

# T4



## Origin at non-motor side

### Ordering method

<b>T4</b>						<b>ERCX</b>			
<b>Model</b>	<b>Lead designation</b> 12: 12mm 6: 6mm 2: 2mm	<b>Brake</b> No entry: No brakes BK: Brakes provided	<b>Option</b> Origin position change Grease type None: Standard Z: Non-motor side None: Standard GC: Clean	<b>Stroke</b> 50 to 300 (50mm pitch)	<b>Cable length</b> <sup>Note 1</sup> 3L: 3.5m (Standard) 5L: 5m 10L: 10m 3K/5K/10K <sup>Note 1</sup>	<b>Controller</b> ERCX ERCD <sup>Note 2</sup>	<b>Usable for CE</b> No entry: Standard E: CE marking	<b>Network option</b> No entry: None CC: CC-Link DN: DeviceNet PB: Profibus EN: Ethernet	<b>Battery</b> B1: 700mAh B2: 2000mAh

Note 1. The robot cable is standard cable, but can be changed to bend-resistant cable. See P.424 for details on robot cable.  
Note 2. To find ERCD selection options, see the ordering method on P.370.

### Specifications

<b>AC servo motor output (W)</b>	30		
<b>Repeatability</b> <sup>Note 1</sup> (mm)	±0.02		
<b>Deceleration mechanism</b>	Ball screw (Class C10)		
<b>Ball screw lead (mm)</b>	12	6	2
<b>Maximum speed (mm/sec)</b>	720	360	120
<b>Maximum payload (kg)</b>	Horizontal	4.5	6
	Vertical	1.2	2.4
<b>Rated thrust (N)</b>	32	64	153
<b>Stroke (mm)</b>	50 to 300 (50mm pitch)		
<b>Overall length (mm)</b>	Horizontal	Stroke+198	
	Vertical	Stroke+236	
<b>Maximum dimensions of cross section of main unit (mm)</b>	W45 × H53		
<b>Cable length (m)</b>	Standard: 3.5 / Option: 5.10		
<b>Linear guide type</b>	2 rows of gothic arch grooves × 1 rail		
<b>Position detector</b>	Resolvers <sup>Note 2</sup>		
<b>Resolution (Pulse/rotation)</b>	16384		

Note 1. Positioning repeatability in one direction.  
Note 2. Position detectors (resolvers) are common to incremental and absolute specifications. If the controller has a backup function then it will be absolute specifications.

### Allowable overhang <sup>Note</sup>

<b>Horizontal installation</b> (Unit: mm)	<b>Wall installation</b> (Unit: mm)	<b>Vertical installation</b> (Unit: mm)
Lead 12	A B C	A B C
2kg	433 87 180	2kg 149 54 376
4.5kg	223 33 75	4.5kg 50 1 148
3kg	515 58 135	3kg 107 24 380
6kg	340 26 62	6kg 31 0 195
3kg	1585 58 142	3kg 113 24 1180
6kg	755 27 66	6kg 32 0 440
Lead 6	A B C	A B C
1.2kg	125 125	1.2kg 125 125
2.4kg	56 57	2.4kg 56 57
3kg	41 42	3kg 41 42
7.2kg	0 0	7.2kg 0 0

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

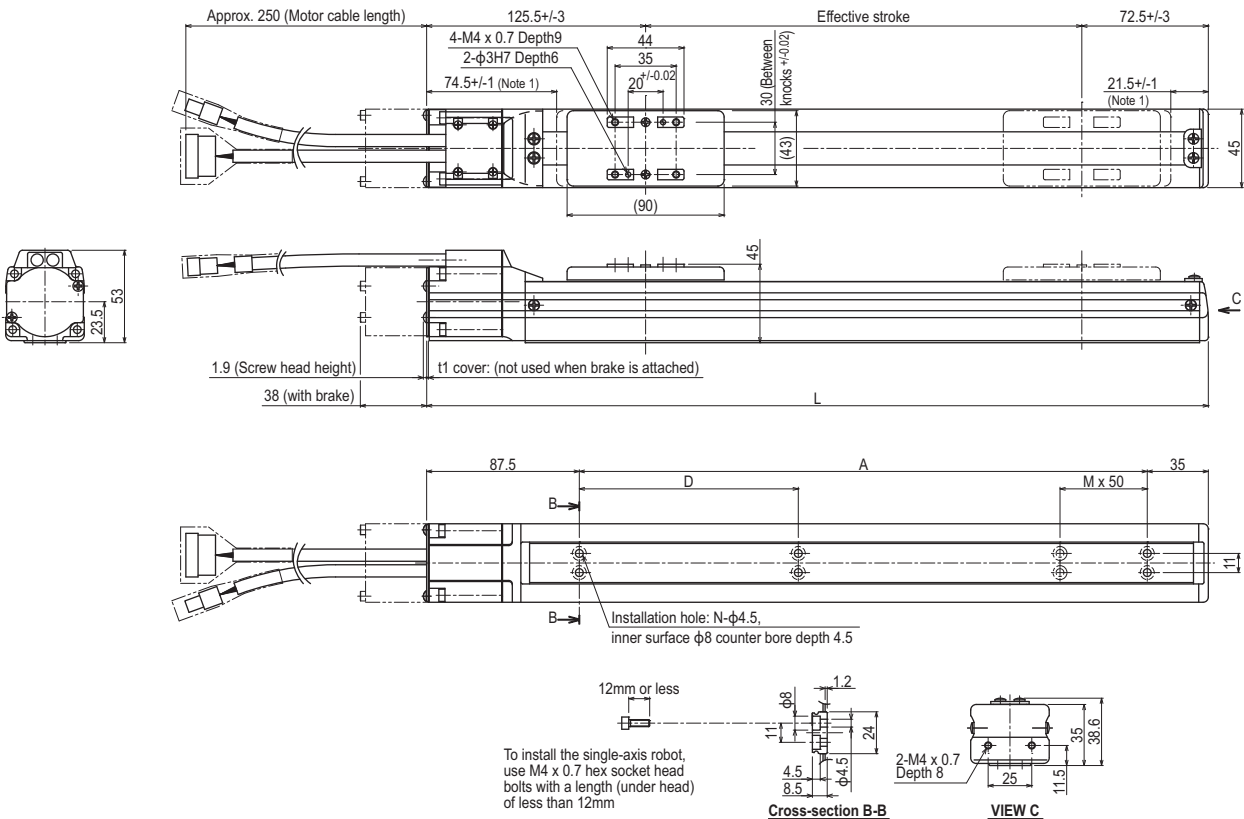
### Static loading moment

(Unit: N-m)
MY MP MR
15 19 18

### Controller

<b>Controller</b>	<b>Operation method</b>
ERCX	Programming / I/O point trace / Remote command / Operation using RS-232C communication
ERCD	Pulse train control / Programming / I/O point trace / Remote command / Operation using RS-232C communication

## T4



<b>Effective stroke</b>	50	100	150	200	250	300
<b>L</b>	248	298	348	398	448	498
<b>A</b>	125.5	175.5	225.5	275.5	325.5	375.5
<b>D</b>	-	-	-	-	125.5	125.5
<b>M</b>	0	1	2	3	0	1
<b>N</b>	4	6	8	10	6	8
<b>Weight (kg)</b> <sup>Note 3</sup>	1.1	1.2	1.3	1.4	1.5	1.6

Note 1. Distance from both ends to the mechanical stopper.  
Note 2. Minimum bend radius of motor cable is R50.  
Note 3. Weight of models with no brake. The weight of brake-attached models is 0.2 kg heavier than the models with no brake shown in the table.