



Articulated Robot - RA605-GC

User Manual

Original Instruction



HIWIN

www.hiwin.tw

HIWIN INDUSTRIE 4.0 Best Partner





• KK, SK • KS, KA KU, KE, KC

Medical / FPD



Multi-Axis Robot

Pick-and-Place / Assembly / Array and Packaging / Semiconductor / Electro-Optical Industry / Automotive Industry / Food Industry

- Articulated Robot

- Integrated Electric Gripper

Rotary Table

Medical / Automotive Industry /

Linear Guideway

• Quiet Type--QH, QE, QW, QR

• Other--RG, E2, PG, SE, RC

Automation / Semiconductor / Medical Ball Type--HG, EG, WE, MG, CG

Machine Tools / Machinery Industry

RAB Series

- RAS Series
- RCV Series RCH Series



Ballscrew

- Precision Ground / Rolled Super S Series
- Super T Series
- Mini Roller
- Ecological & Economical
- Lubrication Module E2

 Rotating Nut (R1)
- Energy-Saving & Thermal-Controlling (Cool Type)
- Heavy Load Series (RD)
- Ball Spline

Bearing

- Machine Tools / Robot
- Crossed Roller Bearing Ballscrew Bearing
- Linear Bearing
- Support Unit



DATORKER®

Robot / Automation Equipment / Semiconductor Equipment / Machine Tools

- WTI-PH Type
- WTI-AH Type

.



AC Servo Motor & Drive

- Semiconductor / Packaging Machine
- / SMT / Food Industry / LCD
- Drives--D1, D2T/D2T-LM, E1 Motors--50W~2000W



Direct Drive Motor

- Machine Tools
- Torque Motor-
- Inspection / Testing Equipment / Robot
- DMS, DMY, DMN, DMT Series

• Iron-core Linear Motor Coreless Linear Motor

Linear Motor Stage Automated Transport /

AOI Application / Precision /

Linear Turbo Motor LMT

Semiconductor

- Planar Servo Motor • Air Bearing Platform
- X-Y Stage
 Gantry Systems
- Single-Axis Linear Motor Stage



Strain Wave Gear

• WUT-PO Type

- WUI-CO Type

Medical Equipment

Hospital / Rehabilitation Centers /

Nursing Homes Robotic Gait Training System

Robotic Endoscope Holder

Torque Motor &

TM-2/IM-2, TMRW Series

Direct Drive Motor-



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0. Warranty Terms and Conditions

The period of warranty shall commence at the received date of HIWIN product (hereafter called "product") and shall cover a period of 12 months. The warranty does not cover any of the damage and failure resulting from:

- The damage caused by using with the production line or the peripheral equipment not constructed by HIWIN.
- Operating method, environment and storage specifications not specifically recommended in the product manual.
- The damage caused by changing installation place, changing working environment, or improper transfer after being installed by the professional installer.
- Product or peripheral equipment damaged due to collision or accident caused by improper operation or installation by the unauthorized staff.
- > Installing non-genuine HIWIN products.

The following conditions are not covered by the warranty:

- > Product serial number or date of manufacture (month and year) cannot be verified.
- Using non-genuine HIWIN products.
- > Adding or removing any components into/out the product without authorized.
- > Any modification of the wiring and the cable of the product.
- Any modification of the appearance of the product; removal of the components inside the product. e.g., remove the outer cover, product drilling or cutting.
- Damage caused by any natural disaster. i.e., fire, earthquake, tsunami, lightning, windstorms and floods, tornado, typhoon, hurricane etc.

HIWIN does not provide any warranty or compensation to all the damage caused by above-mentioned circumstances unless the user can prove that the product is defective.

For more information towards warranty terms and conditions, please contact the technical stuff or the dealer who you purchased with.



| | * | Improper modification or disassemble the robot might |
|---------|---|---|
| | | reduce the robot function, stability or lifespan. |
| | * | The end-effector or the cable for devices should be installed |
| | | and designed by a professional staff to avoid damaging the |
| WARNING | | robot and robot malfunction. |
| | * | Please contact the technical stuff for special modification |
| | | coming from production line set up. |
| | * | For the safety reason, any modification for HIWIN product is |
| | | strictly prohibited. |



Safety Precautions

Safety Information

- Safety Responsibility and Effect
 - This chapter explains how to use the robot safely. Be sure to read this chapter carefully before using the robot.
 - The user of the HIWIN industrial robot has responsibility to design and install the safety device meeting the industrial safety regulations in order to ensure personal safety.
 - In compliance with the safety information on industrial robot described in this manual can't guarantee that *HIWIN* robot will not occur any safety problems.
 - This machine is defined as a partly completed machinery, the associated hazards must be handled by system integrator in accordance with ISO 10218-1/-2.
 - A safety-related part of control system (SRP/CS) should conform to the requirement of performance level (PL)= d and category 3 according to ISO 13849-1.
 - The installation for emergency functions shall be defined by the system integrator in accordance with ISO 10218-1/-2.
- Safety Operation Principle
 - Emergency Stop button (on Teach Pendant or from external emergency stop switch) must be pressed before turning off the power, and then switch off the power switch.
 - While connecting to the external I/O or the signal, please operate in the condition that the power switch is turned off to prevent from a shortcut caused by mistaken touch in the process, and resulting in damage.



Description Related to Safety

I. Safety Symbols

• Carefully read the instructions in the user manual prior to robot use. The following shows the safety symbols used in this user manual.

| Symbol | Description |
|----------------|--|
| | Failure to follow instructions with this symbol may result |
| DANGER | in serious hazard or personal injury. Please be sure to |
| _ | comply with these instructions. |
| | Failure to follow instructions with this symbol may result |
| WARNING | in personal injury or product damage. Please be sure to |
| | comply with these instructions. |
| | Failure to follow instructions with this symbol may result |
| CAUTION | in poor product performance. Please be sure to comply |
| | with these instructions. |

II. Working Person

- The personnel can be classified as follows
 - Operator:
 - Turns robot controller ON/OFF
 - Starts robot program from operator's panel
 - Reset system alarm
 - Programmer or teaching operator:
 - Turns robot controller ON/OFF
 - Starts robot program from operator's panel
 - Reset system alarm
 - Teaches robot
 - Maintenance engineer:
 - Turns robot controller ON/OFF
 - Starts robot program from operator's panel
 - Reset system alarm
 - Teaches robot
 - Does maintenance, adjustment, replacement
- Programmer and the maintenance engineer must be trained for proper robot operation.



III. Robotic Arm Working Range Definition

Working area

The working area of the robot is defined as the area of motion under motion constraints, and the working area must be limited to the minimum required.

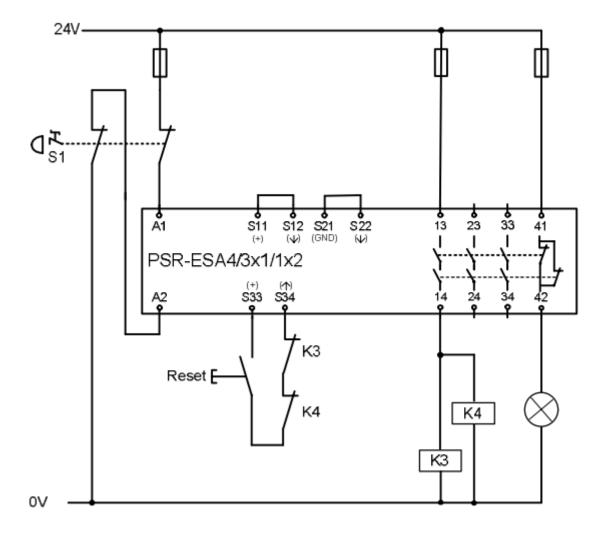
Protective area

Operation must be carried out outside the protected area.

A protected area is an area of the working area that is protected by a safe guard device. Please ensure the protective area includes working area of the robot. A safety-related part of control system (SRP/CS) should conform to the requirement of performance level (PL)= d and category 3 according to ISO 13849-1.

🔔 CAUTION

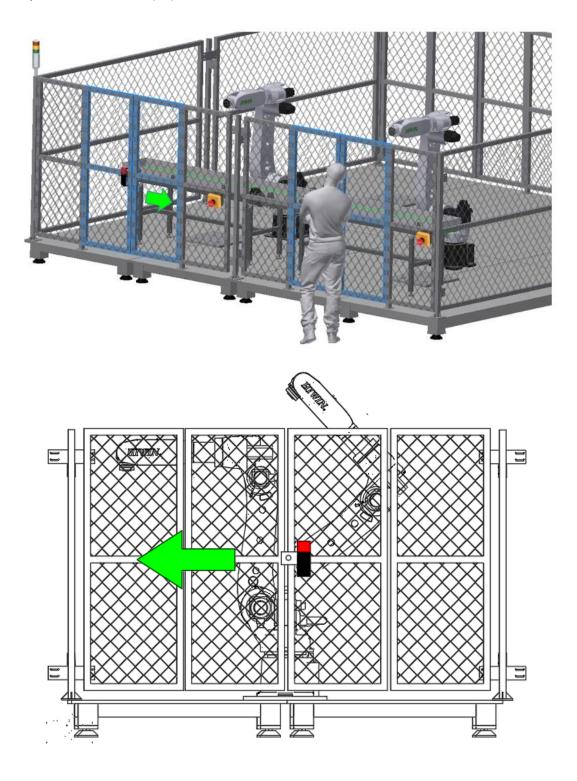
- Please ensure the emergency stop switch is in reset status before the robot functions.
- The external device connected to the emergency stop switch circuit should be dry contact (uncharged) switch. It is forbidden to use a live circuit to connect to the controller emergency stop switch circuit.





CAUTION

It must use EMO-Emergency stop (EN 60947-5-1 positive opening) with safety module to meet ISO 13849-1 performance level (PL)= d



Interlock



IV. Precautions

• Common Safety Issues

| | * | All operating procedures should be assessed by |
|----------|--------------|--|
| | | professional and in compliance with related |
| | | industrial safety regulations. |
| | * | When operating robot, operator needs to wear |
| | | safety equipment, such as workwear for working |
| | | environment, safety shoes and helmets. |
| | * | When encountering danger or other emergency or |
| | | abnormal situation, please press the emergency |
| | | stop button immediately. After danger is |
| | | eliminated, move the robot away with low speed in |
| | | manual mode. |
| | * | When considering safety of the robot, the robot |
| | | and the system must be considered at the same |
| | | time. Be sure to install safety fence or other safety |
| | | equipment and the operator must stand outside |
| | • | the safety fence while operating the robot. |
| | * | A safety zone should be established around the |
| ▲ DANGER | | robot with an appropriate safety device to stop the |
| | * | unauthorized personnel from access. While installing or removing mechanical |
| | * * * | components, be aware of a falling piece which may |
| | | cause injury to operator. |
| | * | Ensure the weight of workpiece does not exceed |
| | • | the rated load or allowable load moment at wrist. |
| | | Exceeding these values could lead to the driver |
| | | alarm or malfunction of the robot. |
| | * | Do not climb on manipulator. |
| | * | The installation for emergency functions shall |
| | | be defined by the system integrator in |
| | | accordance with ISO 10218-1/-2. |
| | * | Do not store the machine in the environment with |
| | | corrosion and flammable gas or close to the |
| | | flammable object. |
| | * | Do not operate the machine in the environment |
| | | with moisture, water or grease. |



| | Do not operate the machine at the place where |
|----------------|--|
| | vibration or the strong impact occurs. |
| | Do not immerse the electric wires into grease or |
| | water. |
| | Do not connect or operate the machine with wet |
| | hands. |
| | \clubsuit Do not operate the machine in potentially |
| | explosive environment. |
| | Please ensure the controller is grounded. |
| | ✤ Keep hands away from the inner part of the |
| | controller while it is connecting to the power or |
| | during operating. |
| | Do not touch the heat sink, regenerative |
| | resistance, the power supply or the computer |
| | inside the controller while it is operating due to its |
| | high temperature. |
| | Be sure power is disconnected prior to repair and |
| | maintenance, and ensure to operate under the |
| | condition of no electrical shock risk. |
| | Do not disassembly the controller without |
| | permission. If there's any issues, please contact our |
| | engineers. |
| | The personnel installing robot should be trained |
| | and licensed. |
| | To ensure personal safety, robot installation must |
| | comply with this manual and related industrial |
| | safety regulations. |
| | The control cabinet should not be placed near high |
| | voltage or machines that generate |
| WARNING | electromagnetic fields to prevent interference that |
| | could cause the robot to deviation or malfunction. |
| | Using non-HIWIN spare parts to repair may cause |
| | robot damage or malfunction. |
| | Beware of the heat generated by the controller and |
| | servo motor. |
| | Do not overbend the cable to avoid poor circuit |
| | |
| | contact or unexpected damage. |



| i | |
|---|--|
| * | Do not stand on the controller or put heavy |
| | objects on it. |
| * | Do not block the vent or put foreign objects into |
| | the controller. |
| * | Please ensure the controller is fixed on the base. |
| * | Do not pull the connector violently or twist the |
| | electric wires excessively. |
| * | Do not frequently switch ON/OFF the power |
| | switch and the control button. |
| * | Please ensure that the robot, the emergency stop |
| | switch and the controller are functioning properly |
| | before performing any work. |
| * | Do not shutdown the power switch during the |
| | operation. |
| * | Do not open, modify, disassemble and maintain |
| | the machine without permission. |
| * | The power must be disconnected when the |
| | machine does not operate in a long time. |
| * | Do not turn off the power of the controller when |
| | modifying the program or parameter. Otherwise, |
| | the data stored in the controller will be damaged. |
| * | After the brake of a servo motor is released, the |
| | robot will be moved due to gravity and it may |
| | injured the operator. |
| * | The industrial robots can be applied for the |
| | different industrial environments, but the |
| | applicable environment should be determined by |
| | professionals. |
| * | When the operating procedures are interrupted, |
| | the special attention should be paid during the |
| | troubleshooting. |



| | * |
|--------|---|
| DANGER | |
| | * |

Teaching, jogging or programming should be done outside of the safety fence. If it is inevitable to enter the safety fence, press the emergency stop button before entrance. Operation should be restricted at low speed and beware of surrounding safety.
 All operations shall be executed by trained staff.

Maintenance

| enance | | | | |
|---------------|---|--|--|--|
| | * | Please contact us if the procedure not specified by | | |
| | | HIWIN is needed. | | |
| | * | Please contact us if the replacement of the | | |
| | | component not specified by HIWIN is needed. | | |
| | * | Be sure to carry out regular maintenance, | | |
| | | otherwise it will affect the service life of the robot | | |
| | | or other unexpected danger. | | |
| DANGER | * | Prior to repair and maintenance, please switch off | | |
| | | power supply. | | |
| | * | Maintenance and repair should be performed by a | | |
| | | qualified operator with a complete understanding | | |
| | | of the entire system to avoid risk of robot damage | | |
| | | and personal injury. | | |
| | * | When replacing the components, avoid foreign | | |
| | | object going into the robot. | | |



• End Effector

The end effector can be classified as two types:

- A. Gripper: Used to load and unload, such as pneumatic gripper, electric gripper and vacuum sucker.
- B. Tool: Used to process, such as welding, cutting and surface treatment.

| | Π | |
|---------------|----|---|
| | * | More attention must be paid to the design of the |
| | | end effector to prevent power loss or any other |
| | | errors that could lead to workpiece falling or |
| | | damage. |
| | * | The tool-type end effector is usually equipped with |
| DANGER | | high voltage, high temperature and active rotary |
| | | shaft. Special attention should be paid to the |
| | | operating safety. |
| | • | |
| | * | The end effector should be mounted firmly on the |
| | | robot to avoid workpiece fall during operation |
| | | which may cause personal injury or hazard. |
| | • | |
| | * | The end effector may be equipped with its own |
| | ** | The end effector may be equipped with its own control unit. During installation, pay attention to |
| | ** | |
| | ** | control unit. During installation, pay attention to |
| | * | control unit. During installation, pay attention to installed location. Ensure that the control unit does |
| ▲ WARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. |
| 🔔 WARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. The gripper-type end effector should prevent the |
| 🔔 WARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. The gripper-type end effector should prevent the workpiece from dropping or damaging when the |
| \rm MARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. The gripper-type end effector should prevent the workpiece from dropping or damaging when the robot experiences a power error or other errors. If potential dangers or abnormal situations exist |
| \rm MARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. The gripper-type end effector should prevent the workpiece from dropping or damaging when the robot experiences a power error or other errors. If potential dangers or abnormal situations exist when using end effector, the associated hazards |
| A WARNING | | control unit. During installation, pay attention to installed location. Ensure that the control unit does not interfere with robot operation. The gripper-type end effector should prevent the workpiece from dropping or damaging when the robot experiences a power error or other errors. If potential dangers or abnormal situations exist |

• Pneumatic, Hydraulic System

| 🔺 DANGER | * | When using the pneumatic or hydraulic system, the gripped workpiece may fall due to insufficient pressure or gravity. The pneumatic or hydraulic system must be equipped with the relief valve, so that it can be applied in an emergency. |
|-----------|---|---|
| 🔔 WARNING | * | More attention should be paid to the pressure remained in the pneumatic systems after the power is disconnected. |



| * | The internal pressure must be released before the |
|---|---|
| | pneumatic systems are maintained. |
| * | More attention should be paid to the pressure in |
| | the pneumatic system as it is several times more |
| | than the atmosphere pressure. |

Emergency Stop Switch

| gency Stop Switch | |
|-------------------|--|
| | The robot or other control component should have |
| | at least one device for immediate halt, such as an |
| | emergency stop switch. |
| | The emergency stop button must be installed in an |
| | easily accessible location for quick stop. |
| | While executing an emergency stop, power to the |
| DANGER | servo motor will be cut, and all movements will be |
| | stopped. And the control system will be shut down. |
| | Emergency stop should be reset if the restoration |
| | of operating procedure is wanted. |
| | ✤ Avoid using emergency stop to replace a normal |
| | stop procedure. This could reduce the lifespan of |
| | the robot. |
| | $\boldsymbol{\diamondsuit}$ The drive power and the control system will be |
| | disconnected to stop all actions during the |
| | emergency stop. |
| | If you want to restart the procedures, you should |
| | reset the emergency stop switch. |
| | Emergency stop established an immediate stop: |
| | Immediately stop the robot system, and disconnect |
| | the driver power. |
| | The emergency stop switch is used for emergency |
| 🔔 WARNING | stop only. |
| | The HIWIN robot is equipped with two emergency |
| | stop switches, where one is installed on the teach |
| | pendant and the other is directly connected to the |
| | controller via a cable. If additional emergency stop |
| | switches are required, other connecting method |
| | can be applied for the same purpose. |
| | Based on the relevant industrial safety regulations, |
| | the emergency stop switch is directly connected to |
| | the controller of the robot via the physical wires. |



| | If the momion of the broking is not emplied to the |
|---------------------------------------|---|
| · · · · · · · · · · · · · · · · · · · | If the version of the braking is not applied to the |
| | whole axis, once the emergency stop is executed |
| | and the heavy objects are loaded on the robot end, |
| | the axis without brake will move due to gravity. This |
| | attention must be paid for safety issue. |

V. Intended use

HIWIN robots are industrial robots and intended for pick-and-place, handling, assembling, debarring, grinding and polishing. Use is only permitted under the specified environment, for more detailed information please see section 1.5 environmental conditions.

Use is not permitted under the following conditions:

- Use in potentially explosive environments
- Use without performing risk assessments
- Transportation of people and animals
- Operation outside the allowed operating parameters

VI. Disposal

The disposal of HIWIN robot shall be in accordance with the local environmental regulations.



1. Transportation and Installation

1.1 Transportation

Sling can be used to transport the robot. The transportation procedure is as follows:

- Step1. Move the robot into its transport posture and the angle of each joint is shown in the Figure 1-1 and Table 1-1.
- Step2. Secure the suspension plate to the robot with four M8×1.25P×12L screws as shown in Figure 1-2.
 Make the sling go through the suspension plate to keep the center of gravity under the hanging point shown as Figure 1-3.
 Please ensure the robot is in stable condition to avoid overturning.
- Step3. Move the robot to the desired position by using sling.
- Step4. Remove the suspension plate.

[Note] The transport suspension plate (RA605Z541-13) is an optional part. Please refer to appendix for the dimensions.

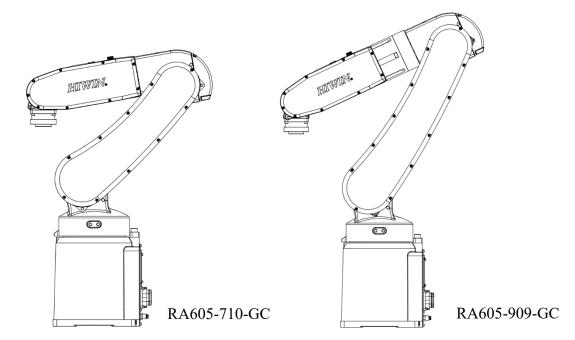


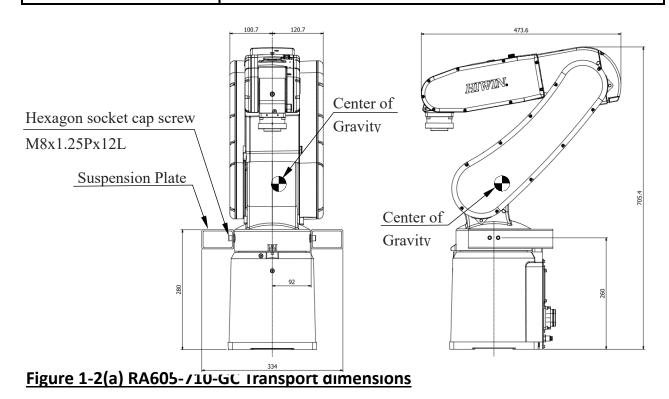
Figure 1-1 Transport posture



| Transport Posture Degree | | | | |
|--------------------------|--------------|--------------|--|--|
| | RA605-710-GC | RA605-909-GC | | |
| J1 | 0° | 0° | | |
| J2 | 45° | 30° | | |
| J3 | -55° | -55° | | |
| J4 | 0° | 0° | | |
| J5 | -80° | -65° | | |
| J6 | 0° | 0° | | |

| Table 1-1 The transport posture angle with each axis about each model of RA605-G | С |
|--|---|
|--|---|

| | - | |
|-----------|---|---|
| | * | Before carrying the robot, be sure to remove the end effector |
| | | which changes the center of gravity. |
| | * | Please keep stable, slow down and avoid excessive vibration |
| | | or shock during transportation. |
| A WARNING | * | While placing the robot be sure to avoid the robot and the |
| | | installation surface collision. |
| | * | After removing the suspension plate, please maintain it |
| | | properly for re-transportation. |
| | * | Before operation, remove the suspension plate to avoid |
| | | danger. |





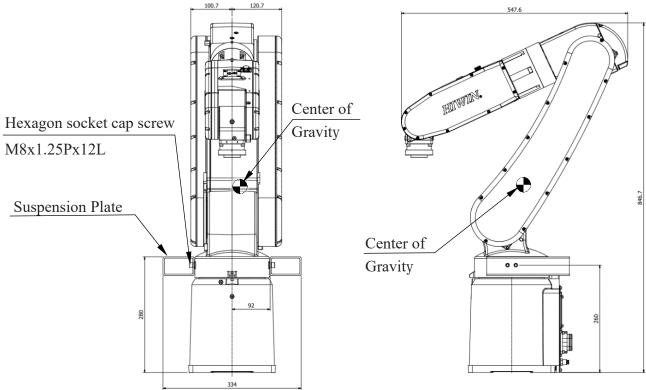


Figure 1-2(b) RA605-909-GC Transport dimensions

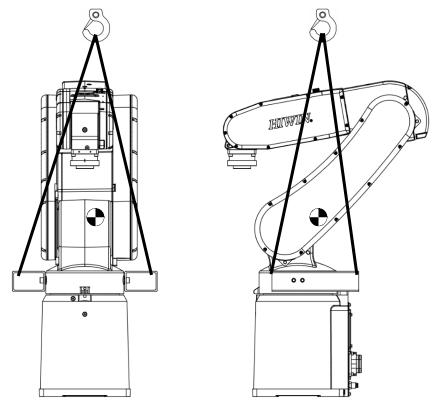
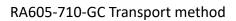


Figure 1-3(a) Crane lifting transportation





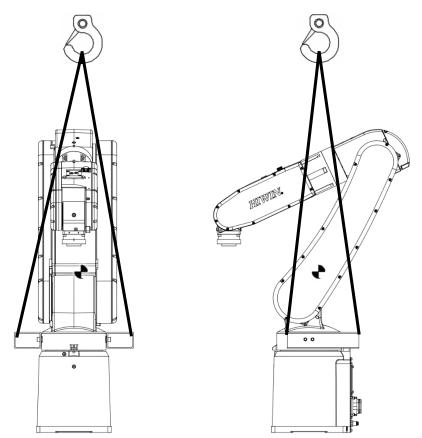


Figure 1-3(b) Crane lifting transportation RA605-909-GC Transport method

| | * | After removing the suspension plate, please keep |
|-----------------|---|--|
| | | it properly for re-transportation. |
| | * | Please always follow the above instructions and |
| | | method to transport the robot for subsequent |
| A DANGER | | transportation. |
| A DANGER | * | If the robot is directly suspended without using the |
| | | specified suspension plate, it will cause danger due |
| | | to an incorrect center of gravity position. |
| | * | Please always stay in stable condition and avoid |
| | | excessive vibration or shock during transportation. |



1.2 Installation

Figure 1-4 shows the installation dimensions of the robot. According to the dimensions, fix the robot on the installation surface with M10 screws, spring washer and flat washer shown as Figure 1-5. Figure 1-6 and table 1-2 and table 1-3 show the forces and moments acting on the installation surface during operation. The strength of surface must be considered when installing the robot. It is recommended to use screws bigger than M10X20L.

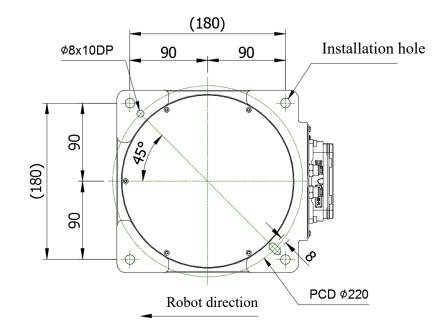


Figure 1-4 Base dimensions

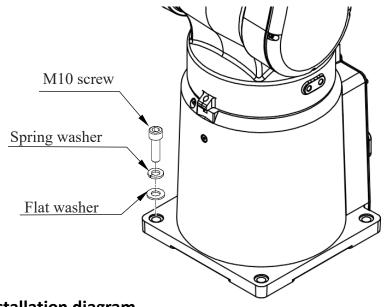


Figure 1-5 Installation diagram



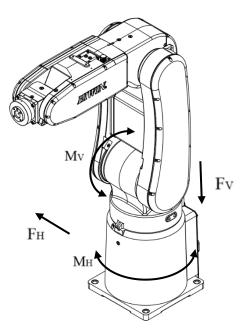


Figure 1-6 Forces and moments acting on the installation surface

| | Vertical moment Mv (Nm) | Vertical force Fv (N) | Horizontal moment Mн (Nm) | Horizontal force Fн (N) |
|-------------------------------|----------------------------|--------------------------|---------------------------------|----------------------------|
| Stop | 144 | 441 | 0 | 0 |
| Acceleration /Deceleration | 382 | 1009 | 149 | 456 |
| Power cut stop | 462 | 1199 | 248 | 760 |

Table 1-3 RA605-909-GC Value of forces and moments acting on the installation surface

| | Vertical moment Mv (Nm) | Vertical force Fv (N) | Horizontal moment Mम (Nm) | Horizontal force Fн (N) |
|-------------------------------|----------------------------|--------------------------|---------------------------------|----------------------------|
| Stop | 160 | 490 | 0 | 0 |
| Acceleration /Deceleration | 526 | 1205 | 244 | 748 |
| Power cut stop | 660 | 1467 | 407 | 1246 |

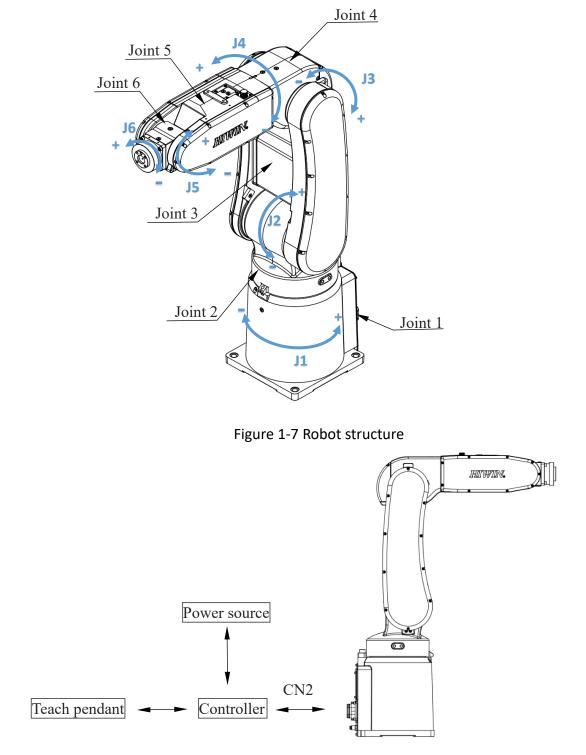


| | * | Ensure the installation surface is smooth plane which is |
|----------------|---|--|
| | | recommended to be 6.3a or less for the roughness. If the |
| | | installation surface is rough, the robot could produce the |
| | | position shift during the operation. |
| | * | Ensure the position of the installation surface for the robot |
| | | will not shift while in operation. |
| WARNING | * | Ensure the strength of the installation surface for the robot |
| | | will not be damaged due to the movement. |
| | * | Do not install the robot at the place with direct sunlight or |
| | | light. If the temperature on the cover is too high, it may cause |
| | | poor performance. |
| | * | When the robot is installed on the ceiling or the wall, the |
| | | parameters must be changed. If you have any inquiry, please |
| | | contact HIWIN. |



1.3 Connection with the Controller

Figure 1-7 shows the structure drawing of the robot. ; Figure 1-8 shows the connection between robot, controller, teach pendant and power source. Figure 1-9 and Figure 1-10 show the interface of J1 and the pin assignment of CN2 connector.





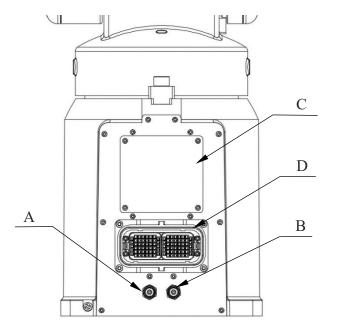


Figure 1-8 Robot and controller connection

| Code | RA605-GC |
|------|---------------------|
| A | Air in/out socket |
| В | Air in/out socket |
| С | Battery box |
| D | Power/signal socket |

Figure 1-9 Interface at the rear of J1

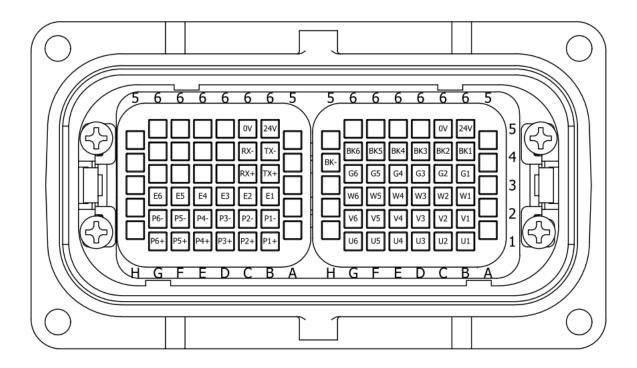


Figure 1-10 Pin assignment of the Power/Signal socket



1.4 Grounding

Figure 1-11 shows the grounding connection of the robot with the screw (M5×0.8P×8L).

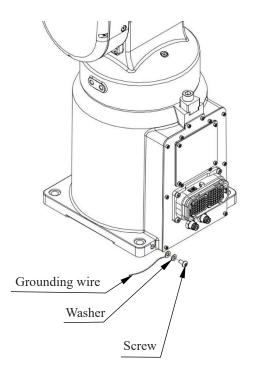


Figure 1-11 Grounding method

| | * | The diameter of a grounding cable should not be larger than 14AWG. |
|------------------|---|---|
| ! CAUTION | * | The grounding cable of the robot should be connected directly to the main system grounding, not to the grounding for other equipment. |

| 🔔 WARNING | * | When connecting the cable, be sure to turn off power supply first. |
|-----------|---|--|
|-----------|---|--|



1.5 Environmental Conditions

Environment condition is shown in Table 1-4.

| Installation/Storage/Transportation Environment | | | |
|---|--|--|--|
| Ambient temperature | 0~45 ℃ [Note 1] | | |
| Ambient relative humidity | Under 75% R.H. | | |
| | No condensation permissible | | |
| Allowable altitude | Up to 1000 m above mean sea level [Note 2] | | |
| Allowable vibration | Under 0.5G | | |
| | Do not use under corrosive environment | | |
| Others | Do not use under flammable environment | | |
| others | Do not use under explosive environment | | |
| | Do not use under radiative environment | | |

Table 1-4 Environmental conditions

[Note 1] : When the robot is stopped for a long period of time at the temperature near 0° C, the robot operation may have greater resistance in the beginning and then an overload alarm may be raised. It is recommended to warm up the robot at low speed for a few minutes.

[Note 2] : The performance level will be de-rated around 10% at an altitude over 1000m.



1.6 Standard and Optional Equipment List

Standard and optional equipment list is shown in Table 1-5.

Table 1-5 Standard and optional equipment list

| | | | Optional | Optional | |
|-------------------------------------|--------------|----------|------------|------------|-------------------------------------|
| Item | HIWIN | Standard | RA605- | RA605- | Remark |
| | Part No. | | 710-GC | 909-GC | |
| | | | | | Including calibration tool |
| Manipulator accessory kit | RA605Z541-1 | • | \bigcirc | \bigcirc | set and End-effector I/O |
| | | | | | cable |
| Calibration tool set | RA605Z541-2 | • | 0 | \bigcirc | Refer to section 4.1 |
| End-effector I/O Cable | RA605Z541-3 | • | 0 | \bigcirc | Refer to section 3.3 |
| R I/O water-proof cover | RA605Z541-4 | • | 0 | \bigcirc | |
| J2 belt | RA605Z541-5 | | 0 | | Refer to section 6.2.2 |
| J2 belt | RA605Z541-6 | | | \bigcirc | Refer to section 6.2.2 |
| J3 belt | RA605Z541-7 | | 0 | | Refer to section 6.2.2 |
| J3 belt | RA605Z541-8 | | | \bigcirc | Refer to section 6.2.2 |
| J5 、J6 belt | RA605Z541-9 | | \bigcirc | \bigcirc | Refer to section 6.2.2 |
| Encoder battery | RA605Z541-10 | | 0 | \bigcirc | Refer to section 6.2.1 |
| Manual brake release device | RA605Z541-11 | | \bigcirc | \bigcirc | Refer to section 5.1 |
| Robot base | RA605Z541-12 | | 0 | \bigcirc | Refer to official website |
| Suspension plate set | RA605Z541-13 | | \bigcirc | \bigcirc | Refer to section 1.1 |
| Adjustable Mechanical Stop set | RA605Z541-14 | | 0 | \bigcirc | |
| Teach Pendant | RC600Z001-1 | • | 0 | \bigcirc | Refer to RCA-GC User manual CH 4 |
| Teach Pendant Shortcut Connector | RC600Z001-2 | • | 0 | \bigcirc | Refer to RCA-GC User manual CH 4 |



| CN1, Main Power Cable 3M | RC600Z001-3 | • | 0 | 0 | Refer to RCA-GC User manual CH 2.3 |
|---|--------------|---|------------|------------|--|
| CN2, Power Signal Cable 3M | RC600Z001-4 | • | 0 | \bigcirc | Refer to RCA-GC User manual CH 2.5 |
| CN2, Power Signal Cable 5M | RC600Z001-5 | | 0 | 0 | Refer to RCA-GC User manual CH 2.5 |
| CN2, Power Signal Cable 10M | RC600Z001-6 | | 0 | 0 | Refer to CH 2.5 |
| CN2, Power Signal Cable 3M for Drag Chain | RC600Z001-7 | | 0 | 0 | Refer to CH 2.5 |
| CN2, Power Signal Cable 5M for Drag Chain | RC600Z001-8 | | 0 | 0 | Refer to CH 2.5 |
| CN2, Power Signal Cable 10M for Drag Chain | RC600Z001-9 | | 0 | \bigcirc | Refer to CH 2.5 |
| CN3 Emergency Stop Switch Unit 5M | RC600Z001-21 | | 0 | \bigcirc | Refer to RCA-GC User manual CH 2.6 |
| GC Controller Accessory Kit | RC600Z001-12 | • | 0 | \bigcirc | Refer to RCA-GC User manual Table 1 |
| External I/O Expansion Module _(Note 1) (Note 1) | RC600Z001-22 | | 0 | \bigcirc | Refer to RCA-GC User manual Table 2 |
| D-Sub Connector Wiring Set 37P(6M) | RC600Z001-26 | | 0 | \bigcirc | Refer to RCA-GC User manual Table 3 |
| Encoder Expansion Module | RC600Z001-27 | | 0 | \bigcirc | Refer to RCA-GC User manual Table 4 |
| CC-Link interface card | RC600Z001-30 | | \bigcirc | \bigcirc | Refer to RCA-GC User manual CH 3.8 |
| PROFINET IO interface card | RC600Z001-31 | | \bigcirc | \bigcirc | Refer to RCA-GC User manual CH 3.9 |
| EtherNet/IP interface card | RC600Z001-32 | | \bigcirc | \bigcirc | Refer to RCA-GC User manual CH 3.10 |

*Note 1:

Include Expansion card and wiring set.

Maximum Expansion: 16 Input and 16 Output.



| Item | HIWIN Part No. | Quantity | Note |
|--------------------------------|----------------|----------|--|
| D-Sub Connector 15P | RC600Z001-13 | 1 | Refer to RCA-GC User manual CH 2.6 |
| Housing of D-Sub Connector 15P | RC600Z001-14 | 1 | Refer to RCA-GC User manual CH 2.6. |
| D-Sub Connector 37P | RC600Z001-15 | 3 | Refer to RCA-GC User manual CH 3.4. |
| Housing of D-Sub Connector 37P | RC600Z001-16 | 3 | Refer to RCA-GC User manual CH 3.4. |
| Cotton Filter | RC600Z001-17 | 4 | Refer to RCA-GC User manual CH 5.1. |
| Fuse 15A(Fuse1~3) | RC600Z001-18 | 3 | Refer to RCA-GC User manual CH 5.2. |
| Fuse 5A(Fuse4) | RC600Z001-19 | 2 | Refer to RCA-GC User manual CH 5.2. |
| Fuse 2A(Fuse5) | RC600Z001-20 | 2 | Refer to RCA-GC User manual CH 5.2. |

Table 1: GC Controller accessory kit contents



Table 2: External I/O Expansion Module contents

| Item | HIWIN Part No. | Quantity | Note |
|---------------------------------------|----------------|----------|--|
| External I/O Extension card | RC600Z001-23 | 1 | Refer to RCA-GC User manual CH 3.4. |
| 37P Terminal Block | RC600Z001-24 | 1 | Refer to RCA-GC User manual CH 3.4. |
| 37P cable with D-Sub connector(6M) | RC600Z001-25 | 1 | Refer to RCA-GC User manual CH 3.4. |

Table 3: D-Sub connector wiring set 37P contents

| Item | HIWIN Part No. | Quantity | Note |
|---------------------------------------|----------------|----------|--|
| 37P Terminal Block | RC600Z001-24 | 2 | Refer to RCA-GC User manual CH 3.4. |
| 37P cable with D-Sub connector(6M) | RC600Z001-25 | 2 | Refer to RCA-GC User manual CH 3.4. |

Table 4: Encoder Expansion Module contents

| Item | HIWIN Part No. | Quantity | Note |
|--|----------------|----------|--|
| Encoder Capture Card | RC600Z001-29 | 1 | Refer to RCA-GC User manual CH 3.4. |
| 37P Terminal Block | RC600Z001-24 | 1 | Refer to RCA-GC User manual CH 3.4. |
| 37P cable with D-Sub connector(10M) | RC600Z001-28 | 1 | Refer to RCA-GC User manual CH 3.4. |

Note2: If some (standard and optional) equipment needs to be assembled in the controller before shipment, please inform sales representative when purchasing.



2. Basic Specifications

2.1 Description of Model Name

There is a model name on the specification label of RA605-GC. The explanation of model name is shown Figure 2-1.

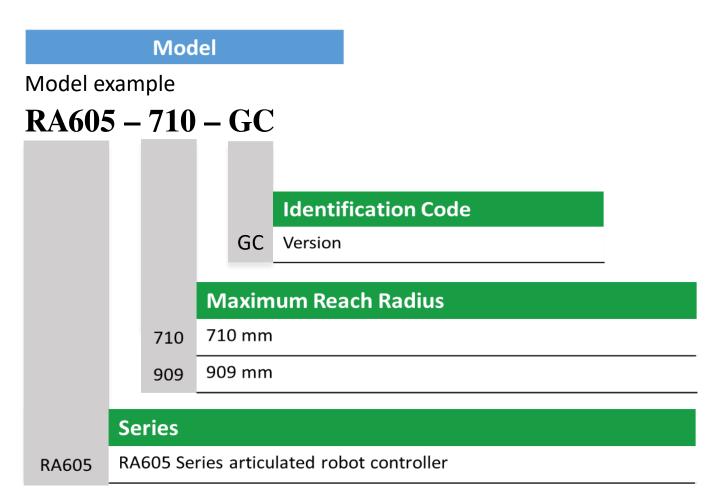


Figure 2-1 Model Diagram



2.2 Labels

The labels on the robot are shown in Table 2-1.

| Labels | s | Name | Description |
|--|---|------------------------------|---|
| | | <u>Collision</u> | Keep safety distance from robot system, and prevent colliding to operator during operation. |
| | | <u>Grounding</u> | Make sure grounding is completed, or it will cause electric shock. |
| | | <u>Read manual</u> | Read manual before operating the robot |
| 4 | 2 | Electric shock | Pay more attention that the robot may have a risk of electric shock. |
| J1 J2 J3 J4 J5 J6 0° 45° -65° 0° 480° 0° | WARNING Dependent to transport position Before moving Robort Transport Position 1 <td< td=""><td><u>Transport</u> position</td><td>Be aware of transport position when transporting robot, please refer to section 1.1 for detailed information.</td></td<> | <u>Transport</u> position | Be aware of transport position when transporting robot, please refer to section 1.1 for detailed information. |





| Read the instruction manual carefully before operate the product. Model: RA610-1476-GC Robot S/N: R18000U-1-08 Controller S/N: R180004-2-09 Manufacture Date: May.2021 Weight: H47 KG Rated Payload: 10 KG Max. Reach: 1476 mm Pneumatic Pressure: 2-7 Bar Robot Type: Industrial Document No: C23UE0 Made in Taiwan No: 7, Jingke Road, Taichung Precision Machinery Park, Taichung 40852, Taiwan | | <u>Specification</u> | Robot specification and serial number. |
|--|------------|----------------------|---|
| | | <u>Air In/Out</u> | The connection port of air tube for air input/output. |
| | GREASE IN | <u>Grease in</u> | The hole for grease in. |
| N | GREASE OUT | | The hole for grease out. |
| CN2 | | <u>CN2</u> | CN2 power & signal cable |
| R-I/0 | | <u>R-1/O</u> | End effector I/O input and output connector |



2.3 Robot Specifications

The robot specifications are shown in Table 2-2.

| ltem | | RA605-GC | |
|------------------------------------|----|--|---------|
| Maximum Reach Radius(mm) | | 710 | 909 |
| Degrees of Freedom | | 6 | |
| Installation [Note 1] | | Floor、slope、wall mounting、ceiling mounting | |
| Nominal Load Capacity(kg) | | 5 [Note 2] | |
| Maximum Load Capacity(kg) | | 7 | |
| Cycle time(sec) [Note 3] | | 0.5 | |
| Position Repeatability(mm) | | ±0.02 | ±0.03 |
| Motion Range | J1 | ±165° | |
| | J2 | +85°~ -125° | |
| | J3 | +185°~ -55° | |
| | J4 | ±190° | |
| | J5 | ±115° | |
| | J6 | ±360° | |
| Maximum Speed | J1 | 360°/ s | 250°/ s |
| | J2 | 288°/ s | 200°/ s |
| | J3 | 420°/ s | 300°/ s |
| | J4 | 444°/ s | 444°/ s |
| | J5 | 450°/ s | 450°/ s |
| | J6 | 720°/ s | 720°/ s |
| Allowable Load Moment at Wrist | J4 | 8.40 N-m | |
| | J5 | 8.40 N-m | |
| | J6 | 5.56 N-m | |
| Allowable Load Inertia at Wrist | J4 | 0.36 kg-m ² | |
| | J5 | 0.36 kg-m ² | |
| | J6 | 0.13 kg-m ² | |
| Manipulator Weight (kg) | | 40 | 45 |
| Integrated signal & power supply | | 6 Input / 4 Output | |
| Integrated air supply [Note 4] | | Two channels of air connection | |
| Protection rating | | IP 65 | |
| Noise level [Note 5] | | Less than 75 dB | |



[Note 1]: Compared to mounting on the ground, the performance of the robot may be different when mounting on the wall or ceiling. Please contact HIWIN if there's any demand for this application.

[Note 2]: For details about load capacity, please refer to section 2.5.

[Note 3]: The cycle time is the time that the robot moves forward and backward in the vertical height 25mm and the horizontal distance 300mm with 1 kg load, as shown in Figure 2-2.

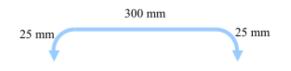


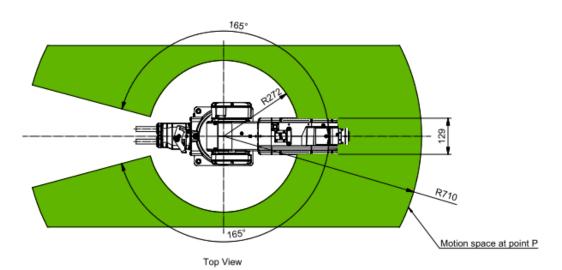
Figure 2-2 Cycle time trajectory

[Note 4]: Apply with M5 thread Ø4 air caliber connector.

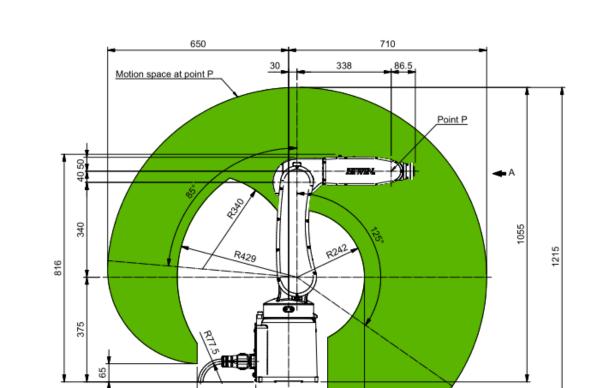
[Note 5]: The noise level is measured at maximum speed and maximum load according to ISO11201.



2.4 Outer Dimensions and Motion Range



The motion range is shown in Figure 2-3(a)~(b).



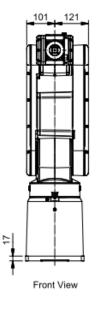
118

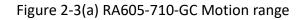
Side View

328

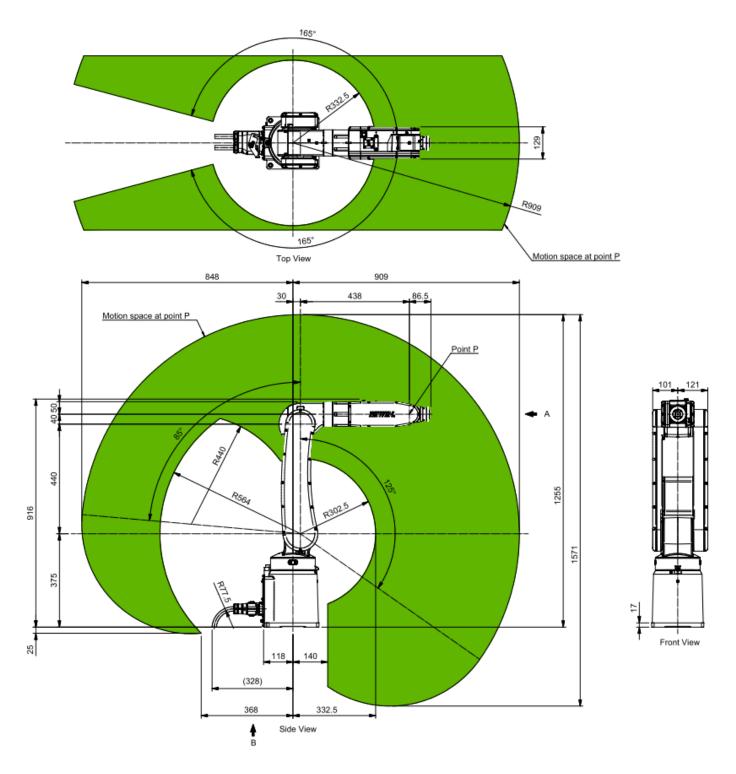
≜ B 140

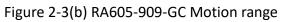
272







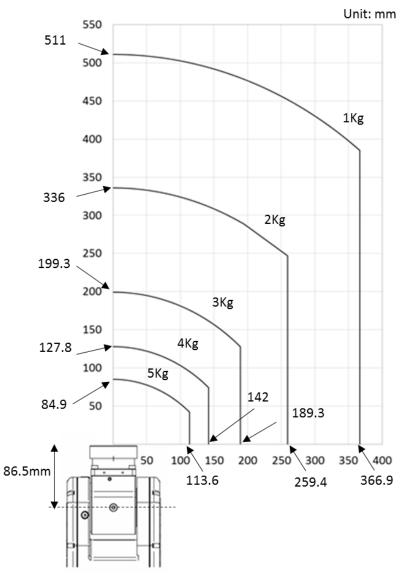


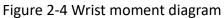




2.5 Wrist Moment Diagram

The load capacity of the robot is not only limited by the weight of the load, but also limited by the center of gravity of the load. Figure 2-4 shows allowable center of gravity of the load when the robot is loaded 1~5kg.







2.6 Mechanical Stopper

Mechanical stoppers are installed at J1-axis to J3-axis to limit the motion range to a minimum value. Please refer to Table 2-3 and Figure 2-5 to Figure 2-9.

| Illustration | Axis applied | Motion range limited |
|--------------|--------------|----------------------|
| | J1 | -170°∼+170° |
| 0 | J2 | -126° |
| 0 | J2 | 86° |
| 0 | J3 | -56° |
| | J3 | 186° |

Table 2-3 Description of mechanical stoppers



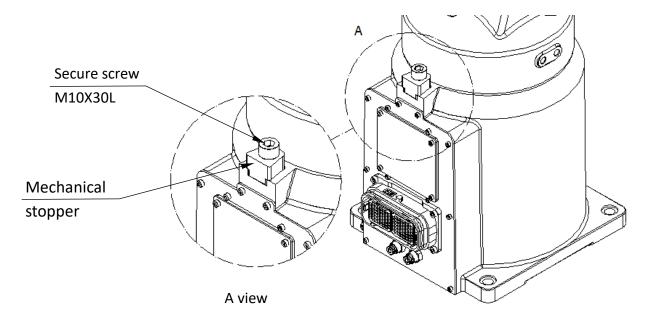


Figure 2-5 J1-axis positive/negative direction limit

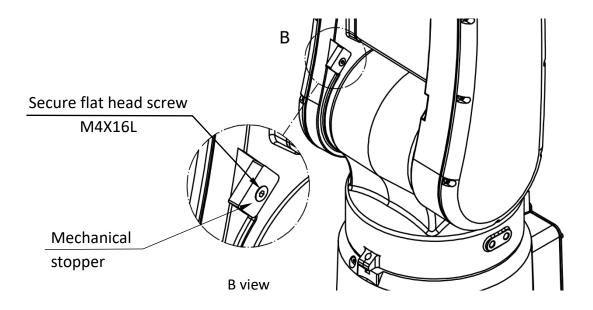


Figure 2-6 J2-axis negative direction limit



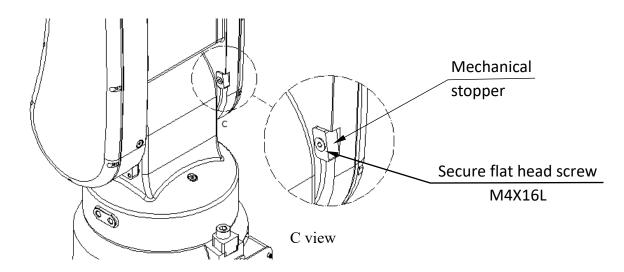


Figure 2-7 J2-axis positive direction limit

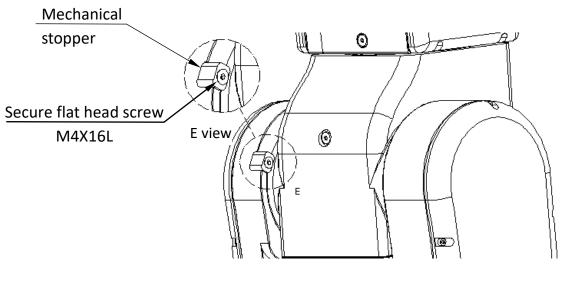


Figure 2-8 J3-axis negative direction limit

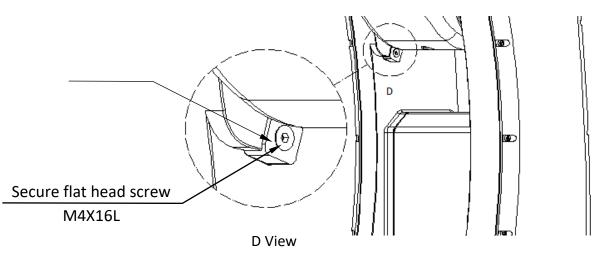


Figure 2-9 J3-axis positive direction limit



3. Equipment Mounting Interface

3.1 Mounting Surface for End Effector

The mounting surface for end effector on the wrist end is shown in Figure 3-1.

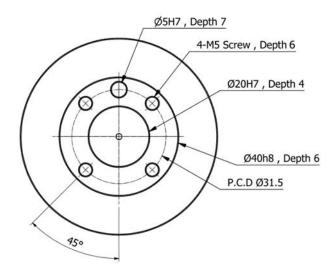


Figure 3-1 End effector Interface

3.2 External device installation interface

The installation interface of other external devices of the robot arm can be used with binding wires and sheet metal.

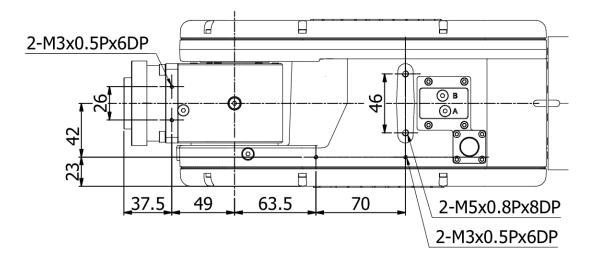


Figure 3-2 Robot arm J5 top view



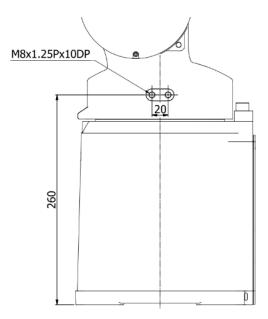


Figure 3-3 Robot base side view

3.3 Pneumatic Interface

The pneumatic holes (AIR IN & AIR OUT) are installed on the rear of J1 as shown in Figure 3-4, and the outer diameter of the air tube in the robot is ϕ 4mm. The secure holes for the nozzle are M5×0.8P.

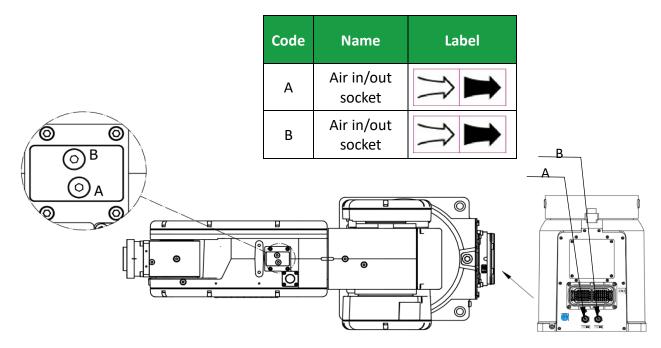
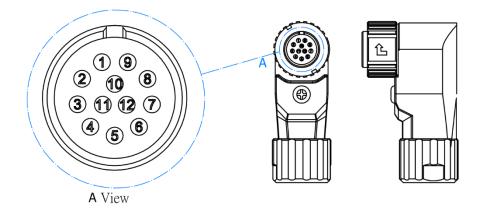


Figure 3-4 R3A605-GC Pneumatic interface



3.4 R-I/O Interface

R-I/O interface for end effector on J5 and the pin assignment of I/O connector are shown in Figure 3-5. Figure 3-6 to Figure 3-9 show the wiring diagram of I/O interface. Figure 3-10 show the two-wire proximity switches connecting method for customers.



| | | | | 1 | | 24V | | 9 | | 0V | | | | _ |
|---|---|------|---|---------------|---|------|---|---------------|---|------|---|-------|---|-------|
| | | 2 | | RI [4] | | 10 | | RI [5] | | 8 | | RI[6] | | |
| 3 | F | RO[1 |] | 11 | F | RO[2 |] | 12 | F | RO[3 |] | 7 | ŀ | RO[4] |
| | | 4 | | RI [1] | | 5 | | RI[2] | | 6 | | RI[3] | | |

| | | | | 1 | Orar | nge(F | Red-) | 9 | Pin | k(Bh | ıe-) | | | |
|---|-----|-------|-------|-------|---------|-------|-------|-------|-------|-------|-------|-------|-------|-----------|
| | | 2 | Oran | ge (E | Blue -) | 10 | Pin | k(Bh | ıe-) | 8 | Yello | ow(B | lue-) | |
| 3 | Gra | y (Re | ed -) | 11 | Orang | e (Re | ed) | 12 | Orang | e (Bl | ue) | 7 | Yello | ow (Red-) |
| | | 4 | Gra | y(Bh | .ue -) | 5 | Wh | ite(R | ed-) | 6 | Whi | te(Bl | lue-) | |

Figure 3-5 Pin assignment of the I/O connector (Power output: 24V/1A)



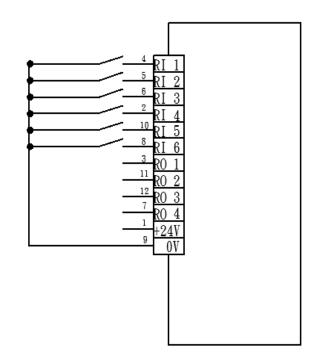


Figure 3-6 Wiring diagram of input (Standard: Sinking type)

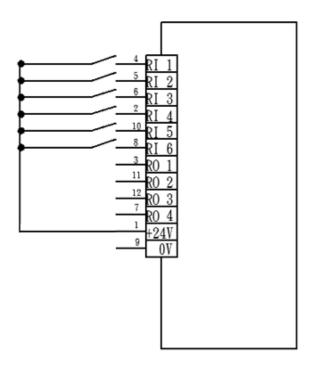


Figure 3-7 Wiring diagram of input (Optional: Sourcing type)



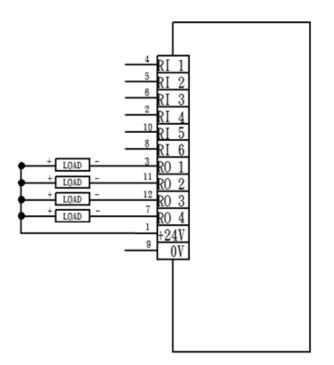


Figure 3-8 Wiring diagram of output (Standard: Sinking type)

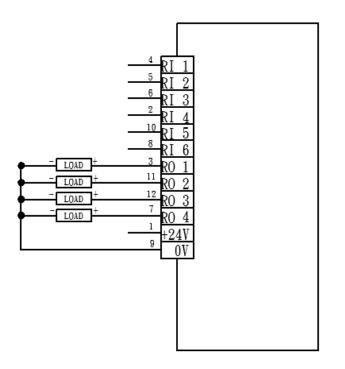


Figure 3-9 Wiring diagram of output (Optional: Sourcing type)

Two-wire proximity switch



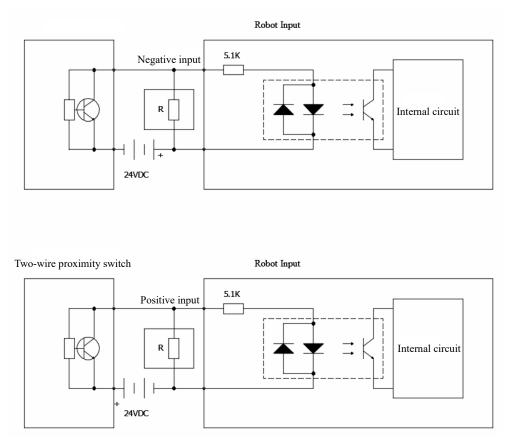


Figure 3-10 Two-wire proximity switch wiring diagram

| | 1 | |
|------------------|---|--|
| | * | Pin 1 and pin 9 are used for 24V/1A signal, not for power |
| | | input of end effector. |
| | * | The maximum output current at each pin is 100mA. |
| ! CAUTION | * | Two-wire proximity switch may cause Robot Input error |
| | | action occur due to residual voltage. Therefore, if you want |
| | | to use two-wire proximity switch, you should connect it |
| | | according to Figure 3-8 and select the matching R value. |



4. Calibration

4.1 Zero Position Setting

The calibration tools (HIWIN part no.: RA605Z541-2) for setting Zero-position are shown in Figure 4-1. The robot is adjusted to the minimum speed during the calibration, and aligns the pinhole with the calibration tool to set up the Zero-position. The procedure of resetting Zero-position with the calibration tools is shown in Figure 4-2 to Figure 4-7 below.

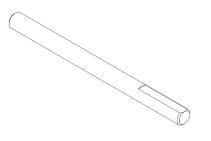




Figure 4-1(a)

Calibration tool (A)

Calibration tool (B)

4-1(b)

Figure 4-1 Calibration tool set

- J1-axis Zero-position setting (please refer to the Figure 4-2)
 - Step1. Operate J1 at low speed to align the pinhole of J2 with the pinhole of J1.
 - Step2. Insert the calibration tool(A) to the pinhole to calibrate Zero-position.
 - Step3. Finish calibration and remove the calibration tool.
 - Step4. Clear encoder by HRSS .
 - Step5. Zero-position setting of J1-axis is completed.

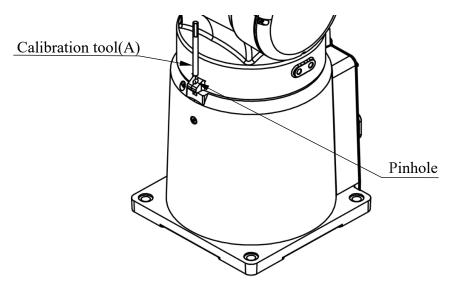


Figure 4-2 Illustration of J1-axis Zero-position setting



- J2-axis Zero-position setting (please refer to the Figure 4-3)
 - Step1. Operate J2 at low speed to align the pinhole of J3 with the pinhole of J2.
 - Step2. Insert the calibration tool (A) to the pinhole to calibrate Zero-position.
 - Step3. Finish calibration and remove the calibration tool.
 - Step4. Clear encoder by HRSS.
 - Step5. Zero-position setting of J2-axis is completed.

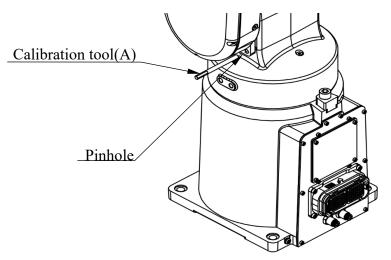


Figure 4-3 Illustration of J2-axis Zero-position setting

- J3-axis Zero-position setting (please refer to the Figure 4-4)
 - Step1. Operate J3 at low speed to align the pinhole of J4 with the pinhole of J3.
 - Step2. Insert the calibration tool (A) to the pinhole to calibrate Zero-position.
 - Step3. Finish calibration and remove the calibration tool.
 - Step4. Clear encoder by HRSS.
 - Step5. Zero-position setting of J3-axis is completed.

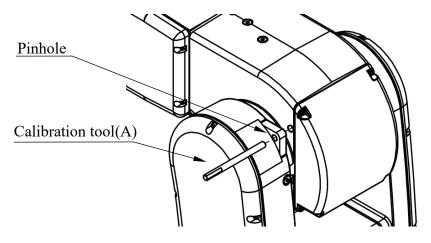


Figure 4-4 Illustration of J3-axis Zero-position setting



- J4-axis Zero-position setting (please refer to the Figure 4-5)
 - Step1. Operate J4 at low speed to align the keyway of J5 with the keyway of J4.
 - Step2. Insert the calibration tool (B) to the keyway to calibrate Zero-position. (hexagon socket cap screw can be screwed first in calibration tool)
 - Step3. Finish the calibration and remove the calibration tool using hexagon socket cap screw.
 - Step4. Clear encoder by HRSS.
 - Step5. Zero-position setting of J4-axis is completed.

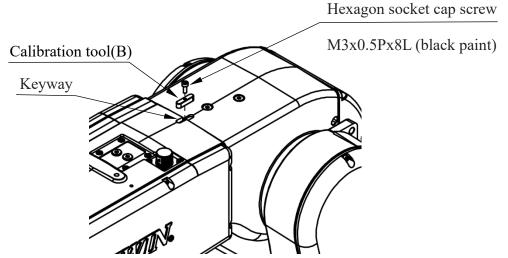


Figure 4-5 Illustration of J4-axis Zero-position setting

- RA605-909-GC J4-axis Zero-position setting (please refer to the Figure 4-6)
 - Step1. Operate J4 at low speed to align the keyway of J5 with the keyway of J4.
 - Step2. Insert the calibration tool (B) to the keyway to calibrate Zero-position. (hexagon socket cap screw can be screwed first in calibration tool)
 - Step3. Finish the calibration and remove the calibration tool using hexagon socket cap screw.
 - Step4. Clear encoder by HRSS.
 - Step5. Zero-position setting of J4-axis is completed.

Hexagon socket cap screw

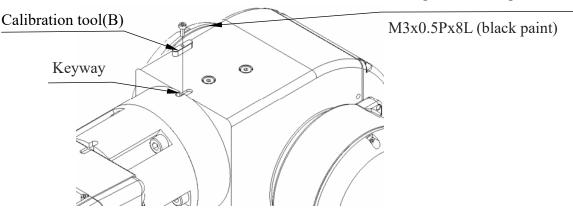


Figure 4-6 Illustration of RA605-909-GC J4-axis Zero-position



- J5-axis Zero-position setting (please refer to the Figure 4-7)
 - Step1. Operate J5 at low speed to align the pinhole of J6 with the pinhole of J5.
 - Step2. Insert the calibration tool (A) to the keyway to calibrate Zero-position.
 - Step3. Finish the calibration and remove the calibration tool.
 - Step4. Clear encoder by HRSS.
 - Step5. Zero-position setting of J5-axis is completed.

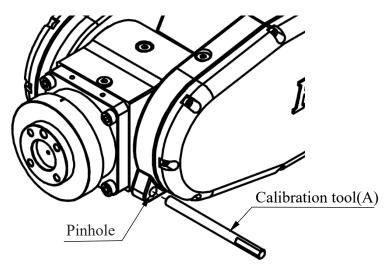


Figure 4-7 Illustration of J5-axis Zero-position setting

- J6-axis Zero-position setting (please refer to the Figure 4-8)
 - Step1. Operate J6 at low speed to align the calibration mark of end effector with the mark of J6.
 - Step2. Clear encoder by HRSS.
 - Step3. Zero-position setting of J6-axis is completed.

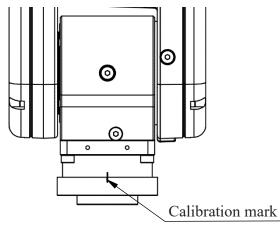


Figure 4-8 Illustration of J6 -axis Zero-position setting



- Clear encoder by HRSS (Please refer to HRSS software manual)
 - Step1. Select the "JOINT" as the coordinate system.
 - Step2. Move the robot to the Zero-position.
 - Step3. Click Main Menu>>Start-up>>Master>> Zero Position.
 - Step4. Double click the axis to clear encoder. (As shown in Figure 4-9)

| File | Calibrate | Zero Position | Click to restore the rob | |
|---------------|---------------------|---------------|--------------------------|--|
| Configuration | Master | Calibration | must be close to the ca | |
| Display | Robot data | | model's respective use | oint is described in each r manual. |
| Diagnosis | Network Config | | Axis 1 | 0 - |
| Start-up | RS-232 | | Axis 2 Axis 3 | |
| Track | System Setting | | Axis 4 | |
| Help | Electric Gripper | | Axis 5 Axis 6 | |
| Shutdown | →(Next) | | | |
| | | | |] |
| | | | | |

Figure 4-9 Clear encoder by HRSS



5. Manual Brake Release Device (optional)

5.1 Safety Precautions

Description:

In accordance with ISO 10218-1, the manual brake release device is a user-safety equipment for changing robot posture temporarily.

| | n | |
|-------------|---|---|
| | * | This device can only be executed by trained staff. |
| | * | When the manual brake release device is executed, |
| | | J4-axis must be securely fixed by a crane to prevent |
| | | an unexpected drop of J2-axis and J3-axis. Please |
| | | carefully read the section "Manual Brake Release |
| | | Device" in this manual before using the brake release |
| <u>_!</u> _ | | device. |
| WARNING | * | Please firmly secure the robot on smooth floor to |
| | | prevent robot tilting, falling or an unexpected |
| | | movement. |
| | * | Please use the socket with grounding and ensure the |
| | | grounding is firmly connected. If not, there would be |
| | | a risk of electric shock. |

5.2 Confirmation before Using

Please confirm the following items before using manual brake release device (detail specifications referring to the Table 5-1; corresponding connector referring to the Figure 5-1).

- (1) Please make sure CN2 connector is matched with the corresponding robot by checking the model name label affixed on the cover of this device.
- (2) Please do not use this device if the manual brake release device and the cable have damages on the appearance.
- (3) Please make sure the voltage of power source and the voltage requirement of the device are the same before connecting this device to the power. Connecting wrong voltage to the device will result in device damage.



| Item wi | th HIWIN Manual Brake Release Device | Specification |
|-----------|--------------------------------------|----------------------------|
| | | RA605-710-GC |
| Model na | ame | RA605-909-GC |
| | Input voltage (VAC) | Single phase, 100-240 |
| Power | Output voltage (VDC) | 24 |
| Power | Voltage frequency (Hz) | 50/60 |
| | Max. rated current (A) | 2 |
| Dimensio | on | 140x170x95 mm ³ |
| Weight | | 1.74kg |
| Protectio | on rating | IP20 |
| Ambient | temperature (°C) | 0-45 |
| Relative | humidity (%RH) | 50~75 (non-condensing) |

Table 5-1 Specifications of HIWIN manual brake release device

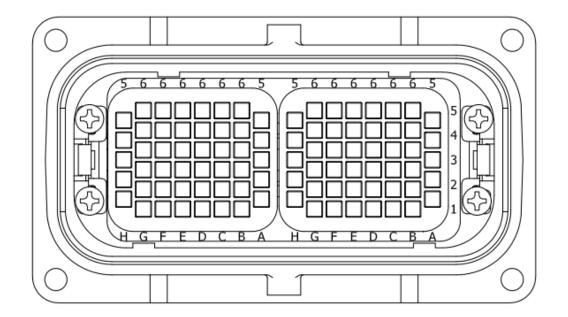


Figure 5-1 Corresponding connector for manual brake release device



5.3 Operation

Name descriptions of the manual brake release device and their functions (refer to Figure 5-2 & Table 5-2 the definition of functional keys with manual brake release device).

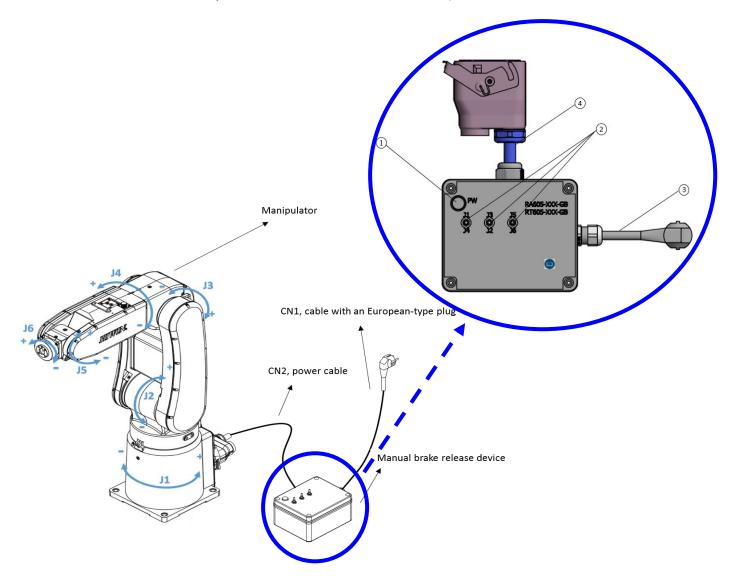


Figure 5-2 the manual brake release device



| No. | Item | Description |
|-----|------------------------|---|
| 1 | Green-light indicator | Power ON/OFF. |
| 2 | | Toggle upward and downward of any switch and |
| | Three-stage revertible | the robot will release the brake of corresponding |
| | toggle switch (Note 1) | axis. When the switch is released to the middle |
| | | position, the brake will be executed. |
| 3 | CN1, cable with an | 1.5M |
| | European-type plug | 1.5101 |
| 4 | CN2, Power cable | 1M |

Table 5-2 the definition of functional keys with manual brake release device

*Note 1:

Normally, the three-stage revertible toggle switch should stay in the middle position, which means the brake is executed. When the switch is toggled upward and downward of any switch and the robot will release the brake of corresponding axis.

| | * | Please note that the axes of the switch are not in sequence due to the gravity comes from releasing |
|---------|---|--|
| | | particular axis' brake. Thus, J2 and J3 are bound together to prevent the unexpected falling when |
| WARNING | | releasing there axis' brake simultaneously. Please confirm the axes before operation to prevent a risk of unexpected motion. |

Please follow the steps below to release the brake:

- (1) The J4-axis of manipulator must be securely fixed by a crane to prevent an unexpected drop of J2-axis and J3-axis.
- (2) Remove the original CN2 cable connected to controller on robot base, and change to the power cable (CN2) of manual brake release device to robot base.
- (3) Connect the cable with an European-type plug (CN1) to power source.
- (4) Based on the axis whose brake needs to be released, toggle the switch to the corresponding axis and the brake would be released immediately.



6. Maintenance and Inspection

This chapter presents the maintenance and periodical inspection procedures to maintain the robot for a reasonable service life. It includes the cover removal and installation as well as internal maintenance, inspection and replacement of the timing belt, the procedures for replacing the battery, and other notes.

RA605-GC robot series are designed with lifetime lubrication technology, and never needs a change of lubricant in the reducer unit. The robust and sealed design makes sure the stability of lubrication inside the robot.

The operating time of the robot is defined as 3840 hours per year. When using the robot beyond this operating time, correct the maintenance frequencies shown in this chapter by calculation in proportion to the difference between the actual operating time and 3840 hours per year.

6.1 Maintenance Items

The maintenance and check can be classified as the daily and periodical inspection procedures, where the items in the daily inspection include the power on/off and operation, representing those before the power on/off and programming respectively, as shown in Table 6-1. The items in the periodical inspection includes those for the routine check A,B,C,D and E. The check contents are shown in Table 6-2. The timetable can be worked out according to periodical inspection, as shown in Table 6-3. By well doing the inspection items, it can ensure the product safety in the reasonable product life time and avoid risk of product malfunction.

| | Inspection item | Remedies |
|---|--|---|
| | Before turni | ng power ON |
| 1 | Are any of the robot installation screws, cover installation screws and end effector installation screws loose? | Securely tighten the screws. |
| 2 | Are all the cables securely connected? Such as the power and signal cable, grounding cable, the cable for teach pendant and the cable connected the robot and other equipment. | Securely connect. If loosen, please ensure the cables are securely connected. |

Table 6-1 Daily Inspection Items



| 3 | Is the pneumatic system normal? Are there any air leak, drain clogging or hose damage? Is the air source normal? | Drain the drainage system and replace the leaking component. If needed, please contact HIWIN directly. |
|---|--|--|
| 4 | Depending on the motion condition and surrounding environment, there might be a few grease permeating through the outside of the rotatory oil seal of each axis. Please check if there is any grease permeating around the bearings of each axis? | Wipe it off when there is any grease permeating around the bearings of each axis. |
| | After turnin | g power ON |
| 1 | Is there any unusual motion or unusual noise when power is ON? | The robot installation screws might not be securely tightened to the installation surface. Securely tighten the screws to appropriate torque. If the roughness of the installation surface is uneven, modify the installation surface to the reasonable surface roughness. The base might not be sufficiently rigid. Please replace the base to make it more rigid. There might be foreign material between the robot and the installation surface. Please remove it. Some operating positions might exceed the mechanism limit. Please reduce the load, speed or acceleration. The timing belt might loosen or not be in correct position. Please replace or adjust the timing belt. (Refer to section 6.2.2) If the above situations has been excluded, it is likely that the rolling surface of bearing or the gear tooth surface of reducer has been damaged. Please contact HIWIN directly. |
| 2 | The repeatability is not within the tolerance. | The Zero-position of the robot might be rewritten. Please set the Zero-position. (Refer to section 4.1) ° The Zero-position data will be lost if the |



| 4.1) ° 3. The Robot J1 base retaining bolt might loosen. Please apply LOCTITE and tighten it to the appropriate torque. |
|--|
|--|

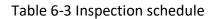
The project and time of periodic inspection refer to Table 6-2 and 6-3.

| | Inspection item | Remedies | | | | |
|---|--|--|--|--|--|--|
| | Inspection item A (1 month / 320 hours) | | | | | |
| 1 | Check if there are any cracks and flows on the robot. | Clean and check each part of the robot. | | | | |
| 2 | Are any of the screws on the manipulator loose? | Securely tighten the screws. | | | | |
| 3 | Are any of the connector fixing screws or terminal block terminal screws loosen? | Securely tighten the screws. | | | | |
| | Inspection item B (3 | months / 960 hours) | | | | |
| 1 | Check the ventilation system of the controller. | If it is dusty, turn off the power and clean the ventilation system of the controller | | | | |
| | Inspection item C (6 months / 1920 hours) | | | | | |
| 1 | Check whether the friction at the timing belt teeth is severe. | If the teeth are missing or the friction at the timing belt is severe, replace it. Refer to section 6.2.2. | | | | |
| 2 | Check whether the tension of timing belts at each axis is abnormal or deviated. | Refer to 6.2.2 Adjust the tension to the standard value, and avoid over tightness or looseness. | | | | |
| | Inspection item D (1 | year / 3840 hours) | | | | |
| 1 | Replace the backup battery in the manipulator. | Replace the backup battery. Refer to section 6.2.1 | | | | |
| 2 | Check the screws of mechanical stoppers are tighten. | Refer to 2.5 Screw types of mechanical stoppers of J1~J3. | | | | |
| | Inspection item E (3years/11520hours) | | | | | |
| 1 | Change the cables inside the robot. | Please contact HIWIN directly. | | | | |
| 2 | Change the timing belt of J1 and J4. | Please contact HIWIN directly. | | | | |





It is normal that the belt produces debris during operation, but if it happens right after cleaning the belt, it is recommended to replace the belt.



| 0 month | | | | | | | | | |
|----------|-------------------|------------|--------|------------|--------|------------|--------|-------------------|--|
| | Inspection item A | | | | | | | | |
| | Inspection item A | | | | | | | | |
| 3 month | Inspection item A | Inspection | item B | | | | | | |
| | Inspection item A | | | | | | | | |
| | Inspection item A | | | | | | | | |
| 6 month | Inspection item A | Inspection | item B | Inspection | item C | | | | |
| | Inspection item A | | | | | | | | |
| | Inspection item A | | | | | | | | |
| 9 month | Inspection item A | Inspection | item B | | | | | | |
| | Inspection item A | | | | | | | | |
| | Inspection item A | | | | | | | | |
| 12 month | Inspection item A | Inspection | item B | Inspection | item C | Inspection | item D | | |
| | | | | | | | | | |
| 36 month | Inspection item A | Inspection | item B | Inspection | item C | Inspection | item D | Inspection item E | |
| | Operating time | 8 | | | | | | Inspection item | |
| 7 | ל | | | | | | | | |

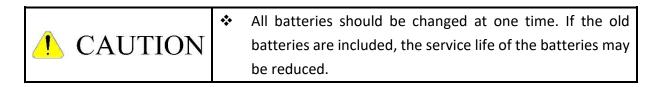


6.2 Maintenance Methods

6.2.1 Backup Batteries Replacement

The absolute encoder of the motor is used to record the position of the robot. When the controller power is turned off, the position data of each -axis is preserved by the backup batteries. The batteries are installed when the robot is delivered from the factory. If the batteries are in use, the annual change of batteries is needed. The service life of the batteries depends on the operating conditions of the robot. In order to avoid the loss of position data, the batteries need to be changed by the user periodically. The procedure for replacing the batteries of the robot is shown in Figure 6-1 and described as below.

- Step1. Press the emergency stop button to prohibit the movement of the robot motion.
- Step2. Ensure the robot and controller are connected with the cables. Keep the power ON.
- Step3. Please remove the battery cover. The screws for battery cover are hexagon head screws (M3×0.5P×6L) and the four batteries are 3.6V.
- Step4. Replace the battery one by one. If all batteries are removed at the same time, the position data will be lost. If so, please reset the robot to the Zero-position. All batteries should be changed one at a time.
- Step5. After replacing the battery, ensure to install the battery cover to prevent the robot being damaged by dust and grease.





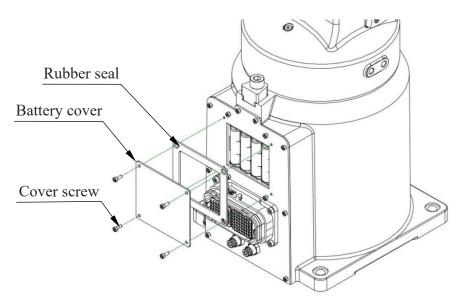


Figure 6-1 The backup batteries replacement

6.2.2 Timing Belt Replacement

The timing belt is used in the robot for the driver system of the J2, J3, J5 and J6 -axis. Although the belt tension has been adjusted before the robot delivery, the timing belt will wear depending on the working conditions. The belt tension might be lower than the standard after operating for a long time. The timing belt should be periodically checked, maintained and replaced.

• Timing Belt replacement period

When the maintenance time is up to (six month), check the belt tension. If the tension is insufficient, adjust the belt tension. If the belt is excessively worn (wearing about half of the tooth width), the belt tooth is cracked or the belt is broken, replace the belt, but you are required to re-origin the points to correct the points.

| ! CAUTION | * | When replacing the belt, the robot system origin may |
|------------------|---|---|
| | | deviate. In this case, the position data must be rechecked if |
| | | the origin is offset. Please refer to section 4.1 for Zero- |
| | | position setting. |

Belt Tension

It is very important to keep proper belt tension. The belt tooth jumping will happen if the belt tension is too loose. If the belt tension is too tight, it will cause damage to the motor or bearing. Measuring methods of the belt by using fingers or tools are shown in Figure 6-2. When the belt is adjusted to the certain extent, you can feel the tension by your finger. If belt is too loose, it will vibrate; on the contrary, you will hear the



sharp sound if it is too tight, and the belt is excessively worn. The sonic tension meter is used to measure the belt tension. The specifications and standard tension of belt are shown in Table 6-4.

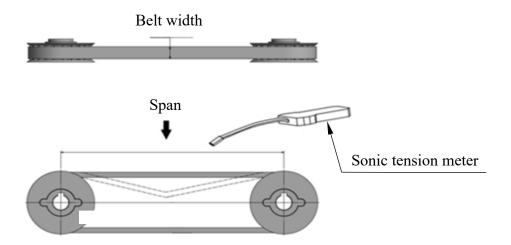


Figure 6-2 Belt tension measurement

| | * | It is normal that the belt produces debris during operation, but if it happens right after cleaning the belt, it is | | |
|---------|-----|--|--|--|
| | .•. | recommended to replace the belt. | | |
| | * | After the robot is operated about 300 hours, the rubbers | | |
| CAUTION | | worn by the belt will be accumulated on the cover. Those | | |
| | | rubber come out due to the friction, not the broken. Please | | |
| | | use cleaning rag to wipe them out and let the robot | | |
| | | continue the work. If the rubbers appear soon after | | |
| | | cleaning it, please wipe them again and replace the belt. | | |

Table 6-4 The belt specifications

| Axis | Applicable model | Belt type | Width(mm) | Span(mm) | Tension(N) |
|------|------------------|-----------|-----------|----------|------------|
| 12 | RA605-710-GC | 365-5GT-9 | 0 | 117.5 | 55~61 |
| J2 | RA605-909-GC | 375-5GT-9 | 9 | 116.9 | |
| 13 | RA605-710-GC | 440-5GT-9 | 9 | 154.9 | 55~6155~61 |
| 12 | RA605-909-GC | 635-5GT-9 | 9 | 254.9 | 10 2210 22 |
| J5 | All models | 285-3GT-6 | 6 | 100.3 | 29~32 |
| J6 | All models | 285-3GT-6 | 6 | 100.3 | 29~32 |

CAUTION *

If the belt of J1 and J4 need to be replaced, please contact HIWIN.



• Cover removal

Before replacing the belt, remove the cover of J3 and J5 as shown in Figure 6-3.

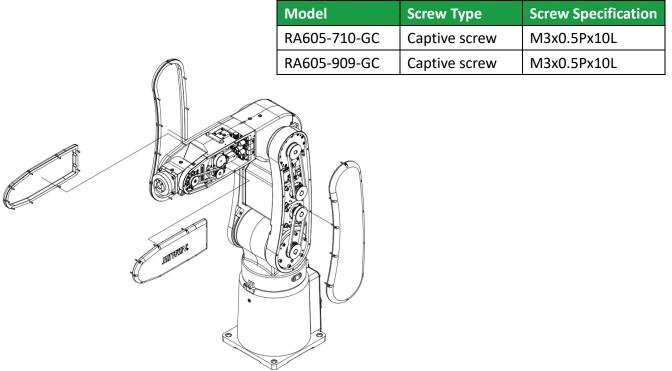
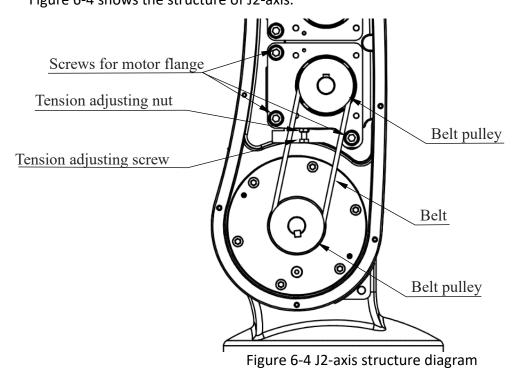


Figure 6-3 Cover removal diagram

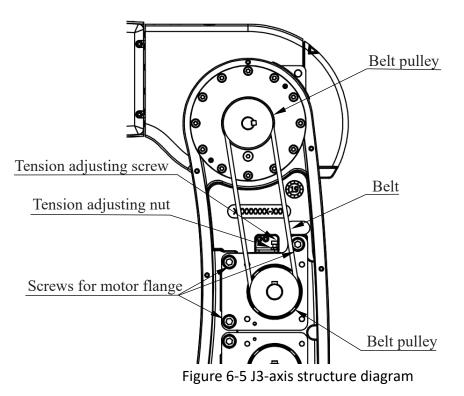
• Inspection, maintenance and replacement of timing belt in J2-axis. Figure 6-4 shows the structure of J2-axis.





- Inspect J2-axis timing belt
 - Step1. Ensure the power of controller is switched off.
 - Step2. Remove the cover of J3.
 - Step3. Check whether the timing belt is normal.
 - Step4. If the timing belt is abnormal, refer to the following paragraph to replace the timing belt.
 - Step5. If the belt tension is lower than the standard, refer to the following paragraph to adjust the belt tension.
- Adjust J2-axis timing belt
 - Step1. Loose the two fixing screws on motor flange, so that the motor can be move. No need to remove the screws.
 - Step2. Refer to Table 6-4, loosen or tighten the adjusting screw to adjust the tension of the belt.
 - Step3. Tighten the two fixing screws on motor flange. (Screw pounds 7.2N-m)
- Replace J2-axis timing belt
 - Step1. Remove the two fixing screws on motor plate.
 - Step2. Loose the adjusting screw to replace the timing belt.
 - Step3. After replacing the belt, refer to the paragraph "Adjust J2-axis timing belt" above to adjust the tension of the belt.
- Inspection, maintenance and replacement of timing belt in J3-axis.

Figure 6-5 shows the structure of J3-axis.





- Inspect J3-axis timing belt
 - Step1. Ensure the power of controller is switched off.
 - Step2. Remove the cover of J3.
 - Step3. Check whether the timing belt is normal.
 - Step4. If the timing belt is abnormal, refer to the following paragraph to replace the timing belt.
 - Step5. If the belt tension is lower than the standard, refer to the following paragraph to adjust the belt tension.
- Adjust J3-axis timing belt
 - Step1. Loose the two fixing screws on motor flange, so that the motor can be move. No need to remove the screws.
 - Step2. Refer to Table 6-4, loosen or tighten the adjusting screw to adjust the tension of the belt.
 - Step3. Tighten the two fixing screws on motor flange. (Screw pounds 7.2N-m)
- Replace J3-axis timing belt
 - Step1. Remove the two fixing screws on motor plate.
 - Step2. Loose the adjusting screw to replace the timing belt.
 - Step3. After replacing the belt, refer to the paragraph "Adjust J3-axis timing belt" above to adjust the tension of the belt.
- Inspection, maintenance and replacement of timing belt in J5-axis.

Figure 6-6 shows the structure of J5-axis.

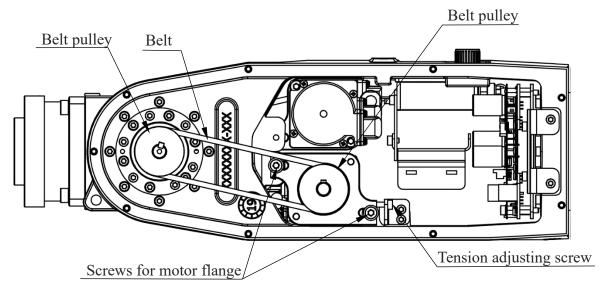


Figure 6-6 J5-axis structure diagram



- Inspect J5-axis timing belt
 - Step1. Ensure the power of controller is switched off.
 - Step2. Remove the cover of J5.
 - Step3. Check whether the timing belt is normal.
 - Step4. If the timing belt is abnormal, refer to the following paragraph to replace the timing belt.
 - Step5. If the belt tension is lower than the standard, refer to the following paragraph to adjust the belt tension.
- Adjust J5-axis timing belt
 - Step1. Loose the two fixing screws on motor flange, so that the motor can be move. No need to remove the screws.
 - Step2. Refer to Table 6-4, loosen or tighten the adjusting screw to adjust the tension of the belt.
 - Step3. Tighten the two fixing screws on motor flange. (Screw pounds 2.2N-m)
- Replace J5-axis timing belt
 - Step1. Remove the two fixing screws on motor plate.
 - Step2. Loose the adjusting screw to replace the timing belt.
 - Step3. After replacing the belt, refer to the paragraph "Adjust J5-axis timing belt" above to adjust the tension of the belt.
- Inspection, maintenance and replacement of timing belt in J6-axis.

Figure 6-7 shows the structure of J6-axis.

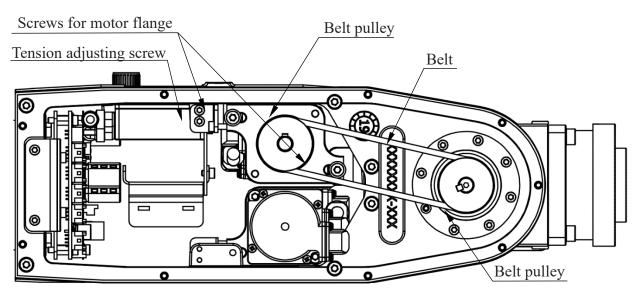


Figure 6-7 J6-axis structure diagram



- Inspect J6-axis timing belt
 - Step1. Ensure the power of controller is switched off.
 - Step2. Remove the cover of J5.
 - Step3. Check whether the timing belt is normal.
 - Step4. If the timing belt is abnormal, refer to the following paragraph to replace the timing belt.
 - Step5. If the belt tension is lower than the standard, refer to the following paragraph to adjust the belt tension.
- Adjust J6-axis timing belt
 - Step1. Loose the two fixing screws on motor flange, so that the motor can be move. No need to remove the screws.
 - Step2. Refer to Table 6-4, loosen or tighten the adjusting screw to adjust the tension of the belt.
 - Step3. Tighten the two fixing screws on motor flange. (Screw pounds 2.2N-m)
- Replace J6-axis timing belt
 - Step1. Remove the two fixing screws on motor plate.
 - Step2. Loose the adjusting screw to replace the timing belt.
 - Step3. After replacing the belt, refer to the paragraph "Adjust J6-axis timing belt" above to adjust the tension of the belt.



7. Safety Certification

RA605-GC have CE marking and it fulfill related Directives and ISO standards (table 7-1).

| CE Compliance | | | | | |
|------------------------------|---|---------------------|--|--|--|
| | 2006/42/EC | | | | |
| | Safety of machinery — General | | | | |
| | principles for design — Risk | EN ISO12100:2010 | | | |
| Machinery Directives(MD) | assessment and risk reduction | | | | |
| | Robots and robotic devices — Safety | | | | |
| | requirements for industrial robots — | EN ISO 10218-1:2011 | | | |
| | Part 1: Robots | | | | |
| | 2014/35/EU | | | | |
| Low Voltage Directives (IVD) | Safety of Machinery - Electrical | | | | |
| Low Voltage Directives (LVD) | equipment of machines - Part 1: | EN 60204-1:2018 | | | |
| | General requirements | | | | |
| | 2014/30/EU | | | | |
| Electromagnetic | Generic standards - Immunity for | | | | |
| Compatibility Directives | industrial environments | EN 61000-6-2 | | | |
| (EMC) | Generic standards. Emission | | | | |
| | standard for industrial environments | EN 61000-6-4 | | | |
| | 2011/65/EU+(EU)/2015/863 | | | | |
| Restriction of Hazardous | Cd(100 ppm ↓) | | | | |
| Substances Directive(RoHS) | Pb,Hg,Cr ⁶⁺ ,PBB,PBDE,DEHP,DBP,BBP,DIBP(1000 ppm ↓) | | | | |

Table 7-1 the corresponding directives and ISO standards of RA605-GC series



8. Robot/Controller Requirements Questionnaire

| Customer | Customer Name: | Addres | s: | | | |
|---------------------------|---|--|---|--|--|--|
| Customer Information | Contact Person: | Phone | No.: | | | |
| Information | Department/Title | : E-mail: | | | | |
| | □ Assembly | | □ Polish & Grinding ^{*Note2} | | | |
| | Electronics | 🗆 Material Handlii | - | | | |
| Application | □ Inspection/Test | | □ Others: | | | |
| | • | sting | | | | |
| | | | | | | |
| | | : | | | | |
| Product | | Weig | | | | |
| Specification | | (mm) x W (mn | | | | |
| | | avity: | | | | |
| Needed | | | Repeatability: +/ (mm) | | | |
| Movement | | ange: (mm) | Cycle Per Minute : (CPM) | | | |
| Installation | Input Power Length of Floor Cable (CN2) | □ 3m(Standard) □ 5m ■ TCP/IP | 05 ≤ RA610) <u>415V /□ 480V /□ 575V</u> (please select) (Option) □ 10m(Option) ■ 8IN/8OUT Function I/O | | | |
| Communication | Standard | Modbus-TCP RS-232C | ■ 24IN/24OUT Digital I/O | | | |
| | Option (1 of 5) | | Digital I/O □ PROFINET □ EthernetIP dule (Encoder, Communication cable, | | | |
| | Expansion | Emergency Stop Switch | 5m) | | | |
| | Module | □ Cable with 37P/ 25P D-type Connector (6m 	10m) | | | | |
| Others | (Option) | □ 37P/ 25P Terminal Board | | | | |
| Others | Special Demand | (If above column couldn't note here) | explain customer demand, please | | | |
| External axis application | □Linear walking axis (cable drag chain) □ Rotate external shaft | | | | | |
| Protection Rating | □ IP32 □ IP54 □ Others | | | | | |



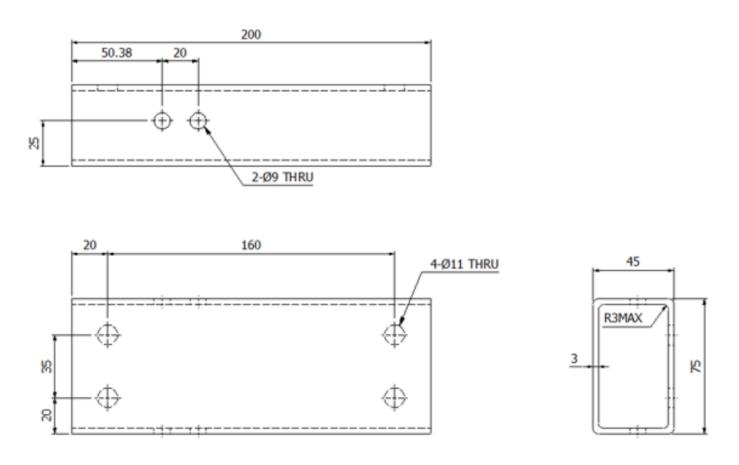
| | Sales Contact | Name: Date: | | | |
|---------------|---------------|-------------|-----------|--|--|
| Model | Recommend | □ RT605GB | □ RA610GC | | |
| Specification | Model | □ RA605GC | | | |
| (by HIWIN or | Remark: | | | | |
| distributor) | | | | | |
| | | | | | |

*Note 1 For palletizing application, need to provide pallet type and space planning

*Note 2 For polish & grinding application, need to provide work part or 3D model and photo of comparison(before and after).

9. Appendix

Suspension plate (refer to section 1.1)



Articulated Robot - RA605-GC (Original Instruction) User Manual

Publication Date : February 2022

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