

# R5



## Ordering method

<b>R5</b>	<b>Cable entry location</b> No entry: Standard (S) B: From the side	<b>Cable length</b> <sup>Note 1</sup> 3L: 3.5m 5L: 5m 10L: 10m 3K/5K/10K (Flexible cable)	<b>TSX</b>	<b>Positioner</b> <sup>Note 2</sup> TS-X	<b>Driver: Power-supply voltage / Power capacity</b> 105: 100V/100W or less 205: 200V/100W or less	<b>LCD monitor</b> No entry: None L: With LCD	<b>I/O selection</b> NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ GW: No I/O board <sup>Note 3</sup>	<b>Battery</b> B: With battery (Absolute) N: None (Incremental)
			<b>SR1-X</b>	<b>Controller</b>	<b>05</b> Driver: Power capacity 05: 100W or less	<b>Usable for CE</b> No entry: Standard E: CE marking	<b>I/O selection</b> N: NPN P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS	<b>Battery</b> B: With battery (Absolute) N: None (Incremental)
			<b>RDV-X</b>	<b>Driver</b>	<b>2</b> Power-supply voltage 2: AC200V	<b>05</b> Driver: Power capacity 05: 100W or less	<b>RBR1</b> Regenerative unit	

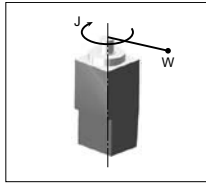
Note 1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.510 for details on robot cable.  
Note 2. See P.446 for DIN rail mounting bracket.  
Note 3. Select this selection when using the gateway function. For details, see P.439.

## Specifications

<b>AC servo motor output (W)</b>	50
<b>Repeatability (°)</b>	+/-0.0083
<b>Maximum speed (°/sec)</b>	360
<b>Maximum allowable moment inertia (kgm<sup>2</sup>[kgfcm<sup>2</sup>])</b>	0.12 [1.2]
<b>Rated torque (Nm[kgfm])</b>	5.29 [0.54]
<b>Speed reduction ratio</b>	1/50
<b>Rotation range (°)</b>	360
<b>Cable length (m)</b>	Standard: 3.5 / Option: 5.10
<b>Speed reducer type</b>	Harmonic drive
<b>Position detector</b>	Resolvers
<b>Resolution (Pulse/rotation)</b>	16384

## Maximum allowable moment inertia

Payload parameters W (kg)	1	2	3	4	5	6	7	8	9	10
<b>Maximum allowable moment inertia J (kgfcm<sup>2</sup>)</b>	0.12	0.24	0.36	0.48	0.60	0.72	0.84	0.96	1.08	1.20



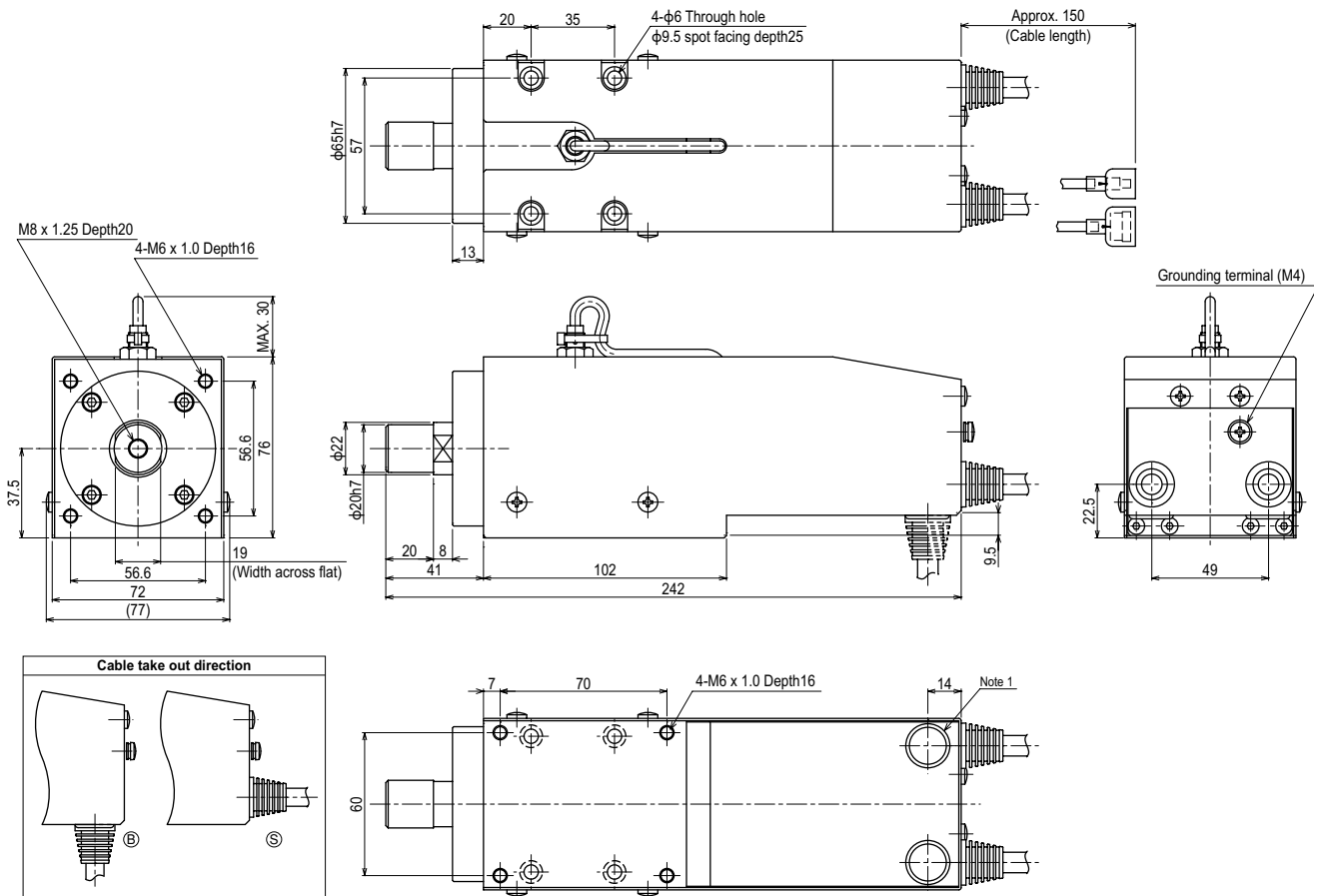
Note. When the weight of a tool or workpiece attached to the shaft R5 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 0.48kgf cm sec<sup>2</sup>.) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value.

Note. For calculation (equation) of the inertia moment, please refer to P.527.

## Controller

Controller	Operation method
SR1-X05 RCX221/222 RCX240/340	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X105 TS-X205	I/O point trace / Remote command
RDV-X205-RBR1	Pulse train control

## R5



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