

R20



Ordering method

R20

Model

Cable entry location

No entry: Standard (S)
B: From the side

Cable length

Note 1

3L: 3.5m
5L: 5m
10L: 10m
3K/5K/10K
(Flexible cable)

TSX

Positioner

TSX: TS-X

Driver: Power-supply voltage / Power capacity

110: 100V/200W or less
210: 200V/200W or less

LCD monitor

No entry: None
L: With LCD

I/O selection

NP: NPN
PN: PNP
CC: CC-Link
DN: DeviceNet™
EP: EtherNet/IP™
PT: PROFINET
GW: No I/O board

Note 3

Battery

B: With battery (Absolute)
N: None (Incremental)

SR1-X

Controller

10

Driver: Power capacity

10: 200W or less

Usable for CE

No entry: Standard
E: CE marking

I/O selection

N: NPN
P: PNP
CC: CC-Link
DN: DeviceNet™
PB: PROFIBUS

Battery

B: With battery (Absolute)
N: None (Incremental)

RDV-X

Driver

2

Power-supply voltage

2: AC200V

10

Driver: Power capacity

10: 200W or less

RBR1

Regenerative unit

Note 1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable.
See P.692 for details on robot cable.

Note 2. See P.600 for DIN rail mounting bracket.

Note 3. Select this selection when using the gateway function.

Specifications

AC servo motor output (W)	200
Repeatability (°)	+/-0.0083
Maximum speed (°/sec)	360
Maximum allowable moment inertia (kgm ² [kgfcm ²])	1.83 [18.7]
Rated torque (Nm[kgfm])	21.46 [2.19]
Speed reduction ratio	1/50
Rotation range (°)	360
Cable length (m)	Standard: 3.5 / Option: 5,10
Speed reducer type	Harmonic drive
Position detector	-
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 (kgfcm ²)	0.93	1.8	2.8	3.7	4.6	5.6	6.5	7.4	8.4	9.3

Payload parameters W (kg)	11	12	13	14	15	16	17	18	19	20
Maximum allowable moment inertia J (kgfcm ²)	10.2	11.2	12.1	13.1	14	14.9	15.9	16.8	17.7	18.7

Note. When the weight of a tool or workpiece attached to the shaft R20 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 3.7kgf cm sec².) Enter the above mass parameter value for the controller, and optimum acceleration is automatically set based on this value.

Controller

Controller	Operation method
SR1-X10 RCX320 RCX340	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X110 TS-X210	I/O point trace / Remote command
RDV-X210-RBR1	Pulse train control

Note. For calculation (equation) of the inertia moment, please refer to P.708.

R20

80

20

35

4-φ6.5 Through hole
φ11 spot facing depth40

Approx. 150
(Cable length)

5-M8 x 1.25
Depth20 (P.C.D.20)

MAX. 30

80

101

50

80

100
(105)

4-M6 x 1.0 Depth15

φ88 -0.2

φ75h8

φ38

φ35h7

30

3

50

60

111.5

275

16

Grounding terminal (M4)

22

39

11

Cable take out direction

20

65

4-M6 x 1.0 Depth20

80

(Note 1)

22

16

Weight (kg)

5.5

Note 1. The cable extraction port can be changed.