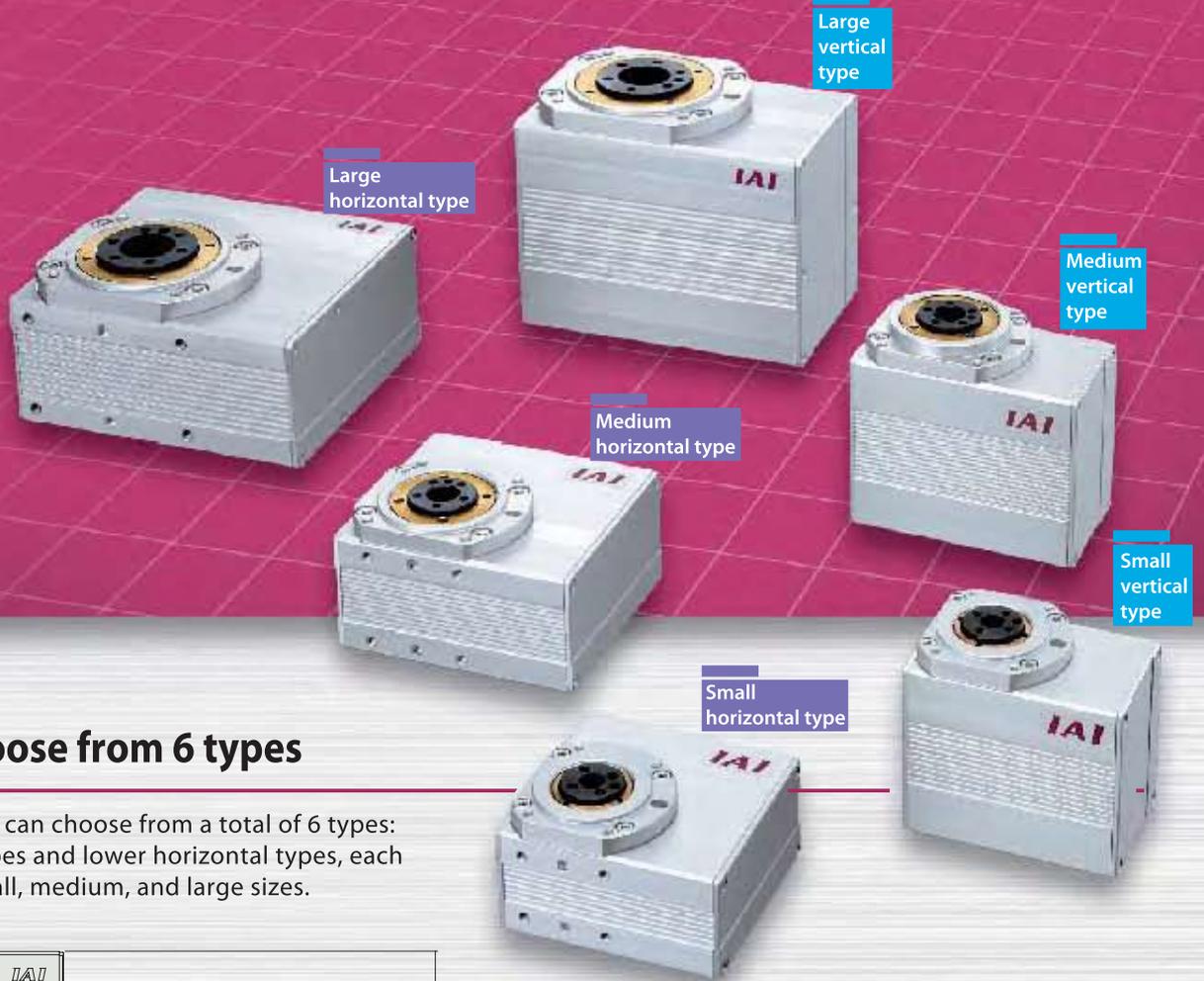


# Rotary-Type Robo Cylinder **RCP2-RT**

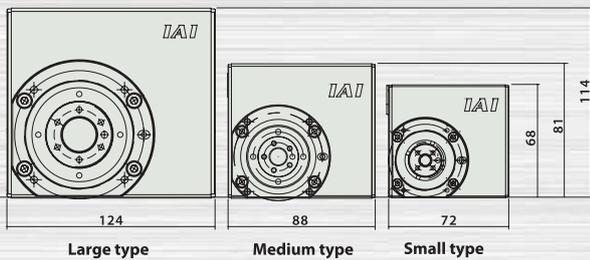


# Now with the addition of the small and large types, our line-up is even stronger



## 1 Choose from 6 types

Now customers can choose from a total of 6 types: slim vertical types and lower horizontal types, each available in small, medium, and large sizes.



## 4 High-precision positioning

The output axis of the horizontal type has a hollow structure, so wires from devices installed along the output axis can be passed through it.

(\*2) The small model is  $\pm 0.05$  degrees.

## 2 Hollow structure

The output axis of the horizontal type has a hollow structure, so wires from devices installed along the output axis can be passed through it.



## 5 Can use up to 1500 positions

If a PSEL controller is used, up to 1500 positions can be used. (\*3)

Customers can choose from the following controller types: positioner, serial communication, pulse line, electromagnetic valve, and program types.

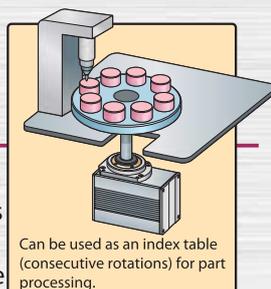
(\*3) Please note that the maximum number of positions varies depending on the controller

## 3 Multiple rotation specifications

All models have multiple rotation specifications that allow rotations exceeding 360 degrees.

They can be operated in the same rotational direction, like a conveyor (\*1).

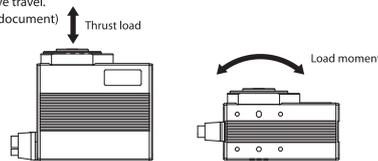
(\*1) One rotation is within  $\pm 360$  degrees.



## Specifications

Type	Small				Medium				Large					
Shape	Vertical		Horizontal		Vertical		Horizontal		Vertical		Horizontal			
Type	RTBS (standard specifications) RTBSL (multiple rotation specifications)		RTCS (standard specifications) RTCSL (multiple rotation specifications)		RTB (standard specifications) RTBL (multiple rotation specifications)		RTC (standard specifications) RTCL (multiple rotation specifications)		RTBB (standard specifications) RTBBL (multiple rotation specifications)		RTCB (standard specifications) RTCBL (multiple rotation specifications)			
Speed reduction ratio	1/30	1/45	1/30	1/45	1/20	1/30	1/20	1/30	1/20	1/30	1/20	1/30		
Operating range	Degrees Standard specifications: 330 degrees. Multiple rotation specifications: ±9999 degrees (*1)													
Reverse rotation specifications	Standard specifications: none. Multiple rotation specifications: yes													
Max. torque (*2)	N·m		0.24	0.36	0.24	0.36	1.1	1.7	1.1	1.7	3	4.6	3	4.6
Max. operating speed (*3)	Degrees/sec		400	266	400	266	600	400	600	400	600	400	600	400
Repeat stop precision (*4)	Degrees		±0.05				±0.01				±0.01			
Backlash	Degrees		±0.1				±0.1				±0.1			
Allowable thrust load (*5)	N		30				50				200			
Allowable load moment (*5)	N·m		3.6				3.9				17.7			
Detection method	Electromagnetic encoder (incremental)													
Origin point detection method	Standard specifications: mechanical stopper method. Multiple rotation specifications: proximity sensor method													
Precision to restore to the original point	Degrees		Standard specifications: Within ±0.05 Multiple rotation specifications: Within ±0.05				Standard specifications: Within ±0.01 Multiple rotation specifications: Within ±0.05				Standard specifications: Within ±0.01 Multiple rotation specifications: Within ±0.03			
Usage environment	Temperature: 0-40°C, Humidity: 20-85% RH or less (no condensation)													
Outer dimensions of main unit (thickness x width x height)	mm		45×72×70		68×72×45		50×88×83.5		81×88×55		76×124×107		114×124×68	
Mass of main unit	kg		0.52		0.48		0.86		0.92		2.3		2.2	
Motor cable type	CB-PCS-MPA□□□□ (Cable with motor and encoder in one)						CB-RCP2-MA□□□□ * The standard motor cable is a robot cable. CB-RCP2-PB□□□□ (CB-RCP2-PB-RB) (*1)							

- (\*1) Multiple rotation specifications: in normal mode, it is possible to move up to ±9999 degrees of consecutive travel.  
 (\*2) Maximum torque changes depending on the speed. (See the front and back sides of the model selection document)  
 (\*3) The maximum speed changes depending on the load.  
 (\*4) Shows the repeat positioning precision from one direction.  
 (\*5) If loads exceeding these values are used, it may cause damage or shorten the lifespan of the unit.  
 (See the diagram on the right for the direction of force)  
 (\*6) Robot cable types are inside ( ).



## Type criteria

□ Type categories

Series	Type	Encoder type	Motor type	Speed reduction ratio	Vibration angle	Applicable controller	Cable length	Options
<b>RCP2</b>	RTBS : Small vertical standard RTBSL : Small vertical multiple rotation RTCS : Small horizontal standard RTCSL : Small horizontal multiple rotation RTB : Medium vertical standard RTBL : Medium vertical multiple rotation RTC : Medium horizontal standard RTCL : Medium horizontal multiple rotation RTBB : Large vertical standard RTBBL : Large vertical multiple rotation RTCB : Large horizontal standard RTCBL : Large horizontal multiple rotation	Incremental	20P: Pulse motor 20 size 28P: Pulse motor 28 size 35P: Pulse motor 35 size	20: Speed reduction ratio 1/20 30: Speed reduction ratio 1/30 45: Speed reduction ratio 1/45	330: 330 degrees 360: 360 degrees (Multiple rotation)	P1: PCON PSEL	N: None P: 1 m S: 3 m M: 5 m	SA: Shaft adapter TA: Table adapter

## Type

Type	Type	Type	
Small	Vertical	Standard specifications	RCP2-RTBS-I-20P-30(45)-330-P1
		Multiple rotation specifications	RCP2-RTBSL-I-20P-30(45)-360-P1
	Horizontal	Standard specifications	RCP2-RTCS-I-20P-30(45)-330-P1
		Multiple rotation specifications	RCP2-RTCSL-I-20P-30(45)-360-P1
Medium	Vertical	Standard specifications	RCP2-RTB-I-28P-20(30)-330-P1
		Multiple rotation specifications	RCP2-RTBL-I-28P-20(30)-360-P1
	Horizontal	Standard specifications	RCP2-RTC-I-28P-20(30)-330-P1
		Multiple rotation specifications	RCP2-RTCL-I-28P-20(30)-360-P1
Large	Vertical	Standard specifications	RCP2-RTBB-I-35P-20(30)-330-P1
		Multiple rotation specifications	RCP2-RTBBL-I-35P-20(30)-360-P1
	Horizontal	Standard specifications	RCP2-RTCB-I-35P-20(30)-330-P1
		Multiple rotation specifications	RCP2-RTCBL-I-35P-20(30)-360-P1

## Cable Length

Type	Type
Standard type	P (1m)
	S (3m)
	M (5m)
Special lengths	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)

## Options

Name	Option Symbol
Reverse rotation specifications	NM
Shaft adapter	SA
Table adapter	TA

\*Option pricing is the same for small, medium, and large types.

## Applicable Controller

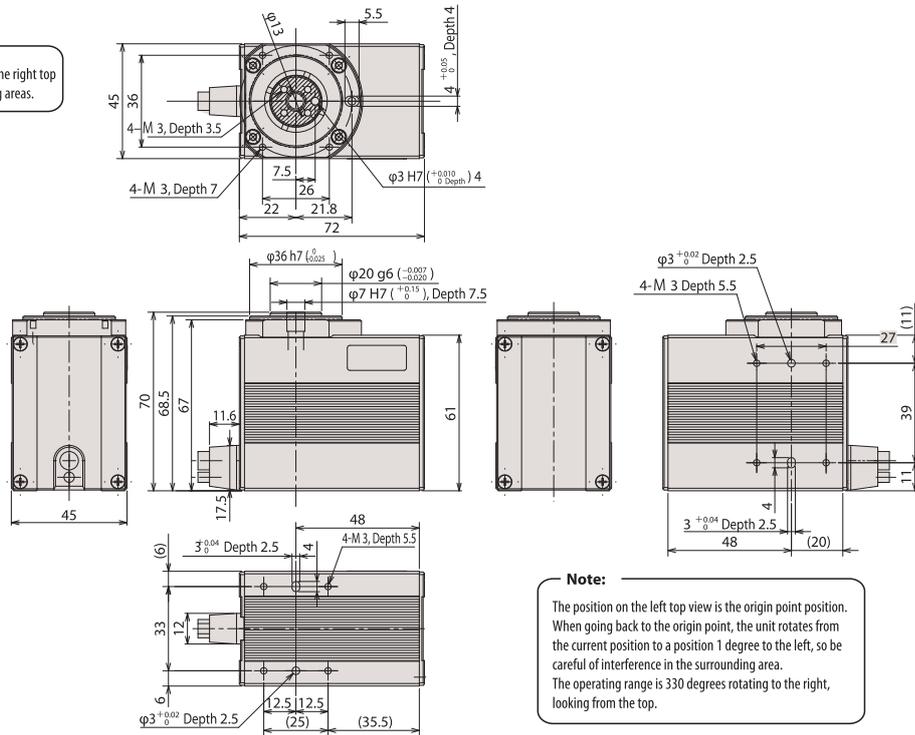
Name	Type
Positioner type	PCON-C-□I-NP-2-0
Safety category compatible type	PCON-CG-□I-NP-2-0
Electromagnetic valve type	PCON-CY-□I-NP-2-0
Pulse line type (differential)	PCON-PL-□I-NP-2-0
Pulse line type (open collector)	PCON-PO-□I-NP-2-0
Serial type	PCON-SE-□I-N-0-0
Field network type	RPCON-□
Program control type	PSEL-C-1-□I-NP-2-0

\* The □ in the above model designations denote numbers representing the motor of the main rotary unit.  
 Example: When operating a large type: PCON-C-35PI-NP-2-0

# Small vertical type



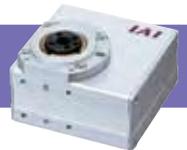
**Note:**  
\* The diagonal lines on the right top view show the rotating areas.



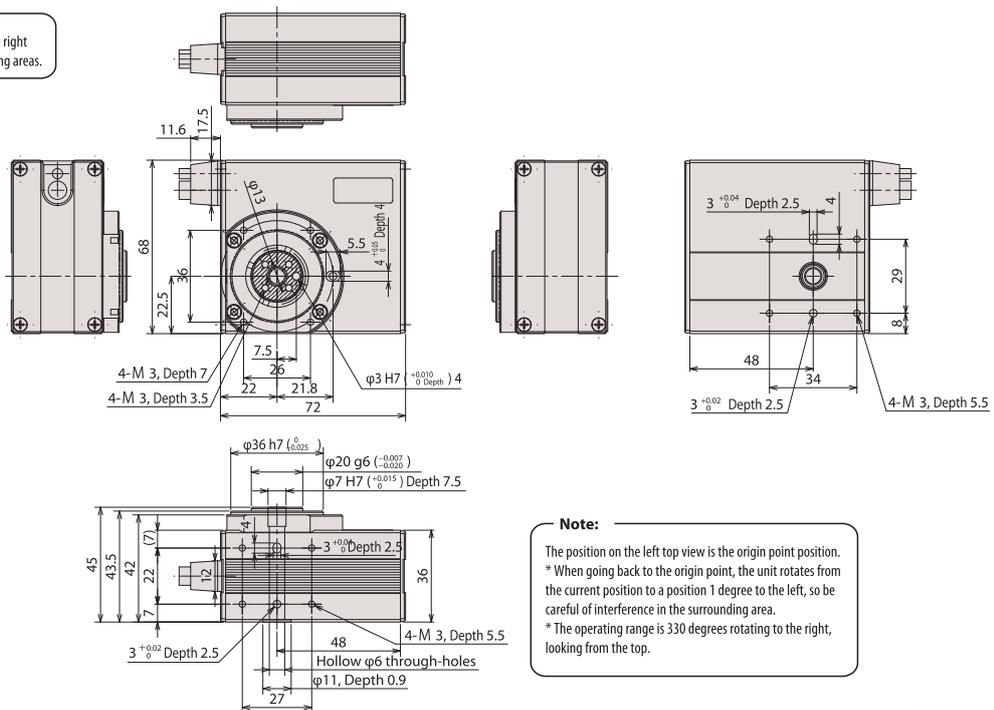
**Note:**  
The position on the left top view is the origin point position. When going back to the origin point, the unit rotates from the current position to a position 1 degree to the left, so be careful of interference in the surrounding area. The operating range is 330 degrees rotating to the right, looking from the top.

Mass (kg)	0.52
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# Small horizontal type



**Note:**  
The diagonal lines on the right top view show the rotating areas.



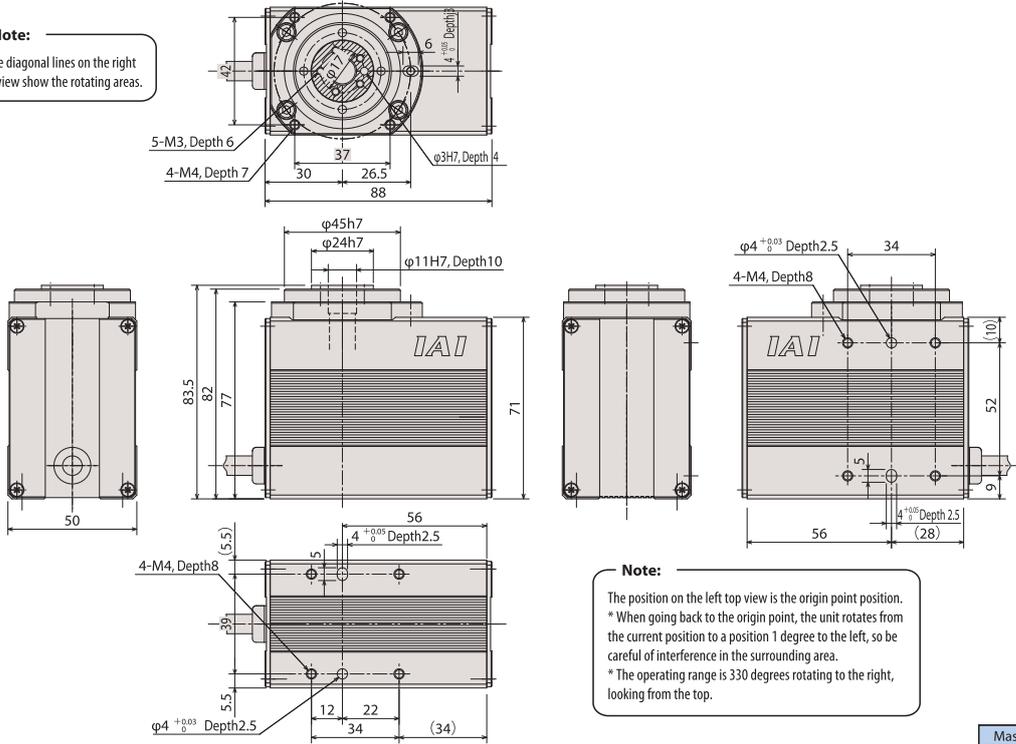
**Note:**  
The position on the left top view is the origin point position. \* When going back to the origin point, the unit rotates from the current position to a position 1 degree to the left, so be careful of interference in the surrounding area. \* The operating range is 330 degrees rotating to the right, looking from the top.

Mass (kg)	0.48
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# Medium vertical type



**Note:**  
\* The diagonal lines on the right top view show the rotating areas.



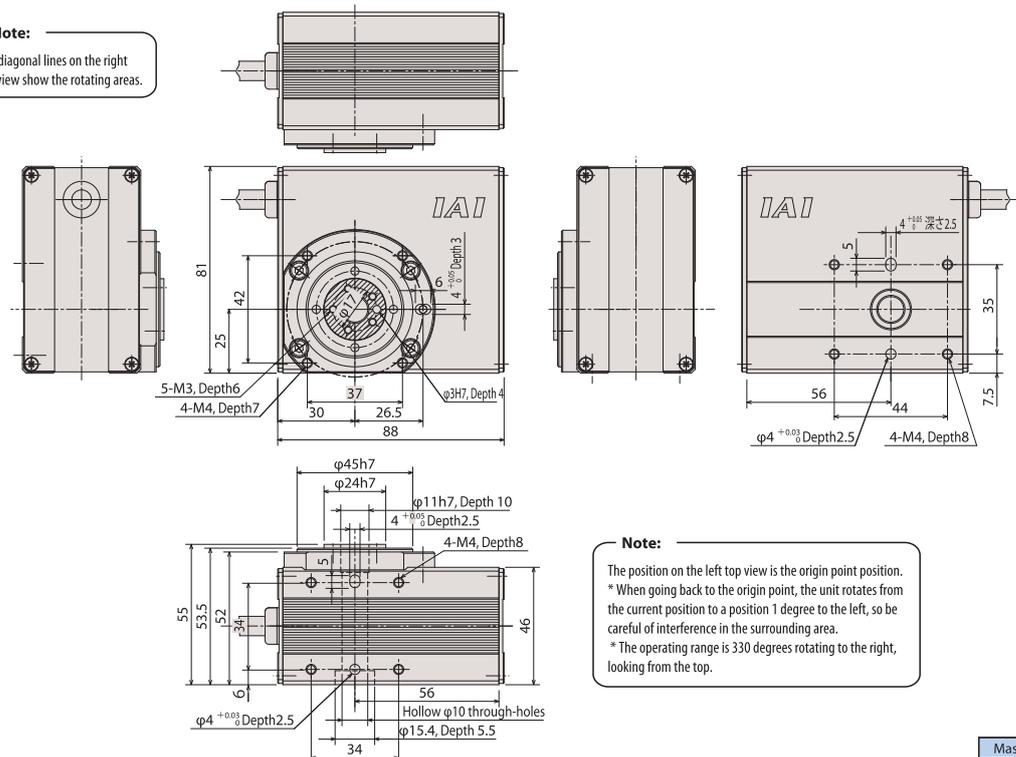
**Note:**  
The position on the left top view is the origin point position.  
\* When going back to the origin point, the unit rotates from the current position to a position 1 degree to the left, so be careful of interference in the surrounding area.  
\* The operating range is 330 degrees rotating to the right, looking from the top.

Mass (kg)	0.86
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# Medium horizontal type



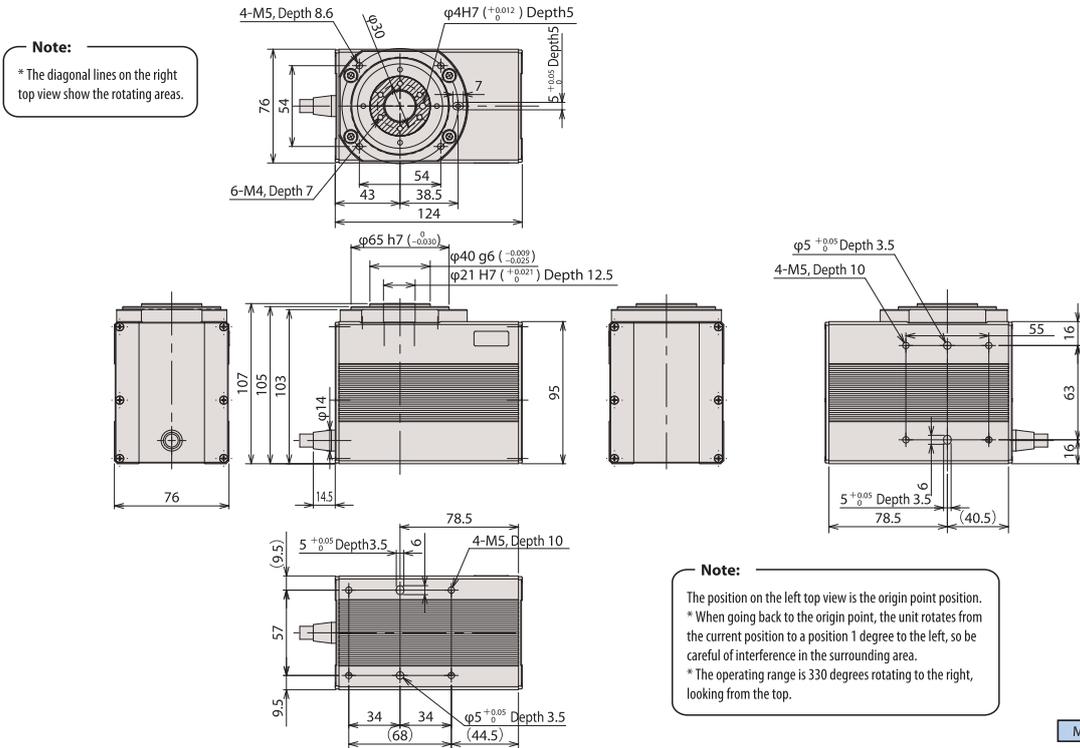
**Note:**  
The diagonal lines on the right top view show the rotating areas.



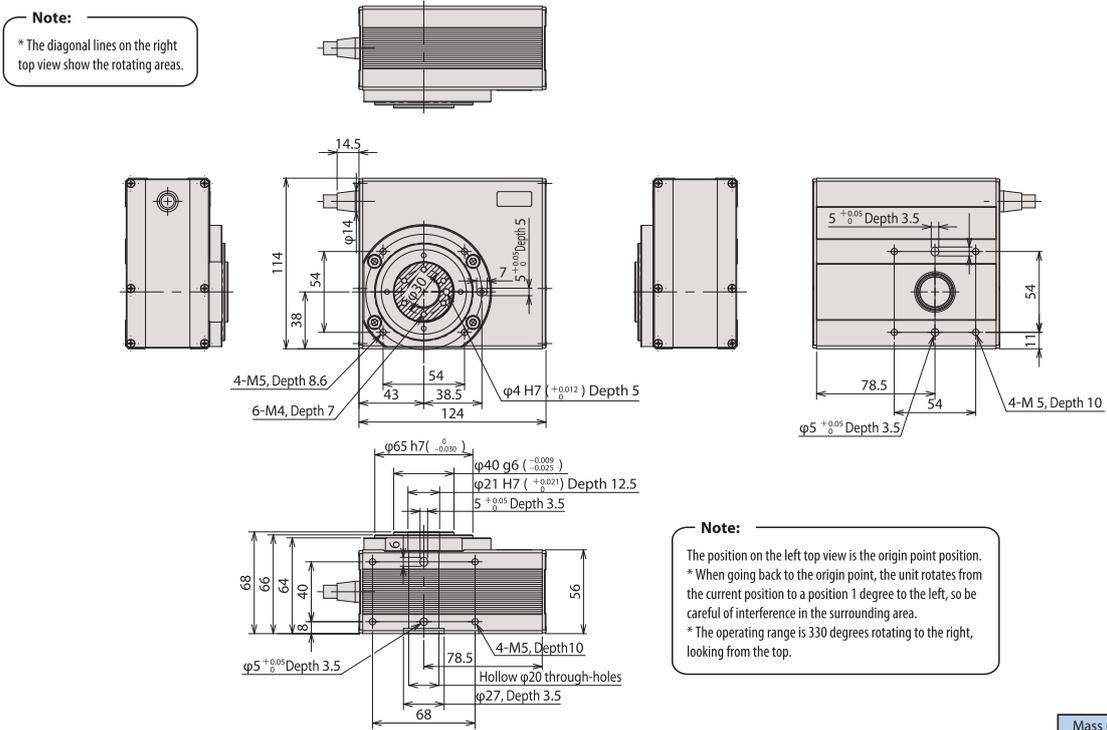
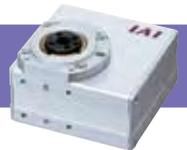
**Note:**  
The position on the left top view is the origin point position.  
\* When going back to the origin point, the unit rotates from the current position to a position 1 degree to the left, so be careful of interference in the surrounding area.  
\* The operating range is 330 degrees rotating to the right, looking from the top.

Mass (kg)	0.92
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# Large vertical type



# Large horizontal type

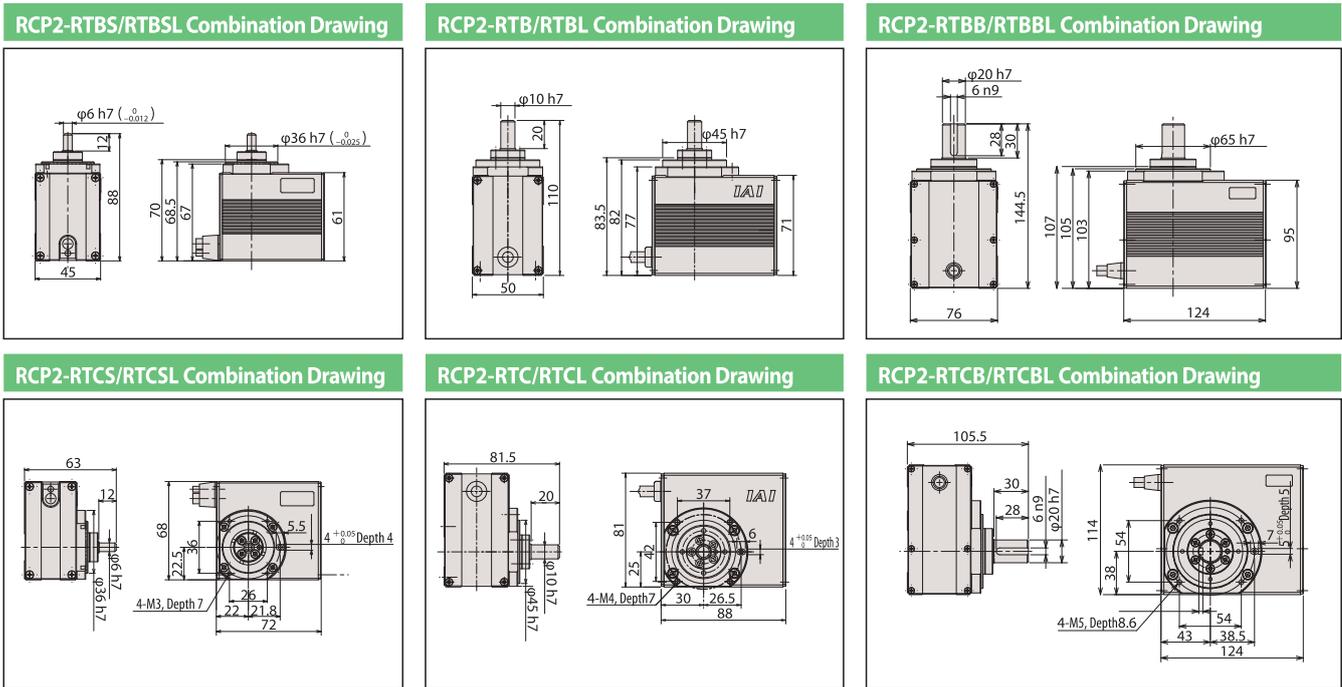


# Options

## Shaft adapter

### □ Model SA

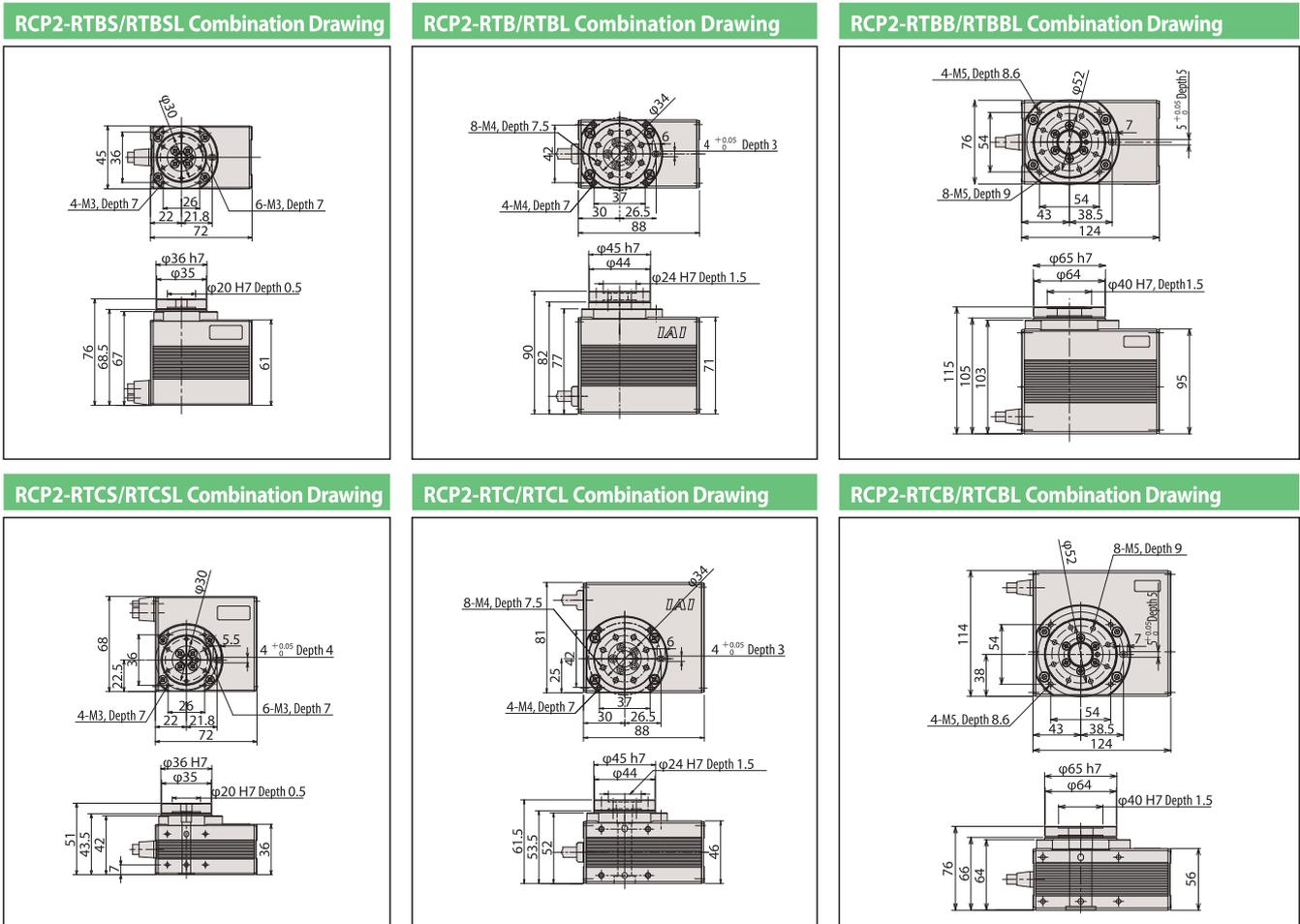
This is a shaft-shaped adapter for attaching jigs, etc. to the rotating areas of the rotary type unit.



## Table adapter

### □ Model TA

This is a table-shaped adapter for attaching jigs, etc. to the rotating areas of the rotary-type unit.



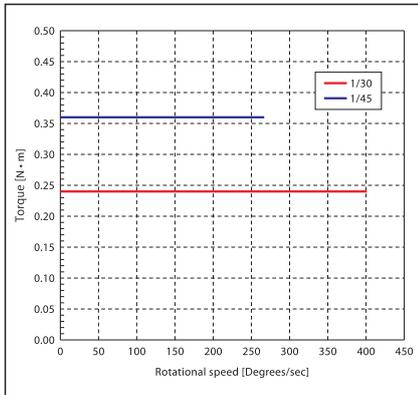
# Selection goals

## Output torque

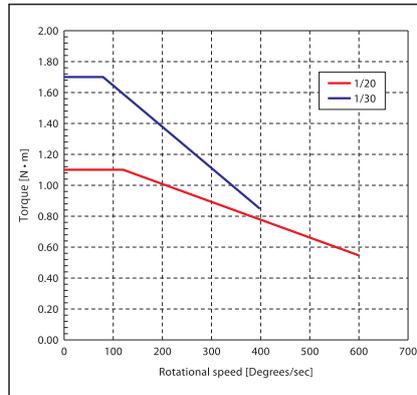
Output torque decreases as rotational speed increases.

\* Please use the bottom graph to verify whether you can get enough necessary speed torque for operation.

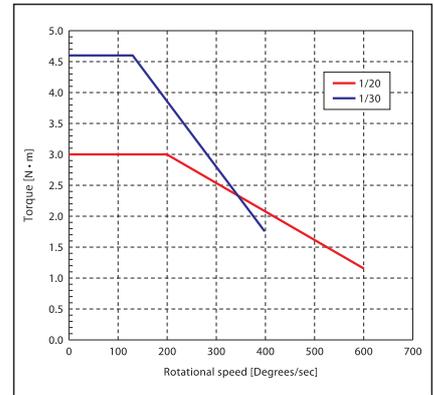
Small vertical type RTBS/RTBSL  
Small horizontal type RTC/RTCCL



Medium vertical type RTB/RTBL  
Medium horizontal type RTC/RTCCL



Large vertical type RTBB/RTBBL  
Large horizontal type RTCB/RTCBL

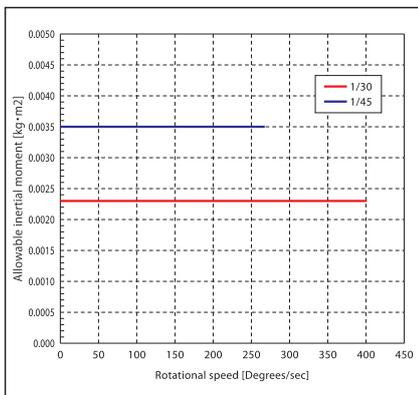


## Allowable inertial moment

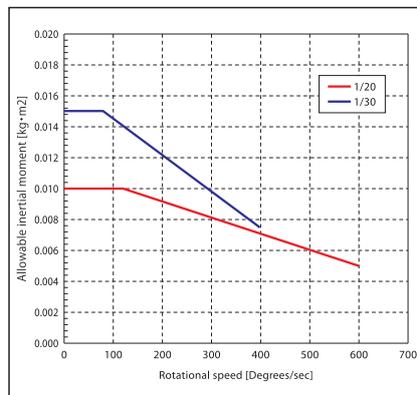
The allowable inertial moment for workpieces that can be rotated differs based on the rotational speed.

\* Please verify the operating conditions and inertial moment of workpieces that can be rotated.

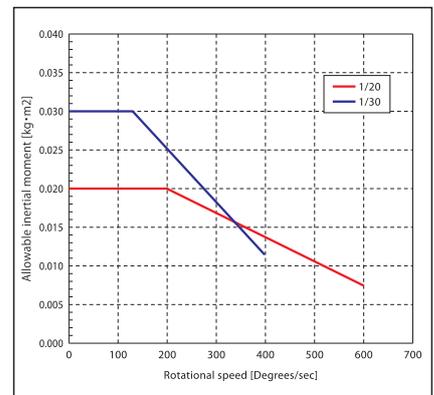
Small vertical type RTBS/RTBSL  
Small horizontal type RTC/RTCCL



Medium vertical type RTB/RTBL  
Medium horizontal type RTC/RTCCL



Large vertical type RTBB/RTBBL  
Large horizontal type RTCB/RTCBL



## Inertial moment

Inertial moment expresses the amount of inertia in the rotational motion, and is equivalent to the mass for linear motion.

The larger the inertial moment, the more difficult it is for that object to move and stop.

That is, when choosing a rotary-type unit, whether or not the inertial moment (of the object that can be rotated) can be controlled or not is a decision-making factor.

\* This type can be used if the inertial moment found in the calculation is smaller than the allowable inertial moment of the rotary type.

### • Calculation method for inertial moment for main shapes

J: Inertial moment (kg · m<sup>2</sup>)/M: Mass (kg)/r: Radius (m)/a.

(1) Cylinder (includes thin disc)  
Position of axis of rotation: center axis

$$J = M \cdot \frac{r^2}{2}$$

(3) Thin rectangular plate (rectangular solid)  
Position of axis of rotation: Pass one end perpendicular to the plate.  
M1: Mass (kg) on a1 side  
M2: Mass (kg) on a2 side

$$J = M_1 \cdot \frac{4a^2 + b^2}{12} + M_2 \cdot \frac{4a^2 + b^2}{12}$$

(2) Thin rectangular plate (rectangular solid)  
Position of axis of rotation: Pass one end perpendicular to the plate.  
(Same, if using a rectangular solid with a thick plate)

$$J = M \cdot \frac{a^2 + b^2}{12}$$