BD07 Belt type

CE compliance

Ordering method

BD07	48	N	N			S2	
Model	Lead	Brake	Origin position	Stroke	Cable length Note 1	Robot positioner	I/O
	48: 48mm	N: With no brake	N: Standard	300: 300mm 500: 500mm 600: 600mm 700: 700mm 800: 800mm 900: 900mm 1000: 1000mm 1200: 1200mm 1500: 1500mm 1800: 1800mm 2000: 2000mm	1K: 1m 3K: 3m 5K: 5m 10K: 10m	S2: TS-S2 Note2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SH			
Robot positioner	I/O	Battery	
SH: TS-SH	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)	

SD	1
Robot driver	I/O cable
SD: TS-SD	1: 1m

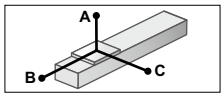
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.498 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.60.

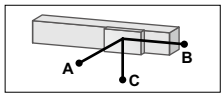
Basic specifications

Motor	56 □ Step motor
Resolution (Pulse/rotation)	20480
Repeatability Note 1 (mm)	+/-0.1
Drive method	Belt
Equivalent lead (mm)	48
Maximum speed Note 2 (mm/sec)	1500
Maximum payload (kg)	14
Stroke (mm)	300/500/600/700/800/900/1000/1200/1500/1800/2000
Overall length (mm) (Horizontal installation)	Stroke + 285.6
Maximum outside dimension of body cross-section (mm)	W70 × H147.5
Cable length (m)	Standard: 1 / Option: 3, 5, 10

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed needs to be changed in accordance with the payload.
See the "Speed vs. payload" graph shown on the right.

Allowable overhang Note





Horizontal installation (Unit: mm)

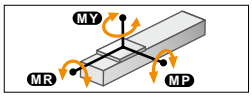
	A	B	C
3kg	5767	1353	1247
8kg	1839	399	458
14kg	829	154	254

Wall installation (Unit: mm)

	A	B	C
3kg	1324	1354	5588
8kg	474	399	1658
14kg	255	151	643

Note. Distance from center of slider upper surface to carrier center-of-gravity at a guide service life of 10,000km (This does not warrant the service life of the product.). (Service life is calculated for 600mm stroke models.)

Static loading moment

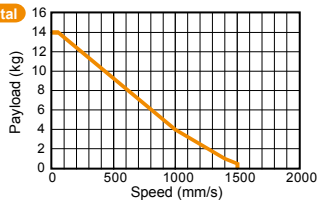


(Unit: N·m)

MY	MP	MR
46	46	101

Speed vs. payload

Horizontal



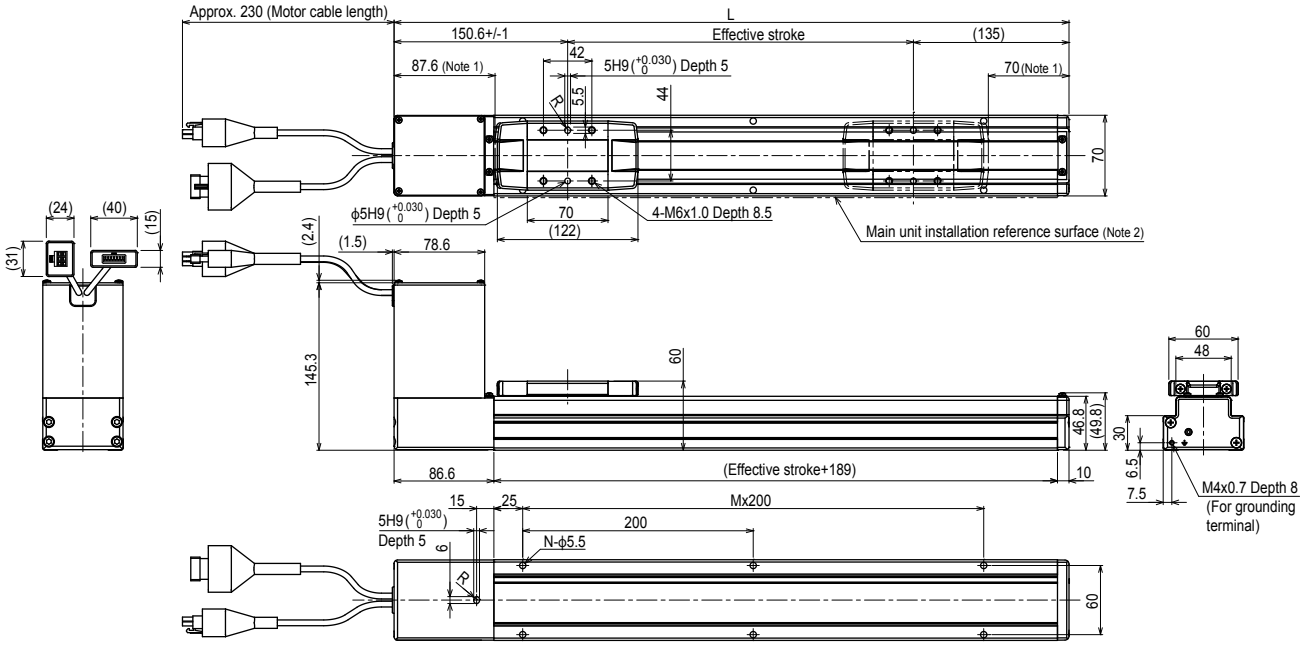
Quick reference

Payload (kg)	Speed (mm/sec)	%
14	50	3
9	525	35
4	1000	66
1	1400	93
0.5	1500	100

Controller

Controller	Operation method
TS-S2 TS-SH	I/O point trace / Remote command
TS-SD	Pulse train control

BD07



Effective stroke	300	500	600	700	800	900	1000	1200	1500	1800	2000
L	585.6	785.6	885.6	985.6	1085.6	1185.6	1285.6	1485.6	1785.6	2085.6	2285.6
M	2	3	3	4	4	5	5	6	8	9	10
N	6	8	8	10	10	12	12	14	18	20	22
Weight (kg)	4.12	4.8	5.14	5.48	5.82	6.16	6.5	7.18	8.2	9.22	9.9

Note 1. Position from both ends to the mechanical stopper. (Movable range during return-to-origin)
Note 2. When installing using the main unit installation reference surface, make the mating or positioning height 2mm or more higher than the reference surface since the R-chamfering is provided on the main unit. (Recommended height, 5mm)
Note 3. The minimum bending radius of the motor cable is R30.

Controller TS-S2 ▸ 490 TS-SH ▸ 490 TS-SD ▸ 500