

C8LH

Origin on the non-motor side is selectable

Ordering method

C8LH

Model	Lead	Option	Stroke	Cable length ^{Note 1}	TSX	SR1-X	RDV-X	Battery
	20: 20mm 10: 10mm 5: 5mm	Origin position change None: Standard Z: Non-motor side	150 to 1050 (50mm pitch)	3L: 3.5m 5L: 5m 10L: 10m 3K/5K/10K (Flexible cable)	Positioner ^{Note 2} TS-X Driver: Power supply voltage / Power capacity 105: 100V/100W or less 205: 200V/100W or less LCD monitor No entry: None L: With LCD	Controller 05 Driver: Power capacity 05: 100W or less Usable for CE No entry: Standard E: CE marking	Driver 2 Power supply voltage 2: AC200V 05: 100W or less	I/O selection N: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 3} Battery B: With battery (Absolute) N: None (Incremental)

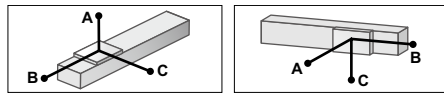
Note 1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.614 for details on robot cable.
 Note 2. See P.522 for DIN rail mounting bracket.
 Note 3. Select this selection when using the gateway function. For details, see P.66.

Basic specifications

AC servo motor output (W)	100
Repeatability ^{Note 1} (mm)	+/-0.01
Deceleration mechanism	Ball screw $\phi 15$
Ball screw lead (mm)	20 10 5
Maximum speed ^{Note 2} (mm/sec)	1000 600 300
Maximum payload (kg)	Horizontal 30 60 80
Rated thrust (N)	84 169 339
Stroke (mm)	150 to 1050 (50mm pitch)
Overall length (mm)	Stroke+389
Maximum outside dimension of body cross-section (mm)	W80 x H75
Cable length (m)	Standard: 3.5 / Option: 5, 10
Degree of cleanliness	CLASS 10 ^{Note 3}
Intake air (N ℓ /min)	30 to 90 ^{Note 4}

Note 1. Positioning repeatability in one direction.
 Note 2. When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.
 Note 3. Per 1cf (0.1um base), when suction blower is used.
 Note 4. The necessary intake amount varies depending on the use conditions and environment.

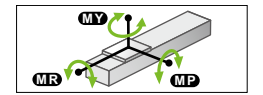
Allowable overhang ^{Note}



	Horizontal installation (Unit: mm)			Wall installation (Unit: mm)		
	A	B	C	A	B	C
Lead 20	10kg	687	274	200	163	225
	20kg	401	125	92	56	76
	30kg	338	76	57	20	27
Lead 10	20kg	622	137	111	74	90
	40kg	472	57	47	8	11
	60kg	375	30	25	-	-
Lead 5	20kg	1087	148	127	89	104
	40kg	844	63	54	15	18
	60kg	707	34	29	-	-
	80kg	594	20	17	-	-

Note. Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

Static loading moment

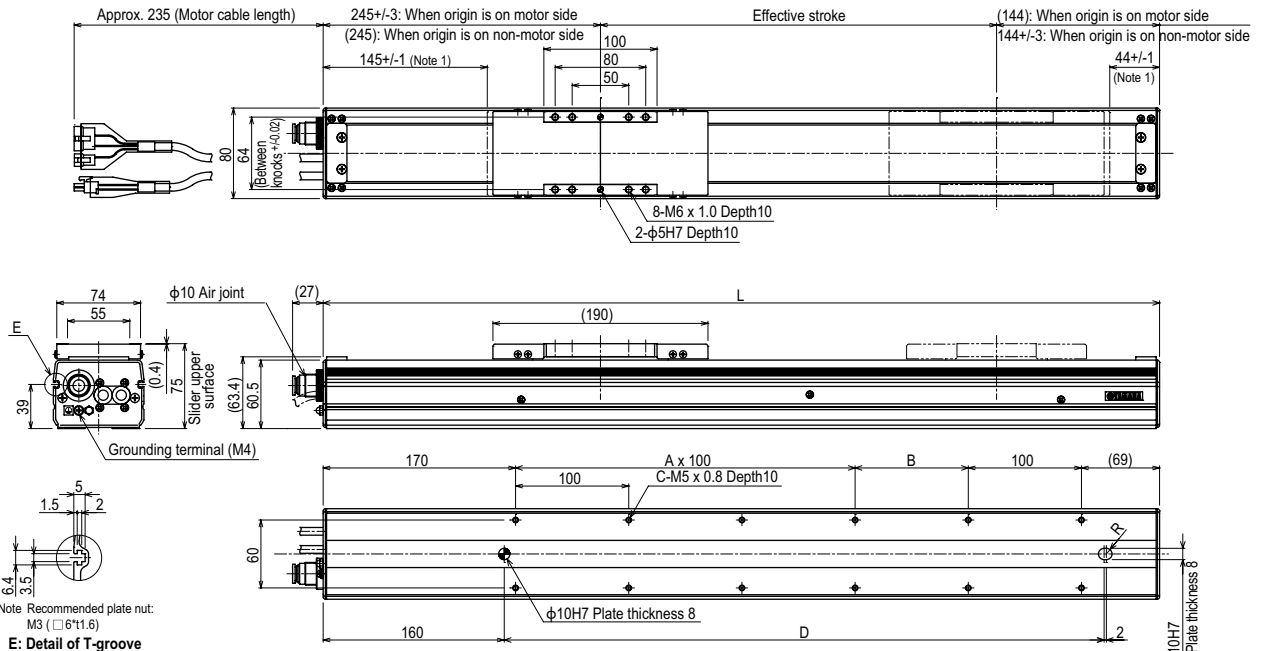


(Unit: N·m)		
MY	MP	MR
128	163	143

Controller

Controller	Operation method
SR1-X05 RCX320 RCX221/222 RCX340	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X105	I/O point trace / Remote command
TS-X205	
RDV-X205-RBR1	Pulse train control

C8LH



Effective stroke	150	200	250	300	350	400	450	500	550	600	650	700	750	800	850	900	950	1000	1050
	L	539	589	639	689	739	789	839	889	939	989	1039	1089	1139	1189	1239	1289	1339	1389
A	1	1	2	2	3	3	4	4	5	5	6	6	7	7	8	8	9	9	10
B	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100
C	8	8	10	10	12	12	14	14	16	16	18	18	20	20	22	22	24	24	26
D	330	380	430	480	530	580	630	680	730	780	830	880	930	980	1030	1080	1130	1180	1230
Weight (kg)	4.7	5.0	5.3	5.6	5.9	6.2	6.6	6.9	7.2	7.5	7.8	8.1	8.4	8.7	9.0	9.3	9.7	10.0	10.3
Maximum speed ^{Note 3} (mm/sec)	Lead 20																		
	Speed setting																		
	Lead 10																		
	Lead 5																		
Speed setting	-																		
	-																		

Note 1. Stop positions are determined by the mechanical stoppers at both ends.
 Note 2. Minimum bend radius of motor cable is R50.
 Note 3. When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.