

R5



Ordering method

R5

Model	Cable entry location	Cable length ^{Note 1}
	No entry: Standard (S) B: From the side	3L: 3.5m 5L: 5m 10L: 10m 3K/5K/10K (Flexible cable)

TSX

Positioner ^{Note 2}	Driver: Power-supply voltage / Power capacity	LCD monitor	I/O selection	Battery
TS-X	105: 100V/100W or less 205: 200V/100W or less	No entry: None L: With LCD	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 3}	B: With battery (Absolute) N: None (Incremental)

SR1-X

Controller	05	Usable for CE	I/O selection	Battery
	Driver: Power capacity 05: 100W or less	No entry: Standard E: CE marking	N: NPN P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS	B: With battery (Absolute) N: None (Incremental)

RDV-X

Driver	2	05	RBR1
	Power-supply voltage 2: AC200V	Driver: Power capacity 05: 100W or less	Regenerative unit

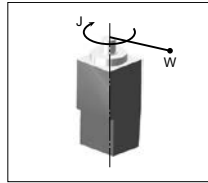
Note 1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.594 for details on robot cable.
Note 2. See P.498 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.60.

Specifications

AC servo motor output (W)	50
Repeatability (°)	+/-0.0083
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm ² [kgfcm ²])	0.12 [1.2]
Rated torque (Nm[kgfm])	5.29 [0.54]
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)	0.12	0.24	0.36	0.48	0.60	0.72	0.84	0.96	1.08	1.20



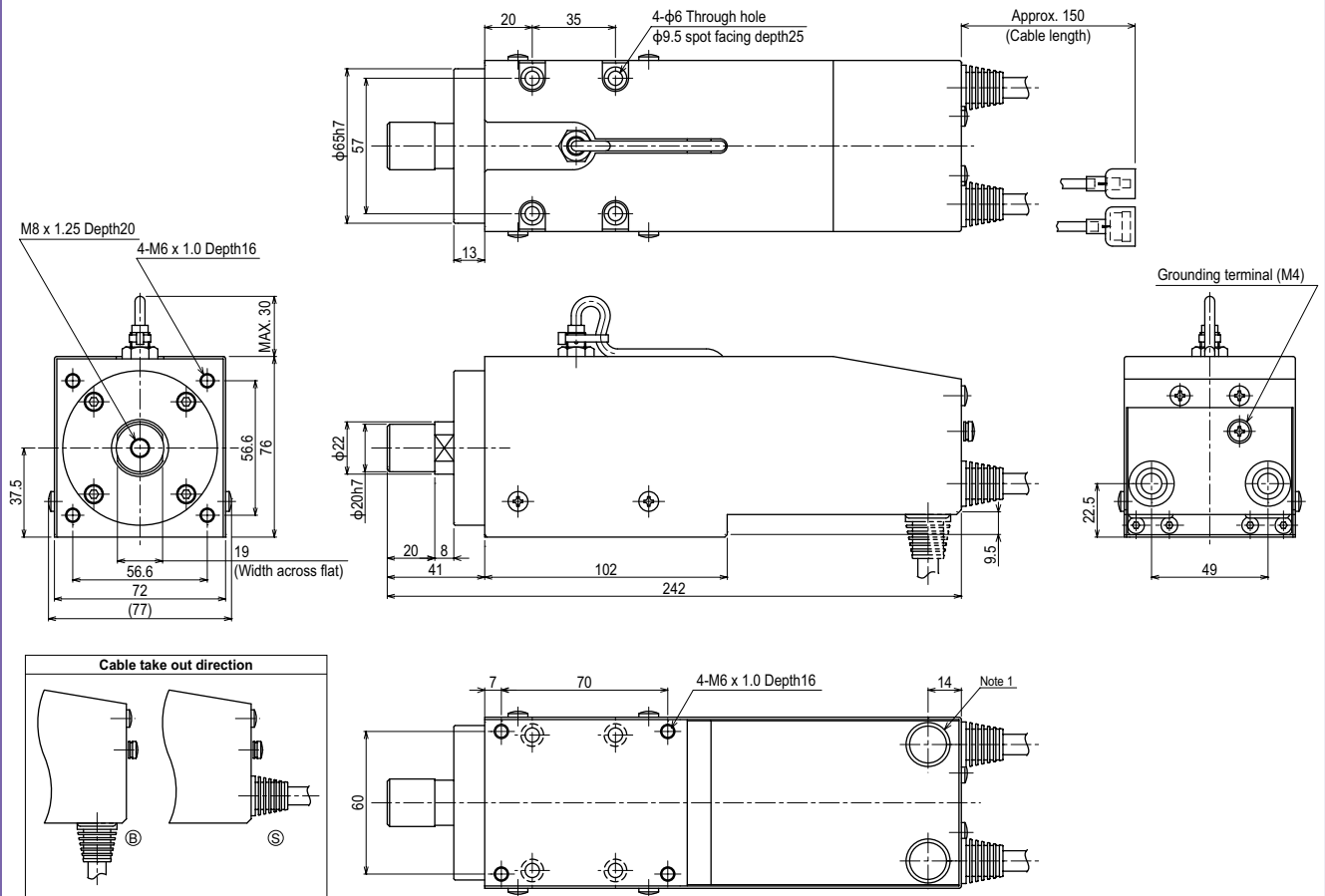
Note. When the weight of a tool or workpiece attached to the shaft R5 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 0.48kgf cm sec².) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value.

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

R5



Weight (kg) 3.0 Note 1. The cable extraction port can be changed.