

D-GN□, R88D-GT□

G-Series servo drive

Compact servo drive family for motion control. Compact size and integrated MECHATROLINK-II motion bus.

- Analog/ Pulse servo drive models
- Response frequency of 1 kHz
- Tuning for easy and quick start-up
- Vibration suppression
- Positioning, speed or torque control
- Separate power and control power supply
- High speed and accurate positioning
- Incremental and absolute encoder

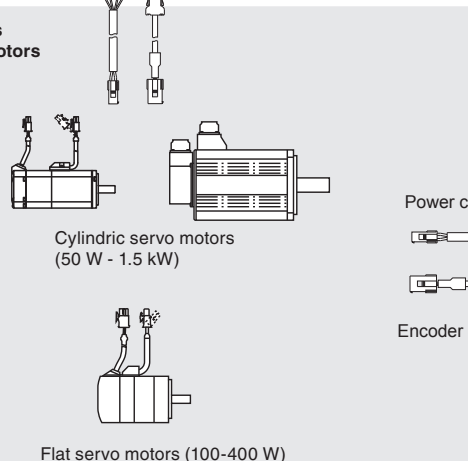
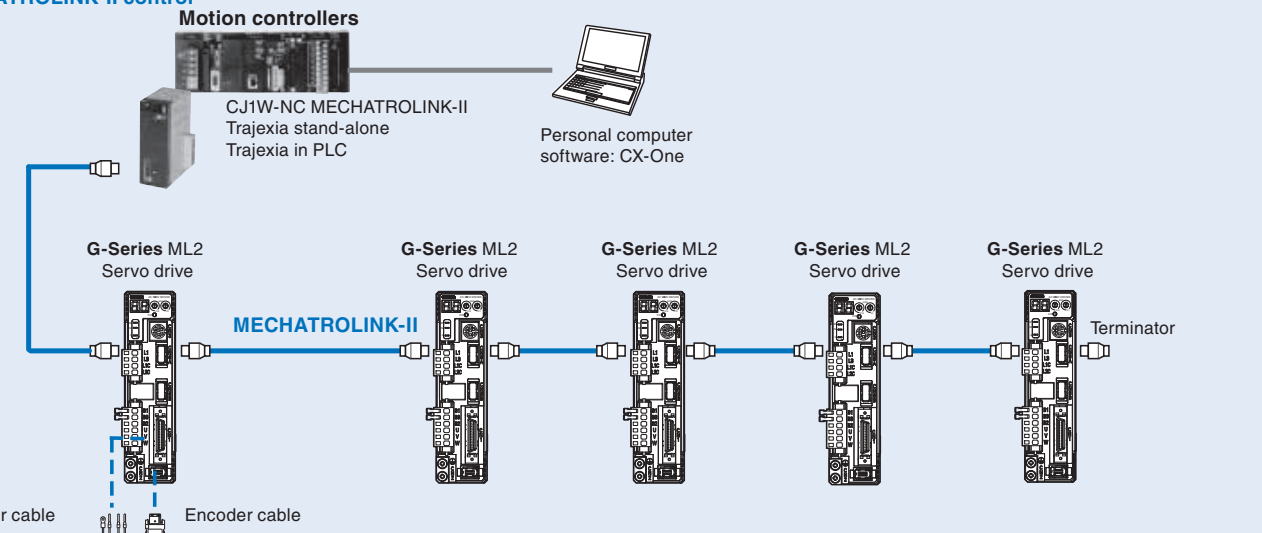
AC Single-phase 100 W to 1.5 kW (8.62 Nm)



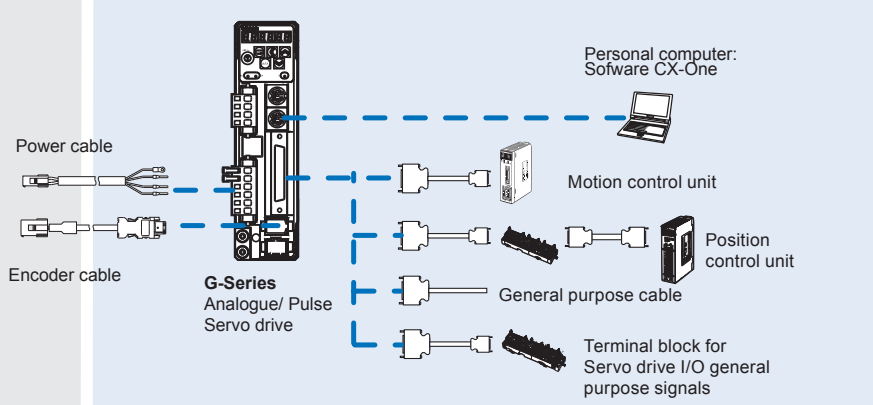
AC Servo systems

System configuration

MECHATROLINK-II control



Open Analogue/Pulse control



Motor supported

	Servo motor						G-Series servo drive	
	Voltage	Speed	Rated torque	Capacity	Model	MECHATROLINK-II	Analog/ Pulse	
750 W	230 V	3000 min ⁻¹	0.16 Nm	50 W	R88M-G05030□-□S2	R88D-GN01H-ML2	R88D-GT01H	
			0.32 Nm	100 W	R88M-G10030□-□S2	R88D-GN01H-ML2	R88D-GT01H	
			0.64 Nm	200 W	R88M-G20030□-□S2	R88D-GN02H-ML2	R88D-GT02H	
			1.3 Nm	400 W	R88M-G40030□-□S2	R88D-GN04H-ML2	R88D-GT04H	
			2.4 Nm	750 W	R88M-G75030□-□S2	R88D-GN08H-ML2	R88D-GT08H	
			3.18 Nm	1000 W	R88M-G1K030T-□S2	R88D-GN15H-ML2	R88D-GT15H	
1500 W		2000 min ⁻¹	3000 min ⁻¹	4.77 Nm	1500 W	R88M-G1K530T-□S2	R88D-GN15H-ML2	R88D-GT15H
				4.8 Nm	1000 W	R88M-G1K020T-□S2	R88D-GN10H-ML2	R88D-GT10H
			7.15 Nm	1500 W	R88M-G1K520T-□S2	R88D-GN15H-ML2	R88D-GT15H	
			8.62 Nm	900 W	R88M-G90010T-□S2	R88D-GN15H-ML2	R88D-GT15H	
400 W	3000 min ⁻¹	3000 min ⁻¹	0.32 Nm	100 W	R88M-GP10030□-□S2	R88D-GN01H-ML2	R88D-GT01H	
			0.64 Nm	200 W	R88M-GP20030□-□S2	R88D-GN02H-ML2	R88D-GT02H	
			1.3 Nm	400 W	R88M-GP40030□-□S2	R88D-GN04H-ML2	R88D-GT04H	

Designation

R88D-GN04H-ML2

G-Series servo drive

Drive type

T: Analogue/ pulse type

N: Network type

Capacity

Model

Blank: Analogue/ pulse type

ML2: MECHATROLINK-II communications

Source voltage

H: 230 V

01	100 W
02	200 W
04	400 W
08	750 W
10	1.0 kW
15	1.5 kW

Drive specifications

Specifications

Model	R88D-G□	01H□	02H□	04H□	08H□	10H□	15H□
	R88M-G□	05030□/10030□	20030□	40030□	75030□	G1K020T□	90010T□ / 1K030T□ / 1K5□0T□
	R88M-GP□	10030□	20030□	40030□	-	-	-
Available motor capacity	W	100	200	400	750	1000	1500
Output current	Arms	1.16	1.6	2.7	4.0	5.9	9.8
Current	Arms	3.5	5.3	7.1	14.1	21.2	28.3
Main circuit	For single-phase, 200 to 240 VAC +10 to -15% (50/60 Hz)			For single-phase/ three-phase, 200 to 240 VAC +10 to -15% (50/60 Hz)			
Control circuit	For single-phase, 200 to 240 VAC + 10 to -15% (50/60 Hz)						
Method	IGBT-driven PWM method						
	Serial encoder (incremental/absolute)						
Storage temperature	0 to +55 °C / -20 to 65 °C						
Storage humidity	90% RH or less (non-condensing)						
	1000m or less above sea level						
Shock resistance	5.88 m/s ² / 19.6 m/s ²						
Mounting	Base mounted						
Weight	Kg	0.8	1.1	1.5	1.7		

MECHATROLINK-II servo drive specifications

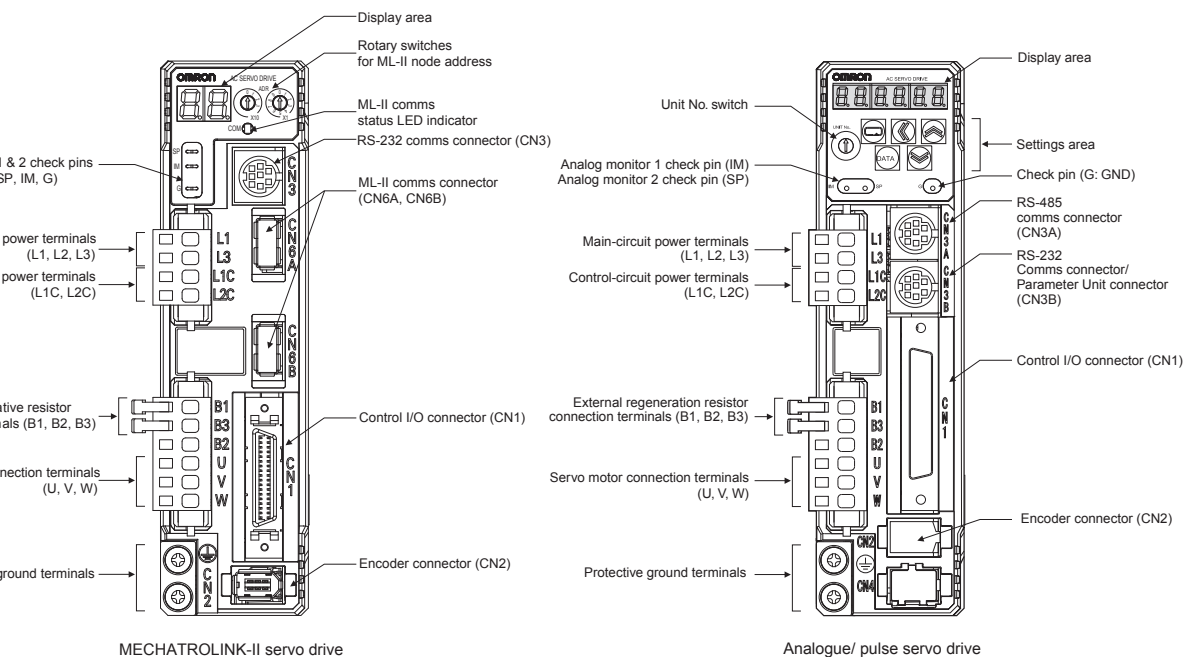
Speed variance	Load variance	During 0 to 100% load ± 0.01 max. (at rated speed)
	Voltage variance	0% at $\pm 10\%$ of rated voltage (at rated speed)
	Temperature variance	0 to 50°C $\pm 0.1\%$ max. (at rated speed)
Frequency characteristics		1 kHz
Torque control accuracy (reproducibility)		$\pm 3\%$ (at 20% to 100% of rated torque)
Start time setting		0 to 10 s (acceleration time and deceleration time can be set)
MECHATROLINK communication		MECHATROLINK-II commands (for sequence, motion, data setting/reference, monitor, adjustment and other commands)
Emergency input signal		Emergency stop, 3 external latch signals, forward/reverse torque limit, forward/reverse run prohibit, origin proximity, 3 general-purpose inputs
Emergency output signal		It is possible to output three types of signals: positioning completed, speed coincidence, rotation speed detection, servo ready, current limit, speed limit, brake release and warning signal
RS-485 communications	Interface	Personal computer
	Transmission rate	From 2400 to 57600 bps
	Functions	Parameter setting, status display, alarm display (monitor, clear, history), servo drive data tracing function, test run/autotuning operations, real time trace, absolute encoder setting, default values function
MECHATROLINK communications	Communications protocol	MECHATROLINK-II
	Transmission rate	10 Mbps
	Data length	32 bytes
	Functions	Parameter setting, status display, alarm display (monitor, clear, history), default values function
Dynamic brake (DB)		Horizontal and vertical axis mode. One parameter rigidity setting. Load inertia detection.
Regenerative processing		Operates when main power OFF, servo alarm, overtravel or servo OFF
Regenerative resistor		Built-in regeneration resistor in models from 750 W to 1.5 kW. External regeneration resistor optionally.
Dynamic braking (DB) prevention function		Dynamic brake, disables torque or emergency stop torque during POT and NOT operation
Emergency stop (STOP)		Emergency stop input
Emergency stop (STOP) prevention function		Emergency stop input
Emergency stop (STOP) prevention function		Optional division pulses possible
Dynamic braking (DB) prevention function		0,01 < Numerator/Denominator < 100
Internal speed setting function		8 internal speeds
Protective functions		Overvoltage, undervoltage, overcurrent, overload, regeneration overload, servo drive overheat
Position monitor Output		The actual servomotor speed, command speed, torque and number of accumulated pulses can be measured using an oscilloscope or other device.
Operator	Display functions	A 2-digit 7-segment LED display shows the servo drive status, alarm codes, parameters, etc. MECHATROLINK-II communications status LED indicator (COM)
	Switches	Rotary switch for setting the MECHATROLINK-II node address

Pulse servo drive specifications

Mode		Position, speed and torque control mode
Speed variance	Load variance	During 0 to 100% load ± 0.01 max. (at rated speed)
	Voltage variance	0% at $\pm 10\%$ of rated voltage (at rated speed)
	Temperature dependence	0 to 50°C $\pm 0.1\%$ max. (at rated speed)
Frequency characteristics		1 kHz
Torque control accuracy (reproducibility)		$\pm 3\%$ (at 20% to 100% of rated torque)
Start time setting		0 to 10 s (acceleration time and deceleration time can be set)
Command pulse	Input pulse type	Signal + pulse, 90° phase displacement 2-phase pulse (phase A/B) or reverse and forward pulses (CW/CCW)
	Input pulse frequency	500 kpps max. line-driver input, 200 kpps max. open-collector input
	Electronic gearing	0,01 < Numerator/Denominator < 100
Speed control	Speed reference voltage	10 VDC at 3000 r/min: set at delivery (the scale can be set by parameters)
	Torque limit	3 VDC at rated torque (torque can be limited separately in positive/negative direction)
	Preset speed control	Preset speed is selectable from 8 internal settings by digital inputs.
Torque control	Torque reference voltage	3 VDC at rated torque: set at delivery (the scale and polarity can be set by parameters).
	Speed limit	Speed limit can be set by parameter.
Emergency input signal		Forward/reverse run prohibit, deviation counter reset, alarm reset, control mode switch, pulse prohibited, speed selection, gain switch, zero speed designation, origin proximity
Emergency output signal		Brake release, servo ready and alarm output. It is possible also to output two types of configurable signals: current limit, rotation speed detection, warning signal, speed coincidence, positioning completed

Communications	Interface	Personal computer
	Transmission rate	From 2400 to 57600 bps
	Functions	Parameter setting, status display, alarm display (monitor, clear, history), servo drive data tracing function, test run/autotuning operations, real time trace, absolute encoder setting, default values function
Communications	Interface	Communication data interface between servo drives and personal computer.
	Transmission rate	From 2400 to 57600 bps
	Functions	Parameter setting, status display, alarm display (monitor, clear, history), servo drive data tracing function, test run/autotuning operations, real time trace, absolute encoder setting, default values function
Horizontal and vertical axis mode	Horizontal and vertical axis mode. One parameter rigidity setting. Load inertia detection.	
Dynamic brake (DB)	Operates when main power OFF, servo alarm, overtravel or servo OFF	
Regeneration processing	Built-in regeneration resistor in models from 750 W to 1.5 kW. External regeneration resistor optionally.	
Dynamic braking (DBT) prevention function	Dynamic brake, disables torque or emergency stop torque during POT and NOT operation	
Emergency stop (STOP)	Emergency stop input	
Parameter setting function	Optional division pulses possible	
Protection functions	Overvoltage, undervoltage, overcurrent, overload, regeneration overload, servo drive overheat	
Speed Feedback Output	The actual servomotor speed, command speed, torque and number of accumulated pulses can be measured using an oscilloscope or other device.	
Display	Display functions	A 6-digit 7-segment LED display shows the servo drive status, alarm codes, parameters, etc.
	Switches	Unit No. switch for serial communications. Value from 0 to F. To identify which servo drive the computer is accessing in RS232 communications when multiple servo drives.

part names



ifications

Circuit connector (CNA) specifications

Name	Function
Main circuits power supply input	AC power input terminals for the main circuit Note: for single-phase connect the power supply input to L1 and L3
Control circuit power supply input	AC power input terminals for the control circuit

Motor connector (CNB) specifications

Name	Function
External regeneration resistor connection terminals	Up to 400 W: If regenerative energy is high, connect an external regeneration resistor between B1 and B2. From 750 W to 1.5kW: Normally B2 and B3 are connected. If regenerative energy is high, remove the short-circuit bar between B2 and B3 and connect an external regeneration resistor between B1 and B2.
Servo motor connection terminals	Terminals for outputs to the servomotor.
Frame ground	Ground terminal. Ground to 100Ω or less.

als (CN1) - Input signals (for MECHATROLINK-II servo drives)

Signal name	Function
+24VIN	Control power supply input for sequence signals: users must provide the +24 V power supply. Allowable voltage range: 12 to 24 VDC
STOP	Emergency Stop Input Input for emergency stop. Emergency stop function factory default: enable.
EXT3 EXT2 EXT1	External Latch Signals This external signal input latches the current value feedback pulse counter. Minimal signal width must be 1 ms.
IN1	External general-purpose Input 0 This input is used as external general-purpose input.
IN0	External general-purpose Input 1
IN2	External general-purpose Input 2
PCL NCL	Forward Torque Limit Input Reverse Torque Limit Input This signal input selects the torque limit.
POT NOT	Forward Run Prohibit Input Reverse Run Prohibit Input Forward/ reverse drive rotation overtravel input. Stops servomotor when movable part travels beyond the allowable range of motion.
DEC	Origin Proximity Input Connect the origin proximity input signal in the origin search operation.
BAT	Battery backup input for absolute encoder
BATCOM	Connecting pin for the absolute backup battery. Do not connect when a battery is connected to the servomotor encoder cable.

als (CN1) - output signals (for MECHATROLINK-II servo drives)

Signal name	Function
/ALM	The output turns OFF when an alarm is generated in the Servo drive.
ALMCOM	
OUTM2 OUTM2COM	General-purpose output.
OUTM3 OUTM3COM	The function for this output is selected by changing the parameter: INP1 (Positioning completed), VCMP (Speed conformity signal), TGON (Servomotor rotation speed detection), READY (Servo ready), CLIM (Current limit detection), VLIM (Speed limit detection), BKIR (Brake interlock), WARN (Warning signal)
OUTM1 OUTM1COM	

als (CN1) - Input signals (for analog/pulse servo drives)

Control mode	Signal name	Function
Position	+24 VCW	Reference pulse input for line driver and open collector according to parameter setting.
	+CW	Input mode: Sign + pulse string Reverse/forward pulse (CCW/CW pulse) Two-phase pulse (90° phase differential)
	-CW	
	+24 VCW	
	+CCW	
	-CCW	Reference pulse input for line driver only.
	+CWLD	
	-CWLD	
+CCWLD		
-CCWLD	Input mode: Reverse/forward pulse (CW/CCW pulse)	
Speed	REF	Speed reference input: ±10 V/rated motor speed (input gain can be modified using a parameter).
Torque	TREF1	Torque reference input: ±10 V/rated motor torque (input gain can be modified using a parameter).
	VLIM	Speed limit input: ±10 V/rated motor speed (input gain can be modified using a parameter).
-	AGND1	Analog signal ground
Torque	TREF2	Torque reference input: ±10 V/rated motor torque (input gain can be modified using a parameter).
Position/Speed	PC1	Forward torque limit input: ±10 V/rated motor torque (input gain can be modified using a parameter).

Control mode	Signal name	Function	
Common	+24 VIN	Control power supply input for sequence signals: users must provide the +24 V power supply (12 to 24 V).	
	RUN	Servo ON: this turn ON the servo.	
Position	DFSEL	Vibration filter switching	Enables vibration filter according parameter setting.
Speed	PNSSEL	Speed command rotation direction switch	
Speed/Torque	VZERO	Zero speed designation	Speed command is regarded as 0. This function is enable/disable by parameter.
	GSEL	Gain switching	Enables gain value according parameter setting.
Common	TLSEL	Torque limit switch.	
	GESEL	Electronic gear switching	Switches the numerator for electronic gear ratio.
Speed	VSEL3	Internal speed selection 3	Input to select the desired speed setting during internally speed operation. The speed selection is combining this input with VSEL1 and VSEL2 inputs.
Position	ECRST	Error counter reset input.	Resets the position error counter.
Speed	VSEL2	Internal speed selection 2	Input to select the desired speed setting during internally speed operation. The speed selection is combining this input with VSEL1 and VSEL3 inputs.
Common	RESET	Alarm reset input.	Release the alarm status. The error counter is reset when the alarm is reset.
Position/ Speed/Torque	TVSEL	Control mode switching	Position ↔ speed
			Position ↔ torque
			Torque ↔ speed

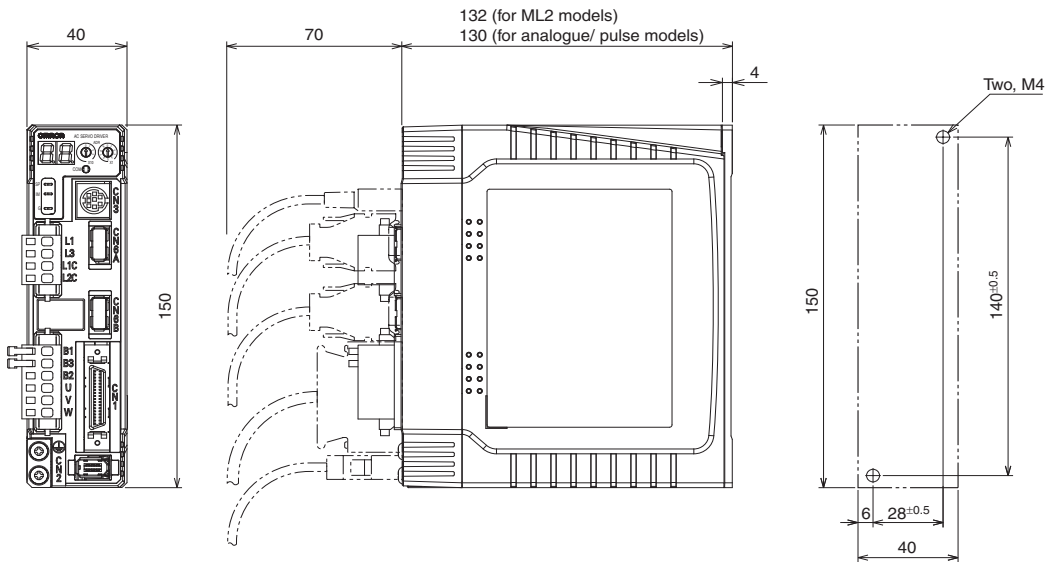
CN1) - Output signals (for analog/pulse servo drives)

Control mode	Signal name	Function	
Position	+A	Encoder phase A+	Encoder signals are output according Encoder Dividing Numerator parameter. This is the line-driver output (equivalent to R422).
	-A	Encoder phase A-	
	+B	Encoder phase B+	
	-B	Encoder phase B-	
	+Z	Encoder phase Z+	
	-Z	Encoder phase Z-	
	Z	Encoder phase-Z output	Phase Z is output for encoder signals. Open-collector output.
	ZCOM	Encoder phase-Z common	
	BKIR	Brake release signal output	Timing signal for operating the electromagnetic brake on a motor.
		BKIRCOM	
		READY	Servo ready: ON if there is not servo alarm when the control/main circuit power supply is turned ON.
		READYCOM	
		/ALM	Servo alarm: turns OFF when an error is detected.
	ALMCOM		
Speed/torque	TGON	Motor rotation speed detection. This output turns ON when the motor rotation speed reaches the speed set in a parameter.	
	TGONCOM		
Position	INP	Positioning complete output: turns ON when position error is equal to setting parameter.	
	INPCOM		
	INP2	Position complete output 2	The function of output signals allocated to pins 11,10, 34 to 39 can be changed with these options by parameters settings.
	P-CMD	Position command status	
	ZSP	Zero speed	
	WARN1	Warning 1	
	WARN2	Warning 2	
	ALM-ATB	Alarm output	
	VCMP	Speed conformity output	
	V-CMD	speed command status	
	V-LIMIT	Speed limit detection	
	T-LIMIT	Torque limit detection	
Position	OUTM1	General-purpose Output 1	Use the parameter settings to assign the desired function
	OUTM2	General-purpose Output2	
	COM	General-purpose common	Output ground common

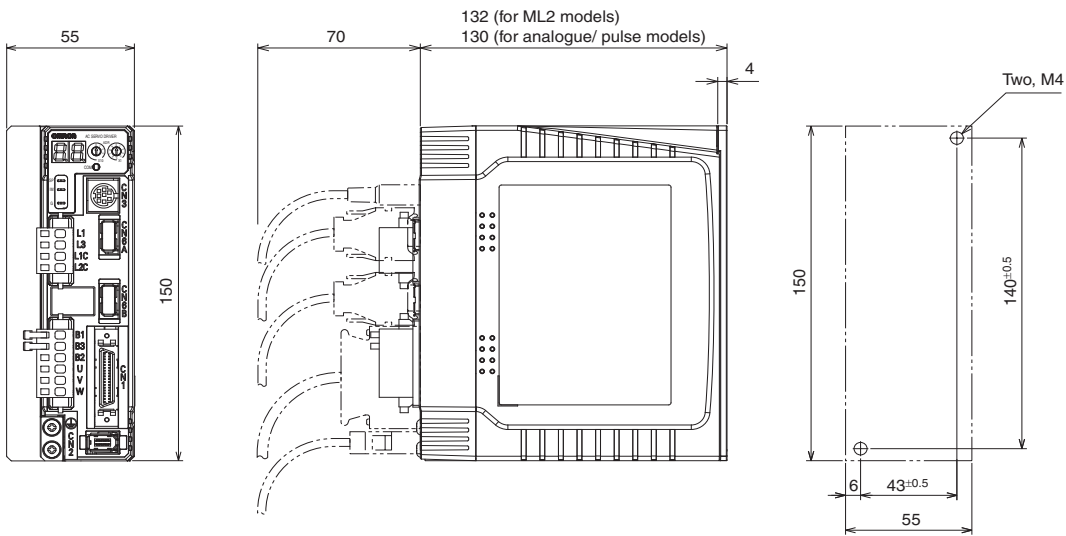
Dimensions

Drives

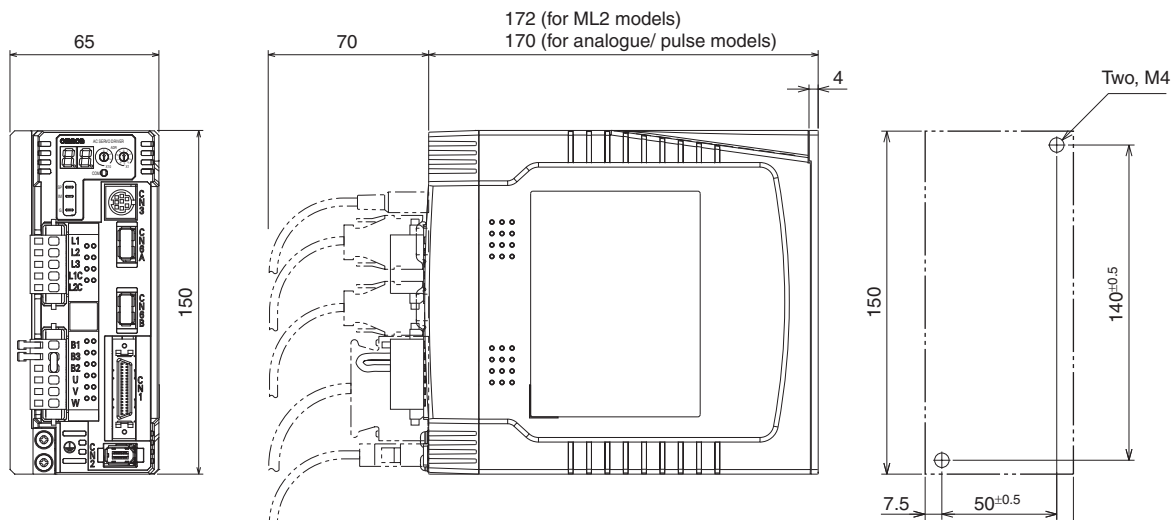
N01/02H-ML2, R88D-GT01/02H (200 V, 100 to 200 W)



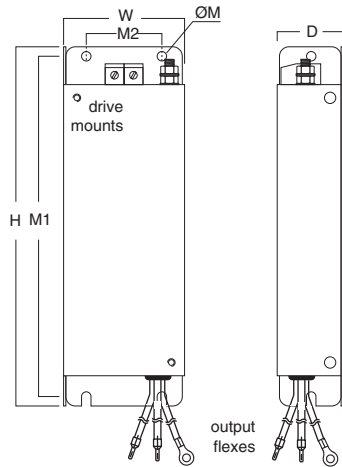
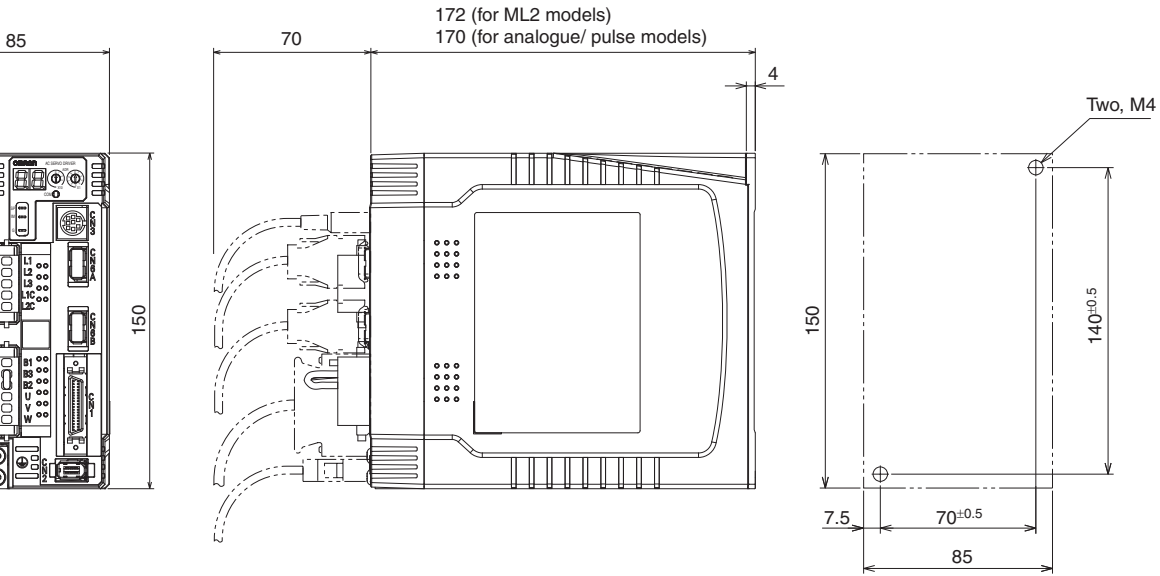
N04H-ML2, R88D-GT04H (200 V, 400 W)



N08H-ML2, R88D-GT08H (200 V, 750 W)



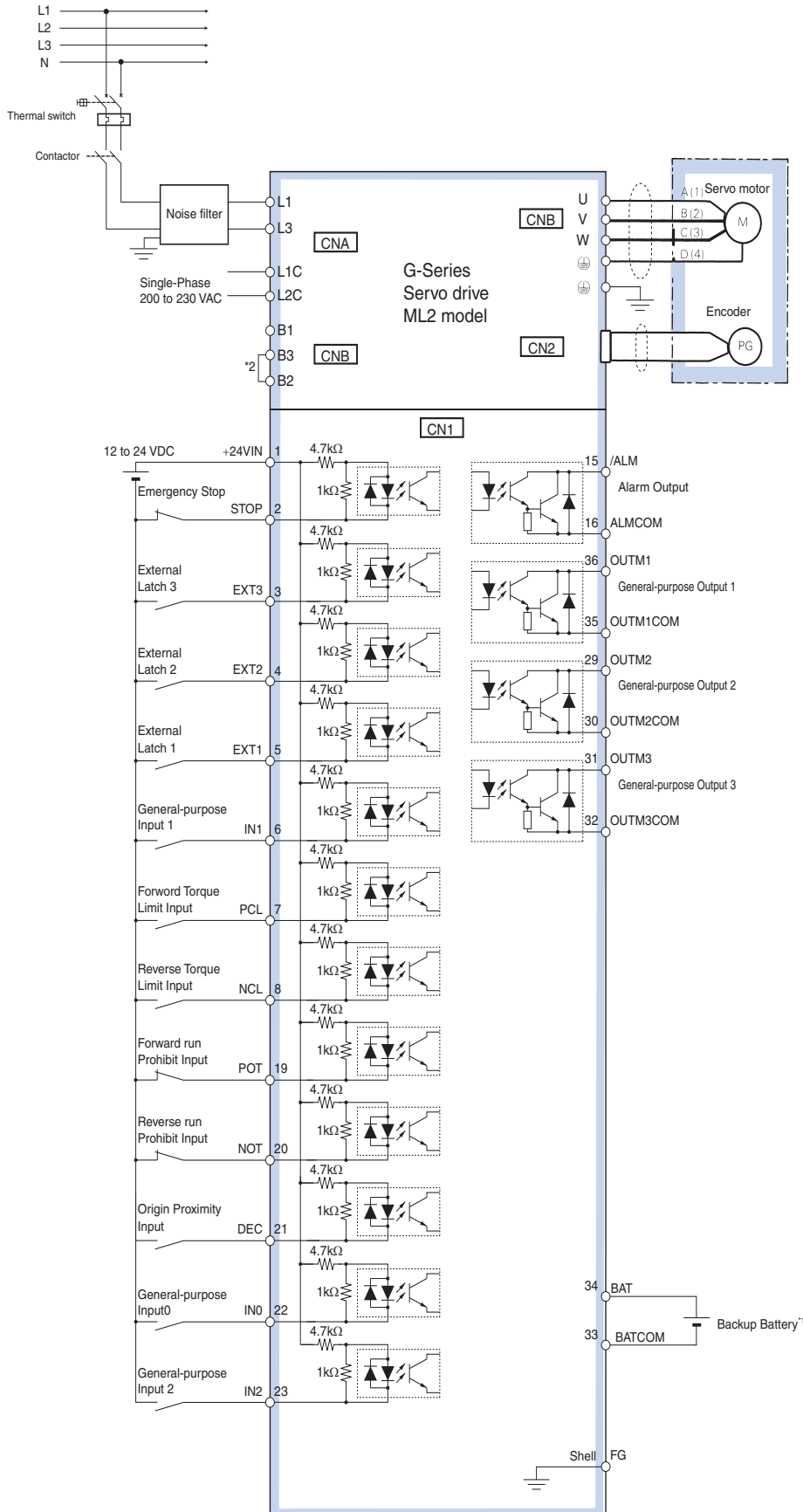
/15H-ML2, R88D-GT10/15H (200 V, 1 kW to 1,5 kW)



	Rated current	Leakage current	External dimensions			Mount dimensions		Filter Fixing	Rated voltage
			H	W	D	M1	M2		
E	2.4 A	3.5 mA	190	42	44	180	20	M4	250 VAC single-phase
E	4.1 A	3.5 mA	190	57	30	180	30	M4	
E	6.6 A	3.5 mA	190	64	35	180	40	M4	
E	14.2 A	3.5 mA	190	86	35	180	60	M4	

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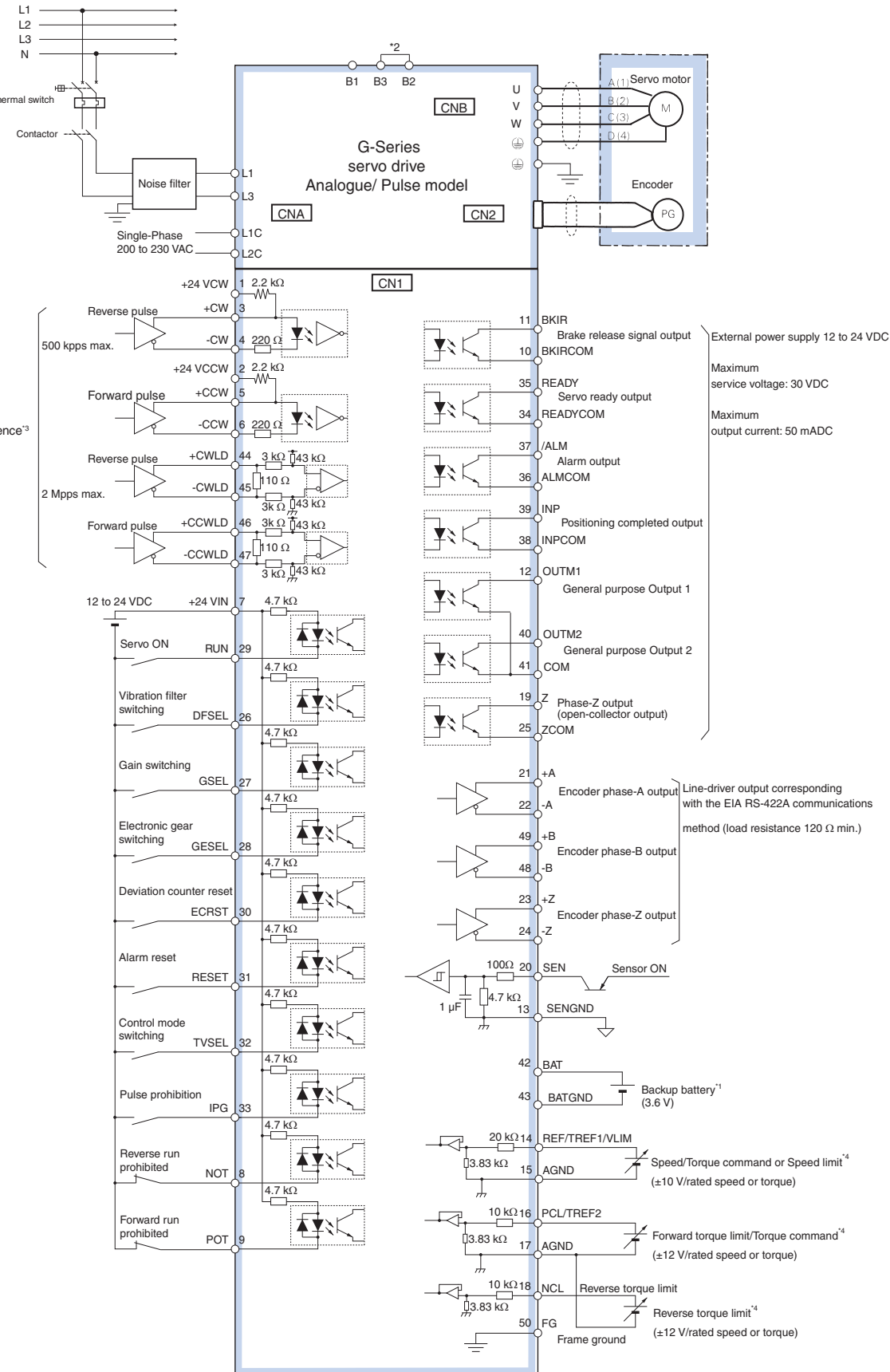
hase, 230 VAC



AC Servo systems

only with an absolute encoder. If a backup battery is connected to CN1 I/O connector, an encoder cable with a battery is not required.

Supply, 230 VAC



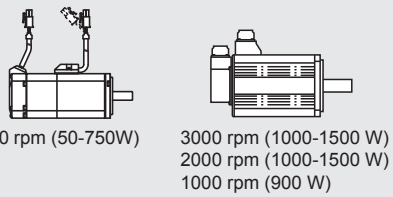
Supply with an absolute encoder. If a backup battery is connected to CN1 I/O connector, an encoder cable with a battery is not required.

Power derives from 750 W, B2 and B3 are short-circuited. If the internal regenerative resistor is insufficient, remove the wire between B2 and

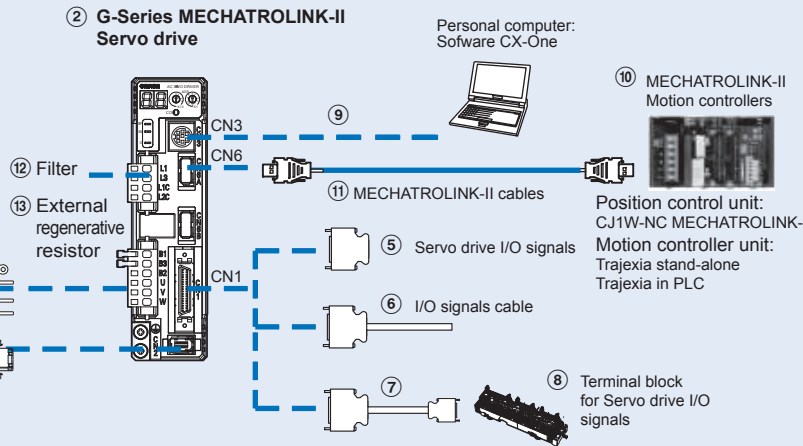
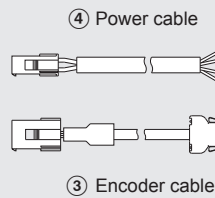
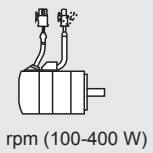
ing information

s MECHATROLINK-II model reference configuration

Series Cylindrical type servo motor



Series Flat type servo motor



AC Servo systems

The symbols ①②③④⑤... show the recommended sequence to select the components in a G-Series servo system

motors, power & encoder cables

③④ Refer to the G-Series servo motor chapter for servomotor, motor cables or connectors selection

drives

Capacity	Servo drive model	① Compatible rotary servo motors	
		Cylindric type	Flat type
0 W	R88D-GN01H-ML2	R88M-G05030□ R88M-G10030□	R88M-GP10030□
0 W	R88D-GN02H-ML2	R88M-G20030□	R88M-GP20030□
0 W	R88D-GN04H-ML2	R88M-G40030□	R88M-GP40030□
0 W	R88D-GN08H-ML2	R88M-G75030□	-
0 kW	R88D-GN10H-ML2	R88M-G1K020T□	-
5 kW	R88D-GN15H-ML2	R88M-G90010T□ R88M-G1K030T□ R88M-G1K520T□ R88M-G1K530T□	-

cables (for CN1)

Name	Connect to	Model
I/O connector kit	Servo drive I/O signals	R88A-CNU01C
General purpose cable		1 m R88A-CPGB001S-E 2 m R88A-CPGB002S-E
Terminal block cable		1 m XW2Z-100J-B33 2 m XW2Z-200J-B33
Terminal block		- XW2B-20G4 XW2B-20G5 XW2D-20G6

er cable (for CN3)

Name	Model
Computer cable RS232	2 m R88A-CCG002P2

ROLINK-II Motion controllers

Name	Model
Trajexia stand-alone motion controller	TJ2-MC64 (64 axes)
	TJ1-MC16 (16 axes)
	TJ1-MC04 (4 axes)
Trajexia-PLC motion controller	CJ1W-MCH72 (30 axes)
	CJ1W-MC472 (4 axes)
Position Controller Unit for CJ1 PLC	CJ1W-NCF71 (16 axes)
	CJ1W-NC471 (4 axes)
	CJ1W-NC271 (2 axes)

MECHATROLINK-II cables (for CN6)

Symbol	Specifications	Length	Model
⑪	MECHATROLINK-II Terminator resistor	-	JEPMC-W6022-E
	MECHATROLINK-II cables	0.5 m	JEPMC-W6003-A5-E
		1 m	JEPMC-W6003-01-E
		3 m	JEPMC-W6003-03-E
		5 m	JEPMC-W6003-05-E
		10 m	JEPMC-W6003-10-E
		20 m	JEPMC-W6003-20-E
		30 m	JEPMC-W6003-30-E

Filters

Symbol	Applicable servodrive	Filter model	Rated current	Leakage current	Rated voltage
⑫	R88D-GN01H□ R88D-GN02H□	R88A-FIK102-RE	2.4 A	3.5 mA	250 VAC single-phase
	R88D-GN04H□	R88A-FIK104-RE	4.1 A	3.5 mA	
	R88D-GN08H□	R88A-FIK107-RE	6.6 A	3.5 mA	
	R88D-GN10H□ R88D-GN15H□	R88A-FIK114-RE	14.2 A	3.5 mA	

External regenerative resistor

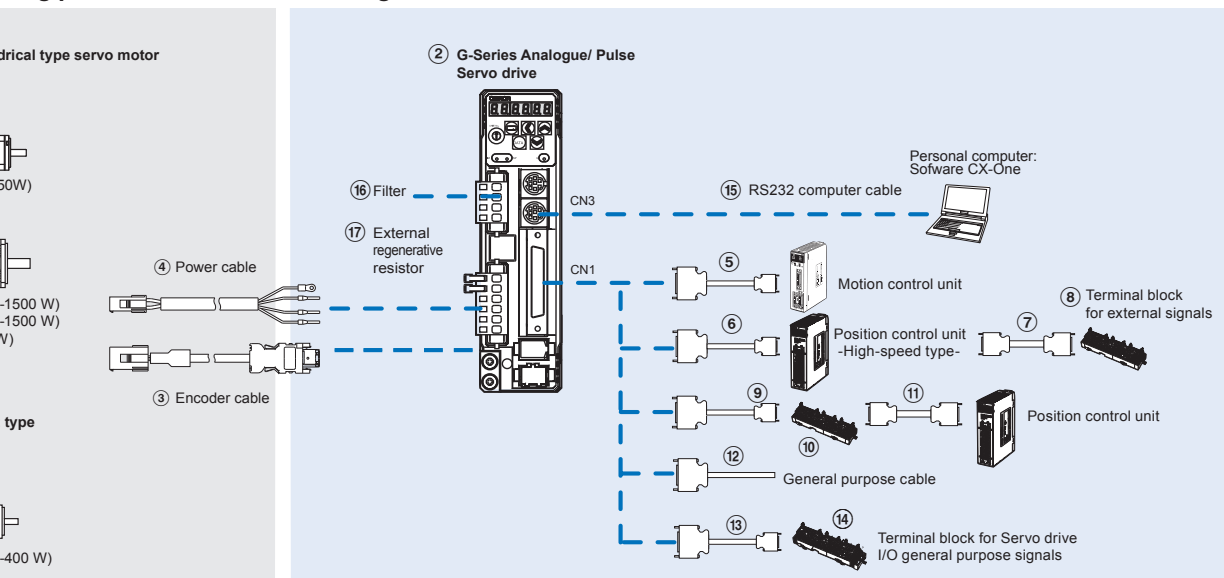
Symbol	Regenerative resistor unit model	Specifications
⑬	R88A-RR08050S	50 Ω, 80 W
	R88A-RR080100S	100 Ω, 80 W
	R88A-RR22047S	47 Ω, 220 W
	R88A-RR50020S	20 Ω, 500 W

Computer software

Specifications	Model
Configuration and monitoring software tool for servo drives and inverters. (CX-drive version 1.70 or higher)	CX-drive
Complete OMRON software package including CX-drive. (CX-One version 3.10 or higher)	CX-One

information

analog/pulse model reference configuration



Numbers ①②③④⑤... show the recommended sequence to select the components in a G-Series servo system

Power, power & encoder cables

Refer to the G-Series servo motor chapter for servomotor, motor cables or connectors selection

Servo drive model		① Compatible rotary servo motors		
		Cylindrical type	Flat type	
200 VAC	100 W	R88D-GT01H	R88M-G05030□ R88M-G10030□	R88M-GP10030□
	200 W	R88D-GT02H	R88M-G20030□	R88M-GP20030□
	400 W	R88D-GT04H	R88M-G40030□	R88M-GP40030□
	750 W	R88D-GT08H	R88M-G75030□	-
	1.0 kW	R88D-GT10H	R88M-G1K020T□	-
	1.5 kW	R88D-GT15H	R88M-G90010T□ R88M-G1K030T□ R88M-G1K520T□ R88M-G1K530T□	- - - -

Cables (for CN1)

Description	Connect to	Model
Cable (100 V) Motion control units	Motion control units CS1W-MC221 CS1W-MC421	1 m R88A-CPG001M1
		2 m R88A-CPG002M1
		3 m R88A-CPG003M1
		5 m R88A-CPG005M1
Cable (100 V) Motion control units	Motion control units CS1W-MC221 CS1W-MC421	1 m R88A-CPG001M2
		2 m R88A-CPG002M2
		3 m R88A-CPG003M2
		5 m R88A-CPG005M2
Cable (100 V) Driver output for 1 axis)	Position control units (high-speed type) CJ1W-NC234 CJ1W-NC434	1 m XW2Z-100J-G9
		5 m XW2Z-500J-G9
		10 m XW2Z-10MJ-G9
Cable (100 V) Collector output for 1 axis)	Position control units (high-speed type) CJ1W-NC214 CJ1W-NC414	1 m XW2Z-100J-G13
		3 m XW2Z-300J-G13
Cable (100 V) Driver output for 2 axis)	Position control units (high-speed type) CJ1W-NC234 CJ1W-NC434	1 m XW2Z-100J-G1
		5 m XW2Z-500J-G1
		10 m XW2Z-10MJ-G1
Cable (100 V) Collector output for 2 axis)	Position control units (high-speed type) CJ1W-NC214 CJ1W-NC414	1 m XW2Z-100J-G5
		3 m XW2Z-300J-G5

Description	Connect to		Model
Terminal block cable for external signals (for input common, forward/reverse run prohibited inputs, emergency stop input, origin proximity input and interrupt input)	Position control units (high-speed type) CJ1W-NC234 CJ1W-NC434 CJ1W-NC214 CJ1W-NC414	0.5 m	XW2Z-C50X
		1 m	XW2Z-100X
		2 m	XW2Z-200X
		3 m	XW2Z-300X
		5 m	XW2Z-500X
		10 m	XW2Z-010X
Terminal block for external signals (M3 screw, pin terminals)		-	XW2B-20G4
Terminal block for ext. signals (M3.5 screw, fork/round terminals)		-	XW2B-20G5
Terminal block for ext. signals (M3 screw, fork/round terminals)		-	XW2D-20G6
Cable from servo relay unit to servo drive	CS1W-NC1□3, CJ1W-NC1□3, C200HW-NC113, CS1W-NC2□3/4□3, CJ1W-NC2□3/4□3, C200HW-NC213/413, CQM1H-PLB21 or CQM1-CPU43 CJ1M-CPU21/22/23	1 m	XW2Z-100J-B25
		2 m	XW2Z-200J-B25
		1 m	XW2Z-100J-B31
		2 m	XW2Z-200J-B31
Servo relay unit	Position control units CS1W-NC1□3, CJ1W-NC1□3 or C200HW-NC113	-	XW2B-20J6-1B (1 axis)
		-	XW2B-40J6-2B (2 axes)
	Position control units CS1W-NC2□3/4□3, CJ1W-NC2□3/4□3 or C200HW-NC213/413 CQM1H-PLB21 or CQM1-CPU43 CJ1M-CPU21/22/23	-	XW2B-20J6-3B (1 axis)
		-	XW2B-20J6-8A (1 axis) XW2B-40J6-9A (2 axes)
		-	
Position control unit connecting cable	CQM1H-PLB21 or CQM1-CPU43	0.5 m	XW2Z-050J-A3
		1 m	XW2Z-100J-A3
	CS1W-NC113 or C200HW-NC113	0.5 m	XW2Z-050J-A6
		1 m	XW2Z-100J-A6
	CS1W-NC213/413 or C200HW-NC213/413	0.5 m	XW2Z-050J-A7
		1 m	XW2Z-100J-A7
	CS1W-NC133	0.5 m	XW2Z-050J-A10
		1 m	XW2Z-100J-A10
	CS1W-NC233/433	0.5 m	XW2Z-050J-A11
		1 m	XW2Z-100J-A11
	CJ1W-NC113	0.5 m	XW2Z-050J-A14
		1 m	XW2Z-100J-A14
	CJ1W-NC213/413	0.5 m	XW2Z-050J-A15
		1 m	XW2Z-100J-A15
	CJ1W-NC133	0.5 m	XW2Z-050J-A18
		1 m	XW2Z-100J-A18
	CJ1W-NC233/433	0.5 m	XW2Z-050J-A19
		1 m	XW2Z-100J-A19
	CJ1M-CPU21/22/23	0.5 m	XW2Z-050J-A33
		1 m	XW2Z-100J-A33
General purpose cable	For general purpose controllers	1 m	R88A-CPG001S
Terminal block cable	For general purpose controllers	2 m	R88A-CPG002S
		1 m	XW2Z-100J-B24
Terminal block (M3 screw and for pin terminals)		2 m	XW2Z-200J-B24
		-	XW2B-50G4
Terminal block (M3.5 screw and for fork/round terminals)		-	XW2B-50G5
Terminal block (M3 screw and for fork/round terminals)		-	XW2D-50G6

er cable (for CN3)

Name		Model
Computer cable RS232	2 m	R88A-CCG002P2

Connectors

Specifications	Model
I/O connector kit, 50 pins (for CN1)	R88A-CNU11C

Computer software

Specifications	Model
Configuration and monitoring software tool for servo drives and inverters. (CX-drive version 1.70 or higher)	CX-drive
Complete OMRON software package including CX-drive. (CX-One version 3.10 or higher)	CX-One

Applicable servodrive	Filter model	Rated current	Leakage current	Rated voltage
R88D-GT01H R88D-GT02H	R88A-FIK102-RE	2.4 A	3.5 mA	250 VAC single-phase
R88D-GT04H	R88A-FIK104-RE	4.1 A	3.5 mA	
R88D-GT08H	R88A-FIK107-RE	6.6 A	3.5 mA	
R88D-GT10H R88D-GT15H	R88A-FIK114-RE	14.2 A	3.5 mA	

regenerative resistor

Regenerative resistor unit model	Specifications
R88A-RR08050S	50 Ω, 80 W
R88A-RR080100S	100 Ω, 80 W
R88A-RR22047S	47 Ω, 220 W
R88A-RR50020S	20 Ω, 500 W

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