

C14H

Origin at non-motor side: Lead 20 • 10



Ordering method

C14H						SR1-X	10					
Model	Lead	Brake	Option	Stroke	Cable length	Controller	Driver	Usable for CE	Regenerative unit	Input/Output selection	Battery	
	20: 20mm 10: 10mm 5: 5mm	No entry: With no brake BK: With brake	Origin position None: Standard Z: Non-motor side	150 to 1050 (100mm pitch)	3L: 3.5m (Standard) 5L: 5m 10L: 10m	SR1-X TS-X	10: 200W 110 (TS-X)	No entry: Standard E: CE marking	No entry: None R: RG1 (SR1-X) R: RGT (TS-X)	N: NPN P: PNP CC: CC-Link DN: DeviceNet PB: Profibus YC: YC-Link	No entry: None (Incremental specification) B: With battery (Absolute specification)	

Note 1. If using 5mm lead specifications then the origin point cannot be changed to the side opposite the motor.
 Note 2. The robot cable is a standard cable and may be changed to a flex-resistant type. (consult factory)
 Note 3. To find TS-X selection options, see the ordering method listed on each controller's page.
 Note 4. When using the vertical model of SR1-X or TS-X, a regeneration unit is required.
 Note 5. Available only for the SR1-X slave.

Basic specifications

AC servo motor output (W)	200		
Repeatability (mm)	+/-0.01		
Deceleration mechanism	Ball screw (Class C7)		
Ball screw lead (mm)	20	10	5
Maximum speed (mm/sec)	1000	500	250
Maximum payload (kg)	Horizontal	Vertical	
	40	80	100
	8	20	30
Rated thrust (N)	170	341	683
Stroke (mm)	150 to 1050 (100mm pitch)		
Overall length (mm)	Horizontal	Stroke+349	
	Vertical	Stroke+379	
Maximum outside dimension of body cross-section (mm)	W136 x H96		
Cable length (m)	Standard: 3.5 / Option: 5, 10		
Degree of cleanliness	CLASS 10		
Intake air (Nl/min)	30 to 90		

Note 1. Positioning repeatability in one direction.
 Note 2. When the stroke is longer than 750mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.
 Note 3. Per 1cf (0.1µm base), when suction blower is used.
 Note 4. The necessary intake amount varies depending on the use conditions and environment.

Allowable overhang

Lead	Horizontal installation (Unit: mm)			Wall installation (Unit: mm)			Vertical installation (Unit: mm)		
	A	B	C	A	B	C	A	C	
Lead 20	10kg	2247	1675	987	1210	1678	4kg	2400	2008
	20kg	1397	855	497	548	958	6kg	1687	1358
	40kg	1037	445	247	217	598	8kg	1287	1033
	30kg	1937	583	402	328	1238	10kg	1347	1088
	50kg	1637	364	227	152	878	15kg	887	718
Lead 10	10kg	1043	775	497	548	958	20kg	657	538
	20kg	683	364	327	217	598	20kg	747	608
	30kg	1937	583	402	328	1238	25kg	663	484
	40kg	1637	364	227	152	878	30kg	491	396
	50kg	1637	364	227	152	878			
Lead 5	10kg	2443	1811	119	74	678			
	20kg	1717	242	197	108	1308			
	30kg	1937	583	127	53	1008			
	40kg	2193	242	85	20	788			
	50kg	2000	202						

Note. Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

Static loading moment

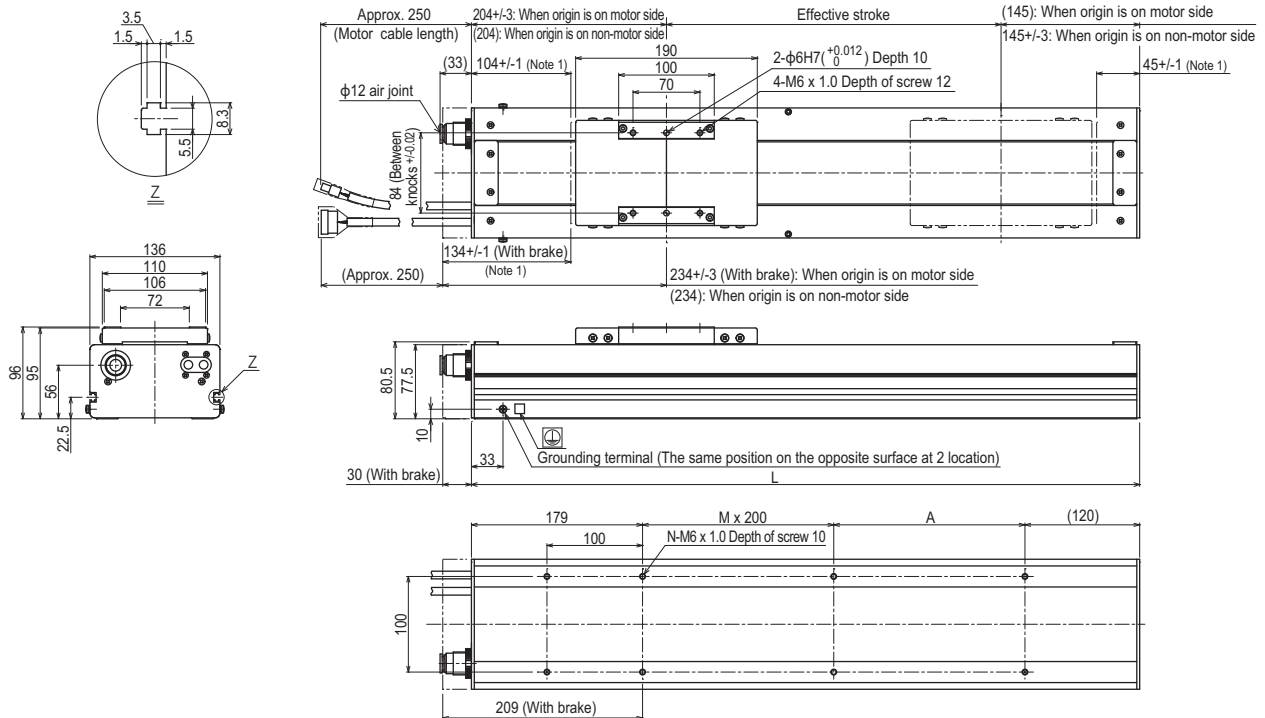
MY	MP	MR
293	294	258

Controller

Controller	Operation method
SR1-X-10	Programming / I/O point trace (BCD) / Remote command / Operation using RS-232C communication
TS-X110	I/O point trace (BCD)

Note. Regenerative unit is required when used vertically.

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Effective stroke	150	250	350	450	550	650	750	850	950	1050	
	L	499	599	699	799	899	999	1099	1199	1299	1399
A	200	100	200	100	200	100	200	100	200	100	
M	0	1	1	2	2	3	3	4	4	5	
N	6	8	8	10	10	12	12	14	14	16	
Weight (kg)	10.7	12.0	13.2	14.5	15.8	17.0	18.3	19.6	20.8	22.1	
Maximum speed (mm/sec)	Lead 20	1000					950	750	600	500	
	Lead 10	500					475	375	300	250	
	Lead 5	250					237	187	150	125	
	Speed setting	-					95%	75%	60%	50%	

Note 1. Distance from both ends to the mechanical stopper.
 Note 2. Minimum bend radius of motor cable is R50.
 Note 3. Weight of models with no brake. The weight of brake-attached models is 0.4 kg heavier than the models with no brake shown in the table.
 Note 4. When the stroke is longer than 750mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.