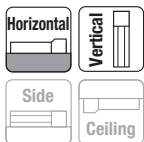


RCS3-RA15R

RoboCylinder, Rod Type with Load Cell, Actuator Width 150mm
200V Servo Motor, Side-mounted Motor Specification

■ Models	RCS3	—	RA15R	—	<input type="checkbox"/>	—	3300	—	<input type="checkbox"/>	—	<input type="checkbox"/>	—	T3	—	<input type="checkbox"/>	—	<input type="checkbox"/>
Specification	Series	—	Type	Encoder type	Motor Type	Lead	Stroke	Applicable Controller	Cable length	Option							
Items				I: Incremental specification A: Absolute specification	3300: Servo motor, 3300 W	3.6: Lead 3.6mm	100: 100mm 500: 500mm (The increment of stroke is 100mm)	T3: SCON-CGB (Servo press specification)	N: No cable P: 1m S: 3m M: 5m X□□: Specified length		Please refer to the options table below. * Please make sure to select an option code for the motor side-mounted direction (MT).						

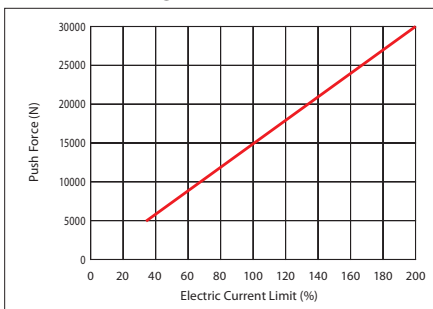
*Controller is not included.



* Depending on the model, there may be some limitations to using the vertical mount position.



Correlation Diagram of Push Force and Current Limit



Caution:

- The correlation between push force and current limit value are strictly for reference purposes. Actual numbers may vary slightly.
- The current limit value should be 20% or more because the push force would be unstable when the current limit value is lower than 20%.

- POINT**
Note on selection
- For push mode operation, please see P. 22 to check the allowable time period of a continuous push-motion with a different thrust force. Also, please check that the allowable continuous operational thrust force (please see P. 23) for the actual push cycle is less than the allowable continuous operational thrust force. (Even if there is no push motion)
 - Customer's tooling is to be mounted on the load cell itself. In case any radial or moment load is applied to the load cell, please consider adding the external guides, etc. to offset those side loads.
 - Please install a support block for the horizontal installation. It is recommended since vibration might occur depending on the operational and installation condition and damage the actuator.
 - Force control is only for pushing motion, not valid for pulling motion.

Actuator Specifications

Lead and Payload

Model number	Motor (W)	Lead (mm)	Max. speed (mm/s)	Max. acceleration (G)	Max. payload		Rated thrust (N)	Max. push force (N) *
					Horizontal (kg)	Vertical (kg)		
RCS3-RA15R-①-3300-3.6-②-T3-③-④	3300	3.6	240	0.1	15	15	15577	30000

Legend: ① Encoder type ② Stroke ③ Cable length ④ Option

Stroke and Maximum Speed

Lead (mm)	Stroke (mm)	100~500

* With 0.01-10mm/s

(Unit: mm/s)

Cable Length

Type	Cable code
Standard type (Robot cable)	P (1m)
	S (3m)
	M (5m)
Special length	X06 (6m) ~X10 (10m)
	X11 (11m)~X15 (15m)
	X16 (16m)~X20 (20m)

* Refer to P. 37 for maintenance cables.
* The standard cable is the robot cable.

Options

Name	Option code	Reference page
Brake	B	Refer to the RoboCylinder General Catalog.
Cable exit direction (Top)	CJT	
Cable exit direction (Right side)	CJR	
Cable exit direction (Left side)	CJL	
Motor side-mounted to the top	MT	
Equipped with load cell (Standard equipment) (*1)	LCT	-

(*1) Please make sure to enter "LCT" in the box of Model Specification Items to select the actuator with load cell.

Actuator Specifications

Item	Description
Drive system	Ball screw Ø36mm, rolled C10
Positioning repeatability	±0.01mm
Rod non-rotation precision	±0 deg.
Lost motion	0.2mm or less
Load cell rated capacity	50000N
Load cell system accuracy	±1% R.C (*2)
Loading repeatability (*1)	±0.5% F.S (*3)
Load cell service life	2 million times
Ambient operating temperature and humidity	0°C~40°C

(*1) Ratio (in percentage) of the load variations caused by the repeated operations to the load cell rated capacity. The ratio is calculated based on actual data at IAI.

(*2) R.C: Rated Capacity

(*3) F.S: Full Scale

