Articulated robots
YA
Linear conveyor modules
LCM100
Compact single-axis robots
TRANSERVO
Motor-less single axis actuator
Robonity
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

Controller SR1-X
Driver Power-supply voltage
I/O selection
Battery

Controller TS-X
Driver Power-supply voltage
I/O selection
Battery

Controller RDV-X
Driver Power-supply voltage
I/O selection
Battery

Specifications
AC servo motor output (W) 50
Repeatability (°/sec) +/-0.00083
Maximum speed (°/sec) 360
Maximum allowable moment inertia (kgm²/rev) 0.12 (1.2)
Rated torque (Nm/rev) 5.29 (0.54)
Speed reduction ratio 150
Rotation range (°) 360
Cable length (m) Standard: 3.5 / Option: 10
Speed reducer type Harmonic drive
Position detector Resolvers
Resolution (Pulse/rotation) 16384

Maximum allowable moment inertia

Payload parameters W (kg)

Maximum allowable moment inertia J (kgm²)

Note: When the weight of a tool or workpiece attached to the shaft R5 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 0.48kgf 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.643.

Ordering method

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.56.