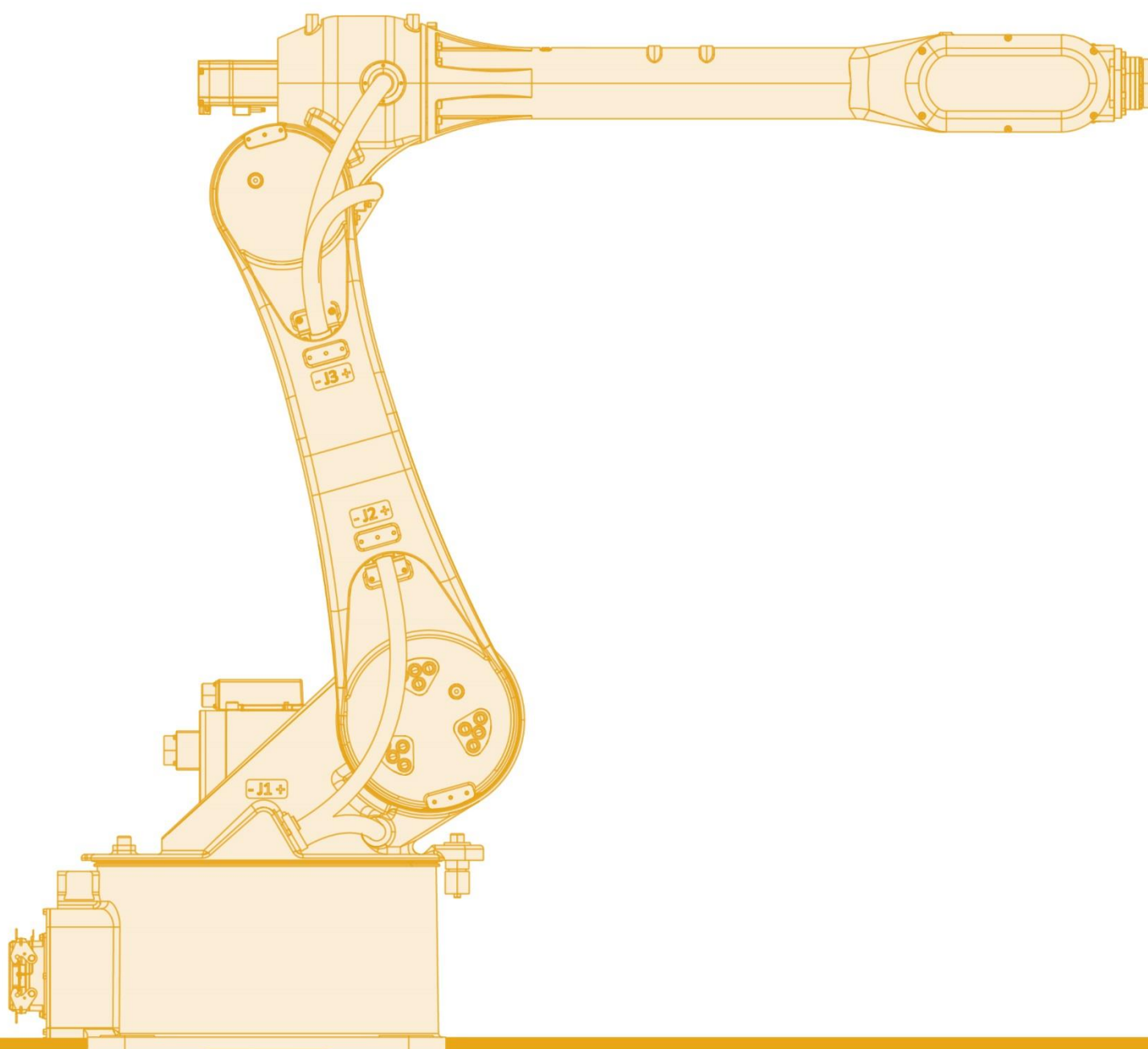


AIR20-2000B Operation Manual

V1.0.5



Foreword

About this manual

This manual is for technicians to install and use the AIR20-2000B industrial robot quickly, correctly, and safely, to be familiar with the relevant precautions, and to perform regular routine maintenance work on the manipulator.

Prerequisites

Before operating the robot, be sure to read the relevant safety instructions and operation instructions of the product carefully. Users must understand the safety knowledge and basic operation knowledge before using the robot.

Please read the following documents when necessary:

- "inCube22 Control Cabinet Manual"
- "AIR-TP teach pendant operation manual"
- "ARL Programming Manual"



Target groups



- Operators
- Product technicians
- Technical service personnel
- Robot teachers

Meaning of common signs

The signs and their meanings in this manual are detailed in Table 1.

Table 1 Signs used in this manual

Sign	Meaning
 Danger	Failure to follow the instructions may result in an accident causing the severe or fatal injury or the great losses of property.
 Warning	Failure to follow the instructions may result in an accident causing the severe or fatal injury or the great losses of property.

Sign	Meaning
 Caution	Prompt for the environmental conditions and important things or shortcuts you shall pay attention to
 Prompt	Prompt for additional literature and instructions for additional information or more detailed operating instructions

Manual description

The contents of this manual are subject to supplementation and modification. Please visit "Download Center" on the website regularly to obtain the latest version of this manual in a timely manner.

Website URL: <http://robot.peitian.com/>

Revision history

The revision history contains the instructions for each document update. The latest version of the document contains updates to all previous versions of the document.

Table 2 Signs used in this manual

Version	Publication date	Modification description
V1.0.0	2021.12.20	1st official release
V1.0.1	2022.01.04	2nd official release Fix known Bug
V1.0.2	2022.01.25	3rd official release Add wall-mounted installation method
V1.0.3	2022.08.18	4th official release Update manipulator overload interface definition
V1.0.4	2022.12.02	5th official release Fix known Bug Section 9.4 adds the model and material of the lifting ring
V1.0.5	2023.03.07	6th official release Update manipulator overload interface definition

Manual Number and Version

The manual-related information is shown in Table 3.

Table 3 Document-related information

Document name	AIR20-2000B Operation Manual
Document number	UM-P05310000060-001
Document version	V1.0.5

Declaration of applicable with product standards

The requirements for industrial robot system design are detailed in Table 4.

Table 4 Declaration of applicable safety standards

Standard	Description	Version
2006/42/EC	Machinery directive: Machinery directive 2006/42/EC (new version) issued by European Parliament and Council on May 17, 2006 to modify 95/16/EC	2006
2014/30/EU	Electromagnetic compatibility directive: 2014/30/EU directive issued by European Parliament and Council on February 26, 2014 to balance the electromagnetic compatibility regulations of member states	2014
2014/68/EU	Pressure facility directive: Electromagnetic compatibility directive: 2014/68/EU directive issued by European Parliament and Council on May 15, 2014 to balance the pressure facility regulations of member states (It is only suitable for the robot with hydraulic balance weight)	2014
ISO 13850	Safety of machinery: Emergency stop function - Principles for design	2015
ISO 13849-1	Safety of machinery: Safety-related parts of control systems - Part 1: General principles for design	2015
ISO 12100	Safety of machinery: General principles for design - Risk assessment and risk reduction	2010
ISO 10218-1	Robots and robotic devices - Safety requirements for industrial robots: Part 1: Robots (Prompt: Information is consistent with ANSI/RIAR.15.06-2012, Part 1)	2011
61000-6-2	Electromagnetic compatibility (EMC): Part 6-2: Generic standards - Immunity for industrial environments	2005
61000-6-4 + A1	Electromagnetic compatibility (EMC): Part 6-4: Generic standards - Emission standard for industrial environments	2011

Standard	Description	Version
60204-1 + A1	Safety of machinery: Electrical equipment of machines - Part 1: General requirements	2009
IEC 60529	IP rating provided by enclosures (IP Code): This standard applies to the IP rating for the electrical equipment with enclosures and the rated voltage exceeding 72.5kv.	2001

General safety description

Thank you for purchasing our manipulator. This description is required for the safe use of the manipulator. before using the operator, please read the manual carefully and use the manipulator correctly on the premise of understanding it.

For the detailed functions of the manipulator, please fully understand its specifications through the relevant instructions.

Safety considerations

In general, the manipulator cannot be operated by a single operation, and only install the end effector, and the frame functions as the peripheral equipment and the system to perform the operation.

When considering its security, the manipulator should not be considered independently, but should be considered in the system environment.

When using the manipulator, be sure to take corresponding measures to the safety fence.

WARNING, CAUTION AND PROMPTS.

This specification includes matters needing attention to ensure the personal safety of operators and prevent damage to operators. According to their safety importance, they are described as "warning" and "caution" in this paper, and the supplementary instructions are described as "prompts".

Before using the operator, the user must read these "warnings ", "cautions" and "prompts ".



In the case of an incorrect operation, it is possible to cause death or serious injury to the operator or other operator.




If the operation is wrong, it may cause the manipulator or other manipulator to slightly injure or damage the equipment.


General considerations





- When connecting or disconnecting related peripheral devices (such as safety fences, etc.) and various signals of the manipulator, be sure to confirm that the manipulator is in a stopped state to avoid incorrect connections.
- Do not use the operator in the situation shown below. Otherwise, it will not only have a negative impact on operators and peripherals, but also cause casualties.

	<ul style="list-style-type: none"> ● Used in flammable environments. ● Used in explosive environments. ● Used in environments where there is a lot of radiation. ● Used in water or in high humidity environments. ● Used for the purpose of transporting people or animals. ● Use as a foot (e.g., on or depending on the operator) ■ Operators who use the operator should wear the safety appliances shown below before carrying out their work. <ul style="list-style-type: none"> ● Work clothes suitable for the job content ● Safety shoes ● Safety helmet
 Prompt	Personnel who carry out programming and maintenance operations must receive appropriate training through the relevant training of the company.


Considerations during installation



 Warning	<ul style="list-style-type: none"> ■ When handling and installing the machines, they must be carried out correctly according to the method shown in our manual. If the operation is carried out in the wrong way, it is possible that the operator will be killed or injured due to the overturning of the operator. ■ When using the operator for the first time after installation, be sure to do so at a low speed, and then gradually accelerate the speed and confirm that there are any anomalies.
--	--

Matters needing attention in operation


 Warning	<ul style="list-style-type: none"> ■ When using the operator, be sure to make sure there are no personnel in the safety fence before carrying out the operation. At the same time, check to see if there is a potential danger, and when it is confirmed that there is a potential danger, be sure to eliminate the danger before carrying out the operation. ■ When using the instruction device, because there may be errors in the operation of wearing gloves, it is important to take off the gloves before carrying out the work.
 Prompt	Information such as programs and system variables can be stored in storage media such as memory cards. In order to prevent data loss caused by unexpected accidents, it is recommended that users back up data regularly.

Considerations in programming

 Warning	When programming, try to do it outside the safety fence, the following matters shall be taken into account when the safety fence needs to be carried out as a last resort:
--	--

	<ul style="list-style-type: none"> ■ Check the safety fence carefully and make sure it is not dangerous before entering the fence. ■ The emergency stop button can be pressed at any time. ■ The manipulator shall be operated at low speed ■ The operation should be carried out after confirming the state of the whole system, so as to avoid the operator falling into a dangerous situation due to the remote-control instructions or actions for the peripheral equipment.
 <p>Caution</p>	<p>After the program is finished, it is important to perform the test operation in accordance with the specified procedure. At this time, the operator must operate outside the safety fence.</p>
 <p>Prompt</p>	<p>For operators who are programmed, it is important to receive appropriate training through the company.</p>

Attention should be paid to maintenance work

 <p>Warning</p>	<ul style="list-style-type: none"> ■ When switching on the power supply, part of the maintenance operation is in danger of electric shock, as far as possible, the maintenance operation should be carried out in the state of power off; professional maintenance personnel should be designated according to the need to carry out maintenance operation; other personnel should be avoided to turn on the power supply when maintaining the operation; even if the power supply must be turned on before the operation can be carried out, the emergency stop button should be pressed and then the operation should be carried out. ■ Please consult our company when you need to replace the parts. ■ The replacement of parts by the client may result in unexpected accidents, which may cause the operator to be damaged and the operator is injured. ■ When entering the security fence, check the whole system carefully and make sure it is not dangerous. If there is a dangerous situation and have to enter the fence, you must grasp the state of the system and be very careful. ■ If you need to replace the parts, be sure to use our specified parts. If you use a part other than the specified part, it may cause damage to the operator. ■ When removing the motor and brake, the crane hoisting and other measures should be taken to remove the motor and brake, so as to avoid the falling of the manipulator arm. ■ When carrying out maintenance operations, when it is necessary to move the operator as a last resort, the following matters should be taken into account: <ul style="list-style-type: none"> ● It is important to ensure that the escape channel is smooth and that the operation should be carried out again under the operation of the whole system in order to avoid blockage of the retreat by the operator and peripherals.
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- Always pay attention to the danger around you and be prepared so that you can press the emergency stop button at any time when you need it.
- The auxiliary equipment such as the crane shall be used when the moving motor and the speed reducer and the like have certain weight parts, so as to avoid the excessive work load for the operators. At the same time, it is necessary to avoid the wrong operation, otherwise, the operation and death of the operation may be caused.
- Be careful not to fall because of the lubricating oil that falls on the ground, wipe the lubricating oil that falls on the ground as soon as possible, and eliminate the possible danger.
- Do not place any part of the body on any part of the manipulator during the operation, and it is prohibited to climb on the manipulator, so as to avoid unnecessary personal injury or adverse effect on the manipulator.
- The following parts will be hot and need attention. When you have to touch the equipment when you have to touch it in the event of heat, you should prepare protective appliances such as heat-resistant gloves:
 - Servo motor
 - reducer
 - Adjacent to motor / reducer
 - Inside the control cabinet
- The parts (such as screws, etc.) removed during the replacement of the parts should be correctly loaded back to their original parts, and if the parts are found to be insufficient or surplus, they should be reconfirmed and installed correctly.
- During the maintenance of the pneumatic system and hydraulic system, it is important to release the internal pressure to zero and operate again.
- After replacing the parts, be sure to carry on the test operation according to the prescribed method. At this point, the operator must operate outside the safety fence.
- After the maintenance operation, the grease, debris and water sprinkled on the ground around the operator and inside the safety fence should be thoroughly cleaned.
- When replacing parts, dust and other foreign bodies should be prevented from entering the manipulator.
- Operators who carry out maintenance and repair operations must receive the training of the company and pass the relevant assessment.
- When carrying out maintenance operations, appropriate lighting appliances should be equipped, but care should be taken not to make the lighting appliances a source of new danger.
- Be sure to refer to this specification for regular maintenance, if not regular maintenance, will affect the service life of the operator, and may lead to accidents.

Safety protection measures before use

Before operating the manipulator and peripheral equipment and the manipulator system composed of them, the safety precautions of the operators and the system must be fully studied.

Figure 1 is a diagram of the safe work of industrial robots.

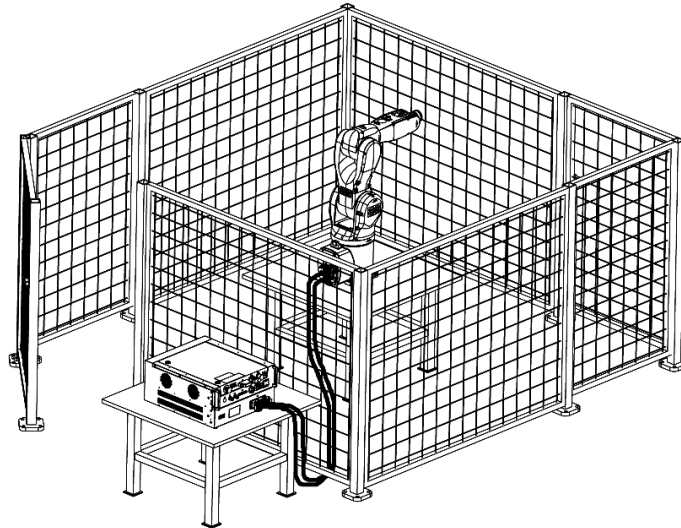


Figure 1 Diagram of safe work of industrial robots

Definition of operating personnel

Manipulator operation personnel consist of operator, teacher and maintenance engineer who shall satisfy the following conditions:

Operator

- Switch on/off the power supply of manipulator.
- Start the manipulator program via the operating panel.
- have no right to operate within the safety barrier

Teacher

- Execute the functions of operator.
- Perform the manipulator teaching, etc. outside the safety barrier.

Maintenance Engineer

- Execute the functions of teacher.
- Perform the maintenance (repair, adjustment, replacement, etc.) of manipulator.

Safety of operation personnel

Operator, teacher and maintenance engineer shall carefully perform the operation, programming and maintenance of manipulator, and shall at least wear the following items:

- Work clothes suitable for task
- Safety shoe
- Helmet

When the auto system is used, be sure to protect the operation personnel. The measures shall be taken to prevent the operation personnel from entering the range of manipulator.

The general precautions are listed below. Please take the appropriate measures to ensure the safety of operation personnel:

- The operation personnel running the manipulator system shall receive the training from the company and pass the relevant assessment.
- While the equipment is running, even if the manipulator seems to have stopped, the manipulator is possibly waiting for the start signal and is about to act. The manipulator shall be regarded as operating at this state. To ensure the safety of operation personnel, it is necessary to confirm that the manipulator is in the operating state via the audible and visual alarms such as the warning lamp
- Be sure to set the safety barrier and safety door around the system so that the operation personnel cannot enter the safety barrier without opening the safety door. The interlock switch, safety pin, etc. shall be set on the safety door so that when the operator opens the safety door, the manipulator will stop.
- Peripheral equipment shall be electrically grounded.
- The peripheral equipment shall be set outside the range of manipulator if possible.
- The range of manipulator shall be clearly marked with the lines on the floor to make the operator understand the range of manipulator including the mechanical arm and other tools.
- A proximity switch or photoelectric switch shall be installed on the floor so that when the operation personnel are about to enter the range of manipulator, the audible and visual alarms such as the buzzer are issued to stop the manipulator, thereby ensuring the safety of operation personnel.
- A lock shall be set to make sure that the manipulator power cannot be turned on except by the operation personnel responsible for the operation.
- Always disconnect the manipulator power when performing the individual commissioning of peripheral equipment.

Safety of operators

Operators are not authorized to perform jobs within the safety barrier:

- Disconnect the power supply of manipulator control cabinet or press the emergency stop button when the manipulator is not operated.
- Operate the manipulator system outside the safety barrier.

- The guard fence and safety door shall be provided to prevent the unrelated personnel from entering the range of manipulator or to prevent operators from entering a hazardous location.
- Emergency stop button shall be set within the reach of operators.



Prompt

Manipulator controller is designed to be connected to an external emergency stop button. With this connection, the manipulator will stop when the external emergency stop button is pressed.

Safety of teachers

In some cases, it is necessary to enter the scope of operation of the manipulator when carrying out the operation of the manipulator, especially at this time, the safety should be paid attention to:

- If you do not need to enter the operation maneuvering range, be sure to operate outside the operating maneuvering range.
- Before proceeding with the teaching, verify that the manipulator or peripheral equipment is in a safe state.
- If it is inevitable to enter the range of manipulator to conduct the teaching, first confirm the positions and states of safety devices (such as the emergency stop button, emergency automatic stop switching of teach pendant, etc.).
- Teachers shall pay special attention to make other people away from the range of manipulator
- Before starting the manipulator, first confirm that there is no people and no abnormality in the range of manipulator.
- After the teaching is over, be sure to perform the test run following the steps below:
 - step1. At low speed, execute at least one cycle intermittently to confirm no abnormality.
 - step2. At low speed, execute at least one cycle continuously to confirm no abnormality
 - step3. At intermediate speed, execute at least one cycle continuously to confirm no abnormality
 - step4. At operating speed, execute at least one cycle continuously to confirm no abnormality
 - step5. Execute the program in automatic operation mode.
- The teacher must evacuate outside the safety fence when the operator operates automatically.

Safety of repair engineer

To ensure the safety of repair engineer, full attention shall be paid to the following items:

- Never enter the range of manipulator while the manipulator is running.

- Perform the repair operation while the controller is powered off if possible. Main circuit breaker shall be locked to prevent other personnel from turning on the power.
- If it is inevitable to enter the range of manipulator when it is powered on, you shall first press the emergency stop button of control cabinet or teach pendant. In addition, the operators shall hang the "Repairing" sign to remind other people not to operate the manipulator.
- Before performing a repair, verify that the manipulator or peripheral equipment is in a safe status.
- Do not perform the automatic operation when there is someone in the range of manipulator.
- When working near the walls and appliances, or when several operators are close to each other, be careful not to block the escape routes of other operators.
- When the manipulator is equipped with a tool, and there are movable devices such as conveyor belts in addition to the manipulator, pay attention to the operation of these devices.
- A person who is familiar with the manipulator system and is able to detect the danger shall be assigned next to the operating panel and operating box so that he can press the emergency stop button at any time.
- When replacing or reassembling the parts, be sure to prevent the foreign matters from sticking or entering.
- In case of the repair inside the controller, If the unit, printed circuit board, etc. may be contacted, be sure to disconnect the power supply of main circuit breaker of controller to prevent electric shock.
- Be sure to replace with the parts designated by us.
- When the manipulator system is restarted after the repair operation, it shall be confirmed in advance that there are no people in the range of manipulator, and the manipulator and peripheral equipment are in a normal status.

Safety of peripheral equipment

Precautions in terms of procedures:

- The detection devices such as the limit switch shall be used to detect the dangerous status, and the manipulator shall be stopped as needed according to the signals of detection device.
- In case of abnormalities of other manipulators or peripheral equipment, the measures shall be taken, such as stopping the manipulator, even if there is no abnormality in the manipulator.
- For the system of which the manipulator is operating synchronously with the peripheral equipment, special care shall be taken to avoid the interference with each other.

- The manipulator may be interlocked with peripheral equipment and the manipulator may be stopped if required so as to control the status of all devices in the system from the manipulator.

Mechanical precautions:

- Manipulator system shall be kept clean and the use environments shall be free of grease, water, dust, etc.
- Do not use the cutting fluids and cleaning agents of unknown nature.
- Limit switches and mechanical brakes shall be used to limit the operation of manipulator to avoid the collisions between the manipulator and peripheral equipment.
- User cables and hoses shall not be added to the manipulator.
- When installing the cable outside the manipulator, do not interfere with the movement of machine.
- For the models of which the cable is exposed, do not conduct the modification that will interfere with the exposed part of cable.
- When installing the external device on the manipulator, be sure not to interfere with other parts of manipulator.
- For the manipulator in action, the frequent power-off operation via the emergency stop button may lead to the fault of manipulator.

Mechanical safety of manipulator

Precautions for operation:

When the manipulator is operated in slow feed mode, the operators shall be highly vigilant regardless of the circumstances and quickly respond to various problems.

Precautions in terms of procedures:

If the ranges of multiple manipulators overlap, care shall be taken to avoid the interference between manipulators.

Be sure to specify an operation origin for the manipulator program and create a program that starts and ends at the origin, so that it is clear from the outside whether the manipulator operation has ended.

Mechanism precautions:

The working environments of manipulator shall be kept clean and free of grease, water, dust, etc.

Safety of end effector

When controlling various types of transmissions (pneumatic, hydraulic, and electrical), after issuing the control command, be sure to fully consider the time difference from the issuance to the actual action and conduct the control with certain room of extension and retraction.

A detection unit shall be set on the end effector to monitor the status of end effector and control the action of manipulator.

Contents

Foreword.....	I
General safety description	V
Safety protection measures before use	IX
Contents	i
1 Overview and basic composition of the AIR20-2000B manipulator	1
1.1 Overview of industrial Robot.....	1
1.2 Basic composition	1
1.3 Basic specifications.....	2
1.4 Product naming rules	3
1.5 Environmental Requirements for Operation.....	3
2 AIR20-2000B manipulator identification definition and meaning.....	5
2.1 Safety sign of manipulator	5
2.2 Manipulator nameplate.....	5
2.3 Direction sign of each axis	6
3 Preparation for installation of AIR20-2000B manipulator.....	7
3.1 Check item.....	7
3.2 Installation tool and required connectors	7
4 AIR20-2000B manipulator installation	9
4.1 Technical specifications.....	9
4.2 Fixed mode.....	9
5 Electrical connection of the AIR20-2000B manipulator	13
5.1 Heavy-duty type of manipulator.....	13
5.2 Definitions of heavy-duty interfaces of manipulator.....	13
6 Adaptation and connection of the AIR20-2000B manipulator and accessories	17
6.1 Examples of accessory types.....	17
6.2 Connection mode	18
6.3 Grounding method of the manipulator.....	18
7 Performance parameters of the AIR20-2000B manipulator	19
7.1 Basic specification	19
7.2 Dimension and working range of each axis	19
7.3 Mechanical limit.....	20
7.4 Speed of each axis	21
7.5 Output flange size	21
7.6 Load and installation method.....	22
8 Calibration of the axes of the AIR20-2000B manipulator.....	27

8.1	General	27
8.2	When calibration is required	27
8.3	Calibration position of each Joint	27
9	AIR20-2000B manipulator transportation and handling	31
9.1	Handing dimensions.....	31
9.2	Handing posture.....	32
9.3	Handing with forklift	33
9.4	Handing with swinging ring.....	34
10	General principles of maintenance.....	35
11	Maintenance items	37
11.1	Daily maintenance.....	37
11.2	First maintenance.....	37
11.3	Regular maintenance	38
12	Project maintenance process	41
12.1	Cleaning of manipulator.....	41
12.2	Check and repair of cable.....	41
12.3	Battery replacement.....	44
12.4	Replace grease	45
12.5	Replacement of synchronous belt.....	49
13	Common faults and treatment	53
14	Conditions of storage	61
14.1	Environmental conditions for long-term storage of manipulator	61
14.2	Precautions for storage of manipulator.....	61
	Appendix A Periodic maintenance schedule of AIR20-2000B manipulator.....	62
	Appendix B Table of screw strength and tightening torque (Nm).....	65

1 Overview and basic composition of the AIR20-2000B manipulator

1.1 Overview of industrial Robot

Industrial robot consists of the following parts is as shown in Figure 1-1:

- Manipulator
- Control cabinet
- Teach pendant
- Connecting cable [power supply], etc.

Figure 1-1 is an example of the composition of the industrial robot system.

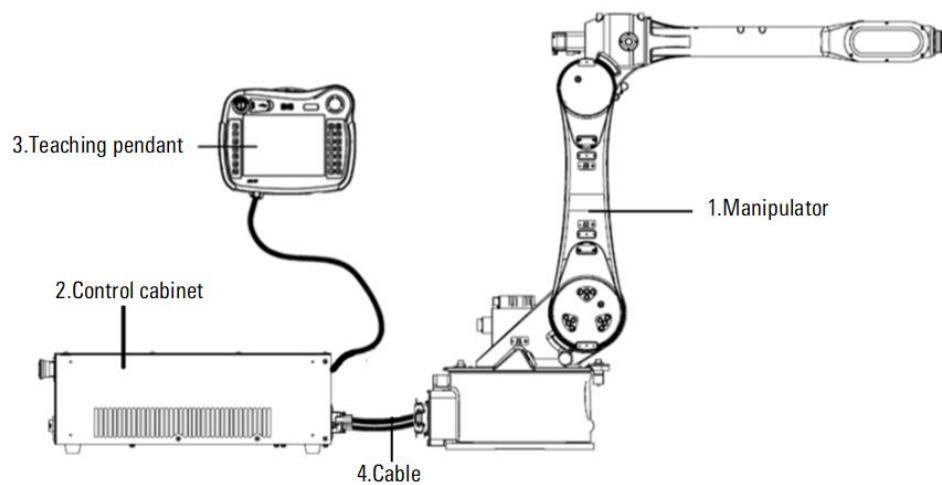


Figure 1-1 Composition of robot system-incube22

1.2 Basic composition

Manipulator refers to the mechanism of robot system to grab or move the objects (tools or workpieces), also known as the robot body. This manipulator is the 6-DOF tandem industrial robot that consists of three swing axes and three rotating axes.

The AIR20-2000B manipulator and the names of its various parts are as shown in Figure 1-2.

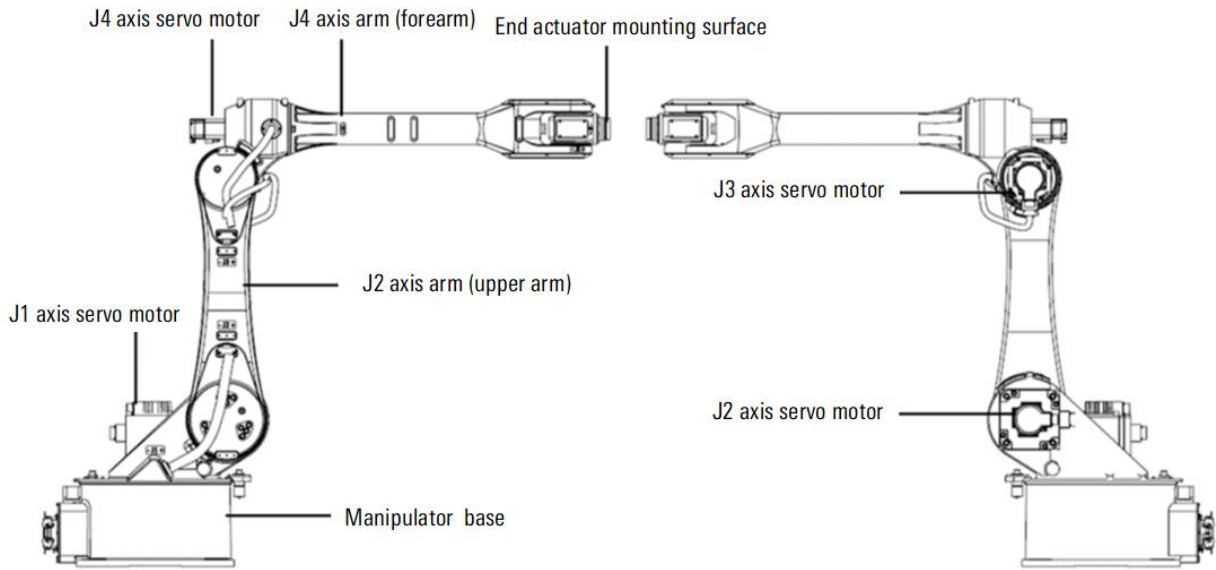


Figure 1-2 AIR20-2000B robot body and its various parts

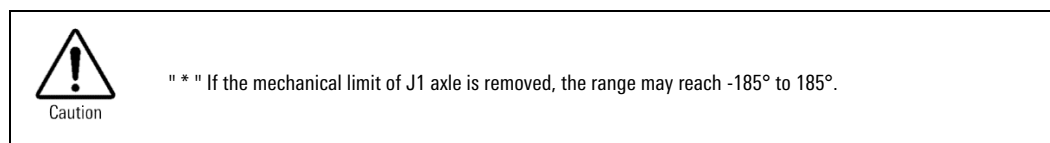
1.3 Basic specifications

The basic specifications of AIR20-2000B robot manipulator are as shown in Table 1-1:

Table 1-1 Basic specifications of AIR20-2000B robot

Parameter		Explanation
Coordinate form		6-DOF articulated robot
Number of control axes		6 axes(J1,J2,J3,J4,J5,J6)
Mounting mode		Ground installation, hoisting installation and wall installation
Range (Upper limit/ lower limit)	J1*	-170° ~170°
	J2	-95° ~155°
	J3	-95° ~170°
	J4	-185° ~185°
	J5	-135° ~135°
	J6	-400° ~400°
Max speed	J1	175° /s
	J2	175° /s
	J3	170° /s
	J4	355° /s
	J5	355° /s
	J6	600° /s
Transport capacity	Wrist	20kg
	Elbow	12kg

Parameter	Explanation
Drive mode	Electrical servo drive with AC servo motor
Repeated positioning accuracy	$\pm 0.03\text{mm}$
Robot weight	296kg
Noise	70dB
IP rating	IP54 (Wrist IP67)
Mounting conditions	<ul style="list-style-type: none"> ■ Ambient temperature :5°C ~45°C ■ Humidity: not more than 95% at constant temperature without condensation ■ Allowable altitude: not more than 1,000m above sea level ■ No corrosive, flammable or explosive gases



1.4 Product naming rules

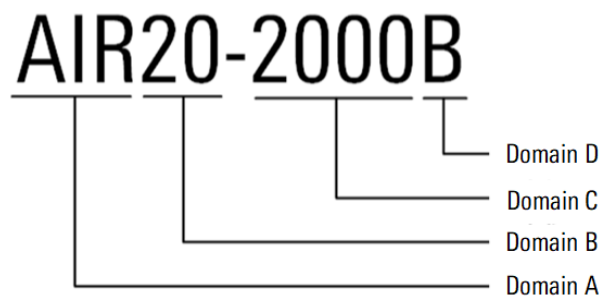


Figure 1-3 Diagram of product naming rules


Table 1-2 Description of product naming rules

Domain	Meaning	Domain value	Explain
Domain A	Product range	AIR	It means that this product belongs to the product series of Peitian AIR
Domain B	Wrist load	20	Indicates that the wrist load of the robot does not exceed 20kg
Domain C	Arm extension	2000	Indicates the arm extension of the robot is 2000mm
Domain D	Generation system	B	Indicates the second generation

1.5 Environmental Requirements for Operation

See Table 1-3 for the operating environment requirements of AIR20-2000B manipulator.

Table 1-3 Operating environment requirements for AIR20-2000B manipulator

Parameter	Explanation	
Temperature	Minimum temperature	5°C
	Maximum temperature	45°C
	 Caution When the ambient temperature is lower than 10°C, it is recommended to heat up the engine for a few minutes before use to avoid robot alarm or performance degradation caused by the change of grease viscosity	
Humidity	The installation environment of the operator shall not exceed the humidity level not higher than 95% specified in the document "IEC 60721-3-3-2002 classification of environmental conditions"	
Altitude	The altitude of the normal working environment of the operator shall not exceed 1000m. Within the altitude range of 1000m-4000m, the manipulator shall be derated for use	
Vibration strength	The manipulator shall be used in an environment without vibration as far as possible. The limit frequency of environmental vibration is 22Hz and the amplitude shall not exceed 0.15mm	
Special environmental requirements	It is forbidden to use this machine in flammable, explosive and corrosive environment	

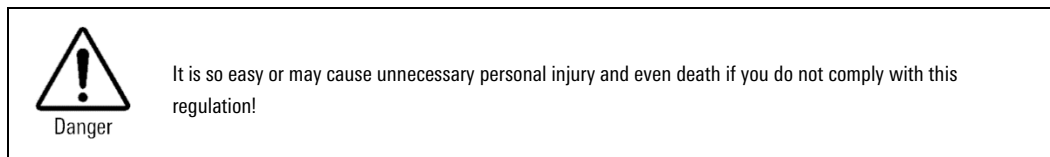
2 AIR20-2000B manipulator identification definition and meaning

2.1 Safety sign of manipulator

A manipulator safety label shall be pasted on the back of the upper arm of the manipulator. As shown in Figure 2-1.



Figure 2-1 Safety signs on the manipulator



2.2 Manipulator nameplate

The nameplate of the manipulator can be seen on the base of the manipulator. The nameplate contains the corresponding model, version number, weight, serial number, production date and other information. As shown in Figure 2-2.

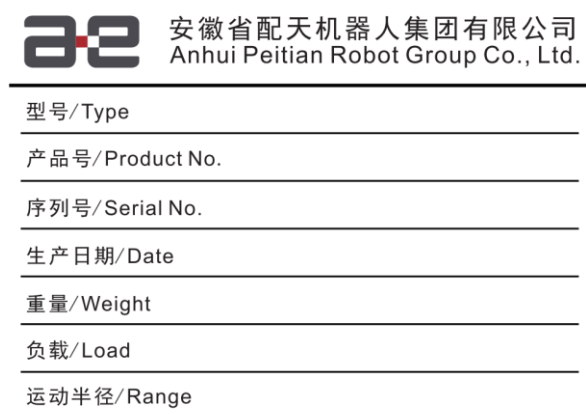


Figure 2-2 Robot nameplate

2.3 Direction sign of each axis

"+" or "-" sign is provided at the rotating or swinging joints of axes 1~6 of manipulator as shown in Figure 2-3 to indicate the moving direction of each Joint. "J1" in sign represents the axis 1 (other axes are represented by the corresponding numbers), "+" indicates the positive direction, and "-" indicates the negative direction.

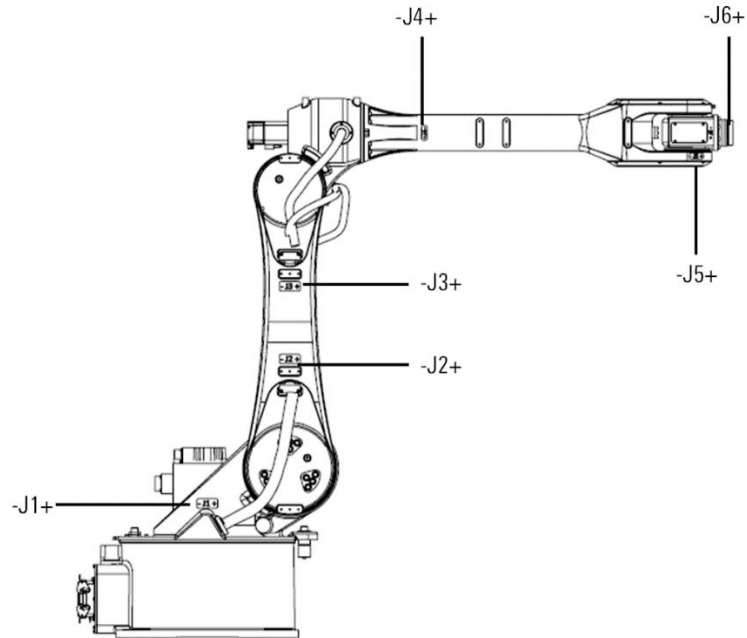


Figure 2-3 Direction sign of each joint on manipulator

3 Preparation for installation of AIR20-2000B manipulator

3.1 Check item

Following requirements shall be strictly adhered to before installation:

- Ensure that the installers pass the relevant training of company and perform the installation according to the international and local laws and regulations.
- After the unpacking, make sure that the product is not bumped or damaged
- Make sure that the carrier bracket, swinging ring screws, etc. are installed to the manipulator as required.
- Make sure the installation environments are as required by Chapter1.5.
- Make sure that the installation site can withstand the pressure or pull from the manipulator and its load.

3.2 Installation tool and required connectors

The following tools may be required to install the manipulator (more tools may be required, depending on the installation method).

- A set of Internal hexagonal wrench;
- Adjustable wrench;
- Torque wrenches of different specifications, etc.

The following connectors may be required to install the manipulator (more connectors may be required, depending on the installation method).

- Several M20 screws with appropriate length and strength grade12.9 or other hexagonal head cap screws;
- A number of chemical bolts of appropriate length and strength grade not less than 4.8;
- Several spring pads of $\Phi 20$ or other specifications;
- Several round pins ($\Phi 10$ mm). Please see Chapter4.2 in this manual for details.

4 AIR20-2000B manipulator installation

4.1 Technical specifications

The forces and torques applied to the foundation during the movement are shown in Table 4-1, Enough thought shall be given to the strength of foundation installation surface for the installation of manipulator. The installation ground inclination shall be less than 5° for manipulator.

Table 4-1 The force applied to foundation by AIR20-2000B manipulator

Load type	Force/torque/mass
Vertical force Fz	<ul style="list-style-type: none"> ■ 6.5kN (In operation) ■ 7.6kN (Emergency stop)
Horizontal force Fxy	<ul style="list-style-type: none"> ■ 6.2kN (In operation) ■ 7.2kN (Emergency stop)
Overturning torque Mxy	<ul style="list-style-type: none"> ■ 5.1kNm (In operation) ■ 10.8kNm (Emergency stop)
Rotary torque Mz	<ul style="list-style-type: none"> ■ 1.9kNm (In operation) ■ 5.1kNm (Emergency stop)
Manipulator quality	296kg
Total weight of load	52kg (20kg+12kg+20kg)

Dimensions of the AIR20-2000B manipulator base are as shown in Figure 4-1.

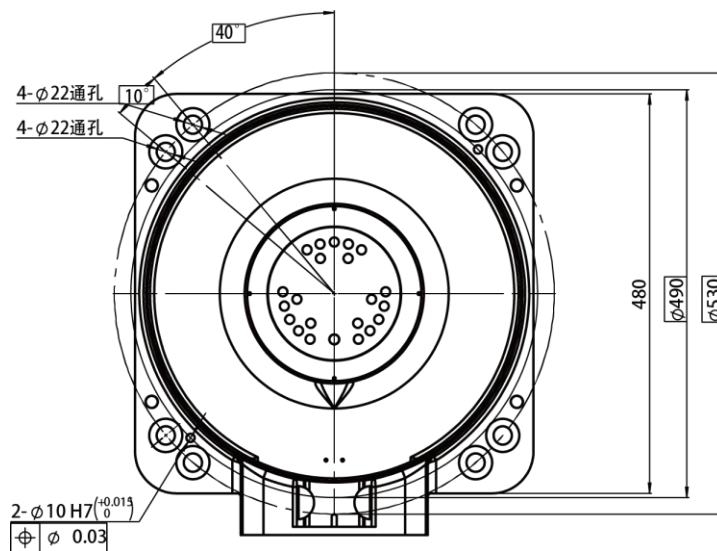



Figure 4-1 Dimensions of the AIR20-2000B manipulator base interface

4.2 Fixed mode

The manipulator supports three installation postures: ground installation, hoisting installation and wall installation. There are differences in fixing methods on the installation contact surface of different materials. When the base is fixed on the concrete floor or bracket, the following fixing methods can be used for installation:


- Ground fixation
- Bracket fixation

 Prompt	<ul style="list-style-type: none"> ■ Specific fixing mode depends on the usage environments. ■ Strength of chemical bolt is subject to the strength of concrete. Therefore, the safety shall be fully considered according to the design guidelines of manufacturer before the construction.
---	--

The names and specifications of parts required to fix the manipulator are as shown in Table 4-2.

Table 4-2 Parts for fixing the manipulator

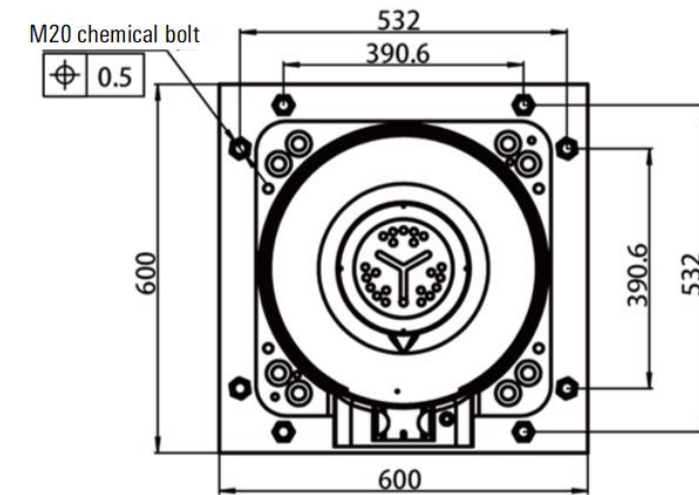
Part Name	Remarks	Ground fixation	Bracket fixation
Fixing screw	4 M20x40 (grade 12.9, 8 brackets fixed)	○	○
Fixing screw	8 M20x50 (grade 12.9)		○
Chemical bolt	8 M20 (not lower than 4.8)	○	
Fixing plate of robot	25mm thick, 1 piece	○	
Adapter plate	25mm thick, 4 pieces		○

 Prompt	<ul style="list-style-type: none"> ■ There shall be no insulating materials between the fixing plate and mounting bracket of robot and the manipulator and concrete. ■ Mark "○" means that the part is in need. ■ Bracket shall be firmly installed on the ground with the strength not less than the fixing strength between the fixing plate of robot and the ground for the ground fixing (mode 1).
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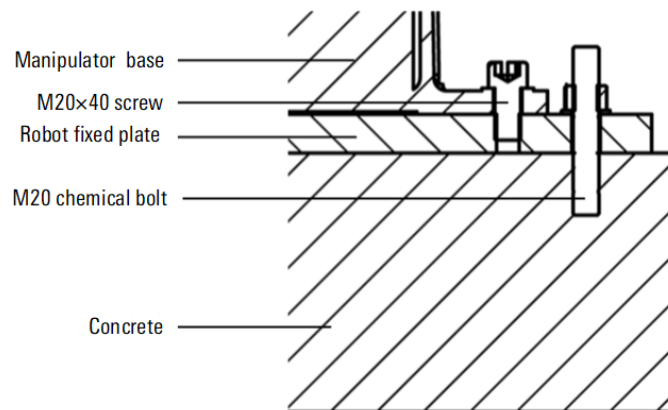
Ground fixation

Fixing steps:

- Step1. Hold the fixing plate of robot close to the mounting surface and secure it with eight M20 chemical bolts (strength not less than Grade 4.8).
- Step2. Use 4 M20x40 bolts (8 M20 bolts are required for inverted and wall mounting), with strength grade of 12.9, and fix the manipulator base on the fixed plate.



(a)



(b)

Figure 4-2 Diagram of ground fixation of manipulator



Prompt

Fixing plate surface shall meet certain roughness and flatness requirements as detailed in Figure 4-2.

Bracket fixation

Fixing steps:

Step1. Fix 4 adapter plates on the bracket with 8 M20x50 bolts (strength grade 12.9).

Step2. Fix the manipulator base on the adapter plate with 8 M20x40 bolts (strength grade 12.9).

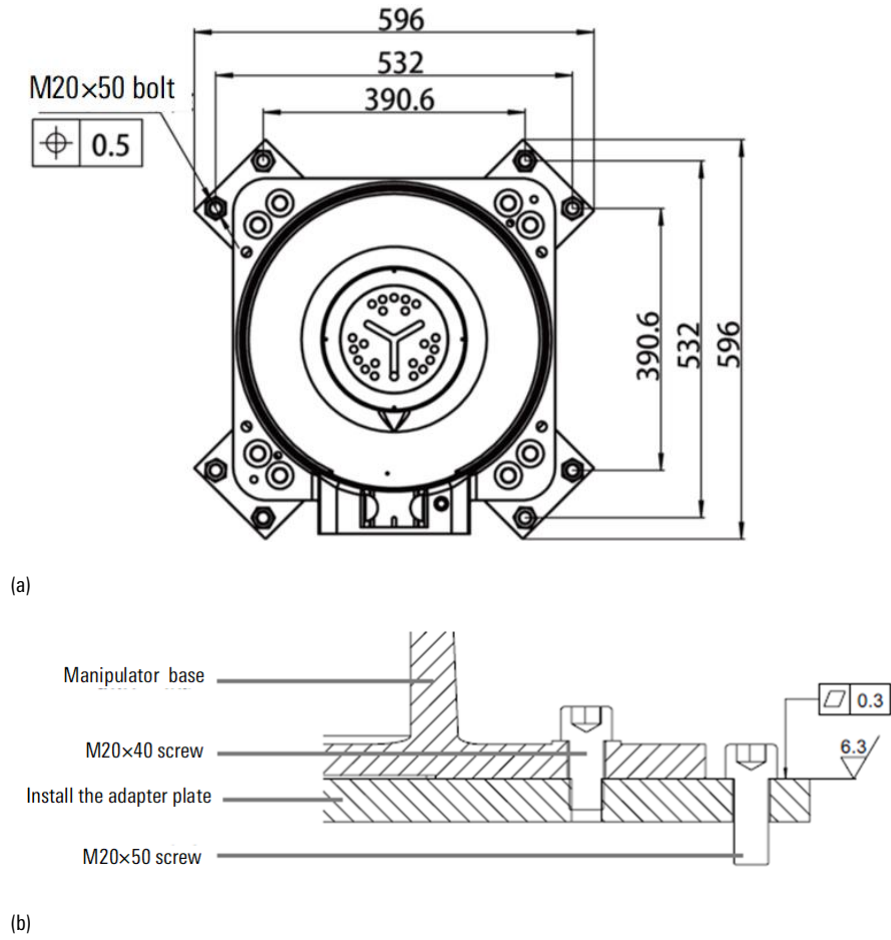


Figure 4-3 Fixing diagram of manipulator bracket

	<p>Mounting surface of bracket shall meet certain flatness requirements as shown in Figure 4-3</p>
<p>Prompt</p>	
	<ul style="list-style-type: none"> ■ Fixing screw M20 of manipulator shall not be shorter than 40 mm, and the insufficient length will cause the poor fixing and other accidents. ■ When installing the manipulator ceiling, the length of fixing screws for manipulator shall be increased to 45mm and the thickness of mounting plate shall be not less than 30mm.
<p>Warning</p>	

5 Electrical connection of the AIR20-2000B manipulator

5.1 Heavy-duty type of manipulator

The two-in-one heavy-duty connector of the AIR20-2000B manipulator, as shown in Figure 5-1.

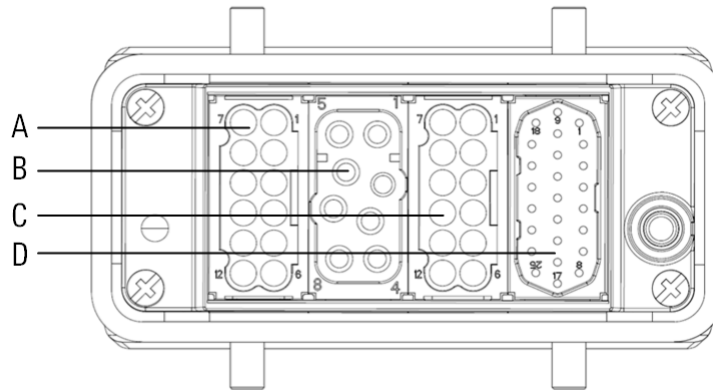


Figure 5-1 inCube22 heavy-duty connector is fitted on the AIR20-2000B manipulator

5.2 Definitions of heavy-duty interfaces of manipulator

Heavy-duty interface of AIR20-2000B manipulator is defined as shown in Table 5-1 and Table 5-2.

Table 5-1 Pin definition of Heavy-duty power line

Pin number	Definition	Internal cables	Use the pin
A 1	U1	red (J1)	CCSM-2.5
A 2	V1	white (J1)	CCSM-2.5
A 3	W1	black (J1)	CCSM-2.5
A 11	U5	red (J5)	CDSM-0.37
A 12	V5	white (J5)	CDSM-0.37
A 13	W5	black (J5)	CDSM-0.37
A 14	U3	red (J3)	CDSM-0.75
B 1	U2	red (J2)	CCSM-2.5
B 2	V2	white (J2)	CCSM-2.5
B 3	W2	black (J2)	CCSM-2.5
B 11	V3	white (J3)	CDSM-0.75
B 12	W3	black (J3)	CDSM-0.75
B 13	U4	red (J4)	CDSM-0.37
B 14	V4	white (J4)	CDSM-0.37
C 1	W4	black (J4)	CESM-0.37

Pin number	Definition	Internal cables	Use the pin
C 2	U6	blue (J6)	CESM-0.37
C 3	V6	orange (J6)	CESM-0.37
C 4	W6	grey (J6)	CESM-0.37
C 5	J1&J2_BK_24V+	brown (J1) + brown (J2)	CESM-1.0
C 6	J3&J4_BK_24V+	brown (J3) + brown (J4)	CESM-1.0
C 7	J5&J6_BK_24V+	brown (J5) + pink(J6)	CESM-0.75
C 8	BK-	yellow(J1) + yellow(J2) yellow(J3) + yellow(J4) yellow(J5) + light blue (J6)	CESM-0.37

Table 5-2 Pin definition of Heavy-duty encoder line

Pin number	Definition	Internal cables	Use the pin
D 1	J1_5V	red (J1)	CSSM-0.25
D 2	J1_0V	blue (J1)	CSSM-0.25
D 3	J1_PS+	black (J1)	CSSM-0.25
D 4	J1_PS-	yellow (J1)	CSSM-0.25
D 5	J2_5V	red (J2)	CSSM-0.25
D 6	J2_0V	blue (J2)	CSSM-0.25
D 7	J2_PS+	black (J2)	CSSM-0.25
D 8	J2_PS-	yellow (J2)	CSSM-0.25
D 9	J3_5V	red (J3)	CSSM-0.25
D 10	J3_0V	blue (J3)	CSSM-0.25
D 11	J3_PS+	black (J3)	CSSM-0.25
D 12	J3_PS-	yellow (J3)	CSSM-0.25
D 13	J4_5V	red (J4)	CSSM-0.25
D 14	J4_0V	blue (J4)	CSSM-0.25
D 15	J4_PS+	black (J4)	CSSM-0.25
D 16	J4_PS-	yellow (J4)	CSSM-0.25
D 18	J5_5V	brown (J5)	CSSM-0.25
D 19	J5_0V	white (J5)	CSSM-0.25
D 20	J5_PS+	yellow (J5)	CSSM-0.25
D 21	J5_PS-	black (J5)	CSSM-0.25
D 22	J6_5V	purple (J6)	CSSM-0.25
D 23	J6_0V	grey (J6)	CSSM-0.25

Pin number	Definition	Internal cables	Use the pin
D 24	J6_PS+	orange (J6)	CSSM-0.25
D 25	J6_PS-	green (J6)	CSSM-0.25



Caution

When the robot is connected, attention should be paid to the one-to-one correspondence between the Heavy-duty on the manipulator and the Heavy-duty on the control cabinet.

6 Adaptation and connection of the AIR20-2000B manipulator and accessories

6.1 Examples of accessory types

The accessory equipment of the manipulator mainly includes mechanical grab (Figure 6-1), hydraulic pressure sucker (Figure 6-2), welding gun welder (Figure 6-3), infrared identification equipment, visual identification equipment, cutting machine, other special equipment, etc.

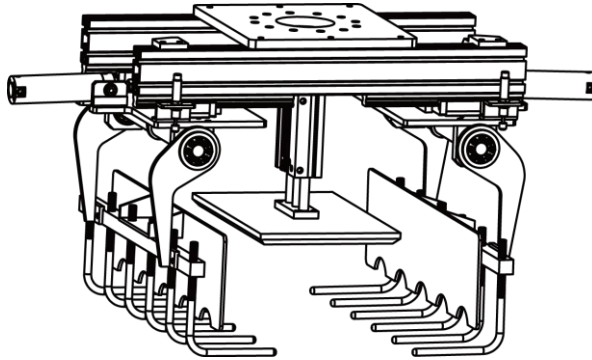


Figure 6-1 Industrial robot grab

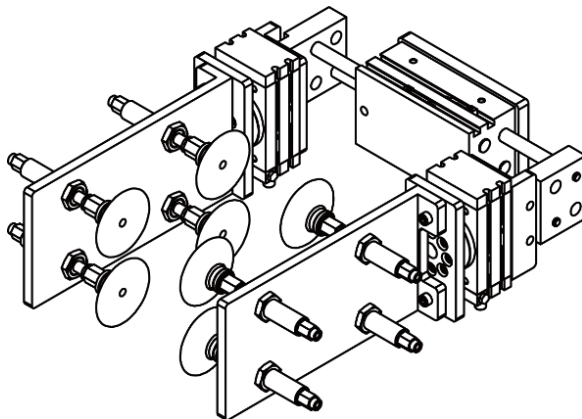


Figure 6-2 Suction cups for industrial robots

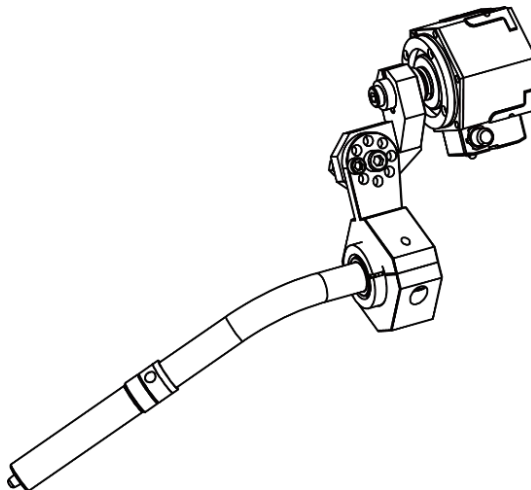


Figure 6-3 Arc welding gun for industrial robot

6.2 Connection mode

Connection between operator and accessories

The connection and load between the external auxiliary equipment and the manipulator are similar to those of the manipulator, and can be directly or indirectly connected to the manipulator through the flange. See Chapter 7.6 of this manual for details.

Connection between manipulator and control cabinet

As described in Chapter 5.2 Definitions of Heavy-duty Interfaces of manipulator of this manual, the heavy-duty connector on the manipulator is connected to the control cabinet through a cable. Both ends of the Heavy-duty line are used to connect the manipulator and the control cabinet respectively (see Figure 6-4).

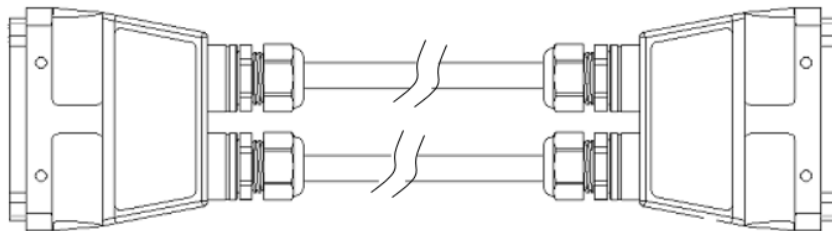


Figure 6-4 Heavy-duty line

6.3 Grounding method of the manipulator

The position of the grounding terminal on the manipulator base is shown in Figure 6-5.

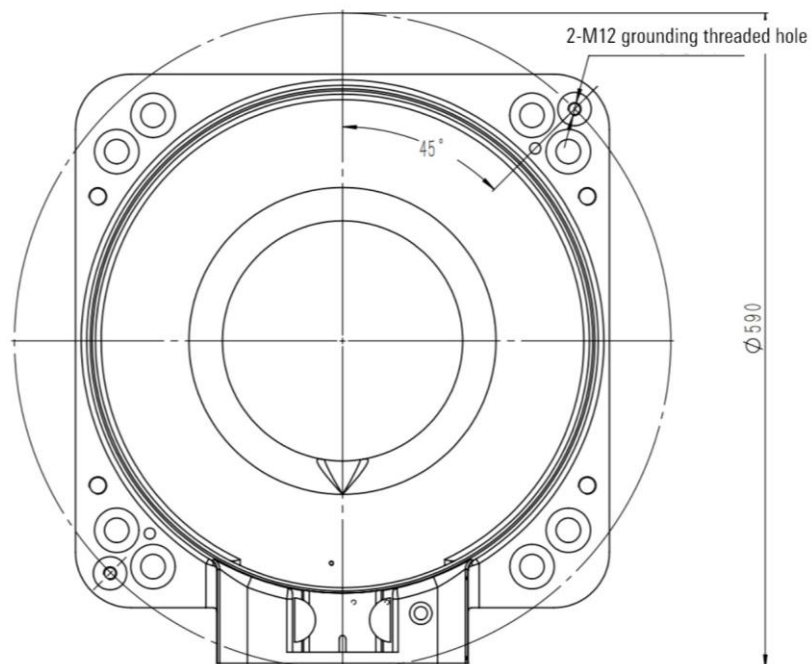


Figure 6-5 Grounding diagram of the manipulator base

7 Performance parameters of the AIR20-2000B manipulator

7.1 Basic specification

See Chapter 1.3 Basic Specifications of this manual for the basic specifications of AIR20-2000B manipulator.

7.2 Dimension and working range of each axis

The motion range of each axis of the AIR20-2000B manipulator is shown in Table 7-1 as follows.

Table 7-1 Motion range of each axis of AIR20-2000B manipulator

Axis number	Motion range (°)
J1*	-170 ~ +170
J2	-95 ~ +155
J3	-95 ~ +170
J4	-185 ~ +185
J5	-135 ~ +135
J6	-400 ~ +400

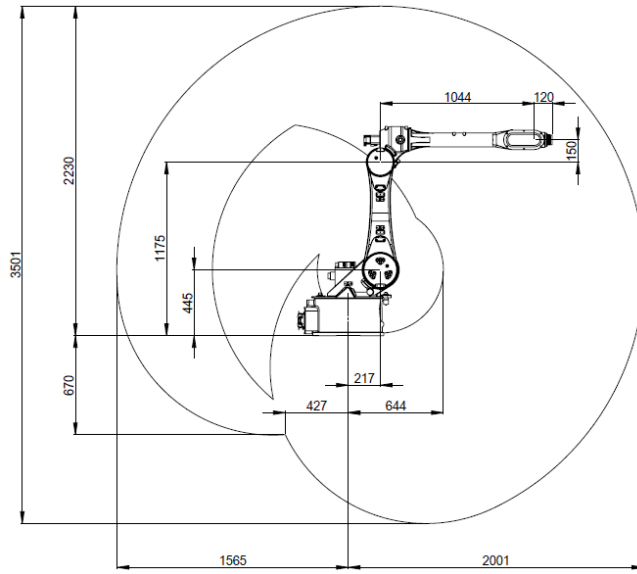


Prompt

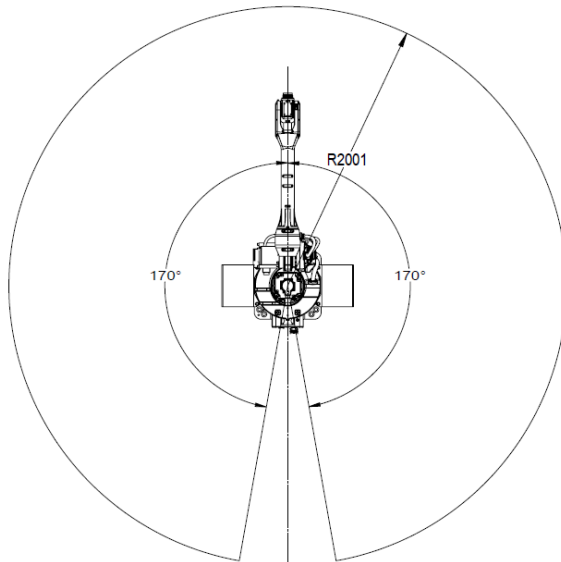
***: If the mechanical limit of J1 axis is removed, the range of motion can reach -180° ~ 180°

See Figure 7-1 for the motion range of the manipulator.

During the installation of peripheral equipment, attention shall be paid to avoid interference with the main part and motion range of the robot. Unit: mm.



(a)



(b)

Figure 7-1 Working range of AIR20-2000B manipulator

7.3 Mechanical limit

Zero point and movable range are respectively set on each axis. As long as the origin position is not lost due to servo system abnormality and system error, the robot is controlled to move within the movable range. In addition, in order to further ensure safety, mechanical brakes are provided on some axes to limit the movable range.

Figure 7-2 shows the position of mechanical brake.

Do not modify the mechanical brake, otherwise the robot may not stop normally.

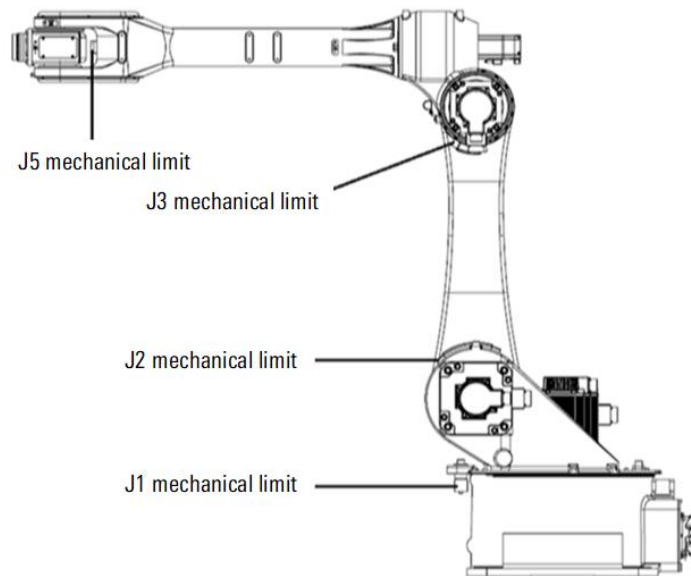


Figure 7-2 Mechanical brake on the AIR20-2000B manipulator

7.4 Speed of each axis

The maximum angular speed of each axis of the manipulator is shown in Table 7-2.

Table 7-2 Maximum angular speed of each axis of the manipulator

Axis number	Maximum angular velocity(°/s)
J1	175
J2	175
J3	170
J4	355
J5	355
J6	600

7.5 Output flange size

The Table 7-3 and Figure 7-3 show output flange specification and connection size. Tightening torque of screws is shown in Appendix B.

Table 7-3 The output mechanical interface specifications

Parameter	Value
Locating circle diameter	18mm or 65mm
Diameter of graduation circle of threaded hole	50mm
Screw grade	12.9 grade
Screw diameter	M6

Parameter	Value
Screw quantity	6
Locating pin	4mm
Screw standard	GB/T 70.1-2000

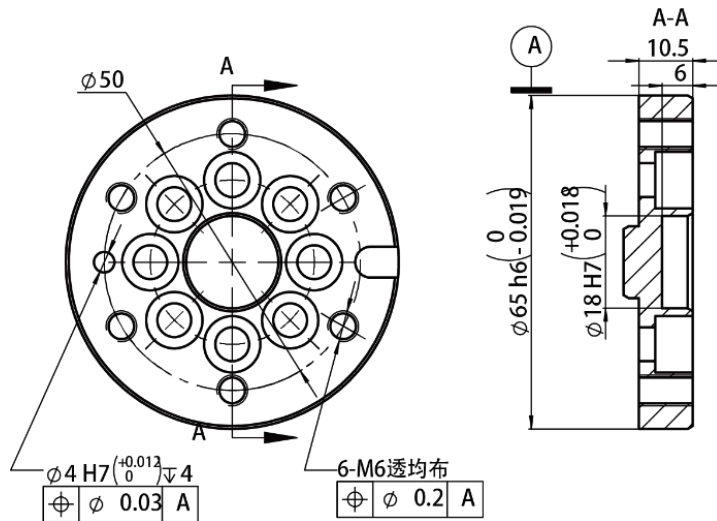



Figure 7-3 The flange dimension diagram of wrist



Warning

When installing the fixture, the depth of the threaded hole and pin hole shall be fully considered for the screws and locating pins used. It is forbidden to install the length beyond the depth of the threaded hole (10.5mm) and the depth of the pin hole (4mm), otherwise the wrist of the manipulator will be damaged.

7.6 Load and installation method

Calculation method of inertia moment

Inertia moment refers to the difficulty of rotation of the load (clamp end + workpiece) when the robot joint starts to rotate (inertia). The moment of inertia increases with the weight of the load and eccentricity. Since this will also increase the load on the joints, please ensure that the inertia moment is within the allowable range.

The moment M ($N \cdot m$) and inertia moment I (kgm^2) can be obtained when the load (clamp end + workpiece) volume is small by the following formula.

$$M(N \cdot m) = m(kg) \times L(m) \times g(m/s^2)$$

$$I(kgm^2) = m(kg) \times L^2(m)$$

Where, M is the load weight (kg), L is the load eccentricity (m), and g is the gravitational acceleration (m/s^2).

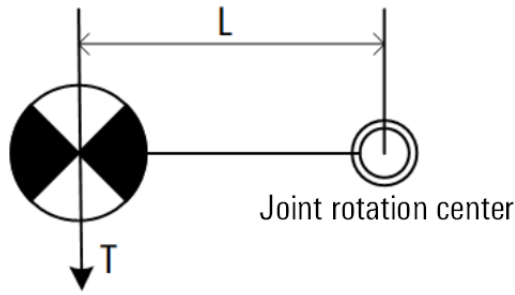
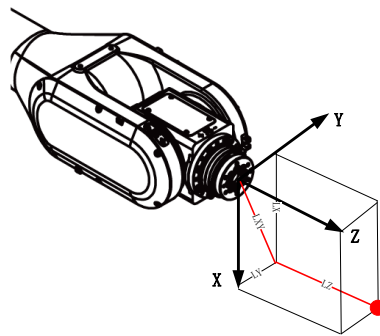


Figure 7-4 Diagram of load eccentricity

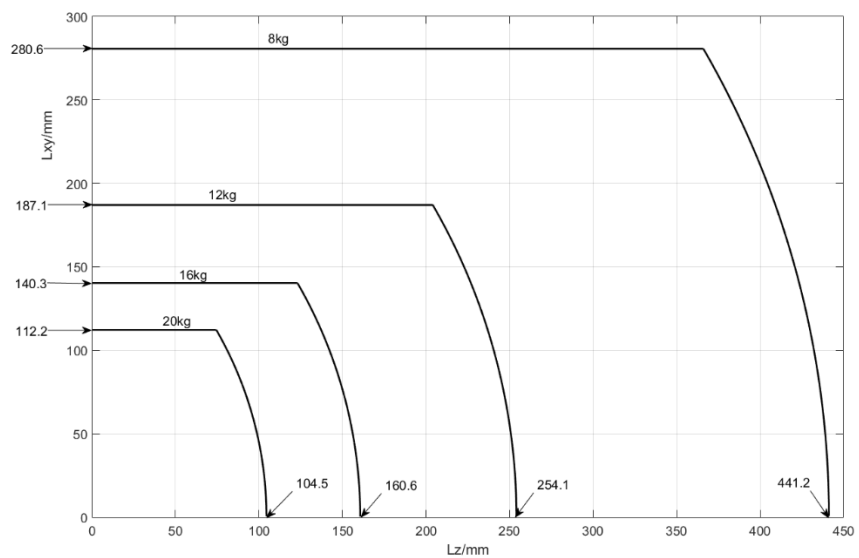
Wrist load installation of manipulator

The wrist load line diagram of AIR20-2000B manipulator is shown in Figure 7-5.

- The load conditions shall be within the limits shown on the chart.
- The allowable wrist torque of axis 4 is less than 44Nm, that of axis 5 is less than 44Nm, and that of axis 6 is less than 22Nm.
- The allowable load moment of inertia of axis 4 and axis 5 is less than 1.04kgm², the allowable load moment of inertia of axis 6 is less than 0.28kgm².
- Please refer to Table 1-1 for specific values.



(a)



(b)

Figure 7-5 Location of wrist load center of AIR20-2000B manipulator

Installation of elbow equipment of axis 3 of manipulator

The specification and size of the installation hole of J3 axis elbow of the AIR20-2000B manipulator are shown in Figure 7-6.

- The elbow and wrist of the AIR20-2000B manipulator can be equipped with external equipment with a weight of no more than 12kg.
- The position of center of mass of elbow load shall be located in the area of 150mm × 80mm as shown in Figure 7-6.
- The height of the center of mass from the installation surface shall not exceed 60mm.

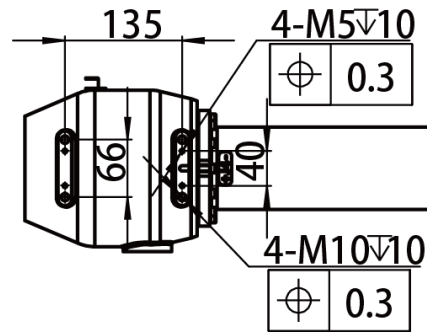



Figure 7-6 AIR20-2000B elbow load interface dimension diagram

When installing the equipment, the reliability of installation shall be fully considered. It is recommended to use 12.9 grade screws to install according to the specified torque, and apply thread glue on the thread, otherwise the long-term operation may lead to looseness or even fracture, resulting in accidents.

 Warning	<ul style="list-style-type: none"> ■ Since it may cause adverse effects on the safety and function of the manipulator, it is absolutely not allowed to add machining holes and screw holes to the Manipulator. ■ When installing the equipment, the screw used shall fully consider the depth of the threaded hole, and the installation length shall not exceed the depth of the threaded hole (10mm), otherwise the elbow of the manipulator will be damaged. ■ The mass center of elbow load shall not exceed the above value, otherwise the manipulator may give an alarm, fail to work normally, or reduce the working life. ■ When installing the equipment at the elbow of the manipulator, pay attention to avoid the interference with the manipulator and the cable, otherwise the main body cable is broken, resulting in unexpected serious faults and consequences.
--	--

Installation position of other parts of the manipulator

In order to facilitate cable fixation on the manipulator, other parts are reserved for the AIR20-2000B manipulator as follows:

Fixed position of manipulator forearm

See Figure 7-7 for the specification and size of the installation hole of the manipulator forearm.

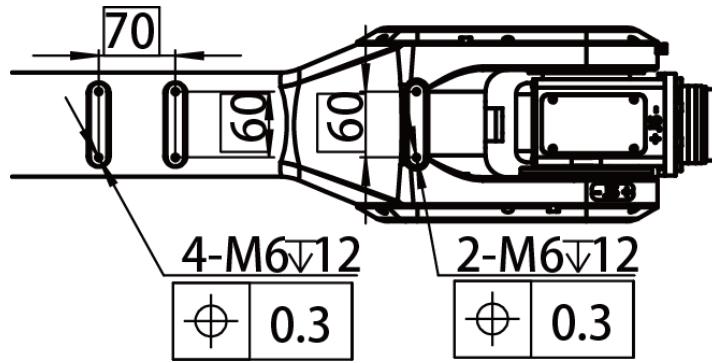


Figure 7-7 Diagram of the AIR20-2000B manipulator forearm

Fixed position of manipulator shoulder

The specifications and dimensions of the mounting hole on the shoulder of the manipulator are shown in Figure 7-8.

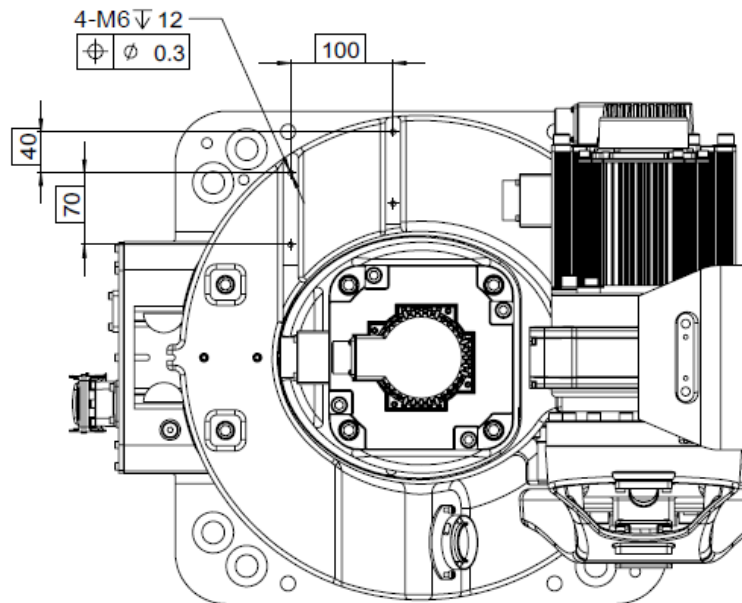


Figure 7-8 Diagram of the AIR20-2000B shoulder interface dimension

Fixed position of manipulator upper arm

The specifications and dimensions of the mounting hole of the manipulator upper arm are shown in Figure 7-9.

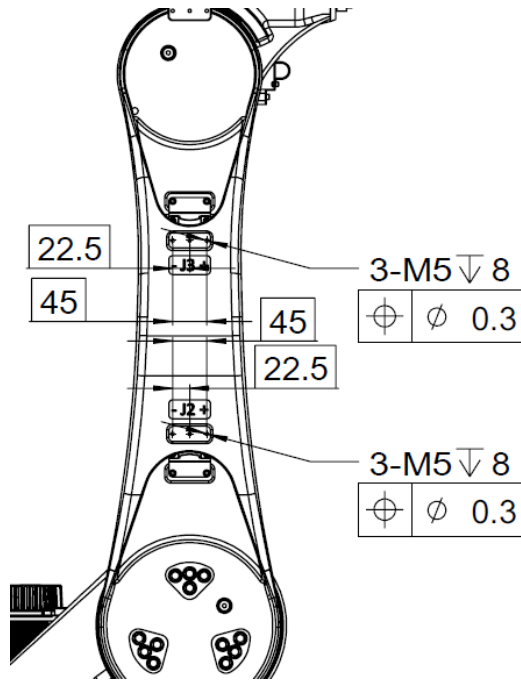



Figure 7-9 Diagram of the AIR20-2000B upper arm Interface dimensional

 Warning	<ul style="list-style-type: none"> ■ The above parts are designed for cable fixation. If equipment is needed to be installed, it should be guaranteed that: <ul style="list-style-type: none"> ● Arm load + wrist load <20kg. ● Shoulder load + arm load + elbow load <37kg.
	<ul style="list-style-type: none"> ■ When installing the equipment, the reliability of installation shall be fully considered. It is recommended to use 12.9 grade screws to install according to the specified torque, and apply thread glue on the thread, otherwise the long-term operation may lead to looseness or even fracture, resulting in accidents.

8 Calibration of the axes of the AIR20-2000B manipulator

8.1 General

This section describes the case where the manipulator needs to be calibrated and the zero-point calibration method under different requirements.

8.2 When calibration is required

The manipulator needs to be recalibrated when the following situations occur:

- Repair such as motor replacement or belt pulley removal.
- Replace the encoder battery.
- The encoder wire of the motor is loose or reinstalled.
- The manipulator has a strong collision.
- Replace the control cabinet or control system (e.g., industrial personal computer).

8.3 Calibration position of each Joint

The position of each axis of the manipulator is shown in Figure 8-1 below, in which, except for the J3 axis, it is 90° , and the other axes are 0° .

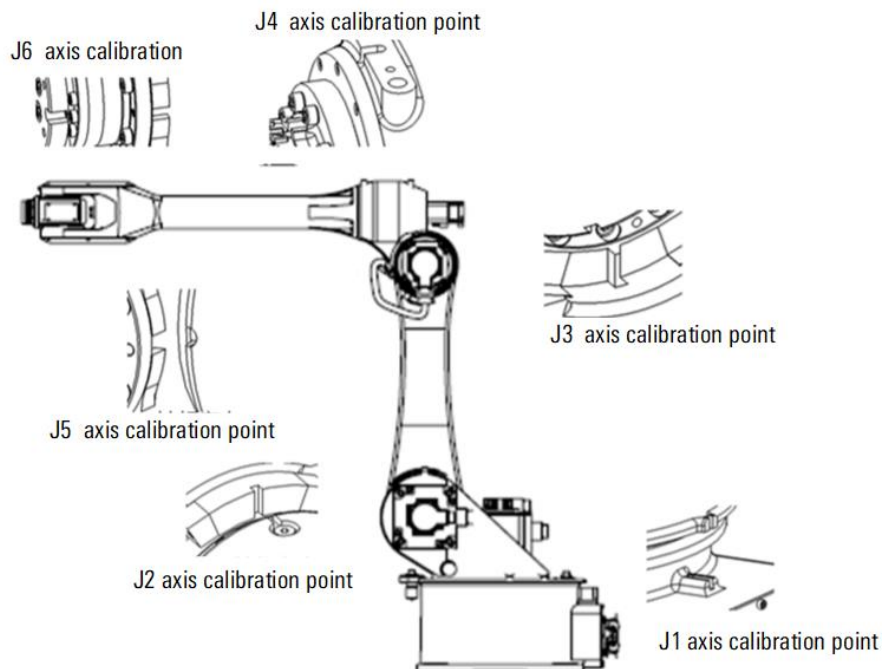


Figure 8-1 AIR20-2000B zero point diagram of each axis



Caution

- The robot calibration must always be performed at the same temperature conditions to avoid errors due to thermal expansion and contraction.
- The AIR20-2000B robot calibration must be calibrated in sequence from the J1 axis to the J6 axis.

Calibration required for high repetitive positioning accuracy

During the operation of the manipulator, only when it is required to have higher repeat positioning accuracy, the positioning accuracy of the path shall not be required. According to the zero point calibration position shown in Figure 8-1, the naked eye shall be used to make the zero point position of each shaft to be aligned, as shown in Figure 8-2.

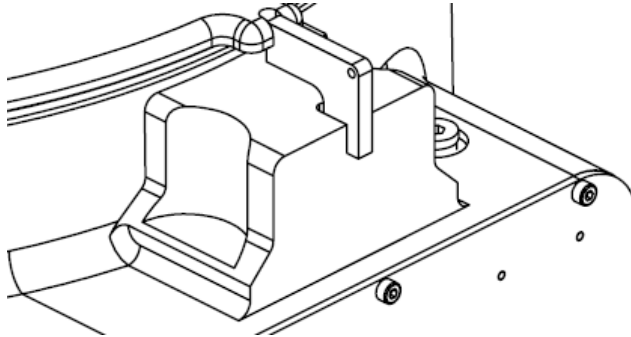



Figure 8-2 Calibration method of naked eye observation zero

 Warning	In the calibration process of the manipulator, the speed should be reduced as much as possible, and the operator should not enter the working range of the robot. After each time the robot stops moving, the alignment of the zero scale on the axis position should be observed.
--	--

Calibration under the requirement of high path positioning accuracy

When the manipulator is required to have high path positioning accuracy, it is necessary to calibrate and compensate the angle and length of each axis accurately, and to contact the company to use special equipment for calibration.

Calibration for rough requirements for path positioning accuracy

When the path positioning accuracy is roughly required, the calibration block is used, as shown in Figure 8-3.

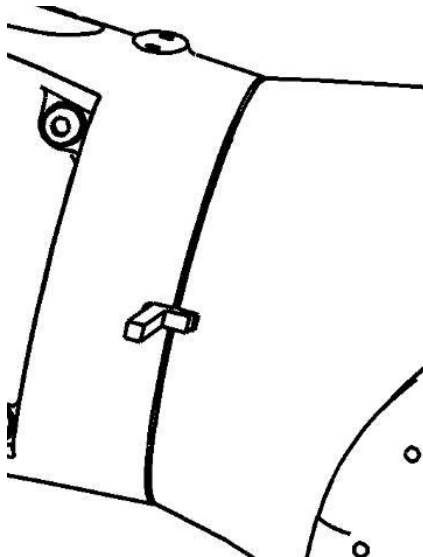



Figure 8-3 Calibration method of zero calibration block


 Warning	In the calibration process of the manipulator, the speed should be reduced as much as possible, and the operator should not enter the working range of the robot. After each time the robot stops moving, the alignment of the zero scale on the axis position should be observed.
--	--



Caution

When the calibration block is used for calibration of the manipulator, the basic alignment of the calibration slot shall be observed with the naked eye, the operating speed of the manipulator is reduced to the manual lowest gear, and after the position of the fine adjustment shaft, the calibration block is used for calibration, and the calibration block can be inserted into the two calibration grooves at the same time after multiple fine adjustment, as shown in Figure 8-3.

9 AIR20-2000B manipulator transportation and handling



Caution

Manipulator shall be equipped with the matching handling bracket. The incorrect handling method may cause the damage to manipulator. Manipulator posture during handling is subject to the description in Chapte9.1. Handling Dimensions of this manual Precautions for manipulator during handing as shown in Chapter9.1.

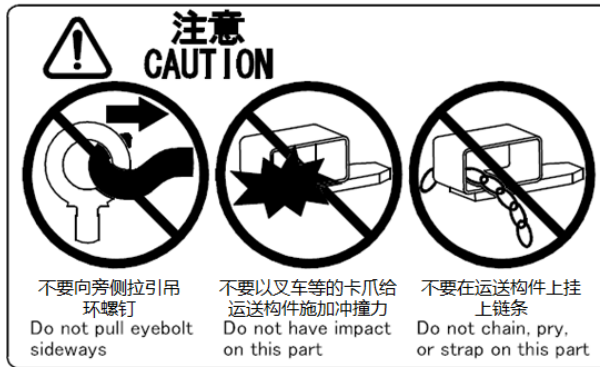


Figure 9-1 Precautions for manipulator during handing

When handling the robot, pay attention to the following matters:

- Do not pull the eyebolt sideways.
- Do not use the claws of forklifts, cranes, etc. to exert impact force on the transport components.
- Do not hang chains, etc. on transport components.

9.1 Handing dimensions

Three views of manipulator during the handling process are as shown in Figure 9-2, Figure 9-3 and Figure 9-4 (it shall be noted that the actual dimensions may be slightly larger than those in the figure).

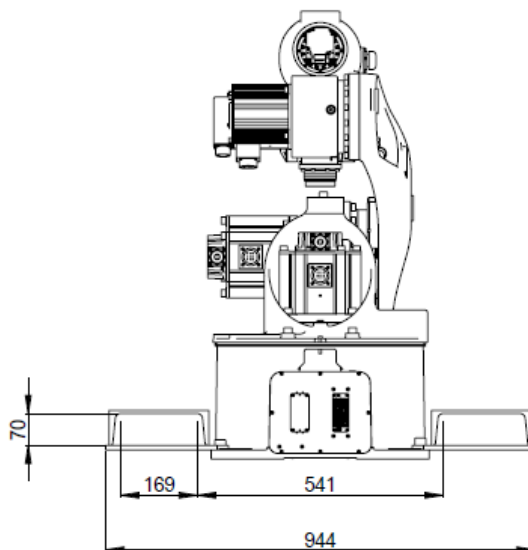


Figure 9-2 AIR20-2000B handling machine dimension diagram

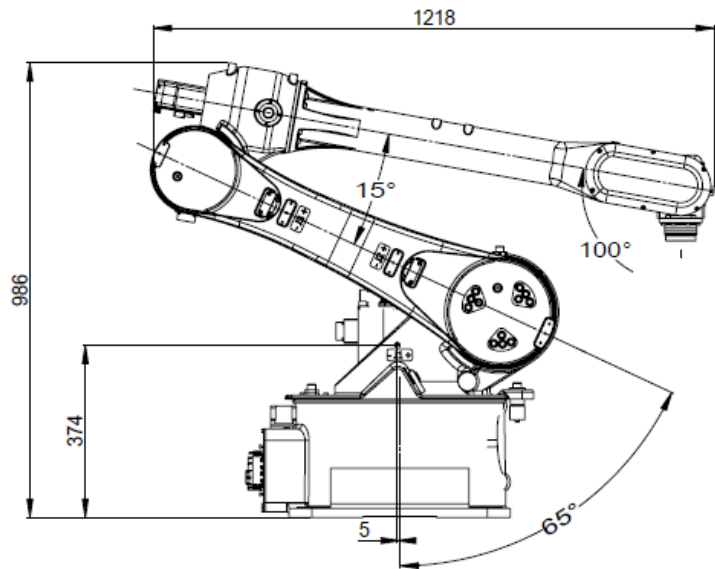


Figure 9-3 AIR20-2000B handling machine dimension diagram

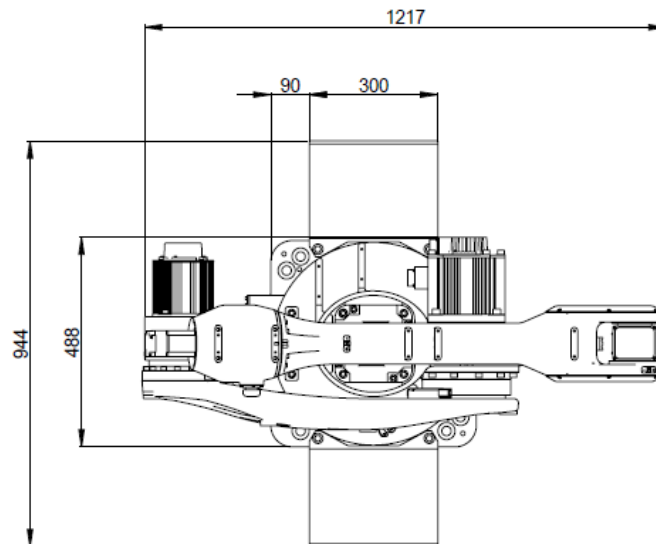


Figure 9-4 AIR20-2000B handling machine dimension diagram

9.2 Handing posture

One to six axis posture of the AIR20-2000B manipulator during handling shall be posed as shown in Table 9-1 and Figure 9-5.

Table 9-1 Angle value of each axis during robot handling

A1	A2	A3	A4	A5	A6
0	-65°	165°	0	80°	0

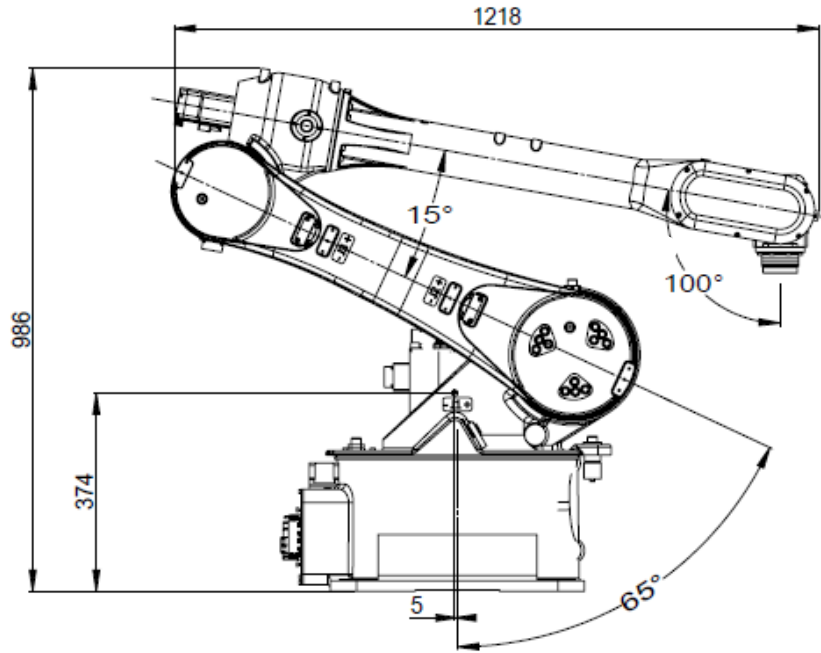



Figure 9-5 Handling posture of AIR20-2000B Manipulator

 Warning	Manipulator shall be handled in strict accordance with the posture in the table, otherwise it may tip over.
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9.3 Handing with forklift

Handing with forklift is as shown in Figure 9-6. Forklift shall meet the requirement for the weight of manipulator. The total weight of manipulator and handling device is about 323kg.

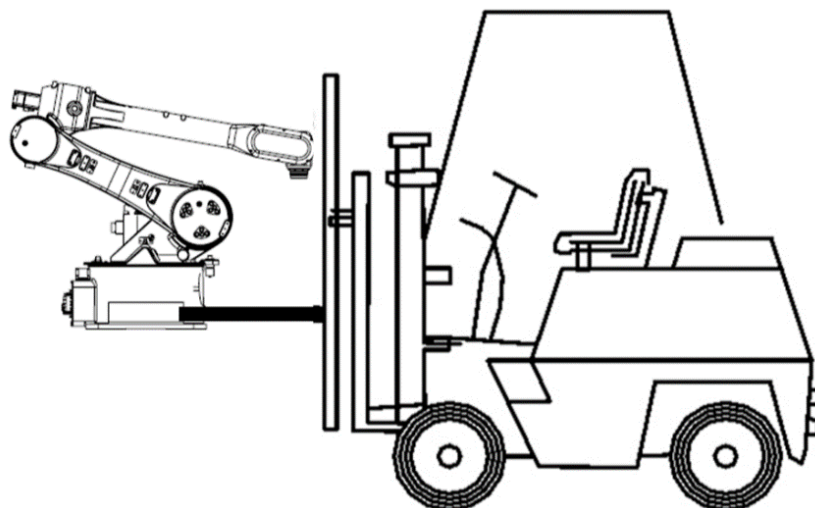



Figure 9-6 Diagram of AIR20-2000B handling with forklift

 Caution	Manipulator shall be equipped with the matching handling bracket. The incorrect handling method may cause the damage to manipulator. Manipulator posture during handling is subject to the description in Chapter9.2 Handling Posture of this manual.
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9.4 Handling with swinging ring

Handling with swinging ring is as shown in Figure 9-7, Lifting device shall meet the requirement for the weight of manipulator. The swinging ring is made of 20 or 25 # steel; The swinging ring is M12. The total weight of manipulator and handling device is about 323kg.

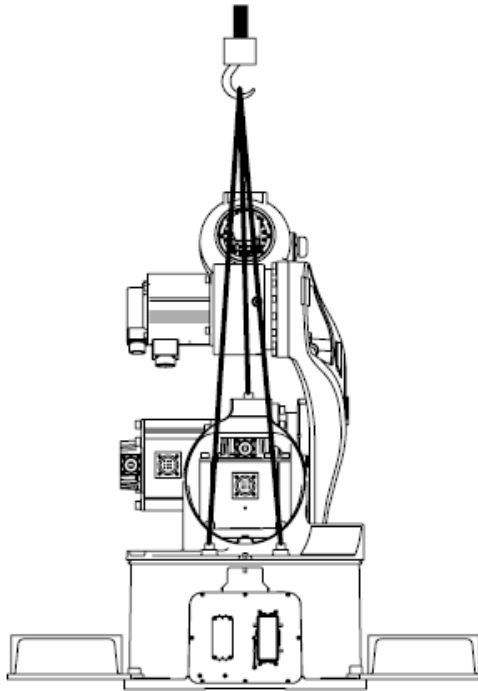


Figure 9-7 Diagram of AIR20-2000B Manipulator handling with swinging ring



Caution

- When manipulator is handled with swinging ring, insert a soft object between the sling and manipulator to avoid the scratching on the manipulator body by sling.
- Manipulator may turn over when transported with swinging ring. During the handling, please take special care to keep the manipulator steady.
- Do not pull the swinging ring to the side to avoid the damage to the manipulator and the unpredictable failure.

10 General principles of maintenance

This manual is a description of preventive maintenance of the AIR20-2000B manipulator. For the maintenance of a complete set of industrial robot systems, it should also include:

- Control cabinet maintenance-see "Control cabinet maintenance manual".
- End-effector maintenance-see related manual.



Warning

- No maintenance can be performed until the Safety guidelines and safety precautions are read, and maintenance can only be done by properly trained technicians.
- The primary objective of preventive maintenance is to ensure the maximum use of the operating system. Every plan, and well-implemented periodic maintenance, should help to achieve this goal. If regular maintenance cannot achieve the goal of shortening the downtime of the device, it is unnecessary to maintain and cause waste.
- Robot systems are designed to work under rather demanding conditions and require minimal maintenance. Nevertheless, daily inspection and regular maintenance must be carried out according to a given interval cycle.
- The time interval in the maintenance table is the recommended value, and the time interval actually required by the maintenance operator can be changed due to the actual working environment of the manipulator.
- When carrying out daily maintenance or maintenance, many precautions must be kept in mind so as not to introduce additional errors or dangers into the system.
- For well-functioning equipment, do not carry out more maintenance than required on a regular basis.
- All surfaces should be wiped clean before starting the maintenance process.
- In order to avoid unnecessary pollution caused by the impurities such as dust, the outside shall be cleaned before opening the control cabinet door and the outer cover of the manipulator.

11 Maintenance items

11.1 Daily maintenance

When running the manipulator every day, the following items should be checked. As shown in Table 1-1.

Table 11-1 Daily Maintenance of Operation Machine

Ordinal	Inspection item	Main points of inspection
1	Vibration, sound, motor heating	Check if there is abnormal vibration, abnormal noise and abnormally high temperature of each axis
2	presence or absence of positioning accuracy change	Check if there is a deviation from the last start up position and if there is a deviation from the stop position
3	Action confirmation of peripherals	Confirm that the operation of the operator and the peripherals are consistent with the instructions

11.2 First maintenance

The manipulator shall run for the first time 320 hours or 1 month (whichever is shorter), and the following items shall be inspected and maintained. As shown in Table 11-2.

Table 11-2 Manipulator First Maintenance Project

Ordinal	Inspection item	Main points of inspection
1	Whether the cable and cable sheath of the operator are damaged differently and whether the motor connector is loose	Observe the cable activity part of the manipulator, check whether the cable is damaged, whether the cable is bent or distorted locally, check whether the cable sheath is damaged or not, and check whether the motor connector is loose (Note 1)
2	Fasten external main bolts	Torque wrench to tighten the end-effector mounting bolts and the external main bolts (Note 2)
3	All parts of the cleaning manipulator	Clean and maintain the parts of the manipulator, and check whether the parts are damaged (Note 3).
4	Whether the terminal actuator cable is damaged or not	Inspect the cable for damage, and the cable sheath is damaged
5	Whether the synchronous belt is worn or not	Check if the synchronous belt is worn, elongated, and broken (note 4)
6	Check if that the stop rubber block at the J1 J2, J3, J5 shaft is damaged	Check whether the limit rubber block is loose, collision damage, aging and so on.

Note 1:

Maintenance site

- Internal cable and cable sheath inside the manipulator base (with the electrical mounting plate removed).
- Big arm of manipulator and internal cable and cable sheath of J1 axle body.
- Connecting cable of manipulator, grounding terminal, user cable joint

Confirmation

- Check the cable sheath for crack and wear, and if so, replace it.
- Check if the lubricating grease on the surface of internal cable of J1 axle body and the internal cable of big arm is disappeared, and if the lubricating grease is about to disappear, add it properly.
- Check the line for wear and replace it if it is exposed.
- Round connector: Turn it manually to see if it is loose.
- Square heavy load: Check if the control lever is off.
- Grounding terminal: Check if it is loose.

Note 2:

Tightening Part

- Tighten the mounting bolts of end effector and fixing bolts of manipulator, etc.
- The external connecting screws of manipulator, especially the connecting screws of shaft and the reducer or gearbox.
- For the tightening torque, please refer to the values suggested in the appendix of this manual.

Note 3:

About Cleaning

- The parts that need to be cleaned, the dust on the plane, and the accumulation of splashes shall be cleaned regularly.
- Special care shall be taken to clean the place between the rotating parts of wrist J5 axle to remove debris in time.
- Check if oil is leaking from the reducer or gearbox.
- If the oil is still seen one day after the oil is wiped off, the oil leakage is possible.

Note 4:

About the Maintenance of Synchronous Belt

- After disassembling the manipulator cover plate, check whether the synchronous belt is worn or damaged. For the details, see Chapter12.5 in this manual.
- Check the inside of synchronous belt teeth for white hair, the belt side for wear, belt teeth for crush, the belt body for breakage and elongation (pre-tightening force is decreasing), etc.

11.3 Regular maintenance

960 hours (3 months) regular maintenance

For every 960 hours or 3 months of operation of the manipulator (whichever is the shorter time), the following items need to be inspected and repaired. As shown in Table 11-3.

Table 11-3 Manipulator 960 hours (3 months) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Control cabinet vent cleaning	If there is a lot of dust stuck to the vent of the control cabinet, please remove it
2	Cleaning of operators	Wipe away dirt, remove accumulated spatter, dust, dust, chips, etc.

1920 hours (6 months) regular maintenance

The manipulator shall run for 1920 hours or 6 months (whichever is shorter), and the following items shall be inspected and repaired. As shown in Table 11-4.

Table 11-4 Manipulator 1920 hours (6 months) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Whether the cable and cable sheath of the manipulator are damaged	See Chapter 11.2
2	Whether the synchronous belt is worn or not	Check the synchronous belt for wear, elongation and fracture

3840 hours (1 year) regular maintenance

For every 3840 hours or 1 year (whichever is the shorter time), the operator needs to carry out the inspection and maintenance of the following items. As shown in Table 11-5.

Table 11-5 Manipulator 3840 hours (1 year) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Whether the cable and cable sheath of the manipulator are damaged	See Chapter 11.2
2	Fasten external main bolts	See Chapter 11.2
3	All parts of the cleaning manipulator	See Chapter 11.2
4	Whether the terminal actuator cable is damaged or not	See Chapter 11.2
5	Replacement of synchronous tape	See Chapter 11.2
6	Whether the J1 shaft limit rubber block is damaged or not	See Chapter 11.2

7860 hours (2 years) regular maintenance

The manipulator shall be operated for 2 years or 7860 hours (whichever is short), and the following items shall be inspected and repaired. As shown in Table 11-6.

Table 11-6 Manipulator 7860 hours (2 years) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Replacement of battery	See Chapter 12.3

11520 hours (3 years) regular maintenance

The manipulator shall be operated for 3 years or 11520 hours (whichever is less), and the following items shall be inspected and repaired. As shown in Table 11-7.

Table 11-7 Manipulator 11520 hours (3 years) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Replacement of synchronous tape	See Chapter 11.2

15360 hours (4 years) periodic maintenance

The manipulator shall be operated for 4 years or 15360 hours (whichever is short), and the following items shall be inspected and repaired. As shown in Table 11-8.

Table 11-8 Manipulator 15360-hour (4-year) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Replacement of internal cable of manipulator	To replace the manipulator cable, please consult with us

19200 hours (5 years) regular maintenance

For every 5 years or 19200 hours (whichever is the shorter time), the manipulator needs to be overhauled and many parts need to be replaced. Please contact us. As shown in Table 11-9.

Table 11-9 Manipulator 19200 hours (5 years) maintenance project

Ordinal	Inspection item	Main points of inspection
1	Overhaul of manipulator	Please consult our company

12 Project maintenance process

12.1 Cleaning of manipulator


To ensure the long-term operation of robot, the manipulator shall be cleaned every 960 h or 3 months (whichever comes first) according to the following process:

Step1. Adjust the robot to the calibration state.

Step2. To prevent the hazards, turn off the power, hydraulic, and pneumatic sources connected to the robot.

Step3. Clean the manipulator with the vacuum cleaner or wipe it with a cloth.

Step4. After all safety conditions are met, conduct the follow-up work of manipulator.

 Warning	■ Do not apply the water jet on the manipulator, especially the joints and seals.
	■ Do not clean the manipulator with compressed air.
	■ Do not remove any protector of manipulator.
	■ Do not clean the manipulator with solvent.

12.2 Check and repair of cable

To ensure the long-term operation of robot, the manipulator cable shall be checked every 1,920 h or 6 months (whichever comes first). Layout for Cables of manipulator as shown in Figure 12-1.

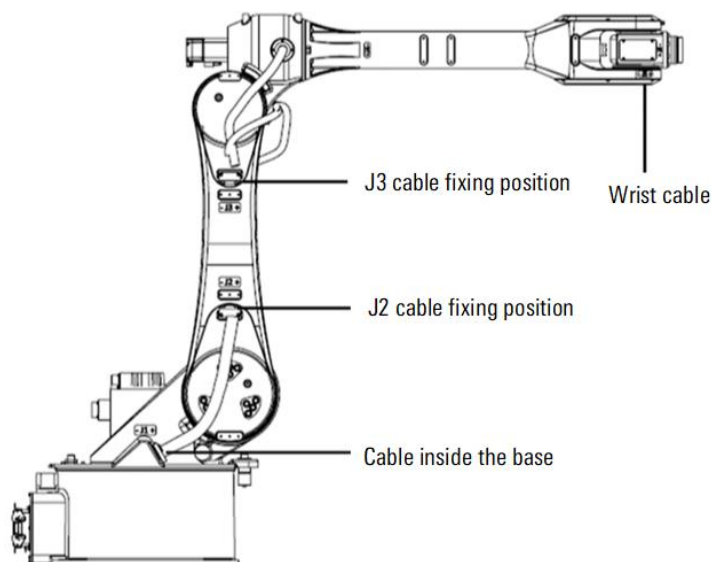


Figure 12-1 Layout for cables of manipulator

Check and repair external cables

Maintenance steps:

- Step1. Adjust the manipulator from J1 to J6's angle is $0^{\circ}, 0^{\circ}, 90^{\circ}, -180^{\circ}, 0^{\circ}, 0^{\circ}$.
- Step2. To prevent the damage, please shutdown the electric power and hydraulic power and pneumatic power of the manipulator.
- Step3. Check all the external cables for wear or damage.
- Step4. Check all the cables connector for wear or damage.
- Step5. Check all the bracket and Tie-down straps are fixed on the operation
- Step6. Check the fixation between the cable and bracket for wear or damage.
- Step7. In case of crack, wear or damage, please contact us for replacement timely

Check and repair the internal cables of the base

Maintenance steps:

- Step1. Remove the electrical mounting plate as shown in Figure 12-2, and pull out the internal cables of base.
- Step2. Check if the fixing plate secures the cables on the mounting plate.
- Step3. Check the fixation between the cables and fixing plate for wear or damage.
- Step4. Check the internal cables for wear or damage.
- Step5. In case of crack, wear or damage, please contact us for replacement timely.
- Step6. Check if the lubricating grease on the internal cable surface has disappeared.
- Step7. If so, it shall be replenished timely.
- Step8. The cable in the base to keep the shape "U" type like the Figure 12-1.
- Step9. Install the cover plate, and coat the joint surface between the cover plate and base with sealant

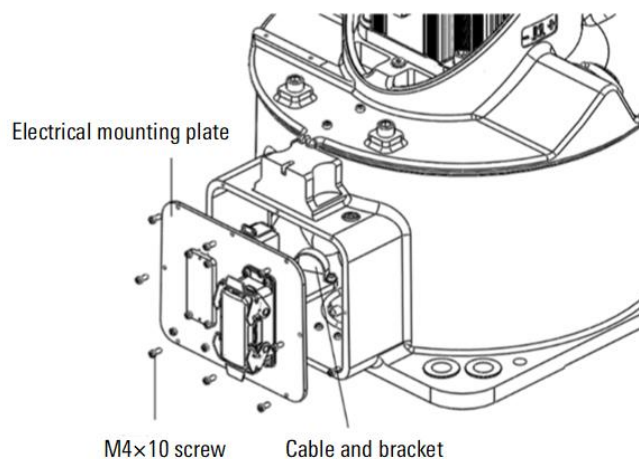


Figure 12-2 Base internal cable

Check and repair the elbow internal cable

Maintenance steps:

- Step1. Remove elbow cable retaining plate as shown in Figure 12-3.
- Step2. Pull out the cable and check whether the cable is reliably connected to the fixed plate.
- Step3. Check whether the cable and the bracket are fixed for wear or damage.
- Step4. Inspect internal cables for wear and tear.
- Step5. In case of cracks, wear or damage, please contact us for replacement.
- Step6. Check internal cable surface grease for disappearance.
- Step7. If the grease on the cable surface disappears, it should be replaced in time.
- Step8. Put the cable inside the elbow.
- Step9. Install cable fixed plate.

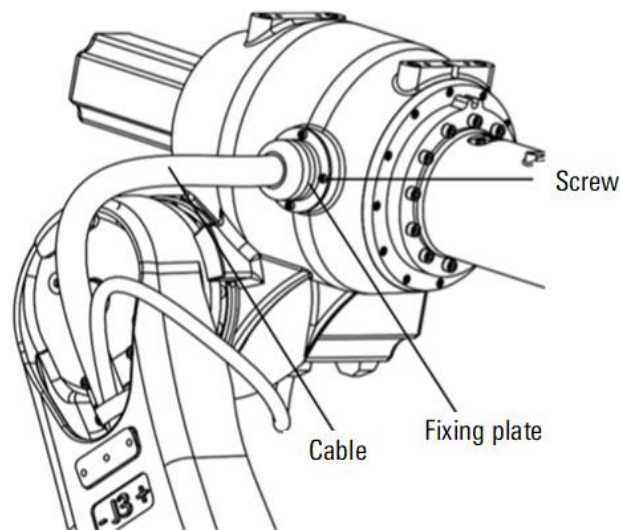


Figure 12-3 Elbow internal cable

Check and repair process for internal cables of the wrist

Maintenance steps:

- Step1. Remove the cover plate as shown in Figure 12-4.
- Step2. Check the fixation between the cable and bracket for wear or damage.
- Step3. Check the internal cables for wear or damage.
- Step4. In case of crack, wear or damage, please contact us for replacement timely.
- Step5. Check if the lubricating grease on the internal cable surface has disappeared.
- Step6. If so, it shall be replenished timely.
- Step7. Install the cover plate, and coat the joint surface between the cover plate and forearm with sealant.

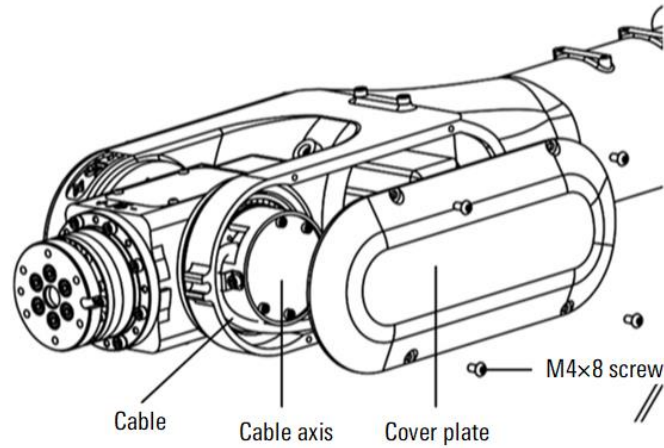


Figure 12-4 Inner cable of the wrist



Please entrust the service department of the company to replace the internal cables of the operator. The use of substandard cables may result in the robot not working properly.

12.3 Battery replacement

The position data of each axis of the manipulator shall be stored by the encoder battery. The battery shall be replaced in time every 7860 hours or 2 years (whichever is shorter).

Maintenance steps:

- Step1. Adjust the robot to the calibration state.
- Step2. To prevent the hazards, turn off the power, hydraulic, and pneumatic sources connected to the robot.
- Step3. Remove the battery cover on the electrical mounting plate of manipulator as shown in Figure 12-5.
- Step4. Remove the old battery from the box and put the new battery into the box. Be sure to keep the positive and negative polarities of battery same as the old one.
- Step5. Reconnect the battery pin connector
- Step6. Install the battery cover.
- Step7. Install the electrical installation plate, and apply sealant on the joint surface between the electrical installation plate and the base casting.
- Step8. Make sure that all safety conditions are met, and then perform the calibration and testing of manipulator.

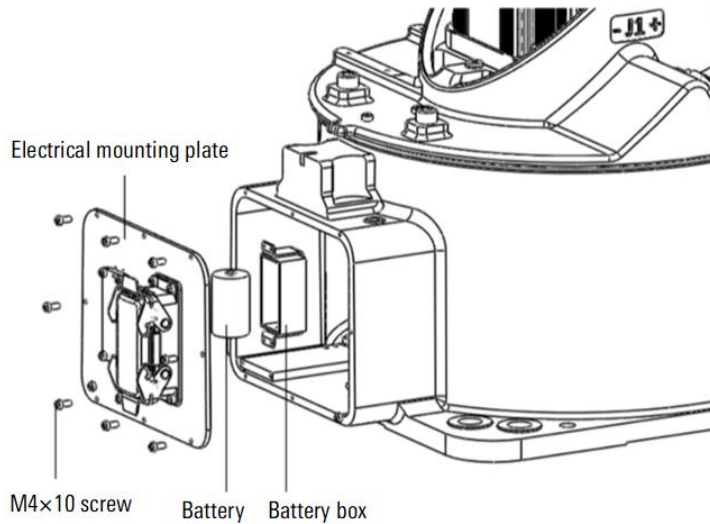


Figure 12-5 Remove manipulator electrical installation panel

12.4 Replace grease

Operation machine J1 axis to J6 axis reducer, every 11520 hours or 3 years (whichever is shorter), need to replace the internal grease.

Grease type and grease quantity, please refer to Table 12-1.

Table 12-1 Grease model and quantity of manipulator

Manipulator model	Replace the grease part	Amount of grease	Grease type
AIR20-2000B	J1 axis reducer	475g	VIGOGREASE RE0
	J2 axis reducer	475g	
	J3 axis reducer	300g	

When replacing the grease, please refer to Table 12-2 for the attitude of the manipulator.

Table 12-2 Grease changing attitude of manipulator

Replace the grease part	J1	J2	J3	J4	J5	J6
J1 axis reducer	170°	0°	90°	any	any	any
J2 axis reducer	0°	0°	90°	any	any	any
J3 axis reducer	0°	45°	-45°	any	any	any



Warning

- Reducer oil temperature may be higher than 90°, to be replaced after cooling.
- Wear gloves to prevent allergic reactions.
- Open the drain carefully and slowly to prevent oil spatter.

J1 axis reducer replacement grease process

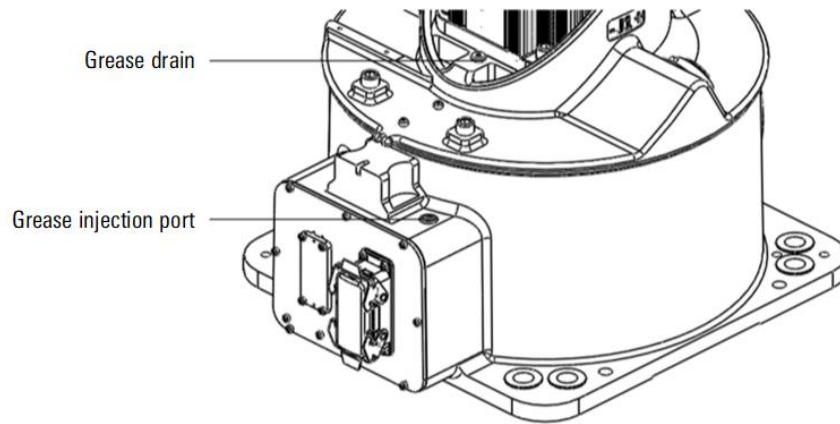


Figure 12-6 Replace the lubricating grease of J1 axis reducer

The replacement process is as follows:

- Step1. Run the manipulator as shown in Table 12-2.
- Step2. To prevent danger, turn off the power, hydraulic and pneumatic sources connected to the robot.
- Step3. Place the waste oil collector near the grease outlet.
- Step4. Remove the grease outlet M10x1 plug, as shown in Figure 12-6.
- Step5. Install grease drain tubing to ensure waste oil flows into the sump tank.
- Step6. Remove the grease injection port M10x1 plug, install the grease injection nozzle, and use manual grease injection gun to inject grease until the new grease is discharged from the outlet.
- Step7. Release the grease pressure inside the reducer as shown in Table 12-3.
- Step8. The amount of oil discharged by weighing shall be equal to the amount of oil injected. If the discharge amount is less than the injection amount, the excess amount is discharged by gas at the fat injection port. If the discharge volume is greater than the injection volume, inject the missing amount from the grease injection port.
- Step9. Remove the grease injector, install the M10x1 plug on the grease outlet and grease injector, and apply the sealing tape/sealant.



Caution

When injecting fat from the fat injection port into the inner part of the operation machine, the fat injection speed by hand pump is less than 8g/s and the fat injection pressure is less than 0.3mpa. In order to ensure the smooth elimination of the old oil inside the reducer, after a period of oil injection, take a rest for a while, such as the oil outlet no old oil discharge to continue the oil injection. When the oil filling speed is too fast, the instantaneous pressure inside the reducer becomes higher, and the grease may cause damage to the motor oil seal and the grease enters the motor.

J2 axis reducer replacement grease process

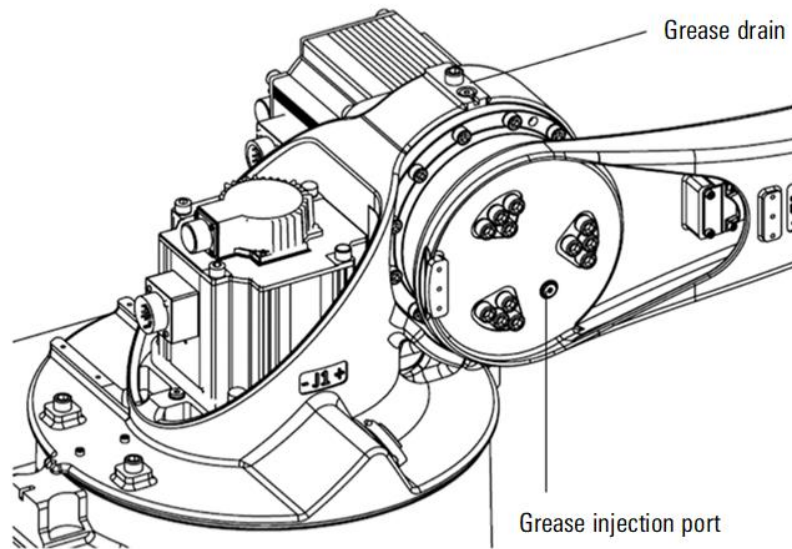


Figure 12-7 Replace the grease of J2 axis reducer

The replacement process is as follows:

- Step1. Run the manipulator as shown in Table 12-2.
- Step2. To prevent danger, turn off the power, hydraulic and pneumatic sources connected to the robot.
- Step3. Place the sump tank for collecting waste oil near the grease outlet.
- Step4. Remove the grease outlet M10x1 plug, as shown in Figure 12-7.
- Step5. Install grease drain tubing to ensure waste oil flows into the sump tank.
- Step6. Remove the grease injection port M10x1 plug, install the grease injection nozzle, and use manual grease injection gun to inject grease until the new grease is discharged from the outlet.
- Step7. Release the grease pressure inside the reducer as shown in Table 12-3.
- Step8. The amount of oil discharged by weighing shall be equal to the amount of oil injected. If the discharge amount is less than the injection amount, the excess amount is discharged by gas at the fat injection port. If the discharge volume is greater than the injection volume, inject the missing amount from the grease injection port.
- Step9. Remove the grease injector, install the M10x1 plug on the grease outlet and grease injector, and apply the sealing tape/sealant.



Caution

When injecting fat from the fat injection port into the inner part of the manipulator, the fat injection speed by hand pump is less than 8g/s and the fat injection pressure is less than 0.3mpa. In order to ensure the smooth elimination of the old oil inside the reducer, after a period of oil injection, take a rest for a while, such as the oil outlet no old oil discharge to continue the oil injection. When the oil filling speed is too fast, the instantaneous pressure inside the reducer becomes higher, and the grease may cause damage to the motor oil seal and the grease enters the motor.

J3 axis reducer replacement grease process

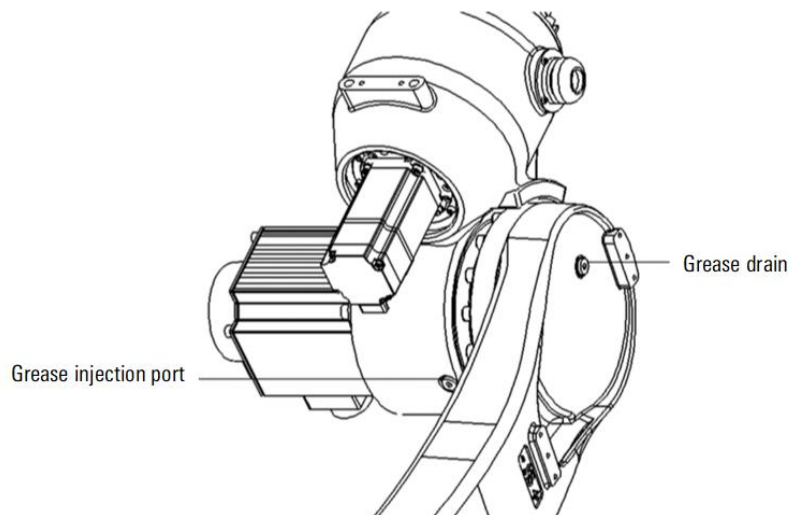


Figure 12-8 Replace the lubricating grease of J3 axis reducer

The replacement process is as follows:

- Step1. Run the manipulator as shown in Table 12-2.
- Step2. To prevent danger, turn off the power, hydraulic and pneumatic sources connected to the robot.
- Step3. Place the sump tank for collecting waste oil near the grease outlet.
- Step4. Remove the grease outlet M10x1 plug, as shown in Figure 12-8.
- Step5. Install grease drain tubing to ensure waste oil flows into the sump tank.
- Step6. Remove the grease injection port M10x1 plug, install the grease injection nozzle, and use manual grease injection gun to inject grease until the new grease is discharged from the outlet.
- Step7. Release the grease pressure inside the reducer as shown in Table 12-3.
- Step8. The amount of oil discharged by weighing shall be equal to the amount of oil injected. If the discharge amount is less than the injection amount, the excess amount is discharged by gas at the fat injection port. If the discharge volume is greater than the injection volume, inject the missing amount from the grease injection port.
- Step9. Remove the grease injector, install the M10x1 plug on the grease outlet and grease injector, and apply the sealing tape/sealant.




When injecting fat from the fat injection port into the inner part of the operation machine, the fat injection speed by hand pump is less than 8g/s and the fat injection pressure is less than 0.3mpa. In order to ensure the smooth elimination of the old oil inside the reducer, after a period of oil injection, take a rest for a while, such as the oil outlet no old oil discharge to continue the oil injection. When the oil filling speed is too fast, the instantaneous pressure inside the reducer becomes higher, and the grease may cause damage to the motor oil seal and the grease enters the motor.

Release grease pressure inside reducer

When releasing the inner grease pressure of the reducer, please install the recovery device at the outlet of the exhaust grease to avoid the splash of the grease and the pollution of the environment.

Table 12-3 Release internal pressure of reducer and gearbox

Replace the grease part	Action point	The action time	The premise
J1 axis reducer	>90°	Ten minutes	Sealing head or oil nozzle shall be installed at the grease injection port, and sealing screws shall not be installed at the grease injection port
J2 axis reducer	>90°	Ten minutes	
J3 axis reducer	>90°	Ten minutes	



Improper fat-feeding operations may cause a sharp increase in the pressure in the reducer or gearbox, damaging internal parts such as the sealing ring, resulting in oil leakage or poor operation.

The following precautions must be observed:

- Be sure to remove the sealing screw on the grease outlet before fatting.
- Use a hand pump to slowly feed the fat.
- Be sure to use the specified grease.
- After the grease supply, install the sealing screw after releasing the internal pressure as shown in Table 12-3.
- Thoroughly remove grease from floor and manipulator to avoid slipping.

Caution

12.5 Replacement of synchronous belt

Synchronous belt of J5 axis shall be replaced every 11520h or 13year (whichever comes first)

For the model of synchronous belt, please see Table 12-4.

Table 12-4 Synchronous belt model for manipulator

Manipulator Model	Position	Model
AIR20-2000B	Axis J5 inside the forearm	GT3, 475-5MGT-9

At the replacement of synchronous belt, the manipulator shall be posed as shown in Table 12-5.

Table 12-5 Posture of manipulator at the replacement of synchronous belt

J1	J2	J3	J4	J5	J6
Arbitrarily	0°	90°	0°	90°	Arbitrarily

Replacement process for synchronous belt of J5 axis

Replacement as follows:

Step1. Operate the manipulator to the attitude shown in Table 12-5.

Step2. Cut off the power supply of the control device.

- Step3. Remove the manipulator cover plate and four M4 screws, as shown in Figure 12-9.
- Step4. Loosen the synchronous belt adjusting screw.
- Step5. Remove four M4 screws from the motor base, as shown in Figure 12-10.
- Step6. Move the motor pulley assembly, remove the old synchronous belt and install the new synchronous belt.
- Step7. Preliminarily install the motor base screw M4.
- Step8. Install the adjusting screw with an Allen key and adjust the timing belt to the appropriate tension; The frequency of synchronous belt is 116Hz~122Hz, which can also be measured by pressure method, with pressure $G=2.9N$ and deformation $f=2.1mm$.
- Step9. Install the motor base screw M4 with the specified torque.
- Step10. Install the manipulator cover plate and apply sealant at the joint.
- Step11. Calibrate the J5 axis of the manipulator.

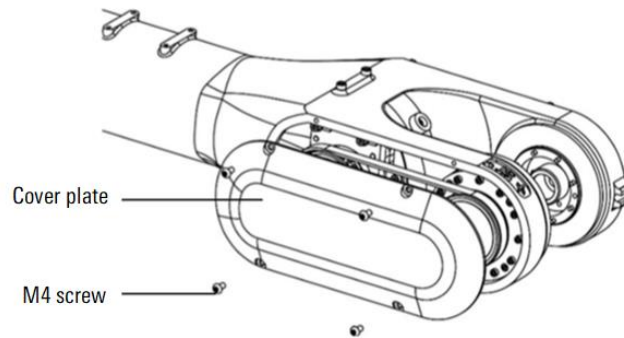


Figure 12-9 Removal of cover plate

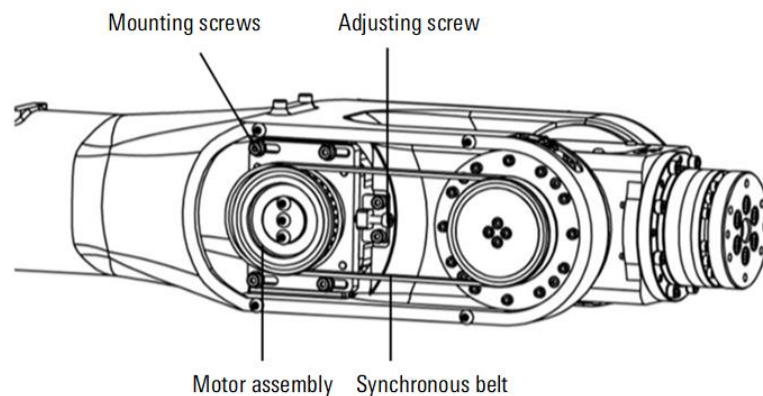


Figure 12-10 Removal of synchronous belt

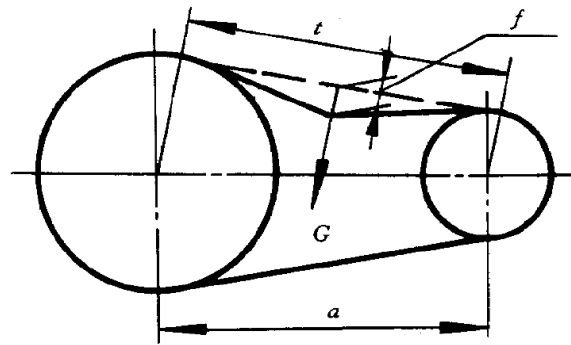


Figure 12-11 Installation deflection of synchronous belt



Warning

After the replacement of synchronous belt, the J5 axis of manipulator shall be calibrated. For details, see Chapter 8.

13 Common faults and treatment

The fault of manipulator may be caused by a number of different reasons. It is often difficult to thoroughly find out the cause. If the wrong handling method is used, the fault may be further deteriorated. Therefore, it is very important to analyze the fault situation and find out the real cause.

Vibration or abnormal noise

The possible fault and causes of manipulator are as shown in Table 13-1. If you are unsure of the cause or do not know how to proceed, please contact us.

Table 13-1 Possible faults and causes of manipulator

Fault	Classification	Possible Causes	Treatment
Vibration Abnormal noise	<ul style="list-style-type: none"> ■ When the manipulator operates, its base floats from the workshop pedestal ■ There is a gap between the base and workshop pedestal ■ The screws connecting the base and workshop pedestal are loose 	Fixation of Base: <ul style="list-style-type: none"> ■ The manipulator base is not firmly fixed on the workshop pedestal ■ The base floats from the workshop pedestal and generates the vibration when the manipulator acts due to the screw looseness, insufficient flatness of base and the foreign objects. 	<ul style="list-style-type: none"> ■ When the screw is loose, tighten it with the torque wrench according to the proper torque ■ Trim the base flatness in accordance with the tolerance ■ Check if the foreign matters are trapped, and if so, remove them ■ Please consult with us
	Workshop pedestal vibrates when the manipulator acts	Workshop Pedestal: <ul style="list-style-type: none"> ■ Pedestal is not completely fixed on the foundation. Therefore, the workshop pedestal vibrates when the manipulator acts. ■ The insufficient rigidity of workshop pedestal, and the reaction force and torque generated by the manipulator cause the deformation and vibration. 	<ul style="list-style-type: none"> ■ Completely fix the workshop pedestal according to the corresponding method ■ Workshop pedestal shall be processed to improve its rigidity ■ For the workshop pedestal with machining difficulty, the vibration may be mitigated through the modification of moving program ■ Please consult with us
Vibration Abnormal noise	<ul style="list-style-type: none"> ■ Vibration at a specific posture during the action ■ No vibration at the slow action ■ Obvious vibration during acceleration and deceleration ■ Simultaneous vibration of multiple axes 	<ul style="list-style-type: none"> ■ Load of manipulator exceeds the allowable value ■ Action procedures are too strict on the manipulator ■ Improper acceleration 	<ul style="list-style-type: none"> ■ Confirm whether the manipulator load exceeds the allowable value, and reduce the load or change the action procedures ■ Mitigate the specific vibrations by reducing speed, reducing acceleration and changing the action procedures

Fault	Classification	Possible Causes	Treatment
	<ul style="list-style-type: none"> ■ Collision or long-term overload operation of manipulator ■ No replacement of lubricating grease for a long time 	<ul style="list-style-type: none"> ■ Mechanical transmission system is subjected to excessive external force due to collision or overload, causing the damage to the gear surface or rolling surface of the gear, bearing, reducer or the peeling due to fatigue ■ The gear surfaces or rolling surfaces of gear, bearing and reducer are damaged due to the foreign matters trapped in the gear, bearing or reducer. ■ The gear surfaces or rolling surfaces of gear, bearing and reducer peel off due to fatigue because of no replacement of lubricating grease for long term ■ The above reasons may cause the periodic vibration or abnormal noise 	<ul style="list-style-type: none"> ■ Make the manipulator operate uniaxially to confirm the Joint that produces the vibration and noise ■ If you need to replace the gear, bearing and reducer, please contact us. ■ Do not use the manipulator at overloaded status ■ If you need to replace the lubricating grease, please contact us. ■ Please consult with us
<p>Vibration Abnormal noise</p>	<p>Causes may not be determined mechanically</p>	<ul style="list-style-type: none"> ■ Fault of the circuit inside the controller, failure of command to transmit to the motor, or the motor information not correctly transmitted to the controller ■ Fault of pulse encoder and the position of motor not correctly transmitted to the controller ■ Failure of motor body to perform its original functions ■ Breakage of internal motor cable of manipulator causes the command not to be correctly transmitted to the motor and control system ■ Voltage reduction and no guarantee for the specified voltage ■ Incorrect control parameters are input 	<ul style="list-style-type: none"> ■ For the fault of controller, see the controller manual ■ Replace the motor of vibrating Joint to confirm whether it vibrates ■ Check the cables of the manipulator body, between the manipulator body and control cabinet, and inside the controller for damage, and if so, replace the cable. ■ Check whether the cable joint is in good contact. In case of the poor contact or looseness, re-tighten or take appropriate measures to ensure the good contact. ■ Check whether the action control parameters are correct, and if not, re-enter the correct parameters. ■ Please consult with us

Fault	Classification	Possible Causes	Treatment
	The mechanical action near the manipulator is closely related to the vibration of robot.	<ul style="list-style-type: none"> ■ Mechanical electrical noise from the manipulator ■ If the grounding wire is not connected properly, the electrical noise will mix into the grounding wire, causing the vibration of manipulator due to the interference with command ■ Poor connection of grounding wire will lead to the unstable grounding, causing the vibration of manipulator due to electrical noise interference. 	<ul style="list-style-type: none"> ■ Connect the grounding wire properly to avoid the electrical noise mixed into the manipulator ■ Please consult with us
Vibration Abnormal noise	<ul style="list-style-type: none"> ■ Abnormal noise after the replacement of lubricating grease ■ Abnormal noise occurs during the operation of robot after a long-term shutdown ■ Abnormal noise at low speed 	Abnormal noise from the manipulator at low speed immediately after the replacement or at the restart after the long-term shutdown.	Observe the operation of manipulator for 1-2 days. Usually, the abnormal noise will disappear.

Shake of manipulator

shows the causes and treatment measures of the shaking of the manipulator. If you cannot determine the cause or how to deal with it, please contact our company.

Table 13-2 Causes and treatment measures of manipulator shaking

Fault	Classification	Possible Causes	Treatment
Shake of manipulator	<ul style="list-style-type: none"> ■ After power-off, some parts of manipulator may be shaken manually. ■ There is a gap between the connecting surfaces of manipulator 	<ul style="list-style-type: none"> ■ Manipulator bolts are loose ■ Connecting bolts on the manipulator are loose due to the overload, collision, etc., thus resulting in the shake 	<p>For each Joint, check if the bolts at the following parts are loose. If so, tighten it with a torque wrench according to a suitable torque.</p> <ul style="list-style-type: none"> ■ Fixing bolts of motor ■ Fixing bolts of reducer shell ■ Fixing bolts of output shaft of reducer ■ Fixing bolts of pedestal ■ Fixing bolts between arms ■ Fixing bolts of shell ■ Fixing bolts of end effector

Fault	Classification	Possible Causes	Treatment
	Turn off the power of manipulator, and confirm that the screws are tightened, and shake the entire head of manipulator manually	Large backlash is resulted from the wear or damage of internal gears of manipulator due to the overload, collision, etc.	If you need to replace the internal gear, please consult with us

Motor overheating

The causes and treatment measures of motor overheating are shown in Table 13-3. If you cannot determine the cause or how to deal with it, please contact our company.

Table 13-3 Causes and treatment measures of motor overheating

Fault	Classification	Possible Causes	Treatment
Motor overheating	<ul style="list-style-type: none"> ■ Ambient temperature rises for installation of manipulator, and the overheating of motor ■ Motor overheats after the cover plate is mounted on the motor ■ Motor overheats after the action procedures of manipulator and load conditions are changed 	<p>Ambient temperature:</p> <ul style="list-style-type: none"> ■ Ambient temperature rises or the deterioration of heat dissipation of motor after the cover plate is installed <p>Load Action:</p> <ul style="list-style-type: none"> ■ Current value of motor exceeds its rated value due to the load and operating procedures 	<ul style="list-style-type: none"> ■ Decrease of ambient temperature may prevent the motor from overheating ■ Improvement of ventilation conditions around the motor, i.e., the heat dissipation of motor, may effectively prevent the motor from overheating. ■ A radiation shielding plate if there is a heat source around the motor may prevent the motor from overheating. ■ Slowing down the action procedures and reducing the load may decrease the average current value of motor, thus preventing the motor from overheating. ■ Please consult with us
	Motor overheats after the action control parameters of manipulator are changed	<p>Control Parameter:</p> <ul style="list-style-type: none"> ■ Improper input parameters will cause the incorrect acceleration and deceleration of robot, so that the average current value of increases. 	<ul style="list-style-type: none"> ■ Enter the appropriate parameters according to the relevant instructions. ■ Please consult with us
	Motor overheats due to the causes other than above ones	<p>Mechanical Fault of Manipulator:</p> <ul style="list-style-type: none"> ■ Mechanical system fault of manipulator causes the overload of motor ■ Motor fault: ■ Brake fault causes the motor to always operate when the brake is 	<ul style="list-style-type: none"> ■ Please rectify the mechanical fault by reference to the instructions of vibration, abnormal noise and looseness. ■ Please confirm whether the brake is released when the motor is powered on.

Fault	Classification	Possible Causes	Treatment
		<p>applied, which causes the motor to withstand excessive load</p> <ul style="list-style-type: none"> ■ Failure of motor body to perform its functions causes the excessive current to flow through the motor 	<ul style="list-style-type: none"> ■ After the motor is replaced, the overheating of motor disappears. It is confirmed that the condition is abnormal. ■ Please consult with us

Leakage of lubricating grease

The causes and treatment measures of grease leakage are shown in Table 13-4. If you cannot determine the cause or how to deal with it, please contact our company.

Table 13-4 Causes of grease leakage and treatment measures

Fault	Classification	Possible Causes	Treatment
Leakage of lubricating grease	Lubricating grease leaks out from the mechanical part	<p>Poor Sealing:</p> <ul style="list-style-type: none"> ■ Crack of casting due to the excessive external force caused by the collision ■ Damage of O-ring during the disassembly and reassembly ■ Scratch of oil seal due to the dust intrusion ■ Poor sealing between the cover plate and casting 	<ul style="list-style-type: none"> ■ In case of casting crack, etc., the sealant may be used to block the lubricating grease as an emergency measure, but in view of the further extension of crack, the part shall be replaced as soon as possible. ■ Please consult with us

Falling of manipulator

Table 13-5 shows the reasons and treatment measures for the falling of the manipulator axis. If you cannot determine the cause or how to deal with it, please contact our company.

Table 13-5 Causes and treatment measures of manipulator axis falling

Fault	Classification	Possible Causes	Treatment
Falling of manipulator axis	<ul style="list-style-type: none"> ■ The brake is completely ineffective and the Joint falls quickly ■ After the brake is contracted, the shaft falls slowly 	<ul style="list-style-type: none"> ■ The damage of brake drive relay causes the brake to always be powered on and not to work. ■ Wear and damage of brake body affect the braking effect. ■ The lubricating oil and grease inside the motor cause the brake to slip. 	<ul style="list-style-type: none"> ■ Check if the brake drive relay is damaged, and if so, replace the relay ■ In case of the wear of brake, the damage of brake body and the lubricating grease inside the motor, replace the motor. ■ Please consult with us

Position offset

The causes and treatment measures of position deviation are shown in Table 13-6. If you cannot determine the cause or how to deal with it, please contact our company.

Table 13-6 Causes of position deviation and treatment measures

Fault	Classification	Possible Causes	Treatment
Position offset	<ul style="list-style-type: none"> ■ Manipulator deviates from the teaching position ■ The repeated positioning accuracy of manipulator is greater than the allowed value 	<p>Mechanical Fault:</p> <ul style="list-style-type: none"> ■ The unstable repeated positioning accuracy may be caused by the mechanical system abnormality, screw looseness, etc. ■ The repeated positioning accuracy keeps stable after the deviation; the joint surface of pedestal surface, Joint casting and reducer may slide due to the excessive load such as the collision. ■ Abnormality of motor encoder 	<ul style="list-style-type: none"> ■ In case of the unstable repeated positioning accuracy, please rectify the mechanical fault by reference to the instructions for the vibration, abnormal noise and shaking. ■ If the repeated positioning accuracy keeps stable, please modify the teaching program. If the collision does not occur again, the deviation may be avoided. ■ In case of the abnormality of motor encoder, replace the motor or encoder. ■ Please consult with us
	Position only deviates from the specific peripheral equipment	<p>Deviation of Peripheral Equipment</p> <ul style="list-style-type: none"> ■ The external equipment under the external force leads to the deviation relative to the manipulator 	<ul style="list-style-type: none"> ■ Please relocate the peripheral equipment ■ Please modify the teaching program ■ Please consult with us

Fault	Classification	Possible Causes	Treatment
	Deviation occurs after the modification of parameters	Parameters: <ul style="list-style-type: none">■ The modification of calibration data causes the loss of manipulator origin	<ul style="list-style-type: none">■ Re-enter the previous correct calibration data■ In case of uncertain calibration data, please recalibrate the manipulator■ Please consult with us

14 Conditions of storage

14.1 Environmental conditions for long-term storage of manipulator

Table 14-1 Environmental conditions for long-term storage of manipulator

Parameter	Value
Min. ambient temperature	-25°C
Max. ambient temperature	55°C
Max. ambient temperature (storage time less than 24 h)	70°C
Max. ambient humidity	Less than 95% at constant temperature, no condensation
Max. vibration condition	Frequency: 22Hz, amplitude: 0.15mm

14.2 Precautions for storage of manipulator

In addition to Chapter 1.5 Environmental Requirements for Operation of this manual, the following shall be paid with attention for the long-term storage of manipulator:

- Before the long-term storage of manipulator, it shall be posed for handling and placed on the horizontal surface. For details, see Chapter9 Transport and Handing of this manual
- When the manipulator is not in use for a long time, cut off all powers, unplug the heavy-duty connector on the body, and cover the heavy-duty connector.
- The exterior protection such as the paper or wooden packing box shall be provided to protect the manipulator body from the long-term exposure of sunlight, water, oil, corrosive liquids, etc.
- The manipulator surface shall be cleaned regularly for dust and pollutant with the specific cleaning cycle depending on the storage environment of manipulator.
- When the storage period is over and the manipulator is put into the operation again, the manipulator shall be checked in accordance with Chapter 3.1 Check item of this manual

Appendix A Periodic maintenance schedule of AIR20-2000B manipulator

Note: ○ indicates that maintenance is required.

Schedule A Periodic maintenance schedule of the manipulator

Item	Maintenance cycle	First Maintenance 320h	3 months 960h	6 months 1,920 h	9 months 2,880 h	1 year 3,840 h	15 months 4,800 h	18 months 5,760 h	21 months 6,720 h	2 years 7,680 h	27 months 8,640 h	30 months 9,600 h	33 months 10,560 h	3 years 11,520 h	39 months 12,480 h	42 months 13,440 h	45 months 14,400 h	4 years 15,360h	51 months 16,320 h	54 months 17,280 h	57 months 18,240 h	5 years 19,200 h
Cleaning of manipulator	0.5h	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○
Cleaning of control cabinet vent	0.1h	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○	○
Check the timing belt for wear	0.5h	○		○	○	○		○		○		○		○		○		○		○		○
Check the manipulator cable for damage	3h	○		○	○	○		○		○		○		○		○		○		○		○
Check the manipulator cable sheath for damage	2h	○		○	○	○		○		○		○		○		○		○		○		○
Check the connecting cable of teach	0.2h	○			○	○				○				○				○				○

Item	Maintenance cycle	First Maintenance 320h	3 months 960h	6 months 1,920h	9 months 2,880h	1 year 3,840h	15 months 4,800h	18 months 5,760h	21 months 6,720h	2 years 7,680h	27 months 8,640h	30 months 9,600h	33 months 10,560h	3 years 11,520h	39 months 12,480h	42 months 13,440h	45 months 14,400h	4 years 15,360h	51 months 16,320h	54 months 17,280h	57 months 18,240h	5 years 19,200h
pendant, control cabinet and manipulator for damage																						
Check the connectors of motor, etc. for looseness	0.2h	○			○	○				○				○					○			○
Tighten the end effector screws	0.2h	○			○	○				○				○					○			○
Tighten the external main screws	1h	○			○	○				○				○					○			○
Check the end effector cable for damage	0.2h	○			○	○				○				○					○			○
Check the limit rubber block for damage	0.1h	○			○	○				○				○					○			○
Replacement of Synchronous	1h					○				○				○					○			○

Item	Maintenance cycle	First Maintenance 320h	3 months 960h	6 months 1,920h	9 months 2,880h	1 year 3,840h	15 months 4,800h	18 months 5,760h	21 months 6,720h	2 years 7,680h	27 months 8,640h	30 months 9,600h	33 months 10,560h	3 years 11,520h	39 months 12,480h	42 months 13,440h	45 months 14,400h	4 years 15,360h	51 months 16,320h	54 months 17,280h	57 months 18,240h	5 years 19,200h
Belt																						
Battery Replacement	0.5h									○								○				
Replace the internal cables of manipulator	8h																	○				
Manipulator overhaul																						○

Appendix B Table of screw strength and tightening torque (Nm)

Appendix B Table of screw strength and tightening torque (Nm)

Thread specification \ Performance level	Performance level		
	8.8 level	10.9 level	12.9 level
M3	1.2	1.6	2.0
M4	2.8	3.7	4.4
M5	5.6	7.5	9
M6	9.5	12.5	15
M8	23	31	36
M10	45	60	70
M12	78	104	125
M14	113	165	195
M16	195	250	305
M20	370	500	600



Prompt

- All screws must be tightened with proper torque.
- Except for the torque specified in the text, the corresponding tightening torque shall be selected according to the screw performance level.
- Remove foreign matters in screws and threaded holes.
- Torque for lightly lubricated screws.
- Screws shall be tightened evenly and symmetrically.
- According to the installation requirements of the reducer and other moving parts, apply thread adhesive to the engagement part of some screws.



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