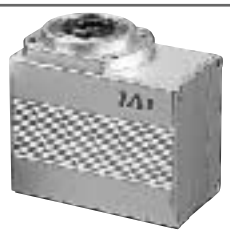
RCP2-RTB

Robo Rotary: Vertical Type (50 mm wide), Pulse Motor

Type	Oscillation angle	Maximum torque
Rotary (50 mm wide)	330 deg	1.7N • m



Model Specification Items

Series	Type	Encoder type	Motor	Gear ratio	Stroke	Applicable controller	Cable length	Options
(Example) RCP2 –	RTB –	I –	PM –	20 –	330 –	P1 –	S –	SA

* Refer to page 37 for details on the specification items.

Model/Specifications

Model	Encoder type	Motor	Gear ratio	Oscillation angle (deg)	Maximum speed (Note 1) (deg/sec)	Maximum torque (Note 2) (N-m)	Allowable inertial moment (kg-m²)
RCP2-RTB-I-PM-20-330-P1-△-☐	Incremental	Pulse motor	1 / 20	330	600	1.1	0.01
RCP2-RTB-I-PM-30-330-P1-△-☐			1 / 30		400	1.7	0.015

* In the above model name, △ indicates the cable length and ☐ the applicable option(s).

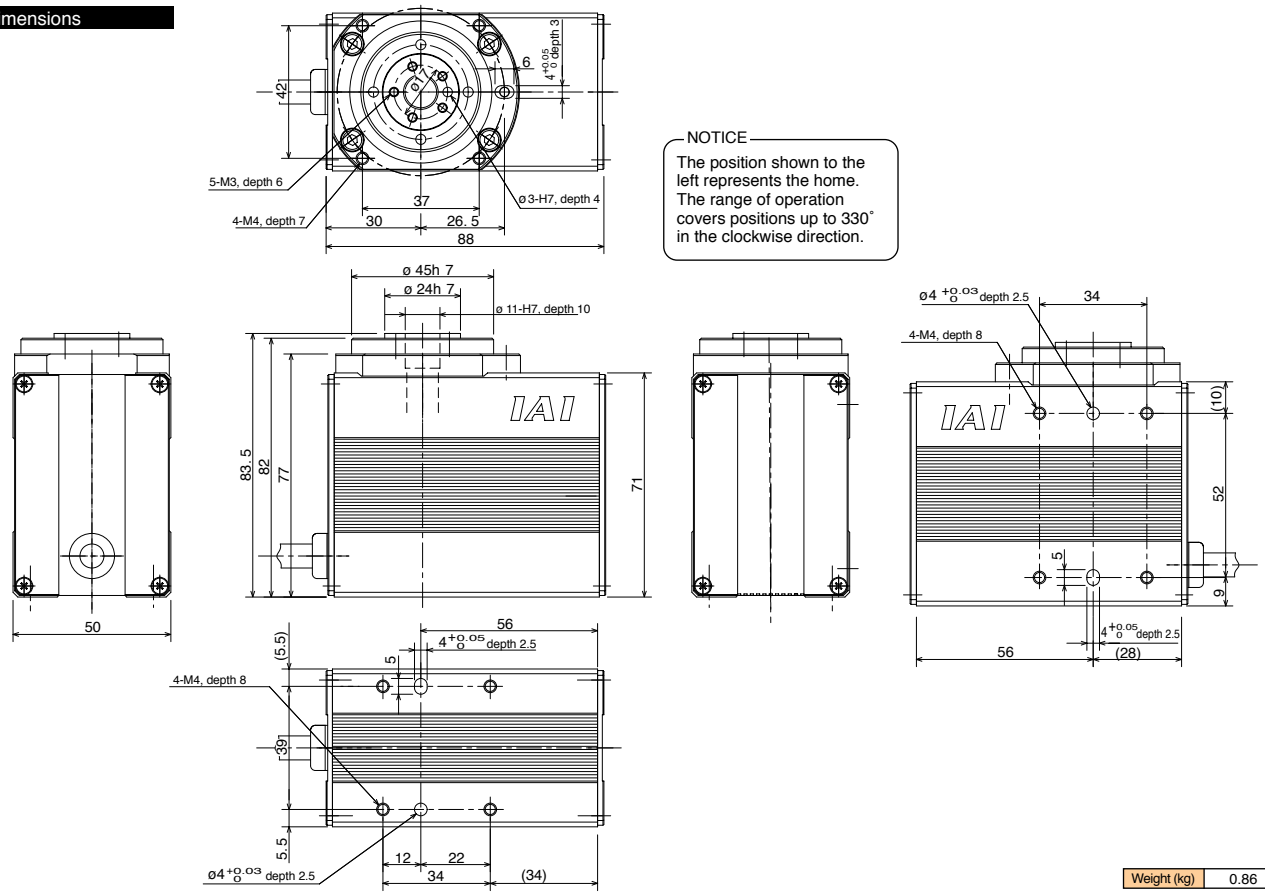
Options

Name	Type	Page
Shaft Bracket	SA	→P140
Flange Bracket	TA	→P140

Common Specifications

Drive system	Hypoid gear
Positioning repeatability (Note 3)	±0.01mm
Backlash	±0.1°
Allowable thrust load	50N
Allowable load moment	3.9N • m
Base	Material: Aluminum with white alumite treatment
Cable length (Note 4)	N: No cable, P: 1 m, S: 3 m, M: 5 m, X☐☐: Length specification, R☐☐: Robot cable
Weight	0.86kg

Dimensions



Weight (kg)	0.86

Specifications

Applicable controller	Maximum number of controlled axes	Compatible encoder type	Program operation	Positioner operation	Pulse-train control	Power-supply voltage	Page
RCP2-C	1 axis	Incremental	×	○	×	DC24V	→P151
RCP2-CG	1 axis	Incremental	×	○	×	DC24V	→P151

Caution

(Note 1) Indicate the maximum speed that can be set under no load.
(Note 2) Indicate the maximum torque that can be generated at low speed. (The generated torque will vary depending on the speed. Refer to page 36 for details.)
(Note 3) The positioning repeatability when the target position is approached from the same direction.
(Note 4) The maximum cable length is 20 m. Specify the desired length in meters (e.g., X08 = 8 m).

* Refer to page 23 for other points to note.