

ERCD

● Dedicated for T4L / T5L / C4L / C5L

Low price and compact in size.

In addition to the conventional functions, a pulse train function is added for a wider application range.

This is a dedicated controller for the FLIP-X series models T4L, T5L, C4L, and C5L.

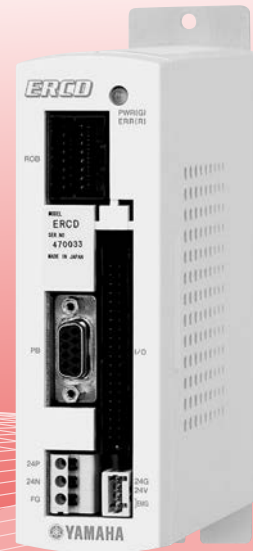
Main functions ▶ P.62



Programming box
▶ HPB/HPB-D
P.561



Support software for PC
▶ POPCOM+
P.554



ERCD

Basic specifications

Item	Model	ERCD	
Number of controllable axes	Single-axis		
Controllable robots	Single-axis robot FLIP-X series	T4L / T5L / C4L / C5L	
Capacity of the connected motor	DC24V 30W or less		
Dimensions	W44 × H166 × D117mm		
Weight	0.45kg		
Input power supply	DC24V +/-10% maximum 3A to 4.5A (Variable depending on robots in use.)		
Drive method	AC full-digital software servo		
Position detection method	Resolver		
Operating method	Normal mode: point trace movement, program operation, operation using RS-232C communication Pulse Train mode: operation by pulse train input		
Position indication units	mm (millimeters)		
Speed setting	1% to 100% (Setting by 1% unit)		
Acceleration setting	1. Automatic speed setting per robot No. and payload 2. Setting based on acceleration and deceleration parameter 1% to 100% (Setting by 1% unit)		
Resolution	16384 P/rev		
Origin search method	Incremental		
Program language	YAMAHA SRC		
Multitasks	4 tasks		
Point-data input method	Manual data input (coordinates input), Direct teaching, Remote teaching		
RAM	32 Kbytes with lithium battery backup (5-year life) Retains programs, point data, parameters and alarm history		
Programs	100 programs (Maximum program number) 255 steps per program 1024 steps / total or less		
Points	1000 points (256 when point tracing)		
External input/output	Normal mode ^{Note 1}	Sequence input	Dedicated input 8 points, General input 6 points
		Sequence output	Dedicated input 3 points, General input 6 points, Open collector output
	Pulse train mode ^{Note 1}	Sequence input	Dedicated input 5 points, General input 6 points
		Sequence output	Dedicated input 3 points, General input 6 points, Open collector output
		Command pulse input	Type
	Mode		Line driver (+5V)
	Feedback pulse output	Frequency	Maximum 2 Mpps
		Terminal name	PA+, PA-, PB+, PB-, PZ+, PZ-
		Type	Phase A / phase B / phase Z
		Mode	Line driver (+5V)
Number of pulse	16 to 4096 P/rev		
Power supply for sequence I/O	External DC +24V input		
Emergency stop input	Normal close contact point input		
Brake output	Relay output (for 24V/300mA brake) 1CH		
External communications	RS-232C 1CH (For communication with HPB or PC)		

Controllable robot	FLIP-X Dedicated for T4L/T5L P.174	Dedicated for C4L/C5L P.442
CE marking	—	Field networks —

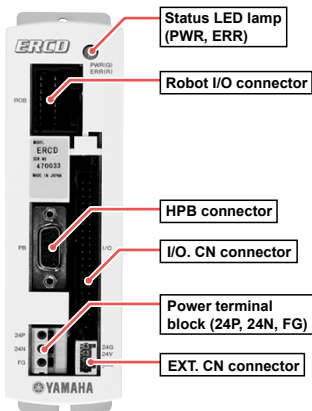
Model Overview	
Name	ERCD
Controllable robot	Dedicated for T4L / T5L / C4L / C5L
Input power	DC24V +/-10% maximum 3A to 4.5A (Variable depending on robots in use.)
Operating method	Pulse train control / Programming / I/O point tracing / Operation using RS-232C communication
Maximum number of controllable axes	Single-axis
Origin search method	Incremental

Ordering method	
ERCD	Controller
	I/O connector specification
	CN1: I/O flat cable 1m (Standard) CN2: Twisted-pair cable 2m (pulse train function)

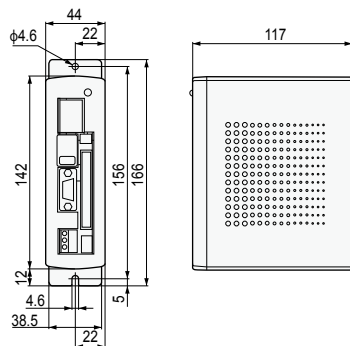
Item	Model	ERCD
Options	Programming box	HPB, HPB-D (with enable switch)
	Support software for PC	POPCOM+
General specifications	Operating temperature	0°C to 40°C
	Storage temperature	-10°C to 65°C
	Operating humidity	35% to 85%RH (non-condensing)
	Noise resistance capacity	IEC61000-4-4 Level 2
	Protective functions	Overload, overvoltage, voltage drop, resolver wire breakage, runaway detection, etc.

Note 1. Switching between the normal mode and pulse train mode is done by use of the parameter.

Part names

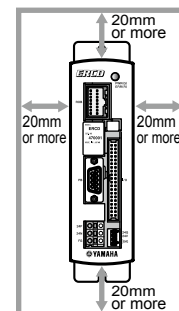


Dimensions



Installation conditions

- Install the ERCD inside the control panel.
- Install the ERCD on a vertical wall.
- Install the ERCD in a well ventilated location, with space on all sides of the ERCD (See fig. below).
- Ambient temperature : 0 to 40°C
- Ambient humidity : 35 to 85% RH (no condensation)



Articulated robots
YA
Linear CONVEYOR modules
LCM100
Compact single-axis robots
TRANSEVO
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
Robot positioner
Pulse string driver
Robot controller
I/V/I/V2 Electric gripper
Option

Connector I/O signals

Terminal number	Signal name	Function
A-1	ABS-PT	Move the point from the origin position
B-1	INC-PT	Move the point from the current position
A-2	AUTO-R	Start automatic operation
B-2	STEP-R	Start step operation
A-3	ORG-S	Return to the origin
B-3	RESET	Reset
A-4	SERVO	Return to servo on
B-4	LOCK	Interlock
A-5	DI 0	General input 0
B-5	DI 1	General input 1
A-6	DI 2	General input 2
B-6	DI 3	General input 3
A-7	DI 4	General input 4
B-7	DI 5	General input 5
A-8	(SVCE)	Service mode input
B-8	DO 5	General output 5
A-9	DO 0	General output 0
B-9	DO 1	General output 1
A-10	DO 2	General output 2
B-10	DO 3	General output 3
A-11	DO 4	General output 4
B-11	END	End normal execution
A-12	BUSY	Executing the command
B-12	READY	Ready for operation
A-13	FG	Frame ground
B-13	FG	Frame ground
A-14	GND	Signal ground
B-14	GND	Signal ground
A-15	NC	Reserved (use inhibited)
B-15	NC	Reserved (use inhibited)
A-16	NC	Reserved (use inhibited)
B-16	NC	Reserved (use inhibited)
A-17	PA+	Feedback pulse output
B-17	PA-	Feedback pulse output
A-18	PB+	Feedback pulse output
B-18	PB-	Feedback pulse output
A-19	PZ+	Feedback pulse output
B-19	PZ-	Feedback pulse output
A-20	NC	Reserved (use inhibited)
B-20	NC	Reserved (use inhibited)

Pulse train I/O connector signals

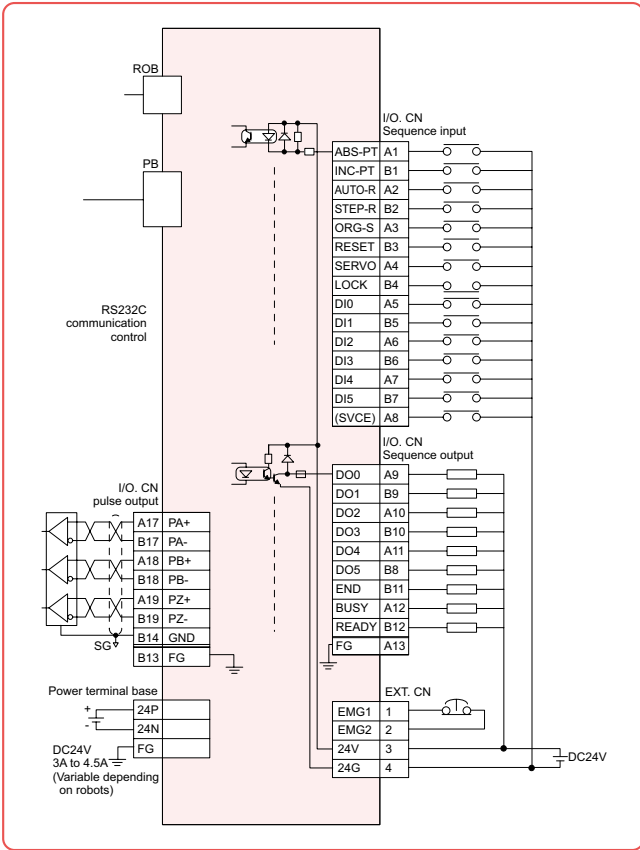
Terminal number	Signal name	Function
A-1	NC	Reserved (use inhibited)
B-1	NC	Reserved (use inhibited)
A-2	NC	Reserved (use inhibited)
B-2	PCLR	Differential clear input
A-3	ORG-S	Return to the origin input
B-3	RESET	Alarm reset input
A-4	SERVO	Servo-ON input
B-4	INH	Command pulse inhibition input
A-5	DI 0	General input 0
B-5	DI 1	General input 1
A-6	DI 2	General input 2
B-6	DI 3	General input 3
A-7	DI 4	General input 4
B-7	DI 5	General input 5
A-8	NC	Reserved (use inhibited)
B-8	DO 5	General output 5
A-9	DO 0	General output 0
B-9	DO 1	General output 1
A-10	DO 2	General output 2
B-10	DO 3	General output 3
A-11	DO 4	General output 4
B-11	IN-POS	In-position output
A-12	SRDY	Servo ready output
B-12	ALM	Alarm output
A-13	FG	Frame ground
B-13	FG	Frame ground
A-14	GND	Signal ground
B-14	GND	Signal ground
A-15	PULS+	Command pulse input
B-15	PULS-	Command pulse input
A-16	DIR+	Command direction input
B-16	DIR-	Command direction input
A-17	PA+	Feedback pulse output
B-17	PA-	Feedback pulse output
A-18	PB+	Feedback pulse output
B-18	PB-	Feedback pulse output
A-19	PZ+	Feedback pulse output
B-19	PZ-	Feedback pulse output
A-20	NC	Reserved (use inhibited)
B-20	NC	Reserved (use inhibited)

Robot Language Table

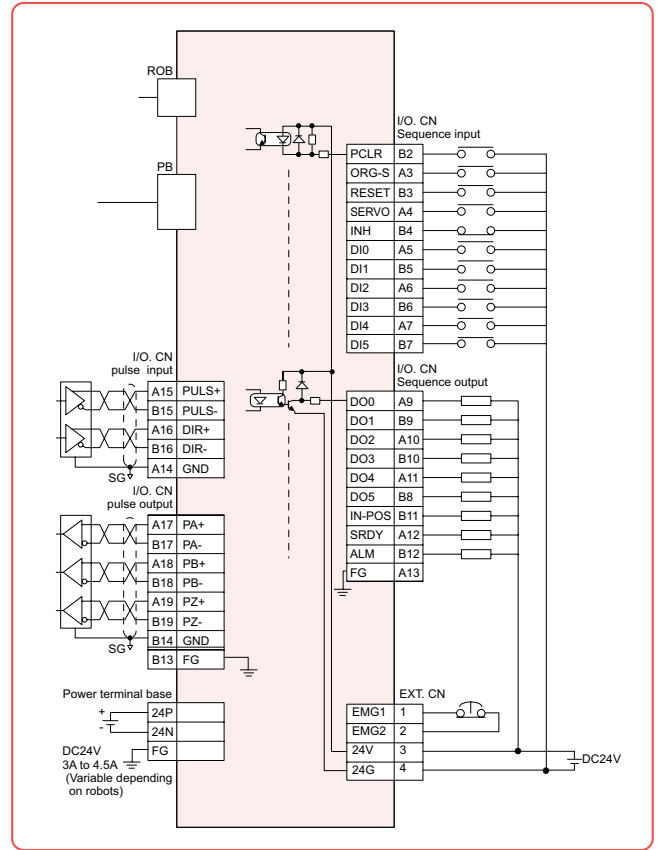
Command	Description
MOVA	Moves to a point data position.
MOVI	Moves from current position by amount of point data.
MOVF	Moves until a specified DI input is received.
JMP	Jumps to a specified label in the specified program.
JMPF	Jumps to a specified label in a specified program according to the input condition.
JMPB	Jumps to a specified label when general-purpose input or memory input is in the specified state.
L	Defines the jump destination for a JMP or JMPF statement, etc.
CALL	Runs another program.
DO	Turns general-purpose output or memory output on or off.
WAIT	Waits until general-purpose input or memory input is in the specified state.
TIMR	Waits the specified amount of time before advancing to the next step.
P	Defines point variable.
P+	Adds 1 to point variable.
P-	Subtracts 1 from point variable.
SRVO	Turns servo on or off.
STOP	Temporarily stops program execution.
ORGN	Performs return-to-origin.
TON	Runs a specified task.
TOFF	Stops a specified task.

Command	Description
JMPP	Jumps to a specified label when the axis position condition meets the specified conditions.
MAT	Defines a matrix.
MSEL	Specifies a matrix to move.
MOVm	Moves to a specified pallet work position on matrix.
JMPC	Jumps to a specified label when the counter array variable C equals the specified value.
JMPD	Jumps to a specified label when the counter variable D equals the specified value.
CSEL	Specifies an array element for counter array variable C.
C	Defines counter array variable C.
C+	Adds a specified value to counter array variable C.
C-	Subtracts a specified value from counter array variable C.
D	Defines counter variable D.
D+	Adds a specified value to counter variable D.
D-	Subtracts a specified value from counter variable D.
SHFT	Shifts the coordinate position by amount of specified point data.
IN	Stores bit information on specified general-purpose input or memory input into counter variable D.
OUT	Outputs the value of counter variable D to specified generalpurpose output or memory output.
LET	Assigns the value of a specified variable to another variable.
TORQ	Defines the maximum torque command value.

Input / output wiring diagram



Pulse train input / output wiring diagram



Pulse train input form

Logic	Command pulse form	CW direction	CCW direction
Positive logic	Phase A / phase B		
	Pulse / code		
	CW / CCW		

Logic	Command pulse form	CW direction	CCW direction
Positive logic	Phase A / phase B		
Negative logic	Pulse / code		
	CW / CCW		

Articulated robots
YA
 Linear CONVEYOR modules
LCM100
 Compact single-axis robots
TRANSERVO
 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
 Robot positioner
 Pulse string driver
 Robot controller
 I/V/I/V2 Electric gripper
 Option

Accessories and part options



ERCD

Standard accessories

- **24V power connector (for EXT. CN)**



Model	KAU-M4422-00	ERCD
-------	--------------	------

- **I/O flat cable (CN1): 1m**

Connects the standard parallel I/O to an external device. The end of the cable is cut and left as it is.



Model	KAU-M4421-00	ERCD
-------	--------------	------

- **I/O twisted-pair cable (CN2): 2m**

Connects the parallel I/O to an external device. The end of the cable is cut and left as it is.



Note. Select CN2 when using the pulse train input equipment.

Model	KAU-M4421-10	ERCD
-------	--------------	------

Options

- **Support software for PC P.554**
POPCOM+

POPCOM+ is a simple to use application software that makes tasks such as robot operation, writing-editing programs, and point teaching easy to visually understand.



Model	KBG-M4966-00	LCC140
		ERCD
		SR1-X
		SR1-P

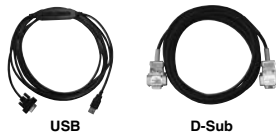
Environment

OS	Microsoft Windows XP / Vista (32bit / 64Bit) / 7 (32bit / 64Bit)
CPU	Processor that meets or exceeds the suggested requirements for the OS being used.
Memory	Suggested amount of memory or more for the OS being used.
Hard disk	50MB of available space required on installation drive.
Disk operation	RS-232C
Applicable controllers	SRCX/ERCX/DRCX/TRCX/SRCP/SRCD/ERCD/SR1/LCC140

Note. Windows is the registered trademark of US Microsoft Corporation in U.S.A. and other countries.

- **Data cables**

Communication cable for POPCOM+. Select from USB cable or D-sub cable.



Model	USB type (5m)	KBG-M538F-00	LCC140
	D-Sub type 9pin-9pin (5m)	KAS-M538F-10	ERCD
			SR1-X
			SR1-P
			RCX221
			RCX222
			RCX240/S
			RCX340

Note. This USB cable supports Windows 2000/XP or later.
Note. Data cable jointly used for POPCOM+, VIP+, RCX-Studio Pro.
Note. USB driver for communication cable can also be downloaded from our website.

- **Programming box P.561**
HPB/HPB-D

This device can perform all operations such as manual robot operation, program entry and edit, teaching and parameter settings.



	HPB	HPB-D	LCC140
Model	KBB-M5110-01	KBB-M5110-21	ERCD
Enable switch	—	3-position	SR1-X
CE marking	Not supported	Applicable	SR1-P

Articulated robots
YA
Linear conveyor modules
LCM100
Compact single-axis robots
TRANSEVO
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
Robot positioner
Pulse string driver
Robot controller
IV/V/VZ Electric gripper
Option