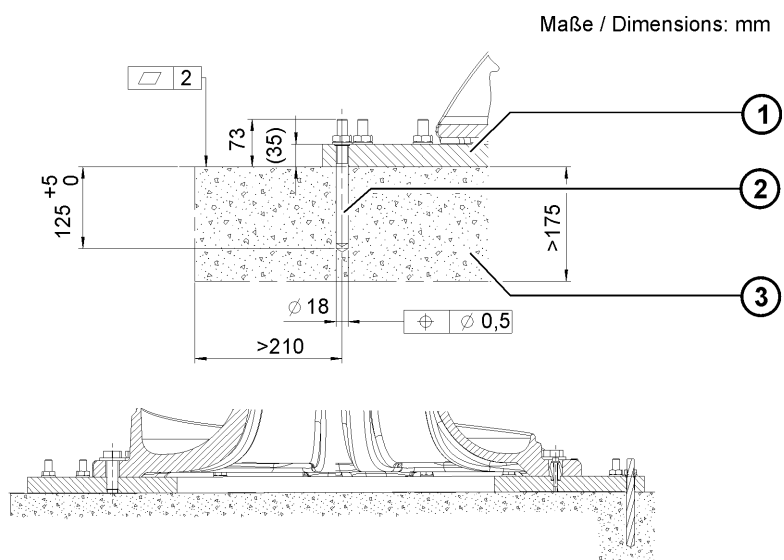


Fig. 6-3: Cross-section of foundation 175 mm

1 Bedplate

2 Chemical anchors (resin-bonded anchors) with Dynamic Set

3 Concrete foundation

6.2 Mounting base 200 mm

Description

The mounting base with centering (>>> Fig. 6-4) is used when the robot is fastened to the floor, i.e. directly on a concrete foundation with a thickness of at least 200 mm.

The mounting base with centering consists of:

- Bedplates
- Chemical anchors
- Fastening elements

This mounting variant requires a level and smooth surface on a concrete foundation with adequate load bearing capacity. The concrete foundation must be able to accommodate the forces occurring during operation. There must be no layers of insulation or screed between the bedplates and the concrete foundation.

The minimum dimensions must be observed.

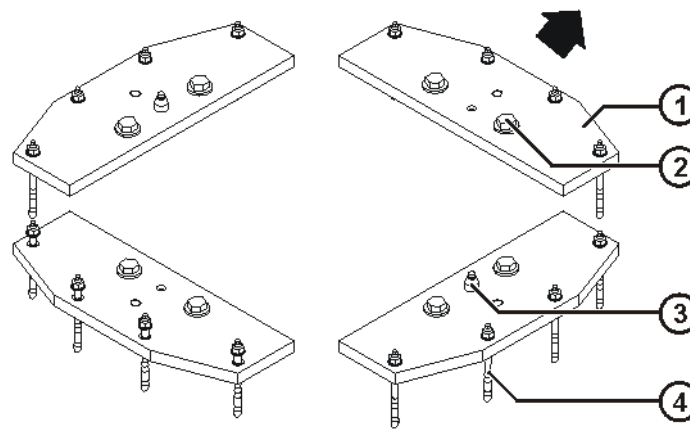


Fig. 6-4: Mounting base 200 mm

- | | |
|----------------|---|
| 1 Bedplate | 3 Pin with Allen screw |
| 2 Hexagon bolt | 4 Resin-bonded anchors with Dynamic Set |

Grade of concrete for foundations

When producing foundations from concrete, observe the load-bearing capacity of the ground and the country-specific construction regulations. There must be no layers of insulation or screed between the bedplates and the concrete foundation. The quality of the concrete must meet the requirements of the following standard:

- C20/25 according to DIN EN 206-1:2001/DIN 1045-2:2008

Dimensioned drawing

The following illustrations provide all the necessary information on the mounting base, together with the required foundation data.

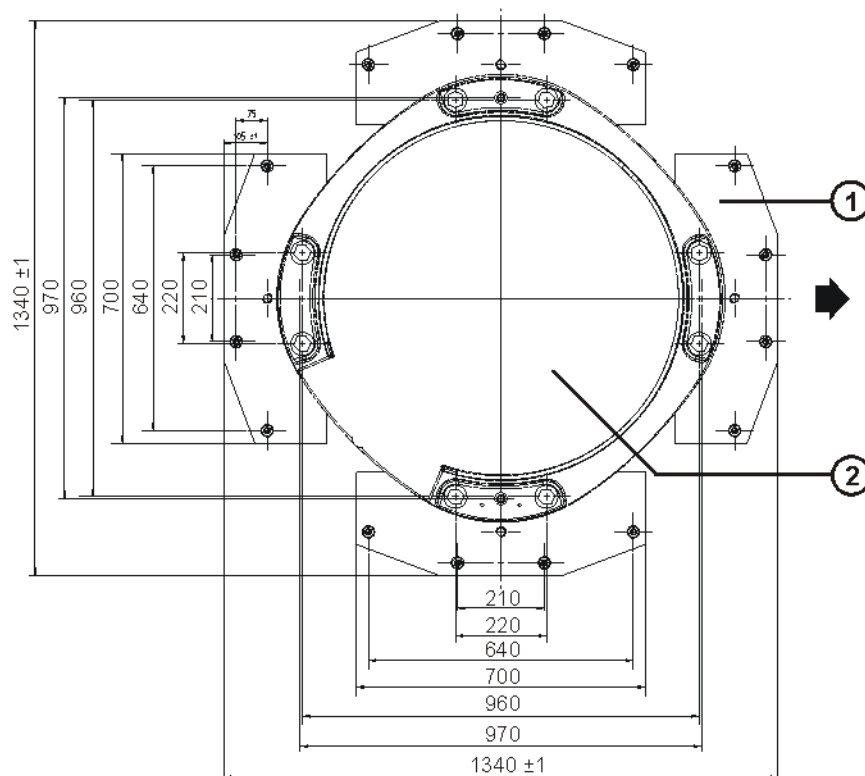


Fig. 6-5: Mounting base 200 mm, dimensioned drawing

1 Bedplates

2 Robot

To ensure that the anchor forces are safely transmitted to the foundation, observe the dimensions for concrete foundations specified in the following illustration.

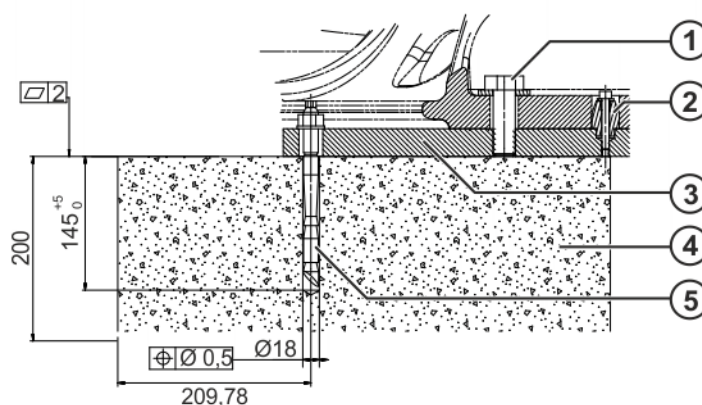


Fig. 6-6: Cross-section of foundation 200 mm

1 Hexagon bolt

2 Pin

3 Bedplate

4 Concrete foundation

5 Resin-bonded anchor

6.3 Machine frame mounting

Description

The machine frame mounting assembly is used when the robot is fastened on a steel structure, a booster frame (pedestal) or a KUKA linear unit. This assembly is also used if the manipulator is installed in an inverted position, i.e. on the ceiling. It must be ensured that the substructure is able to withstand safely the forces occurring during operation (foundation loads). The following diagram contains all the necessary information that must be observed when preparing the mounting surface (>>> Fig. 6-7).

The machine frame mounting assembly consists of:

- Pin with fasteners
- Hexagon bolts with conical spring washers

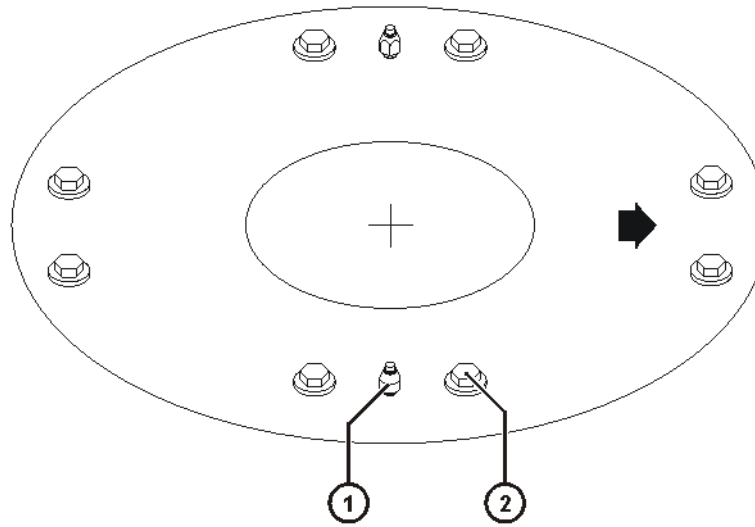


Fig. 6-7: Machine frame mounting

- 1 Pin
- 2 Hexagon bolt

Dimensioned drawing

The following illustrations provide all the necessary information on machine frame mounting, together with the required foundation data.

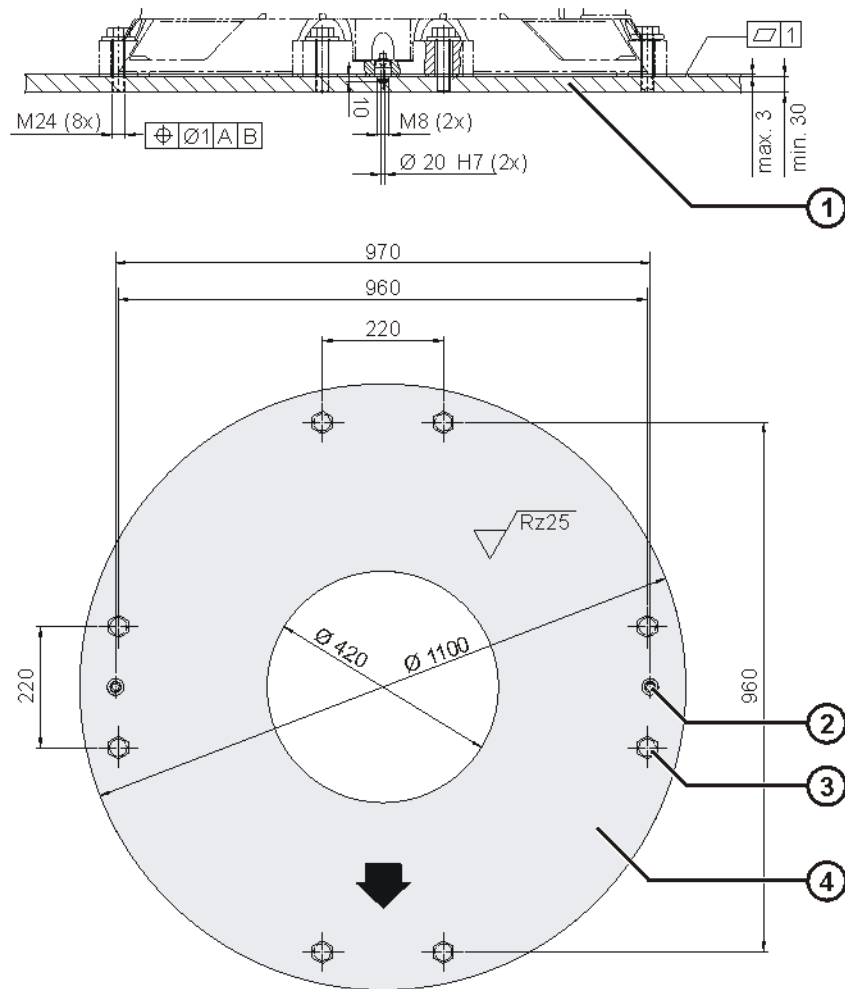


Fig. 6-8: Machine frame mounting, dimensioned drawing

- | | |
|-------------------|---------------------|
| 1 Steel structure | 3 Hexagon bolt (8x) |
| 2 Pins (2x) | 4 Mounting surface |

6.4 Connecting cables and interfaces

Connecting cables

The connecting cables comprise all the cables for transferring energy and signals between the robot and the robot controller. They are connected to the robot junction boxes with connectors. The set of connecting cables comprises:

- Motor cable X20.1 - X30.1
- Motor cable X20.4 - X30.4
- Control cable X21 - X31
- Ground conductor (optional)

Depending on the specification of the robot, various connecting cables are used. Cable lengths of 7 m, 15 m, 25 m, 35 m and 50 m are available. The maximum length of the connecting cables must not exceed 50 m. Thus if the robot is operated on a linear unit which has its own energy supply chain these cables must also be taken into account.



For the connecting cables, a ground conductor is always required to provide a low-resistance connection between the robot and the control cabinet in accordance with DIN EN 60204. The ground conductor is not part of the scope of supply and can be ordered as an option. The connection must be made by the customer. The tapped holes for connecting the ground conductor are located on the base frame of the robot.

The following points must be observed when planning and routing the connecting cables:

- The bending radius for fixed routing must not be less than 150 mm for motor cables and 60 mm for control cables.
- Protect cables against exposure to mechanical stress.
- Route the cables without mechanical stress – no tensile forces on the connectors
- Cables are only to be installed indoors.
- Observe permissible temperature range (fixed installation) of 263 K (-10 °C) to 343 K (+70 °C).
- Route the motor cables and the data cables separately in metal ducts; if necessary, additional measures must be taken to ensure electromagnetic compatibility (EMC).

Interface for energy supply systems

The robot can be equipped with an energy supply system between axis 1 and axis 3 and a second energy supply system between axis 3 and axis 6. The A1 interface required for this is located on the rear of the base frame, the A3 interface is located on the side of the arm and the interface for axis 6 is located on the robot tool. Depending on the application, the interfaces differ in design and scope. They can be equipped e.g. with connections for cables and hoses. Detailed information on the connector pin allocation, threaded unions, etc. is given in separate documentation.

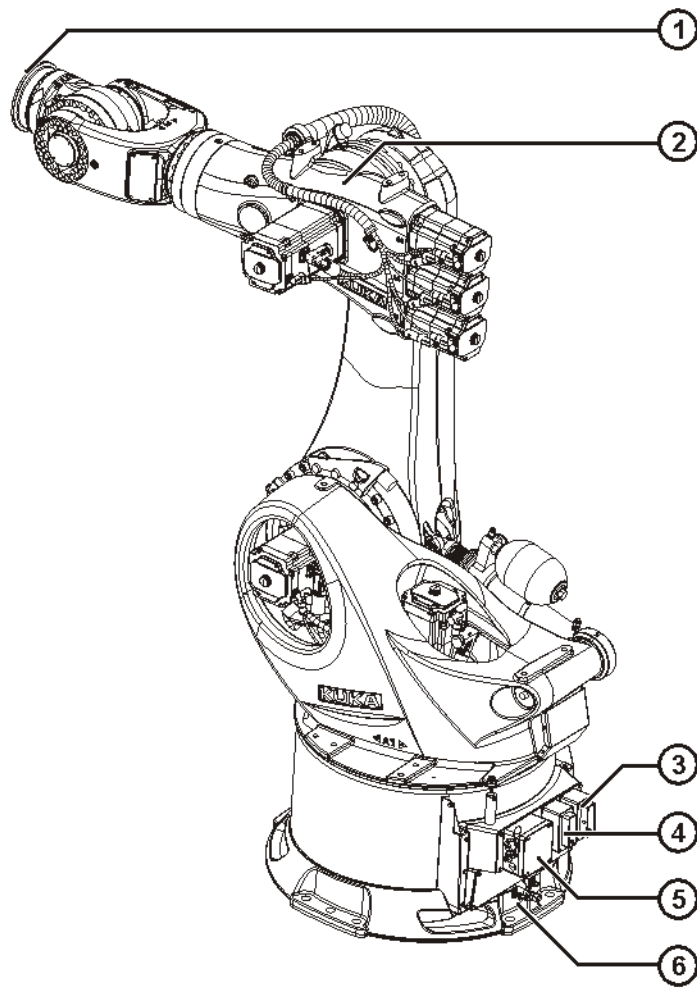


Fig. 6-9: Connecting cables and interfaces

- 1 Interface A6, tool
- 2 Interface A3, arm
- 3 Connection, motor cable X30.4
- 4 Connection, motor cable X30.1
- 5 Connection, control cable X31
- 6 Interface A1, base frame

7 Transportation

7.1 Transporting the robot

Description Move the robot into its transport position each time it is transported. It must be ensured that the robot is stable while it is being transported. The robot must remain in its transport position until it has been fastened in position. Before the robot is lifted, it must be ensured that it is free from obstructions. Remove all transport safeguards, such as nails and screws, in advance. First remove any rust or glue on contact surfaces. Remove any disruptive add-on parts (e.g. energy supply system) before transportation.

Transport position The robot must be in the transport position (>>> Fig. 7-1) before it can be transported. The robot is in the transport position when the axes are in the following positions:

Axis	A1	A2	A3	A4	A5	A6
Angle	0°	-130°	+130°	0°	+90°	0°

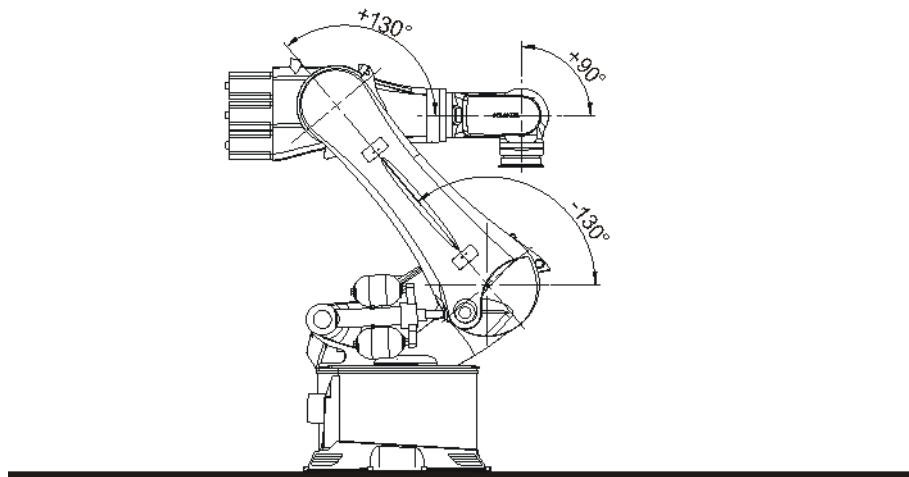


Fig. 7-1: Transport position

Transport dimensions The transport dimensions for the robot can be noted from the following figures. The position of the center of gravity and the weight vary according to the specific configuration. The specified dimensions refer to the robot without equipment.

Maße / Dimensions: mm

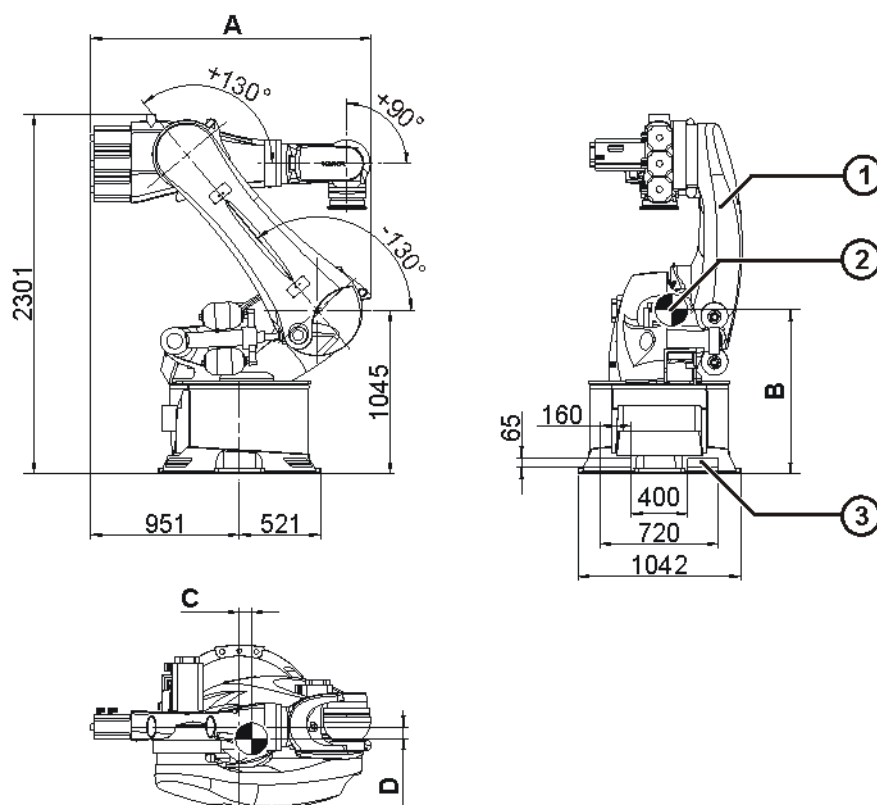


Fig. 7-2: Transport dimensions

- 1 Robot
2 Center of gravity
3 Fork slots

Robot	A	B	C	D
KR 360-3	1,803 mm	1,053 mm	78 mm	77 mm
KR 360-3 F				
KR 360 L240-3	2,290 mm	1,069 mm	122 mm	77 mm
KR 360 L240-3 F				
KR 360 L280-3	2,040 mm	1,059 mm	100 mm	77 mm
KR 360 L280-3 F				
KR 500-3	1,803 mm	1,053 mm	78 mm	77 mm
KR 500-3 F				
KR 500-3 C				
KR 500 L340-3	2,290 mm	1,069 mm	122 mm	77 mm
KR 500 L340-3 F				
KR 500 L420-3	2,040 mm	1,059 mm	100 mm	77 mm
KR 500 L420-3 F				
KR 500 L420-3 C				

Transportation

The robot can be transported by fork lift truck or using lifting tackle.



WARNING Use of unsuitable handling equipment may result in damage to the robot or injury to persons. Only use authorized handling equipment with a sufficient load-bearing capacity. Only transport the robot in the manner specified here.

Transportation by fork lift truck

For transport by fork lift truck (>>> Fig. 7-3), two fork slots are provided in the base frame. The robot can be picked up by the fork lift truck from the front and rear. The base frame must not be damaged when inserting the forks into the fork slots. The fork lift truck must have a minimum payload capacity of 3,500 kg and an adequate fork length.

Ceiling-mounted robots can only be transported by fork lift truck.

NOTICE

Avoid excessive loading of the fork slots through undue inward or outward movement of hydraulically adjustable forks of the fork lift truck. Failure to do so may result in material damage.

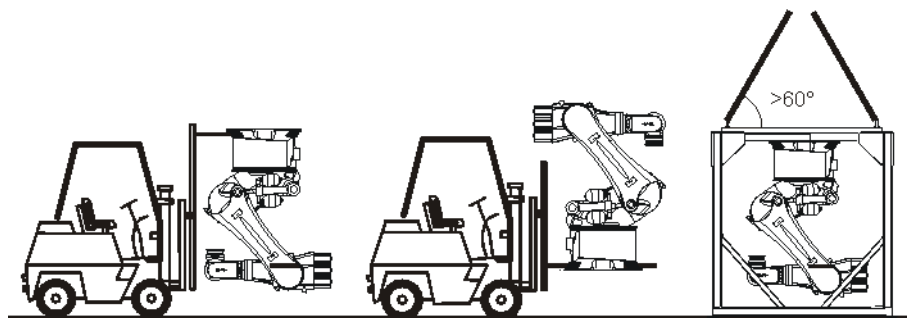


Fig. 7-3: Transportation by fork lift truck

Transportation with lifting tackle

The robot can also be transported using lifting tackle. The robot must be in the transport position.

The lifting tackle must be attached using 3 M20 DIN 580 eyebolts and positioned along the robot as illustrated (>>> Fig. 7-4). The lifting tackle must consist of 3 legs of the following length:

- Length of leg G1: 2020 mm
- Length of leg G2: 2140 mm
- Length of leg G3: 1480 mm

All the legs must be long enough and must be routed in such a way that the robot is not damaged. Installed tools and items of equipment that could be damaged during transportation must be removed.

Installed tools and items of equipment can cause undesirable shifts in the center of gravity, which are liable to cause a collision during transportation. The user shall be liable for any damage to the robot or to other material property resulting from this.

Tools and items of equipment must be removed from a robot before it is exchanged.

WARNING

The robot may tip during transportation. Risk of personal injury and damage to property.

If the robot is being transported using lifting tackle, special care must be exercised to prevent it from tipping. Additional safeguarding measures must be taken. It is forbidden to pick up the robot in any other way using a crane!

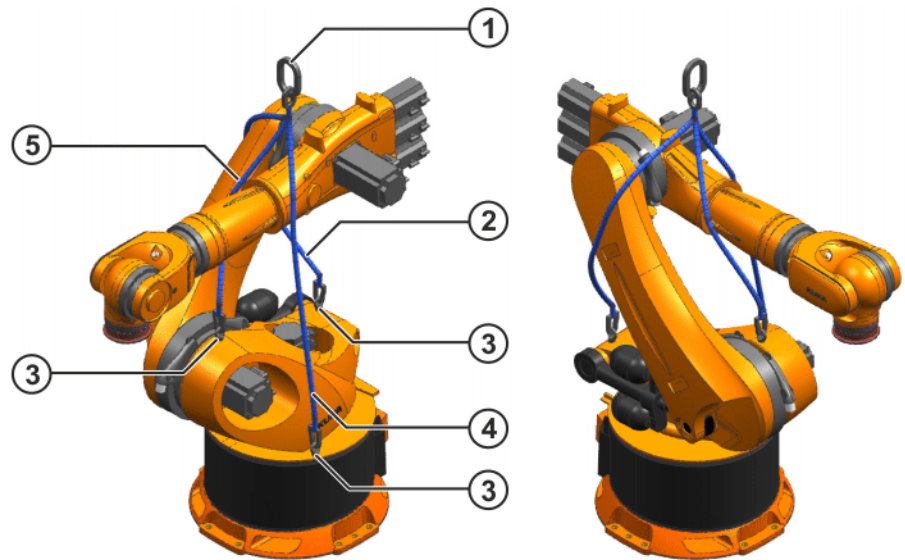


Fig. 7-4: Transportation using lifting tackle

- 1 Lifting tackle assembly
- 2 Leg G1 (length: 2020 mm)
- 3 M20 DIN 580 eyebolt
- 4 Leg G2 (length: 2140 mm)
- 5 Leg G3 (length: 1480 mm)

8 KUKA Service

8.1 Requesting support

Introduction The KUKA Roboter GmbH documentation offers information on operation and provides assistance with troubleshooting. For further assistance, please contact your local KUKA subsidiary.

Information The following information is required for processing a support request:

- Model and serial number of the manipulator
- Model and serial number of the controller
- Model and serial number of the linear unit (if applicable)
- Model and serial number of the energy supply system (if applicable)
- Version of the KUKA System Software
- Optional software or modifications
- Archive of the software
- Application used
- Any external axes used (if applicable)
- Description of the problem, duration and frequency of the fault

8.2 KUKA Customer Support

Availability KUKA Customer Support is available in many countries. Please do not hesitate to contact us if you have any questions.

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