

**Kawasaki Robot Controller  
F Series Controller**

**Installation and  
Connection Manual**

**Robot**

Kawasaki Heavy Industries, Ltd.

## Preface

This manual describes the installation and connection of the controller.

This manual covers the installation and wiring of the controllers and connection with external power. Please refer to "Operation Manual" and "External I/O Manual" for the operation of the controller.

Read and understand the contents of this and "Safety Manual" thoroughly and strictly observe all rules for safety before proceeding with any operation.

This manual describes only the installation and connection of the controller. For the robot arms, please refer to the separate manuals for them.

This manual also describes devices equipped as an option. However, all the controllers might not include the devices explained here.

### [NOTE]

This manual is applicable to the following F series controller model only.

F60

There are two types of F60 controllers: A-type (model example: F60\*-A\*\*\*) and B-type (model example: F60\*-B\*\*\*).

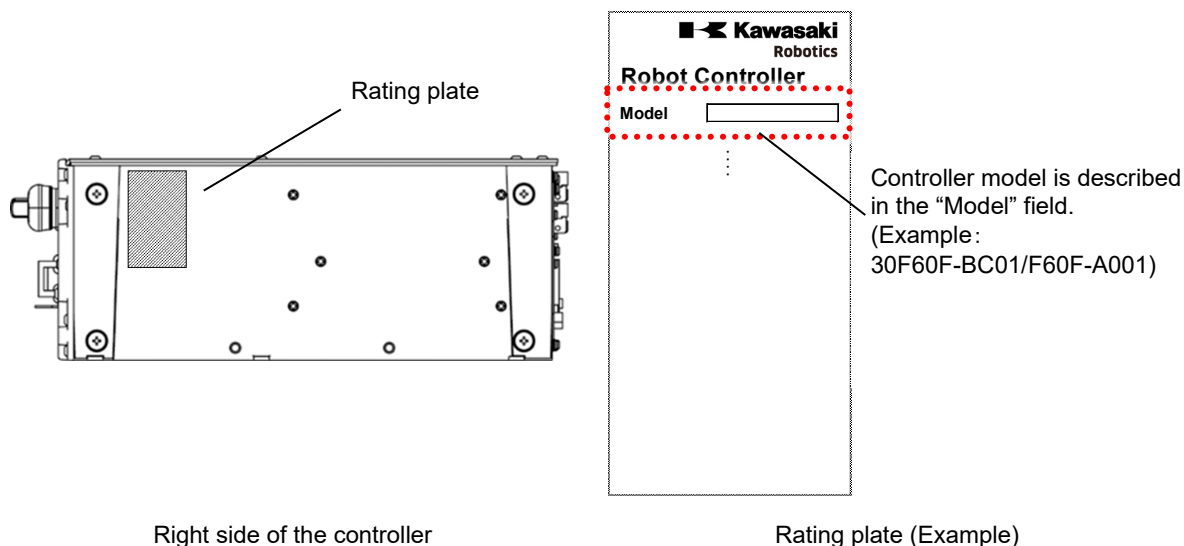
A-type	Model compatible with "Cubic-S" of safety function (Incompatible with CoreCubic-S)
B-type	Model compatible with "CoreCubic-S" of safety function (Incompatible with Cubic-S)

(For details of Cubic-S and CoreCubic-S, refer to the separate "Cubic-S Instruction Manual" or "CoreCubic-S Instruction Manual.")

Although the appearance differs slightly depending on the type, A-type figure is basically shown in this manual because the specifications are the same. For details, see "3.1 Controller Appearance."

## How to Check the Controller Model

To check the controller model, see the description in the “Model” field in the figure below.



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

## Symbols

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

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

 **DANGER**

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

 **WARNING**


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

 **CAUTION**

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

**[NOTE]**

Denotes precautions regarding robot specification, handling, teaching, operation, and maintenance.

 **WARNING**

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

## Introductory Notes

### ■ Hardware keys and switches (button)

F series controller provides hardware keys and switches on the operation panel and the teach pendant for various kinds of operations. In this manual, the names of keys and switches are indicated as follows.

- The names of the hardware keys and switches are enclosed with a square.
- The terms “key” or “switch” which should follow the relevant names are sometimes omitted for simpler expression.
- When pressing two or more keys at the same time, the keys are indicated by “+”.

<b>Example</b>	
<span style="border: 1px solid black; padding: 0 2px;">ENTER</span> :	The hardware key “ENTER”.
<span style="border: 1px solid black; padding: 0 2px;">TEACH/REPEAT</span> :	The mode switch “TEACH/REPEAT” on the operation panel
<span style="border: 1px solid black; padding: 0 2px;">A</span> + <span style="border: 1px solid black; padding: 0 2px;">MENU</span> :	Press <span style="border: 1px solid black; padding: 0 2px;">MENU</span> while pressing and holding down <span style="border: 1px solid black; padding: 0 2px;">A</span> .

### ■ Software keys and switches

F series controller provides software keys and switches which are displayed on the screen of the teach pendant for various kinds of operations depending on specifications and situations. In this manual, the names of keys and switches are indicated as follows.

- The names of software keys and switches are enclosed by “<XXX>” parentheses.
- The terms “key” or “switch” which should follow the relevant names are sometimes omitted for simpler expression.

<b>Example</b>	
<ENTER>:	“ENTER” key that appears on the teach pendant screen
<Next Page>:	“Next Page” key on the teach pendant screen

### ■ Selection items

Very often an item must be selected from a menu or pull-down menu on the teach pendant screen. In this manual, the items are indicated as follows.

- The names of these menu items are enclosed in brackets [XXX].
- To select an item, move the cursor to the relevant item by the arrow keys, and press the ↵ key. For detailed description, this procedure should be described every time, however, “select [XXX] item” will be used instead for simpler expression.

<b>Example</b>	
[Auxiliary Function]:	expresses the item “Auxiliary Function” in a menu.

### ■ Abbreviation

- “TP” will be used instead of “teach pendant” for simpler expression.
- “F key” will be used instead of “function key” for simpler expression.

## Manuals Referenced in This Manual

Manuals referenced in this manual and their document numbers are shown below.

<b>Manual names</b>	<b>Document No.</b>
"Safety Manual"	90801-1001
"AS Language Reference Manual"	90209-1025
"Operation Manual"	90203-1114
"External I/O Manual"	90204-1029
"Cubic-S Instruction Manual"	90210-1334
"CoreCubic-S Instruction Manual"	90201-1489
"General Fieldbus I/O Usage Manual"	90210-1326
"Options Installation Manual"	90210-1339
"Communication Option Manual"	90210-1344
"Troubleshooting Manual"	90206-1057

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## 1 Safety

This chapter only describes safety precautions during installation and connection of the controller. For all other safety matters, refer to the “Safety Manual”, a separate-volume.

\* For details of Cubic-S and CoreCubic-S, refer to the separate "Cubic-S Instruction Manual" or "CoreCubic-S Instruction Manual."

### 1.1 Precautions during Transportation, Installation and Storage of Controller

When installing the Kawasaki Robot controller, strictly observe the following cautions while carrying out the transportation, installation and storage work.

#### [NOTE]

The installation shall be made by qualified installation personnel and should conform to all national and local codes.



#### CAUTION

- 1. Strictly observe the following when carrying out the transportation, installation and storage work. The controller is composed of precision parts.**  
**When transporting or storing a controller:**
  - (1) Keep the ambient temperature within the range of -10 to 60°C.**  
(Ambient temperature during operating time: 0 to 45°C, see “3.3.”)
  - (2) Keep the relative humidity within the range of 35 to 85% RH**  
(Non condensing)
  - (3) Keep free from shock and vibration.**  
\*See “3.3” for vibration conditions during operation.
- 2. To carry out smooth and safe installation, remove all obstacles before installing a controller.**
- 3. Clear a passage for the transportation of controller before using a crane or forklift.**





## CAUTION

Be sure to check the environmental conditions and select the chassis specification.

- In case of standard F60 open specification (IP20)\*<sup>1</sup>

No protection is provided against objects thinner than a finger, conductive foreign matter such as metal particles or other foreign matter that can become conductive in humid conditions, and water. The air filter is attached as standard to prevent foreign matter of 1 mm or larger such as non-conductive particles or dust from entering the controller (see the figure below).

This specification can be used in an environment of up to pollution degree 2\*<sup>2</sup>. Pollution degree 2 is an environment where dust, conductive foreign matter, or water-containing dust does not occur, for example in an office or a clean factory.

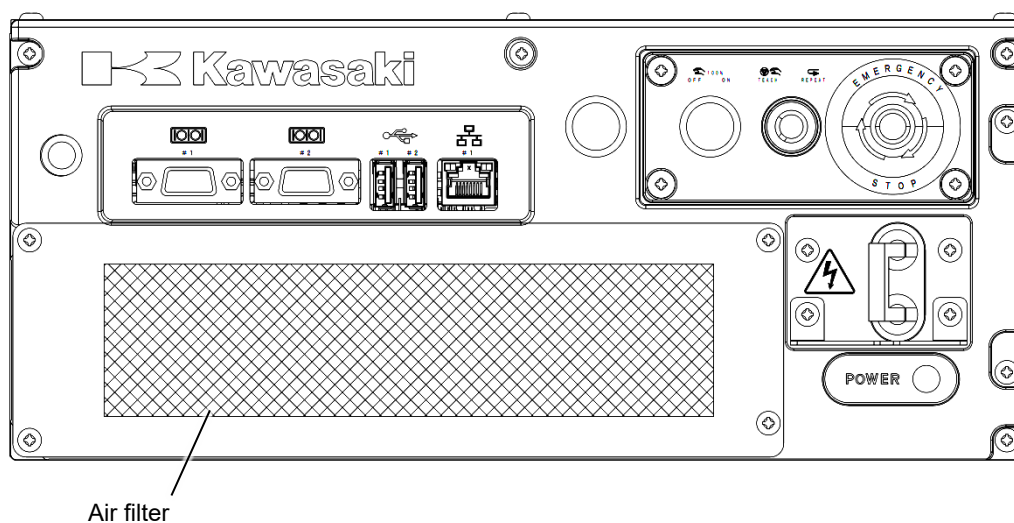
- In case of F60 sealed specification (IP54)\*<sup>1</sup>

This specification prevents dust particle penetration that may cause controller's functional loss and is splash-proof. In environments at pollution degree 3\*<sup>2</sup> where conductive foreign matter, dust, or water-containing dust can be generated and enter the controller, attach an optional sealed chassis. Even with the optional sealed chassis attached, avoid environments where a large amount of metal particles are generated and the controller is exposed directly to the metal particles.

Avoid environments where oil mist is floating in the air leading to high oil content.

\*<sup>1</sup> The IP protection ratings are stipulated by IEC60529.

\*<sup>2</sup> The pollution degree is stipulated by IEC60664-1.



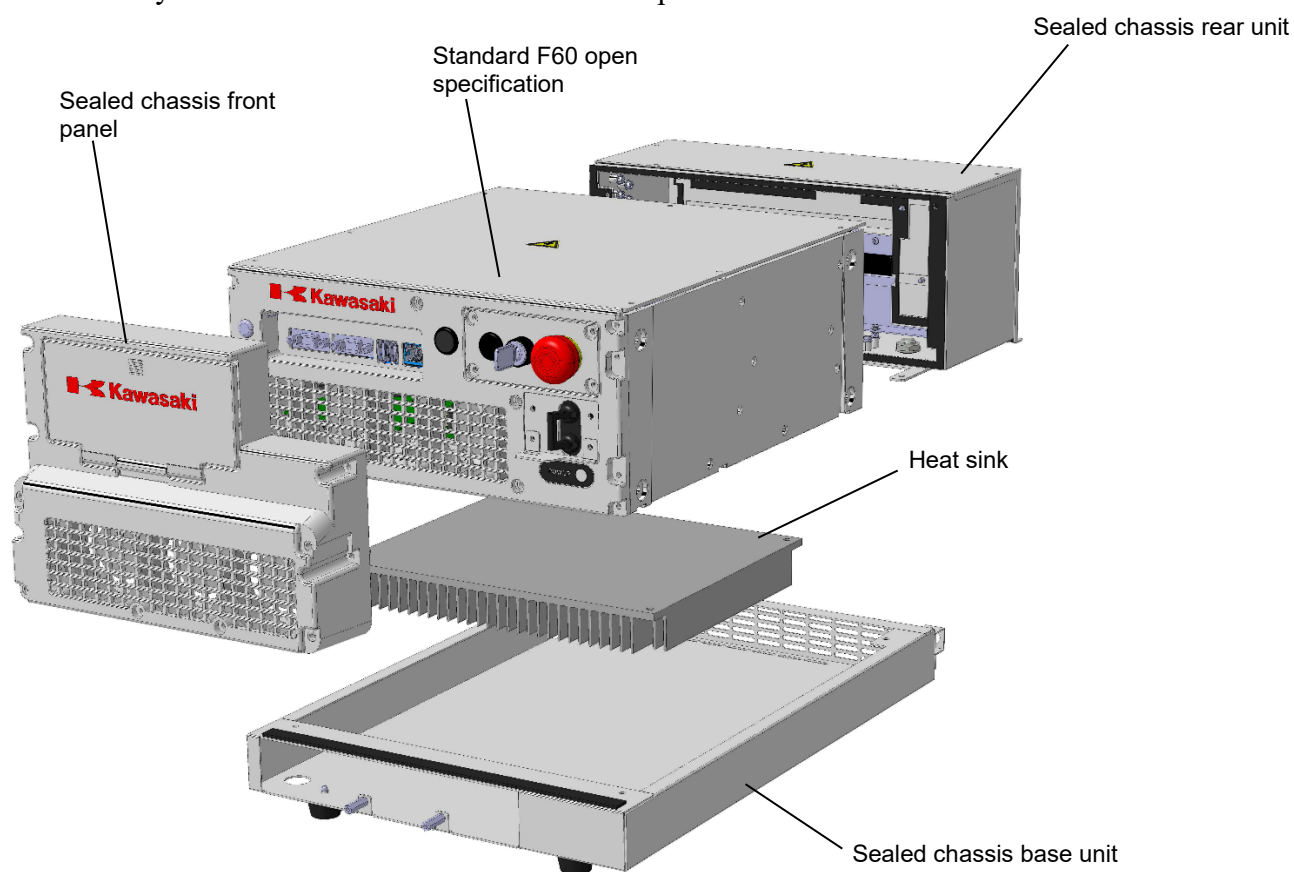
Front view of the controller with air filter attached

## 1.2 Sealed Specification

The F60 controller has an open structure as standard. When installing the controller in an environment at pollution degree 3 specified by IEC60664-1, an optional sealed chassis must be attached.

See the figure below for the optional sealed chassis.

It is necessary to remove the air filter to install the optional sealed chassis.



In the following pages, the chassis consisting of the standard F60 open structure controller and an optional sealed chassis is referred to as “F60 sealed specification”. Refer to the “Options Installation Manual” for how to install the optional sealed chassis.

### 1.3 Installation Environments of Controller

Install the controller in a site that satisfies all the following environmental conditions:

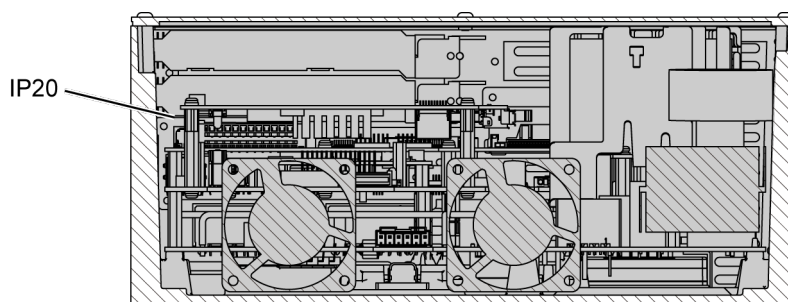
1. Ambient temperature during operation: within 0 to 45°C
2. Relative humidity: 35 to 85%RH (Non condensing)
3. Altitude: up to 1000 meters above mean sea level
4. Environmental conditions related to foreign materials
  - See the precautions in “1.1 Precautions during Transportation, Installation and Storage of Controller.”

In case of standard F60 open specification

- Pollution degree 2 or lower (no condensation)\*

\* The pollution degree is according to IEC60664-1.

See the figure below for the controller IP protection rating specified by IEC60529.



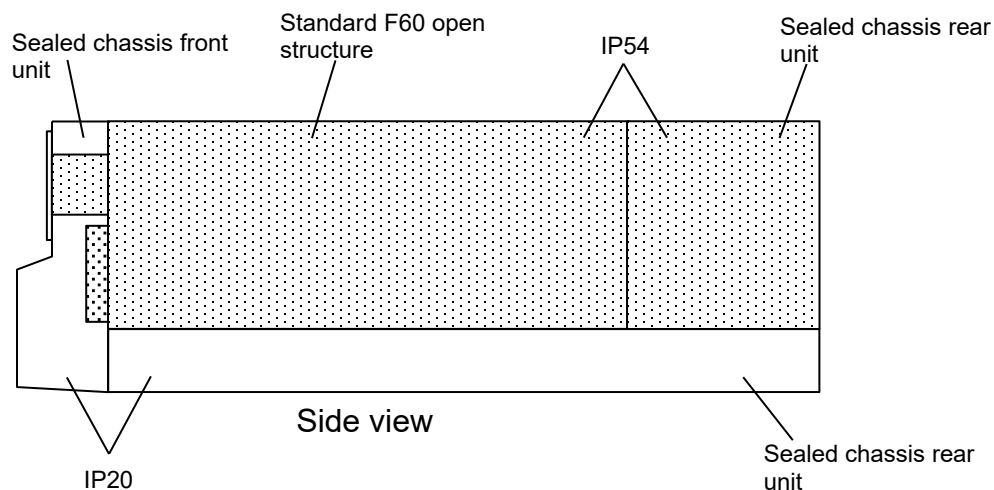
Front view

In case of F60 sealed specification

- Pollution degree 3 or lower (no condensation)\*

\* The pollution degree is according to IEC60664-1.

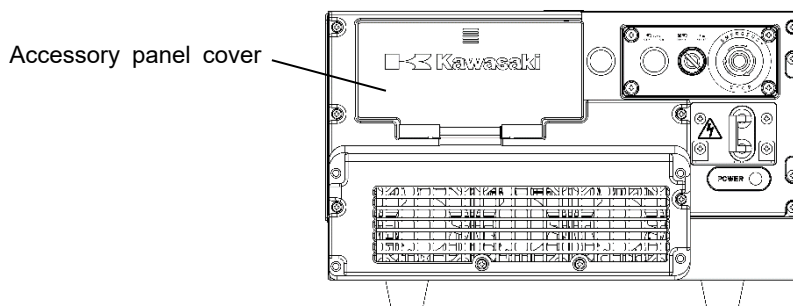
See the figure below for the controller IP protection rating specified by IEC60529.



Side view

Note:

- Close the accessory panel cover of the sealed chassis front unit to ensure the sealability.



Front view of F60 sealed specification

- Read the precautions for the F60 sealed specification in “6.1 Connection between Controller and Robot” carefully.
- Refer to the separate “Options Installation Manual” for the precautions for assembly.

#### 5. Installation site

- Free from electrical noise interference.  
Controller external power noise: 1 kV/1  $\mu$ s or less

**!** **CAUTION**

**If the controller is installed near equipment that generates a lot of electrical noise, be sure to provide appropriate surge killers around that equipment. Noise producing equipment includes: induction motors, electromagnetic brakes, solenoids, or contact equipment, etc.**

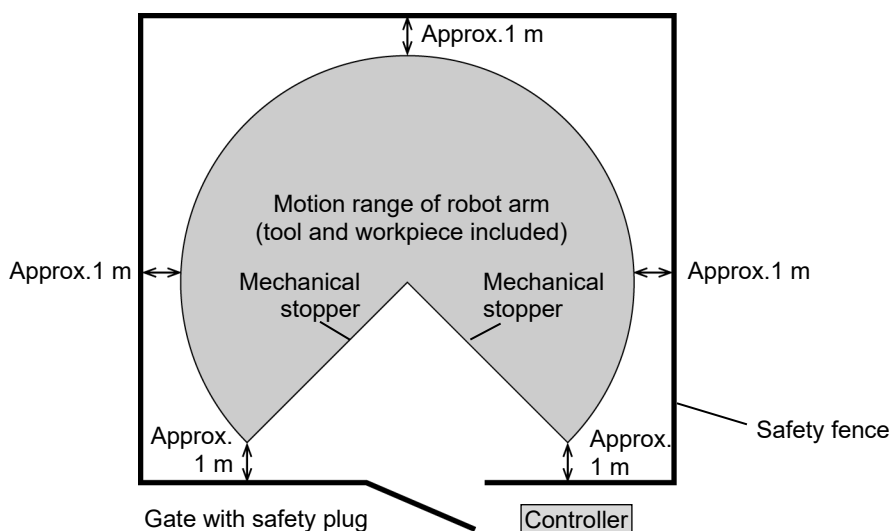
- Free from flammable and/or corrosive liquid and gas. (e.g.: hydrogen sulfide)
- Free from excessively strong vibration.
- Place where power is supplied within specifications.  
Variation rate:  $\pm 10\%$  or less
- Place where dedicated grounding is provided. (100  $\Omega$  or less)

6. Installation conditions of safety fence

- Safety fence should be installed with margin (minimum 1 m) from outside the motion range of robot (with tools and workpieces).
- Ensure the followings when installing a safety fence.
  - Enough space for easy access to the controller in maintenance
  - Installing an entrance gate with a safety plug to the safety fence
  - Referring the requirements established in each region for details of the safety fence  
(e.g. ISO 13854 to 13855, 13857, 14119 to 14120)

**CAUTION**

**The controller shall not be located inside of the robot's motion range, work cell, or safety fence.**



## 1.4 Precautions When Connecting the Harness

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



### WARNING

**In order to prevent electric shock accidents, do not connect the external power until connections between the robot and the controller are complete.**



### CAUTION

- 1. Do not mistake the destination of connectors when connecting the harnesses. Forcing to connect the harness wrongly may damage connectors or cause a break in the electrical system.**
- 2. Prevent people or equipment (forklift etc.) from stepping on or riding over the harnesses. Otherwise, the harness may become damaged or the electrical system may break.**
- 3. Separate the harnesses from any nearby high voltage lines.**
  - (1) Do not run the harnesses in parallel with other power lines.**
  - (2) Do not bundle the harnesses.**
  - (3) Separate the harnesses for 1 m or more from any nearby high voltage/high current power lines. Otherwise, the noise is generated from power lines and will cause malfunctions.**
- 4. Even when the harnesses are long, do not bundle them winded or bended. Bundling the harness causes the heat to build up in the harness, resulting in over-heat and furthermore may cause fire.**

## 1.5 Precautions When Connecting the External Power

Strictly observe the following precautions when connecting the external power.



### DANGER

1. Before connecting the external power, confirm that the external power supply for the controller is cut off at the source. Connecting components while power is supplied may cause electric shock.
2. To prevent external power from being turned ON accidentally, tag the breaker and indicate clearly that work is in progress. Or, assign a supervisor in front of the breaker until the connection is complete.



### WARNING

1. Confirm that the connected supplying power to the controller meets specifications shown on the rating plate. Supplying out-of-specification power will damage electric components in the controller.
2. Ground the controller to prevent against electrical shock and noise without fail.
  - (1) Dedicated ground:  
Dedicated class D grounding with a resistance of 100  $\Omega$  or less
  - (2) Recommended power cable size:  
Ground wire which is 2.0 mm<sup>2</sup> or more (AWG #14 or more)
3. Never share a ground line with workpiece to be welded or another machine (weld machine, etc.).
4. Strictly observe the following precautions when conducting the arc welding.
  - (1) Connect the minus pole of the weld power supply to a jig or directly to workpiece to be welded.
  - (2) Insulate the robot body and controller so that they do not share a common ground line.
5. Before turning ON the external power to controller, make sure the power supply wiring is complete and all the covers are attached properly. Failure to do so may cause electric shock.



### CAUTION

1. **Prepare external power that meets the specifications of the controller in terms of momentary power interruption, voltage fluctuation, power capacity, etc. Supplying out-of-specification power is connected, the power monitoring circuit activates cutting off the power, and an error may be returned.**
2. **If the external power emits a lot of electrical noise, set up a noise filter to reduce the interference.**
3. **Confirm that there are no low noise-resistant devices in the vicinity beforehand. PWM noise generated from robot motor lines may cause malfunction of the devices via external power line.**
4. **Install a separate external power switch (breaker) for the robot, independent and unconnected to the other device such as weld machine.**
5. **To prevent shorting or accidental leakage on the external power switch, install a time delay type ground leakage breaker (sensitivity of 100 mA or more).**
6. **If there is a possibility that surge voltage such as lightning surge might be applied from external power line, decrease the surge voltage level by mounting a surge absorber, etc.**
7. **Use the surge protective device (SPD) that conforms to NFPA79.**

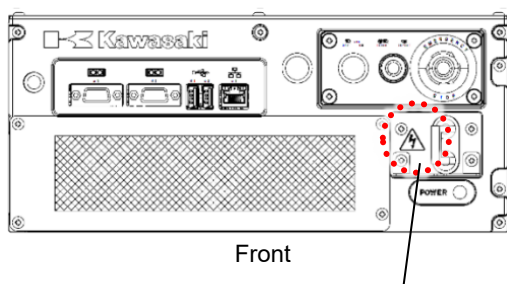
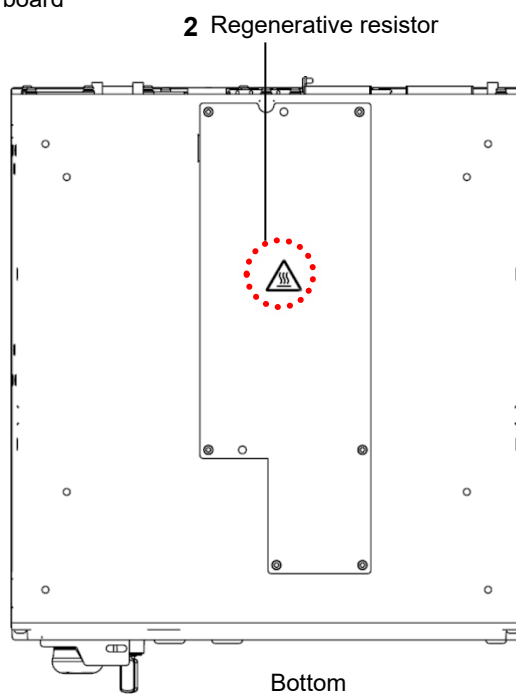
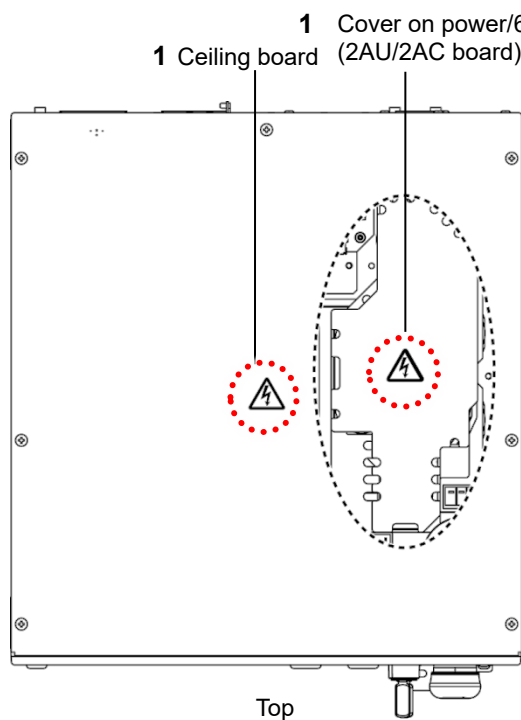


## 1.6 Warning Labels

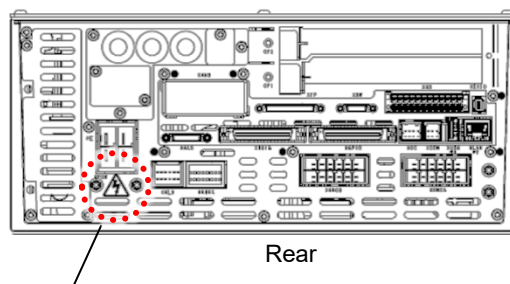
Warning labels for electric shock and high temperature are located on the controller shown below.

### ■ F60 controller

- Standard open specification



1 Controller power switch



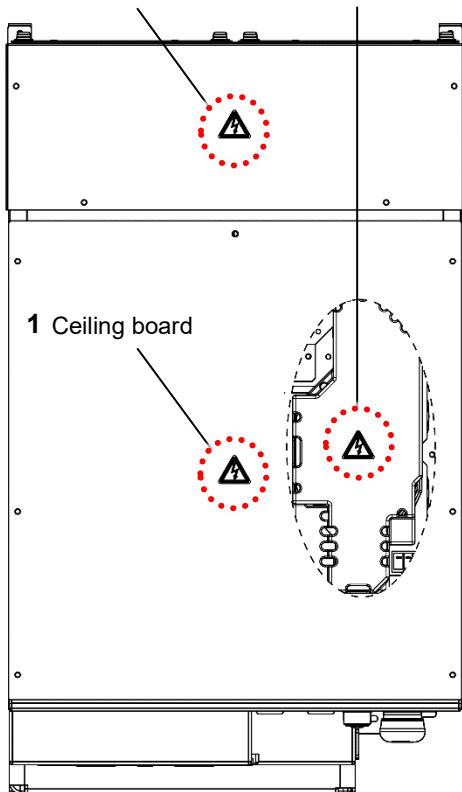
1 External power inlet

- Sealed specification

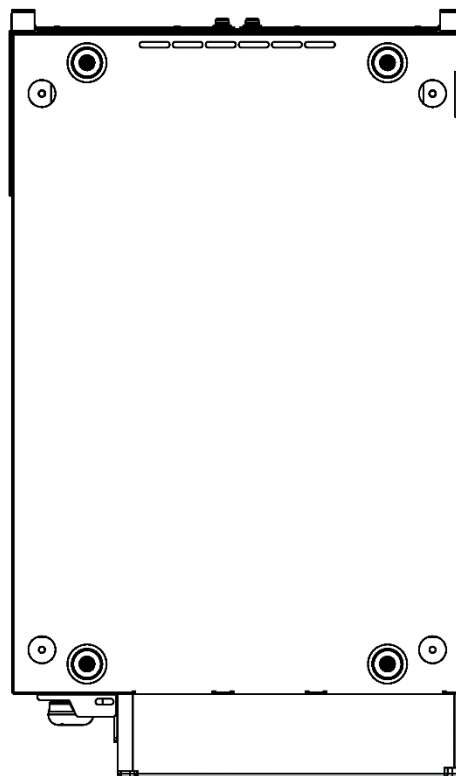


1 Upper part of sealed chassis rear unit

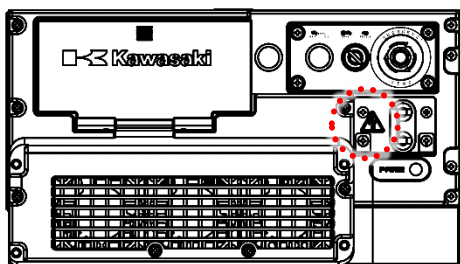
1 Cover on power/6-axis amplifier board (2AU/2AC board)



Top

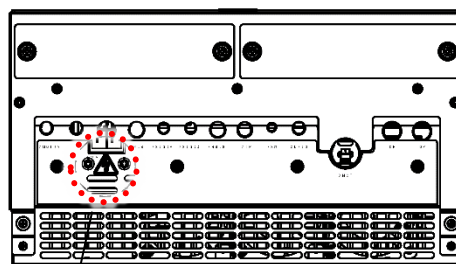


Bottom



Front

1 Controller power switch



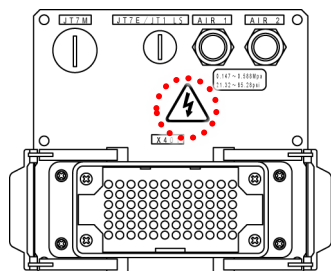
Rear

1 External power inlet (Rear part of standard open structure)

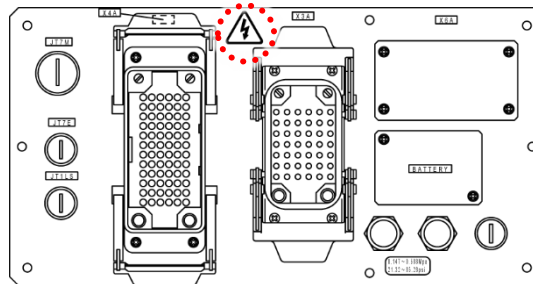
■ Connector plates on arm base section



R series: 003N/005N/005L

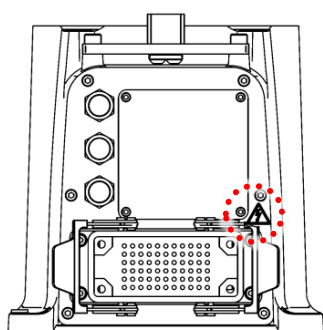


R series: 010N/006L

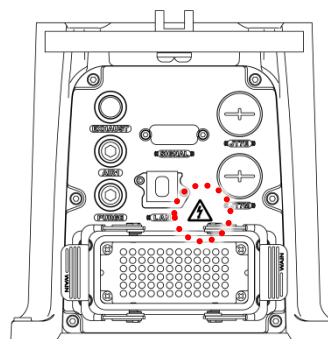


R series: 007N/007L

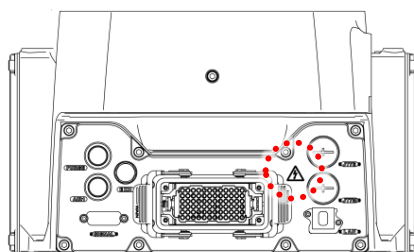
· RS007N-A/RS007L-A



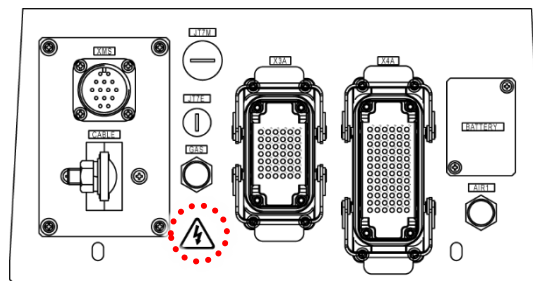
· RS007N-B/RS007L-B



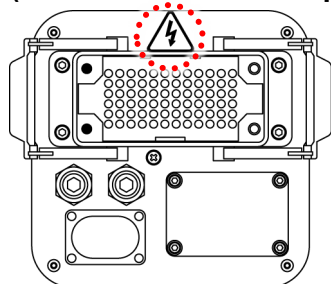
R series: 013N



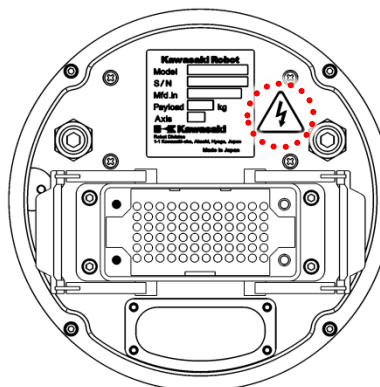
BA



MC  
 (Backside connector spec.)



MC/MS  
 (Base connector spec.)



## 1.7 Battery and Fuse Use and Disposal

Batteries are used for data backup in the robot arm and controller.

If not used and disposed of properly, these batteries may malfunction, ignite, overheat, explode, corrode, leak, etc. Strictly observe the following precautions.



### WARNING

1. **Only use batteries specified by Kawasaki.**
2. **Never re-charge, dismantle, convert and/or overheat batteries.**
3. **Never dispose of batteries into water or fire.**
4. **Batteries with damaged cases may short internally and must not be used.**
5. **Never short the positive and negative poles of a battery with material such as wire.**



### CAUTION

**Never dispose of depleted batteries with garbage that is disposed of in an incinerator, land-fill, dumping-ground, etc. When disposing of batteries, insulate with tape so as not to contact other metal. Comply with local regulations and rules for battery disposal.**

■ Locations of batteries

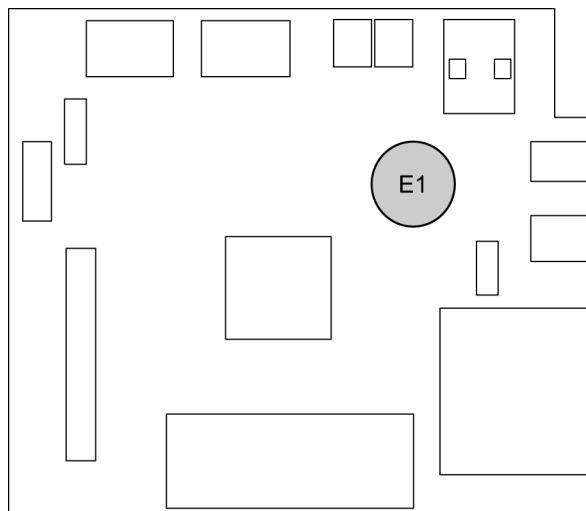
Battery locations of 2AA board and 1HG board are as follows:

- 2AA board

Location Number: E1

Model: BR2032

Manufacturer: Panasonic



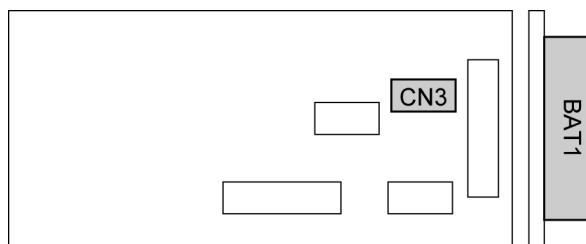
- 1HG board (in robot base)

Location Number: BAT1

Model: 50750-1007 or  
 50750-1018

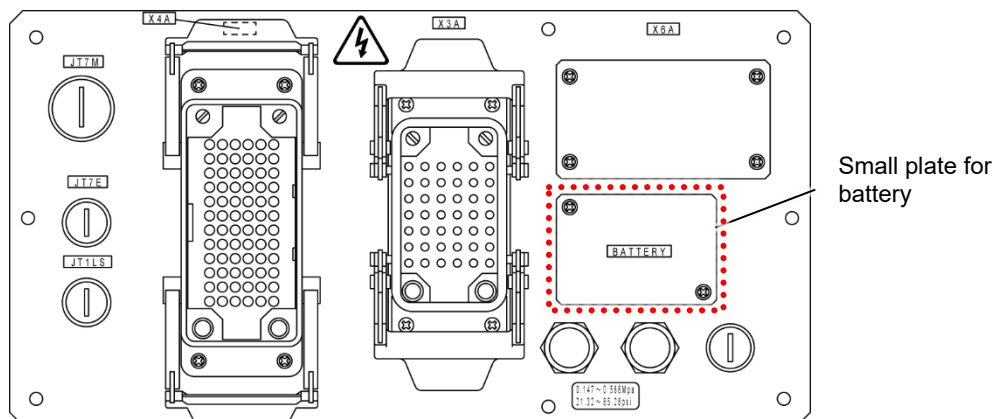
Manufacturer: KHI

Connector: CN3



- Replacement method

Batteries can be replaced only by removing a small plate on which “BATTERY” is written.



## 1.8 Safety Features

To safeguard the user, Kawasaki robot systems are equipped with the following features:

1. All emergency stops are hard-wired.
2. All robot controllers are equipped with a redundant dual channel safety circuit.  
Both channels of the safety circuit must be closed to allow for robot operation in the teach and repeat modes. Refer to the “External I/O Manual” for details.
3. Safety circuits of controllers satisfy requirements of PLe in category 4 defined by ISO 13849-1: Category and Performance level (PL) are determined by the whole system and conditions.
4. (For the arms which are equipped with servo lamp ON) When servo motor power is supplied, the servo ON lamp is illuminated.
5. The teach pendant and operation panel are equipped with emergency stop switches.  
And all robot controllers have external emergency stop inputs.
6. The TP is equipped with three-position, enabling devices. The enabling devices must be pressed and held down to enable motor power in teach and check modes.
7. TCP speeds in teach and check modes are limited to a maximum of 250 mm/s (10.0 in/s).
8. The speed limit can be 250 mm/s (10.0 in/s) or more in the Fast Check Mode if an optional Fast Check Mode switch is used (defined by ISO 10218-1).
9. Enabling Cubic-S or CoreCubic-S functions allows you to use their respective safety functions. For details on each safety function, refer to the separate "Cubic-S Instruction Manual" or “CoreCubic-S Instruction Manual.”



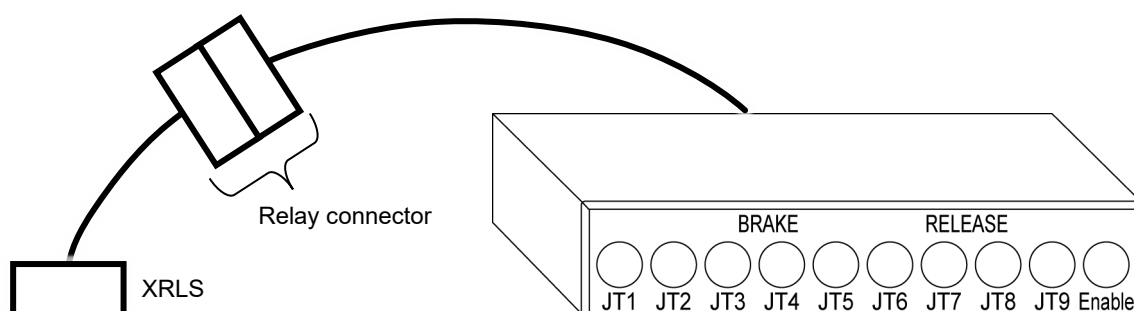
### WARNING

**When operating a robot using the Fast Check function, keep all people out of the safeguarded space and check the operation outside the safety fence.**

## 1.9 Emergency Movement without Drive Power

The brake release switches (option) allow the operator to move arm without using motor drive power for maintenance and emergency situations.

- Brake release switch box (option)



### ■ Precautions

When no motor drive power is applied to the arm, electromagnetic brakes lock to maintain the robot posture. Unsupported axes may fall when pressing the brake release switch.

Axes which are overhung, particularly JT2 and JT3, will fall down the fastest, depending on conditions. Therefore, be careful when operating this switch.

**⚠ WARNING**

**Position yourself to observe the entire robot arm and keep your eyes on the arm when operating the brake release switch.**

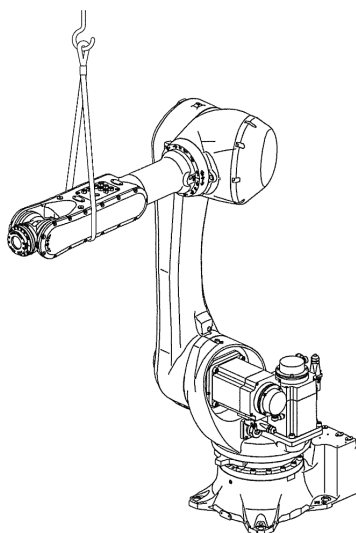
### ■ Operating procedure

To manually release axes brakes, follow the procedure below.

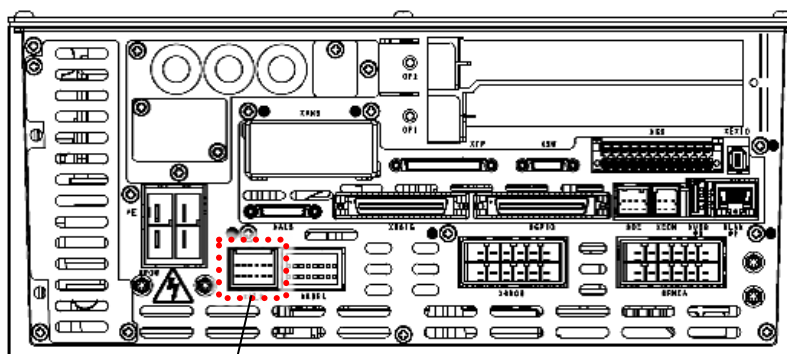
1. Press **EMERGENCY STOP** of the controller and the TP, and cut off the motor power.
2. Make sure that the safety measures are followed.
  - There are no personnel around the robot.
  - Plug of safety fence is inserted.

3. Provide suitable support of the robot arm, end-or-arm tooling, and payload if there is a risk of personal injury and facilities before using the brake release switch. Robot arm can be supported by using a crane and a wire (see figure below).

**⚠ WARNING**  
Failure to take measures may lead to an accident or damage on robot.



4. Connect the harness from the brake release switch box to the brake release switch connection connector.
  - Brake release switch connection connector position of F60 controller

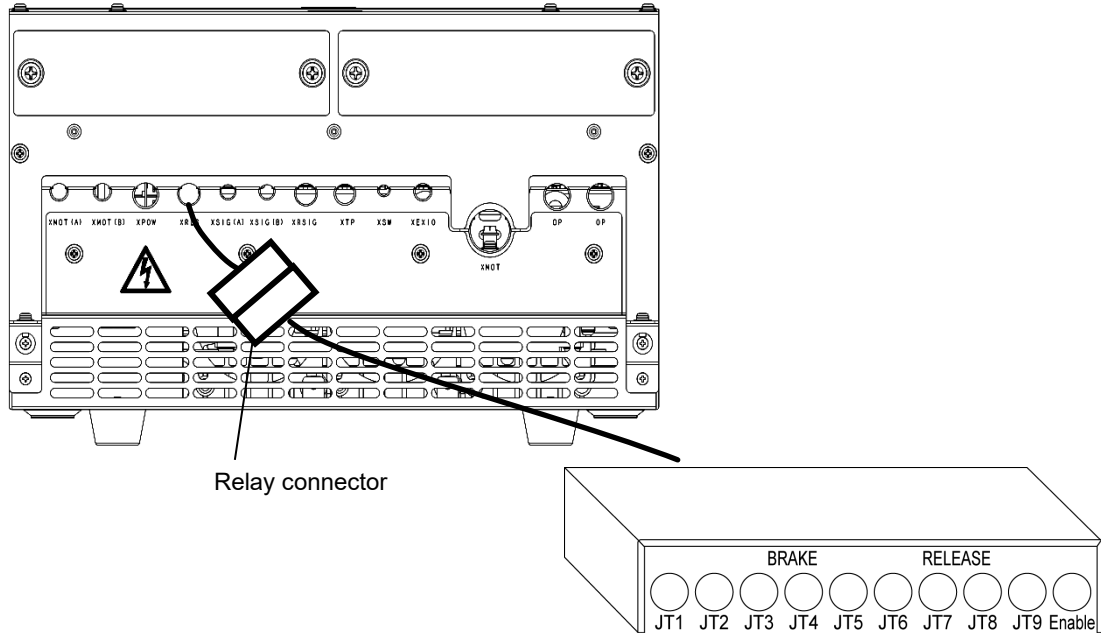


Brake release switch connection connector (XRLS)

**⚠ CAUTION**  
Do not block the front of the XRLS connector so that the connector can be connected to the brake release switch immediately in emergency.

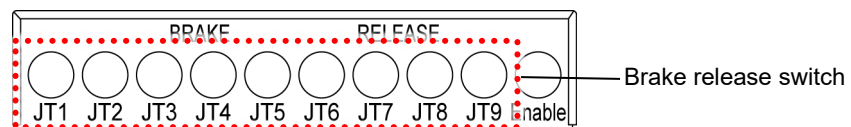


- When connecting the brake release switch box to the sealed chassis, connect the wires so that the relay connector is located outside of the chassis as shown in the figure below.



- Make sure that the brake is not released by pressing one switch.  
If the brake is released, do not use the switch.

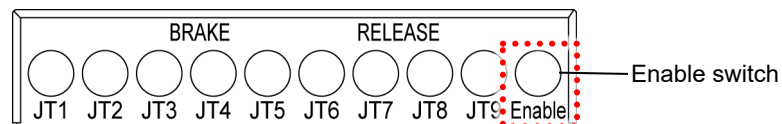
(1) Press the brake release switch for the axis to release the brake for a moment.



**⚠ CAUTION**

**Stop using the brake release switch immediately if the electromagnetic brake is released by pressing only one switch. The switch may be defective.**

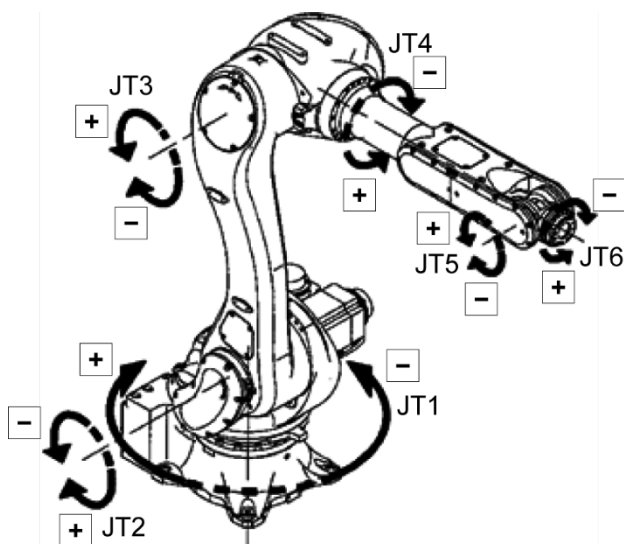
(2) Press and hold the Enable switch.



- Press the brake release switch for the axis to release the brake while pressing the Enable switch.

**⚠ CAUTION**  
**For the safety, release the brake per axis. Pressing more than one switch at the same time may lead to an accident or damage on robot.**

7. The brake remains released until releasing the brake release switch.
  - Robot axis to release the brake

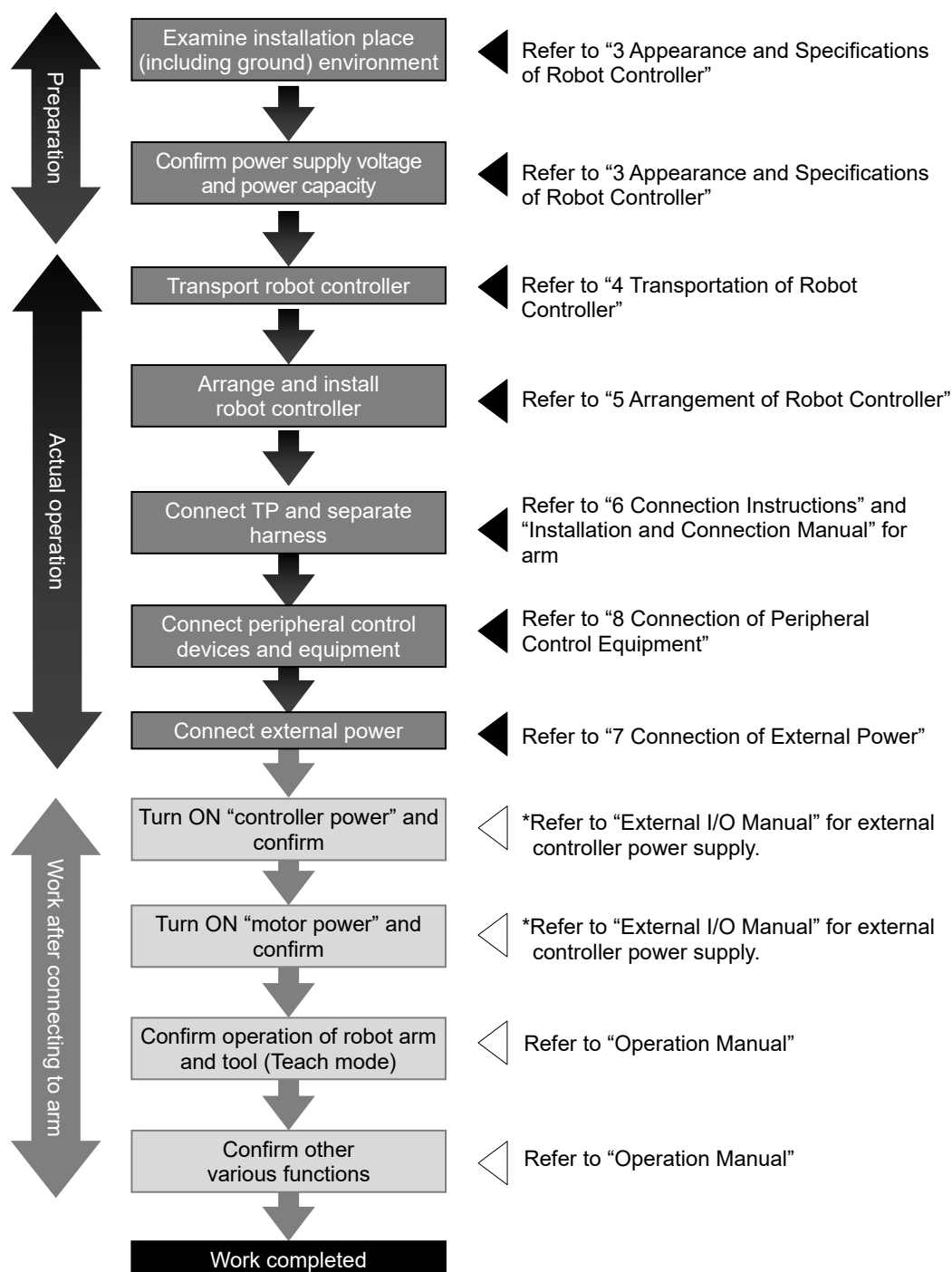


6-axis robot

## 2 Workflow - Robot Controller Installation and Connection

This workflow describes the robot controller.

For the robot arms, refer to “Installation and Connection Manual” for them.



**[NOTE]**

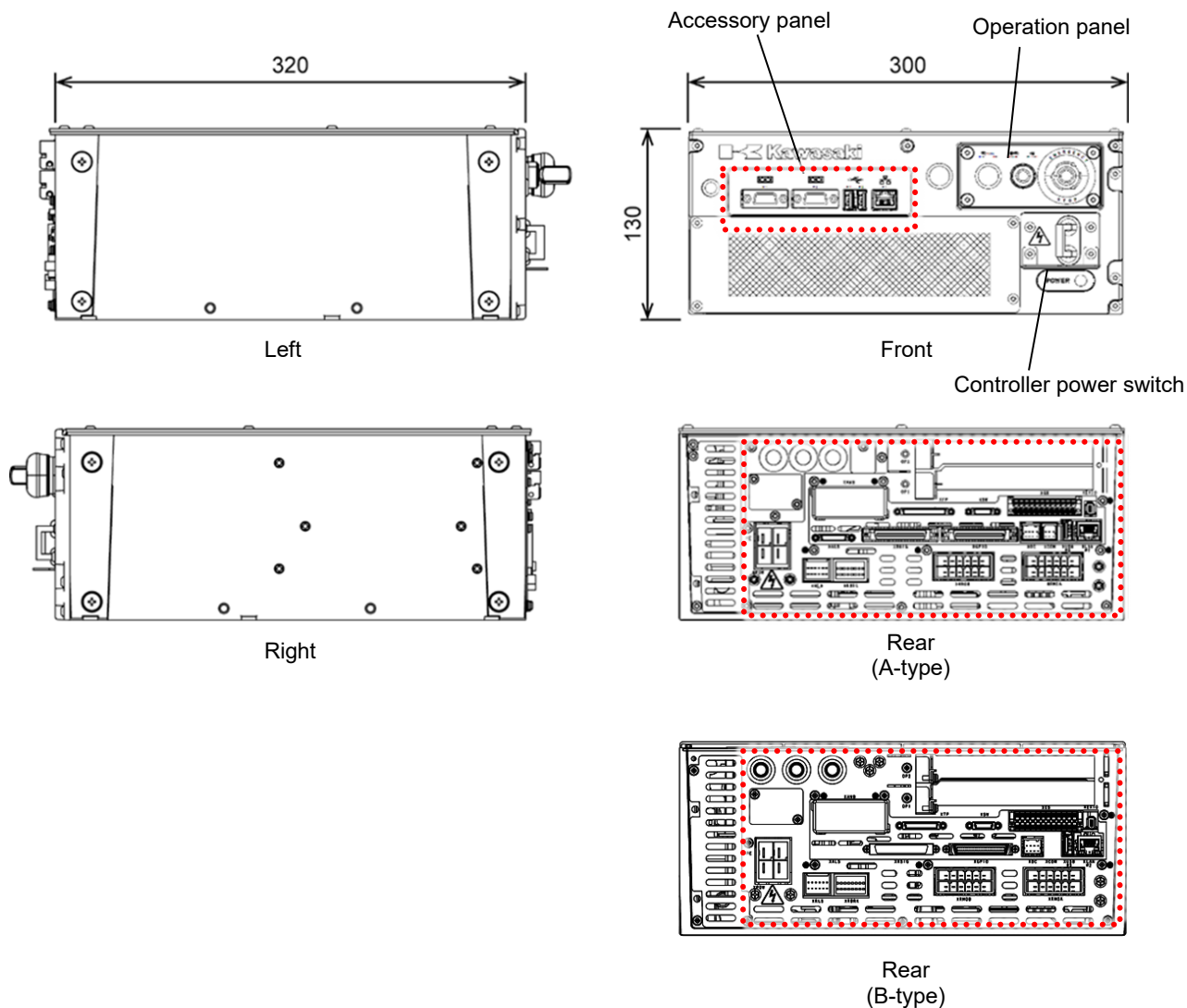
This manual only describes procedures from installation place examination to connection with external power.

### 3 Appearance and Specifications of Robot Controller

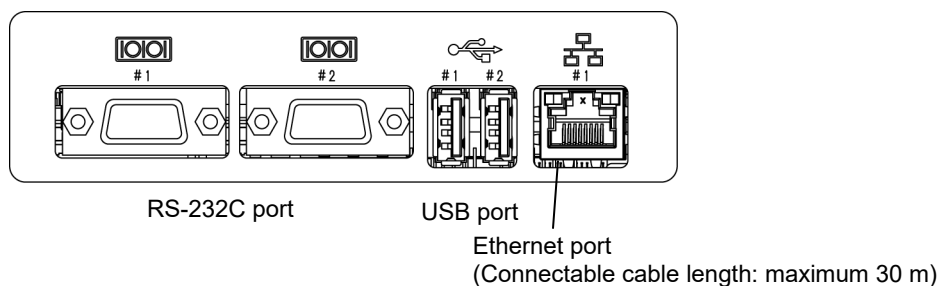
#### 3.1 Controller Appearance

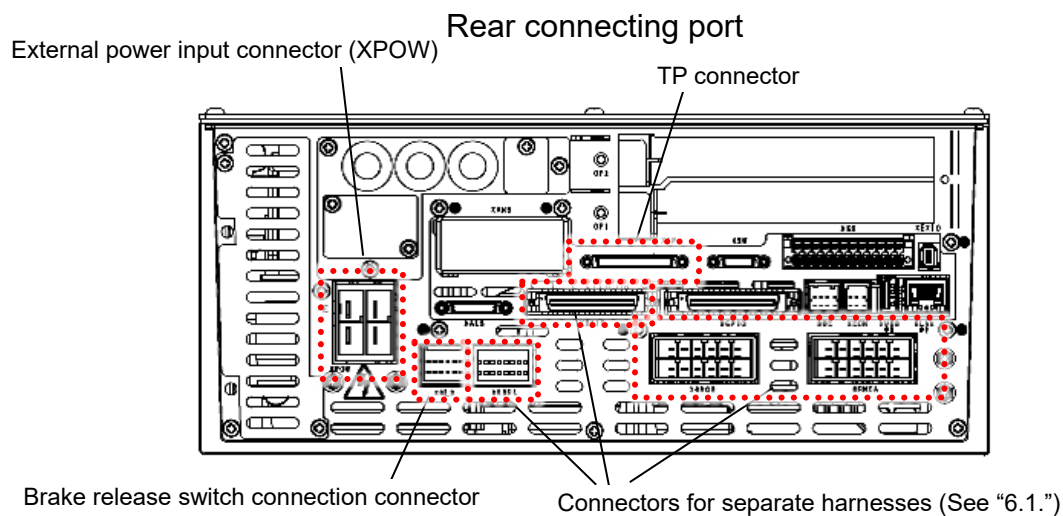
##### ■ F60 controller

- Standard open specification
  - \* Although A-type and B-type have slightly different rear shape, A-type figure is basically shown in this manual because the connector layout is the same.

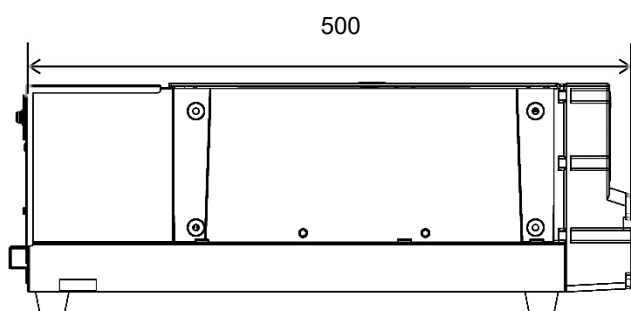


#### Connecting ports in the accessory panel

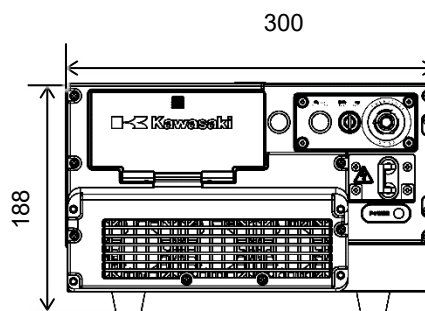




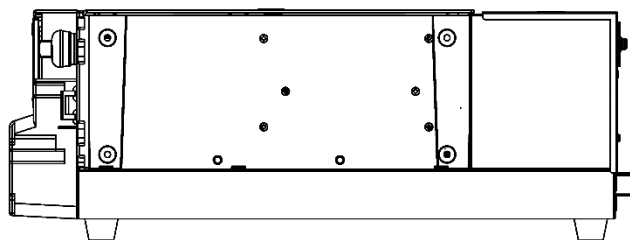
- Sealed specification



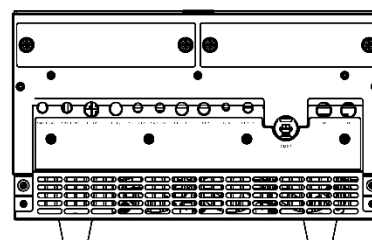
Left



Front

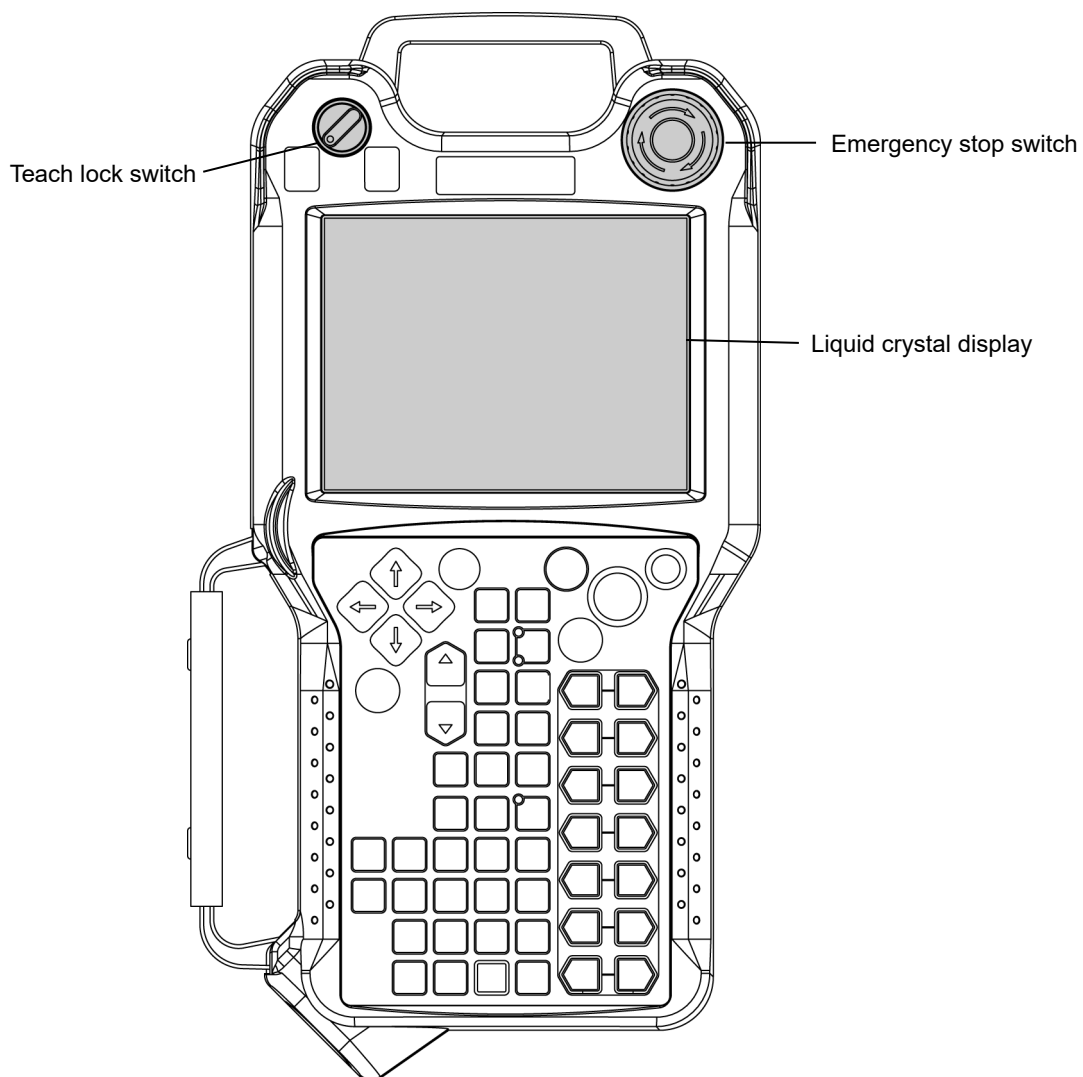


Right



Rear

### 3.2 TP Appearance



### 3.3 F60 Controller Specifications

#### ■ Controller

Specification		Standard open specification	Sealed specification
Structure		Open structure, direct cooling system	Sealed structure, indirect cooling system
Mass		F60: 8.3 kg <sup>*1</sup>	F60: 15 kg <sup>*1</sup>
Ambient environment	Temperature	0 to 45°C	
	Humidity	35 to 85 %RH (Non condensing)	
	Altitude	Up to 1000 meters above mean sea level	
	Pollution degree <sup>*2</sup>	2 or below	3 or below
Vibration condition	10 to 57 Hz	Half amplitude 0.075 mm	
	57 to 150 Hz	1 G	
Power source		AC 200-230 V±10%, 50/60 Hz, Single phase	
Power capacity		Refer to the table below.	
Grounding		Dedicated class D grounding (100 Ω or less)	
TP cable length		5 m/10 m/15 m/20 m/25 m/30 m (A-type) 5 m/10 m/15 m/20 m/25 m/30 m/35 m/40 m/45 m (B-type)	

\*1 Not including optional components

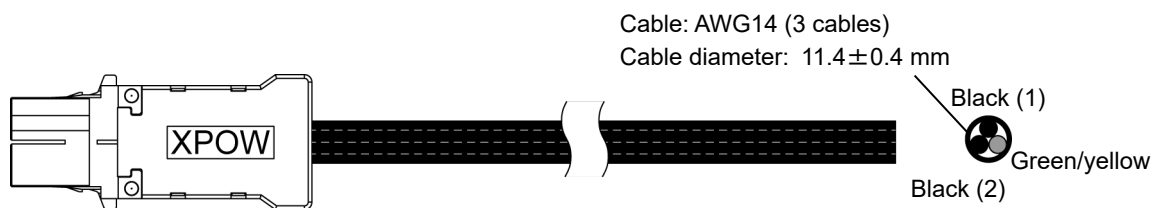
\*2 The pollution degree is stipulated by IEC60664-1.

#### ■ Power capacity for external power connection and cable specifications

F60 controller is equipped with a power cable with connector (AWG14, standard 2 m) as shown in the figure below. See “7 Connection of External Power” for the connecting method.

Controller model	Arm model	Power capacity	Recommended power cable size (including ground wire)	Length requirement
F60 controller	R series 003 to 010, 013* BA/MC/MS * Excluding 010L	2.0 kVA max.	2.0 mm <sup>2</sup> or more (AWG14 or more)	200 m or less

XPOW connector	Model	Manufacturer
Cable side (female)	1971239-1	TE Connectivity
Controller side (male)	1-1318983-2	TE Connectivity



**CAUTION**

**If a cable with an unspecified diameter is used for the sealed specification, sealability cannot be ensured, causing failure. Be sure to use cables with the specified diameter.**

■ **Circuit breaker spec. for external power connection**

Controller model	Rated current	Rated voltage	Rated interrupting capacity
F60 controller	15 A	AC240 V	5000 A (UL489)

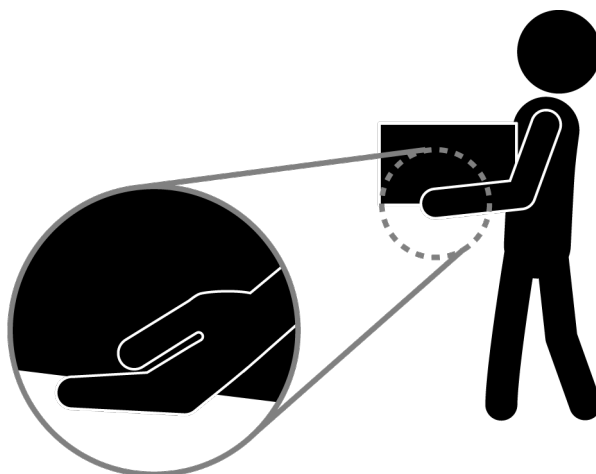


## 4 Transportation of Robot Controller

When transporting the controller, follow the procedure below.



1. Remove harnesses connected to TP and other external devices.
2. Hold the bottom of the controller firmly.
  - F60 controller weight: 8.3 kg (Standard open specification)/15 kg (Sealed specification)
3. Lift up the controller.



## 5 Arrangement of Robot Controller

### 5.1 Horizontal Arrangement of Controller

Horizontal arrangement is the standard for F60 controller. In order for the controller to maintain the proper internal temperature, the installation site must conform to the following.

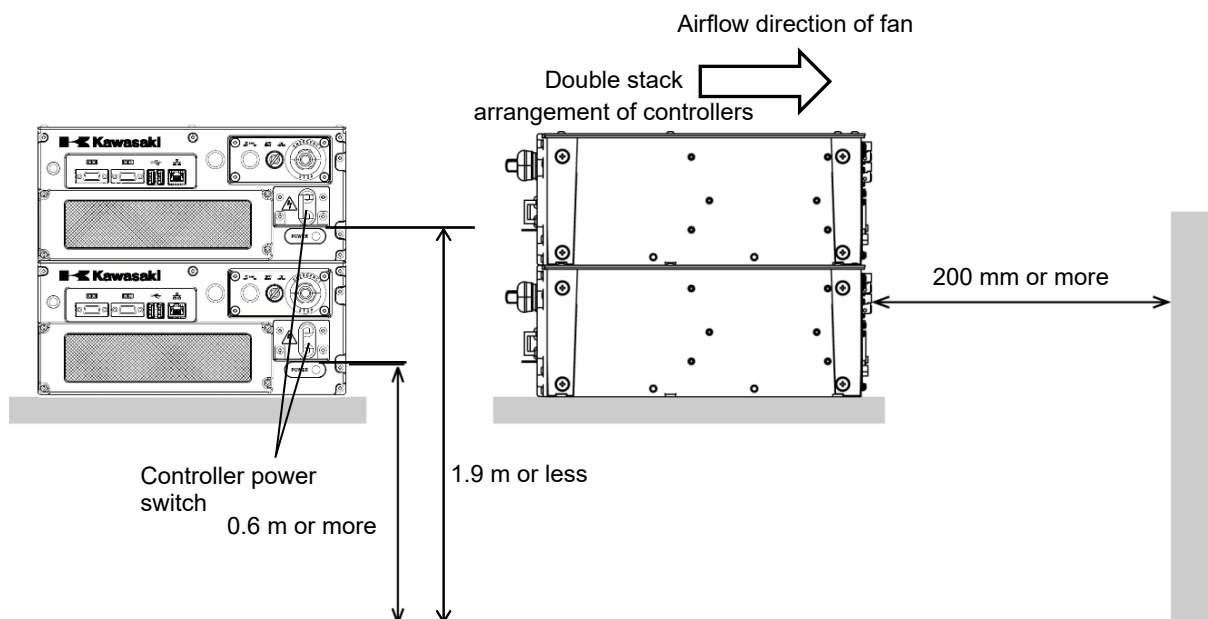
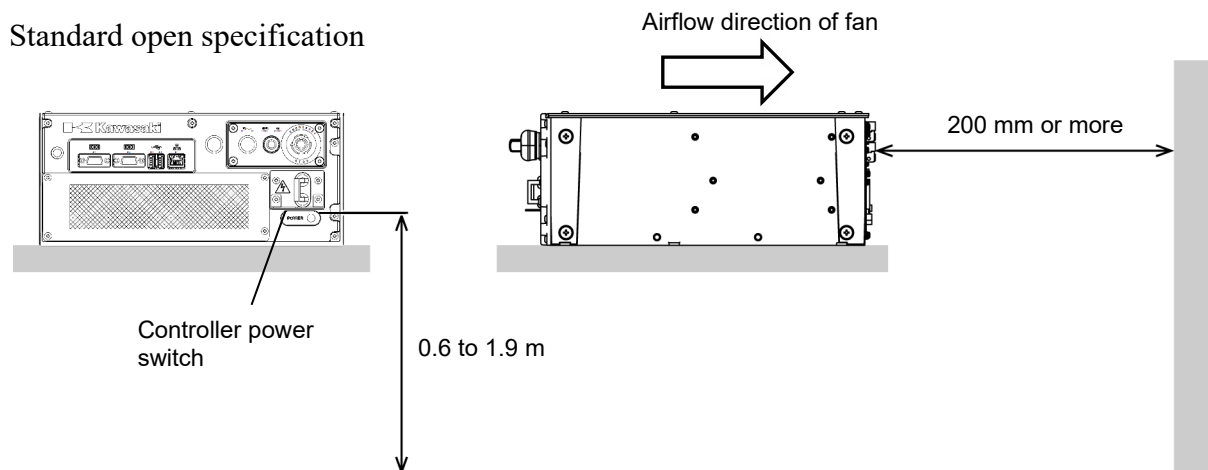
#### ■Precautions

- In case of horizontal installation, up to three controllers can be stacked.
- It is necessary to remove the object on the top surface of the controller in maintenance.

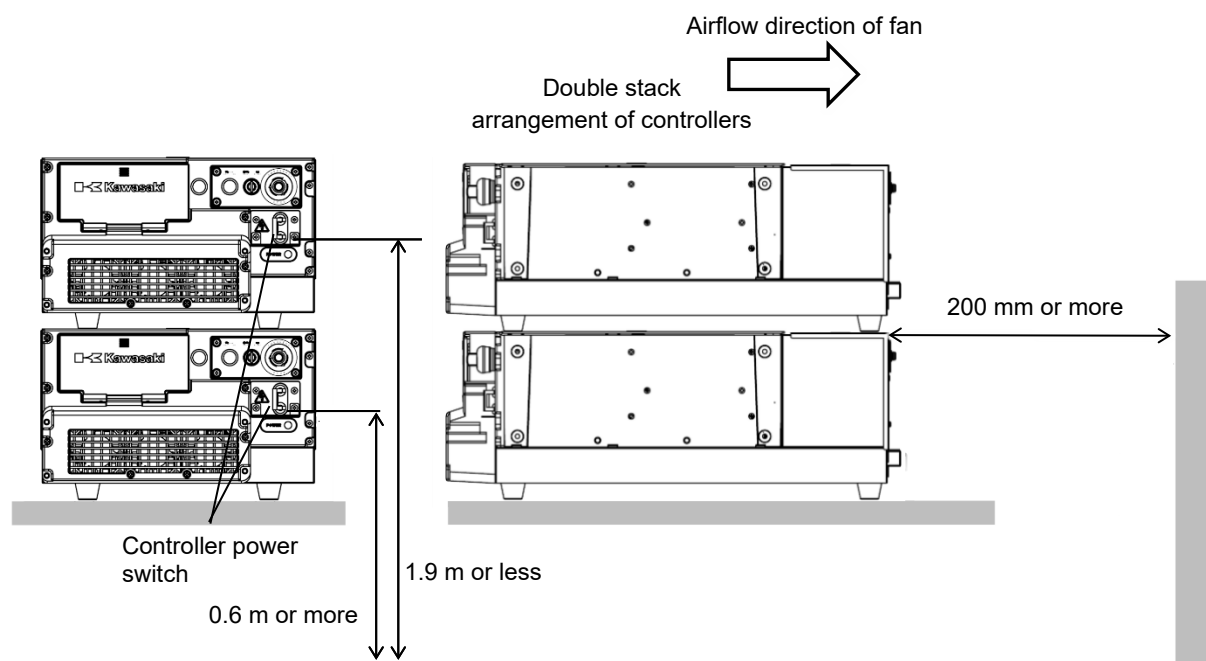
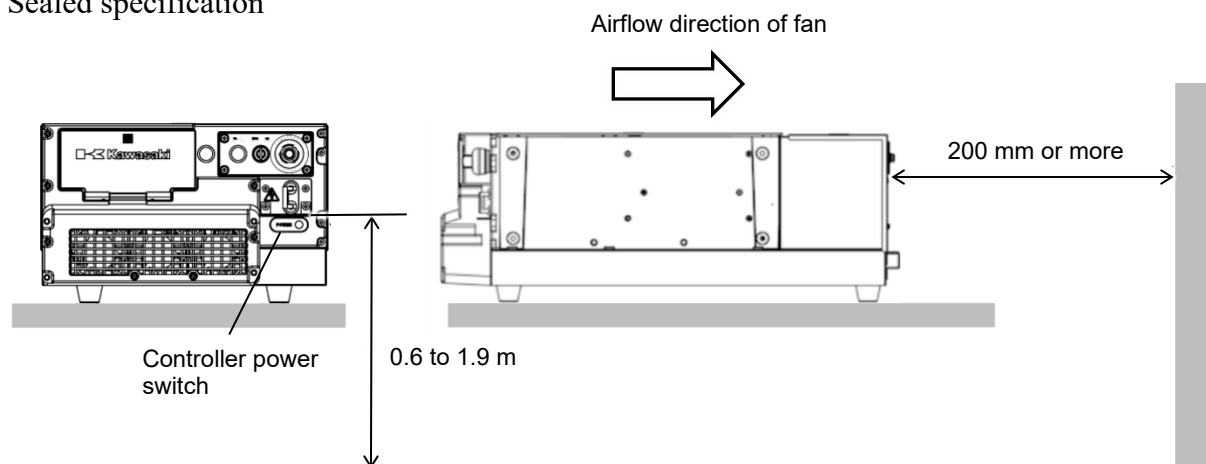
#### ■Locations

- Arrange the controller on a flat, horizontal stand and adjust its height so that the heights of controller power switch and operation switches from the floor are between 0.6 to 1.9 m.
- Provide a clearance of 200 mm or more between the controller rear side and the wall.

Standard open specification



Sealed specification



**⚠ CAUTION**

**Direct the airflow avoiding the fan exhaust opening in the rear of the controller. Foreign matter can enter from the rear of the controller and cause failure.**

## 5.2 Vertical Arrangement of Controller

Follow the procedure below when arranging the controllers vertically.

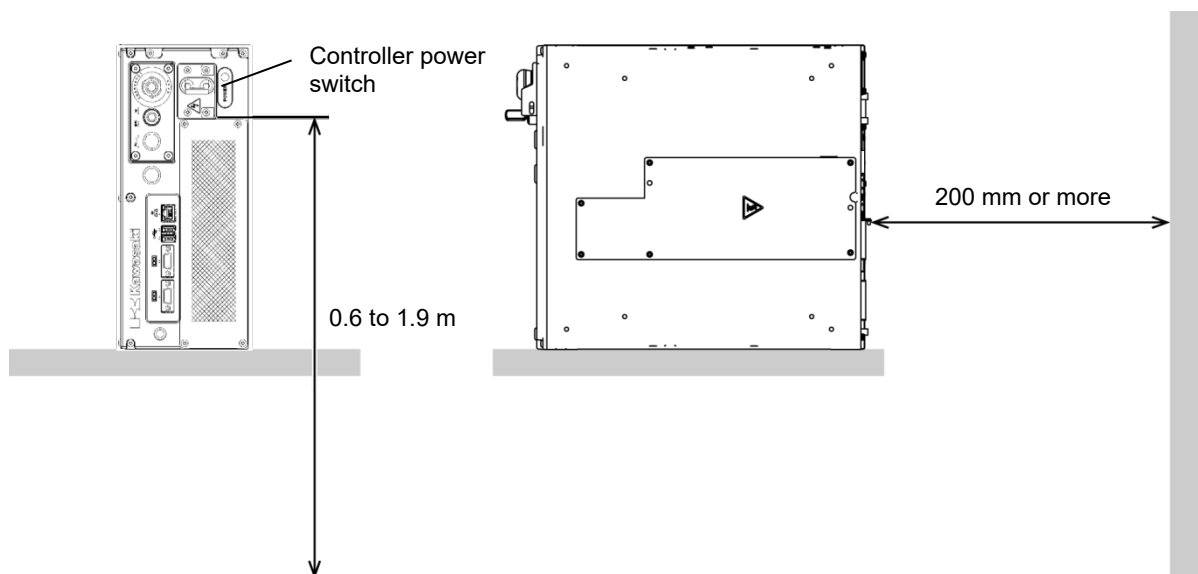
### ■ Precautions

- An object cannot be placed on the top surface of the controller when the controllers are placed vertically.
- When placing the controllers vertically, fix them with the screws, etc. For more details on fixing method, refer to “5.3 Tap Position on the Side of Controller.”

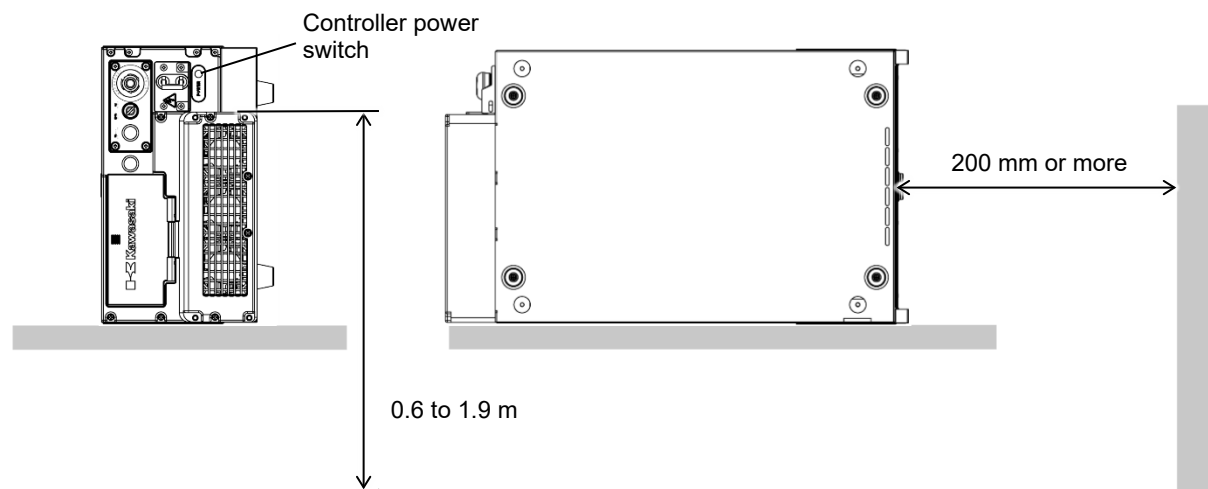
### ■ Locations

- Arrange the controller on a flat, horizontal stand and adjust its height so that the heights of controller power switch and operation switches from the floor are between 0.6 to 1.9 m.
- Arrange the controller with its controller power switch facing upward.
- Provide a clearance of 200 mm or more between the controller rear side and the wall.

Standard open specification



Sealed specification



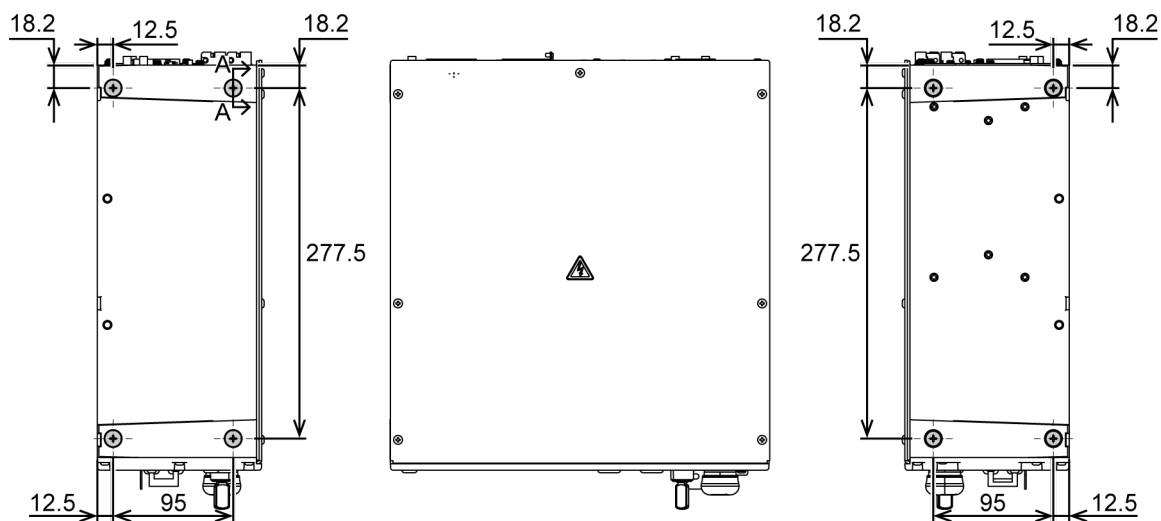
### 5.3 Tap Position on the Side of Controller

When using the tapped holes below, be careful so that bolts do not interfere with internal parts.

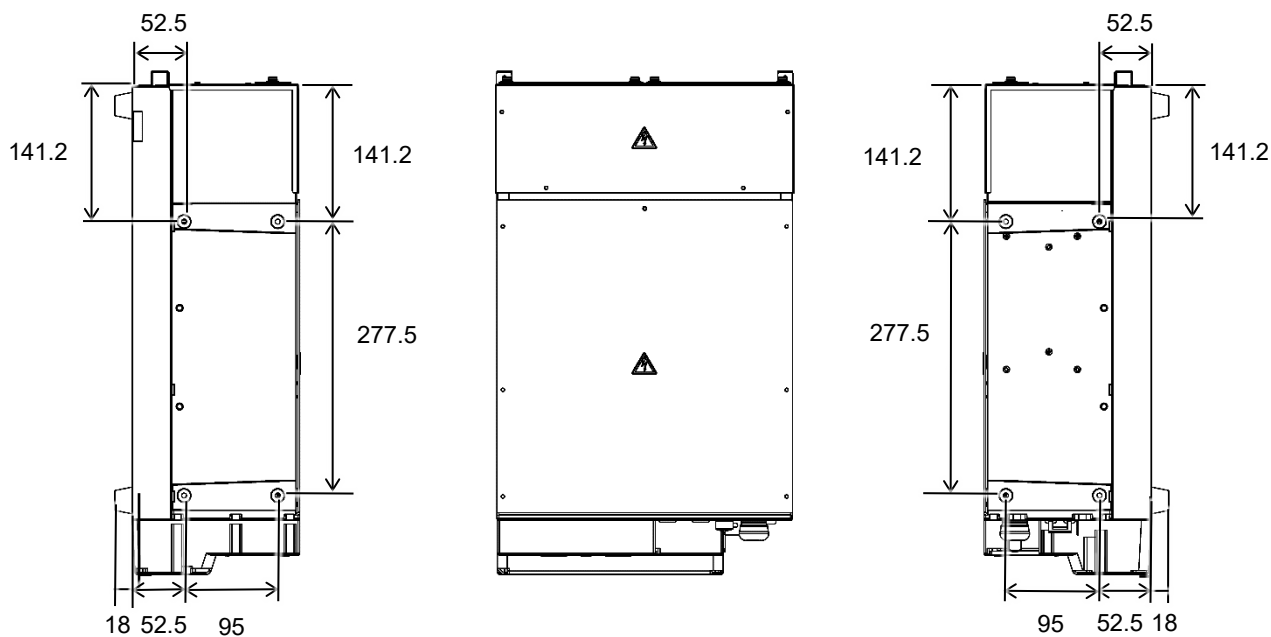
See figures below for lengths of bolts to be used. (Tapped size: M5)

#### ■ F60 controller

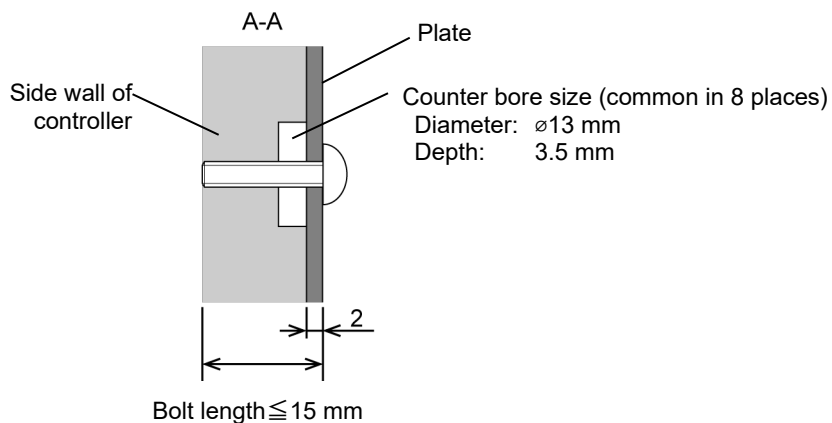
- Standard open specification



- Sealed specification



Example: The bolt length is 15 mm or less when fixing the controller on the plate whose thickness is 2 mm.

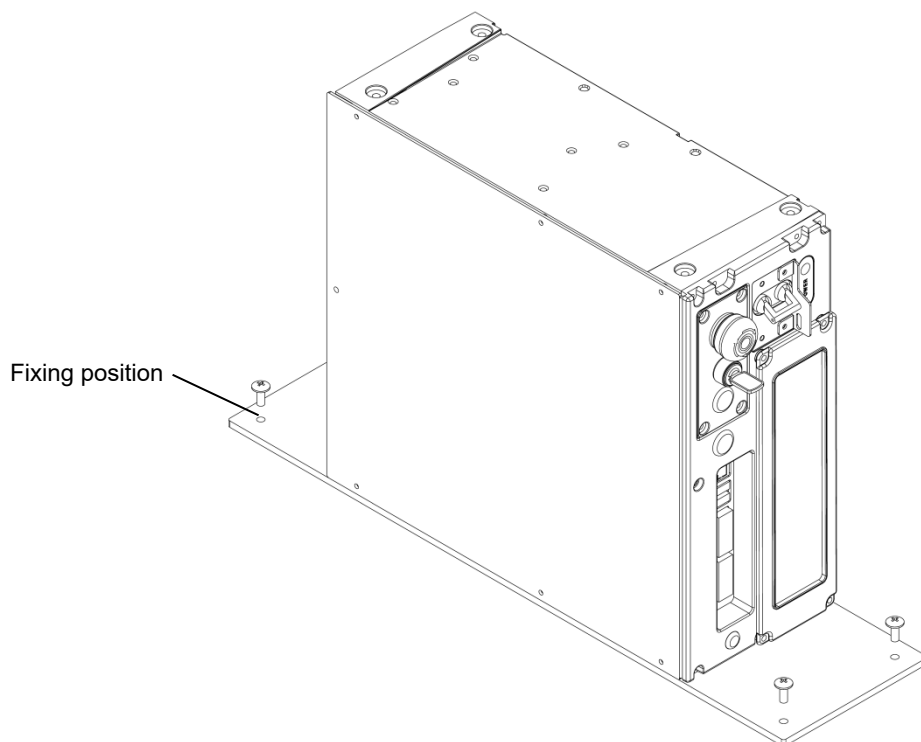


Example: Controller fixing method

**[NOTE]**

When using a controller that is placed vertically, put a mark or a label at the fixing position of the metal plate where the controller is mounted so that the fixing position can be identified easily.

Use a metal plate and fixing screws that have sufficient strength.



## 6 Connection Instructions

### 6.1 Connection between Controller and Robot

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



#### **WARNING**

**In order to prevent electric shock accidents, do not connect the external power until connections between the robot and the controller are complete.**





### CAUTION

1. Do not mistake the destination of connectors when connecting the harnesses. Forcing to connect the harness wrongly may damage connectors or cause a break in the electrical system.
2. Prevent people or equipment (forklift etc.) from stepping on or riding over the harnesses. Otherwise, the harness may become damaged or the electrical system may break.
3. Separate the harnesses from any nearby high voltage lines.
  - (1) Do not run the harnesses in parallel with other power lines.
  - (2) Do not bundle the harnesses.
  - (3) Separate the harnesses for 1 m or more from any nearby high voltage/high current power lines. Otherwise, the noise is generated from power lines and will cause malfunctions.
4. Even when the harnesses are long, do not bundle them winded or bended. Bundling the harness causes the heat to build up in the harness, resulting in over-heat and furthermore may cause fire.
5. Separate the motor harness from the communication and sensor cables, and distribute the lines.
  - (1) Do not run the harnesses in parallel with cables.
  - (2) Do not bundle the harnesses.
6. Connect the communication and sensor cables using shield mesh wire that includes twisted pair lines and connect the mesh wire properly. Otherwise, PWM noise may penetrate into various cables, such as communication cable and cause communication errors.
7. Separate the welder secondary cable from the robot's signal harness. Do not wire them in the same duct.
8. Strictly observe the following precautions so that PWM noise generated from the motor harness (power line) does not interfere with control signal lines.
  - (1) Separate the power and signal lines.
  - (2) Use the shortest length for the power line.
  - (3) Do not bundle or run the harnesses in parallel with the signal line.
  - (4) Do not wire the power and signal line within the same duct/conduit.
  - (5) Set and secure a firm ground line connection for the controller.

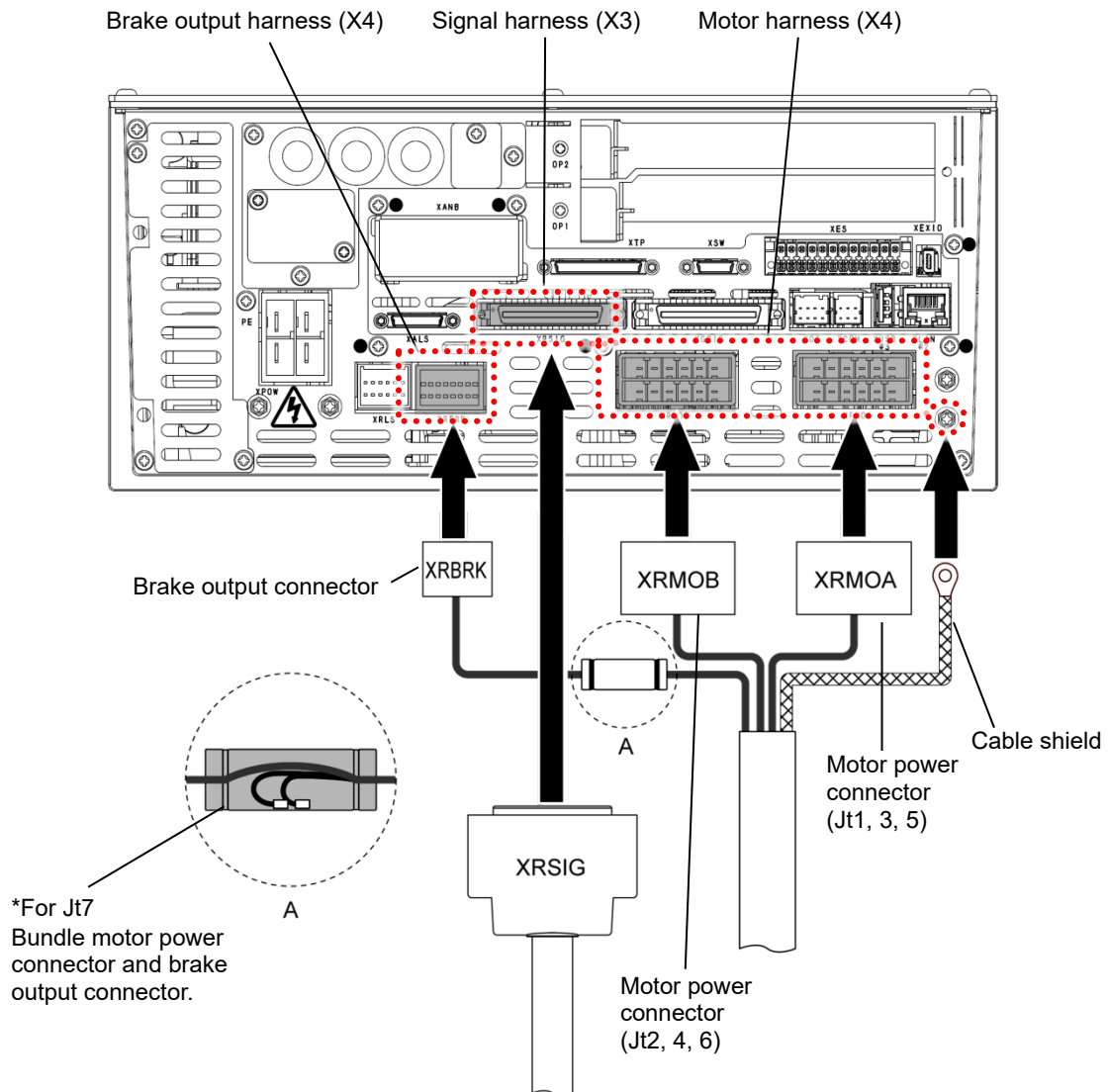
■ **Connecting place**

Connect the separate harnesses to their designated ports as shown below.

**CAUTION**

1. **Fix each connector securely. The robot may malfunction if connectors detach.**
2. **When placing a controller on another controller, connect the separate harnesses so that they do not block the exhaust port of the bottom controller.**

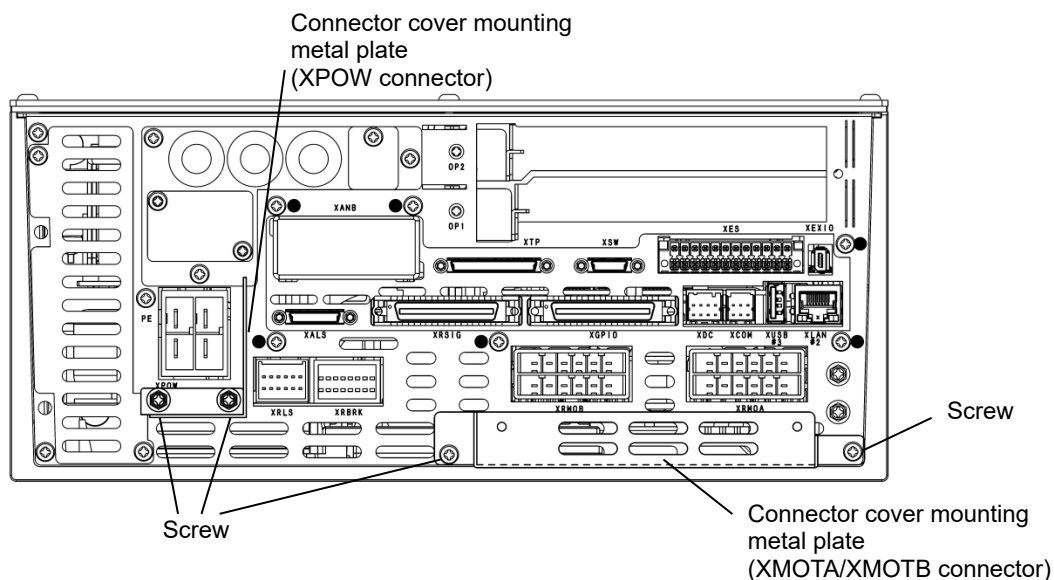
• Controller side



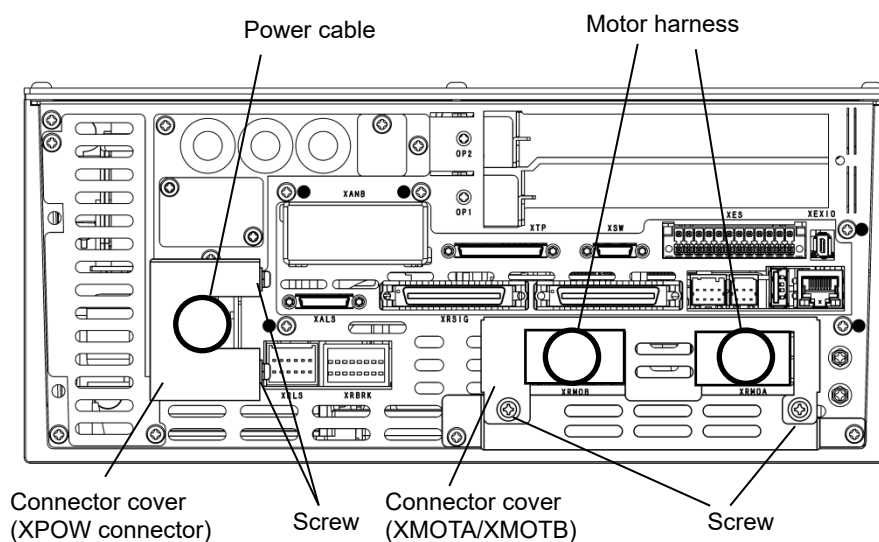
To make the standard F60 open structure controller comply with the UL standard, attach the connector covers in the rear of the controller, following the instructions below.\*

\* The F60 sealed specification controller does not require the connector cover.

1. Attach the connector cover mounting metal plates to the rear of the controller.

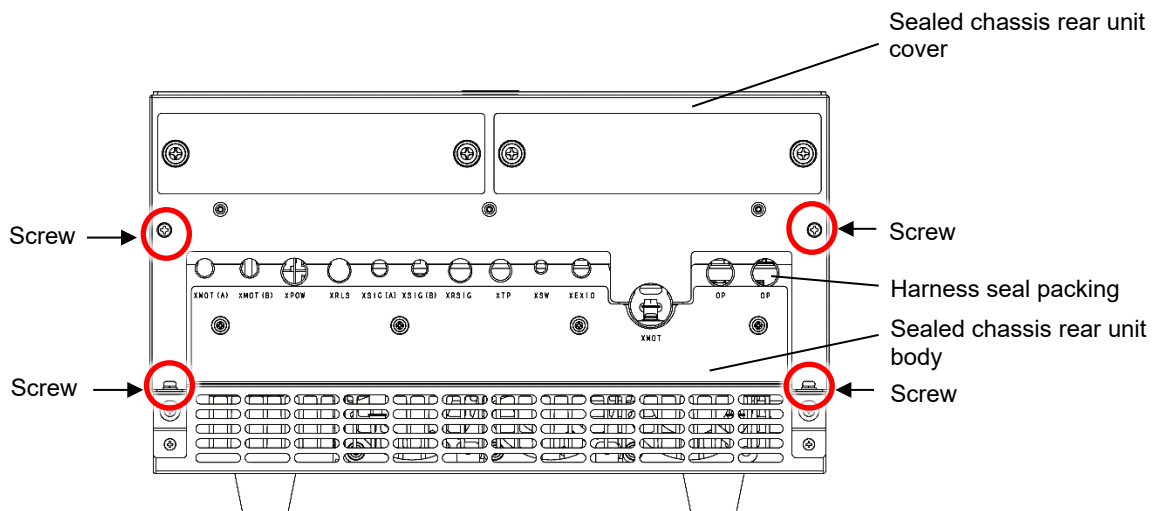


2. Insert the connectors of the motor harnesses and power cable into the controller.
3. Attach the connector covers.

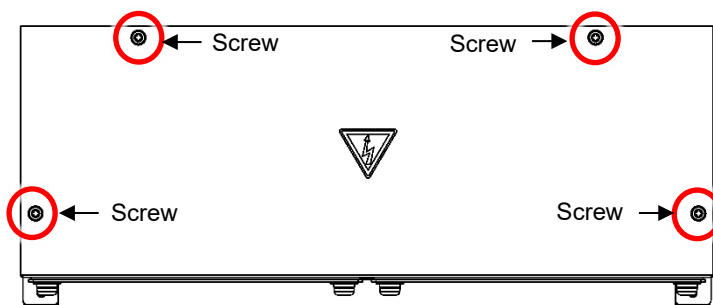


Connect the harnesses for the F60 sealed specification, following the instructions below.

1. Connect the harnesses following the procedure below.
  - (1) Remove the eight rear unit cover fixing screws of the sealed chassis, and remove the cover.
  - (2) Connect the harness connectors to the controller body.
  - (3) Secure the harnesses to the harness seal packing in the sealed chassis rear unit body.
  - (4) Attach the sealed chassis unit cover and secure it with the eight screws.

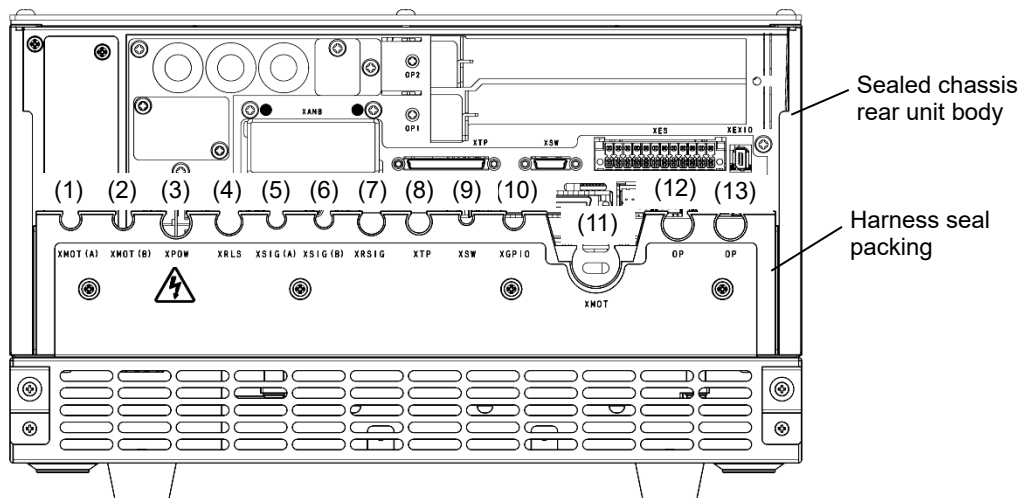


Front view of sealed chassis rear unit body



Top view of sealed chassis rear unit body

2. Secure each harness at the predetermined location of the harness seal packing of the sealed chassis rear unit body as shown in the figure below.



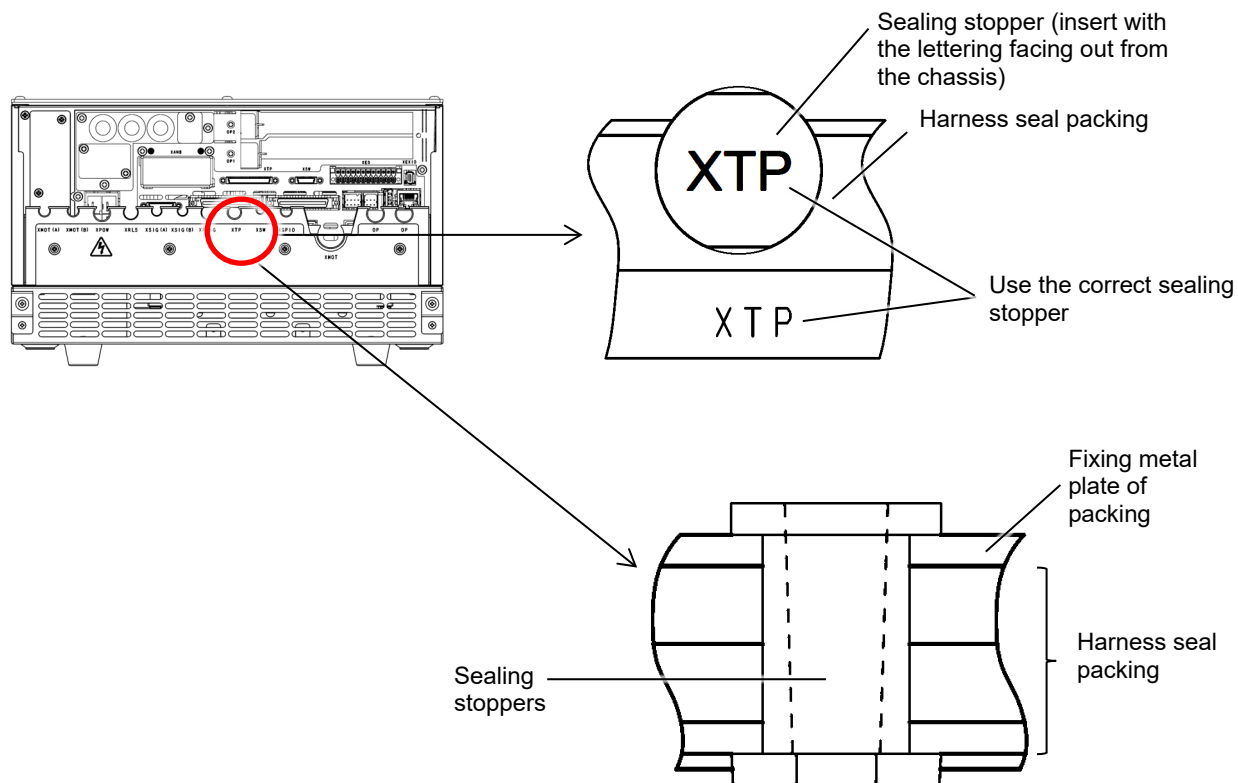
No.	Symbol	Harness name	Specified cable diameter
1	XMOT (A)	External axis (JTA) motor harness	8.1±0.5 mm
2	XMOT (B)	External axis (JTB) motor harness	8.1±0.5 mm
3	XPOW	Power cable	11.4±0.4 mm
4	XRLS	Brake release harness	10.3±0.8 mm
5	XSIG (A)	External axis (JTA) signal harness	7.3±0.2 mm
6	XSIG (B)	External axis (JTB) signal harness	7.3±0.2 mm
7	XRSIG	Arm signal harness	10.3±0.3 mm
8	XTP	TP cable	A-type: 9.4±0.5 mm B-type: 7.6±0.5 mm
9	XSW	External operation panel cable	5.6±0.4 mm
10	XGPIO	General I/O signal cable	8.1 ± 0.5 mm <sup>*2</sup>
11	XMOT	Arm motor harness	19.1±0.5 mm
12 <sup>*1</sup>	OP		12 ± 0.5 mm <sup>*2</sup>
13 <sup>*1</sup>	OP		12 ± 0.5 mm <sup>*2</sup>

Specification for cables provided by KHI

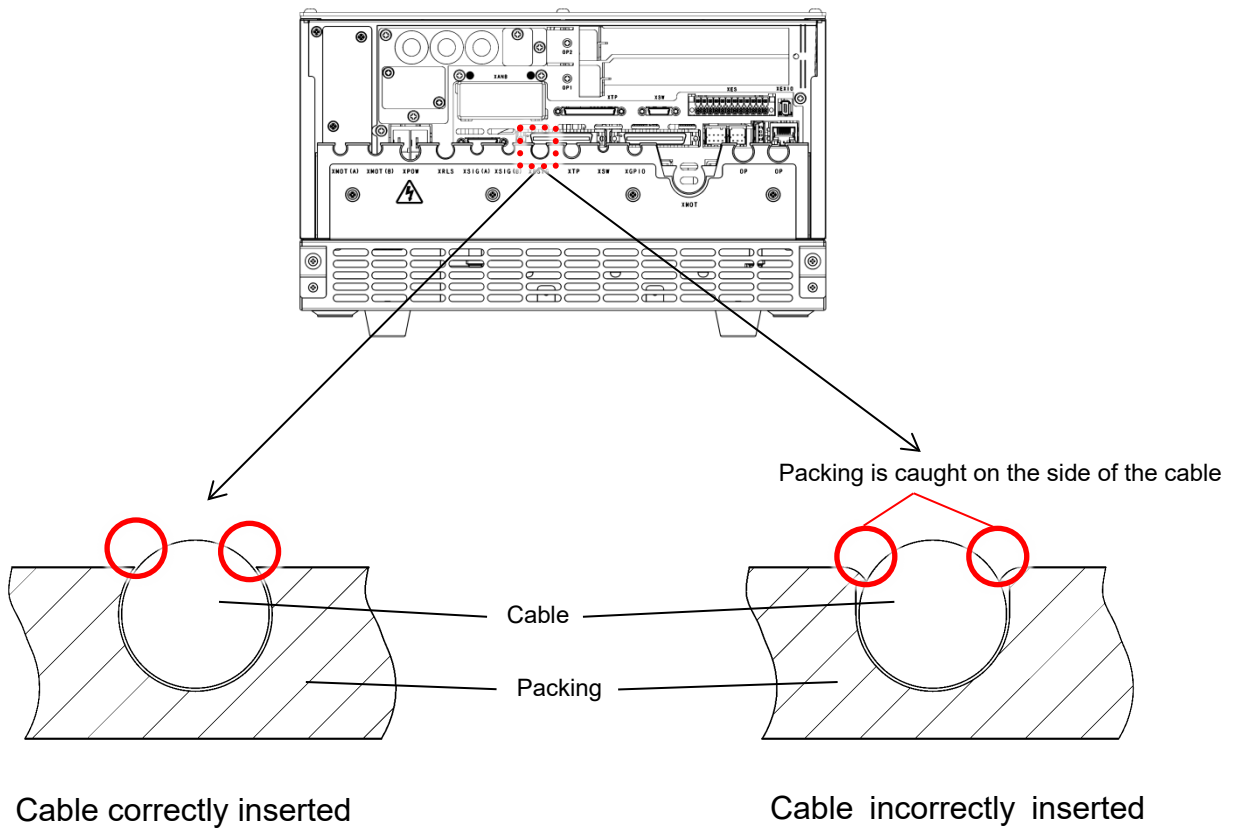
\*1 Use for options other than those listed above

\*2 Use cables with the specified cable diameter listed.

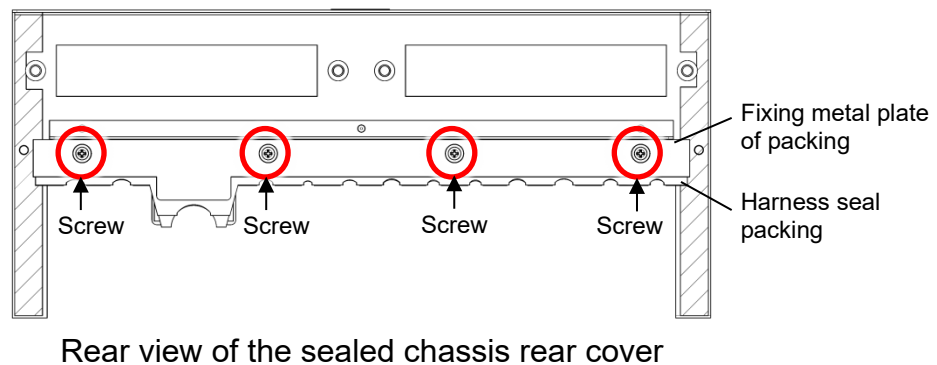
If there is any unused harness in the list above, fit a plastic sealing stopper provided as an accessory into the harness seal packing for the unused harness. The sealing stoppers have the harness codes written on them so that the right stoppers can be placed in the right attachment points. See below for how to insert the sealing stoppers.



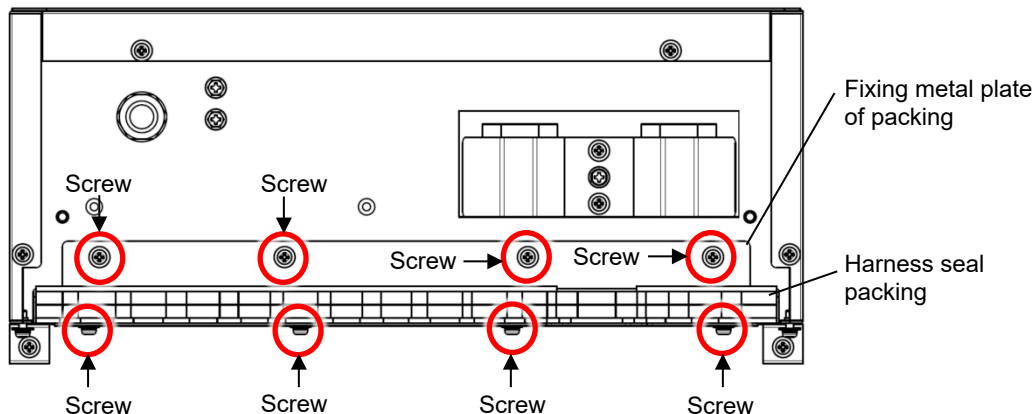
3. When securing each harness to the harness seal packing of the sealed chassis rear unit body, be careful that the packing has not caught on the side of the cable as shown below.



4. When removing the harness from the harness seal packing for replacement or other reasons after the harness has been attached in the sealed chassis rear unit body, replace the harness seal packing with a new one, following the procedure below.
  - (1) Remove the four screws from the harness seal packing fixing metal plate, and replace the harness seal packing with a new one.

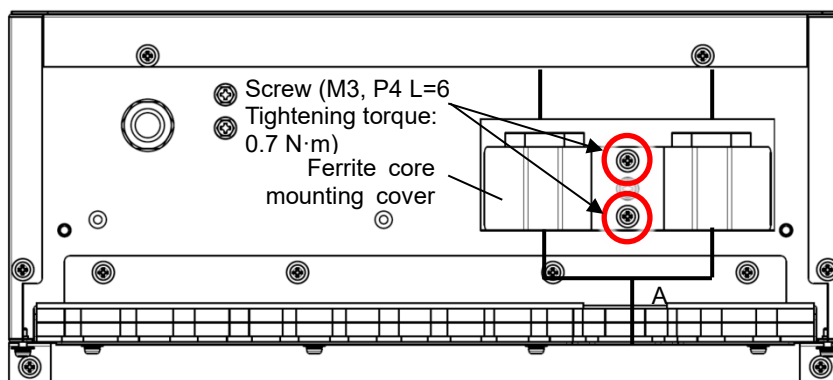


- (2) Remove the eight screws from the harness seal packing fixing metal plate of packing, and replace the harness seal packing with a new one.

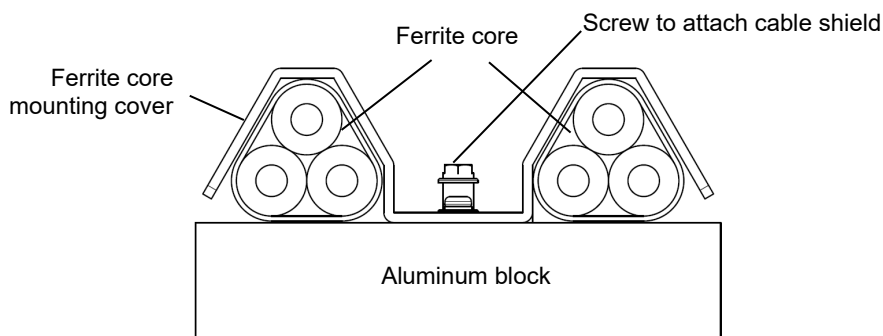


Top view of sealed chassis rear unit body

5. Secure the ferrite core on the XMOT harness in the correct position as shown the figure below.



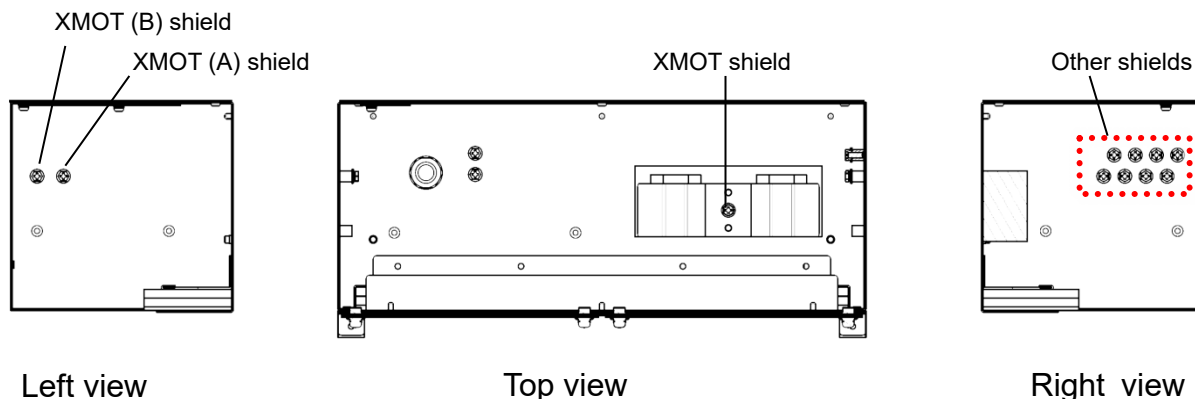
Top view of sealed chassis rear unit body



View A



6. Use the positions shown below to attach the harness shield terminals to the controller.

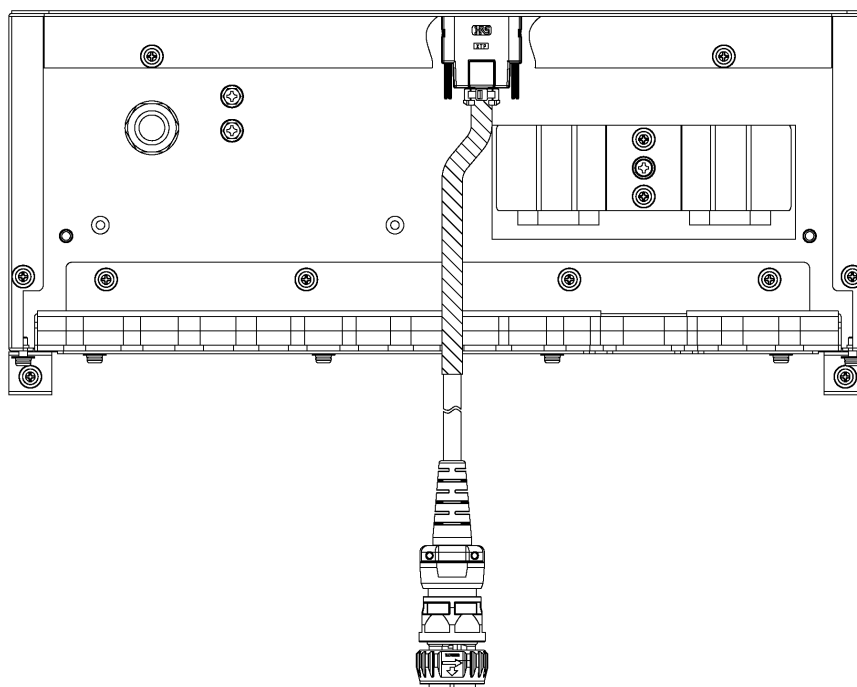


Expanded view of sealed chassis rear unit body

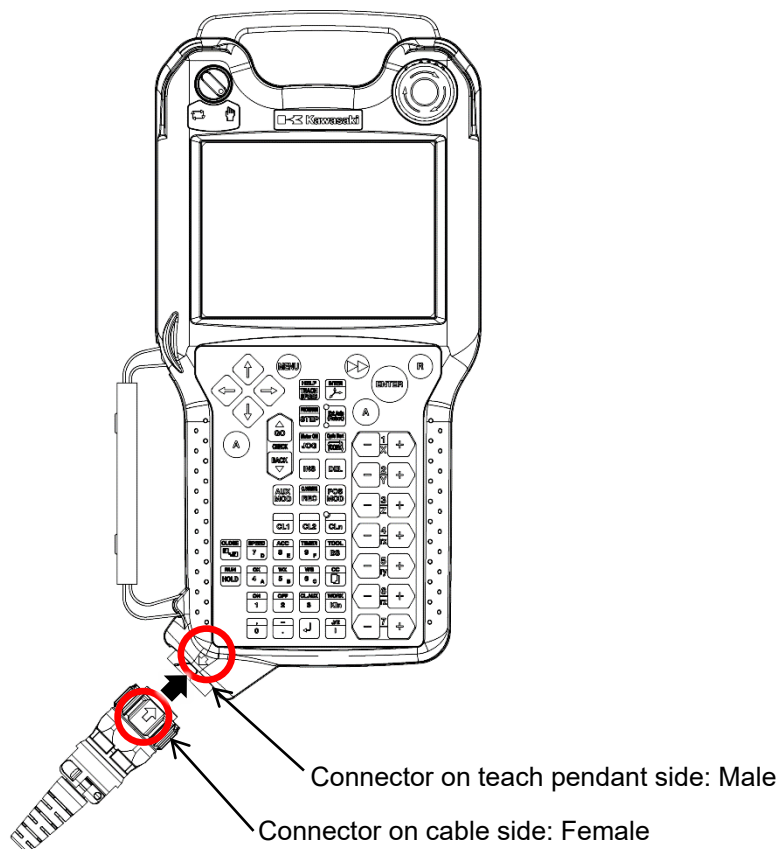
**⚠ CAUTION**

**Read the precautions carefully before attaching separate harnesses.  
 If attached incorrectly, dirt and dust, etc., could get into the controller  
 and cause malfunction or breakdown.**

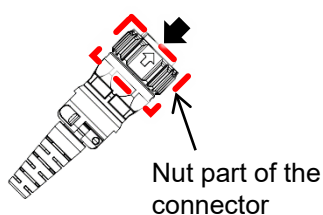
7. Only the B-type XTP harness cable has a cable diameter adjustment tube at the shaded area in the figure. Pull the harness straight out as shown in the figure to ensure the sealability of the harness section.



Connect the other XTP harness connector to the teach pendant connector. Do so by aligning the arrow on the teach pendant with the arrow on the connector and inserting the connector.



When removing the connector, hold the nut part of the connector and rotate approximately 45 degrees counterclockwise. Release the lock, then pull the connector straight out.



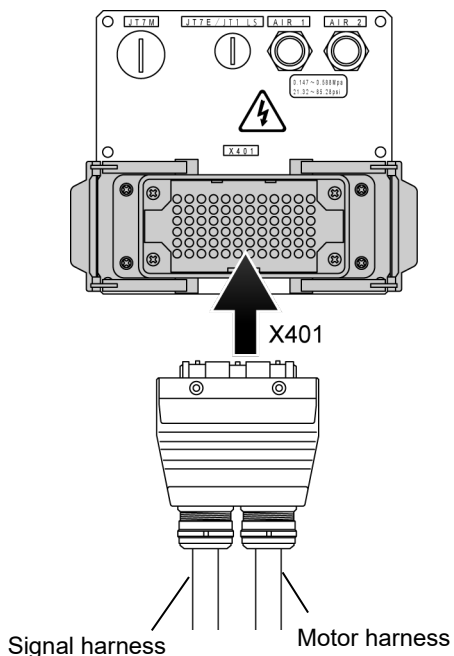
**[NOTE]**

Do not twist the connector further when the lock is released, or forcibly pull the connector before the lock is released. Doing so could damage the connector.

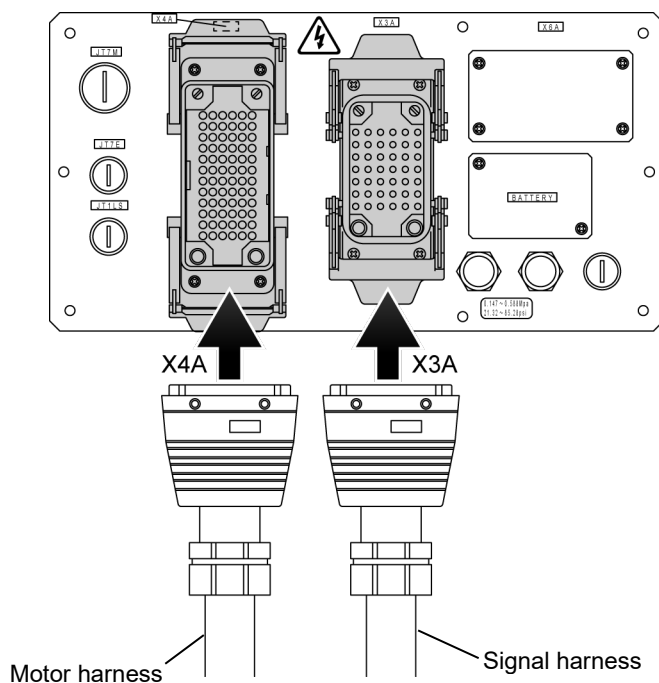
Rotating the nut part of the connector 90 degrees or more may damage the connector. Please contact Kawasaki for repairs.

- Arm side
  - Cable diameter  
 Motor harness: 18.6 to 19.6 mm, Signal harness: 10.0 to 10.6 mm

**R series: 003N/005N/005L**

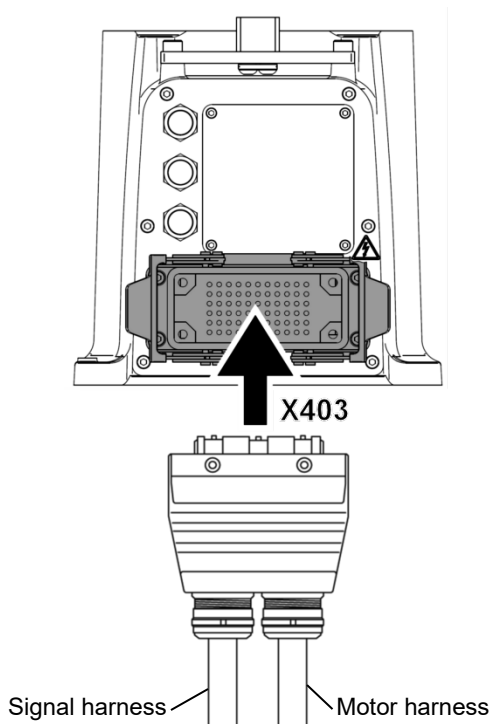


**R series: 010N/006L**

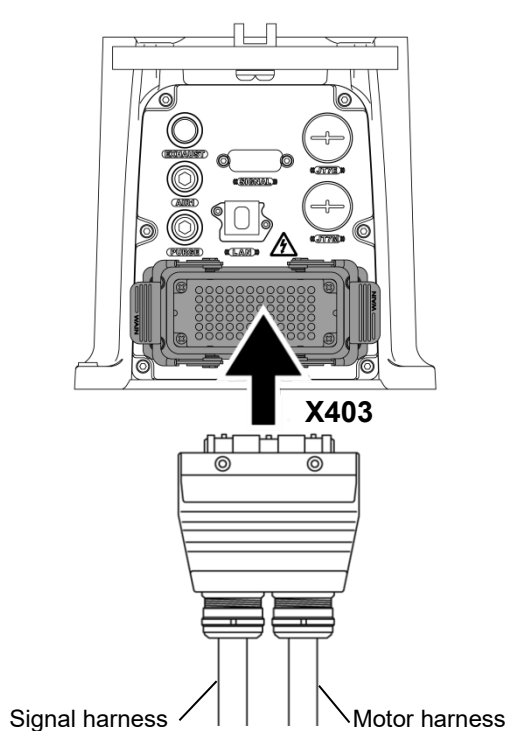


**R series: 007N/007L**

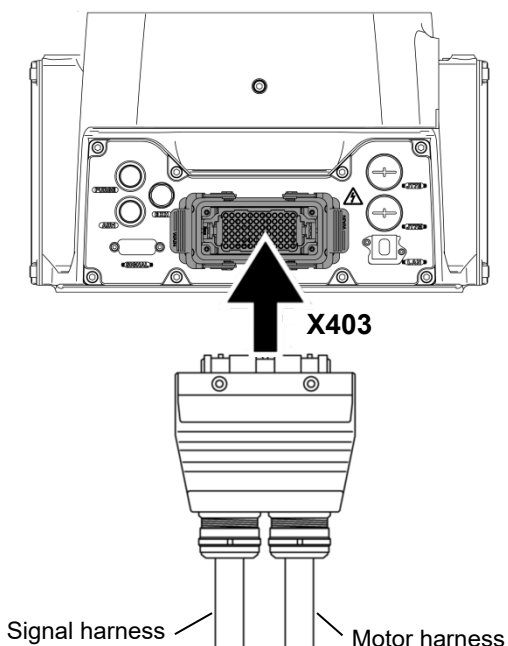
• **RS007N-A/RS007L-A**



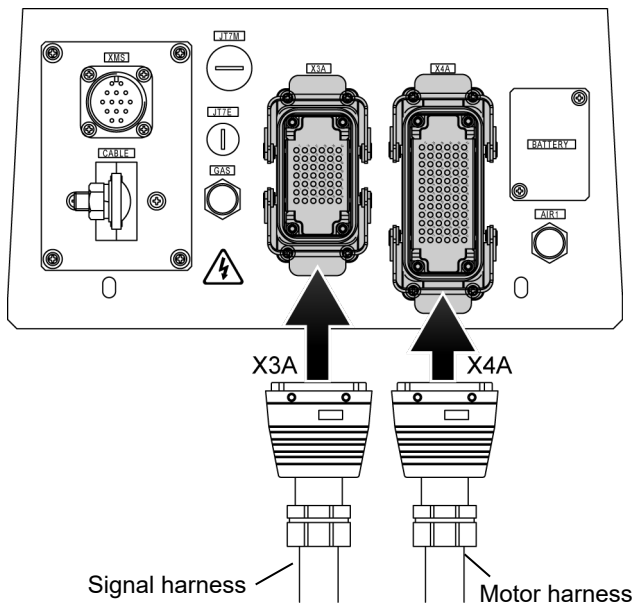
• **RS007N-B/RS007L-B**



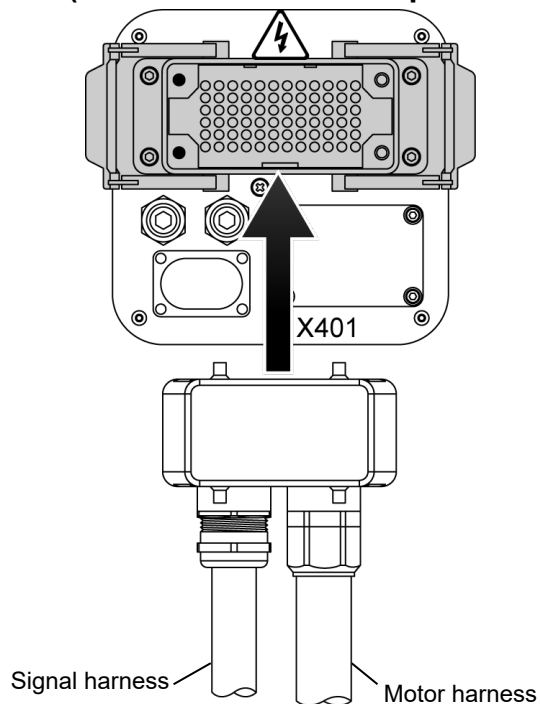
**R series: 013N**



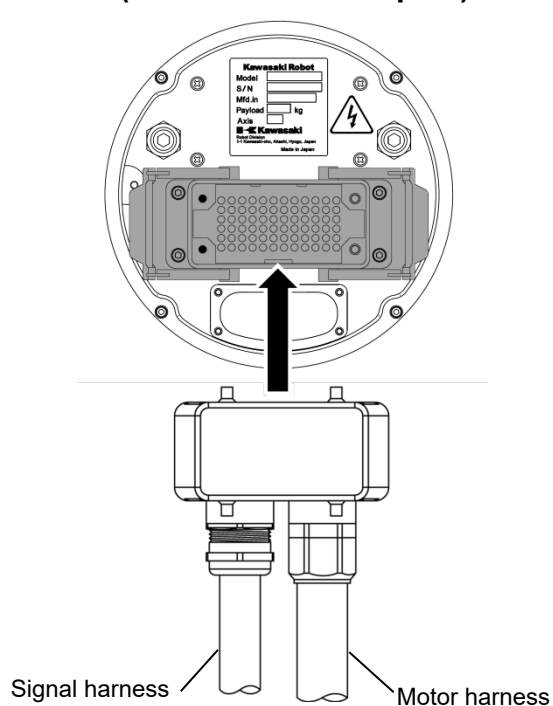
**BA**



**MC (Backside connector spec.)**



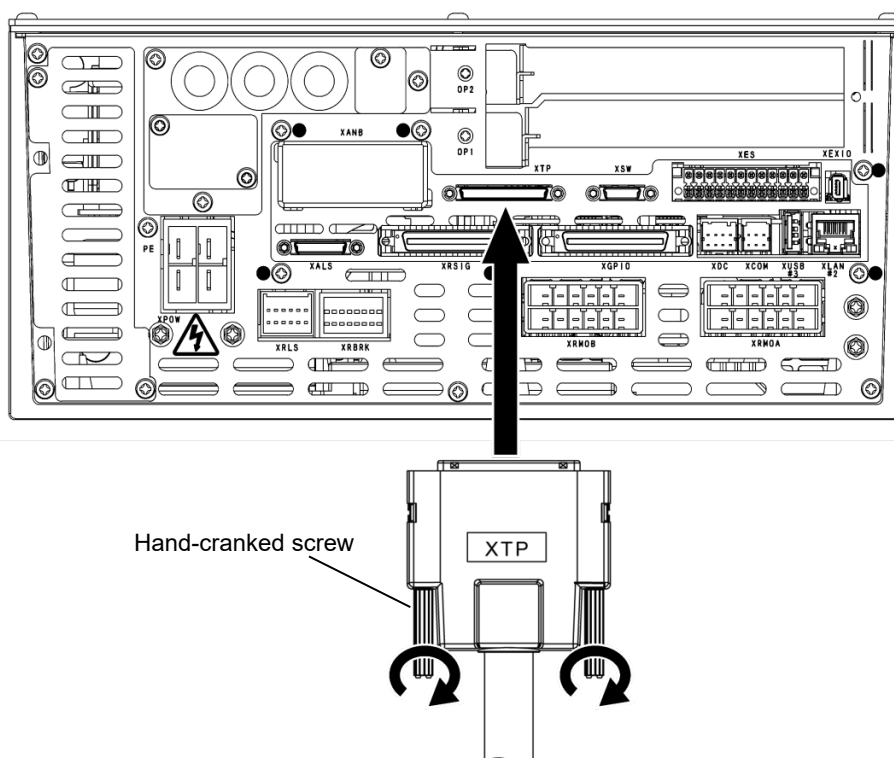
**MC/MS (Base connector spec.)**



## 6.2 Connection between Controller and TP

Connect the TP cable to the controller.

1. Insert the TP cable to the connector (XTP).
2. Turn right/left hand-cranked screws in a clockwise direction, and lock them securely.

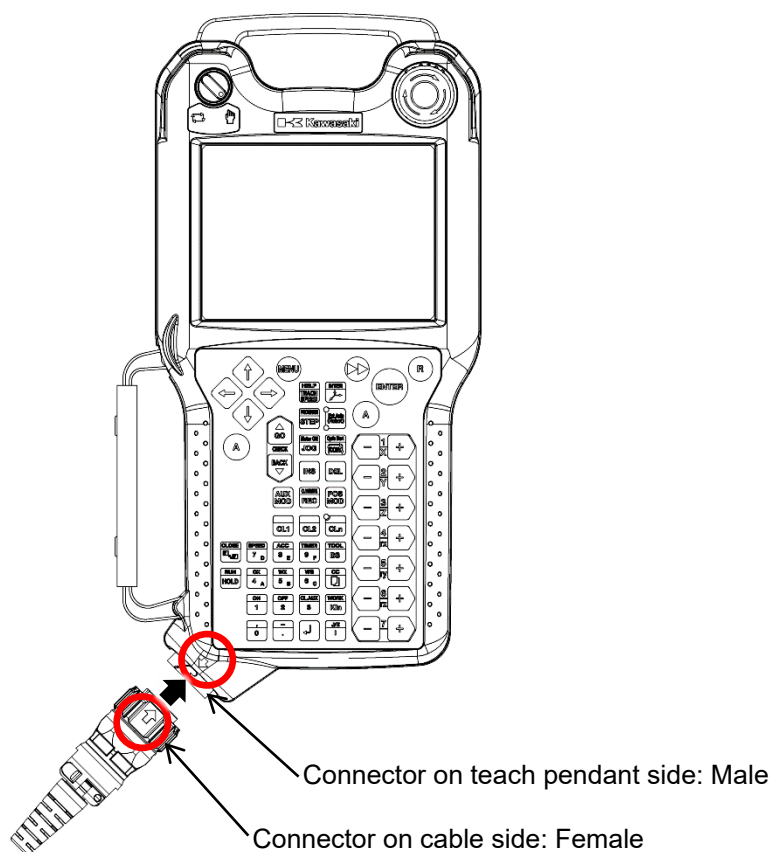


3. In case of the sealed specification, read the precautions for connecting the harnesses for the sealed chassis controller given in “6.1 Connection between Controller and Robot” carefully before connecting the cables.

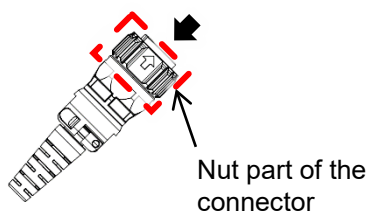
**⚠ CAUTION**

1. If the hand-cranked screws on the right and left side of the XTP connector are loose, a TP screen display error or other failure can result.
2. Do not hot-swap the XTP connectors. Hot-swapping could damage the circuit board.

For B-type only, connect the other XTP harness connector to the teach pendant connector. Do so by aligning the arrow on the teach pendant with the arrow on the connector and inserting the connector.



When removing the connector, hold the nut part of the connector and rotate approximately 45 degrees counterclockwise. Release the lock, then pull the connector straight out.



[NOTE]

Do not twist the connector further when the lock is released, or forcibly pull the connector before the lock is released. Doing so could damage the connector.

Rotating the nut part of the connector 90 degrees or more may damage the connector. Please contact Kawasaki for repairs.

## 7 Connection of External Power

Strictly observe the following precautions when connecting the external power.



### DANGER

1. Before connecting the external power, confirm that the external power supply for the controller is cut off at the source. Connecting components while power is supplied may cause electric shock.
2. To prevent external power from being turned ON accidentally, tag the breaker and indicate clearly that work is in progress. Or, assign a supervisor in front of the breaker until the connection is complete.



### WARNING

1. Confirm that the connected supplying power to the controller meets specifications shown on the rating plate. Supplying out-of-specification power will damage electric components in the controller.
2. Ground the controller to prevent against electrical shock and noise without fail.
  - (1) Dedicated ground:  
Dedicated class D grounding with a resistance of 100  $\Omega$  or less
  - (2) Recommended power cable size:  
Ground wire which is 2.0 mm<sup>2</sup> or more (AWG #14 or more)
3. Never share a ground line with workpiece to be welded or another machine (weld machine, etc.).
4. Strictly observe the following precautions when conducting the arc welding.
  - (1) Connect the minus pole of the weld power supply to a jig or directly to workpiece to be welded.
  - (2) Insulate the robot body and controller so that they do not share a common ground line.
5. Before turning ON the external power to controller, make sure the power supply wiring is complete and all the covers are attached properly. Failure to do so may cause electric shock.

! **CAUTION**

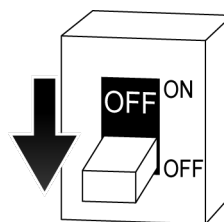
1. Prepare external power that meets the specifications of the controller in terms of momentary power interruption, voltage fluctuation, power capacity, etc. Supplying out-of-specification power is connected, the power monitoring circuit activates cutting off the power, and an error may be returned.
2. If the external power emits a lot of electrical noise, set up a noise filter to reduce the interference.
3. Confirm that there are no low noise-resistant devices in the vicinity beforehand. PWM noise generated from robot motor lines may cause malfunction of the devices via external power line.
4. Install a separate external power switch (breaker) for the robot, independent and unconnected to the other device such as weld machine.
5. To prevent shorting or accidental leakage on the external power switch, install a time delay type ground leakage breaker (sensitivity of 100 mA or more.).
6. If there is a possibility that surge voltage such as lightning surge might be applied from external power line, decrease the surge voltage level by mounting a surge absorber, etc.
7. Use the surge protective device (SPD) that conforms to NFPA79.

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

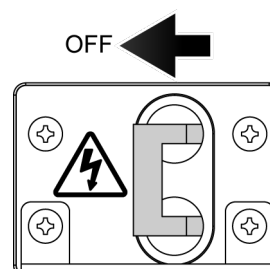
### ■ Operating procedure

Follow the procedure below when connecting the external power.

1. Turn OFF the external power for the controller.

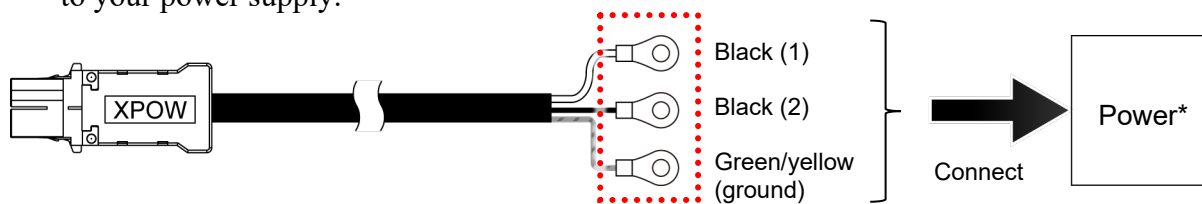


2. Turn OFF the CONTROLLER POWER.





- Process the tip of attached power cable to be connected to F60 controller, and connect it to your power supply.

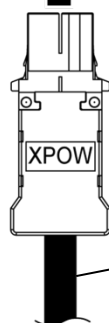
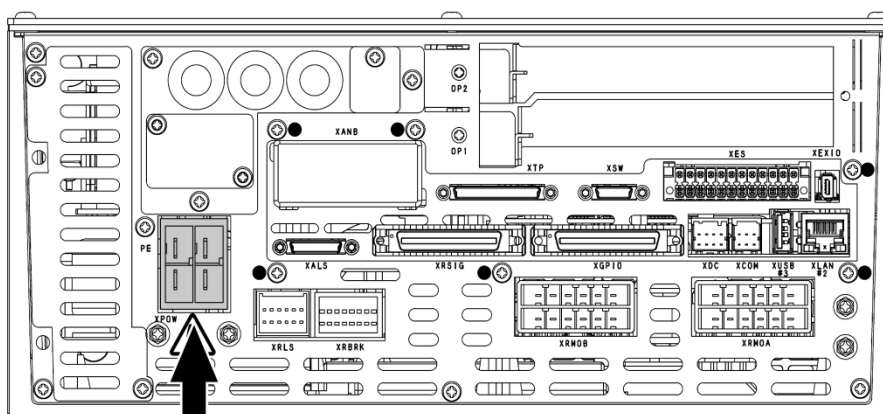


\* Provided by users.

**CAUTION**

**Confirm current requirements and select a power cable with adequate capacity when using cables other than the attached power cable. For details, see “3 Appearance and Specifications of Robot Controller.” For connector models, see “3.3 F60 Controller Specifications.” If the wire is too small in diameter, the voltage may drop or the cable may overheat.**

- Connect the power cable to the XPOW connector of the controller.
  - Black (1), black (2): Single-phase power supply (AC200-230 V ± 10%)
  - Green/yellow: Groud



Cable diameter suitable for the packing for the F60 sealed specification:  
11.4 mm ± 0.4 mm

**CAUTION**

**Conduct grounding when the power is connected without fail. Failure to do so may cause electric shock when a ground leakage occurs.**

## 8 Connection of Peripheral Control Equipment

Refer to “External I/O Manual” for details of the connecting method.

### 8.1 Precautions When Connected

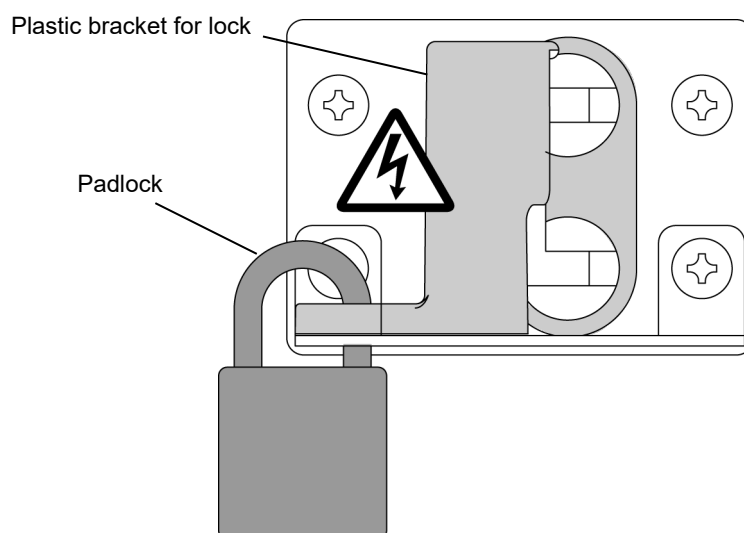
**⚠ DANGER**

1. Before connecting the external I/O, confirm that power supply to the controller and peripheral equipment are cut off. Connecting components while power is supplied may cause electric shock.
2. To prevent breaker from being turned ON, tag the breaker and indicate clearly that work is in progress. Or, assign a supervisor in front of the breaker until the connection of the external I/O is complete.

#### ■ Countermeasures to prevent the controller power from being turned ON during operations

Target: F60 controller

Lock by attached plastic bracket and padlock (user arrange).





### CAUTION

1. **Take the necessary countermeasures noise on equipment with external I/O connections to the controller. Electrical noise that interferes with the I/O signals may cause malfunction or damage to the electrical system.**
2. **Do not mistake pin Nos. on the connectors when connecting external I/O. Forcing to connect the external I/O connectors wrongly may damage connectors or cause a break in the electrical system.**
3. **Prevent people or equipment (forklift etc.) from stepping on or riding over the external I/O cable. Otherwise, the cable may become damaged or the electrical system may break.**
4. **Separate the external I/O cables and power lines by at least 20 cm not to wire the cables close together or in parallel with the power lines (either in or outside the controller). Noise may penetrate into the I/O cables and lead to malfunction.**
5. **Use a shield cable for the external I/O cable and connect the shield wire to the controller cabinet.**
6. **When connecting the external I/O cables to connectors or terminals, fix them with tying bands in the harness support set on the top of the controller, preventing them from excessive force.**
7. **Install the seal connector so that external I/O cables never cause insulation failure or disconnection at the inlet.**

## 8.2 Connection of General Purpose Signal

Refer to “External I/O Manual” for details of connection.

Read the precautions for connecting the separate harness for the sealed specification given in “6.1 Connection between Controller and Robot” carefully before connecting a general purpose signal to the chassis of the F60 sealed specification.

Use cables with a diameter of 8.1 mm ± 0.5 mm.

## 8.3 Connection of Hardware Dedicated Signal

It is possible to construct a safety circuit using the hardware circuit by connecting the external emergency stop signal or hold signal line to the XES terminal connector on the back board.

Refer to “External I/O Manual” for details of connection.

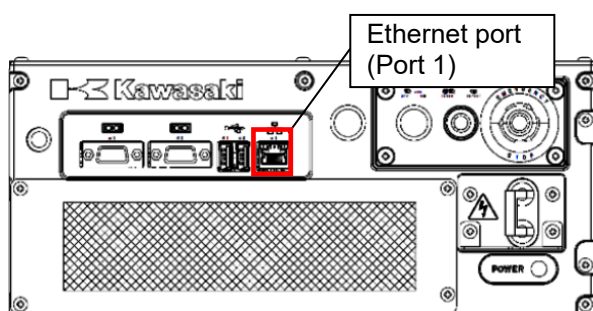
Read the precautions carefully for connecting the separate harness for the sealed specification given in “6.1 Connection between Controller and Robot” before connecting a general purpose signal to the chassis of the F60 sealed specification.

Use cables with a diameter of 8.1 mm ± 0.5 mm.

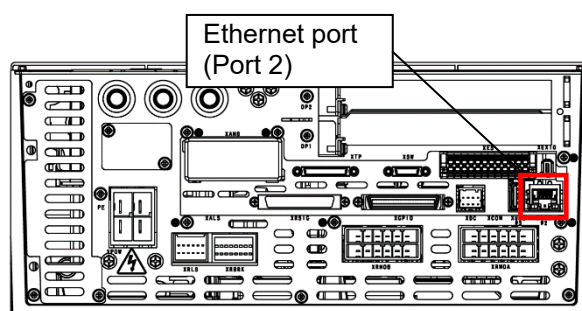
## 8.4 Safety Signal Connection (F60 B-type Only)

For details of connecting using safety I/O board, see the “External I/O Manual” and “CoreCubic-S Instruction Manual.”

When connecting safety network devices and Ethernet/IP Safety, connect to the Ethernet port shown below. (Supported connector: RJ45 connector) For details of the settings, see the “CoreCubic-S Instruction Manual.”



Front of the controller (B-type)



Rear of the controller (B-type)

## 8.5 Connection of Personal Computer

A PC can be used as a terminal for the robot controller when connected.

Refer to “AS Language Reference Manual” for details.

- Connect a PC loaded with terminal software KRterm/KCwin32 to the RS-232C port in the accessory panel with RS-232C cable.
- Connect a PC loaded with KRterm/KCwin TCP/IP to the Ethernet port on the accessory panel with Ethernet cable.

## 8.6 Connection of RS-232C Serial Signal (Option)

Data communication is possible with the host computer when the host computer is connected to the RS-232C port in the accessory panel with an RS-232C cable. Refer to the “Communication Option Manual” for details.

## 8.7 Connection of Ethernet Communication Signal

It is possible to build an Ethernet LAN of 10BaseT/100BaseTX/1000BaseT using the Ethernet port in the accessory panel. Refer to the “Communication Option Manual” for details.

## 8.8 Connection of Fieldbus (Option)

Adding the optional fieldbus communication module on the rear XAB connector enables communication with peripheral devices such as DeviceNet on the fieldbus. Refer to the “General Fieldbus I/O Usage Manual” for details.

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**Kawasaki Robot Controller** F Series Controller  
Installation and Connection Manual

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