

R5

Standard

Robot ordering method

R5 - 3L - SR1-X - 05 - E^{Note 1} - N - B^{Note 1}

Model	Cable length	Applicable controller	Driver	Usable for CE	Inputs/Outputs selection	Battery
	- 3L : 3.5m (Standard) - 5L : 5m - 10L : 10m	- SR1-X - RDX (see page 52)	- 05 : 100W or less - 10 : 200W - 20 : 400 to 600W	- No entry : Standard - E : CE specification	- N : NPN - P : PNP - CC : CC-Link - DN : DeviceNet - PB : Profibus - YC : YC-Link ^{Note 2}	- No entry : None (Incremental specification) - B : Battery (Absolute specification)

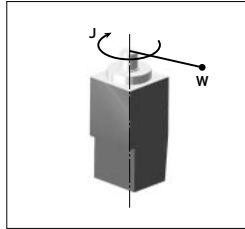
Note 1 : It will be a customer's choice.
Note 2 : Available only for the slave.

Basic specifications

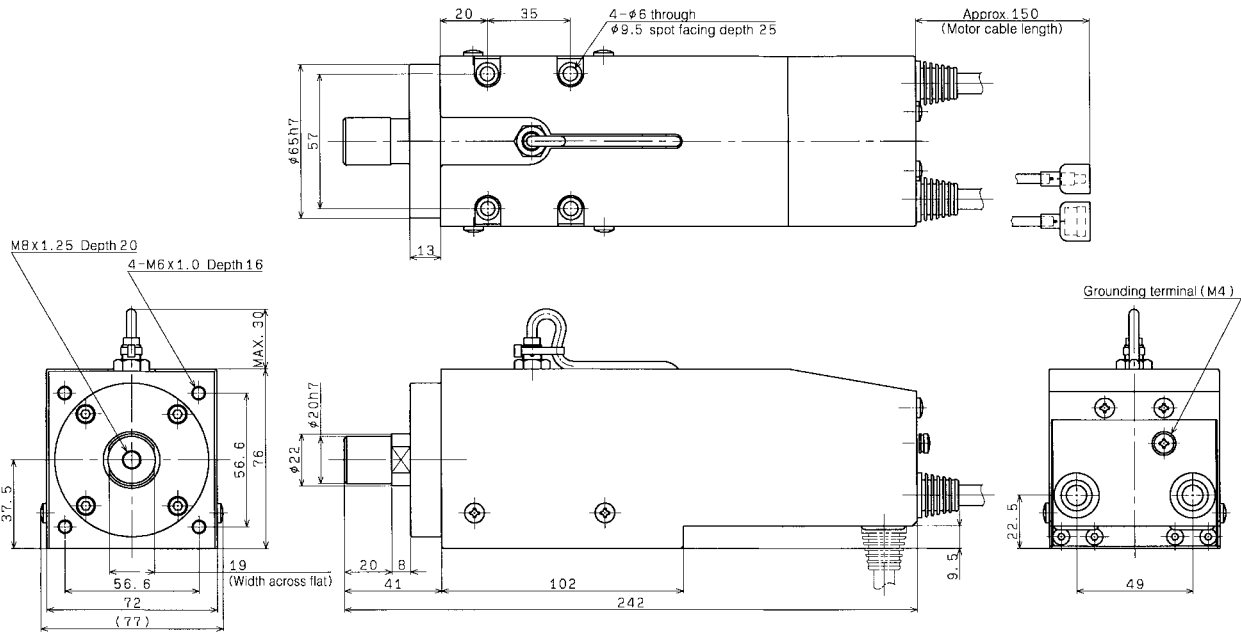
AC servo motor output(W)	50
Maximum speed(deg/sec)	360
Repeatability(sec)	+/-30
Maximum allowable moment inertia(kgf, cm, sec ²)	1.2(0.12kg, m ²)
Rated torque(kg, m)	0.54
Speed reduction ratio	1/50
Rotation range(deg)	360
Cable length(m)	3.5(Standard), 5, 10
Controller	SR1-X-05
Robot driver	RDX-05-RBR1

Maximum allowable moment inertia

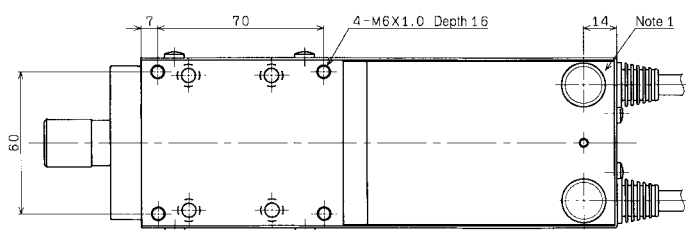
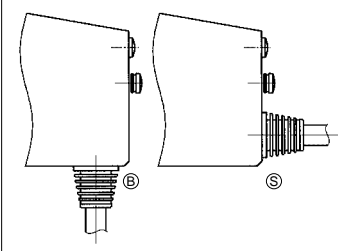
Weight parameter W(kg)	1	2	3	4	5	6	7	8	9	10
Maximum allowable moment inertia J(kgf, cm, sec ²)	0.12	0.24	0.36	0.48	0.60	0.72	0.84	0.96	1.08	1.20



Note : When the weight of the tool and work installed to the shaft of R5 is Wkg, adjust so that its inertia moment value J is smaller than that in the above table. If it exceeds that value, enter the corresponding value in the above table.
(Example: When W is 3kg and J is 0.48kgf, cm, sec², enter 4kg.)



Direction of robot cable connection



Weight(kg) 3.0

Note 1 : The port where the cable is taken out can be changed.