

Large Diameter Hollow Rotary **RCS2-RTC**



SIGNIFICANT INCREASE IN ACCURACY/SPEED/TORQUE

Adoption of the hollow structure provides a large diameter hollow rotary series with improved usability



1. Hollow Construction

Large-diameter hollow structure, allows installation of rotating wires and laying of pipes easier.

2. High Precision

Hypoid gear with high resolution (0.0015 to 0.0007 deg/pulse) encoder allows high accuracy ± 0.005 degree. Can be used as a high precision table.

3. Multi-turn Operation

The operating range is up to ± 9999 degrees * from home. It is also possible to rotate indefinitely in the same direction.
*Depending upon the model

4. High Rigidity

To achieve high rigidity, cross-roller bearings are used in the large diameter spindle and table. Available in small, medium, and large body sizes.

5. No Return to Home

Homing is not required with the absolute encoder type. In the case of an emergency stop, work can resume from the last stopped position.

6. Internal Brake (Optional)

Since the brake specification can be selected, the actuator can be powered off but still hold position of the table during an emergency stop.



1

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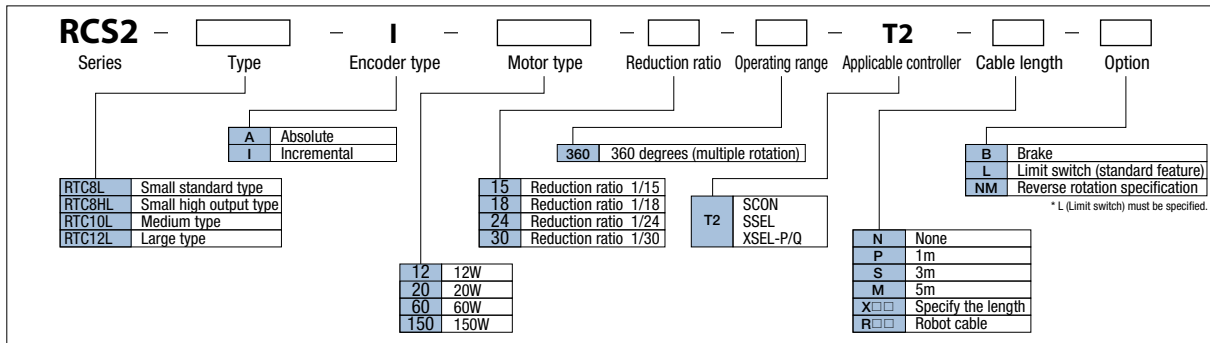
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Rotary type		Type code	Output torque (N·m)	Maximum speed (degree/s)	Allowable load moment (N·m)	Repeated Positioning Accuracy (degree)		
NEW Servo motor specification (RCS2 series)	Large diameter hollow type	Small type	RTC8L	0.55	750	±0.005		
		High, standard output	RTC8HL	0.85	1200			
		Medium type	RTC10L	2.8	1200			
		Large type	RTC12L	8.6	800	25		
	Pulse motor specification (RCP2 series)	Vertical type	Small type	RTBS RTBSL	0.36	400	3.6	±0.05
			Medium type	RTB RTBL	1.7	600	3.9	±0.01
			Large type	RTBB RTBBL	4.6	600	17.7	
		Flat type	Small type	RTCS RTCSL	0.36	400	3.6	±0.05
			Medium type	RTC RTCL	1.7	600	3.9	±0.01
Large type			RTCB RTCBL	4.6	600	17.7		

* Please note that the product cannot be operated when both the output torque and maximum speed values are simultaneously at the settings given in the above table.

Type



Type

Type	Model	Standard price	
Small standard type	Absolute type	RCS2-RTC8L-A-12-24-360-T2	—
	Incremental type	RCS2-RTC8L-I-12-24-360-T2	—
Small high output type	Absolute type	RCS2-RTC8HL-A-20-15(24)-360-T2	—
	Incremental type	RCS2-RTC8HL-I-20-15(24)-360-T2	—
Medium type	Absolute type	RCS2-RTC10L-A-60-15(24)-360-T2	—
	Incremental type	RCS2-RTC10L-I-60-15(24)-360-T2	—
Large type	Absolute type	RCS2-RTC12L-A-150-18(30)-360-T2	—
	Incremental type	RCS2-RTC12L-I-150-18(30)-360-T2	—

* The value in the brackets shows an alternative reduction ratio that can be selected.

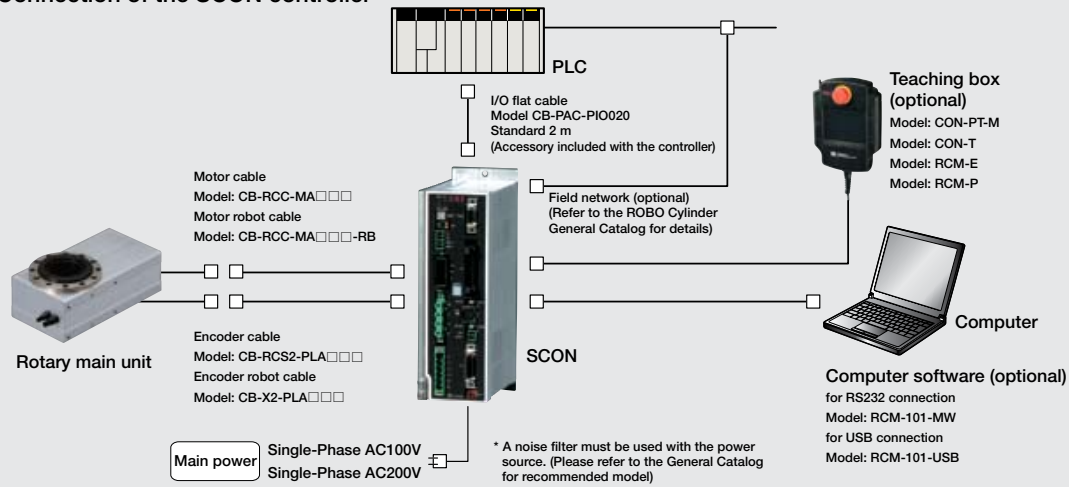
Cable

Name	Cable symbol	Standard price
Standard type	P (1m)	—
	S (3m)	—
	M (5m)	—
Special length	X06(6m)~X10(10m)	—
	X11(11m)~X15(15m)	—
	X16(16m)~X20(20m)	—
Robot cable	R01(1m)~R03(3m)	—
	R04(4m)~R05(5m)	—
	R06(6m)~R10(10m)	—
	R11(11m)~R15(15m)	—
	R16(16m)~R20(20m)	—

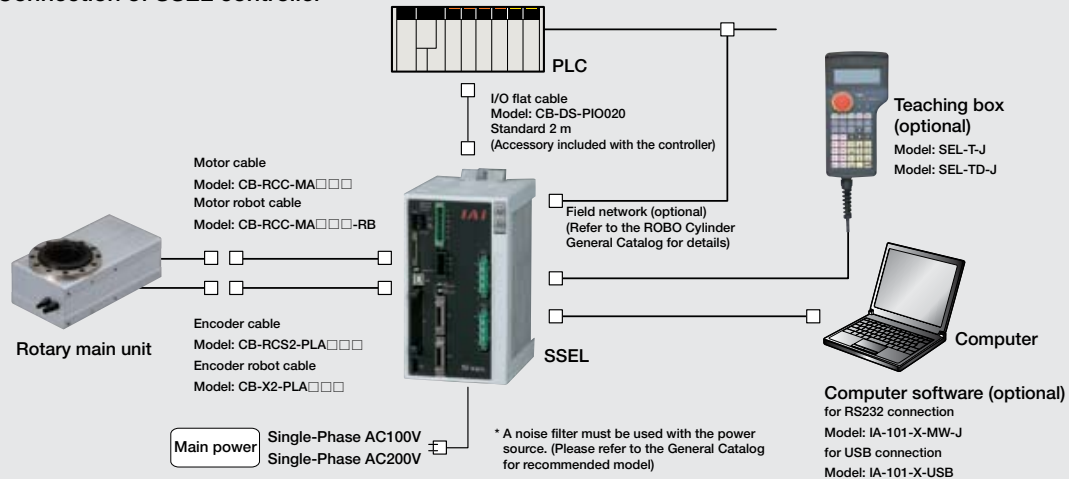
Actuator option

Name	Option code	Standard price
Brake	B	—
Limit switch (standard feature)	L	Free of cost
Reverse rotation specification	NM	Free of cost

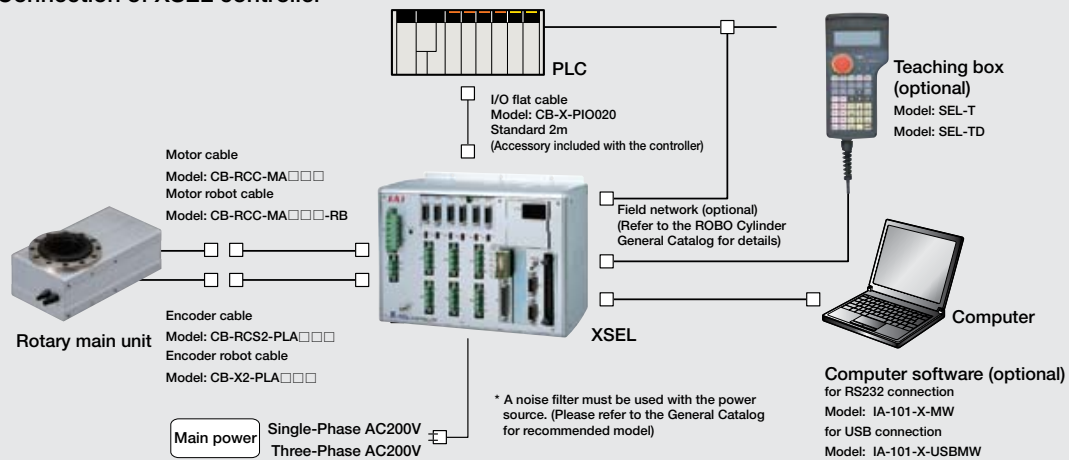
■ Connection of the SCON controller



■ Connection of SSEL controller



■ Connection of XSEL controller



Specification

Name of type		Small standard type	Small high output type		Medium type		Large type	
Model		RTC8L	RTC8HL		RTC10L		RTC12L	
Speed reduction ratio		1/24	1/15	1/24	1/15	1/24	1/18	1/30
Operating range	Degree	±360 (Note 1)						
Motor output	W	12	20		60		150	
Output torque	N·m	0.55	0.53	0.85	1.7	2.8	5.2	8.6
Maximum operation speed	Degree/s	750	1200	750	1200	750	800	600
Positioning repeatability	Degree	±0.005						
Backlash	Degree	±0.05 or lower						
Allowable inertial moment	kg·m ²	0.011	0.01	0.017	0.033	0.054	0.1	0.17
Allowable thrust load	N	400			600		800	
Allowable load moment	N·m	5			10		25	
Home detection method		Optical encoder (Incremental type/Absolute type)						
Origin point detection method		Proximity sensor method						
Brake retention torque	N·m	0.42			0.45		1.0	
Operational environment		Temperature 0 - 40°C, humidity 20 to 85%RH or less (no condensation)						
Inside diameter of hollow shaft	mm	ø30		ø40		ø54		
Outer dimensions of the main body (W×L×H)	mm	85×135×77		85×150×77		99×171×86		123×233×92
Weight of the main body	kg	2.3		2.4		3.5		6.5

(Note 1) Operation range is up to ±9999 degrees.

Applicable Controller

Name	Model	Standard price
Positioner type (Absolute)	SCON-C-□A-NP-2-□	—
Positioner type (Incremental)	SCON-C-□I-NP-2-□	—
Program control, 1 axis type (Absolute)	SSEL-C-1-□A-NP-2-□	—
Program control, 1 axis type (Incremental)	SSEL-C-1-□I-NP-2-□	—
Program control, multi-axis type (Absolute)	XSEL-□-□-□A-N1-EEE-2-□	Contact us
Program control, multi-axis type (Incremental)	XSEL-□-□-□I-N1-EEE-2-□	

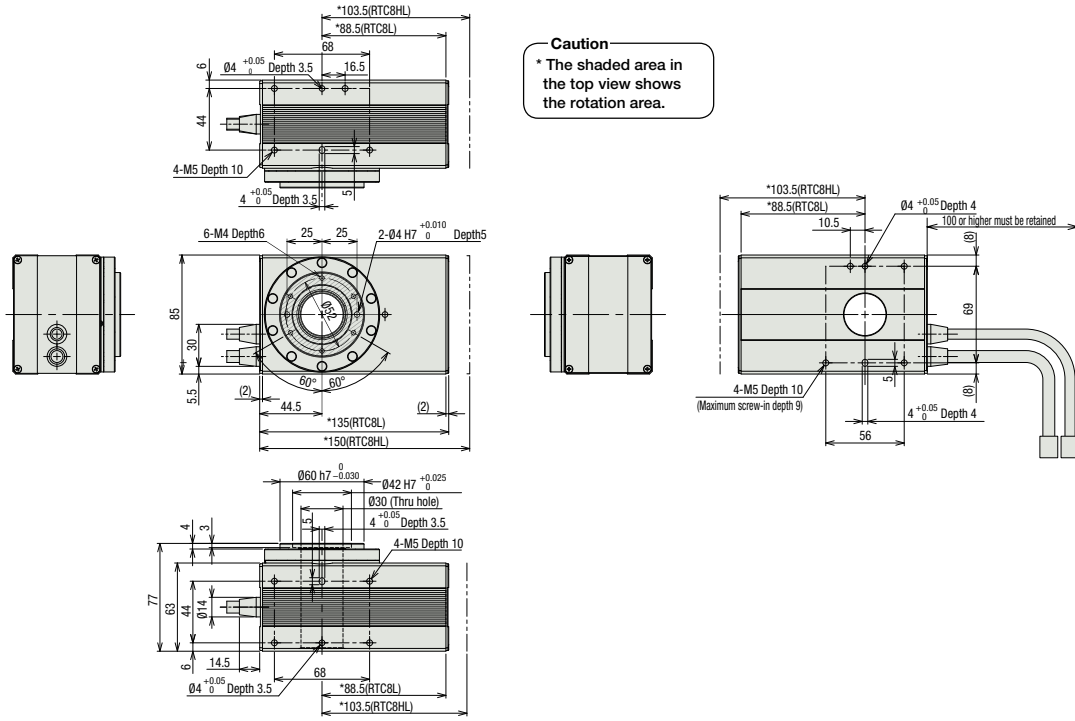
* Controller models vary according to the motor output of the rotary and the model/power-supply voltage of the controller. Please refer to the Controller page in the ROBO Cylinder General Catalog for details.

Options

Supported controllers		Feature	Model	Standard price
For position controller (PCON, ACON, SCON, ROBONET, PSEP, ASEP, ERC2)	Teaching box	Easy operation type provided with a touch panel	CON-PT-M	—
		IP54-compliant standard type	CON-T	—
		Affordable basic type	RCM-E	—
		Solely dedicated to data entry with no movement feature	RCM-P	—
	Computer software	RS232C connection type	RCM-101-MW	—
		USB port connection type	RCM-101-USB	—
For program controller (PSEL,ASEL,SSEL, XSEL)	Teaching box	IP54-compliant standard type (for XSEL controller)	SEL-T	—
		IP54-compliant standard type (for PSEL/ASEL/SSEL controller)	SEL-T-J	—
		3-Position Enable Switch type (for XSEL controller)	SEL-TD	—
		3-Position Enable Switch type (for PSEL/ASEL/SSEL controller)	SEL-TD-J	—
	Computer software	RS232C connection type (for XSEL controller)	IA-101-X-MW	—
		RS232C connection type (for PSEL/ASEL/SSEL controller)	IA-101-X-MW-J	—
		USB port connection type (for PSEL/ASEL/SSEL controller)	IA-101-X-USB	—
		USB port connection type with an emergency stop switch (for XSEL controller)	IA-101-X-USBMW	—

■ Small type

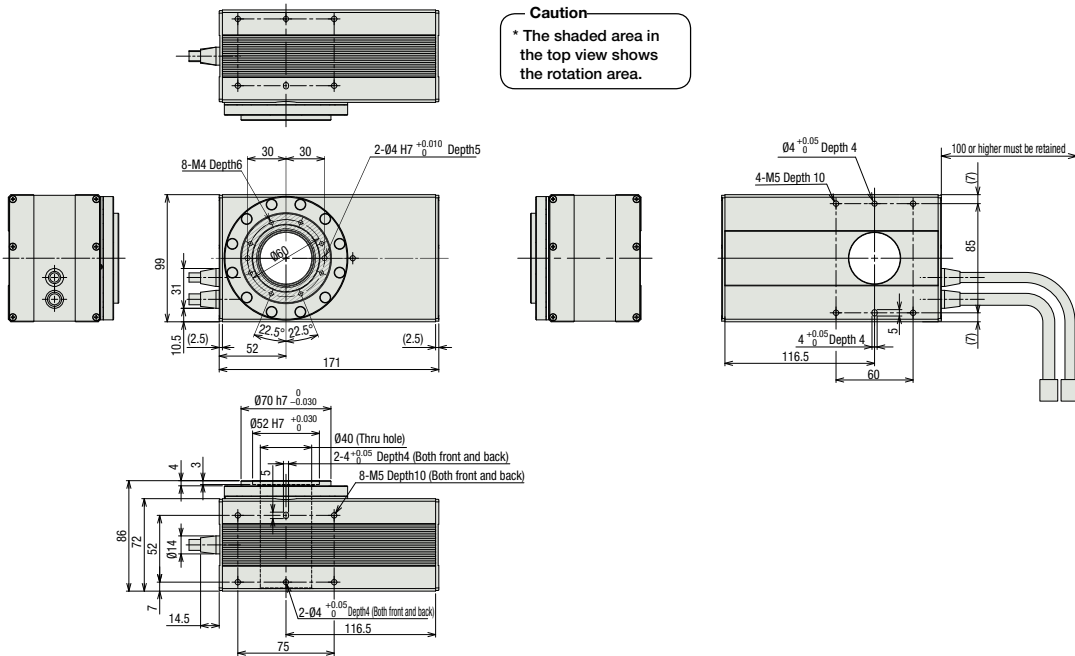
RCS2-RTC8L (Small standard type)
RCS2-RTC8HL (Small high output type)



■ Medium type

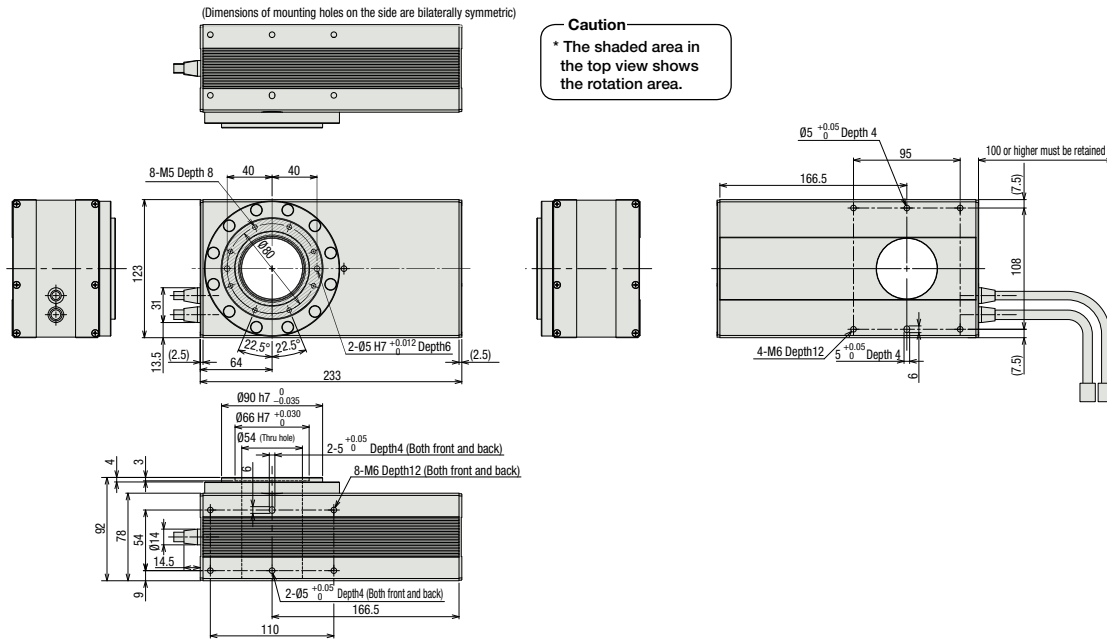
RCS2-RTC10L

(Dimensions of mounting holes on the side are bilaterally symmetric)



Large type

RCS2-RTC12L



Precautions for Use

Carrier Load

Guidelines for Offset Distance
 The more the work part's center of gravity separates from the center of the rotary shaft, the more it vibrates. Design the tool with reference to the following table.

Model	Offset distance (m)
RTC8L	0.10
RTC8HL	0.12
RTC10L	0.15
RTC12L	0.20

Brake

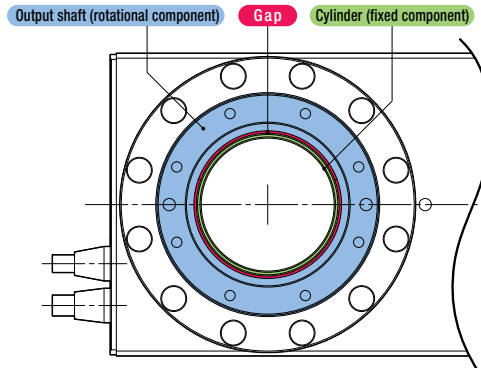
- The brake is provided for retention purposes. It should not be used for braking or emergency stop purposes.
- Use the brake switch on the controller to manually unlock the brake.
 There is no brake unlock switch on the robot side.
- ※ Allowable inertia and allowable brake torque do not function simultaneously. You must check the retention torque.

Please refer to the Specification Sheet for the values and details of the specifications.

- Acceleration**
 - Please set between 0.1 and 0.3G.
- Speed**
 - Maximum speed that the actuator can achieve is shown.
 - It depends on the operational conditions (acceleration, operational range)
- Operational range**
 - Please note that the operational range can vary with the speed reduction ratio.
- Torque**
 - The torque specified on the specification is rated torque. Up to three times the torque may be reached momentarily.
- Allowable load**
 There are three items as shown below.
 Values over the specified load may shorten the product lifetime or cause damage. Loads must be set at the allowable value or lower.
 - Allowable inertial moment
 - Allowable thrust load
 - Allowable load moment

Others

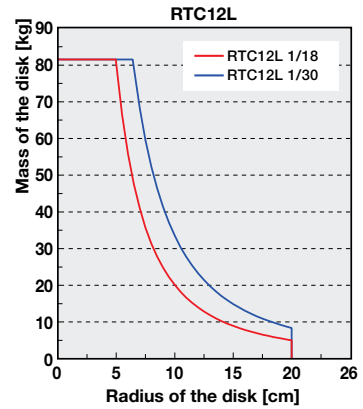
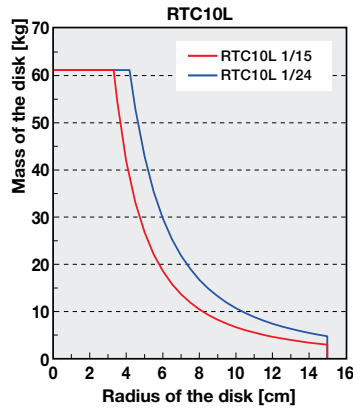
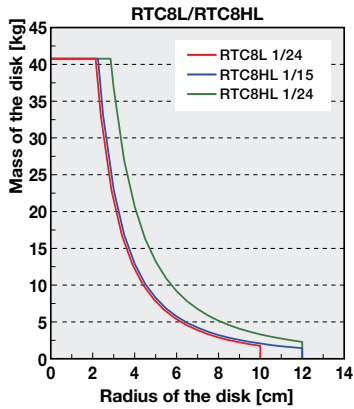
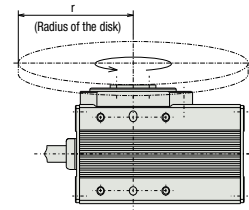
- There is a 1mm gap between the output shaft (rotational component) and the cylinder (fixed component). (See the diagram below)
- Please prevent foreign matter from getting into the unit as this may cause trouble or malfunction.



Guidelines for selecting model: Please refer to the following figures to select the model according to the shape and mass of the objects mounted on the output shaft.

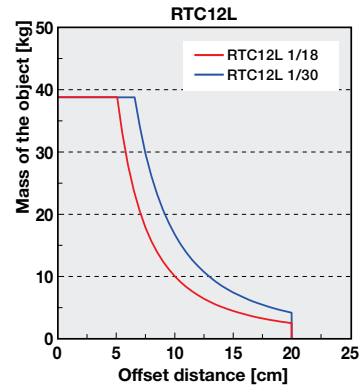
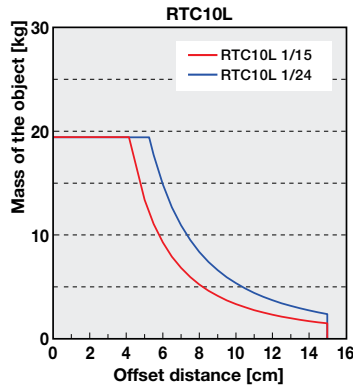
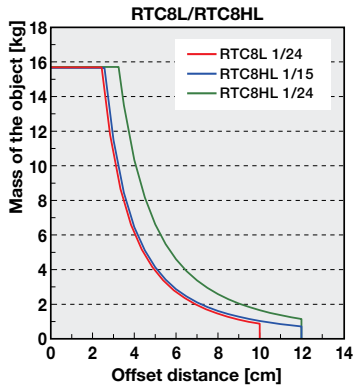
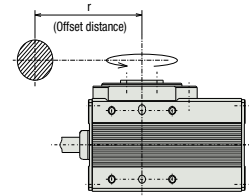
A Disk-shaped object mounted at the center of the output shaft

For disk shaped objects having their center positioned at the center of the rotary's output shaft, please refer to the following graphs to find the model that meets both the mass and radius of the disk.



B Object mounted offset from center of output shaft

For objects offset from the rotary's output shaft, please refer to the following graphs to select the model that meets both the mass and offset distance of the object.



*When using a rotation shaft in the horizontal direction, gravitational loading torque is generated when an object's center of the gravity is located away from the center of rotation. Either decrease the rotational velocity or reduce the mounted weight.