

# R10



## Ordering method

<b>R10</b>		<b>SR1-X</b>	<b>05</b>				
<b>Model</b>	Cable entry location No entry: Standard (S) B: From the side	<b>Cable length Note 1</b> 3L: 3.5m (Standard) 5L: 5m 10L: 10m 3K/5K/10K Note 1	<b>Controller</b> SR1-X TS-X Note 2 RDX Note 2	<b>Driver</b> 05: 100W or less	<b>Usable for CE</b> No entry: Standard E: CE marking	<b>Regenerative unit</b> No entry: None	<b>I/O selection</b> N: NPN P: PNP C: CC-Link D: DeviceNet PB: Profibus YC: YC-Link Note 3
							<b>Battery</b> 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. (not supported on RDX). See page 423 for details on robot cable.

Note 2. To find TS-X, RDX selection options, see the ordering method listed on each controller's page (TS-X: P.355, RDX: P.365).

Note 3. Available only for the slave.

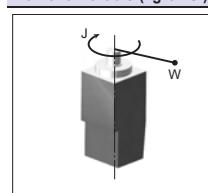
## Specifications

AC servo motor output (W)	100
Repeatability (sec)	+/-30
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm <sup>2</sup> )(kgfcm <sup>2</sup> )	0.36 [3.71]
Rated torque (Nm[kgfm])	10.78 [1.10]
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 <sup>2</sup> )	0.25	0.49	0.74	0.99	1.24	1.48	1.73	1.98	2.23	2.47

Payload parameters W (kg)	11	12	13	14	15
Maximum allowable moment inertia J (kgfcms <sup>2</sup> )	2.72	2.97	3.22	3.46	3.71



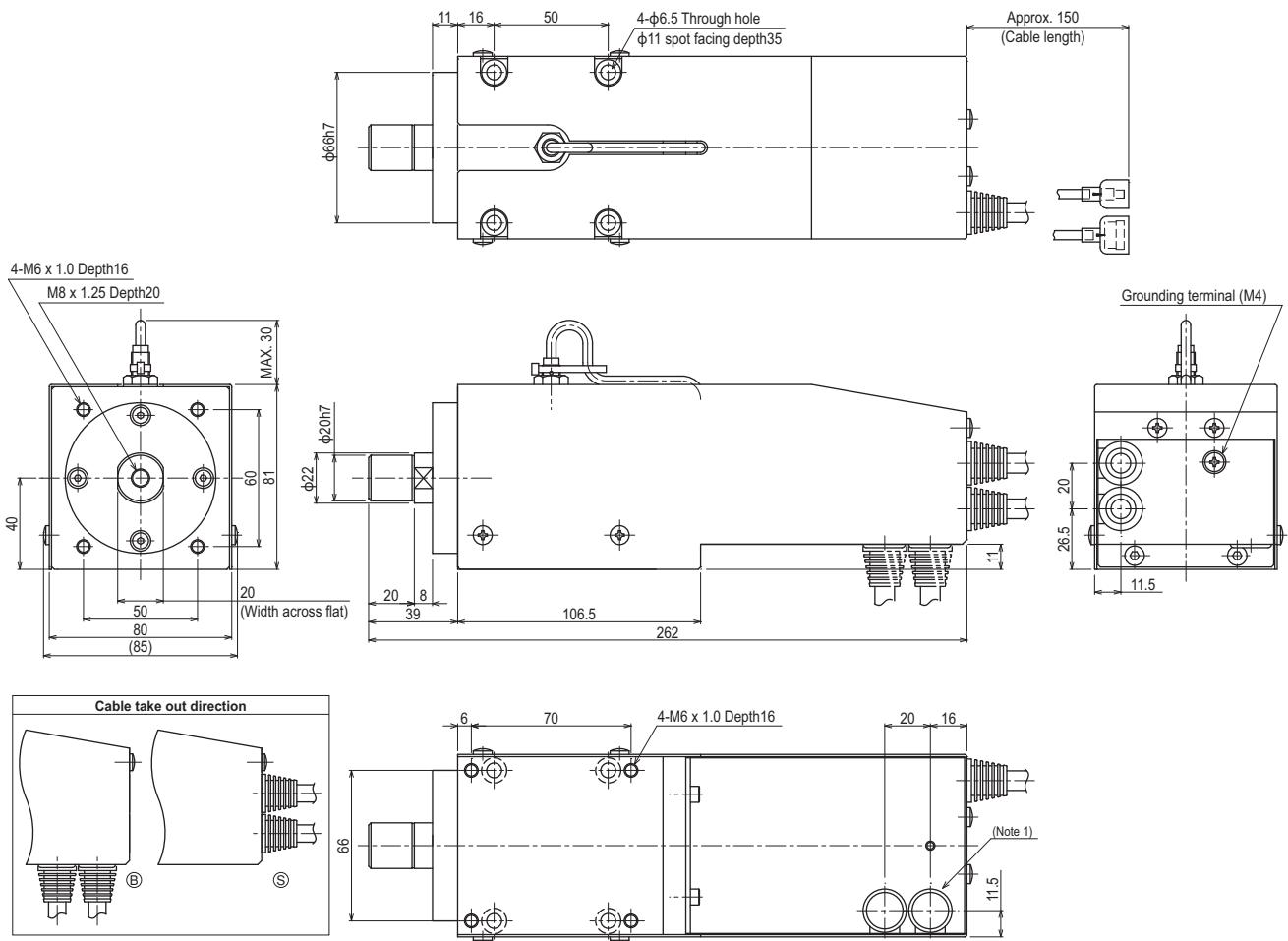
Note. When the weight of a tool or workpiece attached to the shaft R10 is W (kg), its moment of inertia (J) must be smaller than the values shown in the table above. (For example, enter 4kg if W is 3kg and J is 0.99kgf cm sec<sup>2</sup>.) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value.

Note. For calculation (equation) of the inertia moment, please refer to P.434.

## Controller

Controller	Operation method
SR1-X-05	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X205	I/O point trace
RDX-05-RBR1	Pulse train control

## R10



Weight (kg)

3.5

Note 1. The cable extraction port can be changed.

APPLICATION	Single-axis robots
TRANSEROV	Compact
FLIP-X	Single-axis robots
PHASER	single-axis robots
X-Y-X	Cartesian
YK-XG	SCARA robots
YP-X	Pick & place robots
CLEAN	Clean room
CONTROLLER	Controller
INFORMATION	Information
T type	
F type	
N type	
R type	