

Rev.	Desc.	Appr.	Date
1	Brake axis 6 added sh 9, 10 affected	NAH JKCS	84.20

C | Overview scheme Block diagram | Kretsdiagramma Circuit diagram

D | 6397 001-TR
Industrial robot IRB 60/2
ASEA
Kokkistamies
BR JKCS 82 37

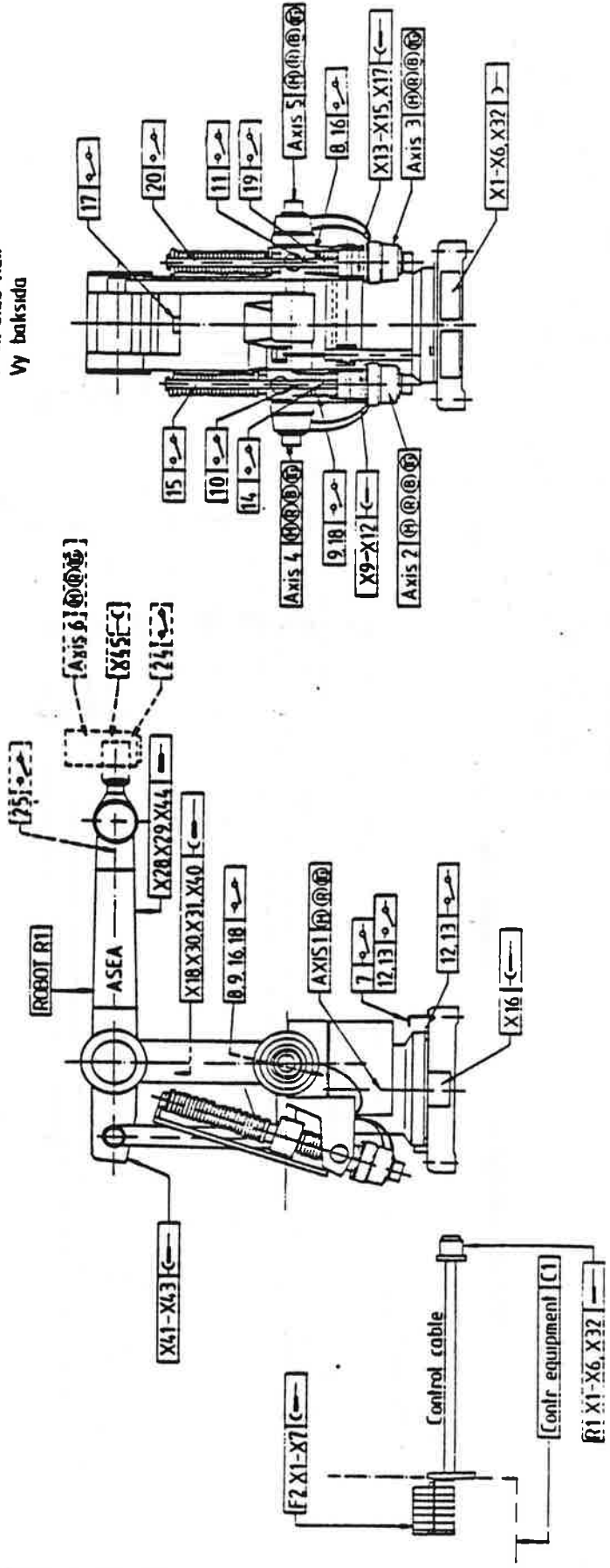
Sheet	Contents
2-5	Control cable
6	Axis 1
7	Axis 2, axis 4
8	Axis 3, axis 5
9	Customer connection
10	Axis 6

Review: Location axis, connectors (←) and switches (→)

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Bildkort

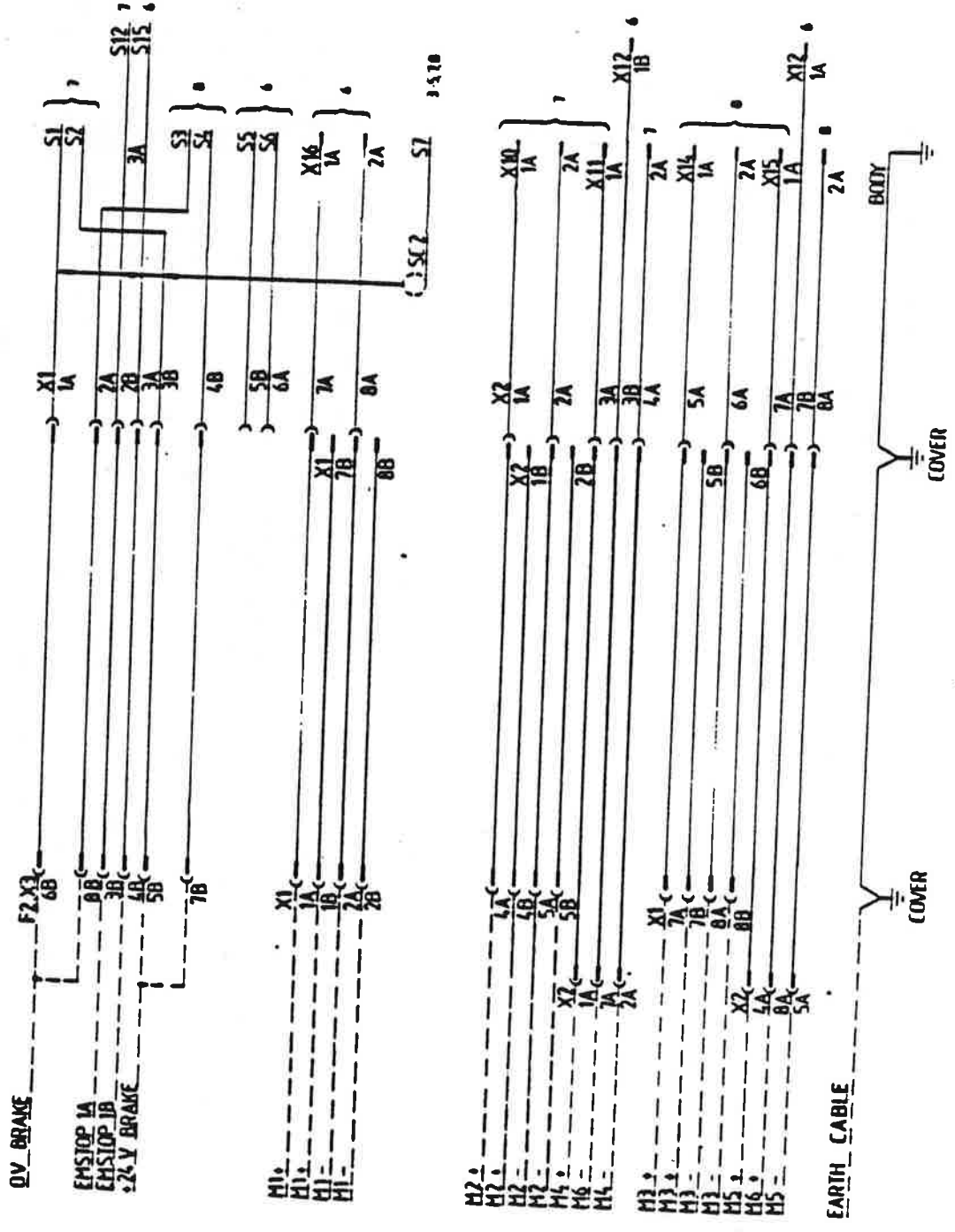
Back side view
Vy baksida

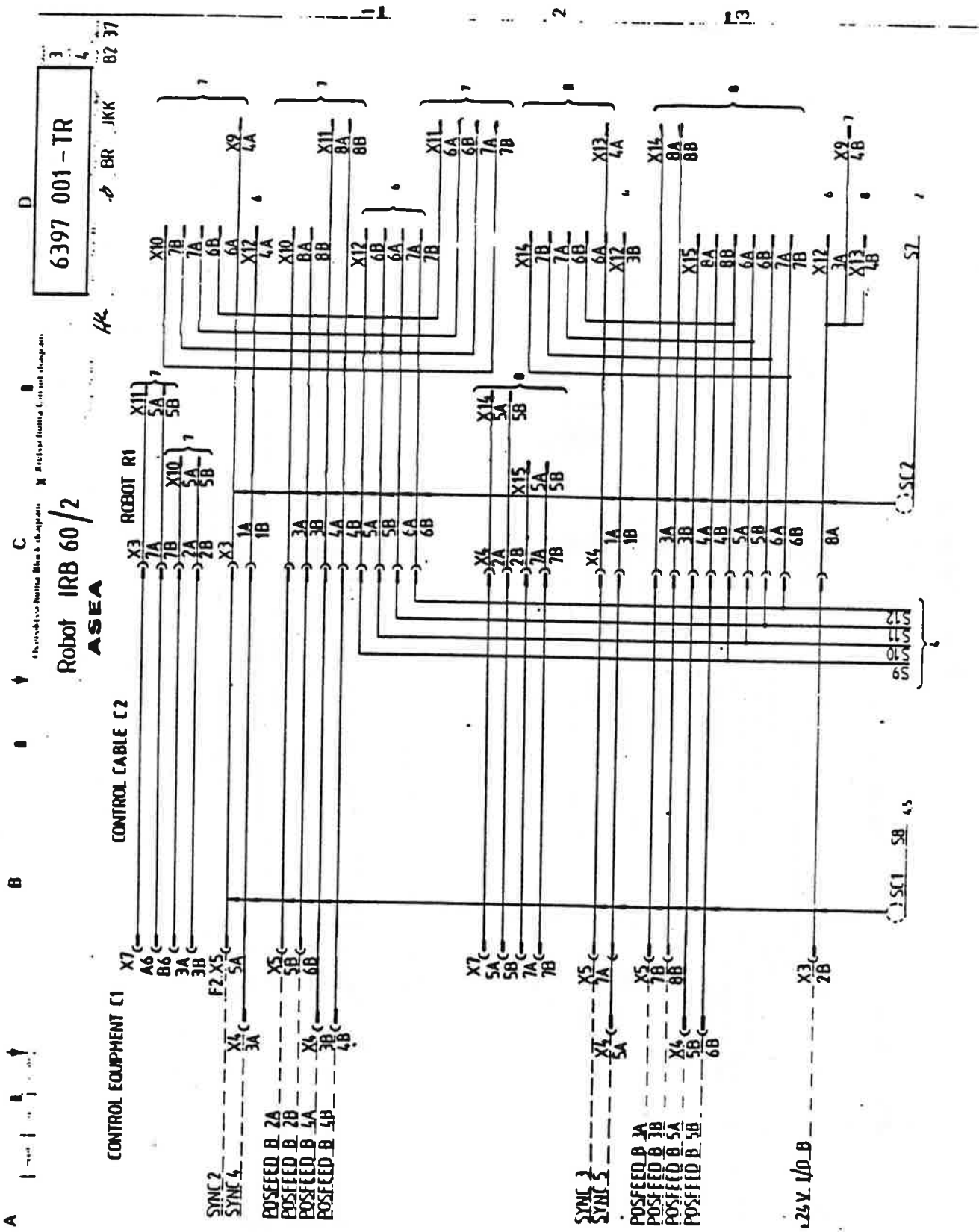


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CONTROL EQUIPMENT C1 CONTROL CABLE C2 ROBOT R1





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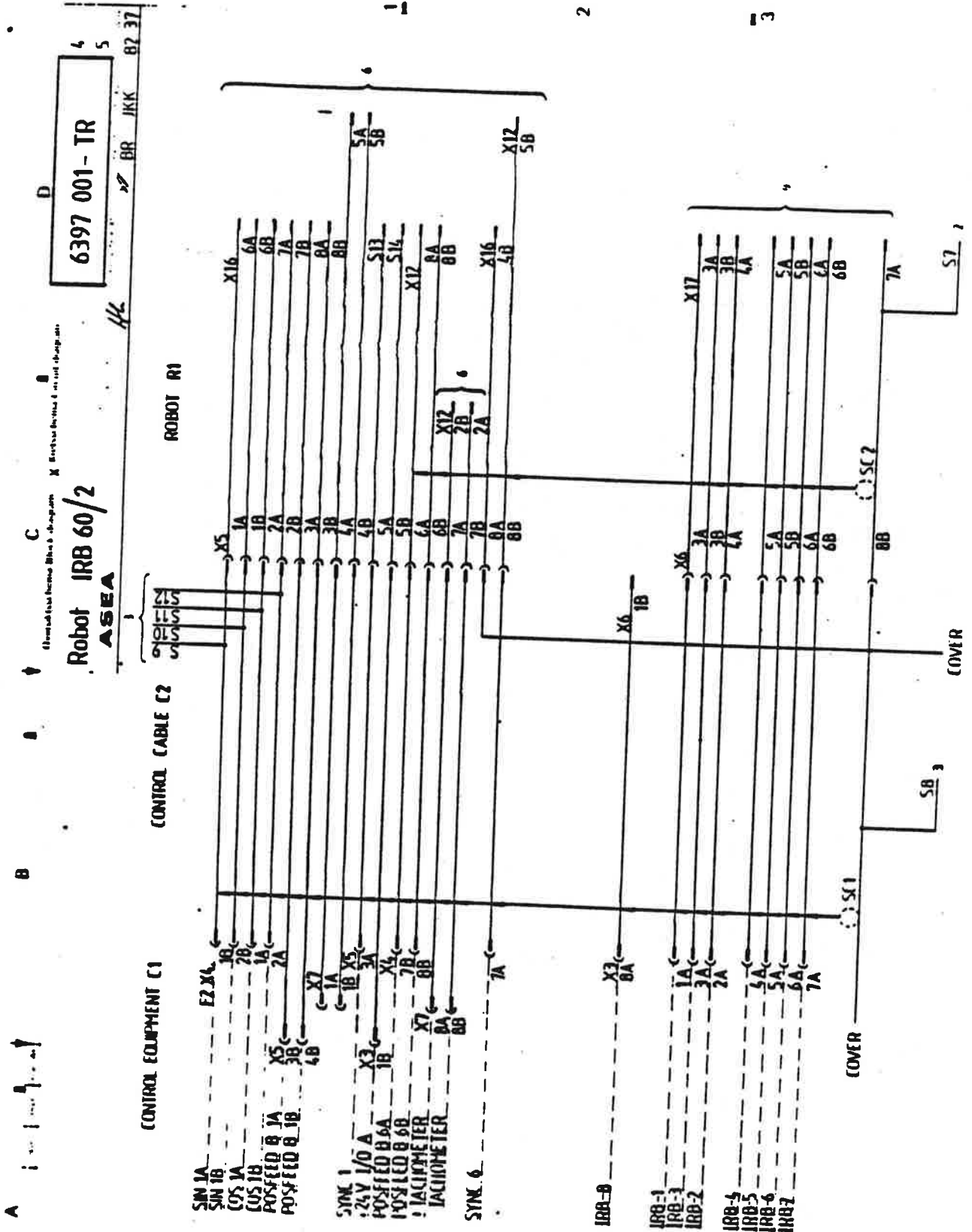
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CONTROL CABLE C2

CONTROL EQUIPMENT C1

ROBOT R1

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1

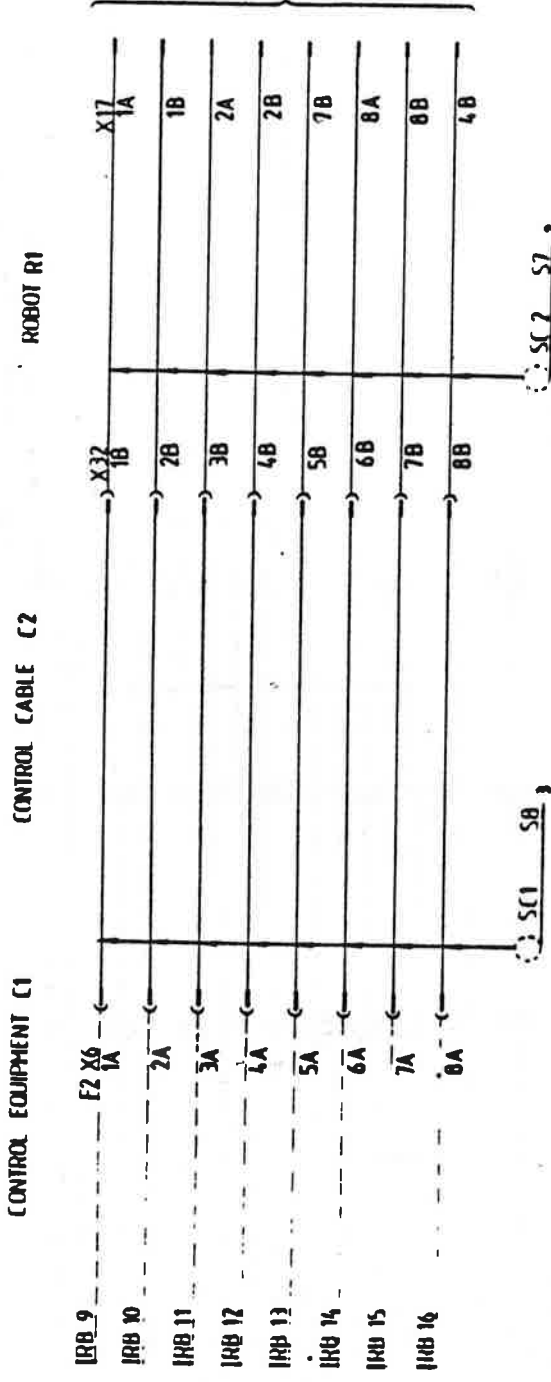
2

3

Robot

3

5
 6
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 Hk
 Robot IRB 60/2
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 Overkyllo Inmat Blue & Rappan X Kattokäyttöön 1 vuosi takuu
 A B C



Bidkon

1

2

3

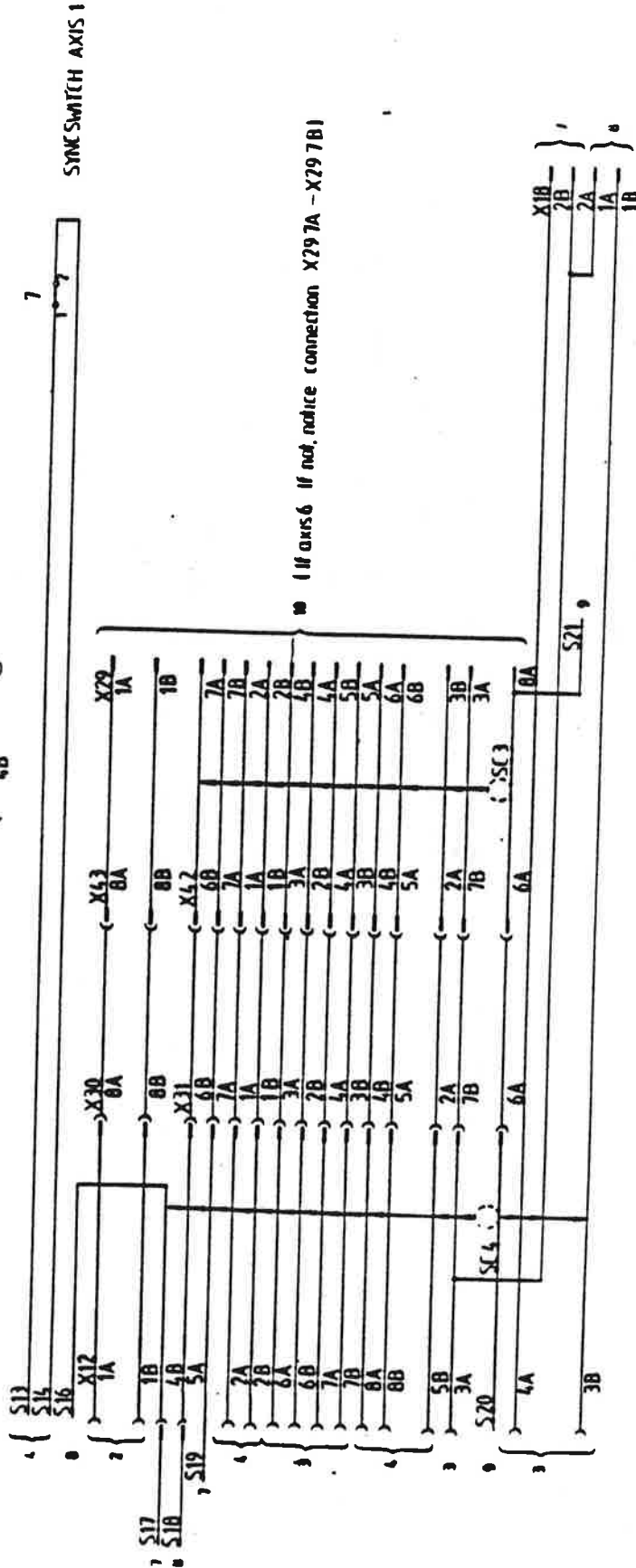
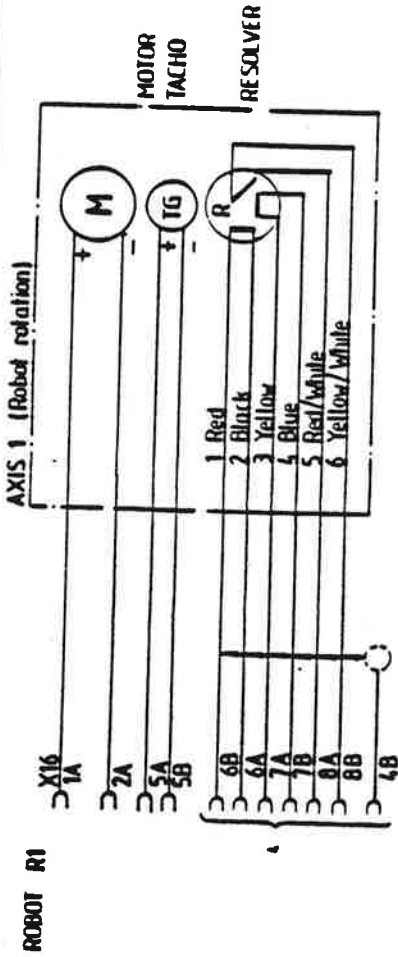
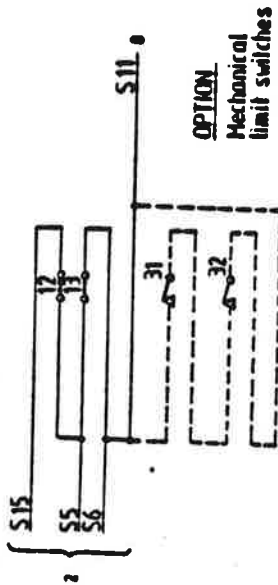
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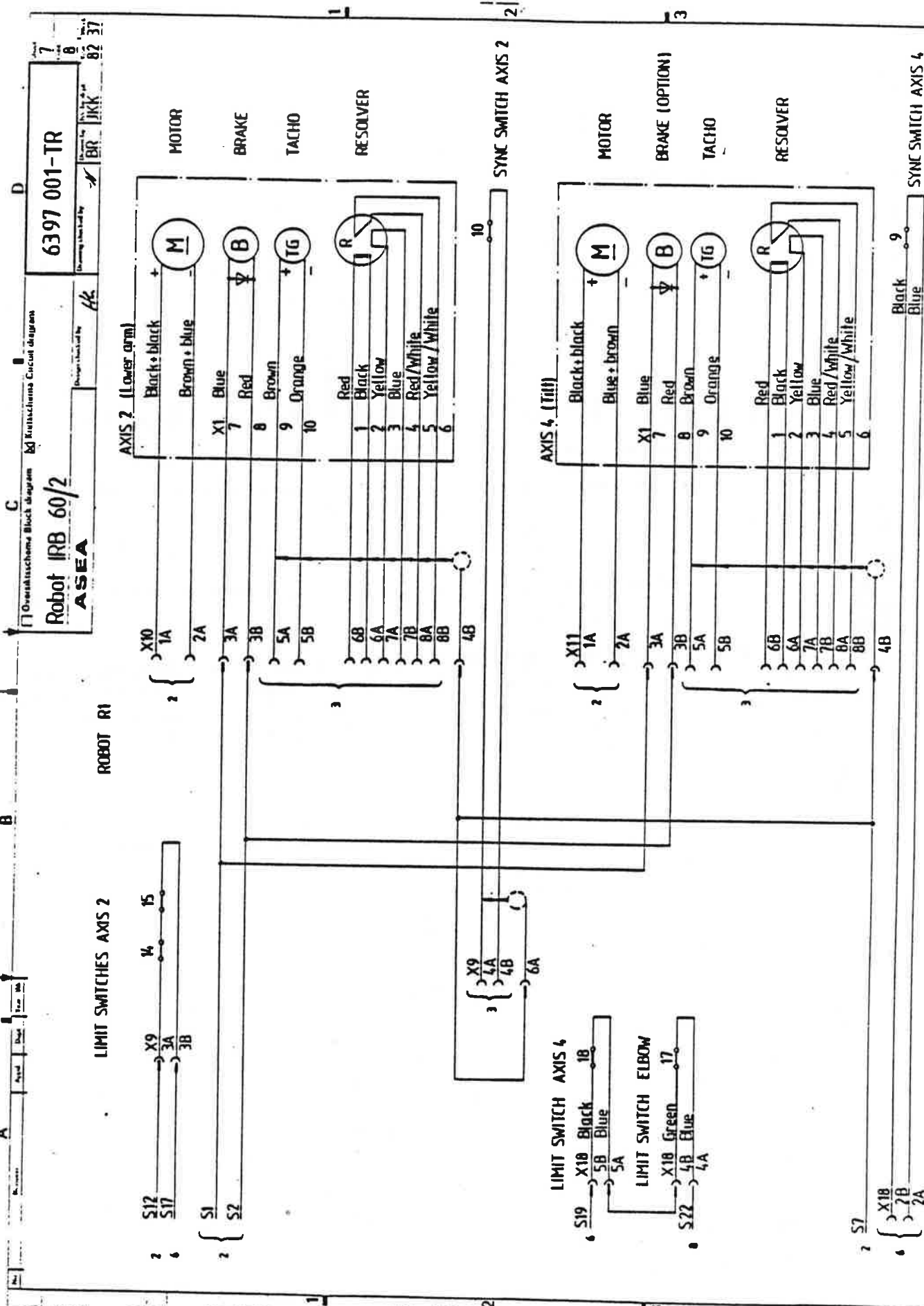
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LIMIT SWITCHES AXIS 1

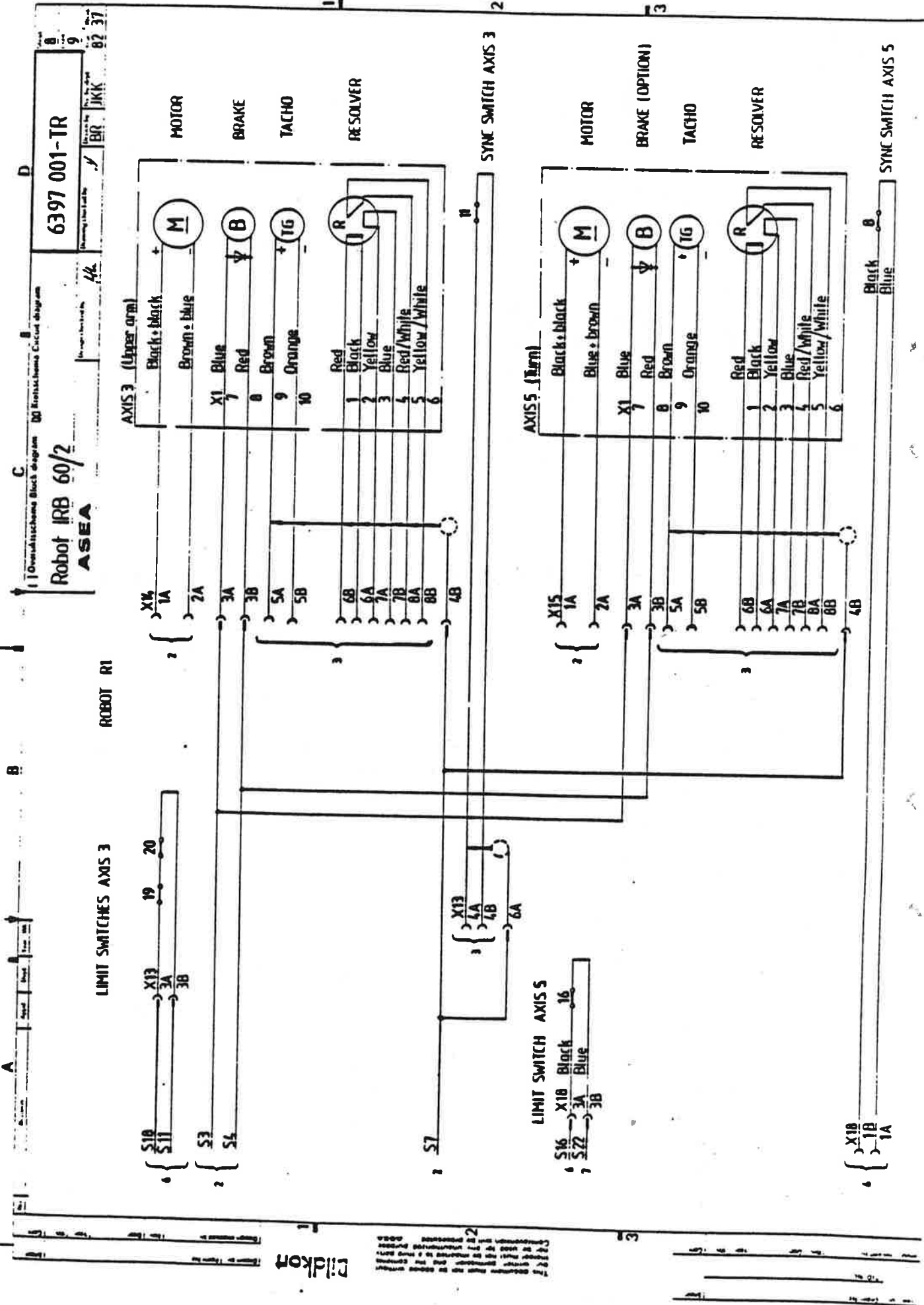




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5017 0500 AA (0543) 02 08



The customer may not be aware of the
 fact that the motor and the resolver
 are not to be connected to a 240V AC
 supply. The motor and the resolver
 are to be connected to a 240V AC
 supply through a transformer.

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1 Note added

A NAH JKCS B4 20

B

C

D

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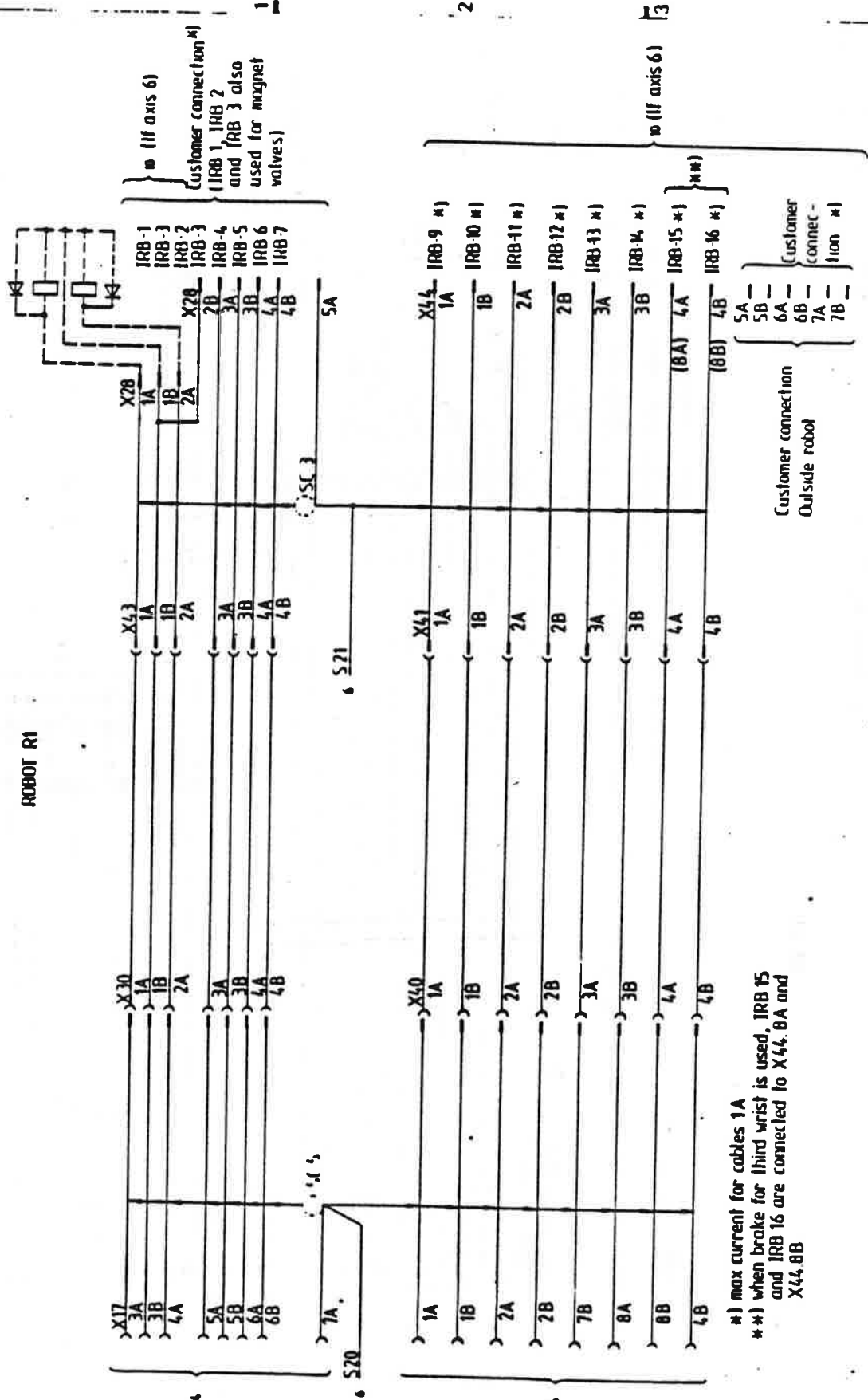
9

10

BR JKK B2 37

Robot IRB 60/2

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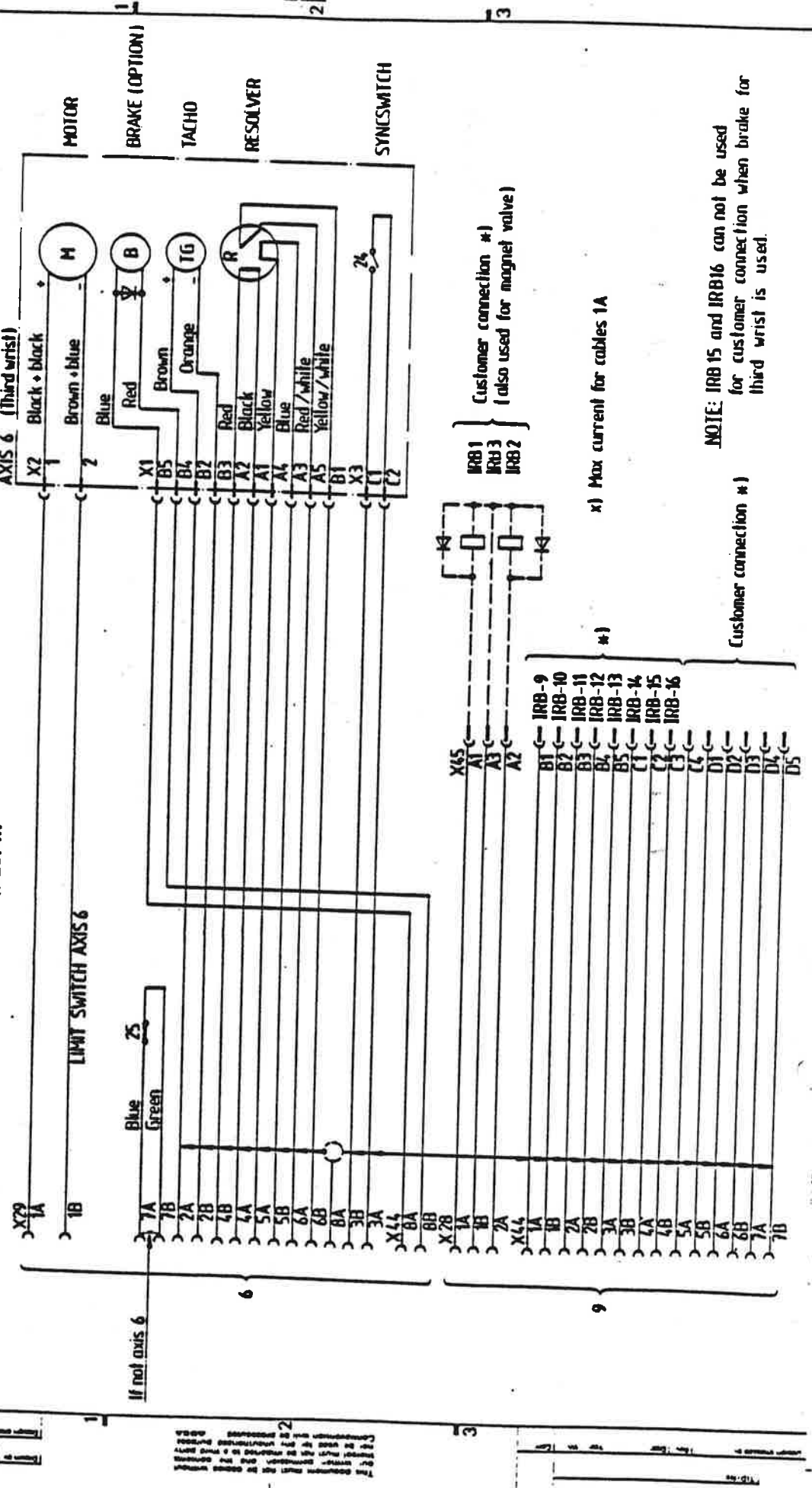
*) max current for cables 1A
 **) when brake for third wrist is used, IRB 15
 and IRB 16 are connected to X44, 8A and
 X44, 8B

Ridkoff

1 Conn. for SYNC SW (X1B) JKS 84 20
 X1B 5 Brake add. JKS 84 20
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 JKS 84 20
 JKS 84 20

OPTION

ROBOT R1



Customer connection #)
(also used for magnet valve)

x) Max current for cables 1A

NOTE: IRB 15 and IRB16 can not be used for customer connection when brake for third wrist is used.

Customer connection #)

EM STOP ROBOT
IRB 60/2

