

C5



● Origin at non-motor side

Ordering method

| | | | | | | | | | | | | | | |
|--------------|--------------------|---|--|---|---------------------------|---|------------------------------------|-------------------------------------|--|---------------------------|--|--|--|--|
| C5 | | | | | | | | | | ERCX | | | | |
| Model | Lead | Brake | Direction of air coupler installation | Option | Stroke | Cable length <small>Note 1</small> | Controller | Usable for CE | Network option | Battery | | | | |
| | 12: 12mm 6: 6mm | No entry: With no brake BK: With brake | L: Left (Standard) R: Right | Origin position change None: Standard Z: Non-motor side | 50 to 600 (50mm pitch) | 3L: 3.5m (Standard) 5L: 5m 10L: 10m | ERCX ERCD <small>Note 2</small> | No entry: Standard E: CE marking | No entry: None CC: CC-Link DN: DeviceNet PB: Profibus EN: Ethernet | B1: 700mAh B2: 2000mAh | | | | |

Note 1. The robot cable is standard cable and may be changed to a flex-resistant type. See P.423 for more information on robot cables.
Note 2. To find ERCD selection options, see the ordering method on P.370.

Basic specifications

| | | |
|---|--------------------------------|--------------|
| AC servo motor output (W) | 30 | |
| Repeatability <small>Note 1</small> (mm) | ±0.02 | |
| Deceleration mechanism | Ball screw (Class C10) | |
| Ball screw lead (mm) | 12 | 6 |
| Maximum speed (mm/sec) | 800 | 400 |
| Maximum payload (kg) | Horizontal | 5 |
| | Vertical | 9 |
| Rated thrust (N) | Horizontal | 1.2 |
| | Vertical | 2.4 |
| Stroke (mm) | 50 to 600 (50mm pitch) | |
| Overall length (mm) | Horizontal | Stroke+201.5 |
| | Vertical | Stroke+236.5 |
| Maximum outside dimension of body cross-section (mm) | W55 × H65 | |
| Cable length (m) | Standard: 3.5 / Option: 5, 10 | |
| Degree of cleanliness | CLASS 10 <small>Note 2</small> | |
| Intake air (Nl/min) | 20 to 30 <small>Note 3</small> | |

Note 1. Positioning repeatability in one direction.
Note 2. Per 1cf (0.1µm base), when suction blower is used.
Note 3. The necessary intake amount varies depending on the use conditions and environment.

Allowable overhang

| Horizontal installation (Unit: mm) | | | | Wall installation (Unit: mm) | | | | Vertical installation (Unit: mm) | | | |
|------------------------------------|-----|------|-----|------------------------------|-----|-----|-----|----------------------------------|-------|-----|-----|
| | A | B | C | | A | B | C | Lead 6 | A | C | |
| Lead 12 | 2kg | 1166 | 159 | 406 | 2kg | 364 | 126 | 1073 | 1.2kg | 246 | 245 |
| | 5kg | 551 | 59 | 155 | 5kg | 123 | 28 | 438 | | | |
| Lead 6 | 3kg | 1194 | 104 | 294 | 3kg | 259 | 72 | 354 | | | |
| | 9kg | 624 | 31 | 89 | 9kg | 50 | 0 | 154 | 2.4kg | 110 | 110 |

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

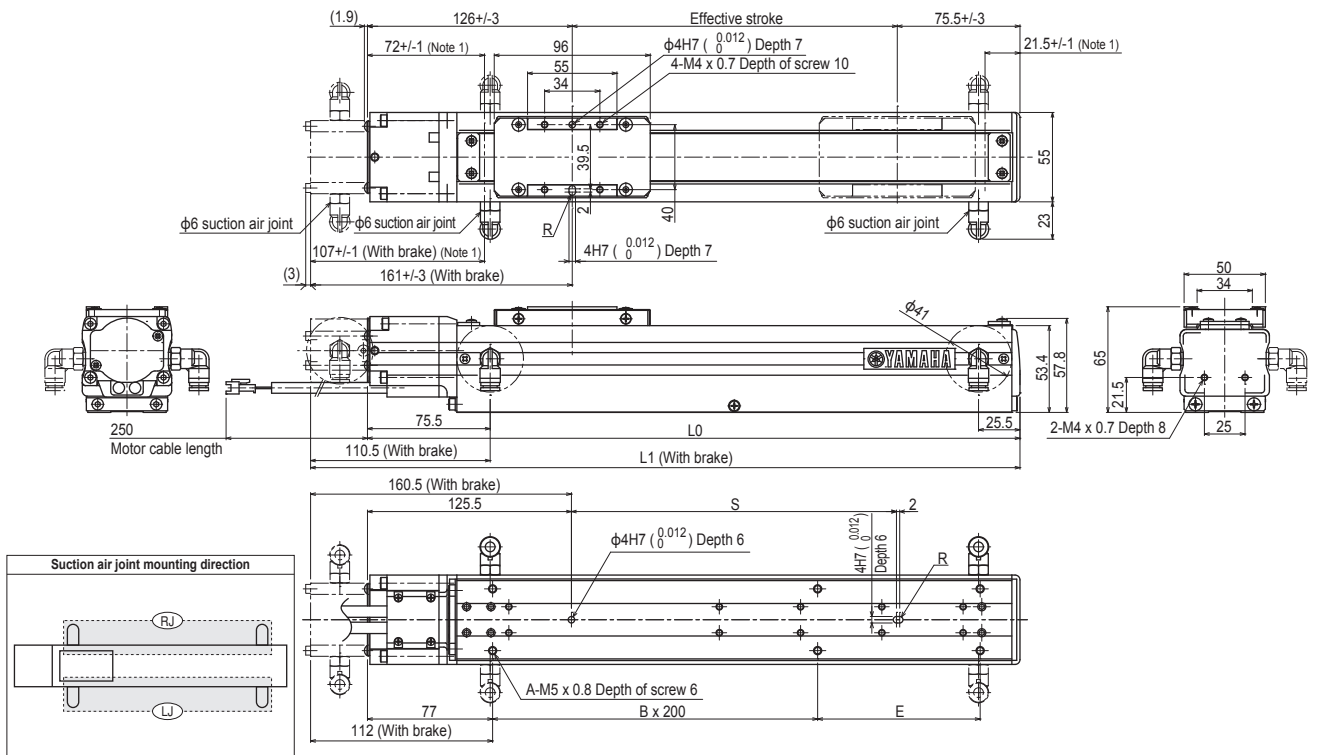
Static loading moment

| (Unit: N-m) | | |
|-------------|----|----|
| MY | MP | MR |
| 30 | 34 | 40 |

Controller

| Controller | Operation method |
|------------|--|
| ERCX | Programming / I/O point trace / Remote command / Operation using RS-232C communication |
| ERCD | Pulse train control / Programming / I/O point trace / Remote command / Operation using RS-232C communication |

C5



| Effective stroke | 50 | 100 | 150 | 200 | 250 | 300 | 350 | 400 | 450 | 500 | 550 | 600 |
|--|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|
| A | 4 | 4 | 4 | 6 | 6 | 6 | 6 | 8 | 8 | 8 | 8 | 10 |
| B | 0 | 0 | 0 | 1 | 1 | 1 | 1 | 2 | 2 | 2 | 2 | 3 |
| E | 100 | 200 | 200 | 100 | 100 | 200 | 200 | 100 | 100 | 200 | 200 | 100 |
| L0 | 251.5 | 301.5 | 351.5 | 401.5 | 451.5 | 501.5 | 551.5 | 601.5 | 651.5 | 701.5 | 751.5 | 801.5 |
| L1 | 286.5 | 336.5 | 386.5 | 436.5 | 486.5 | 536.5 | 586.5 | 636.5 | 686.5 | 736.5 | 786.5 | 836.5 |
| S | 50 | 100 | 150 | 200 | 250 | 300 | 350 | 400 | 450 | 500 | 550 | 600 |
| Weight (kg) <small>Note 4</small> | 2.3 | 2.4 | 2.6 | 2.8 | 2.9 | 3.1 | 3.3 | 3.4 | 3.6 | 3.8 | 3.9 | 4.1 |

Note 1. Distance from both ends to the mechanical stopper.
Note 2. Either right or left can be selected for the installation direction for the φ6 intake air joint.
Note 3. Minimum bend radius of motor cable is R50.
Note 4. Weight of models with no brake. The weight of brake-attached models is 0.2 kg heavier than the models with no brake shown in the table.

320

Controller
ERCX ▶ 374 ERCD ▶ 370

APPLICATION
TRANSMISSION
Compact single-axis robots
FLIP-X
Single-axis robots
PHASER
Linear motor single-axis robots
XY-X
Cartesian robots
YK-XG
SCARA robots
YP-X
Pick & place robots
CLEAN
CONTROLLER INFORMATION
Single-axis
Cartesian
SCARA