

C5H



Origin at non-motor side

Ordering method

C5H							SR1-X	05				
Model	Lead	Brake	Direction of air coupler installation	Option	Stroke	Cable length <small>Note 1</small>	Controller	Driver	Usable for CE	Input/Output selection	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	SR1-X TS-X <small>Note 2</small> RDX <small>Note 2</small>	05: 100W or less	No entry: Standard E: CE marking	N: NPN P: PNP CC: CC-Link DN: DeviceNet PB: Profibus YC: YC-Link <small>Note 3</small>	No entry: None (Incremental specification) B: With battery (Absolute specification)	

Note 1. The robot cable is a standard cable and may be changed to a flex-resistant type. See P.423 for more information on robot cables.
 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.

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	Vertical
	5	9
Rated thrust (N)	32	
Stroke (mm)	50 to 600 (50mm pitch)	
Overall length (mm)	Horizontal	Vertical
	Stroke+201.5	Stroke+236.5
Maximum outside dimension of body cross-section (mm)	W55 x 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

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

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

Static loading moment

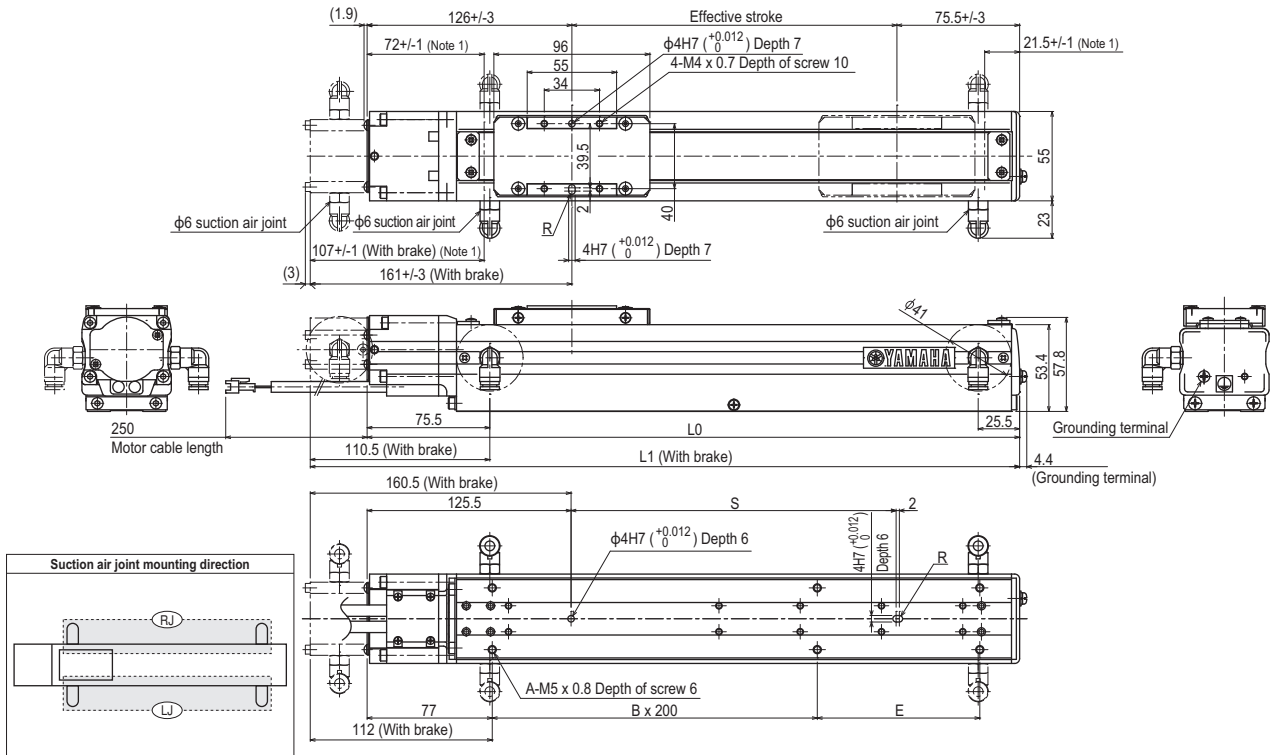
(Unit: N-m)

MY	MP	MR
30	34	40

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	Pulse train control

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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.

APPLICATION
 TRANSERO 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