

R10



Ordering method

R10	Model	Cable entry location No entry: Standard (S) B: From the side	Cable length <small>Note 1</small> 3L: 3.5m 5L: 5m 10L: 10m 3K/5K/10K (Flexible cable)	TSX	Positioner <small>Note 2</small> 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	I/O selection NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board <small>Note 3</small>	Battery B: With battery (Absolute) N: None (Incremental)
	SR1-X	Controller	05	Driver: Power capacity 05: 100W or less	Usable for CE No entry: Standard E: CE marking	I/O selection N: NPN P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS	Battery B: With battery (Absolute) N: None (Incremental)		
	RDV-X	Driver	2	Power-supply voltage 2: AC200V	05	Driver: Power capacity 05: 100W or less	RBR1	Regenerative unit	

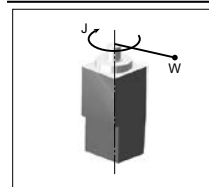
Note 1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable.
See P.594 for details on robot cable.
Note 2. See P.498 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.60.

Specifications

AC servo motor output (W)	100
Repeatability (°)	+/-0.0083
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm ² [kgfcm ²])	0.36 [3.71]
Rated torque (Nm[kgfm])	10.78 [1.10]
Speed reduction ratio	1/50
Rotation range (°)	360
Cable length (m)	Standard: 3.5 / Option: 5.10
Speed reducer type	Harmonic drive
Position detector	Resolvers
Resolution (Pulse/rotation)	16384

Maximum allowable moment inertia

Payload parameters W (kg)	1	2	3	4	5	6	7	8	9	10
Maximum allowable moment inertia J (kgfcm ²)	0.25	0.49	0.74	0.99	1.24	1.48	1.73	1.98	2.23	2.47
Payload parameters W (kg)	11	12	13	14	15					
Maximum allowable moment inertia J (kgfcm ²)	2.72	2.97	3.22	3.46	3.71					



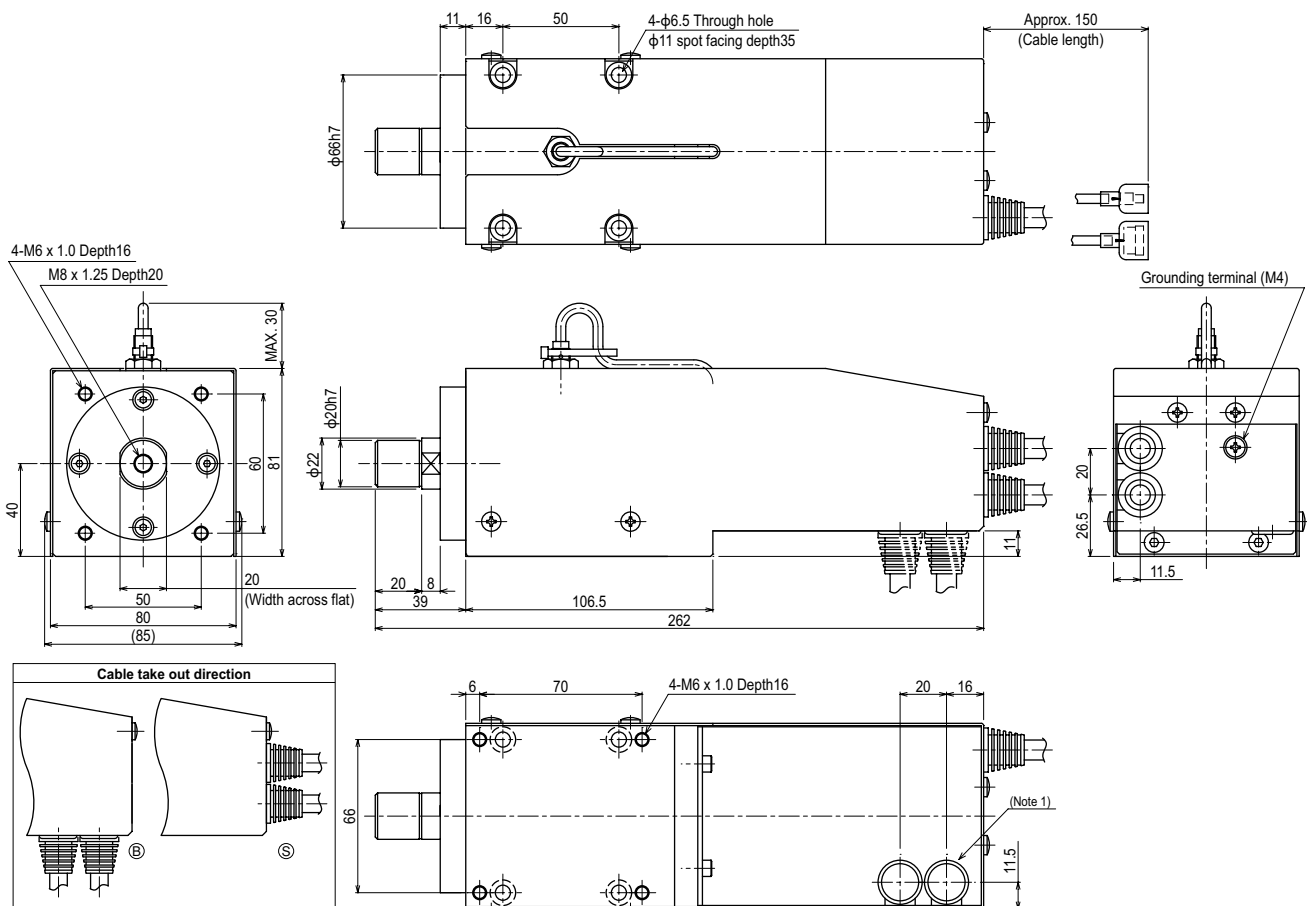
Note. When the weight of a tool or workpiece attached to the shaft R10 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 0.99kgf cm sec².) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value.

Note. For calculation (equation) of the inertia moment, please refer to P.611.

Controller

Controller	Operation method
SR1-X05 RCX221/222 RCX240/340	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X105	I/O point trace / Remote command
TS-X205	Remote command
RDV-X205-RBR1	Pulse train control

R10



Weight (kg) 3.5 Note 1. The cable extraction port can be changed.

Articulated robots
YA

Linear conveyor modules
LCM100

Compact single-axis robots
TRANSEVO

Single-axis robots
FLIP-X

Linear motor single-axis robots
PHASER

Cartesian robots
XY-X

SCARA robots
YK-X

Pick & place robots
YP-X

CLEAN

CONTROLLER INFORMATION

T type

F type

GF type

N type

R type