

X-axis Linear Ball Guide: KXT04015/KXT06015

KXT04015-L

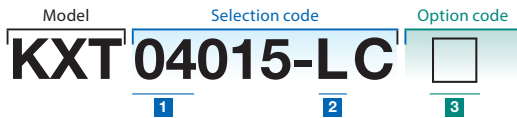


KXT06015-L



RoHS

* This photos shows a cover position is an image in case of L.
The holes and the shape may differ in certain respects from the actual product.

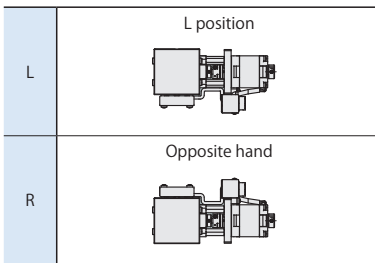


▶ Cable P.1-207~
▶ Electrical specification P.1-019~

1 Table size

04	<input type="checkbox"/> 40mm
06	<input type="checkbox"/> 60mm

2 Sensor cover location



3 Cable option

Code	Specification	Cable type
F	Robot cable 2m	D214-2-2R
G	Robot cable 2m one end loose	D214-2-2RK
H	Robot cable 4m	D214-2-4R
J	Robot cable 4m one end loose	D214-2-4RK
Blank	Cable is not included (Standard)	—

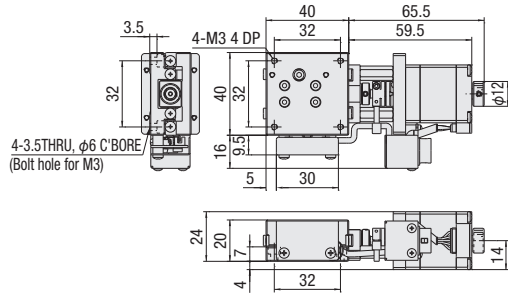
* The one end loose side might be on an opposite side of stage.
See page ▶ P.1-207,209~ for cable details.
Please select "Code F or H" when connect with stepping motor controller(DS102/112).

SPEC

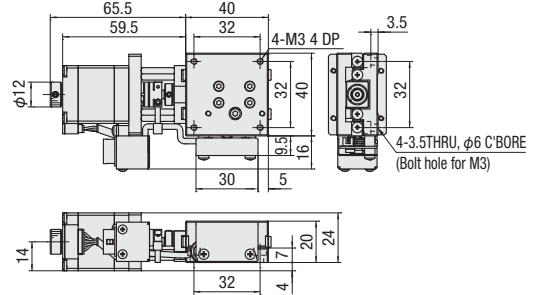
Model	KXT04015-LC		KXT06015-LC	
	KXT04015-RC		KXT06015-RC	
(Right or left handed/opposite hand)				
Travel length			15mm	
Table size	40×40mm		60×60mm	
Feed screw (Ball screw)	φ6 lead 1			
Guide	Linear ball guide			
Main materials-Finishing	Steel—Opposite side of the end face finishing			
Weight	0.38kg		0.60kg	
Resolution (Pulse)	2 μm (Full)/1 μm (Half)			
MAX speed	10mm/sec			
Uni-directional positioning accuracy	Within 10 μm			
Repeatability positioning accuracy	±1 μm			
Load capacity	10kgf [98N]			
Moment stiffness	Pitch 0.38/yaw 0.35/roll 0.21 ["/N · cm]		Pitch 0.1/yaw 0.08/roll 0.05 ["/N · cm]	
Lost motion	Within 2.5 μm			
Straightness	Within 10 μm			
Parallelism	Within 20 μm			
Pitching/Yawing	Within 30" / Within 25"		Within 35" / Within 30"	
Limit sensor	Installed			
Origin sensor	Installed			
Provided screw (Hexagon-headed bolt)	4 of M3—8		4 of M3—8	

Dimensional outline drawings

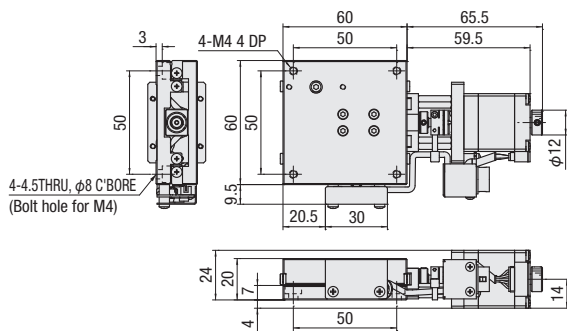
KXT04015-L



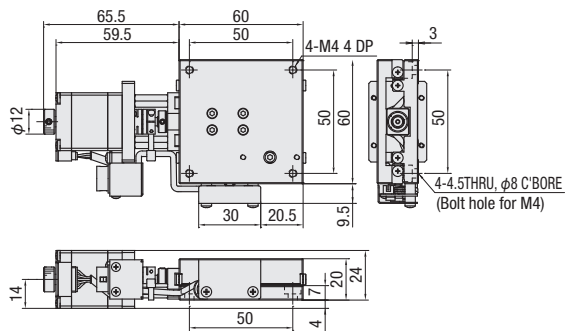
KXT04015-R



KXT06015-L



KXT06015-R



Motorized Stage

X

XY

Z

Horizontal Z

XYZ

Goniometer

Rotary

Unit

Controller

Linear Ball

CAVE-X Linear ball

Cross Roller

Slide Guide

φ40

φ50

φ60

φ70

φ80

φ100

φ120

Other

1

018

Motorized Stage

Electrical Specification: KXT04015/KXT06015

Motorized Stage

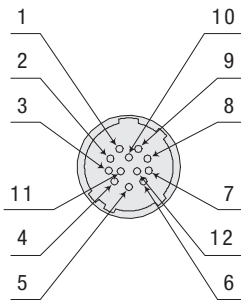
Electrical specification

Models		KXT04015	KXT06015
Motor (*1)	Type	5 phase stepping motor 0.75A/Phase	
	Maker	Oriental Motor Co.,Ltd.	
	Model (*2)	C005C-90215P	
	Step angle	0.72°	
Connector	Model	HR10A-10R-12PC (71) (Hirose Electric Co.,Ltd.)	
	Receiving connector	HR10A-10P-12S (73) (Hirose Electric Co.,Ltd.)	
Sensor	Limit sensor	Installed	
	Origin sensor	Installed	
	Model	Photo microsensor EE-SX4320 (Omuron Co.,Ltd.)	
	Power voltage	DC5~24V ±10%	
	Consumption current	Total 60mA or less	
	Control output	NPN open collector output DC5~24V 8mA or less Residual voltage 0.3V or less when the load current is 2mA	
	Output logic	On detection (light shield condition): Output transistor OFF (Non-continuity)	

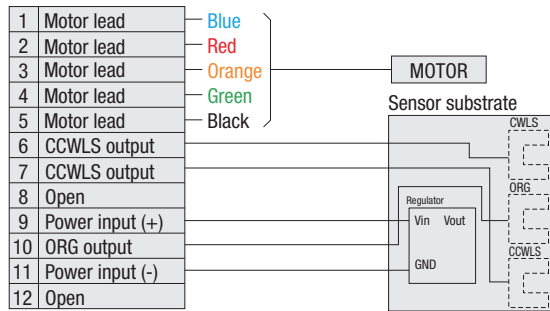
*1 See page P.1-213~ for details of single motor specification.

*2 Model is our own management model.

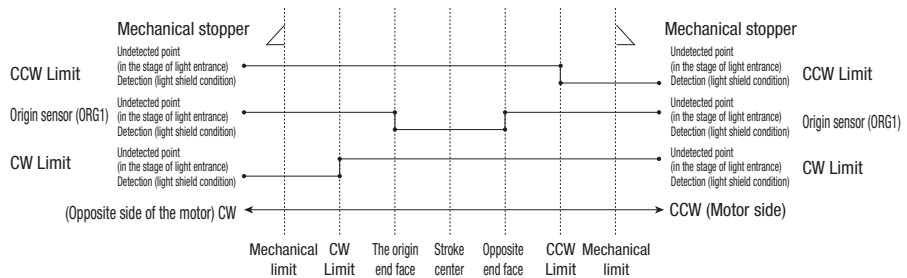
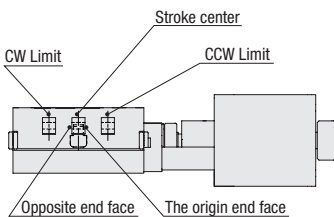
Pin allocation



Connection diagram



Timing chart



Unit [mm]	Direction of CW	Direction of CCW							
		Reference coordinate	Mechanical limit	CW Limit	The origin end face	Stroke center	Opposite end face	CCW Limit	Mechanical limit
KXT	Return to origin		7	6.2	0	1.5	3	9.2	10
	Stroke center		8.5	7.7	1.5	0	1.5	7.7	8.5

* Return to origin means that is performed return to origin type 4 using DS102/DS112 series.

* The coordinate value should be on the design. Dimension error may occur about plus or minus 0.5 deg.

Note: The timing chart shows only timing of sensor, it is not for output signal logic.

Refer to ON/OFF display of output transistor that shows on electrical specifications-sensor-output logic for output signal logic.

Linear Ball

CAVE-X Linear ball

Cross Roller

Slide Guide

φ40

φ50

φ60

φ70

φ80

φ100

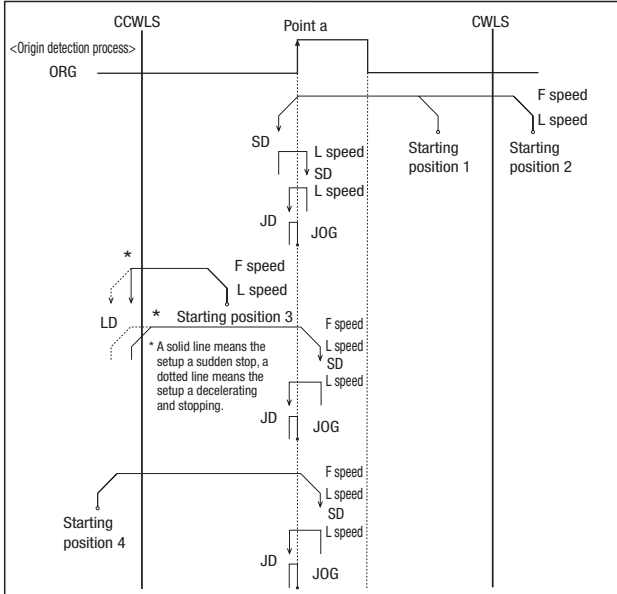
φ120

Other

KXT series recommendation return to origin method

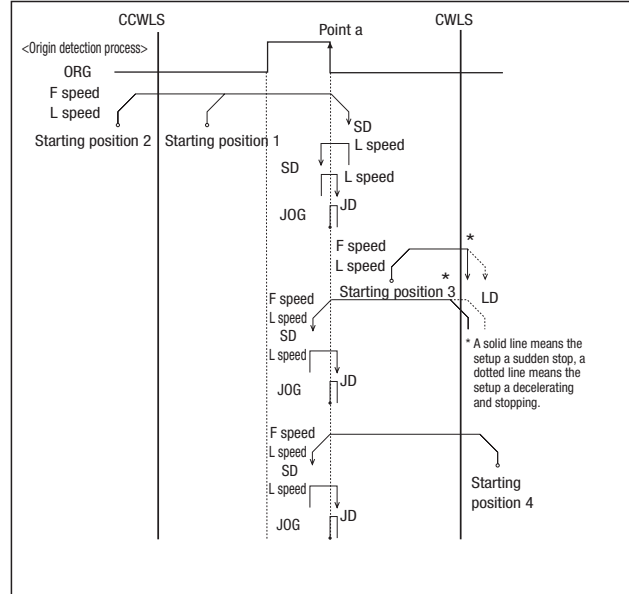
Suruga's motorized stages are different from the specification depending on the models. Therefore return to origin method other than recommendation may not be working correctly. Set to the way of recommendation return origin when using our controller.

[Type3] Detect in the direction of CCW and perform detected process for CCW edge (a point) of ORG signal.



[Type9] After finished Type3, perform detected process for CCW edge of TIMING signal.

[Type4] Detect in the direction of CW and perform detected process for CW edge of ORG signal.



[Type10] After finished Type4, perform detected process for CW edge of TIMING signal.

Return to origin sequence ▶ P.1-201~

Adaptive driver

■ **Driver** ▶ P.1-205~

DC24 type input

Model	CRD5107P	SD5107P3-A22
Divisions	1~1/250 (16 steps)	Full/Half

AC100V input

Model	RKD507-A
Divisions	1~1/250 (16 steps)

Adaptive stepping motor controller

■ **Controller** ▶ P.1-197~

Input power	General-purpose input/output port	Driver type (Divisions)	
		Normal (Full/Half)	Micro step (1~1/250 [16 steps])
AC100-240V	Without	DS102NR	DS102MS
	With	DS102NR-IO	DS102MS-IO
DC24V	Without	DS112NR	DS112MS
	With	DS112NR-IO	DS112MS-IO



Motorized Stage

- X
- XY
- Z
- Horizontal Z
- XYZ
- Goniometer
- Rotary
- Unit
- Controller

Linear Ball

CAVE-X Linear ball

Cross Roller

Slide Guide

- φ40
- φ50
- φ60
- φ70
- φ80
- φ100
- φ120
- Other