

ROBOTICS

Product specification

IRB 390



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Product specification

IRB 390 - 15/1300

IRB 390 - 10/1300

IRC5

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Revision: J

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Original instructions.

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Overview of this manual

About this manual

This manual contains instructions for:

- mechanical and electrical installation of the robot
- maintenance of the robot
- mechanical and electrical repair of the robot.

Usage

This manual should be used during:

- installation, from lifting the robot to its work site and securing it to the foundation, to making it ready for operation
- maintenance work
- repair work and calibration.

Who should read this manual?

This manual is intended for:

- installation personnel
- maintenance personnel
- repair personnel.

Prerequisites

A maintenance/repair/installation craftsman working with an ABB Robot must:

- be trained by ABB and have the required knowledge of mechanical and electrical installation/repair/maintenance work.

References

Documentation referred to in the manual, is listed in the table below.

Document name	Document ID
<i>Product manual, spare parts - IRB 390</i>	3HAC066567-001
<i>Product manual - IRB 390</i>	3HAC066566-001
<i>Product specification - Controller IRC5</i> IRC5 with main computer DSQC1000.	3HAC047400-001
<i>Product specification - Controller software IRC5</i> IRC5 with main computer DSQC1000 and RobotWare 6.	3HAC050945-001
<i>Technical reference manual - System parameters</i>	3HAC050948-001
<i>Technical reference manual - Lubrication in gearboxes</i>	3HAC042927-001
<i>Circuit diagram - IRB 390</i>	3HAC060545-009

Revisions

Revision	Description
A	First edition.

Continues on next page

Revision	Description
B	Published in release 21A. The following updates are made in this revision: • Minor changes.
C	Published in release 21B. The following updates are done in this revision: • Text regarding fastener quality is updated. • Updated the general description in Load diagrams section.
D	Published in release 21D. The following updates are done in this revision: • Modified the value for Performance according to ISO 9283. • Dimension changed in tool flange, see Mechanical interface of the tool flange.
E	Published in release 22B. The following updates are done in this revision: • New option 1584-1 Remote Brake Release added.
F	Published in release 22C. The following updates are made in this revision: • Updated dimension of attachment holes on delta unit mechanical interface for IRB 390-10/1300.
G	Published in release 22D. The following updates are made in this revision: • The general introduction for Load diagrams updated.
H	Published in release 25.3. The following updates are done in this revision: • Company name updated to reflect current legal entities. • Updated portal name from myABB to ABB Robotics One.
J	Published in release 26.1. The following updates are done in this revision: • Company name updated to reflect current legal entities.

1 Description

1.1 Structure

1.1.1 Introduction to structure

Robot family

The new IRB 390 FlexPacker™ can support customized packaging, vertical packing and high-speed, high-variation sorting and on demand order picking in logistics and e-commerce fulfillment centers.

The IRB 390 FlexPacker robot will be available as a four and five axis variant delta robot. It is 35 per cent faster than the IRB 360-8/1130 FlexPicker, with a 45 per cent increase in reachable volume and payload of up to 15 kg.

Designed for customers in Food & Beverage, logistics, pharmaceutical and consumer-packaged goods industries, the IRB 390 will be ideal for secondary packaging and higher payload applications, with the speed and flexibility to support Shelf Ready Packaging (SRP) and Retail Ready Packaging (RRP).

Operating system

The robot is equipped with the IRC5 controller and robot control software, RobotWare. RobotWare supports every aspect of the robot system, such as motion control, development and execution of application programs, communication etc. see *Product specification - Controller IRC5*.

Safety

Safety standards valid for complete robot, manipulator and controller.

Additional functionality

For additional functionality, the robot can be equipped with optional software for application support - for example gluing and welding, communication features - network communication - and advanced functions such as multitasking, sensor control etc. For a complete description on optional software, see *Product specification - Controller software IRC5*.

PickMaster® is a specific application software for vision guided picking with high speed conveyors. It provides a task-oriented programming and execution of random flow pick and place operations on the fly, see *Product specification - PickMaster® Twin*.

Hygienic compliance

All exposed surfaces are compliant with FDA regulations for incidental food contact. The gearboxes are lubricated with food grade oil of class NSF-H1 (H1 lubricants are food-grade lubricants used in food-processing environments where there is the possibility of incidental food contact.) All greases behind exposed seals, and recommended service greases, are NSF-H1 compliant materials

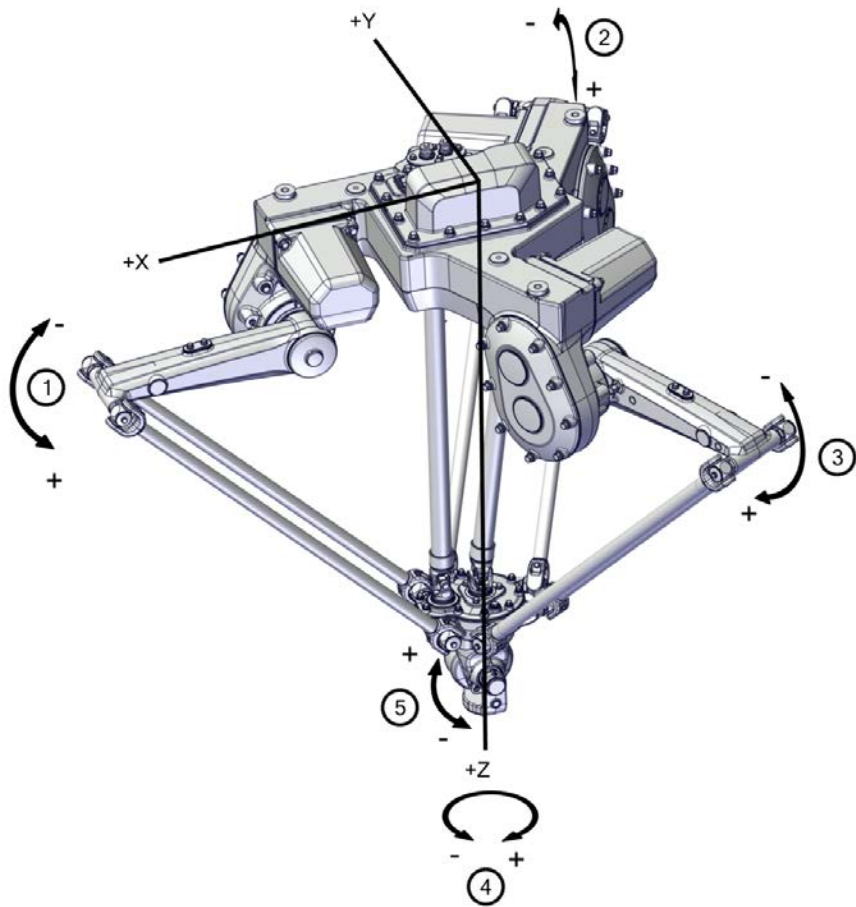
Continues on next page

1 Description

1.1.1 Introduction to structure

Continued

Robot axes



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Pos	Description	Pos	Description
1	Axis 1	2	Axis 2
3	Axis 3	4	Axis 4
5	Axis 5		

1.1.2 Different robot variants

General

The IRB 390 is available in two different variants.

Robot variants

The following different standard robot variants are available:

Robot variant	Handling capacity (kg)
IRB 390-15/1300	15 kg
IRB 390-10/1300	10 kg

1 Description

1.1.3 Technical data

1.1.3 Technical data

Weight, robot

The table shows the weight of the robot.

Robot model	Nominal weight
IRB 390	IRB 390 - 15/1300: 133 kg IRB 390 - 10/1300: 148 kg



Note

The weight does not include additional options, tools and other equipment fitted on the robot.

Mounting positions

The table shows valid mounting positions and the installation (mounting) angle for the manipulator.

Mounting position	Installation angle
Suspended in robot frame	0°

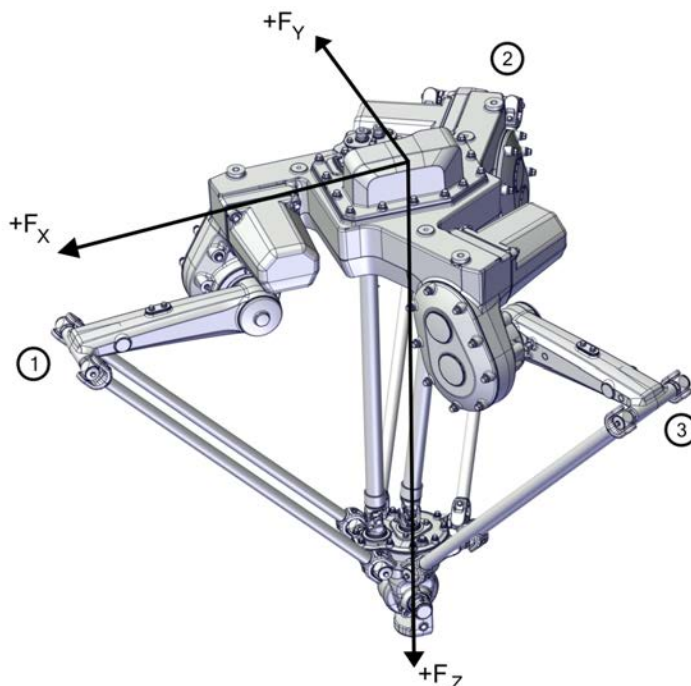


Note

The actual mounting angle must always be configured in the system parameters, otherwise the performance and lifetime is affected. See the product manual for details.

Continues on next page

Loads on foundation, robot



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The table shows the various forces and torques working on the robot during different kinds of operation.



Note

These forces and torques are extreme values that are rarely encountered during operation. The values also never reach their maximum at the same time!



WARNING

The robot installation is restricted to the mounting options given in following load table(s).

Suspended in robot frame

Force	Endurance load (in operation)	Maximum load (emergency stop)
Force xy	$\pm 1.8 \text{ kN}$	$\pm 4.0 \text{ kN}$
Force z	$1.4 \pm 0.6 \text{ kN}$	$1.4 \pm 1.9 \text{ kN}$
Torque xy	2.0 kNm	4.3 kNm
Torque z	0.6 kNm	1.2 kNm

Continues on next page

1 Description

1.1.3 Technical data

Continued

Requirements, foundation

The table shows the requirements for the foundation where the weight of the installed robot is included:

Requirement	Value	Note
Flatness of foundation surface	0.3 mm	Flat foundations give better repeatability of the resolver calibration compared to original settings on delivery from ABB. The value for levelness aims at the circumstance of the anchoring points in the robot base.
Minimum resonance frequency	35 Hz  Note It may affect the manipulator lifetime to have a lower resonance frequency than recommended.	The value is recommended for optimal performance. Due to foundation stiffness, consider robot mass including equipment. ⁱ For information about compensating for foundation flexibility, see the description of <i>Motion Process Mode</i> in the manual that describes the controller software option, see References on page 7 .

ⁱ The minimum resonance frequency given should be interpreted as the frequency of the robot mass/inertia, robot assumed stiff, when a foundation translational/torsional elasticity is added, i.e., the stiffness of the pedestal where the robot is mounted. The minimum resonance frequency should not be interpreted as the resonance frequency of the building, floor etc. For example, if the equivalent mass of the floor is very high, it will not affect robot movement, even if the frequency is well below the stated frequency. The robot should be mounted as rigid as possible to the floor.

Disturbances from other machinery will affect the robot and the tool accuracy. The robot has resonance frequencies in the region 10 – 20 Hz and disturbances in this region will be amplified, although somewhat damped by the servo control. This might be a problem, depending on the requirements from the applications. If this is a problem, the robot needs to be isolated from the environment.

Storage conditions, robot

The table shows the allowed storage conditions for the robot:

Parameter	Value
Minimum ambient temperature	-25 °C
Maximum ambient temperature	55 °C
Maximum ambient temperature (less than 24 hrs)	70 °C
Maximum ambient humidity	95%

Operating conditions, robot

The table shows the allowed operating conditions for the robot:

Parameter	Value
Minimum ambient temperature	0 °C ⁱ
Maximum ambient temperature	+50 °C
Maximum ambient humidity	95% at constant temperature

ⁱ At low environmental temperature < 10°C is, as with any other machine, a warm-up phase recommended to be run with the robot. Otherwise there is a risk that the robot stops or run with lower performance due to temperature dependent oil and grease viscosity.

Continues on next page

Protection classes, robot

The table shows the available protection types of the robot, with the corresponding protection class.

Protection type	Protection class ⁱ
Manipulator, protection type Standard	IP67
External brake release box (option)	IP54

ⁱ According to IEC 60529.

Environmental information

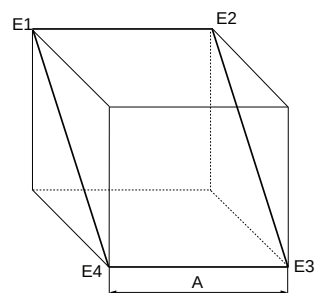
The product complies with IEC 63000. *Technical documentation for the assessment of electrical and electronic products with respect to the restriction of hazardous substances.*

Other technical data

Data	Description	Note
Airborne noise level	The sound pressure level outside the working space	< 68 dB (A) Leq (acc. to Machinery directive 2006/42/EG)

Representative power consumption at nominal payload

Type of movement	IRB 390 - 15/1300	IRB 390 - 10/1300
ISO Cube	1.25	1.28
Average power consumption (kW)		



xx1000000101

Pos	Description
A	320 mm

1 Description

1.2.1 Applicable standards

1.2 Safety standards

1.2.1 Applicable standards



Note

The listed standards are valid at the time of the release of this document. Phased out or replaced standards are removed from the list when needed.

General

The product is designed in accordance with ISO 10218-1:2011, Robots for industrial environments - Safety requirements -Part 1 Robots, and applicable parts in the normative references, as referred to from ISO 10218-1:2011. In case of deviations from ISO 10218-1:2011, these are listed in the declaration of incorporation which is part of the product delivery.

Normative standards as referred to from ISO 10218-1

Standard	Description
ISO 9283:1998	Manipulating industrial robots - Performance criteria and related test methods
ISO 10218-2	Robots and robotic devices - Safety requirements for industrial robots - Part 2: Robot systems and integration
ISO 12100	Safety of machinery - General principles for design - Risk assessment and risk reduction
ISO 13849-1:2006	Safety of machinery - Safety related parts of control systems - Part 1: General principles for design
ISO 13850	Safety of machinery - Emergency stop - Principles for design
IEC 60204-1	Safety of machinery - Electrical equipment of machines - Part 1: General requirements

Deviations from ISO 10218-1:2011 for IRC5 with MultiMove

A deviation exists towards ISO 10218-1:2011, paragraph 5.9 *Control of simultaneous motion*, for the option MultiMove. See the application manual for MultiMove.

Region specific standards and regulations

Standard	Description
ANSI/RIA R15.06	Safety requirements for industrial robots and robot systems
ANSI/UL 1740	Safety standard for robots and robotic equipment
CAN/CSA Z 434	Industrial robots and robot Systems - General safety requirements

Other standards used in design

Standard	Description
ISO 9787:2013	Robots and robotic devices -- Coordinate systems and motion nomenclatures

Continues on next page

Standard	Description
IEC 61000-6-2	Electromagnetic compatibility (EMC) – Part 6-2: Generic standards – Immunity standard for industrial environments
IEC 61000-6-4	Electromagnetic compatibility (EMC) – Part 6-4: Generic standards – Emission standard for industrial environments
ISO 13732-1:2006	Ergonomics of the thermal environment - Part 1
IEC 60974-1:2012 ⁱ	Arc welding equipment - Part 1: Welding power sources
IEC 60974-10:2014 ⁱ	Arc welding equipment - Part 10: EMC requirements
ISO 14644-1:2015 ⁱⁱ	Classification of air cleanliness
IEC 60529:1989 + A2:2013	Degrees of protection provided by enclosures (IP code)

ⁱ Only valid for arc welding robots. Replaces IEC 61000-6-4 for arc welding robots.

ⁱⁱ Only robots with protection Clean Room.

1 Description

1.3.1 Introduction to installation

1.3 Installation

1.3.1 Introduction to installation

General

IRB 390 is adapted for normal industrial environment. Depending on the robot version, an end effector with max. weight including payload, can be mounted on the tool flange (axis 6). See [Load diagrams on page 32](#).

Extra loads

The upper arm can handle an additional load of 0.5 kg.

Working range limitation

Working range can only be limited by software, not mechanically. Customer can set cartesian workspace limits if needed.

1.3.2 Operating requirements

Protection standard

Robot variant	Protection standard IEC529
All variants, manipulator	IP67

Explosive environments

The robot must not be located or operated in an explosive environment.

Working range limitations

No mechanical limitation.

Ambient temperature

Description	Protection class	Temperature
Manipulator with food grade lubrication during operation	Standard	+ 5 °C ⁱ (41 °F) to + 50 °C (122F)

ⁱ At low environmental temperature < 10°C is, as with any other machine, a warm-up phase recommended to be run with the robot. Otherwise there is a risk that the robot stops or run with lower performance due to temperature dependent oil and grease viscosity.

Relative humidity

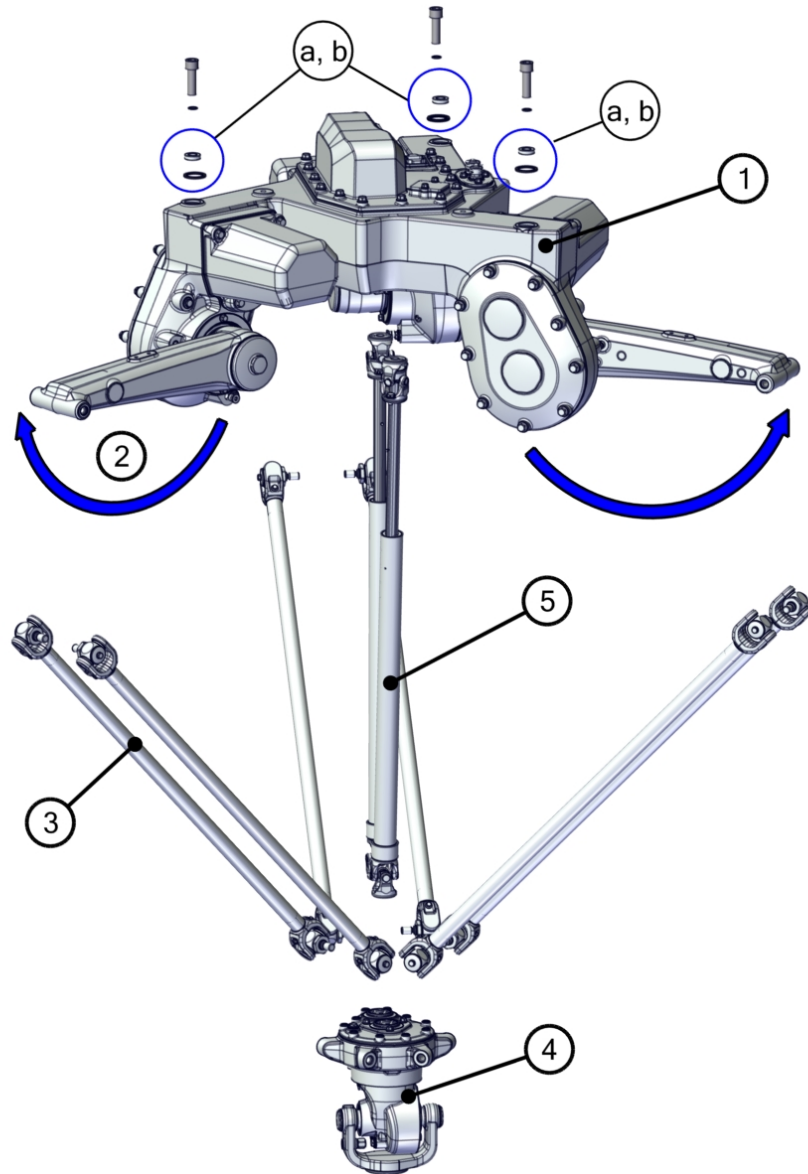
Description	Relative humidity
Complete robot during operation, transportation and storage	Max. 95% at constant temperature

1 Description

1.3.3 Mounting the manipulator

1.3.3 Mounting the manipulator

Assembly illustration



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Assembly order	
1	Install the base unit.  Note The mounting washer (a) and sealing (b) are packed separately in the delivery.
2	Move the upper arms into synchronization position.
3	Attach the lower arms to the upper arms.
4	Attach the delta unit to the lower arms.

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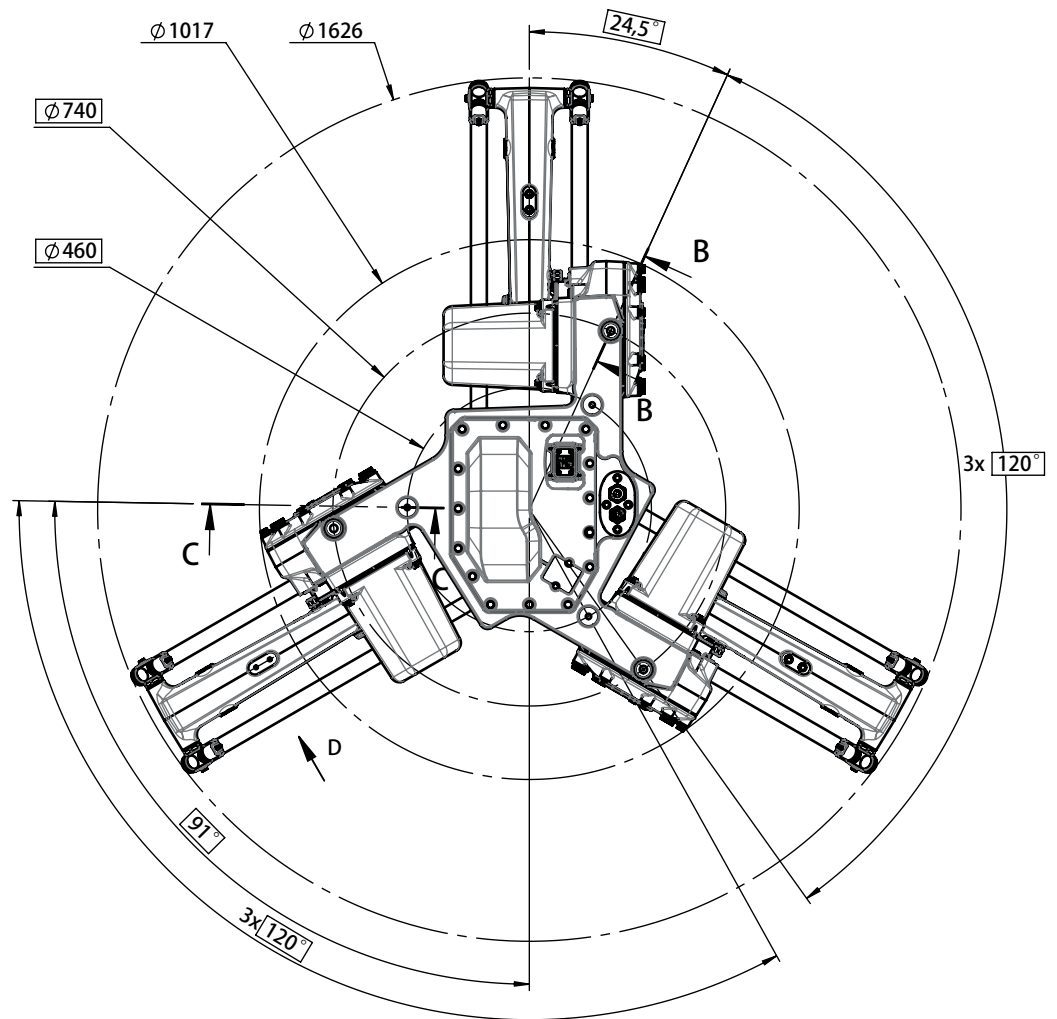
	Assembly order
5	Attach the telescopic unit.
6	Calibrate the robot.

Note regarding M_{xy} and F_{xy}

The bending torque (M_{xy}) can occur in any direction in the XY-plane of the base coordinate system. The same applies to the transverse force (F_{xy}).

Fastening holes robot base

View from above.

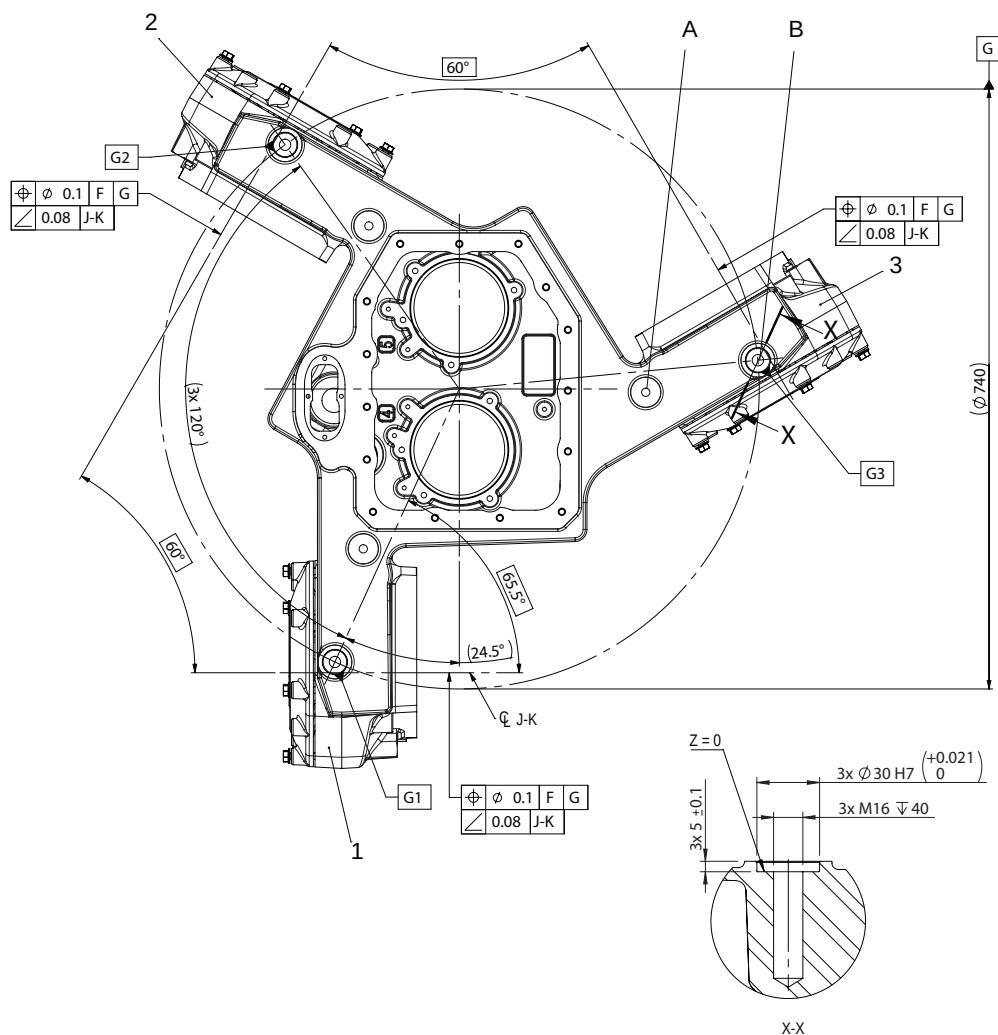


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This illustration shows the hole configuration used when securing the robot.



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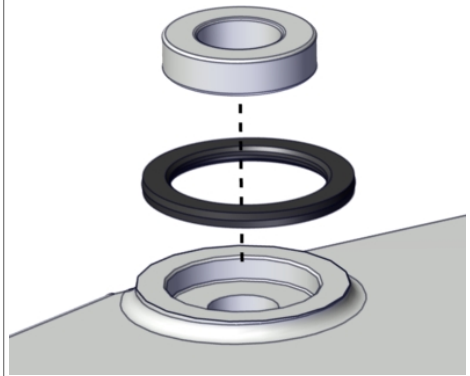
1	Axis-1 gearbox
2	Axis-2 gearbox
3	Axis-3 gearbox
A	Attachment holes for lifting eyes
B	Robot mounting holes
G1, G2, G3	Reference plane for each gearbox.

The three support points of the manipulator base box shall be mounted against three flat surfaces with a flatness within the specification. Use shims if necessary. See specification in [Requirements, foundation on page 14](#).

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Attachment screws

The table below specifies the type of securing screws and washers to be used for securing the robot to the base foundation.

Suitable screws	M16 stainless steel. Minimum length of thread engagement: 24 mm
Quantity	3 pcs
Quality	Minimum quality: A4-80
Suitable washer	12.5x24x6.5 Steel 17x25x3 coated stainless steel
Distance washer and sealing	Distance washer: 3HAC070543-001. Sealing ring: 3HAC074660-001.  xx2000000260 Included in the manipulator delivery. Replace if damaged.
Tightening torque	250 Nm
Level surface requirements	0.3 mm

1 Description

1.3.4 Type of lubrication in gearboxes

1.3.4 Type of lubrication in gearboxes

Introduction

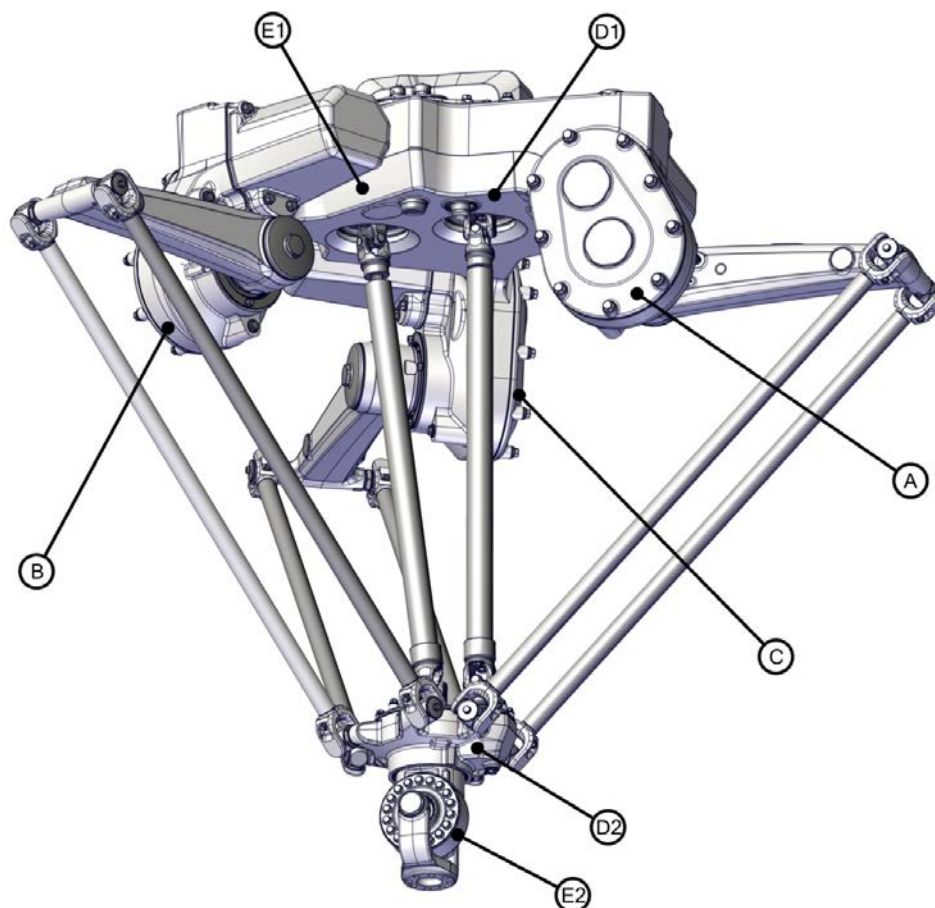
This section describes where to find information about the type of lubrication, article number and the amount of lubrication in the specific gearbox. It also describes the equipment needed when working with lubrication.

Type and amount of oil in gearboxes

Information about the type of lubrication, article number as well as the amount in the specific gearbox can be found in *Technical reference manual - Lubrication in gearboxes* available for registered users via ABB Robotics One, <https://one.robots.abb.com/en/knowledge-hub>.

Location of gearboxes

The figure shows the location of the gearboxes.



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A	Axis-1 gear
B	Axis-2 gear
C	Axis-3 gear
D1	Axis-4 gear prestage

Continues on next page

D2	Axis-4 gear
E1	Axis-5 gear prestage
E2	Axis-5 gear

1 Description

1.3.5 Installing a brake release box (option)

1.3.5 Installing a brake release box (option)

General

The robot cable harness is prepared for connecting a brake release box, as an option and as an addition to the standard brake release button.

This option is valuable if access to the standard brake release button is limited.

Brake release box installation

The figure shows a routed cable from the brake release box to the SMB battery compartment located on top of the base unit.



CAUTION

Risk of unintended contact with the push button. Place the brake release box in a way that eliminates the risk of unintended contact with the push button.



Note

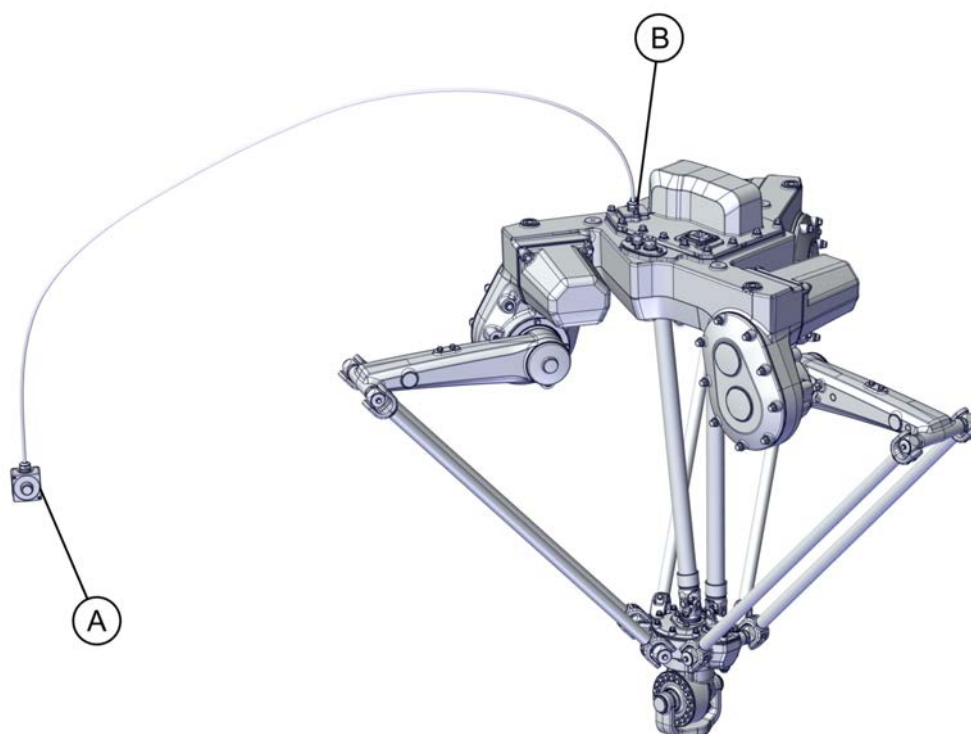
The equipment must be installed in accordance with the specified protection class, see [Protection classes, robot on page 15](#).



Note

Place the equipment in a manner that makes it obvious which manipulator it is connected to. There must be no doubt on which manipulator is affected when activating the button.

Continues on next page



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A	Brake release box assembly
B	Connection to robot cable harness connector R3.H1

Technical specification

Function	Data
Signal	24V DC
Current	13A continuously

Required equipment

Equipment	Note
2-core cable, shielded	Maximum cable length: 3 m.
Cable connector	
Cable gland	To be installed in the SMB battery cover.
Push button, momentary push to make	Passive actuator with open spring return push button. Must not be susceptible to ESD. Make an installation assembly with the push button, to be fitted to the robot frame or a similar appropriate location. CAUTION Risk of unintended contact with the push button. Place the brake release box in a way that eliminates the risk of unintended contact with the push button.

1 Description

1.4.1 Calibration methods

1.4 Calibration and references

1.4.1 Calibration methods

Overview

This section specifies the different types of calibration and the calibration methods that are supplied by ABB.

More information is available in the product manual.

Types of calibration

Type of calibration	Description	Calibration method
Standard calibration	The calibrated robot is positioned at calibration position. Standard calibration data is found on the SMB (serial measurement board) or EIB in the robot.	Axis Calibration

Brief description of calibration methods

Axis Calibration method

Axis Calibration is a standard calibration method for calibration of IRB 390. It is the recommended method in order to achieve proper performance.

The following routines are available for the Axis Calibration method:

- Fine calibration
- Update revolution counters
- Reference calibration

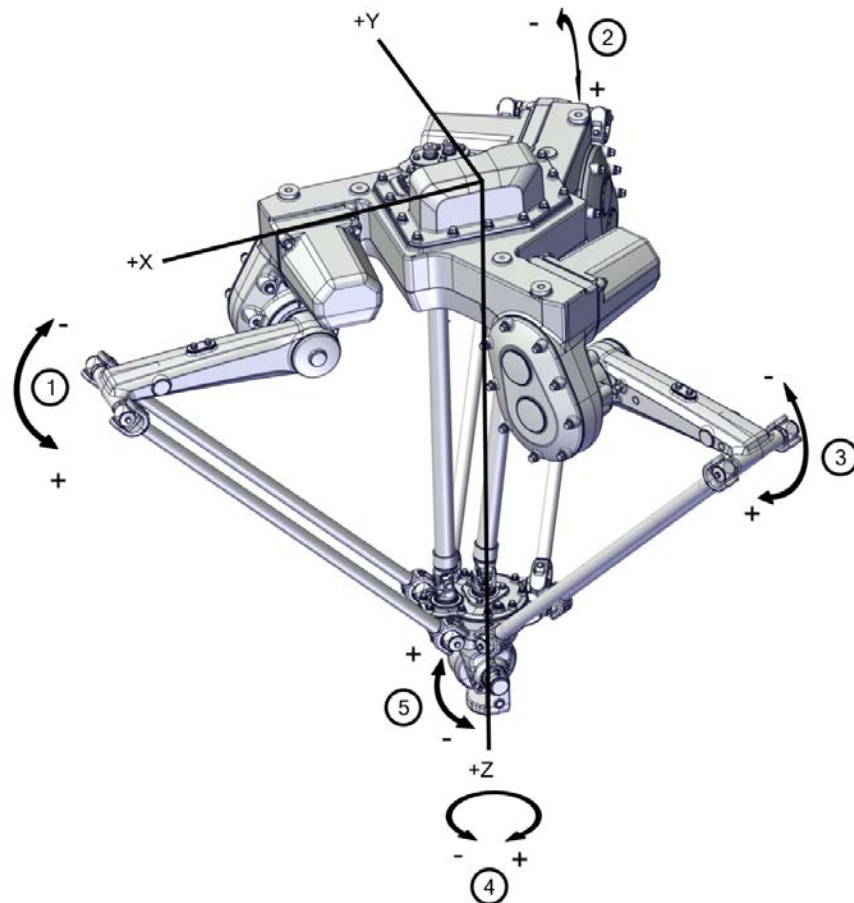
The calibration equipment for Axis Calibration is delivered as a toolkit.

The actual instructions of how to perform the calibration procedure and what to do at each step is given on the FlexPendant. You will be guided through the calibration procedure, step by step.

1.4.2 Fine calibration

General

The fine calibration is done with the Axis calibration method.



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Axes

Pos	Description	Pos	Description
1	Axis 1	2	Axis 2
3	Axis 3	4	Axis 4
5	Axis 5		

1 Description

1.4.3.1 Synchronization marks and synchronization position for axes

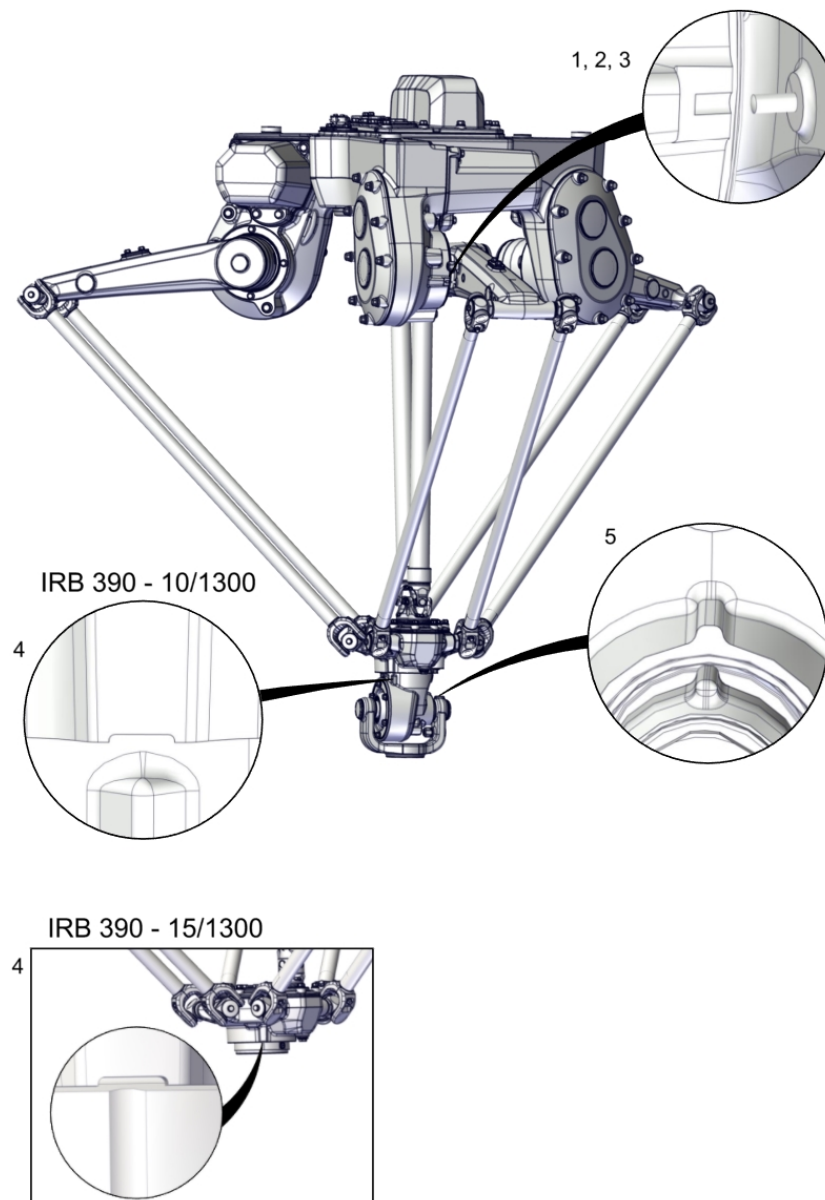
1.4.3 Synchronization marks and axis movement directions

1.4.3.1 Synchronization marks and synchronization position for axes

Introduction

This section shows the position of the synchronization marks and the synchronization position for each axis.

Synchronization marks, IRB 390



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1.4.3.2 Calibration movement directions for all axes

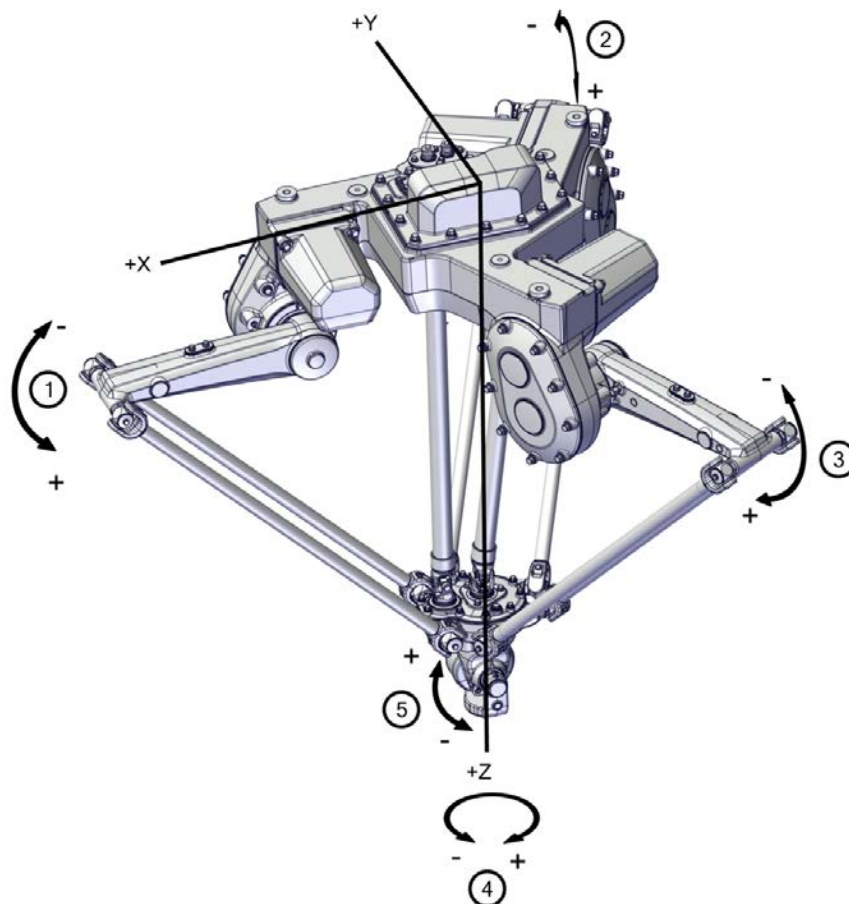
Overview

When calibrating, the axis must consistently be run towards the calibration position in the same direction in order to avoid position errors caused by backlash in gears and so on. Positive directions are shown in the graphic below.

Calibration service routines will handle the calibration movements automatically and these might be different from the positive directions shown below.

Calibration movement and jogging directions

The following graphic shows the positive and negative directions for each axis and the linear directions when jogging the robot in the base coordinate system.



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1 Description

1.5.1 Introduction

1.5 Load diagrams

1.5.1 Introduction



WARNING

It is very important to always define correct actual load data and correct payload of the robot. Incorrect definitions of load data can result in overloading of the robot.

If incorrect load data is used, and/or if loads outside the load diagram are used, the following parts can be damaged due to overload:

- motors
- gearboxes
- mechanical structure



WARNING

Robots running with incorrect load data and/or with loads outside the load diagram, will not be covered by robot warranty.

General

The load diagrams include a nominal payload inertia. The J_0 for the IRB 390 - 15/1300 is 0.08 kgm^2 and for IRB 390 - 10/1300 is 0.15 kgm^2 . High inertia payloads affect performance.

The maximum allowable inertia around axis 5 and 4 is 2 kgm^2 . The distance from the customer interface to axis 5 rotational centre is 0.097 meter.

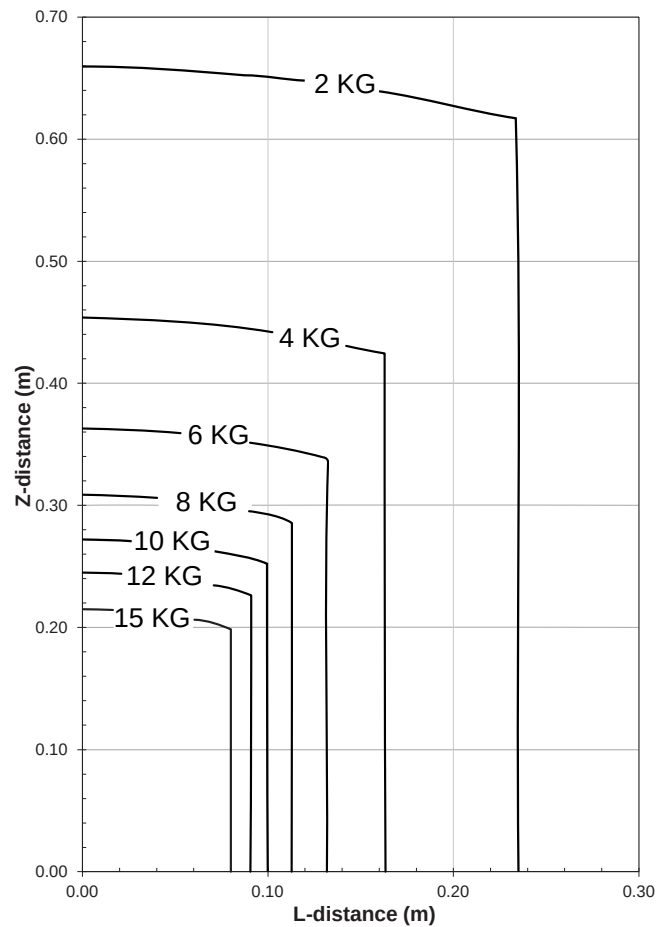
The IRB 390 can only be used hanging from the ceiling, other orientations are not allowed.

1.5.2 Load diagrams

**Note**

The weight permitted for loads includes grippers etc.

The data types `loaddata` and `tooldata` with moment of inertia must be used!

IRB 390 - 15/1300

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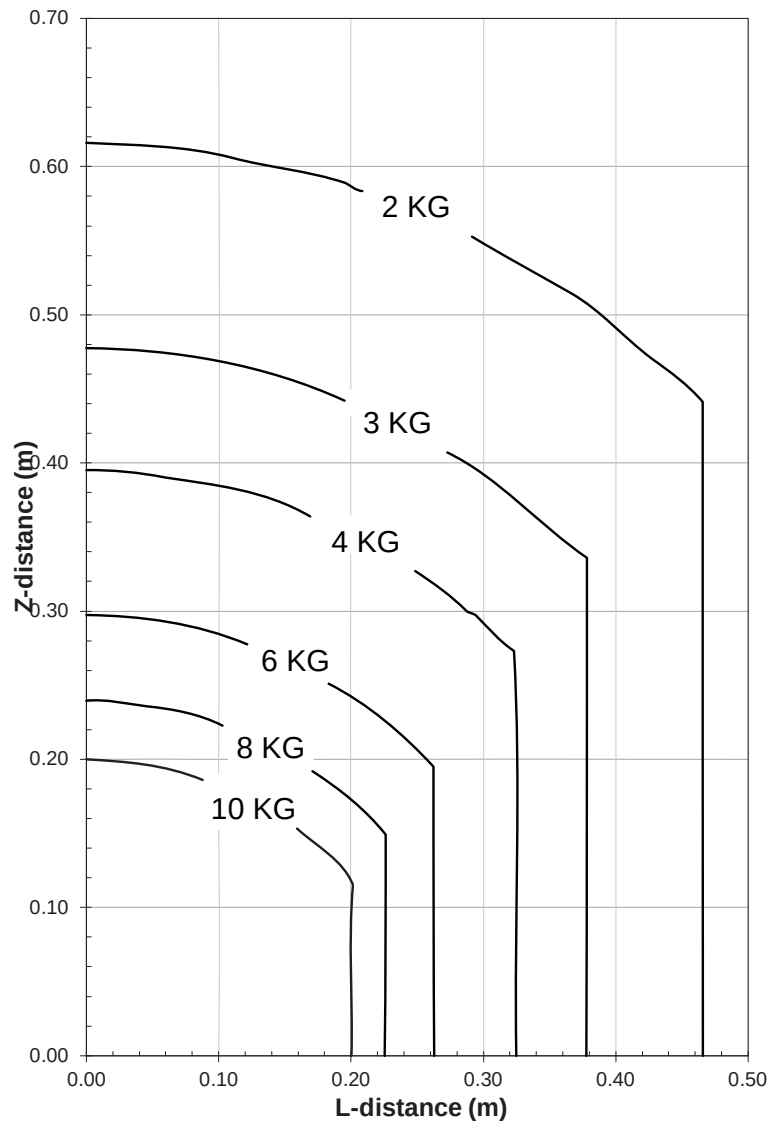
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1 Description

1.5.2 Load diagrams

Continued

IRB 390 - 10/1300



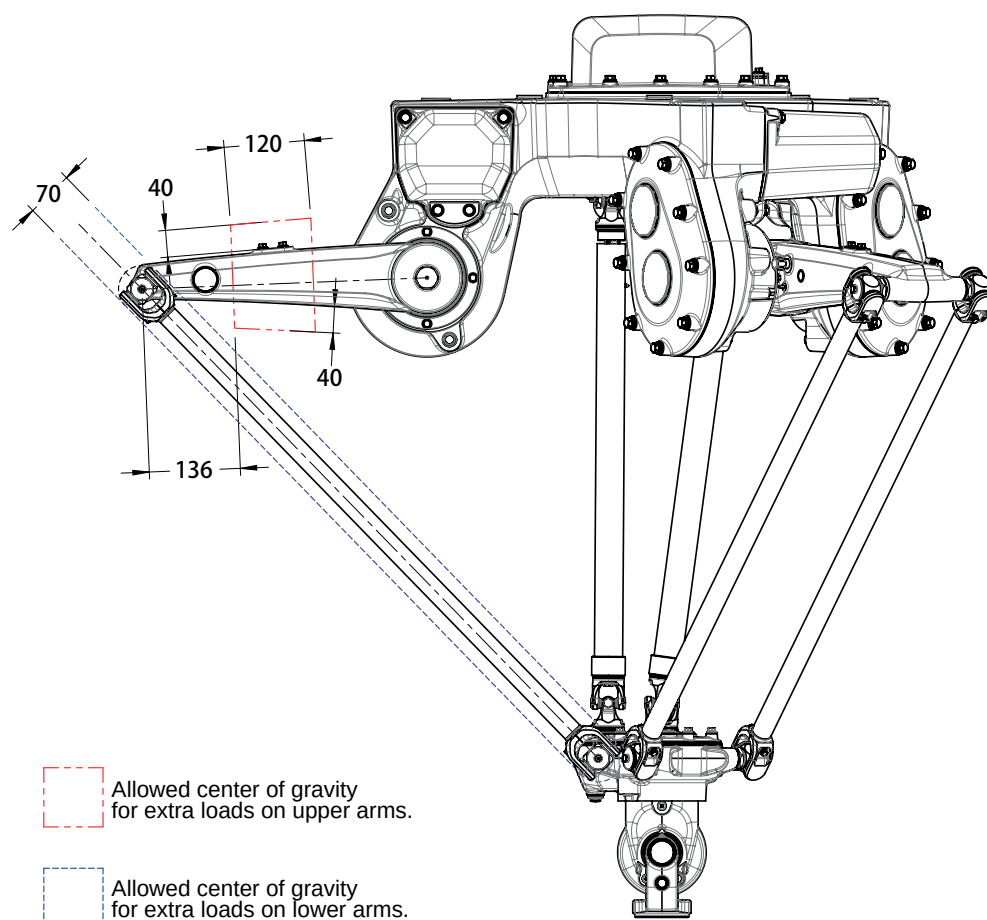
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Extra equipment mounted on the manipulator arms

Upper arm loads have to be declared as arm loads for joint 1, 2 and 3 respectively. The extra load on the delta housing should be added as arm load data (identified in RobotWare as r1_load_4). The extra lower arm loads can be divided between the respective upper arm load and the delta housing load.

Maximum extra load on upper arm	0.5 kg
Lower arm	0.15 kg
Delta housing	0.5 kg

Continues on next page



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1 Description

1.5.3 Maximum TCP acceleration

1.5.3 Maximum TCP acceleration

Maximum Cartesian design acceleration for nominal loads

Robot type	E-stop Max acceleration at nominal load COG [m/s ²]	Controlled Motion Max acceleration at nominal load COG [m/s ²]
IRB 390-15/1300	99	82
IRB 390-10/1300	141	98



Note

Acceleration levels for E-stop and controlled motion includes acceleration due to gravitational forces. Nominal load is define with nominal mass and cog with max offset in Z and L (see load diagram).

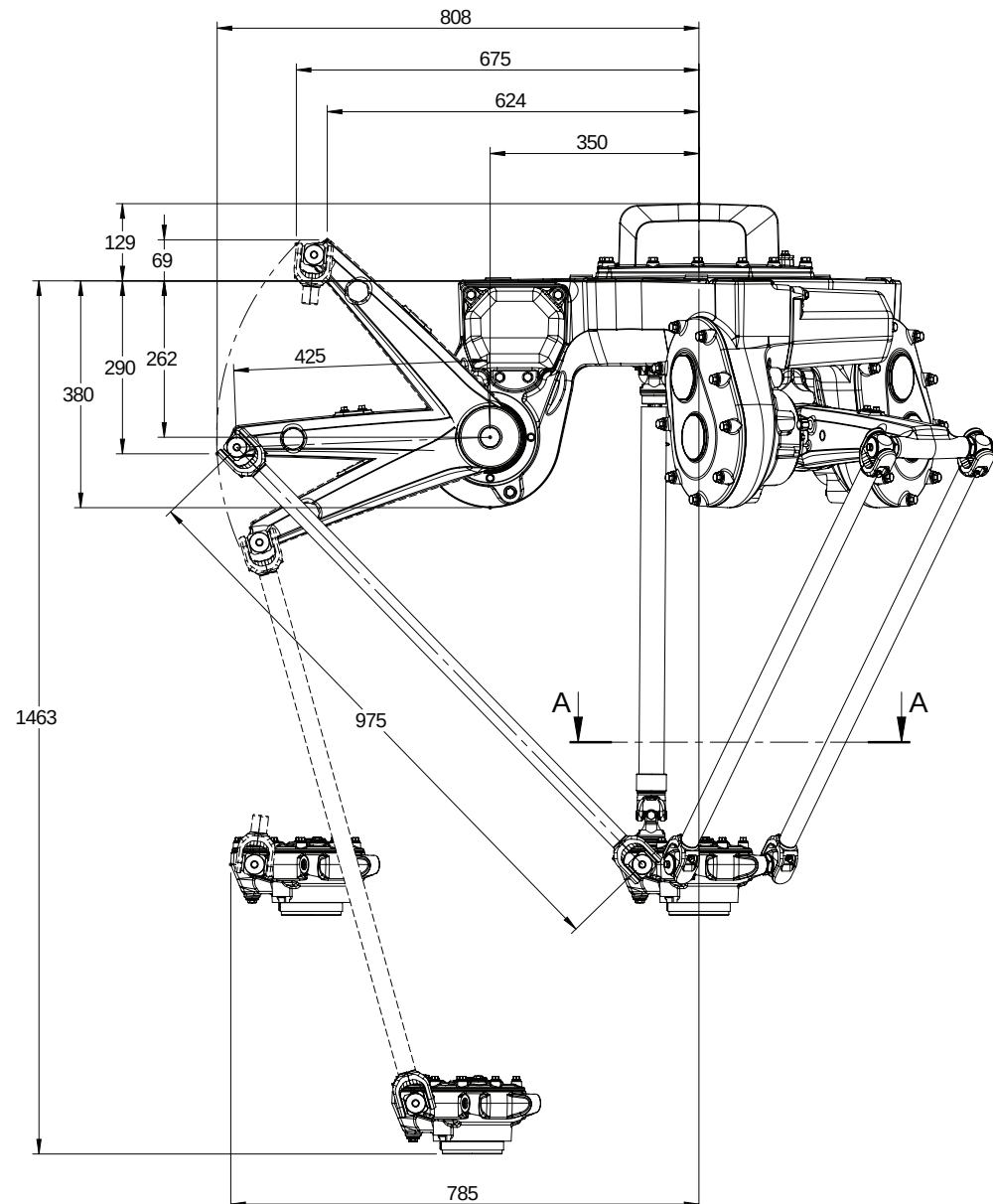
1.6 Fitting equipment on the robot (robot dimensions)

Robot dimensions

The figure shows the dimension of the robot.

The view A-A is shown in [Attachment holes for extra loads on the delta unit on page 44](#).

IRB 390 - 15/1300



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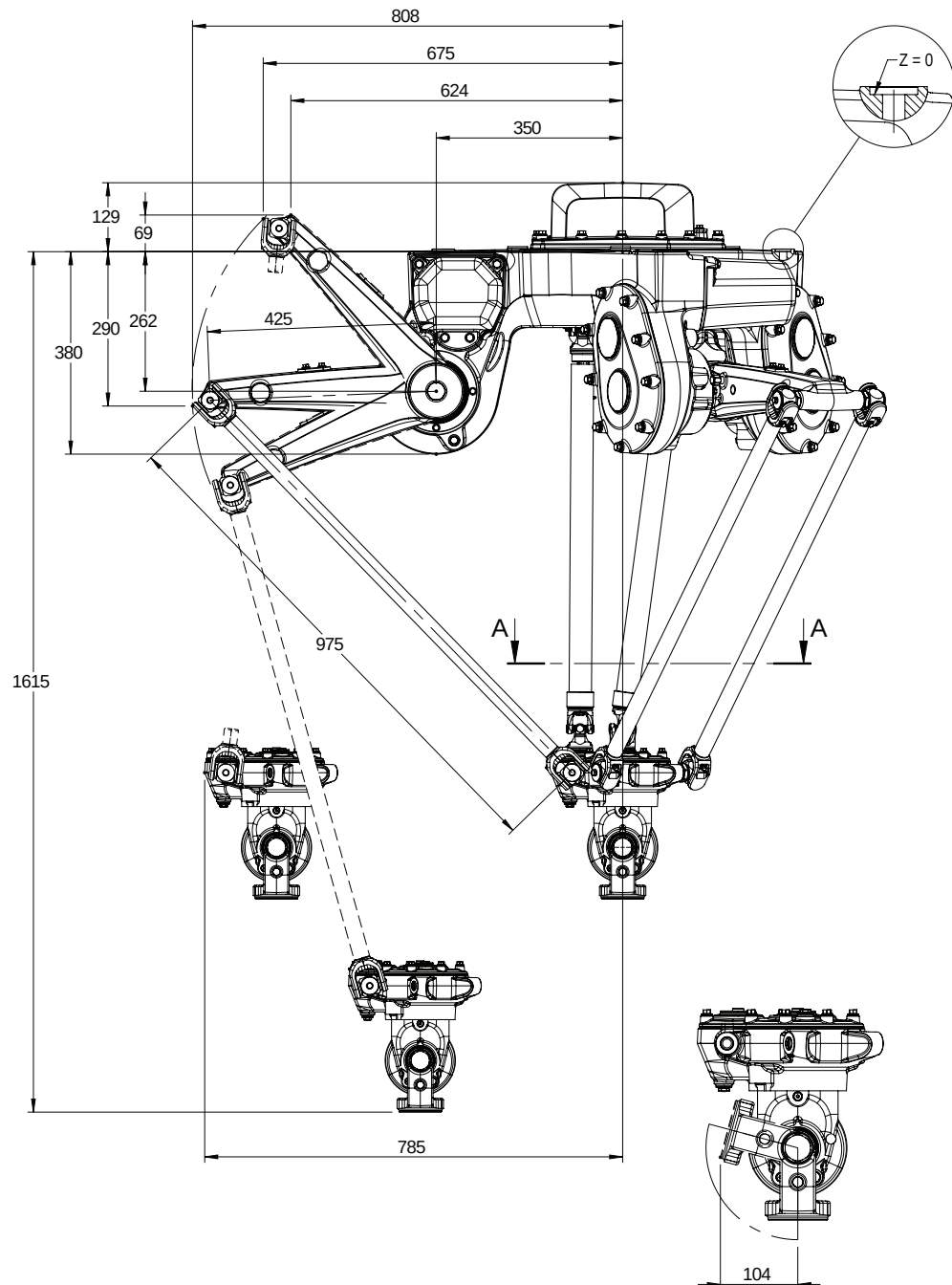
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1 Description

1.6 Fitting equipment on the robot (robot dimensions)

Continued

IRB 390 - 10/1300



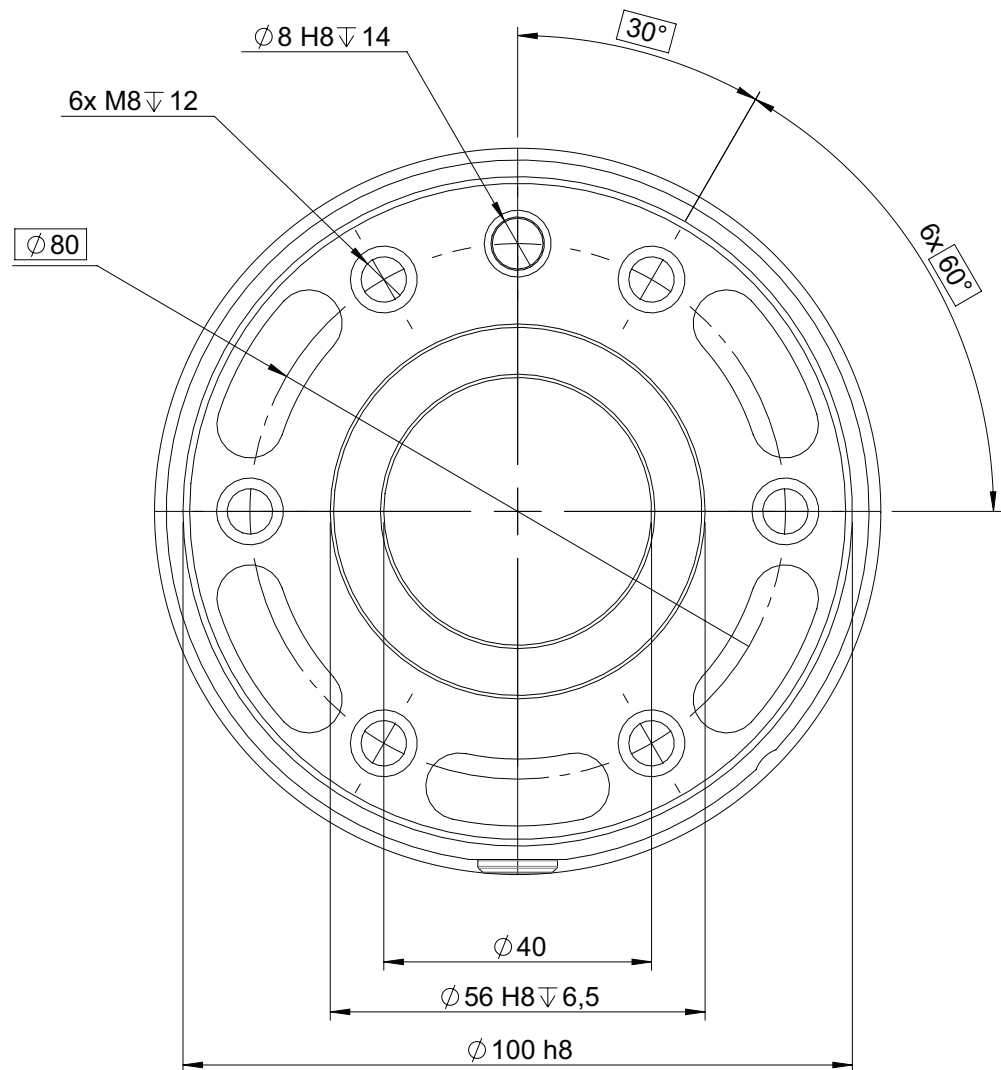
xx2000001839

The view A-A is shown in [Attachment holes for extra loads on the delta unit on page 44](#).

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Mechanical interface of the tool flange

IRB 390 - 15/1300



xx2200001033

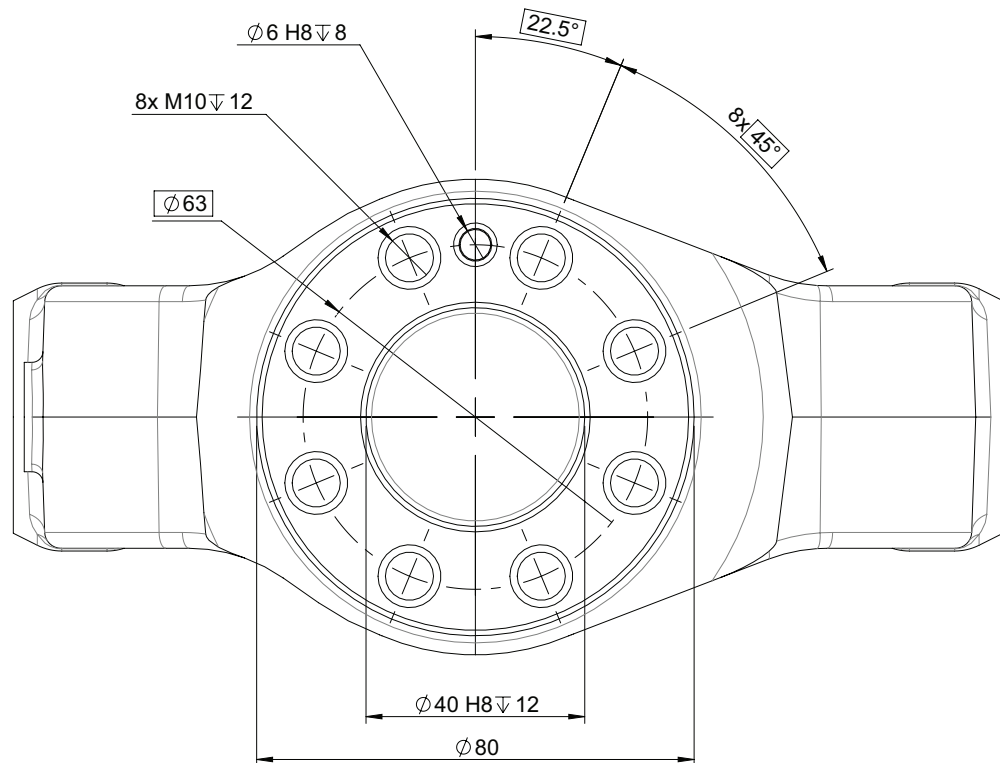
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1 Description

1.6 Fitting equipment on the robot (robot dimensions)

Continued

IRB 390 - 10/1300



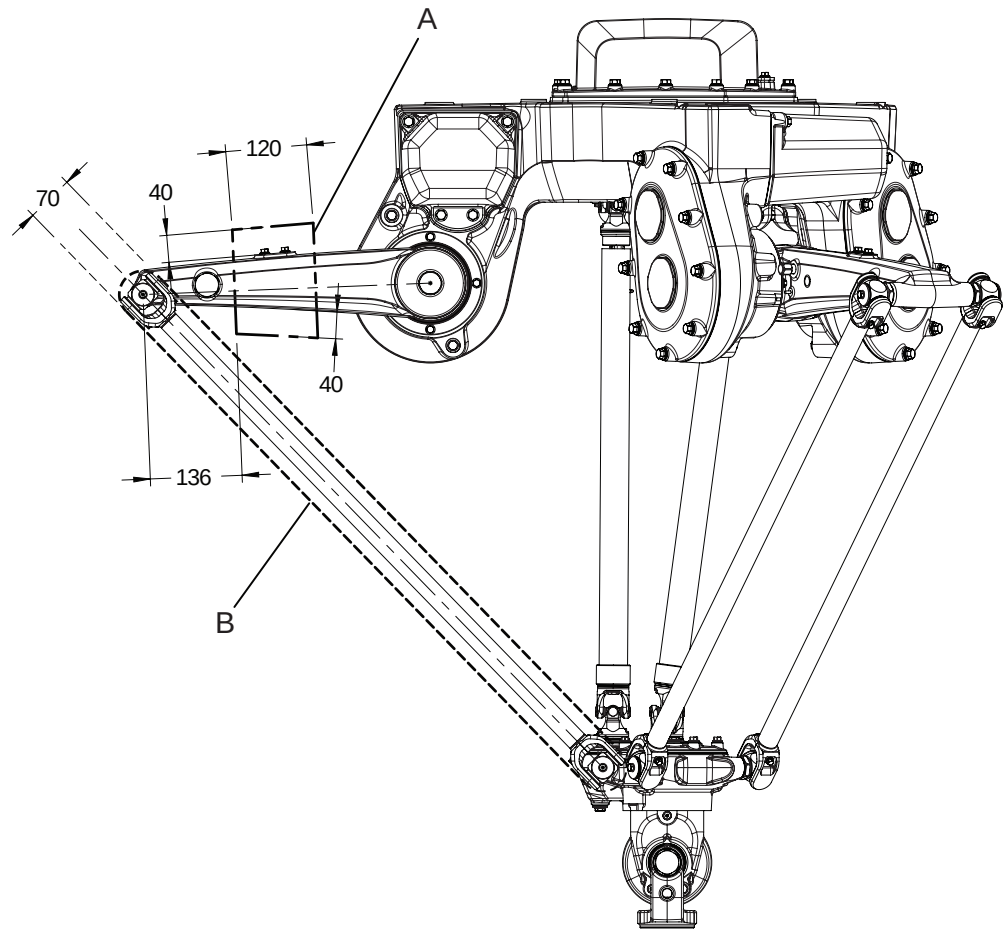
xx2000002064

Attachment holes and dimensions for extra loads

Extra loads can be mounted on robot. Definitions of dimensions and masses are shown in the following figures. The robot is supplied with holes for fitting extra equipment. Maximum allowed arm load depends on center of gravity of arm load and robot payload.

Continues on next page

Center of gravity for extra loads on upper and lower arms



xx2000002341

A	Allowed center of gravity for extra loads on upper arms.
B	Allowed center of gravity for extra loads on lower arms.

Continues on next page

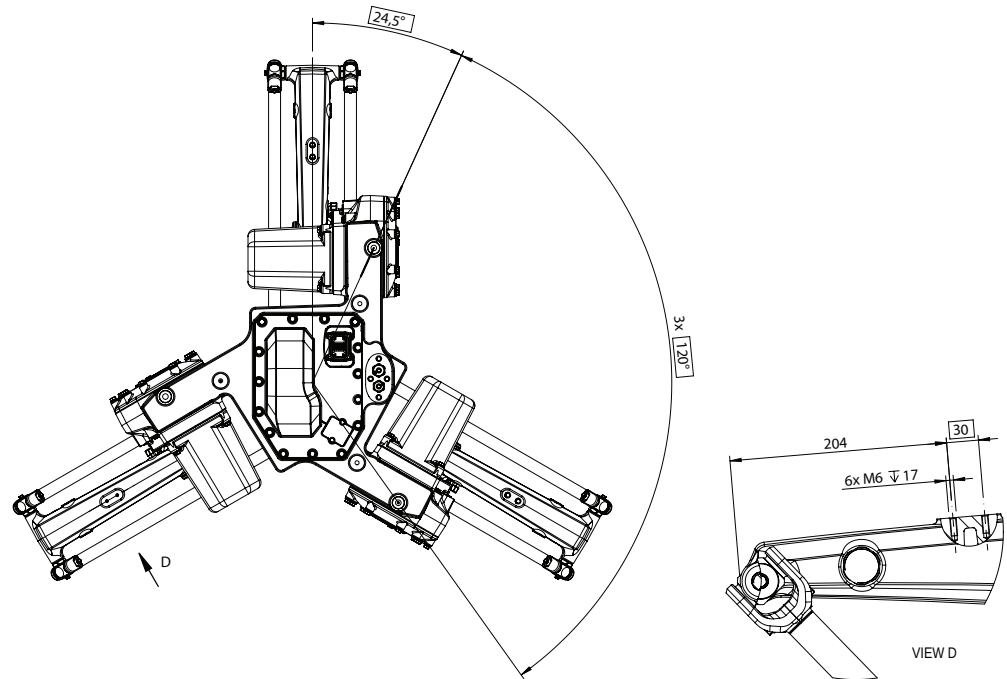
1 Description

1.6 Fitting equipment on the robot (robot dimensions)

Continued

Attachment holes for extra loads on the upper arms

There is a set of two M6 holes on top of each upper arm, that can be used for attaching equipment. Maximum extra load: 0.5 kg/upper arm.

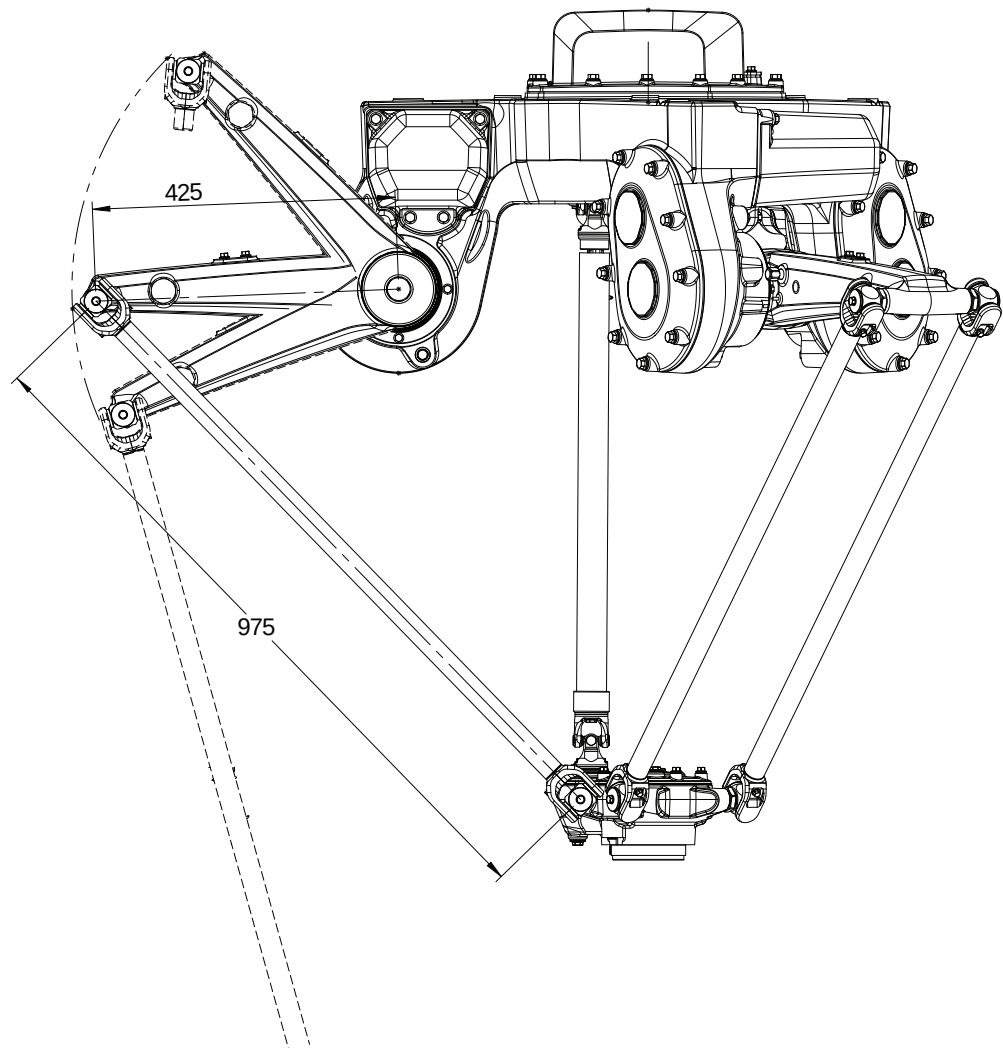


Attachment of extra loads on the lower arms

No holes for fitting extra equipment are available on the lower arms. If attaching extra equipment to the lower arms, use shaped clamping blocks. Plastic cable ties

Continues on next page

can be used but risk damaging of the paint. Do not use metal directly on the lower arms. Maximum extra load: 0.15 kg/lower arm.



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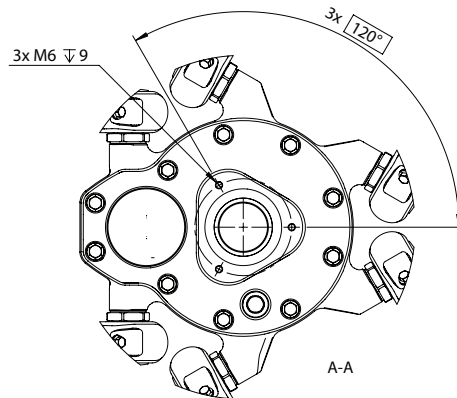
1 Description

1.6 Fitting equipment on the robot (robot dimensions)

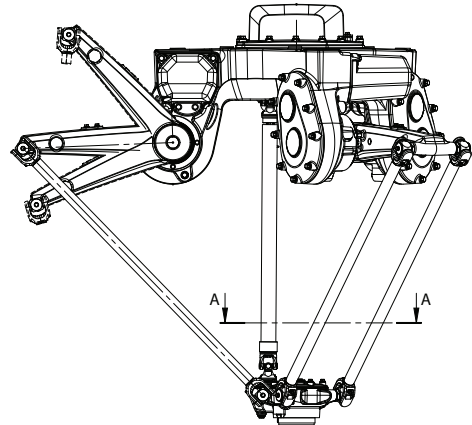
Continued

Attachment holes for extra loads on the delta unit

There is a set of three M6 holes on top of the delta unit that can be used for attaching equipment. Maximum extra load on the delta unit: 0.5 kg.



xx2000001848



Fastener quality

When fitting tools on the tool flange, only use screws with quality 12.9. For other equipment use suitable screws and tightening torque for your application.

1.7 Maintenance and troubleshooting

General

The robot requires only minimum maintenance during operation. It has been designed to make it as easy to service as possible:

- Maintenance-free AC motors are used.
- Oil is used for the gear boxes.
- All cabling is fixed, no movements. In the unlikely event of a failure, its modular design makes it easy to change.

Maintenance

The maintenance intervals depend on the use of the robot, the required maintenance activities also depends on selected options. For detailed information on maintenance procedures, see *Product manual - IRB 390*.

1 Description

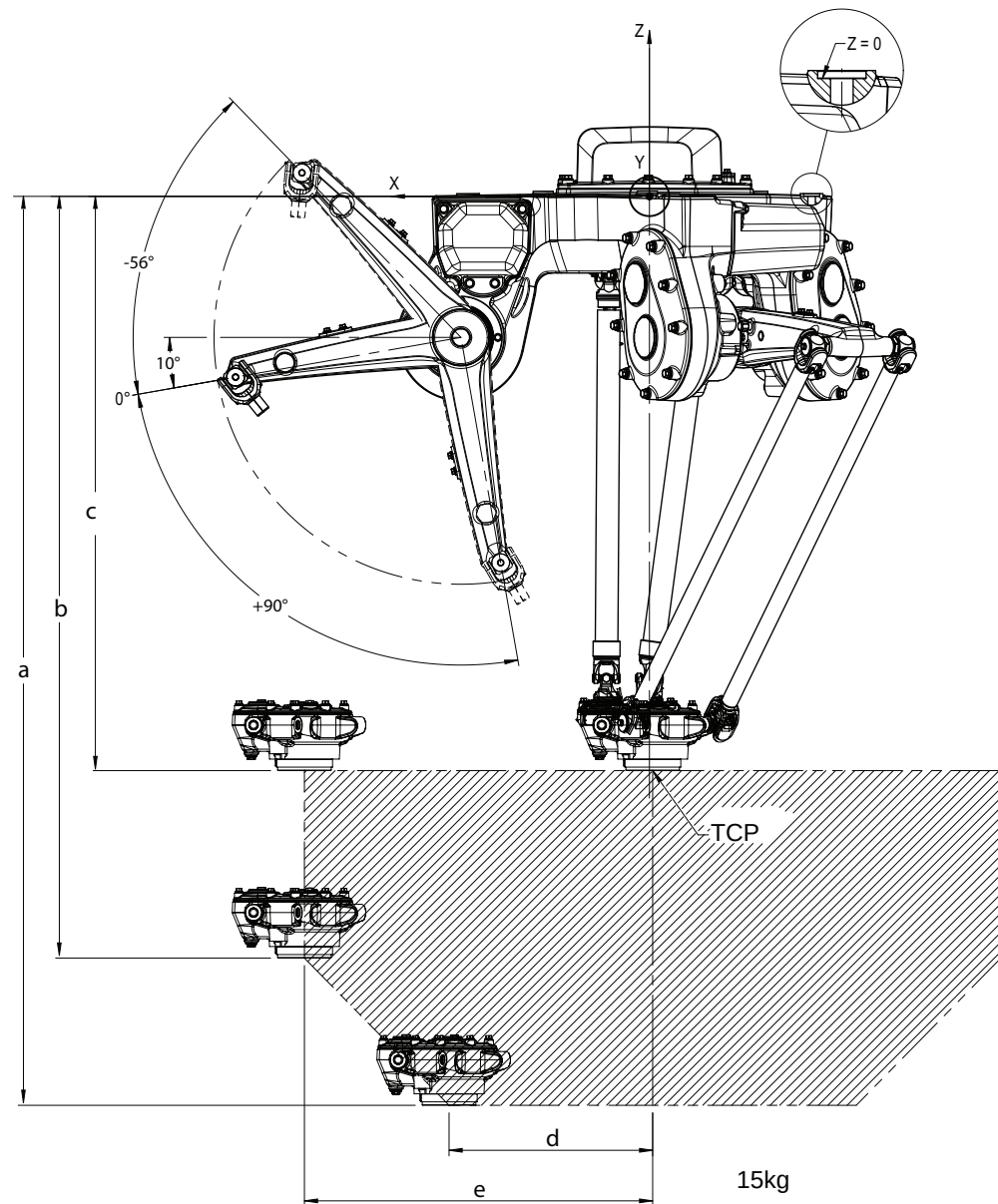
1.8.1 Working range

1.8 Robot motion

1.8.1 Working range

Illustration, working range IRB 390 - 15/1300

This illustration shows the unrestricted working range of the robot.



xx1900001423

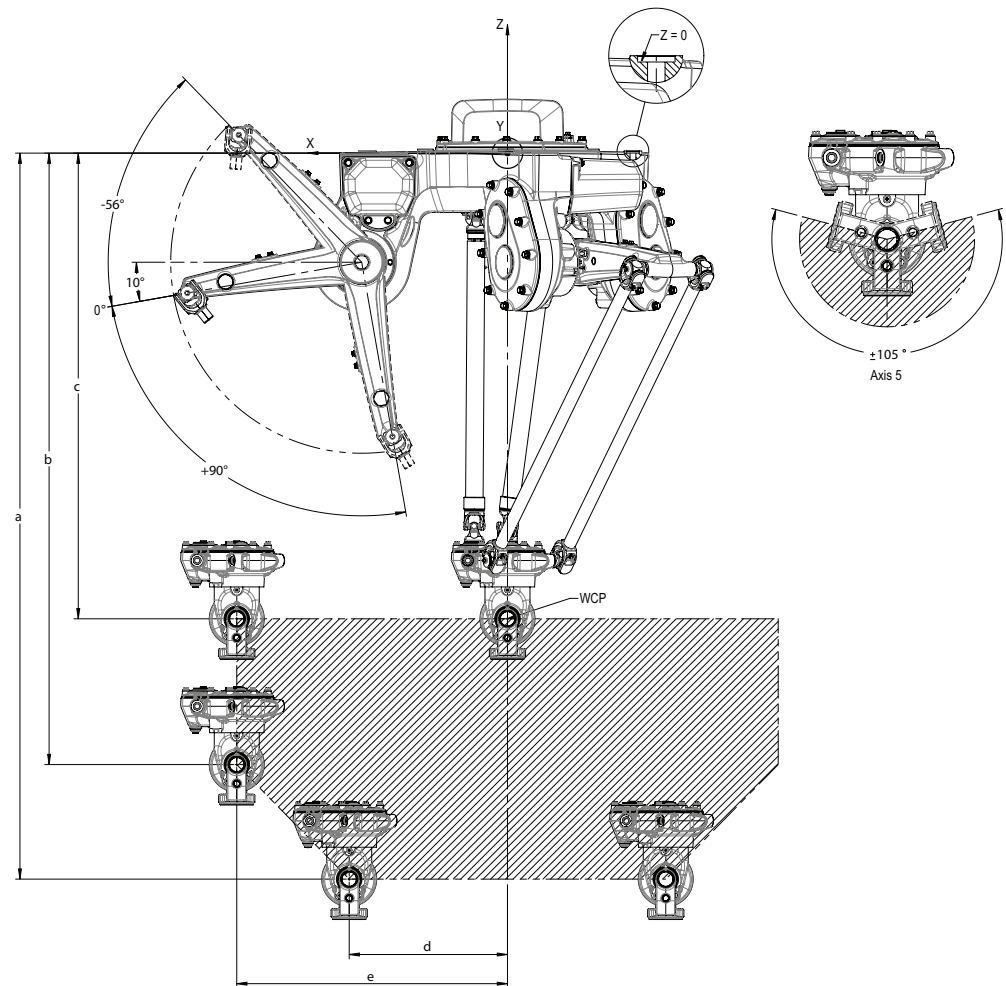
Dimensions

Measurement a	Measurement b	Measurement c	Measurement d	Measurement e
1,463 mm	1,274 mm	1,063 mm	475 mm	650 mm

Continues on next page

Illustration, working range IRB 390 - 10/1300

This illustration shows the unrestricted working range of the robot.



xx1900001422

Dimensions

Measurement a	Measurement b	Measurement c	Measurement d	Measurement e
1,518 mm	1,329 mm	1,118 mm	380 mm	650 mm

1 Description

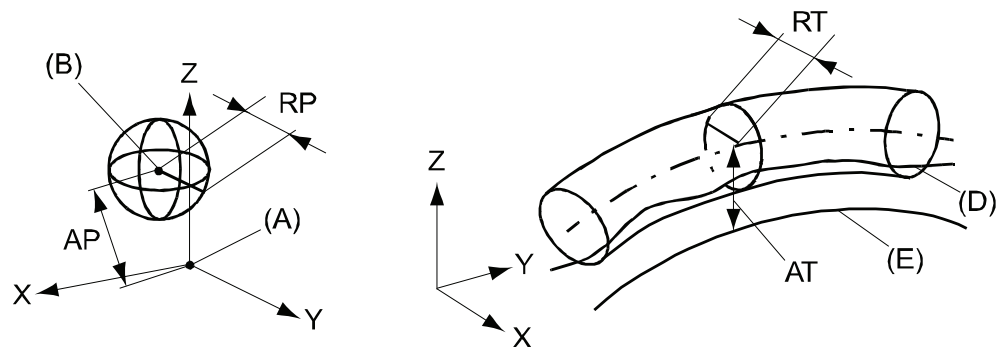
1.8.2 Performance according to ISO 9283

1.8.2 Performance according to ISO 9283

General

At rated load and 1.6 m/s velocity on ISO test plane with all four robot axes in motion, with different payload. Values in the table below are the average result of measurements on a small number of robots. The result may differ depending on where in the working range the robot is positioning, velocity, arm configuration, from which direction the position is approached, the load direction of the arm system. Backlashes in gearboxes also affect the result.

The figures for AP, RP, AT and RT are measured according to figure below.



xx0800000424

Position	Description	Position	Description
A	Programmed position	E	Programmed path
B	Mean position at program execution	D	Actual path at program execution
AP	Mean distance from programmed position	AT	Max deviation from E to average path
RP	Tolerance of position B at repeated positioning	RT	Tolerance of the path at repeated program execution

IRB 390	IRB 390 - 15/1300	IRB 390 - 10/1300
Pose accuracy, AP ⁱ (mm)	0.02	0.07
Pose repeatability, RP (mm)	0.02	0.07
Pose stabilization time, PSt (s) within 0.1 mm of the position	0.14	0.30
Pose stabilization overshoot, PSo	0.16	0.29
Path accuracy, AT (mm)	0.65	1.29
Path repeatability, RT (mm)	0.03	0.05

ⁱ AP according to the ISO test above, is the difference between the taught position (position manually modified in the cell) and the average position obtained during program execution.

Backlash axis 4 and 5

Protection class	Value
Standard	20 arc minute

Continues on next page

Velocity

Direction	Description
IRB 390 - 15/1300	5.7 m/s
IRB 390 - 10/1300	5 m/s

1 Description

1.8.3 Robot stopping distances and times

1.8.3 Robot stopping distances and times

Introduction

The stopping distances and times for category 0 and category 1 stops, as required by EN ISO 10218-1 Annex B, are listed in *Product specification - Robot stopping distances according to ISO 10218-1 (3HAC048645-001)*.

1.9 Typical cycle times

1.9.1 Introduction to typical cycle times

General

Both cycles incorporate an air activation time of 35 ms for picking and 35 ms for placing. Air activation takes place during the cycle time.

Description of typical cycles
Cycle 1 is a 90 - 400 - 90 movement, with 90 degrees rotation of axis 4.
Cycle 2 is a 90 - 700 - 90 movement, with 90 degrees rotation of axis 4.

Approximate cycle times

	IRB 390-15/1300	
Payload	5.0 kg	15.0 kg
Cycle 1	0.67	0.79
Cycle 2	0.81	0.96

	IRB 390-10/1300	
Payload	5.0 kg	10.0 kg
Cycle 1	0.74	0.79
Cycle 2	0.90	0.98

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2 Specification of variants and options

2.1 Introduction to variants and options

General

The different variants and options for the IRB 390 are described in the following sections. The same option numbers are used here as in the specification form.

The variants and options related to the robot controller are described in the product specification for the controller.

2 Specification of variants and options

2.2 Manipulator

2.2 Manipulator

Variants

Option	Description
435-140	IRB 390-15/1300
435-141	IRB 390-10/1300

Protection class

Option	Description
287-4	Standard, IP67

Signs on manipulator

Option	Description
334-1	ABB
334-3	NONE

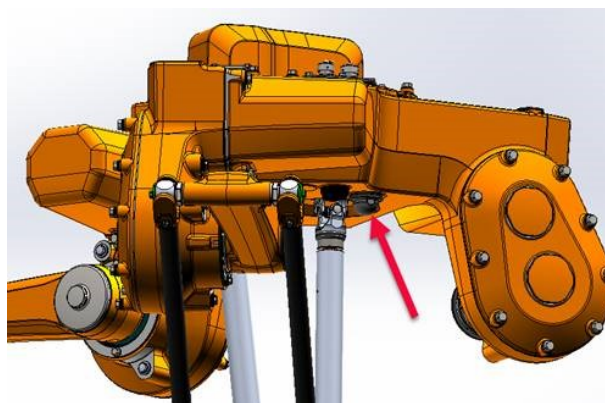
Resolver connection, axis 7

A connector for resolver signals for axis 7 located on the base box.

Option	Description
864-1	On base

Safety lamp

Option	Description
213-1	A safety lamp with an orange fixed light can be mounted on the robot frame. Cable length 400 mm. The lamp is active in MOTORS ON mode.



xx2000002036

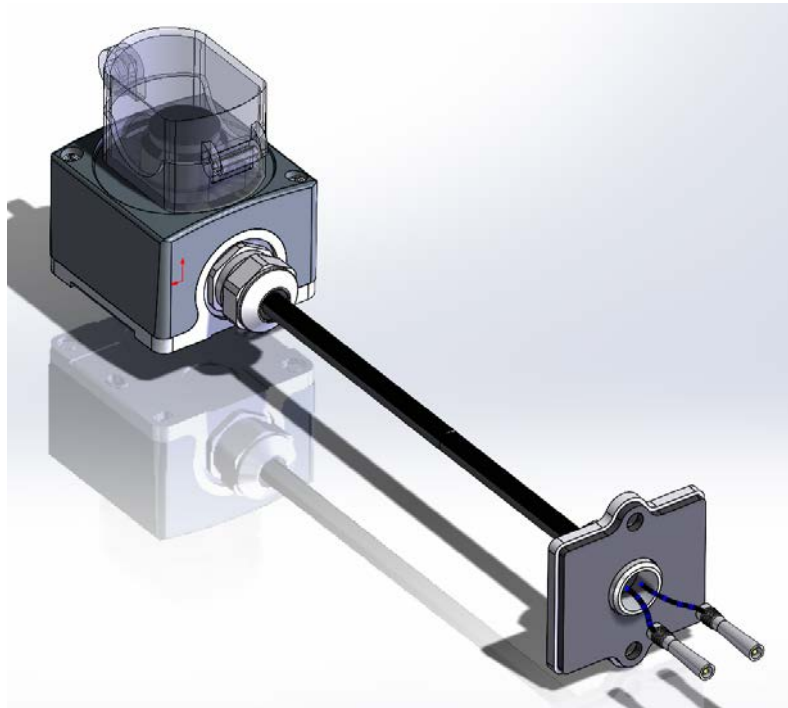
Remote brake release kit

Option	Description
1584-1	Remote brake release

Continues on next page

General

The remote brake release is an extra brake release button not installed on the manipulator. With a cable connected to the manipulator it can be located where it is suitable in or outside of the production cell.



xx2100002104

2 Specification of variants and options

2.3 Floor cables

2.3 Floor cables

Manipulator cable - length

Option	Description
210-1	3 m
210-2	7 m
210-3	15 m
210-4	22 m
210-5	30 m

2.4 Process

Process module

Option	Type	Description
768-1	Empty cabinet small	See <i>Product specification - Controller IRC5 with FlexPendant</i>
768-2	Empty cabinet large	See <i>Product specification - Controller IRC5 with FlexPendant</i>
715-1	Installation kit	See <i>Product specification - Controller IRC5 with FlexPendant</i>

2 Specification of variants and options

2.5 Warranty

2.5 Warranty

Warranty

For the selected period of time, ABB will provide spare parts and labor to repair or replace the non-conforming portion of the equipment without additional charges. During that period, it is required to have a yearly *Preventative Maintenance* according to ABB manuals to be performed by ABB. If due to customer restrains no data can be analyzed with ABB Connected Services for robots with OmniCore controllers, and ABB has to travel to site, travel expenses are not covered. The *Extended Warranty* period always starts on the day of warranty expiration. Warranty Conditions apply as defined in the *Terms & Conditions*.



Note

This description above is not applicable for option *Stock warranty* [438-8]

Option	Type	Description
438-1	Standard warranty	Standard warranty is 12 months from <i>Customer Delivery Date</i> or latest 18 months after <i>Factory Shipment Date</i> , whichever occurs first. Warranty terms and conditions apply.
438-2	Standard warranty + 12 months	Standard warranty extended with 12 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-4	Standard warranty + 18 months	Standard warranty extended with 18 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-5	Standard warranty + 24 months	Standard warranty extended with 24 months from end date of the standard warranty. Warranty terms and conditions apply. Contact Customer Service in case of other requirements.
438-6	Standard warranty + 6 months	Standard warranty extended with 6 months from end date of the standard warranty. Warranty terms and conditions apply.
438-7	Standard warranty + 30 months	Standard warranty extended with 30 months from end date of the standard warranty. Warranty terms and conditions apply.
438-8	Stock warranty	Maximum 6 months postponed start of standard warranty, starting from factory shipment date. Note that no claims will be accepted for warranties that occurred before the end of stock warranty. Standard warranty commences automatically after 6 months from <i>Factory Shipment Date</i> or from activation date of standard warranty in WebConfig. Note Special conditions are applicable, see <i>Robotics Warranty Directives</i>.

3 Accessories

3.1 Introduction to accessories

General

There is a range of tools and equipment available, especially designed for the manipulator.

Basic software and software options for robot and PC

For more information, see *Product specification - Controller IRC5* and *Product specification - Controller software IRC5*.

PickMaster and vision system

For more information, see *Product specification - PickMaster® Twin*.

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