

Replacing the Kinetek Controller

Parts required for this service:

10 mm socket

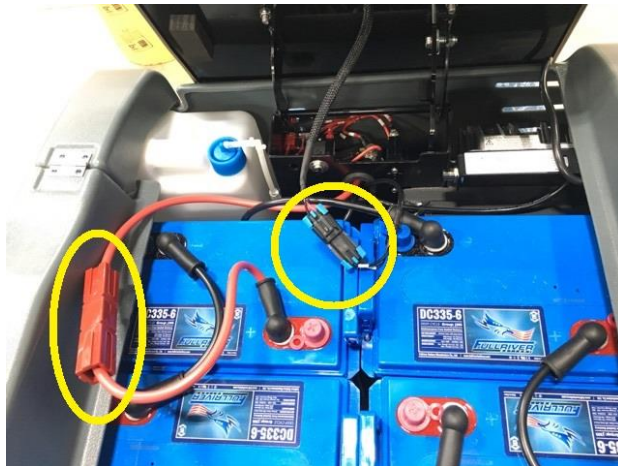
13mm socket

½ in. socket

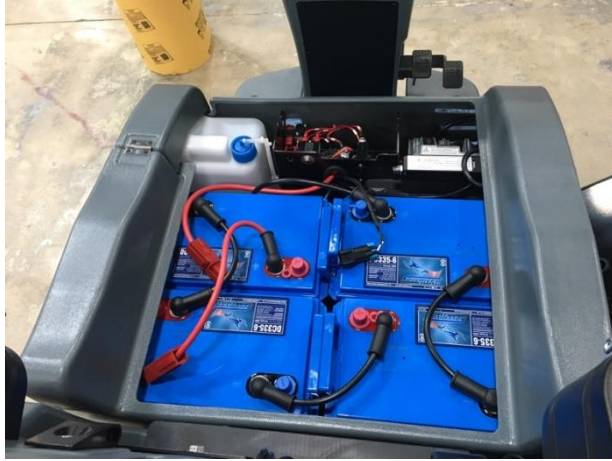
Torque wrench

Torque Paint

Turn the key to power off the scrubber. Raise the seat and disconnect the red battery coupling and the seat sensor connection.



Lift the seat up and off the scrubber and set it on the floor

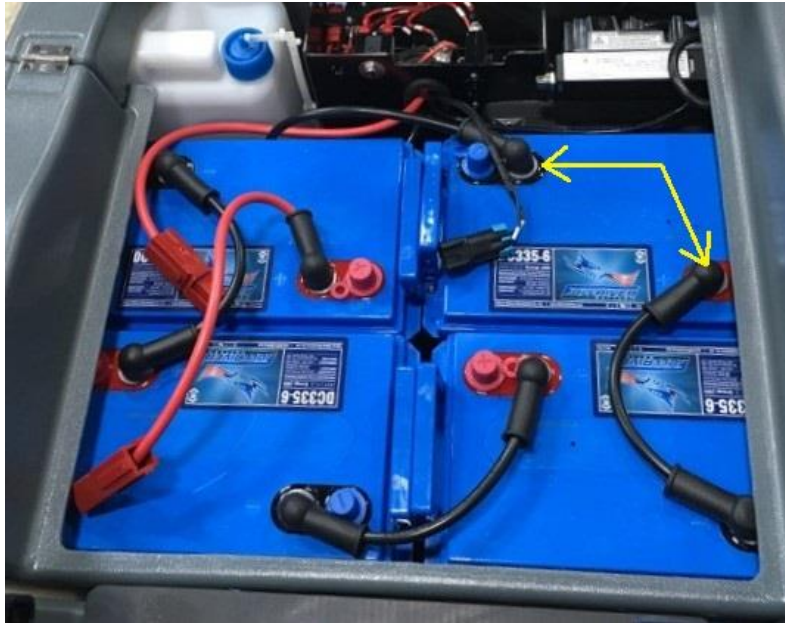


Use a size 13 mm socket and remove the two bolts shown below, then lift the housing straight up and off the scrubber unit.



Disconnect the battery terminals labeled in the image below and lift the battery out.

This will expose the Kinetek controller to be removed.



Before disconnecting any of the wire bundles, it may be useful to use a marker and write the number position on the yellow strain relief. You should also take a photo with your phone before disconnecting just in case



Using a 10 mm socket, remove the brass screws which connect the wire bundles to the Kinetek. Decouple the four wire connector bundles from the lower right. Use a 3 mm hex driver to remove the two screws on either side of the Kinetek.

Remove the old Kinetek, attach the new and correctly reconnect all the cabling. Be sure to use the proper torque when reconnecting the cables to the brass bolts.



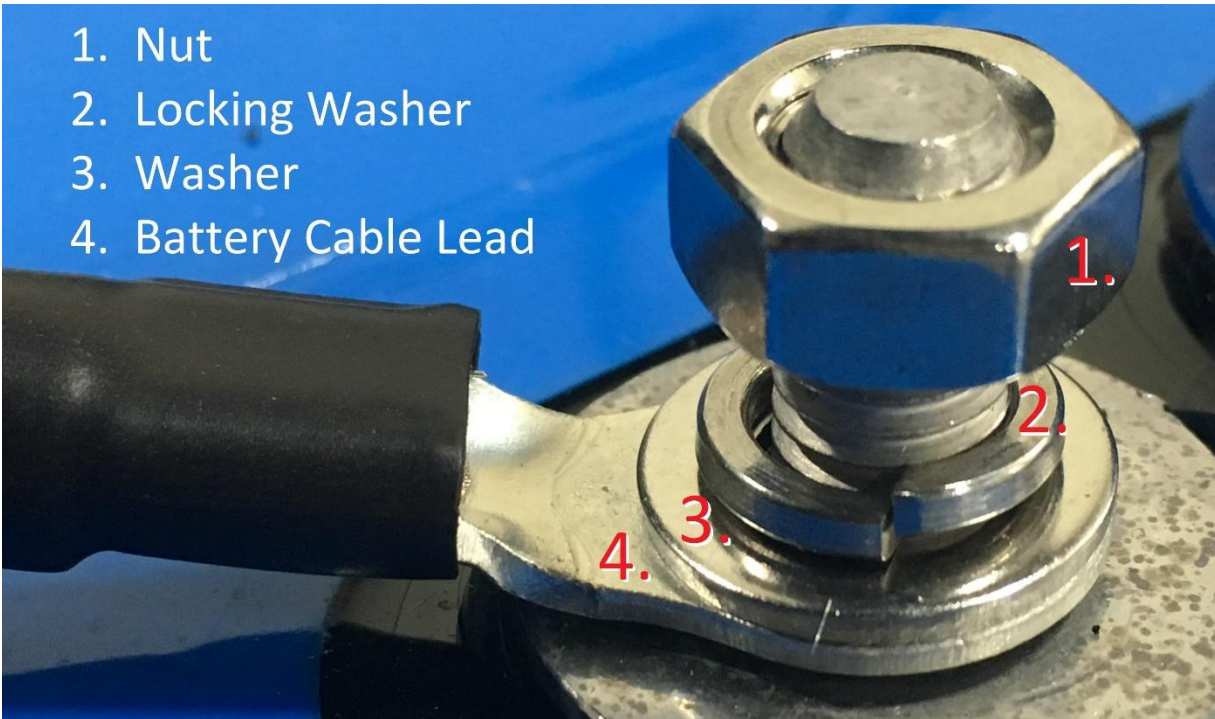
When reinstalling the battery terminals, the following torque specs should be satisfied:

Fullriver AGM Blue Battery

65 inch lbs.



The terminal hardware is to be in the following order:



Apply torque paint onto the terminal hardware as shown and be sure to leave the terminals covered with the rubber/plastic sleeves.



Replace the scrubber housing and secure it with the two front bolts. Replace the seat, while being careful not to break the 5A circuit breaker. Reconnect the seat sensor and the red battery coupling. Turn the key to

power on the unit and ensure proper start up and system operation. There should be no faults on the User Interface, and the scrubber should work in manual mode.

If possible, train and autonomously run a short test route to verify autonomous operation.