

R20



- APPLICATION
- TRANSEURO
- FLIP-X
- PHASER
- XY-X
- YK-XG
- YP-X
- CLEAN
- CONTROLLER
- INFORMATION
- T type
- F type
- N type
- R type

Ordering method

R20			SR1-X	10				
Model	Cable entry location No entry: Standard (S) B: From the side	Cable length ^{Note 1} 3L: 3.5m (Standard) 5L: 5m 10L: 10m 3K/5K/10K ^{Note 1}	Controller SR1-X TS-X ^{Note 2} RDX ^{Note 2}	Driver 10: 200W	Usable for CE No entry: Standard E: CE marking	Regenerative unit No entry: None	I/O selection N: NPN P: PNP CC: CC-Link DN: DeviceNet PB: Profibus YC: YC-Link ^{Note 3}	Battery No entry: None (Incremental specification) B: Battery (Absolute specification)

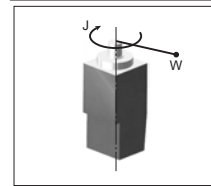
Note 1. The robot cable is standard cable, but can be changed to bend-resistant cable. (not supported on RDX). See page 423 for details on robot cable.
 Note 2. To find TS-X, RDX selection options, see the ordering method listed on each controller's page (TS-X: P.355, RDX: P.365).
 Note 3. Available only for the slave.

Specifications

AC servo motor output (W)	200
Repeatability (sec)	+/-30
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm²[kgfcm²])	1.83 [18.7]
Rated torque (Nm[kgfm])	21.46 [2.19]
Speed reduction ratio	1/50
Rotation range (°)	360
Cable length (m)	Standard: 3.5 / Option: 5.10
Speed reducer type	Harmonic drive
Position detector	-
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 (kgfcm²)	0.93	1.8	2.8	3.7	4.6	5.6	6.5	7.4	8.4	9.3
Payload parameters W (kg)	11	12	13	14	15	16	17	18	19	20
Maximum allowable moment inertia J (kgfcm²)	10.2	11.2	12.1	13.1	14	14.9	15.9	16.8	17.7	18.7



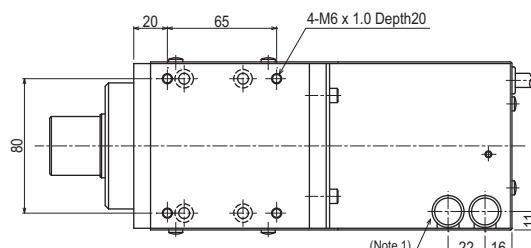
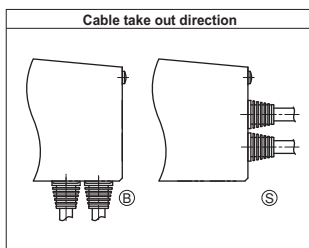
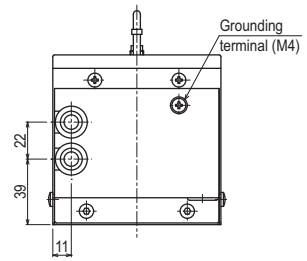
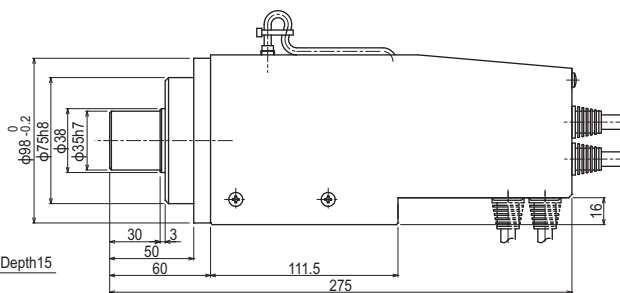
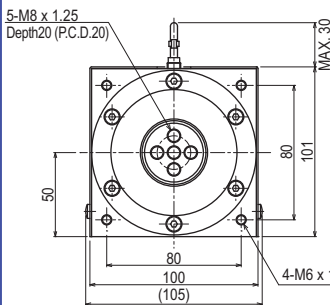
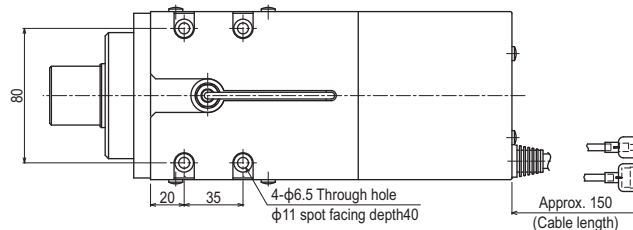
Note. When the weight of a tool or workpiece attached to the shaft R20 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 3.7kgf cm sec²) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value

Note. For calculation (equation) of the inertia moment, please refer to P.434.

Controller

Controller	Operation method
SR1-X-10	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X210	I/O point trace
RDX-10-RBR1	Pulse train control

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Weight (kg) 5.5 Note 1. The cable extraction port can be changed.