R5

Ordering method

R5 – [ ] – [ ] – SR1-X – 05 – [ ] – [ ] – [ ] – [ ]

Model	Cable entry location	Cable length Note 1	Controller	Driver	Usable for CE	Regenerative unit	I/O selection	Battery
	No entry: Standard (S) B: From the side	3L: 3.5m (Standard) 5L: 5m 10L: 10m	SR1-X TS-X Note 2	05: 100W or less 105 (TS-X)	No entry: Standard E: CE marking	No entry: None	N: NPN P: PNP CC: CC-Link DN: DeviceNet PB: Profibus YC: YC-Link Note 3	No entry: None (Incremental specification) B: Battery (Absolute specification)

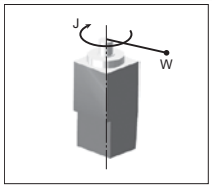
Note 1. The robot cable is standard cable, but can be changed to bend-resistant cable. (consult factory)
Note 2. To find TS-X selection options, see the ordering method listed on each controller's page.
Note 3. Available only for the SR1-X slave.

Specifications

AC servo motor output (W)	50
Repeatability (sec)	+/-30
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm^2[kgfcms^2])	0.12 [1.2]
Rated torque (Nm[kgfm])	5.29 [0.54]
Speed reduction ratio	1/50
Rotation range (°)	360
Cable length (m)	Standard: 3.5 / Option: 5,10
Speed reducer type	Harmonic drive
Position detector	Resolvers
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 (kgfcms^2)	0.12	0.24	0.36	0.48	0.60	0.72	0.84	0.96	1.08	1.20

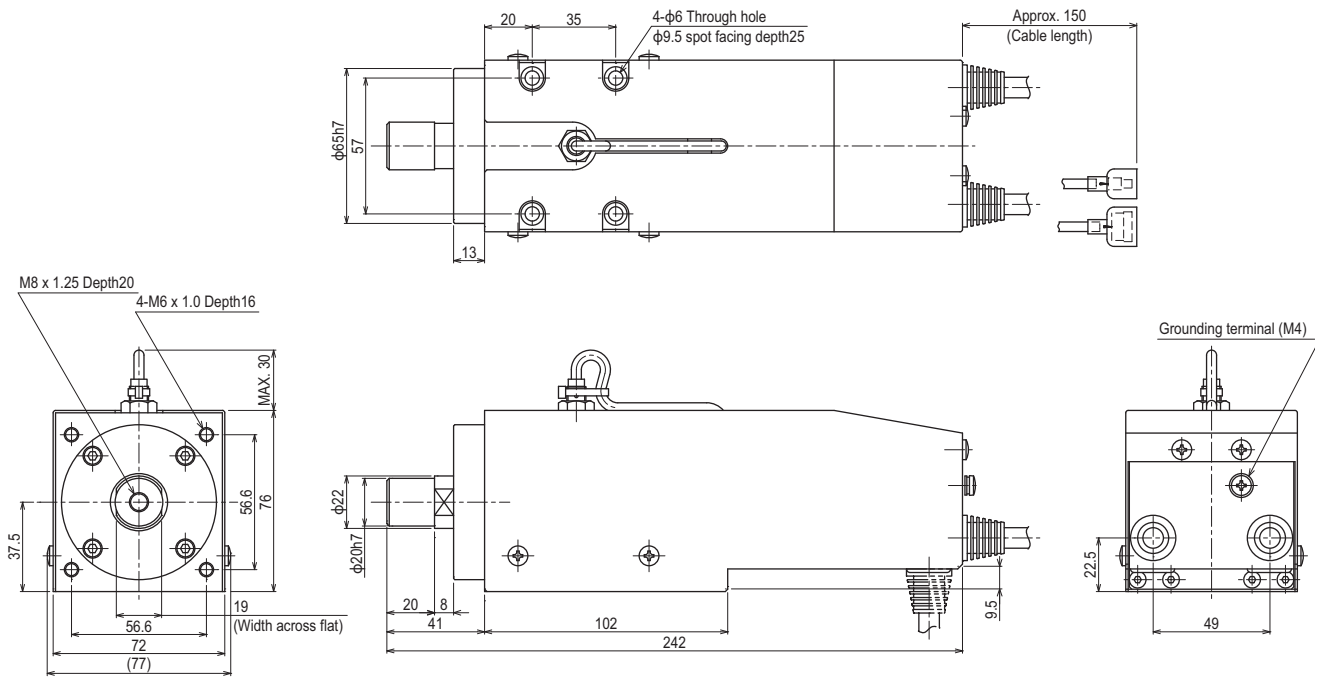


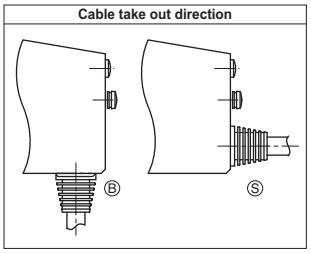
Note. When the weight of a tool or workpiece attached to the shaft R5 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 0.48kgf cm sec^2.) Enter the above mass parameter value for the controller, and optimum acceleration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

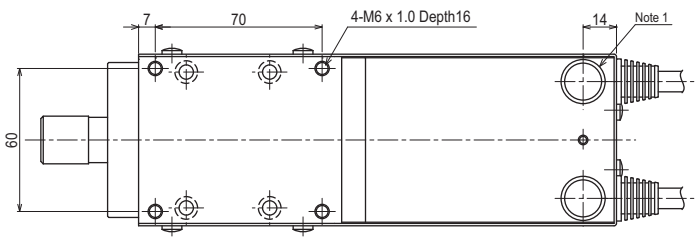
Controller

Controller	Operation method
SR1-X-05	Programming / I/O point trace (BCD)/ Remote command / Operation using RS-232C communication
TS-X105	I/O point trace (BCD)

R5







Weight (kg)	3.0

Note 1. The cable extraction port can be changed.