

ROBOTICS

Product specification

IRB 1010



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Product specification

IRB 1010-1.5/0.37

OmniCore

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Overview of this specification

About this product specification

This product specification describes the performance of the manipulator or a complete family of manipulators in terms of:

- The structure and dimensional prints
- The fulfilment of standards, safety, and operating equipment
- The load diagrams, mounting or extra equipment, the motion, and the robot reach
- The specification of available variants and options

The specification covers the manipulator using the OmniCore controller.

Usage

Product specifications are used to find data and performance about the product, for example to decide which product to buy. How to handle the product is described in the product manual.

The specification is intended for:

- Product managers and product personnel
- Sales and marketing personnel
- Order and customer service personnel
- Integrators and customers

References

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

Document name	Document ID
<i>Product manual - IRB 1010</i>	<i>3HAC081964-001</i>
<i>Product specification - OmniCore E line RW 7 (RobotWare 7)</i>	<i>3HAC079823-001</i>
<i>Product specification - OmniCore E line RobotWare 8 (RobotWare 8)</i>	<i>3HAC098716-001</i>
<i>Product specification - OmniCore C line RW 7 (RobotWare 7)</i>	<i>3HAC065034-001</i>
<i>Product specification - OmniCore C line RobotWare 8 (RobotWare 8)</i>	<i>3HAC098715-001</i>
<i>Product manual - OmniCore E10 Type A</i>	<i>3HAC095278-001</i>
<i>Product manual - OmniCore C30 Type B</i>	<i>3HAC097281-001</i>

Revisions

Revision	Description
A	First edition.
B	Published in release 22D. The following updates are done in this revision: • Minor changes.
C	Published in release 23C. The following updates are done in this revision: • The updated robot stopping distances and times are moved to this document, and removed from the generic document, see Robot stopping distances and times on page 59.

Continues on next page

Revision	Description
D	Published in release 24B. The following updates are done in this revision: Added support for OmniCore C30 Type A.
E	Published in release 24C. The following updates are done in this revision: Updated the figure illustrating the top view of the working range.
F	Published in release 24D. The following updates are done in this revision: Added options <i>[3203-X] Mains cable</i>.
G	Published in release 25.3. The following updates are made in this revision: - Company name updated to reflect current legal entities. - Added support for OmniCore E10 Type A controller and removed information for E10. - Updated power consumption data. - Added Clean Room suitability information. - Updated portal name from myABB to ABB Robotics One.
H	Published in release 26.1. The following updates are made in this revision: - Company name updated to reflect current legal entities. - Updated robot introduction and added information of intended use. - Added the section Impacting robot lifetime on page 14. - Reorganized the layout of chapter Technical data for IRB 1010 on page 21 to improve readability. - Added section Accessories on page 79. - Added support for RobotWare 8. - Added support for OmniCore C30 Type B controller and removed information for C30 Type A.
J	Published in release 26B. The following updates are made in this revision: Minor changes.

1 Description of IRB 1010

1.1 About the IRB 1010

General introduction

The IRB 1010 is ABB’s smallest ever industrial robot. With the highest payload of 1.5 kg, class-leading precision 0.01mm, and 30% smaller size, the IRB 1010 allows for the highest productivity and high quality manufacturing.

The robot is equipped with the OmniCore E10 and OmniCore C30 controller and robot control software RobotWare.

Intended use

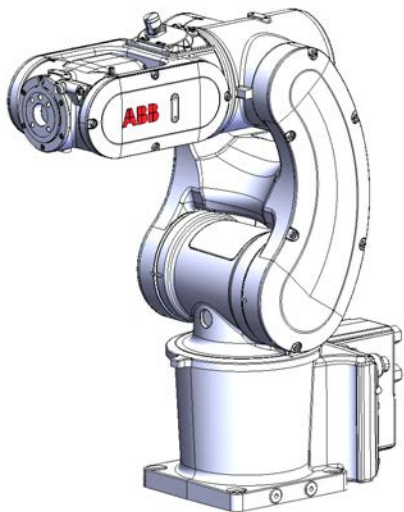
IRB 1010 is designed to meet the trend towards the manufacture of miniaturized electronics and wearable devices. Benefit from its smaller size and lighter weight, the IRB 1010 is easy for deployment and suitable for manufacturing processes in limited spaces, e.g. film peeling.

The IRB 1010 is also an ideal solution for educational applications. Its compact design makes it suitable for installation on classroom desktops, while its ease-of-use enables both teachers and students to quickly master the skills needed for programming and operation.

See [Impacting robot lifetime on page 14](#).

Available variants

The IRB 1010 is available in the following variant(s).



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Robot variant	Handling capacity (kg)	Reach (m)
IRB 1010-1.5/0.37	1.5 kg	0.37 m

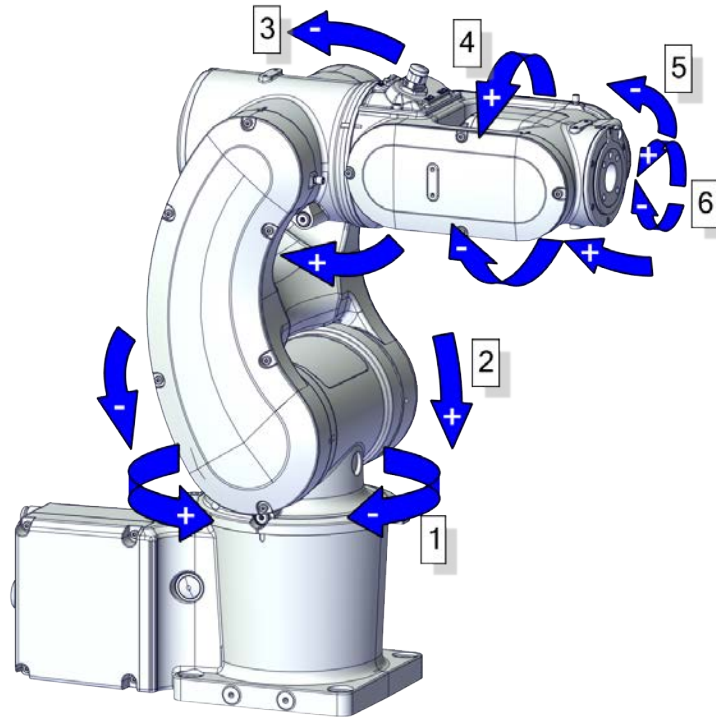
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1 Description of IRB 1010

1.1 About the IRB 1010

Continued

Robot axes

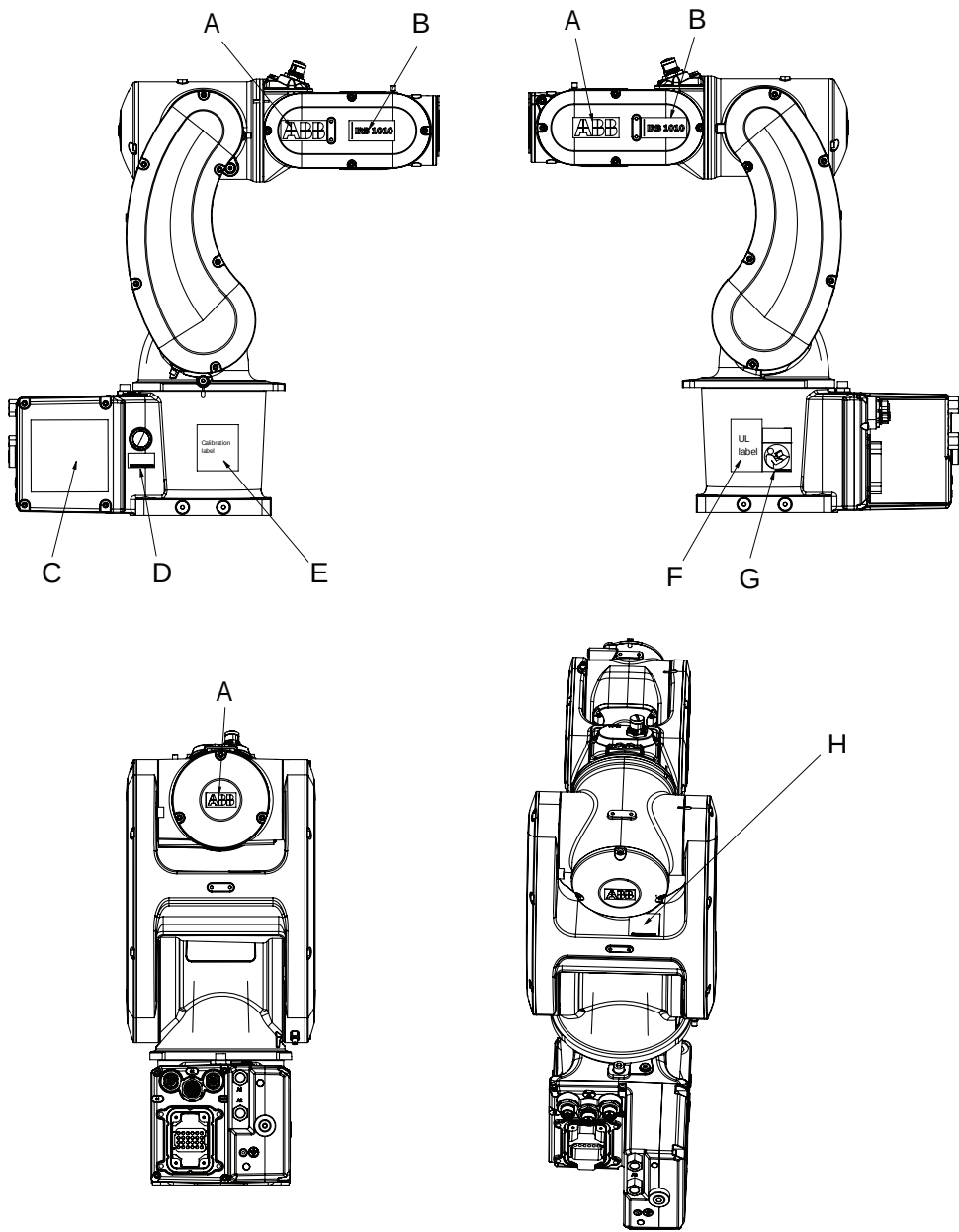


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Location of labels

These figures show the location of the information labels to be inspected.



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A	ABB logo
B	Robot model
C	Rating label, CE label and AbsAcc label
D	Instruction label Brake release
E	Calibration label
F	UL label

Continues on next page

1 Description of IRB 1010

1.1 About the IRB 1010

Continued

G	Read manual label, also specifying warning labels
H	Warning label Crush

Control system

The robot is equipped with the OmniCore 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 *Operating manual - OmniCore*.

We have added a range of software products - all falling under the umbrella designation of Active Safety - to protect not only personnel in the unlikely event of an accident, but also robot tools, peripheral equipment and the robot itself.

The IRB 1010 manipulator can be connected to the following robot controllers:

- OmniCore C30
- OmniCore E10

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 communication features - network communication - and advanced functions such as multitasking, sensor control etc. For a complete description on optional software, see the product specification for the robot controller.

1.2 Standards

1.2.1 Applicable standards

General

This product is designed according to the global product standard ISO 10218-1:2025, *Robots for industrial environments - Safety requirements - Part 1 Robots*. In case of deviation from ISO 10218-1:2025, these are listed in the declaration of incorporation. The declaration of incorporation is part of the delivery.

Robot standards

Standard	Description
ISO 9283	Manipulating industrial robots – Performance criteria and related test methods
ISO 9787	Robots and robotic devices – Coordinate systems and motion nomenclatures
ISO 9946	Manipulating industrial robots – Presentation of characteristics

Other standards used in design

Standard	Description
ISO 9283	Manipulating industrial robots - Performance criteria and related test methods
ISO 9787	Robots and robotic devices -- Coordinate systems and motion nomenclatures
ISO 9946	Manipulating industrial robots - Presentation of characteristics
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
IEC 61326-3-1	Immunity requirements for safety-related systems and for equipment intended to perform safety-related functions (functional safety) – General industrial applications
IEC 61340-5-1	Protection of electronic devices from electrostatic phenomena - General requirements
ANSI/ESD S20.20	Protection of Electrical and Electronic Parts, Assemblies and Equipment (Excluding Electrically Initiated Explosive Devices)

Region specific standards

Standard	Description
UL 1740 (option) CSA Z434 (option)	Standards For Safety - Robots and Robotic Equipment Industrial robots and robot Systems - General safety requirements Valid for USA and Canada.

1.3 Impacting robot lifetime

Introduction

The expected lifetime of a robot is an important factor when planning an installation. This information is aiming to help you to maximize the lifetime of your robot and avoid unnecessary downtime or repair.

The lifetime of a robot is influenced by the following, but not limited to, factors:

- [Robot type selection on page 14](#)
- [Duty factor on page 14](#)
- [Environmental conditions on page 15](#)
- [Application and usage on page 15](#)
- [Design limitations on page 16](#)
- [Maintenance on page 17](#)
- [Individual lifetime variability on page 17](#)
- [Extreme usage on page 17](#)

Robot type selection

Selecting the right robot for the application is generally done based on payload and reach criteria, but other factors can influence the selection, such as the duty factor. Selecting the most suitable variant is crucial to achieve the expected high performance, uptime, and lifetime. Always select a robot in accordance with the intended use, see [Intended use on page 9](#).

ABB robots are capable of high accelerations and speeds. It is generally recommended to use RobotStudio to find out if a robot model is suitable for a specific application and duty factor. RobotStudio is an excellent tool to help with the assessment of the duty factor and the selection of the most suitable robot variant.

This robot is not specifically designed for use in demanding applications with a very high duty factor. If used in such conditions, a significant reduction in lifetime is possible for all axes, depending on the cycle. See [Extreme usage on page 17](#).

When selecting the robot variant, consider using application-specific robot, and suitable protection type.



Note

Use the Mechanical Analysis add-in in RobotStudio (see details below) for help with the assessment, or get technical support from ABB.

Duty factor

Duty factor is the percentage of time the robot is moving divided by the total time, including movement and wait time during the complete robot work cycle. It is a measurement of how much the robot is being used. Gearbox lifetime is reduced more rapidly by a higher duty cycle than by a lower one. See [Extreme usage on page 17](#).

Continues on next page



Note

The duty factor impact on lifetime can be analyzed in the add-in *Mechanical Analysis* in RobotStudio (see details below) and *Service Information System* (SIS) data in the controller. Contact ABB to analyze the SIS data.

Environmental conditions

Following factors within environmental conditions of the robot has an impact on the robot lifetime:

- Temperature:

The robot usage at high temperatures or extreme usage can lead to gearbox and motor cooling problems. Observe operating temperature limits stated in manipulator product manual. Extreme usage normally requires means of reduction of motor and gearbox oil heat.



Note

The add-in *Mechanical Analysis* in RobotStudio (see details below) or technical support from ABB can provide recommendation whether means of reduction of motor and gearbox oil heat is required.

- Exposure to chemicals might impact sealings, which can cause oil leakage.
- Vibrations caused by not following the foundation requirements might cause reduction of lifetime, for example for bearings. See [Requirements, foundation on page 23](#).
- Cleaning. Wrong cleaning can cause particles entering the sealings which can cause oil leakage. Proper cleaning is described in *Product manual - IRB 1010*.

Application and usage

Following factors within robot application and usage has an impact on the robot lifetime:

- Payload definition and overload:

It is important to define the payload within specification and correctly defined tool data. See section [Load diagrams on page 46](#), and *Technical reference manual - RAPID Overview*.

The service routine for load identification, *LoadIdentify*, is available to support tool data definition. See *Operating manual - OmniCore*.

- Acceleration/deceleration:

The gearbox lifetime is reduced more rapidly by high accelerations/decelerations than by lower ones.



Note

Smoother movements bring reduced energy consumption.

Continues on next page

1 Description of IRB 1010

1.3 Impacting robot lifetime

Continued



Note

Acceleration/deceleration can be modified with the instruction AccSet. See *Technical reference manual - RAPID Overview*.

Acceleration/deceleration is optimized by using automatic path planning functionality, either offline, or in RobotStudio, or using the online software.

- Limited movements:

If the range or the rotation angle for an axis is 10° or less, the expected life of the reduction gears may be reduced due to poor lubrication of internal parts or the internal parts being subject to a concentrated load. Add extra lubrication motion to the robot program or to maintenance schedule.



Note

Use RobotStudio *Signal Analyzer* or get technical support from ABB.

- High forces applied externally to the manipulator:

Some applications or not correctly programmed paths apply external forces to the manipulator, which might reduce its lifetime. Example of external force: gripper under constraint when gripping a part or load sharing between multiple robots.

- Number of collisions:

Collisions, especially at high speed and/or with high loads reduce the lifetime of the gearboxes. Avoid collisions and set collision detection sensitivity to the appropriate level.



Note

See the application manual for the controller software, section *Collision detection*, listed in [References on page 7](#).

- Number of emergency stops:

Emergency stops, especially at high speed and/or high loads reduce the lifetime of the gearboxes. Whenever permitted by risk assessment, set the robot stopping functions to stop category 1.



Note

See the product manual for the robot controller, listed in [References on page 7](#).

Design limitations

See the section *Expected component life* in *Product manual - IRB 1010*.

Continues on next page

Maintenance

The maintenance and use of the robot will affect the performance and lifetime. For example:

- Preventive maintenance will optimize the lifetime of the robot. The recommended maintenance activities and intervals are described in *Product manual - IRB 1010*.
- Observance of lubricant types and maintenance periods recommended by ABB.
- Possible pollution of the lubricant by an external cause, for example, water in the oil caused by high humidity.
- Extreme usage, for example high duty factor or environmental factors, will affect the maintenance schedule, for example, shorter intervals for oil change.

Contact your local ABB office to get technical support from ABB.

Individual lifetime variability

The lifetime varies with individual robots. For example, a cycle with a lower duty factor may fail earlier than one with a higher duty factor. But a cycle with a higher duty factor is more likely to fail earlier than a cycle with lower duty factor.

Extreme usage

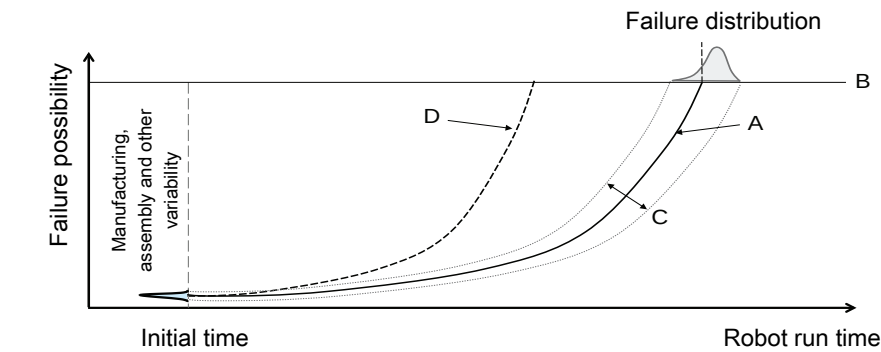
Examples of extreme usage in regard to movement: a stress index range that shows up as red (51) in the RobotStudio add-in *Mechanical Analysis*, press tending application, very severe palletizing applications, major use of axis 1, 2, or 3 movement.

The controller can issue a duty factor warning on the FlexPendant, if applicable. See the chapter *Troubleshooting* in *Product manual - IRB 1010*.

Extreme usage requires specific maintenance, for example, shorter interval for oil change. See *Maintenance schedule* in *Product manual - IRB 1010*.

Summary

The diagram illustrates the relationship between robot run time and failure possibility.



xx2500001942

A	Design lifetime
---	-----------------

Continues on next page

1 Description of IRB 1010

1.3 Impacting robot lifetime

Continued

B	Failure threshold
C	Individual variability
D	Negatively affected lifetime

The curve (A) represents the design lifetime, showing how failure probability increases over time following a normal distribution pattern. The failure threshold (B) indicates the point at which component failure becomes likely.

Individual variability between robots is shown by the dotted lines (C), representing the natural variation in component life due to manufacturing, assembly, and other factors. This variability means that while most robots will follow the design lifetime curve, some individual units may experience earlier or later failures within the normal distribution.

As highlighted with the curve (D) in the diagram, robot lifetime can be negatively affected by not following best practices in the key areas discussed in this chapter:

- [Robot type selection on page 14](#)
- [Duty factor on page 14](#)
- [Environmental conditions on page 15](#)
- [Application and usage on page 15](#)
- [Maintenance on page 17](#)

By adhering to the recommendations outlined in each of these sections, users can maximize their robot's operational lifetime and ensure performance stays within the design lifetime curve, avoiding premature failure and unnecessary downtime.

Available tools

There are several tools available throughout the lifecycle of an ABB robot, from support with selecting the most suitable manipulator and optimizing its lifetime, to operation, maintenance, and repair:

ABB toolbox	Type	Product lifecycle		
		Sales, pre-study	Installation, commissioning	Operation, maintenance, repair
Product specification	Document	x	x	
Product manual	Document		x	x
Mechanical Analysis add-in	Add-in in RobotStudio	x	x	x
Service Information System (SIS) / Condition Based Maintenance (CBM)	RobotWare functionality / Customer service analysis		x	x
Connected Services	Hardware and Software		x	x
Automatic Path Planning	RobotStudio functionality and online software	x	x	(x)

Continues on next page

ABB toolbox	Type	Product lifecycle		
		Sales, pre-study	Installation, commissioning	Operation, maintenance, repair
Signal Analyzer / TuneMaster	RobotStudio functionality / Software	x	x	x
ABB support	Customer support	x	x	x

1 Description of IRB 1010

1.4 Maintenance and troubleshooting

1.4 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 gearboxes.
- The cabling is routed for longevity, and in the unlikely event of a failure.

Maintenance

The maintenance intervals depend on the use of the robot. The required maintenance activities also depend on the selected options. For detailed information on maintenance procedures, see the maintenance section in *Product manual - IRB 1010*.

Troubleshooting

The robot has built-in communication that shows information on the FlexPendant. These messages facilitates troubleshooting and are an integral part of the control system. Troubleshooting procedures are describes in the product manual for the manipulator and the controller respectively.

2 Technical data for IRB 1010

2.1 Technical data

Weight, robot

The table shows the weight of the robot.

Robot model	Nominal weight
IRB 1010	13.5 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
Floor mounted	0° ⁱ
Suspended	180°

ⁱ A tilt of up to 5° does not affect the payload or reach, but it can have a negative impact on performance and lifetime. The actual value must be set in the system parameters.



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.

On robots running RobotWare 8, it is also possible to configure the mounting position on the FlexPendant, see the integrator's guide for the controller.

Loads on foundation, robot

The illustration shows the directions of the robots stress forces.

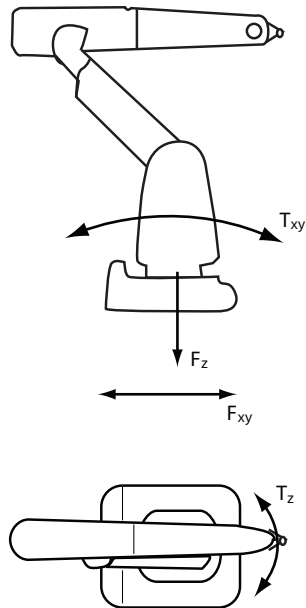
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2 Technical data for IRB 1010

2.1 Technical data

Continued

The directions are valid for all floor mounted, table mounted, wall mounted and suspended robots.



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F_{xy}	Force in any direction in the XY plane
F_z	Force in the Z plane
T_{xy}	Bending torque in any direction in the XY plane
T_z	Bending torque in the Z plane

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).

Floor mounted

Force	Endurance load (in operation)	Maximum load (emergency stop)
Force xy	150 N	264 N
Force z	200 N	353 N
Torque xy	70 Nm	121 Nm
Torque z	30 Nm	51 Nm

Continues on next page

Suspended

Force	Endurance load (in operation)	Max. load (emergency stop)
Force xy	150 N	340 N
Force z	340 N	493 N
Torque xy	70 Nm	121 Nm
Torque z	30 Nm	51 Nm

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	0.1/500 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. In order to compensate for an uneven surface, the robot can be recalibrated during installation. If resolver/encoder calibration is changed this will influence the absolute accuracy
Minimum resonance frequency	22 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 .
Minimum foundation material yield strength	150 MPa	

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 (-13 °F)
Maximum ambient temperature	+55 °C (+131 °F)
Maximum ambient temperature (less than 24 hrs)	+70 °C (+158 °F)

Continues on next page

2 Technical data for IRB 1010

2.1 Technical data

Continued

Parameter	Value
Maximum ambient humidity	95% at constant temperature (gaseous only)

Operating conditions, robot

The table shows the allowed operating conditions for the robot:

Parameter	Value
Minimum ambient temperature	0 °C ⁱ (32 °F)
Maximum ambient temperature	+45 °C (113 °F)
Maximum ambient humidity	95% at constant temperature

ⁱ At low environmental temperature (below 10 °C) a warm-up phase is recommended to be run with the robot. Otherwise there is a risk that the robot stops or runs with lower performance due to temperature dependent oil and grease viscosity.

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	IP40

ⁱ According to IEC 60529.

Clean room suitability, robot

The table shows the suitability for clean room environment for the valid protection types of the robot.

Protection type	Protection class
Manipulator, suitability class (protection type Standard)	ISO 5 ⁱ

ⁱ Air Cleanliness Class for the robot was assessed in compliance with DIN EN ISO 14644-1, -14.

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.*

2.2 Other technical data

Airborne noise level

Description	Note	Data
Airborne noise level	The sound pressure level outside the working space.	56.2 dB (A) Leq (acc. to machinery directive 2006/42/EC)



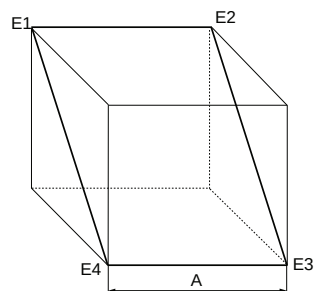
Note

The noise emission from a robot system, actual application, depends on programmed path, payload, cycle time, mounting position, environment etc.

Power consumption at max load

Type of movement	IRB 1010 (all variants)
ISO Cube Max. velocity	0.16 kW

Robot in calibration position	IRB 1010 (all variants)
Brakes engaged	0.06 kW
Brakes disengaged	0.06 kW



xx1000000101

Pos	Description
A	170 mm

2 Technical data for IRB 1010

2.3.1 Introduction to installation

2.3 Mechanical data for installation

2.3.1 Introduction to installation

General

IRB 1010 is available in one variant and it can be floor mounted, inverted, or tilted mounted.

All detailed installation instructions are described in *Product manual - IRB 1010*.

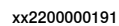
Attachment screws

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

Suitable screws	M8x30 (robot installation directly on foundation)
Quantity	4 pcs
Quality	8.8
Suitable washer	8.4 x 16 x 1.6
Guide pins	2 pcs, D6x20, ISO 2338 - 6m6x20 - A1
Tightening torque	20 Nm±2 Nm
Length of thread engagement	Minimum 14 mm for ground with material yield strength 150 MPa
Level surface requirements	0.1/500 mm

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



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3HAC081966-001 Revision: J

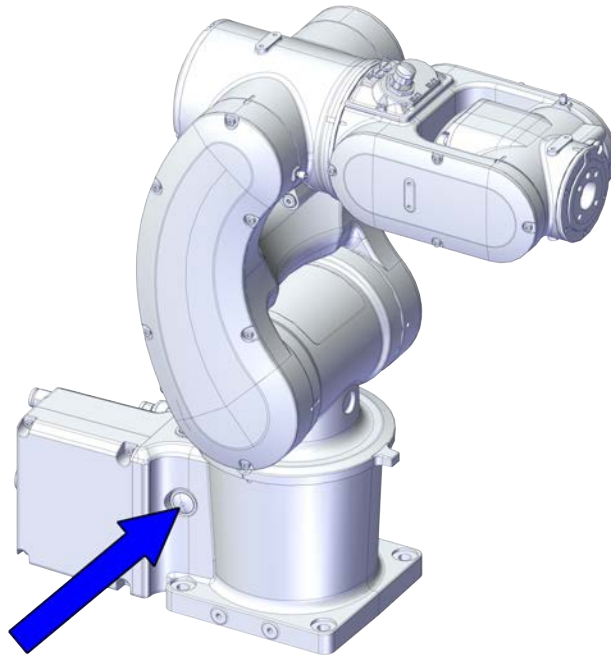
2 Technical data for IRB 1010

2.3.1 Introduction to installation

Continued

Location of the brake release unit

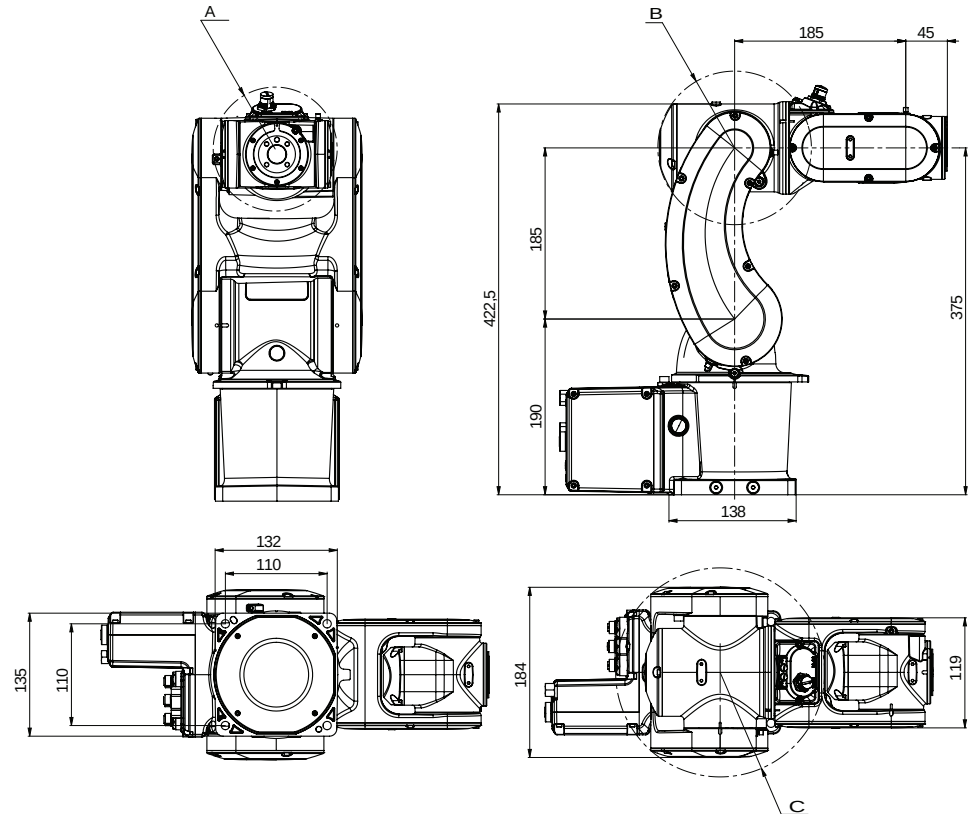
The brake release unit is located as shown in the figure.



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2.3.2 Dimensions

Main dimensions of IRB 1010-1.5/0.37



xx2200000188

Pos	Description
A	Turning radius: R67
B	Turning radius: R83
C	Turning radius: R113

2 Technical data for IRB 1010

2.3.3 Fitting equipment on the robot

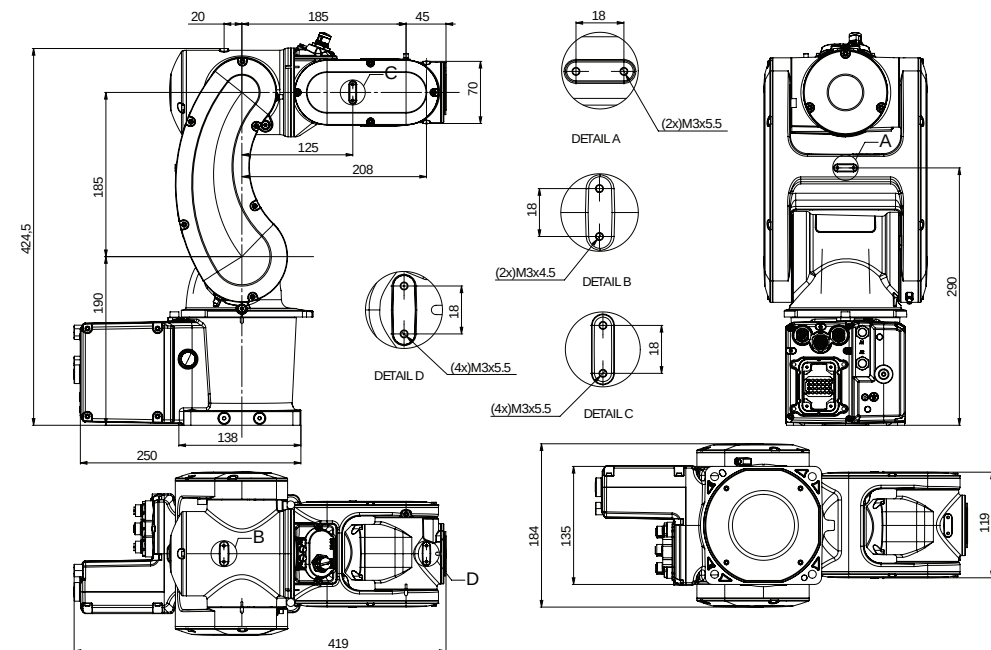
2.3.3 Fitting equipment on the robot

Attachment holes and dimensions

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.

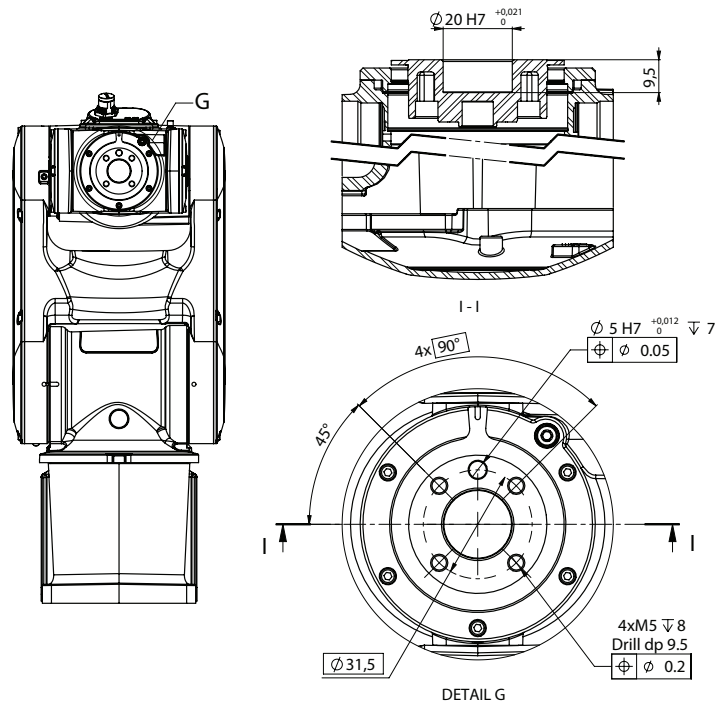
Holes for fitting extra equipment



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Continues on next page

Tool flange standard



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CAUTION

To calibrate the axis 6, the notch on the wrist must be aligned with the marked pin hole on the tool flange. Before installing a tool on the tool flange, make sure a visible mark has been made to the tool at the corresponding position.

For details about the synchronization mark, see [Synchronization marks and synchronization position for axes on page 39](#).

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.

2 Technical data for IRB 1010

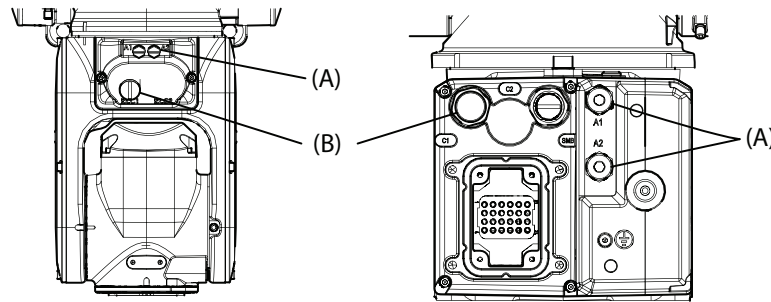
2.3.4 Customer connections

2.3.4 Customer connections

Introduction to customer connections

The cables for customer connection are integrated in the robot and the connectors are placed on the wrist and at the base. There is one connector R2.C1 at the wrist. Corresponding connector R1.C1 is located at the base.

Hose for compressed air is also integrated into the manipulator. There are 2 inlets at the base (R1/8") and 2 outlets (M5) on the wrist.



xx2200000194

Position	Connection	Description	Number	Value
A	Air	Max. 5 bar	2	Outer diameter of air hose: 4 mm
B	(R1)R2.C1	Customer power/signal	12 wires	30 V, 1.54 A

Connector kits (optional)

Connector kits, base

R1.C1 connector on the base is part of the CP/CS cable. For details about the robot cabling, see "Robot cabling and connection points" in robot product manual.

Connector kits, wrist

The table describes the CP/CS connector kits for wrist.

Position	Description		Art. no.
Connector kits	CP/CS	M12 CPCS Male straight connector kits	3HAC066098-001
		M12 CPCS Male angled connector kits	3HAC066099-001

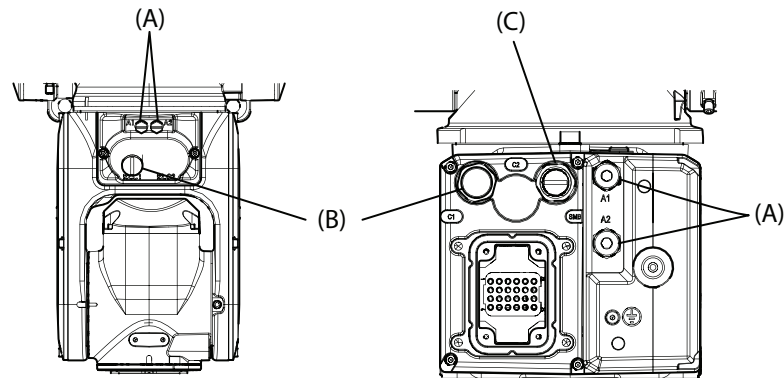
Protection covers

Protection covers for water and dust proofing

Protection covers are delivered together with the robot and must be well fitted to the connectors in any application requiring water and dust proofing.

Always remember to refit the protection covers after removing them.

Continues on next page



xx2200000195

A	Air hose connector protection covers
B	CP/CS connector protection covers
C	SMB connector protection cover

2.3.5 Setting the system parameters for an inverted or a tilted robot

General

The robot is configured for mounting parallel to the floor, without tilting, on delivery. If the robot is mounted in any other angle than 0° , then the system parameters that describe the mounting angle (how the robot is oriented relative to the gravity) must be re-defined.



Note

With inverted installation, make sure that the gantry or corresponding structure is rigid enough to prevent unacceptable vibrations and deflections, so that optimum performance can be achieved.



Note

The mounting positions are described in [Mounting positions on page 21](#), and the requirements on the foundation are described in [Requirements, foundation on page 23](#).

System parameters



Note

The mounting angle must be configured correctly in the system parameters so that the robot system can control the movements in the best possible way. An incorrect definition of the mounting angle will result in:

- Overloading the mechanical structure.
- Lower path performance and path accuracy.
- Some functions will not work properly, for example *Load Identification* and *Collision detection*.

Gravity Beta

When the robot is mounted other than floor-standing (rotated around the y-axis), the robot base frame and the system parameter *Gravity Beta* must be redefined. If the robot is mounted upside down (inverted), then *Gravity Beta* should be π (+3.141593).

The *Gravity Beta* is a positive rotation direction around the y-axis in the base coordinate system. The value is set in radians.

Gravity Alpha

The *Gravity Alpha* is a positive rotation direction around the x-axis in the base coordinate system. The value is set in radians.

Continues on next page



Note

The system parameter *Gravity Alpha* is not supported for all robot types.
If the robot does not support *Gravity Alpha*, then use *Gravity Beta* along with the re-calibration of axis 1 to define the rotation of the robot around the x-axis.



Note

The parameter is supported for all robots on track when the system parameter *7 axes high performance motion* is set, see *Technical reference manual - System parameters*.

Gamma Rotation

Gamma Rotation defines the orientation of the robot foot on the travel carriage (track motion).

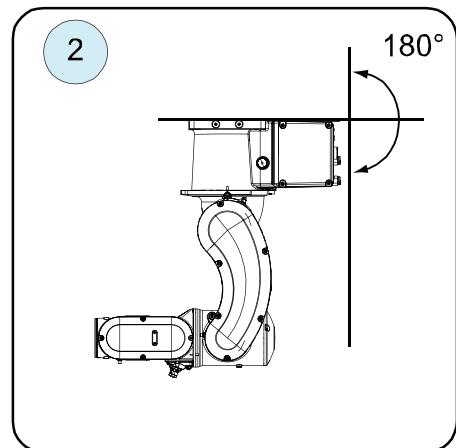
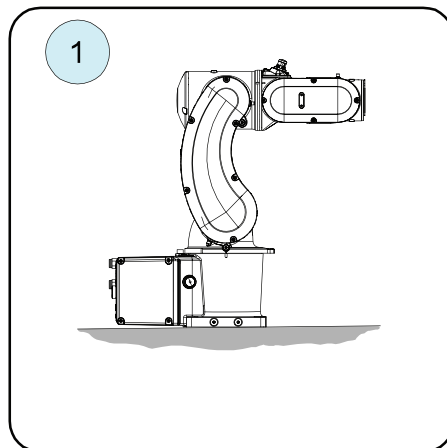
Mounting angles and values

The parameter *Gravity Beta* (or *Gravity Alpha*) specifies the mounting angle of the robot in radians. It is calculated in the following way.

$\text{Gravity Beta} = A^\circ \times 3.141593/180 = B \text{ radians}$, where A is the mounting angle in degrees and B is the mounting angle in radians.

Example of position	Mounting angle (A °)	Gravity Beta
Floor mounted	0°	0.000000 (Default)
Inverted mounting	180°	3.141593

Examples of mounting angles tilted around the Y axis (*Gravity Beta*)



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Pos 1	Floor mounted
Pos 2	Mounting angle 180° (Suspended)

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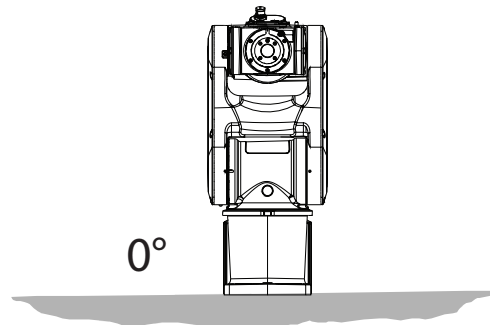
2 Technical data for IRB 1010

2.3.5 Setting the system parameters for an inverted or a tilted robot

Continued

Examples of mounting angles tilted around the X axis (*Gravity Alpha*)

The following illustration shows the IRB 120, but the same principle applies for all robots.



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Mounting angle	Gravity Alpha
0° (Floor mounted)	0



Note

For suspended robots (180°), it is recommended to use *Gravity Beta* instead of *Gravity Alpha*.

Defining the system parameters in RobotWare

The value of the system parameters that define the mounting angle must be redefined when changing the mounting angle of the robot. The parameters belong to the type *Robot*, in the topic *Motion*.

The system parameters are described in *Technical reference manual - System parameters*.

The system parameters are configured in RobotStudio or on the FlexPendant.

2.4 Calibration and references

2.4.1 Calibration methods

Overview

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

The original calibration data delivered with the robot is generated when the robot is floor mounted. If the robot is not floor mounted, then the robot accuracy could be affected. The robot needs to be calibrated after it is mounted.

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
Absolute accuracy calibration (optional)	Based on standard calibration, and besides positioning the robot at synchronization position, the Absolute accuracy calibration also compensates for: - Mechanical tolerances in the robot structure - Deflection due to load Absolute accuracy calibration focuses on positioning accuracy in the Cartesian coordinate system for the robot. Absolute accuracy calibration data is found on the serial measurement board (SMB) or other robot memory. A robot calibrated with Absolute accuracy has the option information printed on its name plate (OmniCore). To regain 100% Absolute accuracy performance, the robot must be recalibrated for absolute accuracy after repair or maintenance that affects the mechanical structure.	CalibWare
Optimization	Optimization of TCP reorientation performance. The purpose is to improve reorientation accuracy for continuous processes like welding and gluing. Wrist optimization will update standard calibration data for axes 4 and 5.  Note For advanced users, it is also possible to do the wrist optimization using the RAPID instruction <code>WristOpt</code> , see <i>Technical reference manual - RAPID Instructions, Functions and Data types</i> . This instruction is only available for OmniCore robots.	Wrist Optimization

Continues on next page

2 Technical data for IRB 1010

2.4.1 Calibration methods

Continued

Brief description of calibration methods

Axis Calibration method

Axis Calibration is a standard calibration method for calibration of IRB 1010. 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.

Wrist Optimization method

Wrist Optimization is a method for improving reorientation accuracy for continuous processes like welding and gluing and is a complement to the standard calibration method.

The actual instructions of how to perform the wrist optimization procedure is given on the FlexPendant.

CalibWare - Absolute Accuracy calibration

The CalibWare tool guides through the calibration process and calculates new compensation parameters. This is further detailed in the *Application manual - CalibWare Field*.

If a service operation is done to a robot with the option Absolute Accuracy, a new absolute accuracy calibration is required in order to establish full performance. For most cases after replacements that do not include taking apart the robot structure, standard calibration is sufficient.

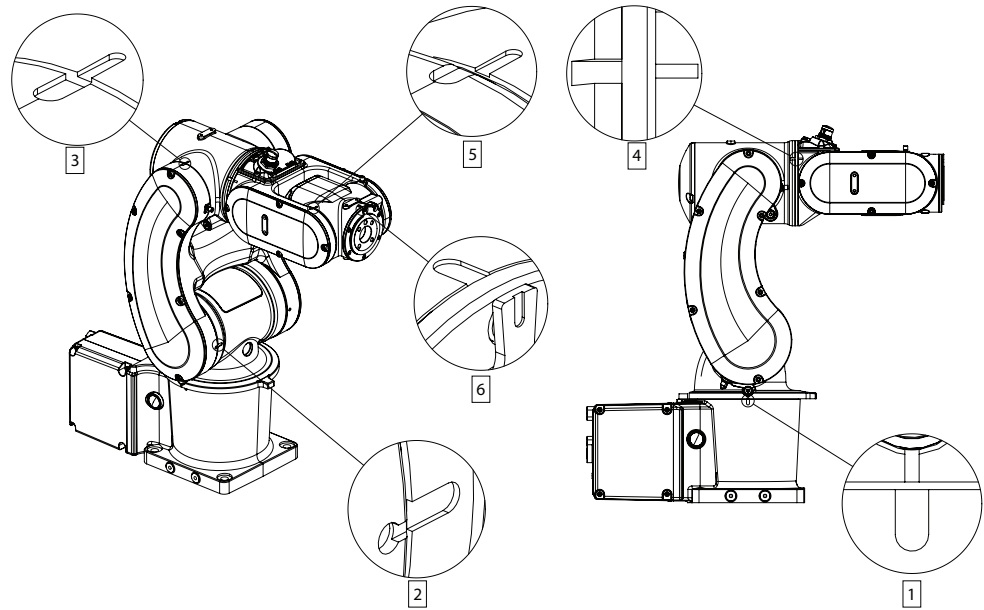
The Absolute Accuracy option varies according to the robot mounting position. This is printed on the robot name plate for each robot. The robot must be in the correct mounting position when it is recalibrated for absolute accuracy.

2.4.2 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 1010



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2 Technical data for IRB 1010

2.4.3 Calibration movement directions for all axes

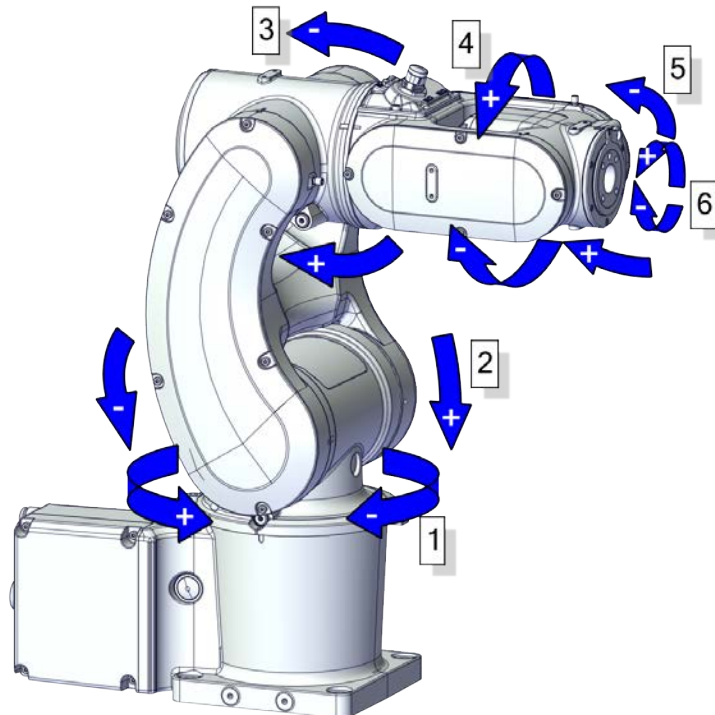
2.4.3 Calibration movement directions for all axes

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.

Manual movement directions

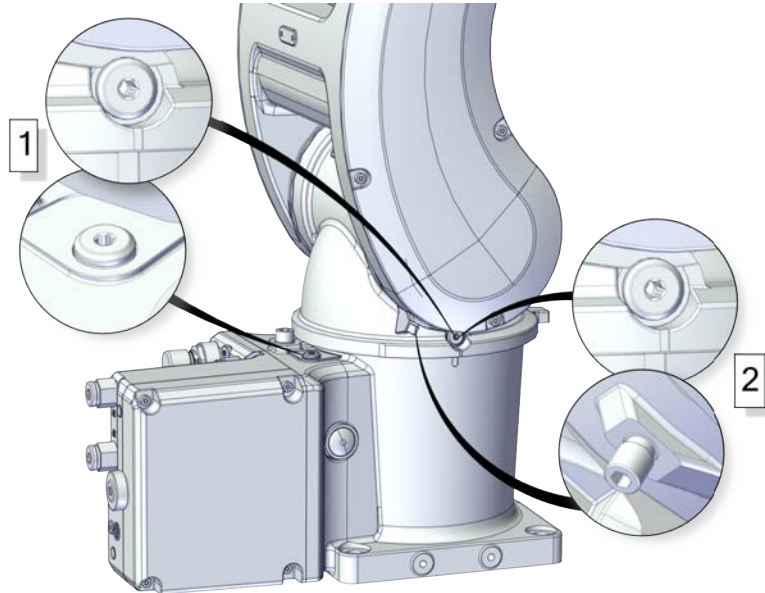


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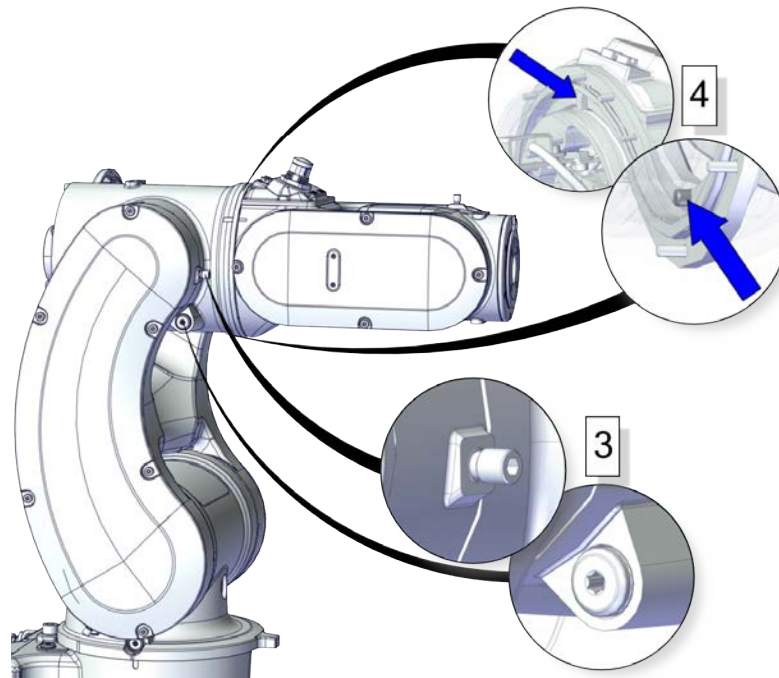
2.4.4 Fine calibration

General

The fine calibration is done with the Axis calibration method.



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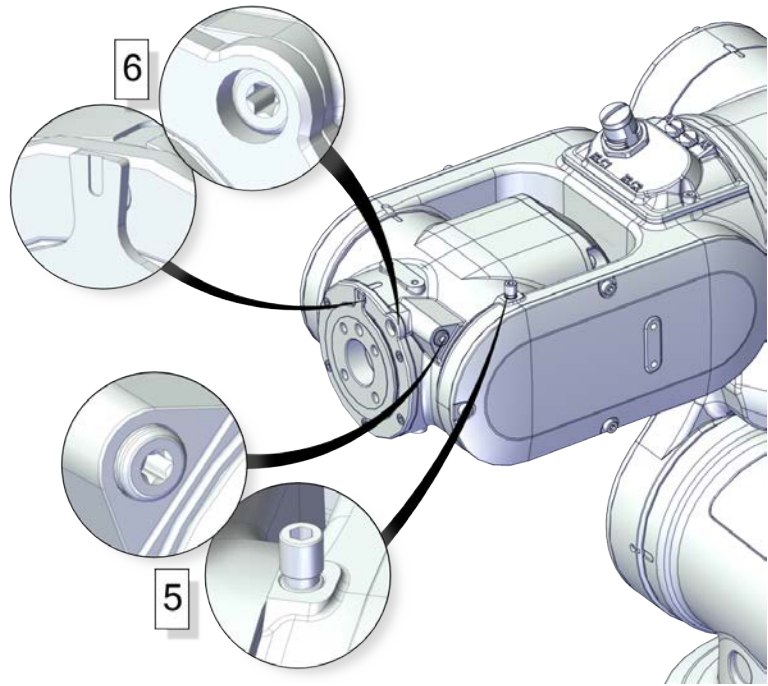


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2 Technical data for IRB 1010

2.4.4 Fine calibration
Continued



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Calibration tools for Axis Calibration

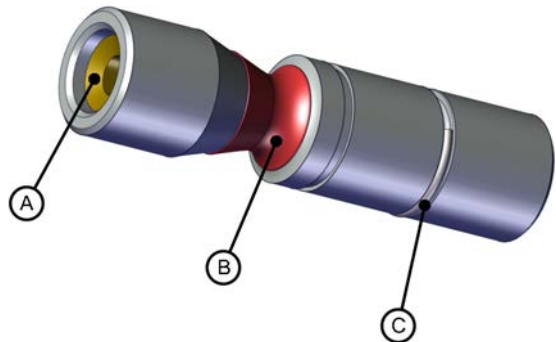
Check prior to usage

Before using the calibration tool, make sure that the tube insert, the plastic protection and the steel spring ring are present.



WARNING

If any part is missing or damaged, the tool must be replaced immediately.



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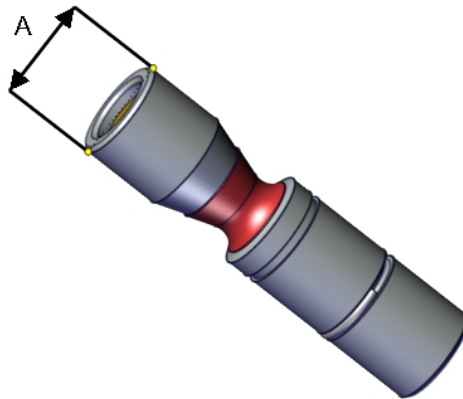
A	Tube insert
B	Plastic protection
C	Steel spring ring

Continues on next page

Periodic check of the calibration tool

If including the calibration tool in a local periodic check system, the following measures should be checked.

- Outer diameter within $\varnothing 12g4$ mm, $\varnothing 8g4$ mm or $\varnothing 6g5$ mm (depending on calibration tool size).
- Straightness within 0.005 mm.



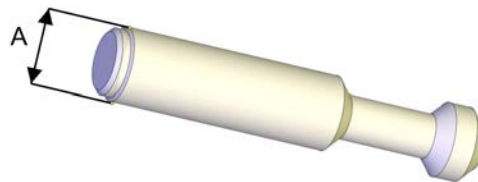
xx1500000951

A	Outer diameter
---	----------------

Periodic check of the calibration tool with smaller outer diameter (3HAC058238-001)

If including the calibration tool with smaller outer diameter in a local periodic check system, the following measures should be checked.

- Outer diameter within $\varnothing 5g5$ mm.
- Straightness within 0.005 mm.



xx1600001142

A	Outer diameter
---	----------------

2.4.5 Absolute Accuracy calibration

Purpose

Absolute Accuracy is a calibration concept that improves TCP accuracy. The difference between an ideal robot and a real robot can be several millimeters, resulting from mechanical tolerances and deflection in the robot structure. *Absolute Accuracy* compensates for these differences.

Here are some examples of when this accuracy is important:

- Exchangeability of robots
- Offline programming with no or minimum touch-up
- Online programming with accurate movement and reorientation of tool
- Programming with accurate offset movement in relation to, for example, vision systems or offset programming
- Re-use of programs between applications

The option *Absolute Accuracy* is integrated in the controller algorithms and does not need external equipment or calculation.



Note

The performance data is applicable to the corresponding RobotWare version of the individual robot.



Note

Singularities might appear in slightly different positions on a real robot compared to RobotStudio, where *Absolute Accuracy* is off compared to the real controller.

What is included

Every *Absolute Accuracy* robot is delivered with:

- compensation parameters saved in the robot memory
- a birth certificate representing the *Absolute Accuracy* measurement protocol for the calibration and verification sequence.

A robot with *Absolute Accuracy* calibration has a label with this information on the manipulator.

Absolute Accuracy supports floor mounted, wall mounted, and ceiling mounted installations. The compensation parameters that are saved in the robot memory differ depending on which *Absolute Accuracy* option is selected.

When is *Absolute Accuracy* being used

Absolute Accuracy works on a robot target in Cartesian coordinates, not on the individual joints. Therefore, joint based movements (e.g. MoveAbsJ) will not be affected.

If the robot is inverted, the *Absolute Accuracy* calibration must be performed when the robot is inverted.

Continues on next page

Absolute Accuracy active

Absolute Accuracy will be active in the following cases:

- Any motion function based on robtargets (e.g. MoveL) and ModPos on robtargets
- Reorientation jogging
- Linear jogging
- Tool definition (4, 5, 6 point tool definition, room fixed TCP, stationary tool)
- Work object definition

Absolute Accuracy not active

The following are examples of when Absolute Accuracy is not active:

- Any motion function based on a jointtarget (MoveAbsJ)
- Independent joint
- Joint based jogging
- Additional axes
- Track motion



Note

In a robot system with, for example, an additional axis or track motion, the Absolute Accuracy is active for the manipulator but not for the additional axis or track motion.

RAPID instructions

There are no RAPID instructions included in this option.

Production data

Typical production data regarding calibration are:

Robot	Positioning accuracy (mm)		
	Average	Max	% Within 1 mm
IRB 1010-1.5/0.37	N/A	N/A	N/A

2.5 Load diagrams

2.5.1 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 and/or loads are outside load diagram is used the following parts can be damaged due to overload:

- motors
- gearboxes
- mechanical structure



WARNING

In the robot system the service routine LoadIdentify is available, which allows the user to make an automatic definition of the tool and load, to determine correct load parameters.

See *Operating manual - OmniCore*, for detailed information.



WARNING

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

General

At different moment of inertia the load diagram will be changed. For robots that are allowed floor, tilted or inverted mounted, the load diagrams as given are valid and thus it is also possible to use RobotLoad within those tilt and axis limits.

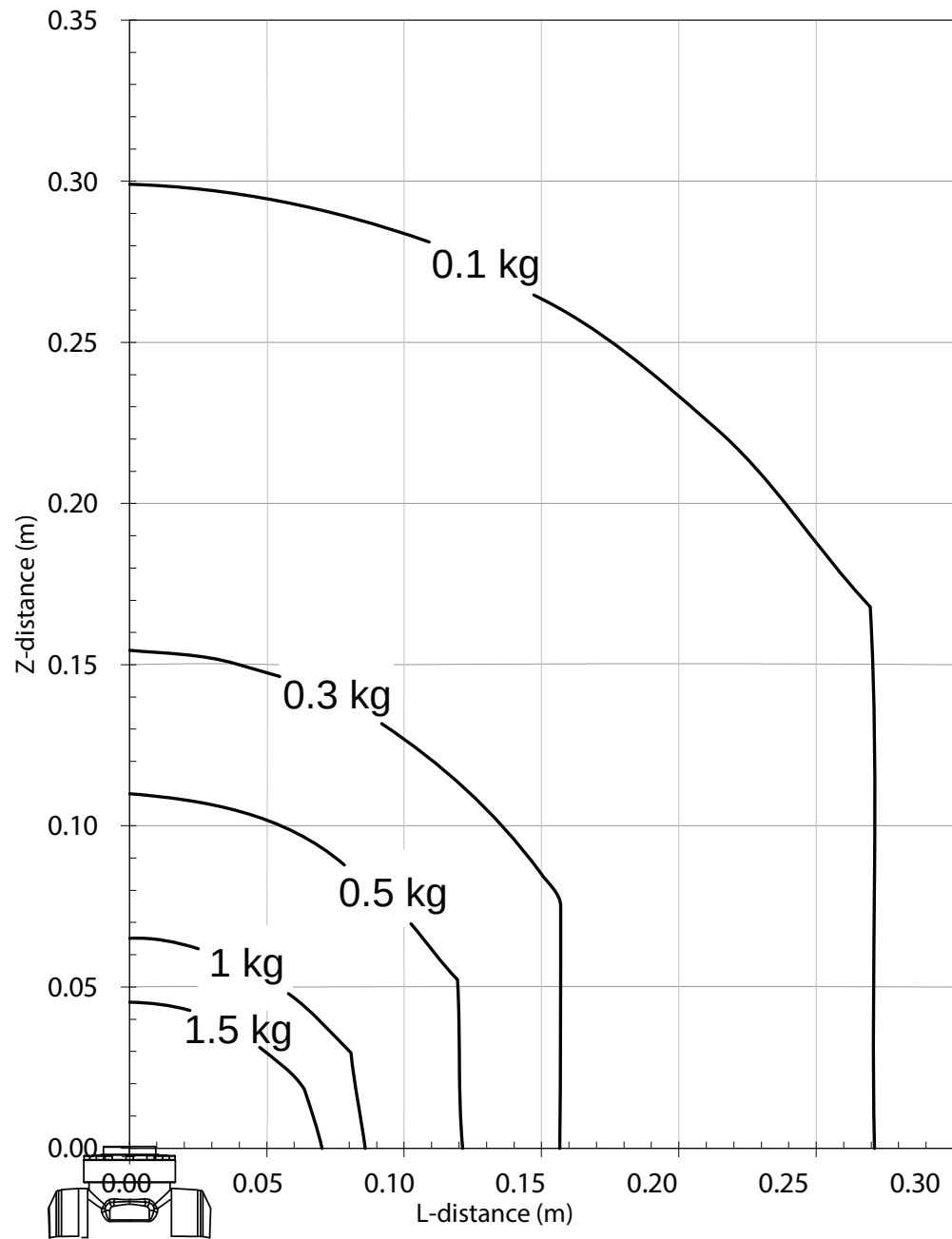
Control of load case by "RobotLoad"

To verify a specific load case, use the RobotStudio add-in RobotLoad.

The result from RobotLoad is only valid within the maximum loads and tilt angles. There is no warning if the maximum permitted arm load is exceeded. For over-load cases and special applications, contact ABB for further analysis.

2.5.2 Diagrams

Diagrams of IRB 1010-1.5/0.37



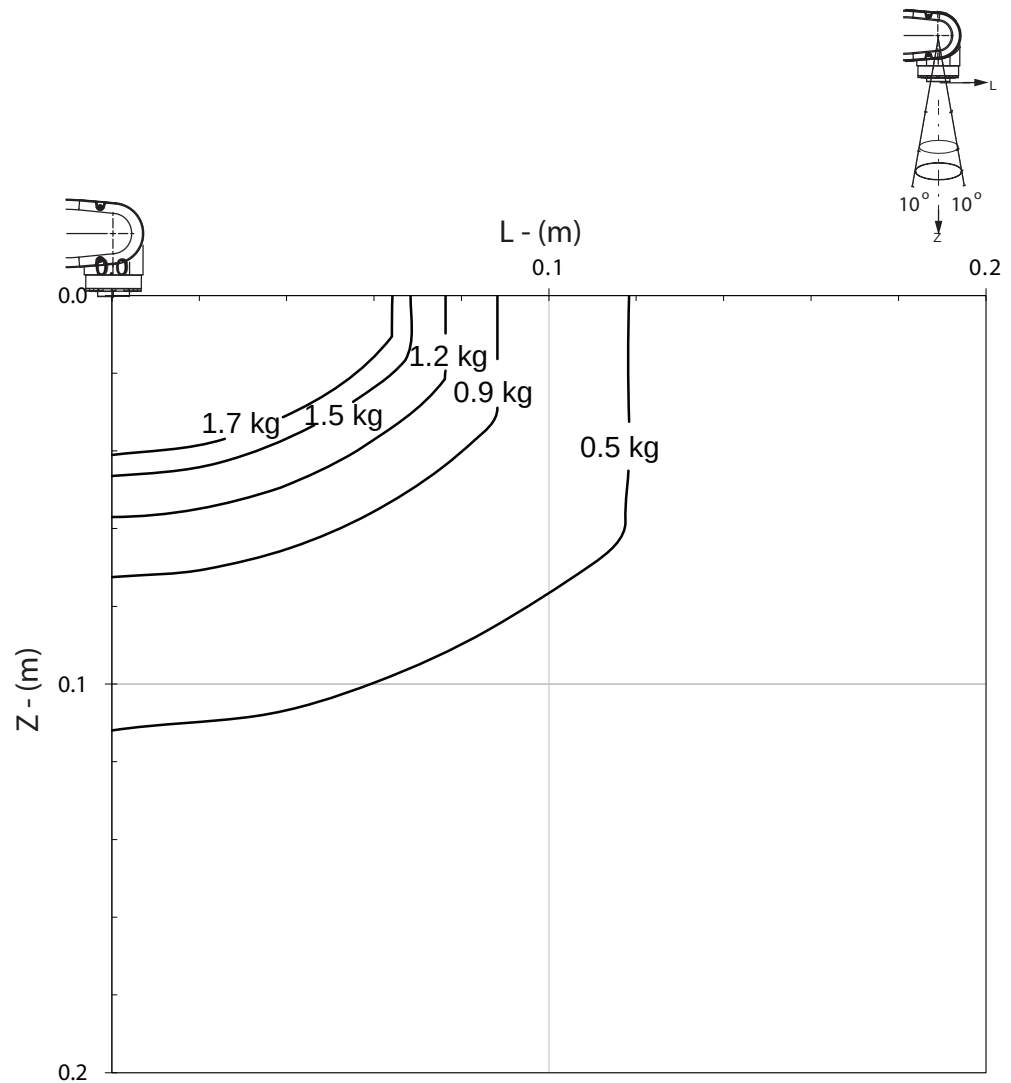
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2 Technical data for IRB 1010

2.5.2 Diagrams
Continued

Diagrams of IRB 1010-1.5/0.37"Vertical Wrist" ($\pm 10^\circ$)



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For wrist down (0° deviation from the vertical line).

	Description
Max load	1.7 kg
Z _{max}	0.041 m
L _{max}	0.064 m

2.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement

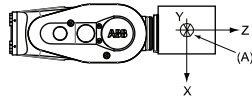
2.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement

**Note**

Total load given as: mass in kg, center of gravity (Z and L) in meters and moment of inertia (J_{ox} , J_{oy} , J_{oz}) in kgm^2 . $L = \sqrt{X^2 + Y^2}$, see the following figure.

Full movement of axis 5 ($\pm 125^\circ$)

5	IRB 1010-1.5/0.37	$Ja_5 = \text{Load} \times ((Z + 0.043)^2 + L^2) + \max(J_{ox}, J_{oy}) \leq 0.016 \text{ kgm}^2$
6	IRB 1010-1.5/0.37	$Ja_6 = \text{Load} \times L^2 + J_{oz} \leq 0.011 \text{ kgm}^2$



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Pos	Description
A	Center of gravity

	Description
J_{ox} , J_{oy} , J_{oz}	Max. moment of inertia around the X, Y and Z axes at center of gravity.

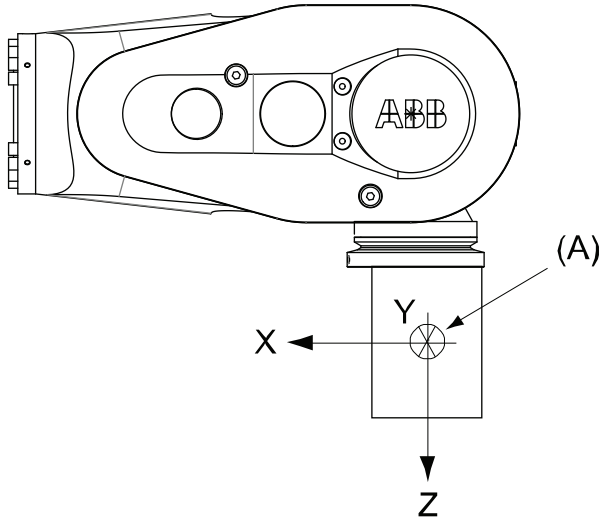
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2 Technical data for IRB 1010

2.5.3 Maximum load and moment of inertia for full and limited axis 5 (center line down) movement *Continued*

Limited axis 5, center line down

5	IRB 1010-1.5/0.37	$Ja_5 = \text{Load} \times ((Z + 0.043)^2 + L^2) + \max(J_{0x}, J_{0y}) \leq 0.016 \text{ kgm}^2$
6	IRB 1010-1.5/0.37	$Ja_6 = \text{Load} \times L^2 + J_{0z} \leq 0.011 \text{ kgm}^2$



xx1400002029

Pos	Description
A	Center of gravity
Description	
J_{0x}, J_{0y}, J_{0z}	Max. moment of inertia around the X, Y and Z axes at center of gravity.

2.5.4 Wrist torque



Note

The wrist torque values are for reference only, and should not be used for calculating permitted load offset (position of center of gravity) within the load diagram, since those also are limited by main axes torques as well as dynamic loads. Furthermore, arm loads will influence the permitted load diagram. To find the absolute limits of the load diagram, use the RobotStudio add-in RobotLoad.

Torque

The table below shows the maximum permissible torque due to payload.

Robot variant	Max wrist torque axis 4 and 5	Max wrist torque axis 6	Max torque valid at load
IRB 1010-1.5/0.37	1.3 Nm	1 Nm	1.5 kg

2 Technical data for IRB 1010

2.5.5 Maximum TCP acceleration

2.5.5 Maximum TCP acceleration

General

Higher values can be reached with lower loads than the nominal because of our dynamical motion control QuickMove2. For specific values in the unique customer cycle, or for robots not listed in the table below, we recommend to use RobotStudio.

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 1010-1.5/0.37	80.6	44.7



Note

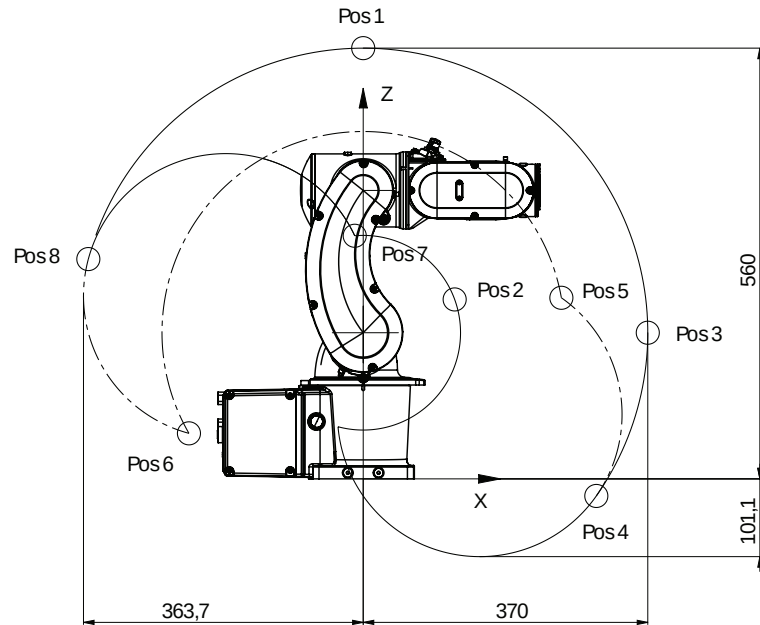
Acceleration levels for emergency stop and controlled motion includes acceleration due to gravitational forces. Nominal load is defined with nominal mass and cog with max offset in Z and L (see the load diagram).

2.6 Working range

2.6.1 Working range

Illustration, working range IRB 1010-1.5/0.37

This illustration shows the unrestricted working range of the robot.



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Positions at wrist center and angle of axes 2 and 3

Position in the figure	Positions at wrist center (mm)		Angle (degrees)	
	X	Z	axis 2	axis 3
pos0	+185	+375	0°	0°
pos1	0	+560	0°	-90°
pos2	+118.9	+233.3	0°	+50°
pos3	+370	+190	+90°	-90°
pos4	+303.1	-22.2	+125°	-90°
pos5	+270.5	+225.6	+125°	-180°
pos6	-226.6	+59.2	-75°	-180°
pos7	-11.0	+316.1	-75°	+50°
pos8	-357.4	+285.8	-75°	-90°

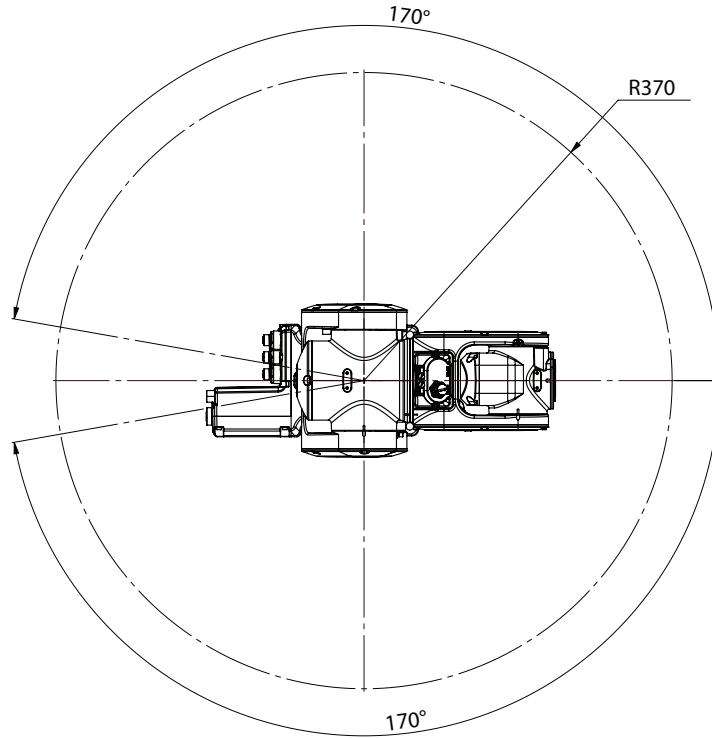
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2 Technical data for IRB 1010

2.6.1 Working range

Continued

Top view of working range



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Working range

Axis	Working range	Note
Axis 1	$\pm 170^\circ$	
Axis 2	$-75^\circ / +125^\circ$	
Axis 3	$-180^\circ / +50^\circ$	
Axis 4	$\pm 170^\circ$	
Axis 5	$\pm 125^\circ$	
Axis 6	$\pm 360^\circ$	Default value.
	$\pm 242^\circ$	Maximum revolution value. The default working range for axis 6 can be extended by changing parameter values in the software.

2.6.2 Adjusting the working range

Reasons for adjusting the manipulator working range

The working range of each manipulator axis is configured in the software. If there is a risk that the manipulator may collide with other objects at installation site, its working space should be limited. The manipulator must always be able to move freely within its entire working space.

Working range configurations

The parameter values for the axes working range can be altered within the allowed working range and according to available options for the robot, either to limit or to extend a default working range. Allowed working ranges and available options for each manipulator axis are specified in [Working range on page 54](#).

Mechanical stops on the manipulator

Mechanical stops are and can be installed on the manipulator as limiting devices to ensure that the manipulator axis does not exceed the working range values set in the software parameters.



Note

The mechanical stops are only installed as safety precaution to physically stop the robot from exceeding the working range set. A collision with a mechanical stop always requires actions for repair and troubleshooting.

Axis	Fixed mechanical stop ⁱ	Movable mechanical stop ⁱⁱ
Axis 1	yes	yes The working range can be reduced by altering the parameter values. Installation of additional mechanical stops is recommended as a safety measure. Additional mechanical stops are not delivered with the robot and shall be designed according to actual applications and site requirements. See Installing movable mechanical stops on axis 1 on page 56 for hole dimensions when designing and preparing the stops. Contact ABB for more information.
Axis 2	yes	no
Axis 3	yes	no
Axis 4	yes	no
Axis 5	yes	no
Axis 6	no	no

ⁱ Part of the casting or fixed on the casting and can not /should not be removed.

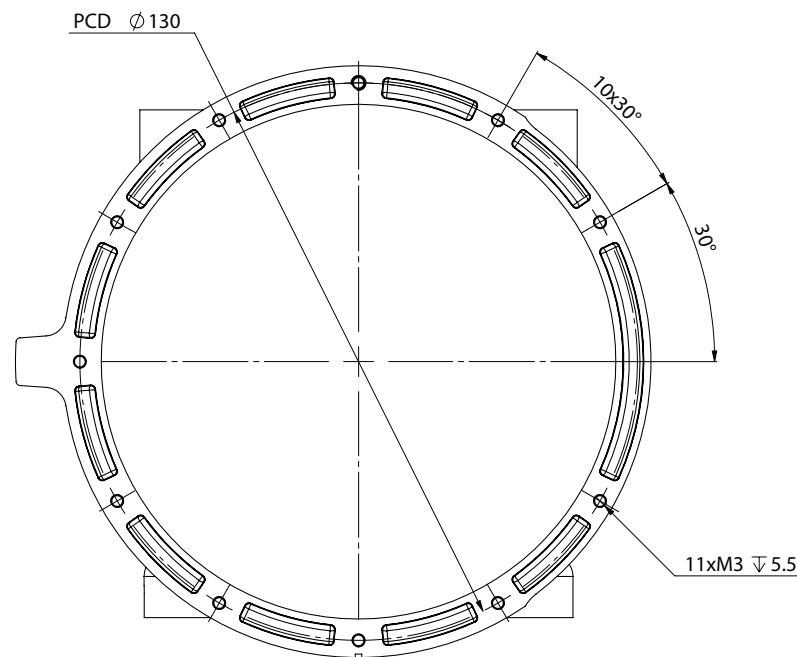
ⁱⁱ Can be installed in one or more than one position, to ensure a reduced working range, or be removed to allow extended working range.

2.6.3 Installing movable mechanical stops on axis 1

Reduction of the axis-1 working range

The working range of axis 1 is limited by system parameter configuration. To reduce the working range from default range, first adjust the parameter values and then install additional mechanical stops as a safety measure.

Additional mechanical stops shall be designed according to actual application and site requirements. Refer to the following hole dimension on swing bottom to prepare the stops.



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Note

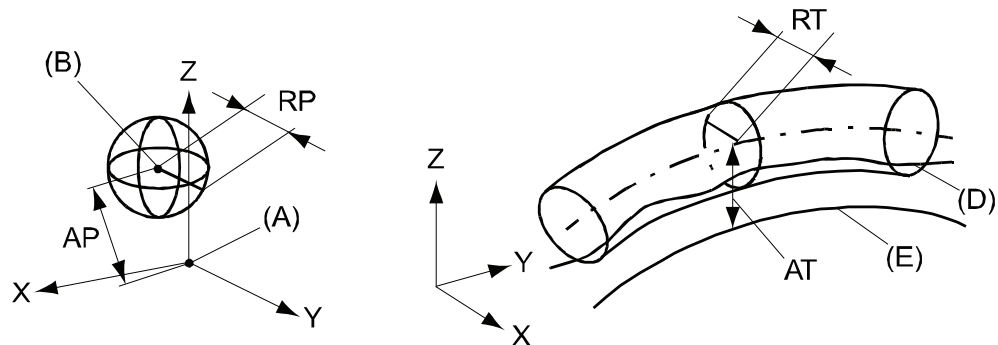
Additional mechanical stops are not delivered with the robot. Contact ABB for more information.

2.7 Performance according to ISO 9283

General

At rated maximum load, maximum offset and 1.6 m/s velocity on the inclined ISO test plane, with all six axes in motion. 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.



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Pos	Description	Pos	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 1010	IRB 1010-1.5/0.37
Pose accuracy, AP ⁱ (mm)	0.01
Pose repeatability, RP (mm)	0.01
Pose stabilization time, PSt (s) within 0.1 mm of the position	0.04
Path accuracy, AT (mm)	0.45
Path repeatability, RT (mm)	0.01

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.

2 Technical data for IRB 1010

2.8 Velocity

2.8 Velocity

Maximum axis speed

Robot type	Axis 1	Axis 2	Axis 3	Axis 4	Axis 5	Axis 6
IRB 1010-1.5/0.37	320 °/s	320 °/s	375 °/s	500 °/s	470 °/s	500 °/s

There is a supervision function to prevent overheating in applications with intensive and frequent movements (high duty cycle).

2.9 Robot stopping distances and times

2.9.1 Robot stopping distances according to ISO 10218-1

About the data for robot stopping distances and times

All measurements and calculations of stopping distances and times are done according to ISO 10218-1, with single axis motion on axes 1, 2, and 3. If more than one axis is used for the movement, then the stopping distance and time can be longer or shorter. The movement of the axes does not necessarily represent the actual application. Therefore, the braking distance must be validated for each application.

Normal delays of the hardware and software are taken into account. See more about the delays and their impact on the results, [Reading the data on page 61](#).

The stopping distances and times are presented using the tool data and extension zones presented for the respected robot variant. These variables are 100%, 66%, and 33% of the maximum values for the robot.

The stop categories 0 and 1 are according to IEC 60204-1.



Note

The category 0 stop is not necessarily the worst case (depending on load, speed, application, wear, etc.).



Note

The stop category 1 is a controlled stop and will therefore have less deviation from the programmed path compared with a stop category 0.

Loads

The tool data that is used is presented for the respective robot variant.

The used loads represent the rated load. No arm load is used. See the [Load diagrams on page 46](#).

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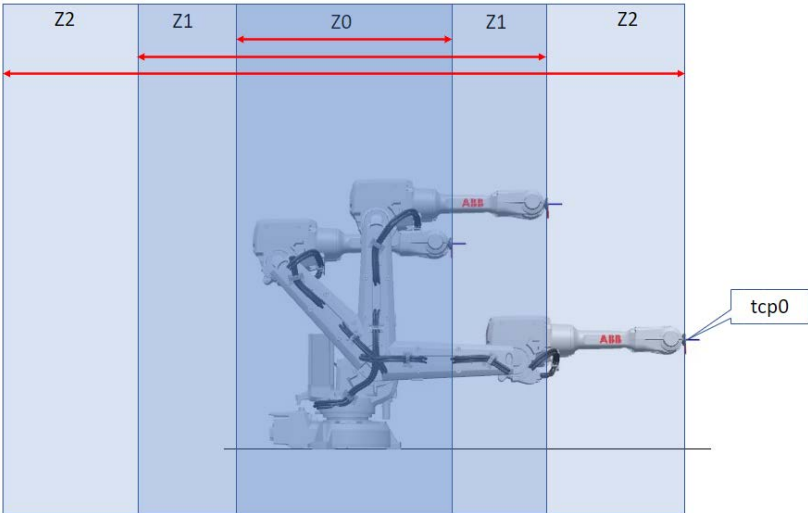
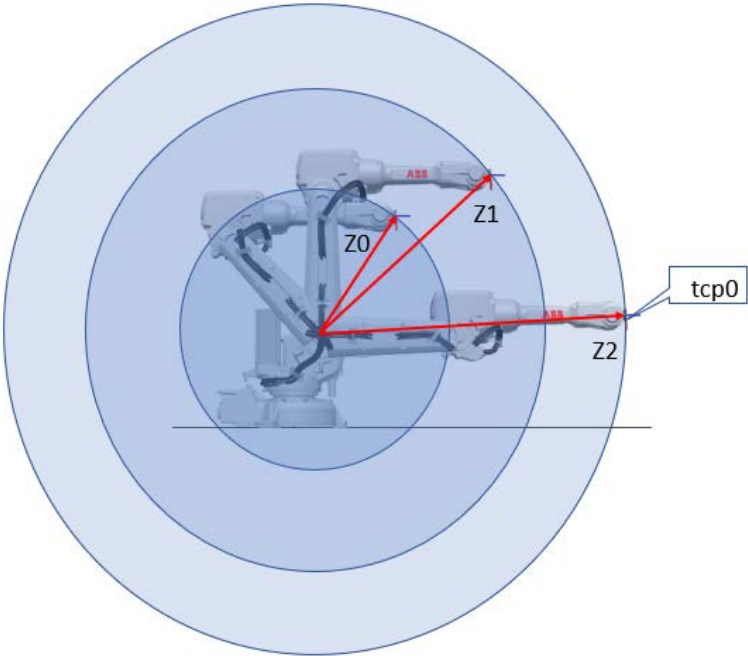
2 Technical data for IRB 1010

2.9.1 Robot stopping distances according to ISO 10218-1
Continued

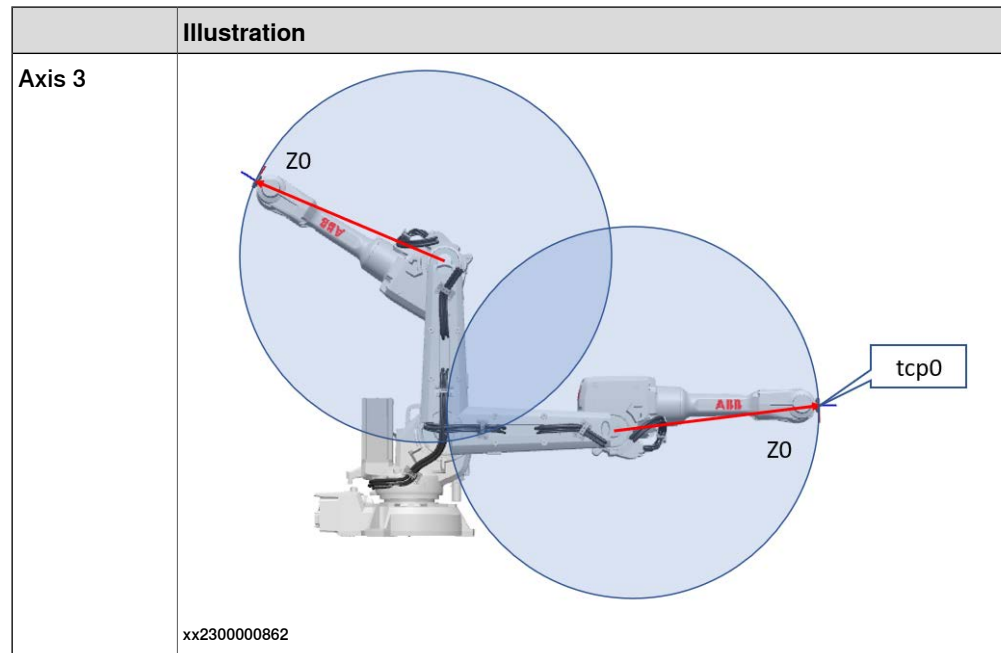
Extension zones

The extension zone for the stop category 1 is based on the tool mounting interface (tool flange) with the axis angles according to the following illustrations. The zone data is presented for the respective robot variant.

The extension zone outer limits are defined by the TCP0 position for the stated angles.

	Illustration
Axis 1	 xx2300000860
Axis 2	 xx2300000861

Continues on next page



Speed

The speed in the simulations is based on TCP0.

The TCP0 speed is measured in meters per second when the stop is triggered.

Stopping distances

The stopping distance is measured in degrees.

Stopping times

The stopping time is measured in seconds.

Limitations

The stopping distance can vary depending on additional loads on the robot.

The stopping distance for category 0 stops can vary depending on the individual brakes and the joint friction.

Reading the data

The data for stop category 0 is presented in tables, with distance and time for each axis.

The data for stop category 1 is presented as graphs with curves representing the different loads.

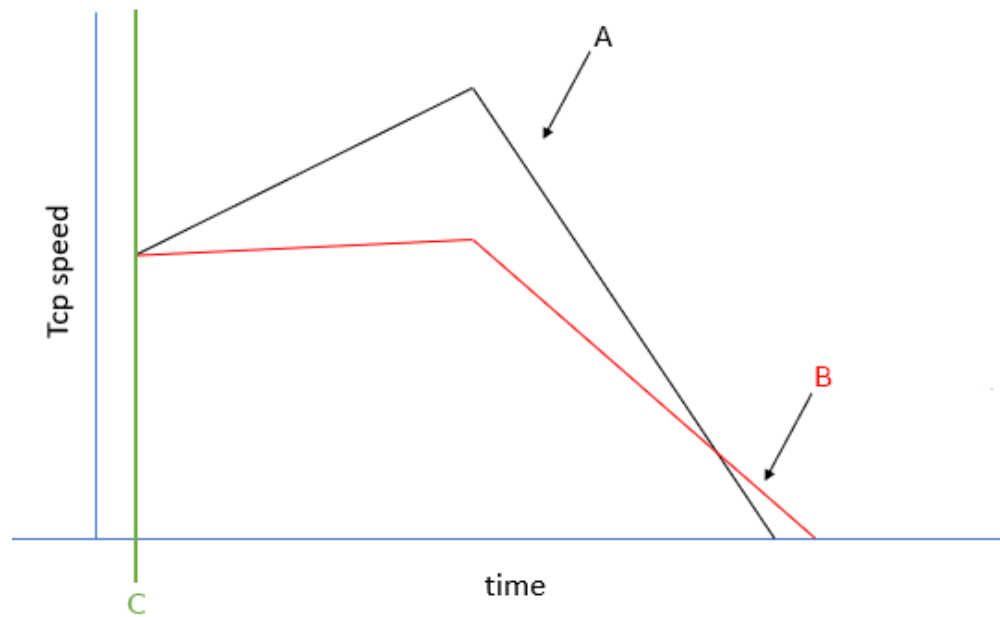
There is a short delay in the stop, which means that if the axis is accelerating when the stop is initiated (C), it will continue to accelerate during this delay time. This can result in graphs where a higher load (A) gives shorter stopping distance than a smaller load (B).

Continues on next page

2 Technical data for IRB 1010

2.9.1 Robot stopping distances according to ISO 10218-1

Continued



xx2300001041

The tcp speed is the actual speed when the stop is initiated, which is not necessarily the programmed speed.

2.9.2 Measuring stopping distance and time

Preparations before measuring

For measurement and calculation of overall system stopping performance, see ISO 13855:2010.

The measurement shall be done for the selected stop category. The emergency stop button on the robot controller is configured for stop category 0 on delivery. A risk assessment can conclude the need for another stop category. The stop category can be changed through the system parameter *Function* (topic *Controller*, type *Safety Run Chain*). In case of deviations of the default configuration of stop category 0, then this is detailed in the product specification for the respective manipulator.



CAUTION

The measurement and calculation of overall stopping performance for a robot must be tested with its correct load, speed, and tools, in its actual environment, before the robot is taken into production.

All load and tool data must be correctly defined (weight, CoG, moment of inertia). The load identification service routine can be used to identify the data.

The measurement and calculation can also be included in a yearly maintenance.



CAUTION

Follow the safety instructions in the respective product manual for the robot.

Measuring with TuneMaster

The software TuneMaster can be used to measure stopping distances and times for ABB robots. The TuneMaster software contains documentation on how to use it.

- 1 Download TuneMaster from www.abb.com/robotics, section **RobotStudio - Downloads - RobotWare Tools and Utilities**.
- 2 Install TuneMaster on a computer. Start the TuneMaster app and select **Log Signals**.
- 3 Connect to the robot controller.
- 4 Define the I/O stop signal to use for measurement, for example, ES1 for emergency stop.
- 5 Define the signal number to use for measurement, 1298 for axis position. The value is given in radians.
- 6 Start the logging in TuneMaster.
- 7 Start the test program on the controller.



Tip

Use the tool and zone definitions for the respective variant in this document to get results that are comparable with this document.

Continues on next page

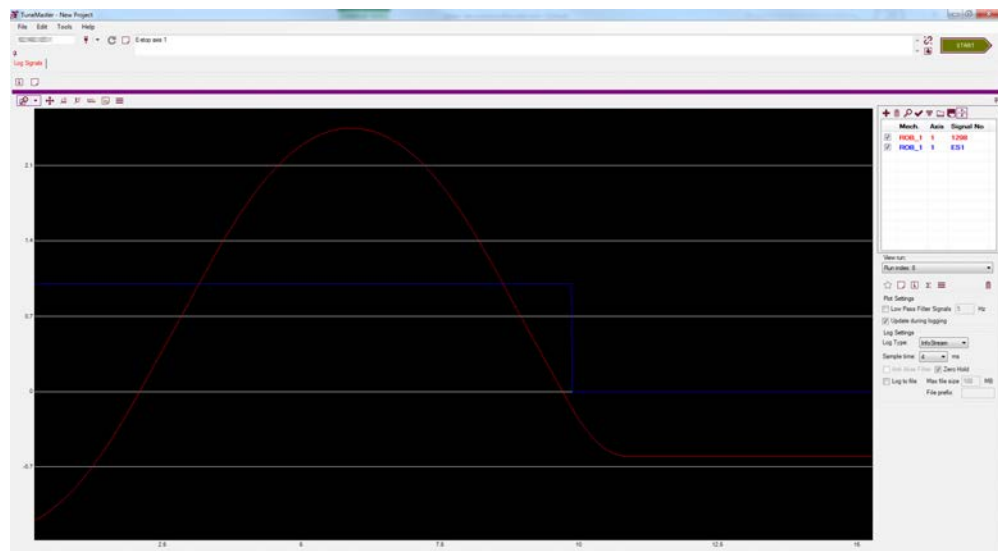
2 Technical data for IRB 1010

2.9.2 Measuring stopping distance and time

Continued

- 8 When the axis has reached maximum speed, press the emergency stop button.
- 9 In TuneMaster, measure the stopping distance and time.
- 10 Repeat for all installed emergency stop buttons until the identified hazards due to stopping distance and time for axes have been verified.

Example from TuneMaster



xx1600000386

2.9.3 IRB 1010-1.5/0.37

Used tooldata

```
PERS tooldata P100:= [ TRUE, [[0, 0, 0], [1, 0, 0, 0]], [1.5, [0,
0, 50], [1, 0, 0, 0], 0.00063, 0.00063, 0.00063]];
PERS tooldata P66:= [ TRUE, [[0, 0, 0], [1, 0, 0, 0]], [1, [0, 0,
33], [1, 0, 0, 0], 0.00028, 0.00028, 0.00028]];
PERS tooldata P33:= [ TRUE, [[0, 0, 0], [1, 0, 0, 0]], [0.5, [0,
0, 17], [1, 0, 0, 0], 7E-5, 7E-5, 7E-5]];
```

Category 0

The following table describes the stopping distance and time for category 0 stop.

Axis	Distance	Stop time
1	33.8°	0.15 s
2	36.7°	0.17 s
3	40.6°	0.16 s

Category 1, extension zones

For definitions of the zones, see [Extension zones on page 60](#).

The zone border is the mounting interface location for axis 2 and axis 3.

Axis 1

Zone border	Axis 2	Axis 3
z0-z1	-42°	42°
z1-z2	6°	-6°

Axis 2

Zone border	Axis 2	Axis 3
z0-z1	48°	30°
z1-z2	90°	-30°

Axis 3

Only one zone exists.

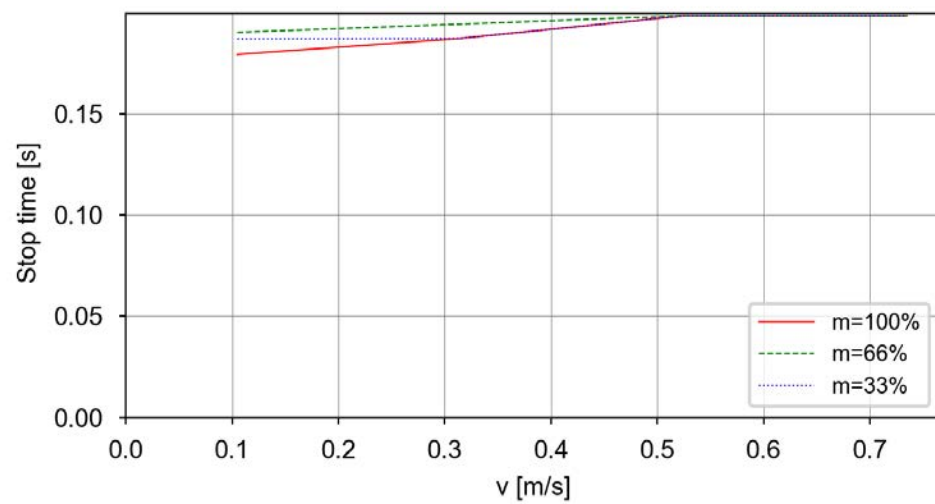
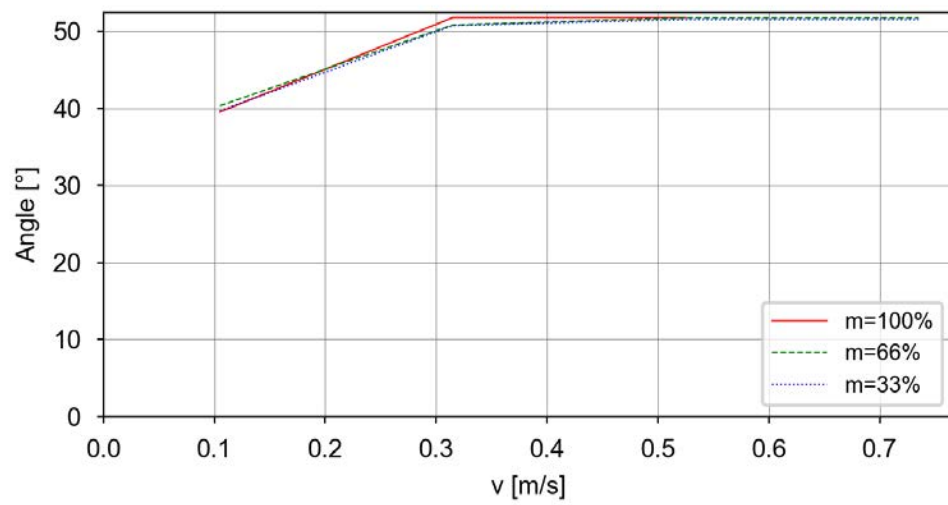
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2 Technical data for IRB 1010

2.9.3 IRB 1010-1.5/0.37

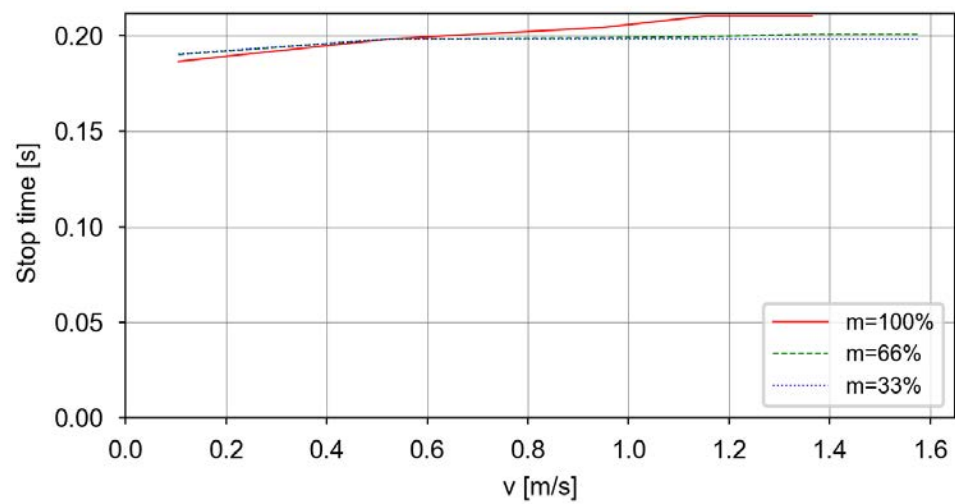
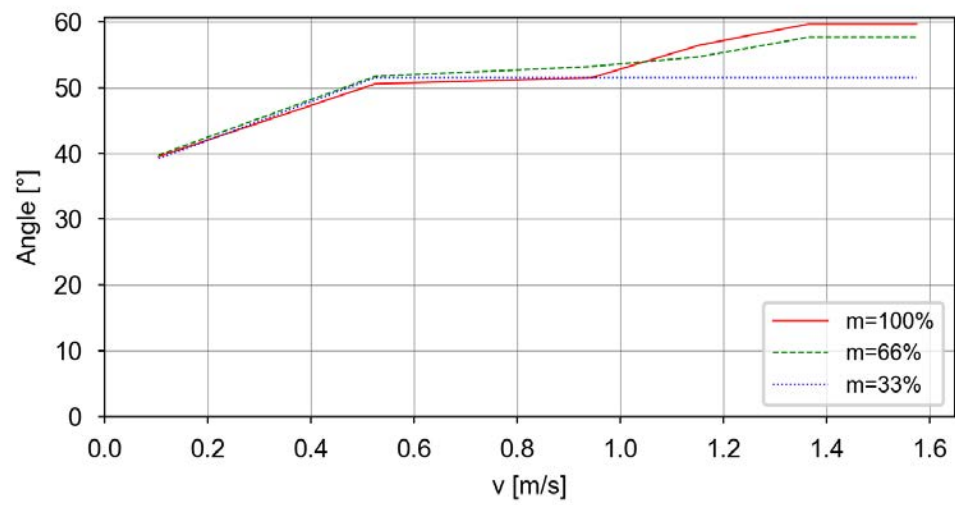
Continued

Category 1, Axis 1, Extension zone 0, stopping distance and stopping time



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Category 1, Axis 1, Extension zone 1, stopping distance and stopping time



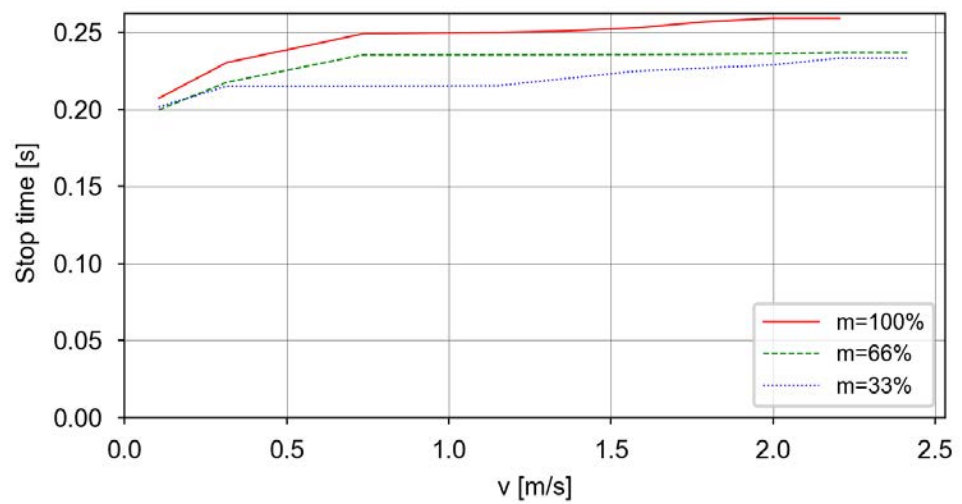
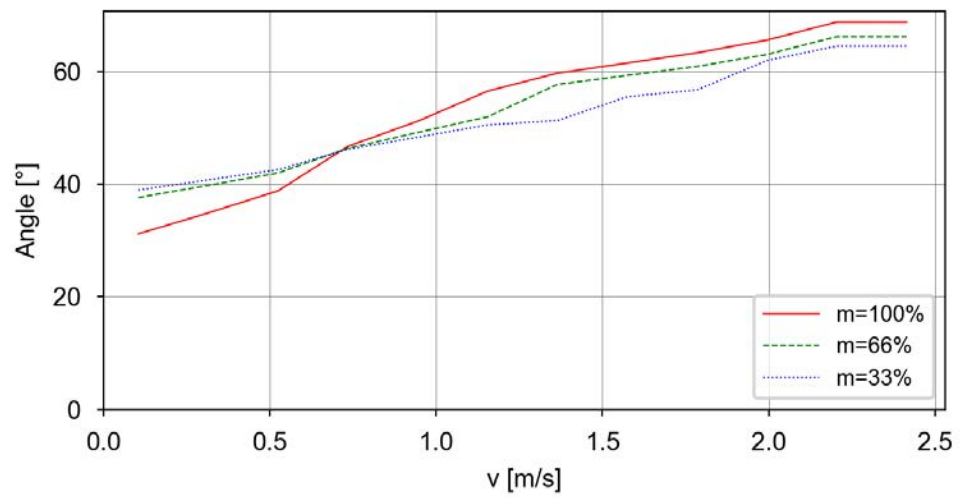
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2 Technical data for IRB 1010

2.9.3 IRB 1010-1.5/0.37

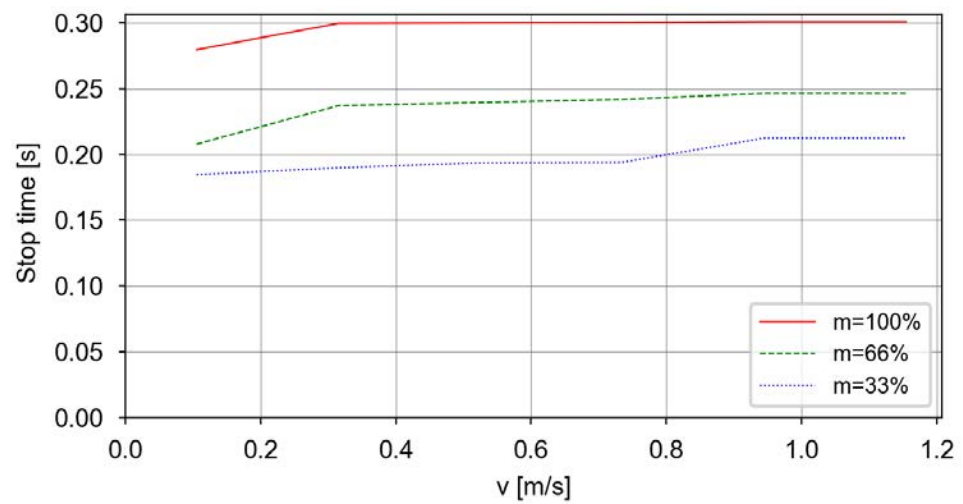
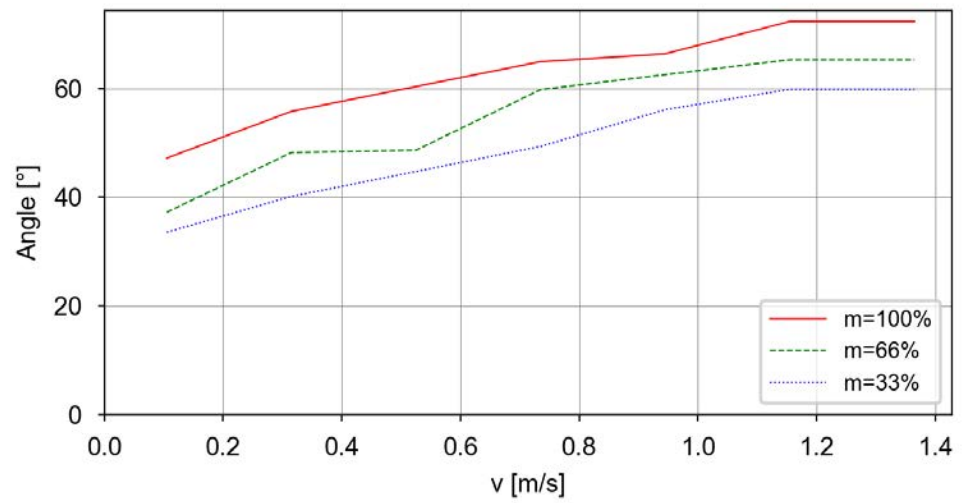
Continued

Category 1, Axis 1, Extension zone 2, stopping distance and stopping time



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Category 1, Axis 2, Extension zone 0, stopping distance and stopping time



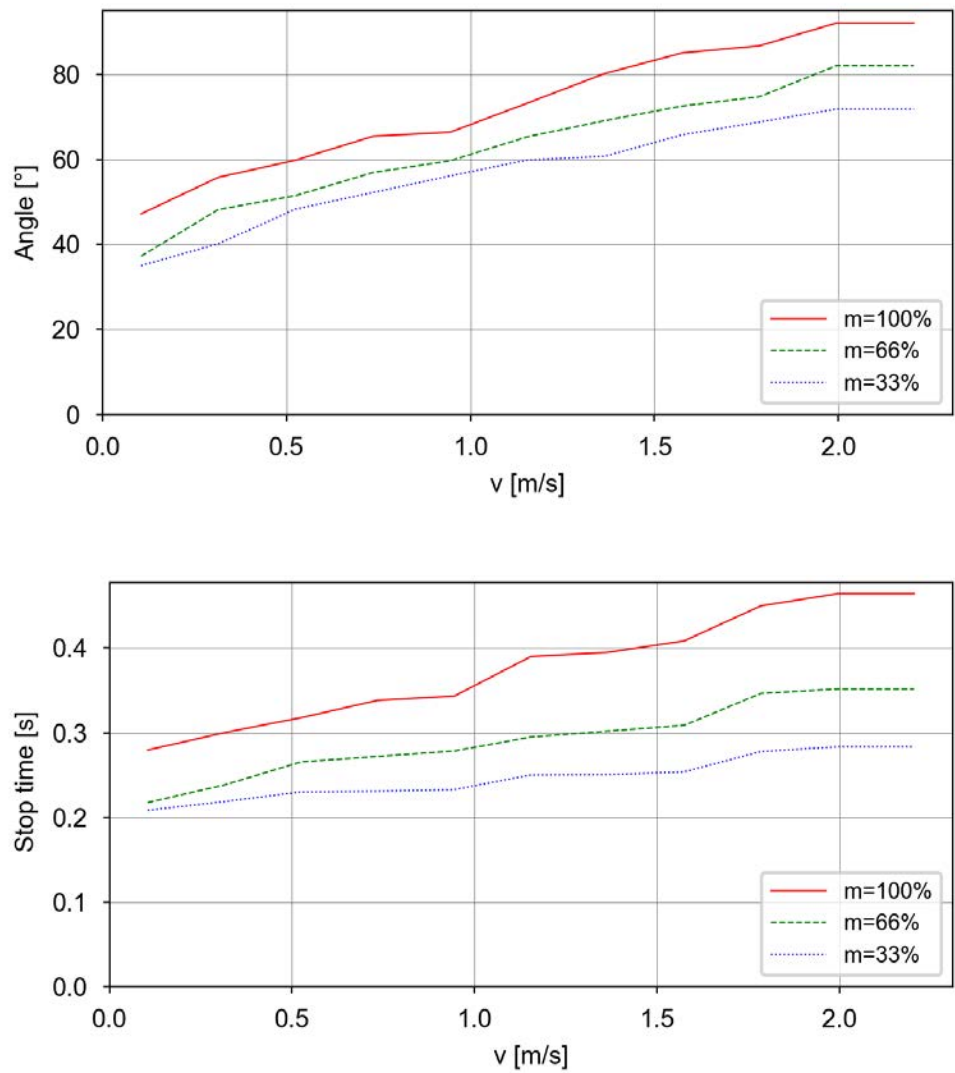
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2 Technical data for IRB 1010

2.9.3 IRB 1010-1.5/0.37

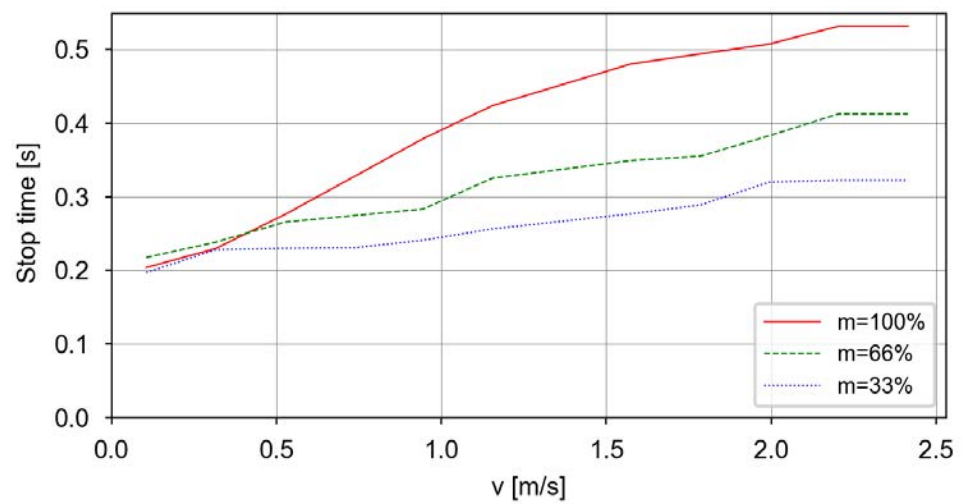
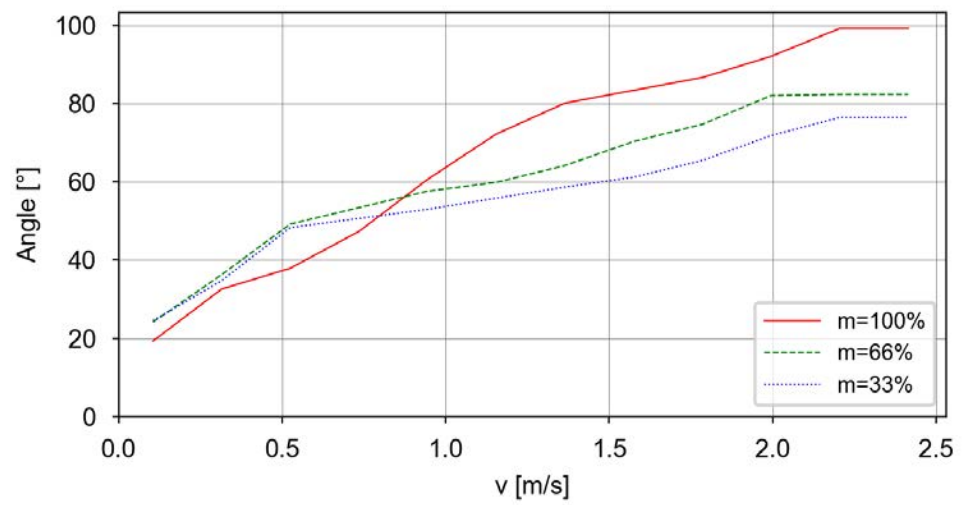
Continued

Category 1, Axis 2, Extension zone 1, stopping distance and stopping time



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Category 1, Axis 2, Extension zone 2, stopping distance and stopping time



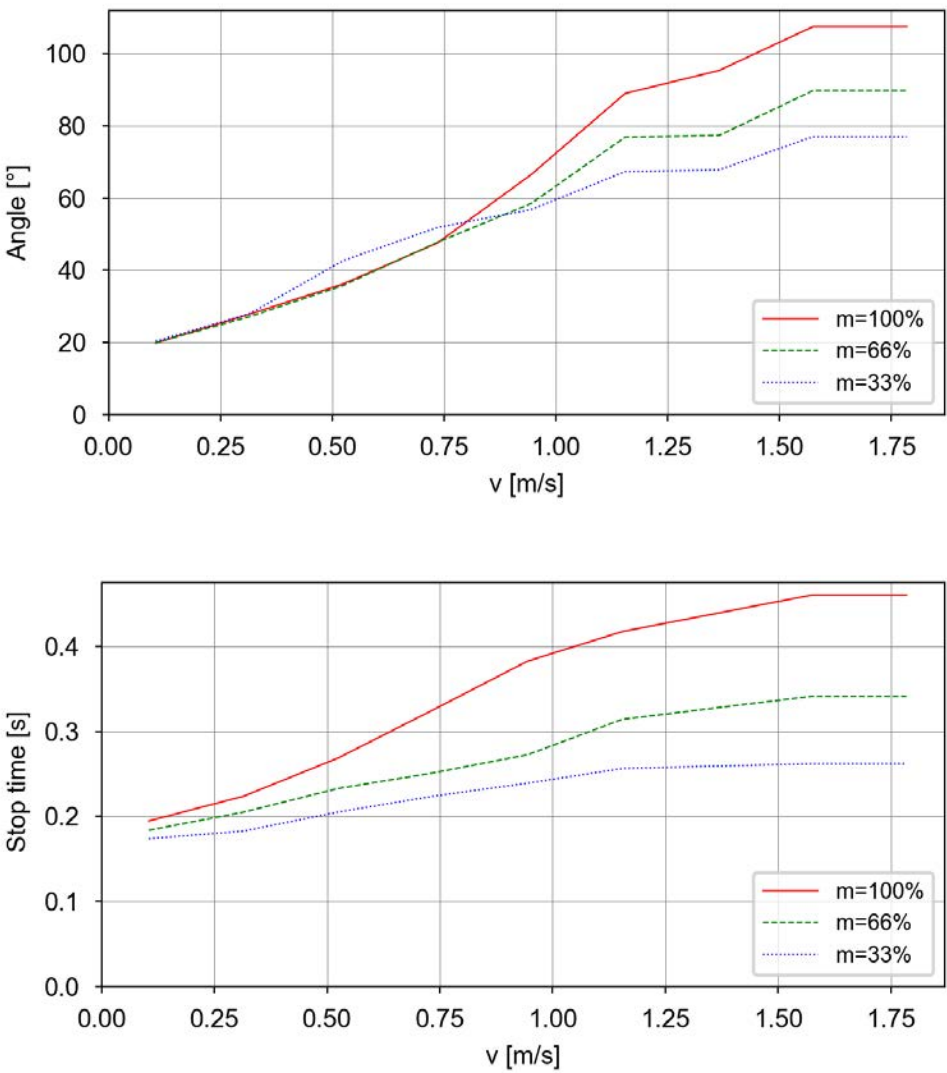
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2 Technical data for IRB 1010

2.9.3 IRB 1010-1.5/0.37

Continued

Category 1, Axis 3, Extension zone 0, stopping distance and stopping time



3 Specification of variants and options

3.1 Introduction to variants and options

General

The different variants and options for the IRB 1010 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.

3 Specification of variants and options

3.2 Manipulator

3.2 Manipulator

Manipulator variants

Option	IRB Type	Handling capacity (kg)	Reach (m)
3300-56	IRB 1010	1.5	0.37

Manipulator color

Option	Description	RAL code ⁱ
209-202	ABB Graphite White std	RAL 7035

ⁱ The colors can differ depending on supplier and the material on which the paint is applied.

Manipulator protection

Option	Description
3350-400	Base 40, IP40



Note

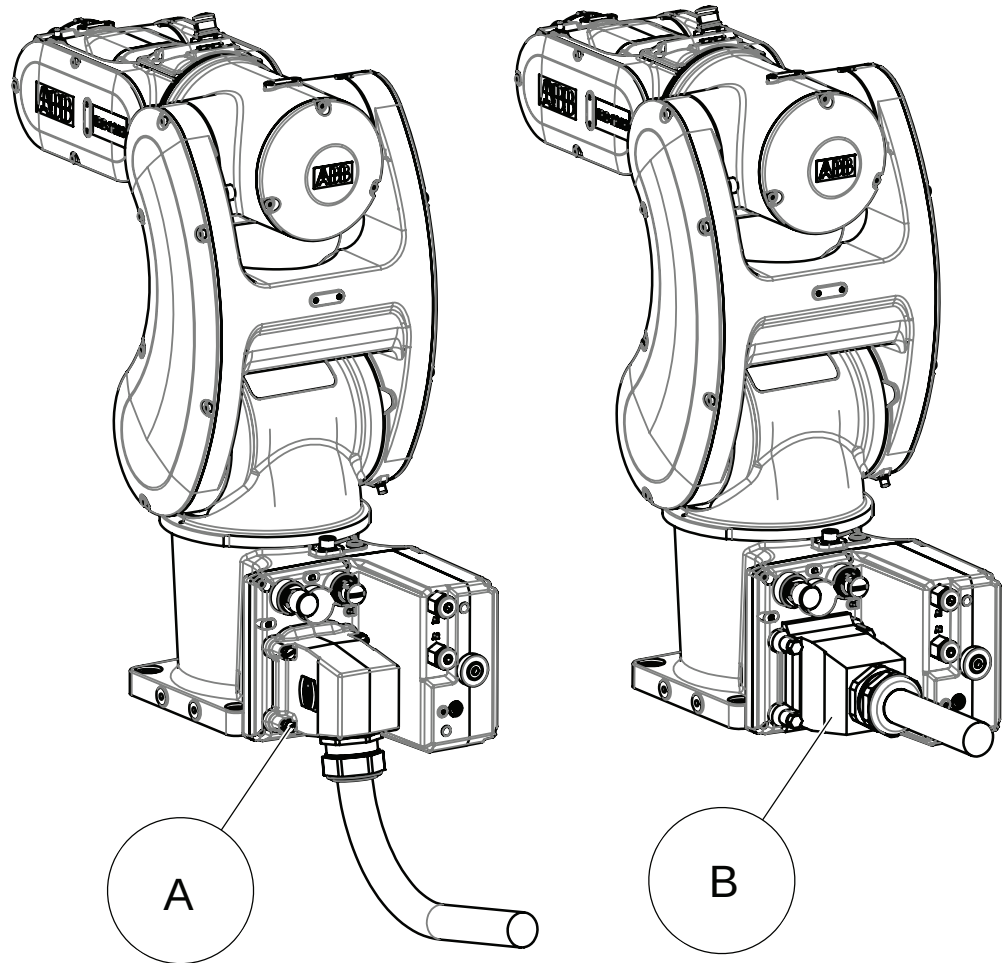
Base 40 includes IP40, according to standard IEC 60529.

The IRB 1010 has protection class IP40 as default and also fulfill Clean room class 5 standard according to DIN EN ISO 14644-1, -14.

Robot cabling routing

Option	Description
3309-1	Under the base
3309-2	From side of base

Continues on next page



xx2200000412

Pos	Description
A	Under the base
B	From side of base

Media & Communication

Option	Type	Description
3303-1	Parallel & Air	Includes CP/CS (C1) and air.

Connector kits manipulator

The kit consists of connectors, pins and sockets. And the options required [3303-x] when choosing.

Option	Description
3304-1	Male-type, Straight arm connector kits
3305-1	Male-type, Angled arm connector kits

Continues on next page

3 Specification of variants and options

3.2 Manipulator

Continued



xx2200000570



Note

The image shown here is indicative only. If there is inconsistency between the image and the actual product, the actual product shall govern.

The kits are designed and used for connectors on upper arm.

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.

Continues on next page

Option	Type	Description
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 Specification of variants and options

3.3 Floor cables

3.3 Floor cables



Note

To comply with the EMC directive, the total cable length (including cables for the motor connection box) must not exceed 30 m between:

Controller and robot (IRB)

Controller and motor & gear units (MU/GU) or track motion (IRT)

Controller and positioner (IRP)

Manipulator cable length

Option	Lengths
3200-1	3 m
3200-2	7 m
3200-3	15 m

Mains cable

Option	Lengths	Description
3203-1	EU mains cable, 3 m	Cable assembly with CEE7/VII line-side plug
3203-2	UK mains cable, 3 m	Cable assembly with BS1363 line-side plug, 5A fused
3203-5	CN mains cable, 3 m	Cable assembly with CPCS-CCC line-side plug
3203-6	AU mains cable, 3 m	Cable assembly with AS/NZS 3112 line-side
3203-7	All regions cable, 5 m	Cable assembly without line-side plug



Tip

The option *Mains cable* requires option *3000-105 OmniCore E10* or *3000-130 OmniCore C30*.

Connection of parallel communication

Required 3303-1 Parallel & Air or 3303-2 Ethernet, Parallel, Air.

Option	Lengths
3201-1	3 m
3201-2	7 m
3201-3	15 m

4 Accessories

General

There is a range of tools and equipment available.

Basic software and software options for robot and PC

For more information, see the application manual for the controller software and the product specification for the robot controller.

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ABB Robotics Sweden AB
S-721 71 VÄSTERÅS, Sweden
Telephone +46 10-732 50 00

ABB Robotics Norway AS
Nordlysvegen 7, N-4340 BRYNE, Norway
Box 265, N-4349 BRYNE, Norway
Telephone: +47 22 87 2000

ABB Robotics (Shanghai) Limited
No. 39, 99 Miaoqiao Road,
Pudong New Area,
Shanghai, 201315, China
Telephone: +86 21 6105 6666

ABB Robotics LLC
1250 Brown Road
Auburn Hills, MI 48326
USA
Telephone: +1 248 391 9000

abb.com/robotics