


- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor

# PSEP

Model C/CW  
3-position controller for RCP2/RCP3  
Position Controller

# ASEP

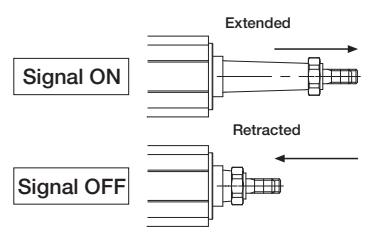
Model C/CW  
3-position controller for RCA/RCA2/RCL  
Position Controller



## Feature

### 1 Can operate with same signal as a solenoid valve.

The signal that operates the actuator is the same as the signal that operates the air cylinder. Therefore, the PLC program currently in use can be used without modification even if the air cylinder is replaced by an electric-powered cylinder. Either a single solenoid or a double solenoid may be used.



### 2 Establishes a dustproof type that supports IP53.

We provide dustproof type controllers with an IP53 equivalent (\*1) protection structure, so that the controller can be mounted outside the control panel.

(1) Bottom surface excluded.

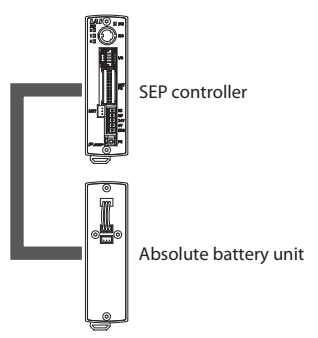


### 3 Provides the simple absolute type that can be operated immediately upon power-ON without homing.

Since the simple absolute type can store the current position with the assistance of the absolute battery unit during power-up or after the emergency stop is deactivated; it can start the next operation at that position.

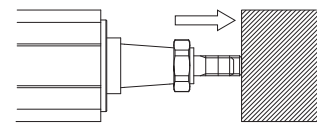
(Note 1) When the actuator is connected to the simple absolute type controller, the model is considered an incremental model.  
(Note 2) It can not be used for the linear servo type.

The absolute battery unit is required to place below the SEP controller due to the counter measures against heat.



### 4 Pushing and intermediate stop operation is available.

Like air cylinders, the pushing operation is available. In this operation, you can stop with a rod being pushed to a workpiece. Since the force for the push operation is adjustable within a range between 20 to 70 % of the maximum pushing force and a signal is generated when it reaches the specified pushing force, it can be used to determine clamping or size of workpieces.







Push force is adjustable within the range of 20 to 70% of the maximum pushing force

### 5 Easy data entry with the dedicated touch panel teaching unit.

Data, such as setting target positions or pushing force, are easily entered with the optional touch panel teaching model: CON-PT. Since the touch panel teaching unit provides an interactive menu and can be controlled directly on the screen, you can operate intuitively with no assistance from operation manuals.

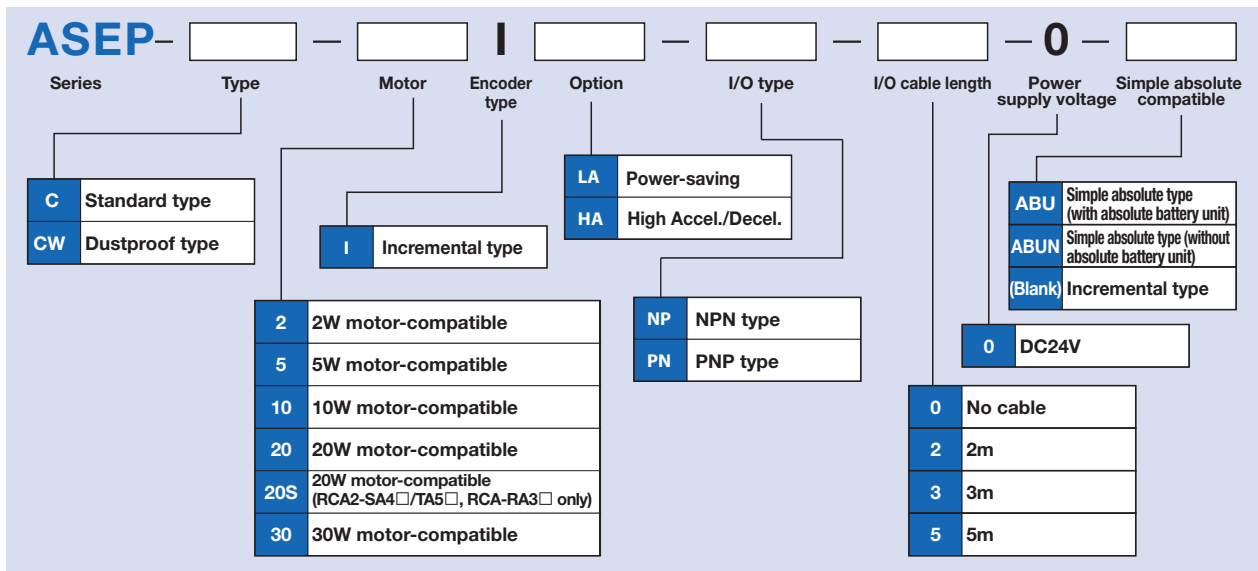
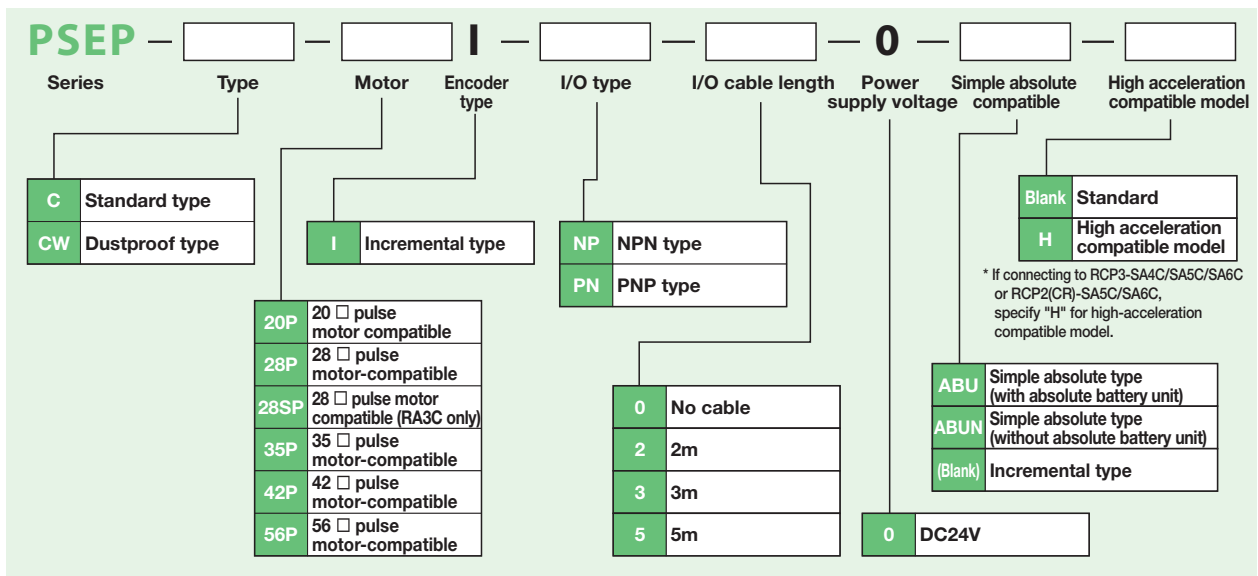


Model List

Series name	PSEP				ASEP			
	C		CW		C		CW	
Type	Standard		Dustproof		Standard		Dustproof	
Name	Standard		Dustproof		Standard		Dustproof	
Positioning method	Incremental encoder	Simple absolute type	Incremental encoder	Simple absolute type	Incremental encoder	Simple absolute type	Incremental encoder	Simple absolute type
External View								
Description	Position controller, for pulse motors, specialized to 2 positions / 3 positions positioning and easier control		PSEP-C dustproof type with an IP53 equivalent protection structure		Position controller, for servo motors, specialized to 2 positions / 3 positions positioning and easier control		ASEP-C dustproof type with an IP53 equivalent protection structure	
Number of positions	2 positions / 3 positions							

\* The absolute battery unit is attached to the simple absolute type (see P500).

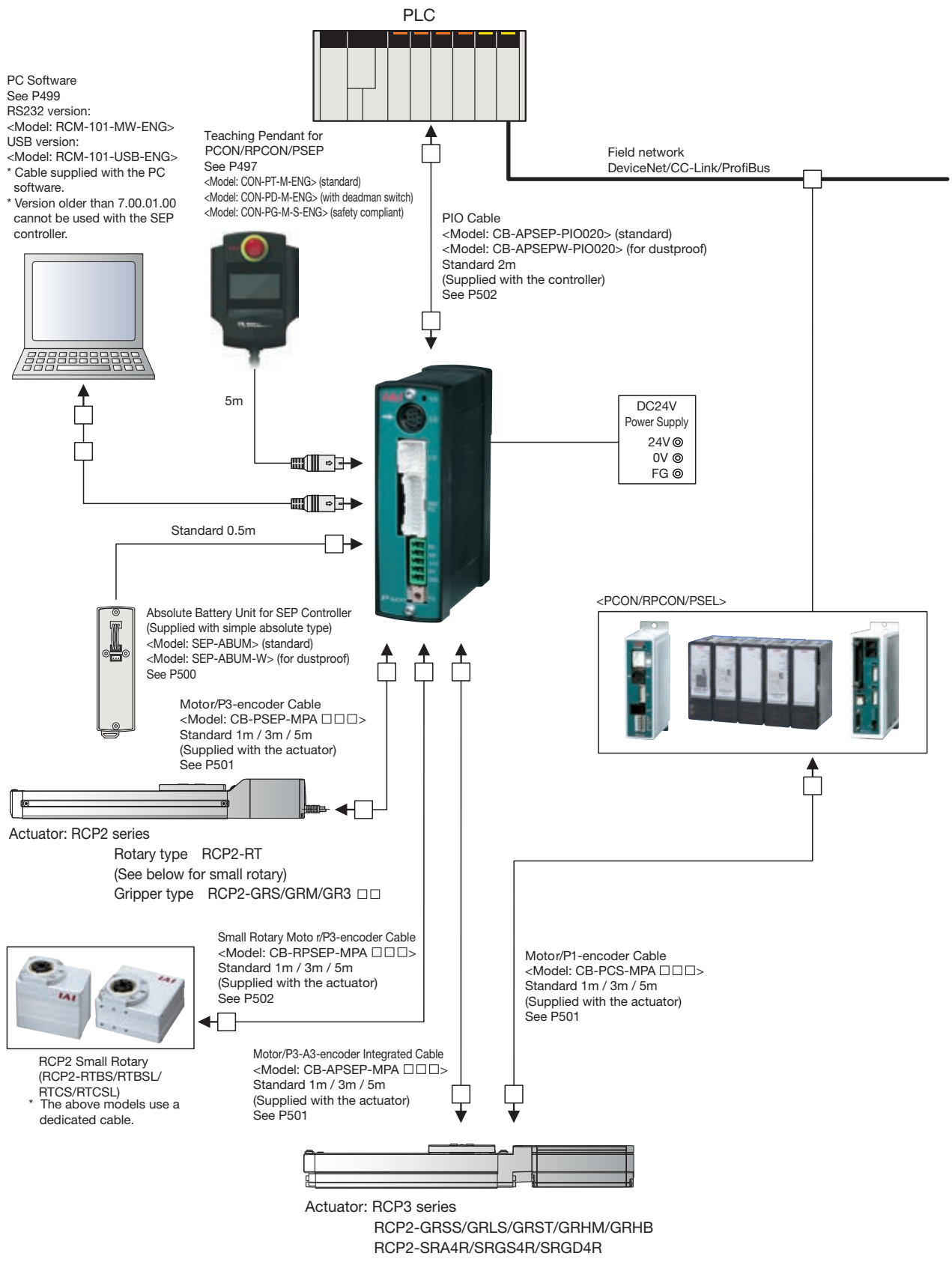
Model



- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor

## System structure

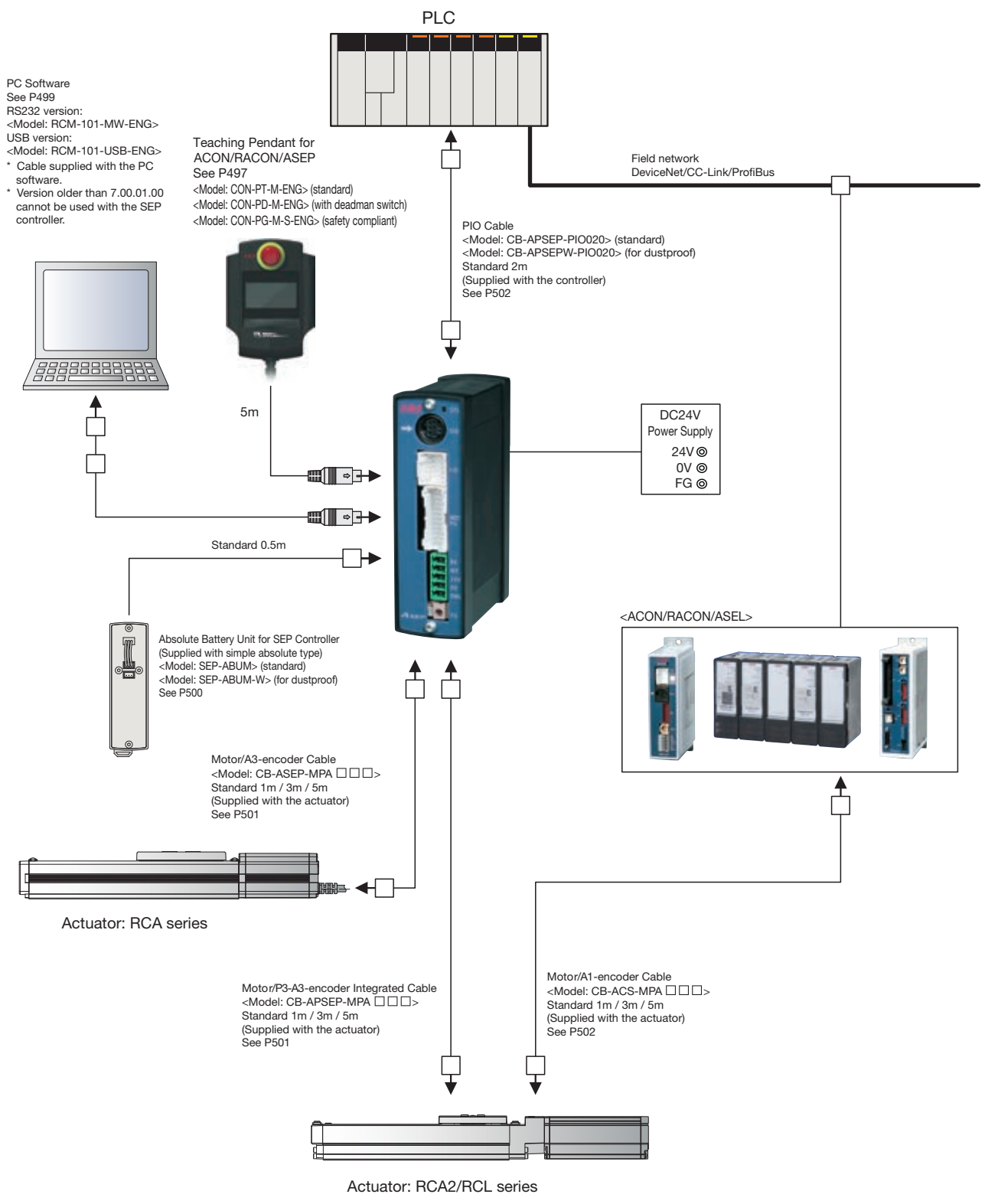
### [PSEP]



- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
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- Servo Motor (230V)
- Linear Motor

System structure

[ASEP]



PC Software  
See P499  
RS232 version:  
<Model: RCM-101-MW-ENG>  
USB version:  
<Model: RCM-101-USB-ENG>  
\* Cable supplied with the PC software.  
\* Version older than 7.00.01.00 cannot be used with the SEP controller.

Teaching Pendant for ACON/RACON/ASEP  
See P497  
<Model: CON-PT-M-ENG> (standard)  
<Model: CON-PD-M-ENG> (with deadman switch)  
<Model: CON-PG-M-S-ENG> (safety compliant)

PIO Cable  
<Model: CB-APSEP-PIO020> (standard)  
<Model: CB-APSEPW-PIO020> (for dustproof)  
Standard 2m  
(Supplied with the controller)  
See P502

DC24V Power Supply  
24V ⊕  
0V ⊕  
FG ⊕

Absolute Battery Unit for SEP Controller  
(Supplied with simple absolute type)  
<Model: SEP-ABUM> (standard)  
<Model: SEP-ABUM-W> (for dustproof)  
See P500

Motor/A3-encoder Cable  
<Model: CB-ASEP-MPA □□□>  
Standard 1m / 3m / 5m  
(Supplied with the actuator)  
See P501

Actuator: RCA series

Motor/P3-A3-encoder Integrated Cable  
<Model: CB-APSEP-MPA □□□>  
Standard 1m / 3m / 5m  
(Supplied with the actuator)  
See P501

Motor/A1-encoder Cable  
<Model: CB-ACS-MPA □□□>  
Standard 1m / 3m / 5m  
(Supplied with the actuator)  
See P502

Actuator: RCA2/RCL series

- Slider Type
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- Controllers Integrated
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- Mini
- Standard
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- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
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- Servo Motor (24V)
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- Linear Motor

PIO Pattern Description

The SEP controller provides the following six PIO patterns from which you can choose for operation. Also, PIO patterns 0 to 2 support both the single solenoid and double solenoid signal configurations.

PIO Pattern Number		0		1		2		3		4		5		
PIO Pattern Name		Standard 2-position movement		Moving speed change		Position Data Change		2-input 3-position travel		3-input 3-position travel		Continuous cycle operation		
Feature		Continuous cycle operation		2-position motion		2-position motion		3-position motion		3-position motion		Continuous motion between 2 positions		
		Push		Push		Push		Push		Push		Push		
		-		Changing speed during motion		Motion position data change		-		-		-		
Supported solenoid configurations		Single	Double	Single	Double	Single	Double	-		-		-		
Input		0	Motion signal	Motion signal 1	Motion signal	Motion signal 1	Motion signal	Motion signal 1	Motion signal 1	Retract motion signal	Continuous operation signal			
		1	Pause signal	Motion signal 2	Pause signal	Motion signal 2	Pause signal	Motion signal 2	Motion signal 2	Extend motion signal	Pause signal			
		2	- (Reset signal)		Moving speed change signal (reset signal)		Target position change signal (reset signal)		- (Reset signal)		Intermediate motion signal (reset signal)		- (Reset signal)	
		3	-/Servo-ON signal		-/Servo-ON signal		-/Servo-ON signal		-/Servo-ON signal		-/Servo-ON signal		-/Servo-ON signal	
Output		0	Retract motion output signal		Retract motion output signal		Retract motion output signal		Retract motion output signal		Retract motion output signal		Retract motion output signal	
		1	Extend motion output signal		Extend motion output signal		Extend motion output signal		Extend motion output signal		Extend motion output signal		Extend motion output signal	
		2	Homing completion signal / Servo-ON output signal		Homing completion signal / Servo-ON output signal		Homing completion signal / Servo-ON output signal		Midpoint position output signal		Midpoint position output signal		Homing completion signal / Servo-ON output signal	
		3	Alarm output signal / Servo-ON output signal		Alarm output signal / Servo-ON output signal		Alarm output signal / Servo-ON output signal		Alarm output signal / Servo-ON output signal		Alarm output signal / Servo-ON output signal		Alarm output signal / Servo-ON output signal	

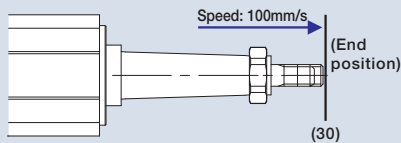
\* For the signals above, see the controller manuals (downloadable from our website).

PIO Pattern 0 (Standard 2-Position travel)

This PIO pattern involves movements between two positions—the end position and the home position. The positions can be set numerically to any position (by inputting to the controller using the optional touch panel teaching pendant).

Two motions are possible: A “positioning motion” moves the rod or the slider to the specified position, and a “pushing motion” pushes the rod against a workpiece.

Positioning Motion (Single Solenoid)

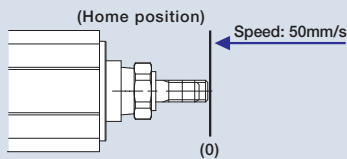


Input Signals

Input 0	ON
Input 1	-
Input 2	-
Input 3	-

When Input 0 is turned ON, the slider/rod moves to the end position (30mm coordinate) at a speed of 100mm/s.

End Position Data	
Position	30
Speed	100
Pushing force	-
Width	-



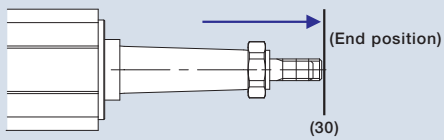
Input Signals

Input 0	OFF
Input 1	-
Input 2	-
Input 3	-

When input 0 is turned OFF, the slider/rod returns to the home position (0mm coordinate) at a speed of 50mm/s.

Home Position Data	
Position	0
Speed	50
Pushing force	-
Width	-

### Positioning Motion (Double Solenoid)

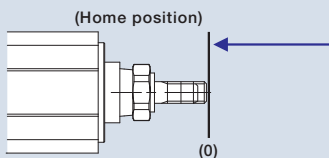


End Position Data	
Position	30
Speed	100
Pushing force	-
Width	-

#### Input Signals

Input 0	OFF
Input 1	ON
Input 2	-
Input 3	-

When Input 1 is turned ON and Input 0 is turned OFF, the slider/rod moves to the end position (30mm coordinate) at a speed of 100mm/s.



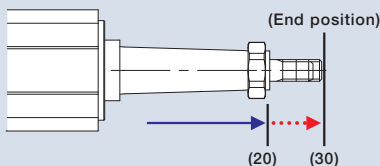
Home Position Data	
Position	0
Speed	50
Pushing force	-
Width	-

#### Input Signals

Input 0	ON
Input 1	OFF
Input 2	-
Input 3	-

When Input 0 is turned ON and Input 1 is turned OFF, the slider/rod returns to the home position (0mm coordinate) at a speed of 50mm/s.

### Push motion (single solenoid)



End Position Data	
Position	30
Speed	100
Pushing force	50
Width	10

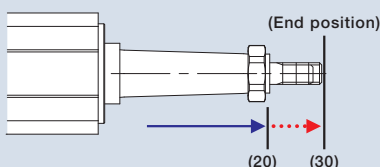
#### Input Signals

Input 0	ON
Input 1	-
Input 2	-
Input 3	-

When Input 0 is turned ON, the rod moves to the 20mm position at 100mm/s, and then starts pushing from the 20mm position to the 30mm position at slow speed.

\* The pushing motion is performed only if there is a numerical value for the pushing force in the controller's position data. (If there is no numerical value for the pushing force, a positioning motion will be performed instead.)

### Push motion (double solenoid)



End Position Data	
Position	30
Speed	100
Pushing force	50
Width	10

#### Input Signals

Input 0	OFF
Input 1	ON
Input 2	-
Input 3	-

When Input 1 is turned ON and Input 0 is turned OFF, the rod moves to the 20mm position at 100mm/s, and then starts pushing from the 20mm position to the 30mm position at slow speed.

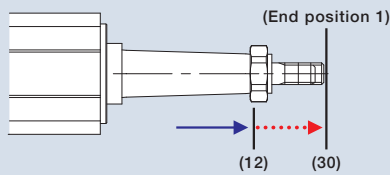
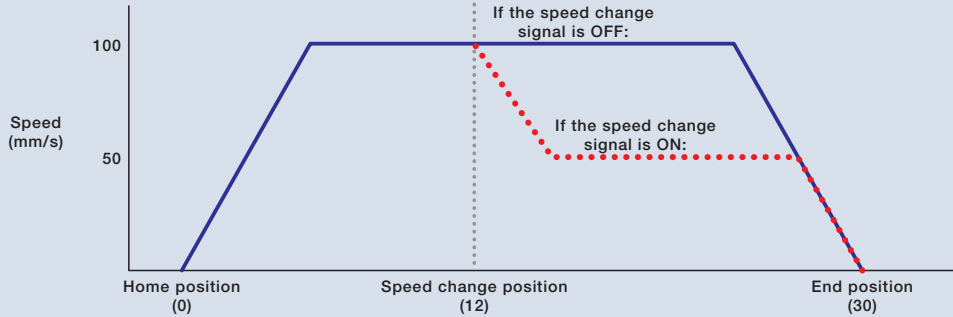
\* The pushing motion is performed only if there is a numerical value for the pushing force in the controller's position data. (If there is no numerical value for the pushing force, a positioning motion will be performed instead.)

- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
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- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
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- ERC2
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- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
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- Linear Motor

### PIO Pattern 1 (Speed Change During Movement)

This PIO pattern involves movements between two positions—the end position and the home position. The speed can be changed in 2 stages. (The speed can be either increased or decreased.) The speed change occurs when the rod/slider passes the speed change position, specified in the position values.

#### (Single Solenoid)



#### Input Signals

Input 0	ON
Input 1	-
Input 2	ON
Input 3	-

When Input 0 is turned ON while Input 2 is turned ON, the rod moves at the initial speed up to the trigger point. After it passes the trigger point, the speed changes. If Input 2 is not turned ON, the speed will not change.

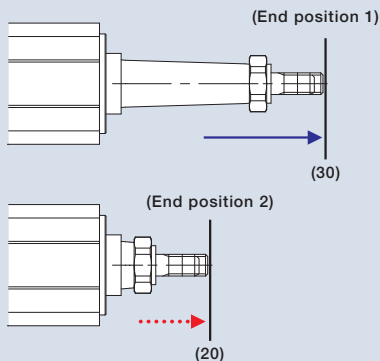
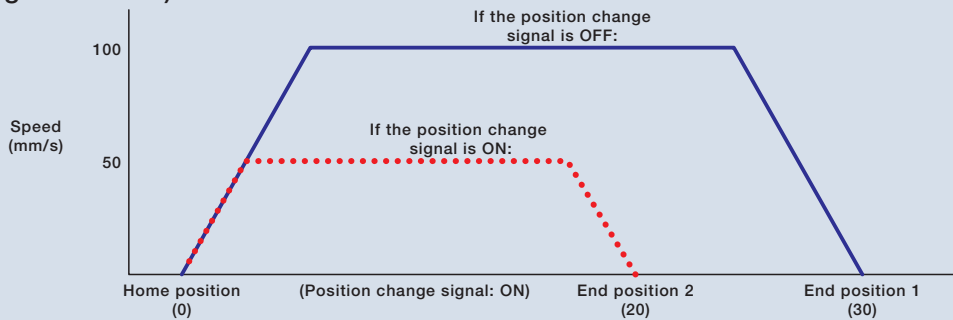
Home Position Data	
Position	0
Speed	50
Trigger point	12
Trigger speed	100
Pushing force	-
Width	-

End Position Data	
Position	30
Speed	100
Trigger point	12
Trigger speed	50
Pushing force	-
Width	-

### PIO Pattern 2 (Position Change)

This PIO pattern involves movements between two positions—the end position and the home position. You can set 2 sets of data for the end / home positions, speed, pushing force, and pushing width. Switching between the 2 sets of data can be done by turning ON/OFF Input 2, which is the signal for switching the target position.

#### (Single Solenoid)



#### Input Signals

Input 0	ON
Input 1	-
Input 2	ON
Input 3	-

If Input 2 (position change signal) is OFF when Input 0 is turned ON, the rod moves according to the position and speed set in "End Position Data 1" (position: 30 / speed: 100).  
 If Input 2 is ON when Input 0 is turned ON, the rod's movement changes to the position and speed set in "End Position Data 2" (position: 20 / speed: 50).  
 If Input 2 is OFF when the movement starts, but is turned ON in transit, the target position and speed is changed from that position.

End Position Data 1	
Position	30
Speed	100
Pushing force	-
Width	-

End Position Data 2	
Position	20
Speed	50
Pushing force	-
Width	-

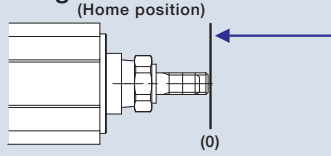


### PIO Pattern 3 (2-Input 3-Position Travel)

This PIO pattern involves movements between 3 positions—the end position, the home position, and an intermediate position.

Changing between the positions is done by a combination of 2 signals, Input 0 and Input 1.

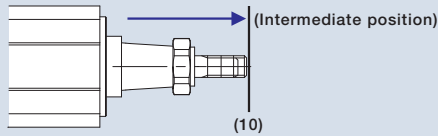
#### Positioning Motion



#### Input Signals

Input 0	ON
Input 1	OFF
Input 2	-
Input 3	-

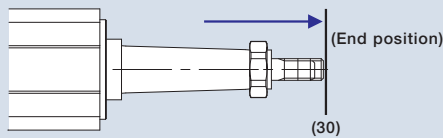
When only Input 0 is turned ON, the rod moves to the home position at the specified speed.



#### Input Signals

Input 0	ON
Input 1	ON
Input 2	-
Input 3	-

When Input 0 and Input 1 are both turned ON, the rod moves to the intermediate position at the specified speed.



#### Input Signals

Input 0	OFF
Input 1	ON
Input 2	-
Input 3	-

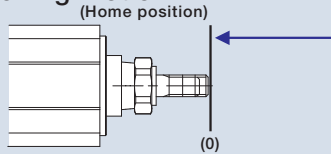
When only Input 1 is turned ON, the rod moves to the end position at the specified speed.

### PIO Pattern 4 (3-Input 3-Position Travel)

This PIO pattern involves movements between 3 positions—the end position, the home position, and an intermediate position.

Changing between positions is done by three signals—Input 0, Input 1 and Input 2, which are commanded to move to the home, end and intermediate positions, respectively.

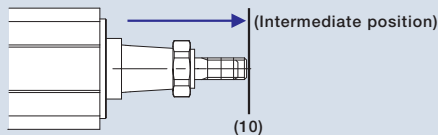
#### Positioning Motion



#### Input Signals

Input 0	ON
Input 1	OFF
Input 2	OFF
Input 3	-

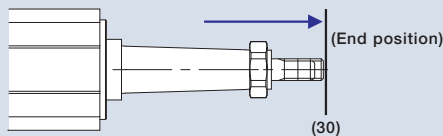
When Input 0 is turned ON, the rod moves to the home position at the specified speed.



#### Input Signals

Input 0	OFF
Input 1	OFF
Input 2	ON
Input 3	-

When Input 2 is turned ON, the rod moves to the intermediate position at the specified speed.



#### Input Signals

Input 0	OFF
Input 1	ON
Input 2	OFF
Input 3	-

When Input 1 is turned ON, the rod moves to the end position at the specified speed.

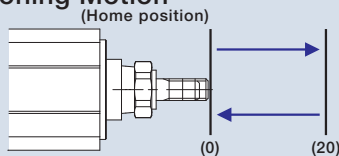
### PIO Pattern 5 (Continuous Cycle Operation)

This PIO pattern involves continuous cycling between 2 positions—the end and home positions.

When Input 0 (continuous operation signal) is turned ON, the rod continuously moves between the specified 2 positions.

If Input 0 is turned OFF while in motion, it stops after reaching the current destination.

#### Positioning Motion



#### Input Signals

Input 0	ON
Input 1	-
Input 2	-
Input 3	-

When Input 0 is turned ON, the rod moves continuously between the end and home positions at the specified speed.

- Slider Type
- Mini
- Standard
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- XSEL
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- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor



## I/O Signal

Pin No.	Cable color	PIO pattern		0		1		2		3		4		5	
		PIO pattern name		Standard 2-position motion		Speed change		Position change		2-input 3-position travel		3-input 3-position travel		Continuous cycle operation	
		Solenoid type		Single	Double	Single	Double	Single	Double	Single	Double	-		-	
1	Brown	COM		24V		24V		24V		24V		24V		24V	
2	Red	COM		0V		0V		0V		0V		0V		0V	
3	Orange	Input	0	ST0	ST0	ST0	ST0	ST0	ST0	ST0	ST0	ST0	ST0	ASTR	
4	Yellow		1	*STP	ST1(-)	*STP	ST1(-)	*STP	ST1(-)	ST1	ST1	ST1	ST1	-/*STP	
5	Green		2	-(RES)		SPDC(RES)		CN1(RES)		-(RES)		ST2(RES)		-(RES)	
6	Blue		3	-/SON		-/SON		-/SON		-/SON		-/SON		-/SON	
7	Purple	Output	0	LS0/PE0		LS0/PE0		LS0/PE0		LS0/PE0		LS0/PE0		LS0/PE0	
8	Grey		1	LS1/PE1		LS1/PE1		LS1/PE1		LS1/PE1		LS1/PE1		LS1/PE1	
9	White		2	HEND/SV		HEND/SV		HEND/SV		LS2/PE2		LS2/PE2		HEND/SV	
10	Black		3	*ALM/SV		*ALM/SV		*ALM/SV		*ALM/SV		*ALM/SV		*ALM/SV	

Note: The above signals with asterisks (\*) are normally ON, and OFF during operation.

## Specification Table

Item	Type							
	PSEP				ASEP			
Controller type	C		CW		C		CW	
Connected actuators	RCP2/RCP3 series actuator				RCA/RCA2/RCL series actuator			
Number of control axes	1							
Operating method	Positioner Type							
Number of positions	2 positions/3 positions (4 positions*2)							
Backup memory	EEPROM							
I/O connector	10 pin connector							
Number of I/O points	4 input points / 4 output points							
I/O power supply	External power supply DC24V±10%							
Dedicated type for serial communication	RS485 1ch							
Communication cable for peripheral equipment	CB-APSEP-PIO□□□		CB-APSEP-PIO□□□		CB-APSEP-PIO□□□		CB-APSEP-PIO□□□	
Position detection method	Incremental encoder (Attaching an absolute battery unit makes the simple absolute specification possible *3)							
Motor-encoder cable	For RCP2 connection		CB-PSEP-MPA□□□				(Connection not possible)	
	For RCA connection		(Connection not possible)				CB-ASEP-MPA□□□	
	For RCP3/RCA2 connection		CB-APSEP-MPA□□□					
	For RCP2 mini rotary connection		CB-RPSEP-MPA□□□				(Connection not possible)	
Input voltage	DC24V±10%							
Controlled power supply capacity	0.5A (0.8A for the simple absolute specification)							
Motor power capacity	Motor size	Rated value	Max.( <sup>*4</sup> )	Motor power output	Rated value	Maximum		
	20P	0.4A	2.0A	2W	0.8A	Power-saving ( <sup>*5</sup> )	Standard ( <sup>*6</sup> ) high-acceleration / deceleration	
	28P	0.4A	2.0A	5W	1.0A	Not specified	4.6A	
	35P	1.2A	2.0A	10W (for RCL)	1.3A	Not specified	6.4A	
	42P	1.2A	2.0A	10W (for RCA/RCA2)	1.3A	2.5A	4.4A	
	56P	1.2A	2.0A	20W	1.3A	2.5A	4.4A	
	-	-	-	20W (for 20S motor)	1.7A	3.4A	5.1A	
-	-	-	30W	1.3A	2.2A	4.4A		
Inrush current ( <sup>*1</sup> )	Max. 10A							
Amount of heat generated	8.4W				9.6W			
Dielectric strength voltage	DC500V 1MΩ							
Resistance to vibration	XYZ directions	10~57Hz	One-side width 0.035mm (continuous), 0.075mm (intermittent)					
		58~150Hz	4.9m/s <sup>2</sup> (continuous), 9.8m/s <sup>2</sup> (intermittent)					
Ambient operating temperature	0~40°C							
Ambient operating humidity	10~85%RH (non-condensing)							
Ambient operating environment	No corrosive gases							
Protection level	IP20		IP53 ( <sup>*7</sup> )		IP20		IP53 ( <sup>*7</sup> )	
Weight	About 130g		About 160g		About 130g		About 160g	

(\*1) Upon power-ON, an electrical current of 5 to 12 times as much as the rated current, called "in rush current" flows for 1 to 2 ms. Note that the amount of inrush current varies based on the impedance of power source lines.

(\*2) This applies to the case where two position data points are set at each of the end and home positions during a "position change" motion pattern process.

(\*3) The simple absolute type controllers cannot be used for the linear servo type.

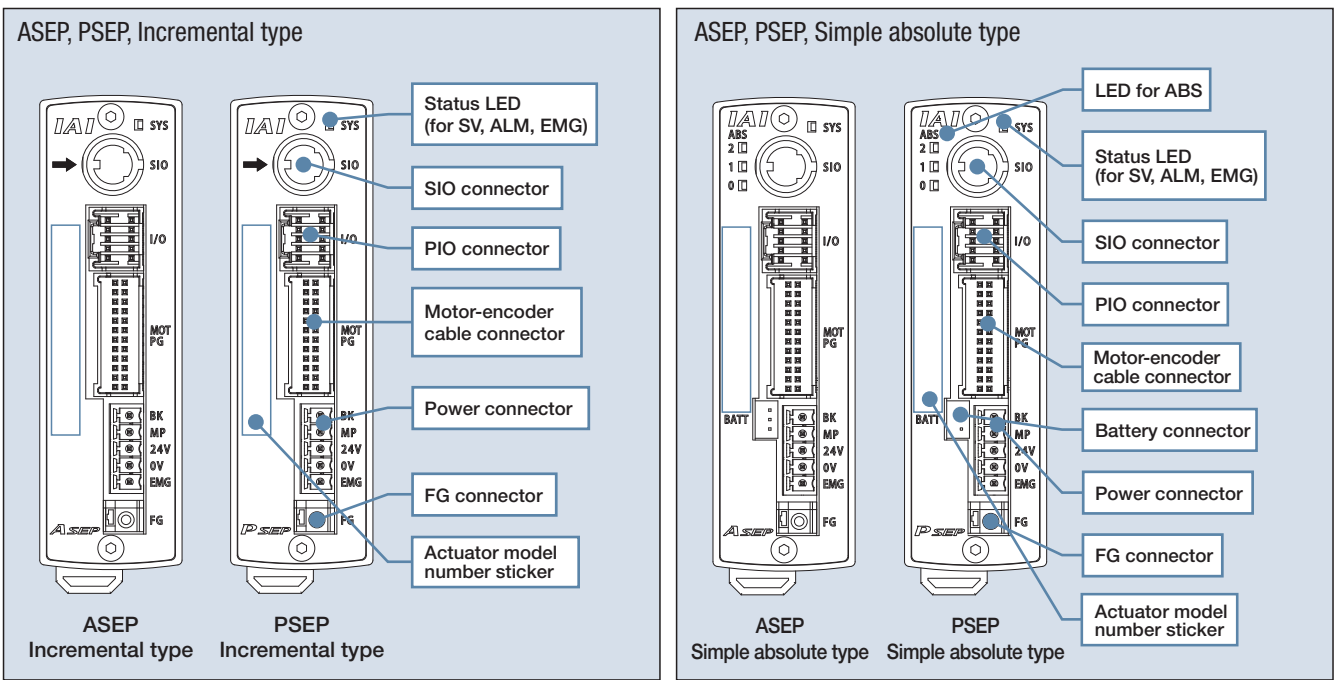
(\*4) The current reaches its maximum level during the servo motor excitation phase detection performed during the initial servo ON process after the power has been turned on. (Usually: Approx. 1 to 2 seconds, max. 10 seconds.)

(\*5) When power to the motor is turned ON after shutting it OFF, current of about 6.0 A flows (for approx.1~2ms).

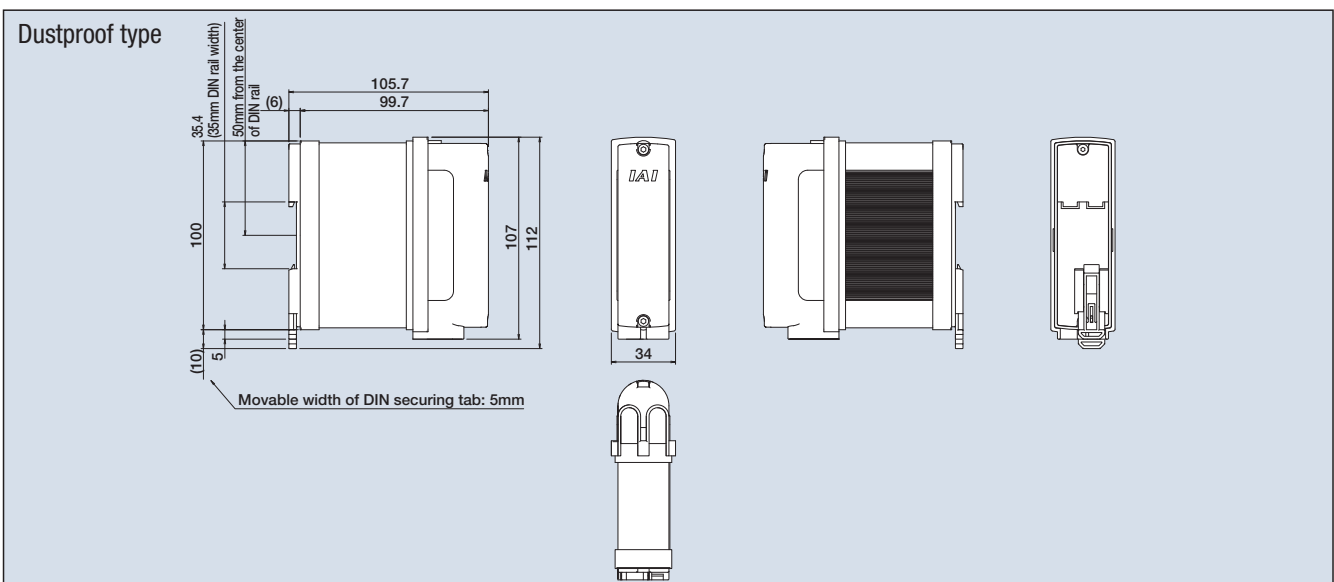
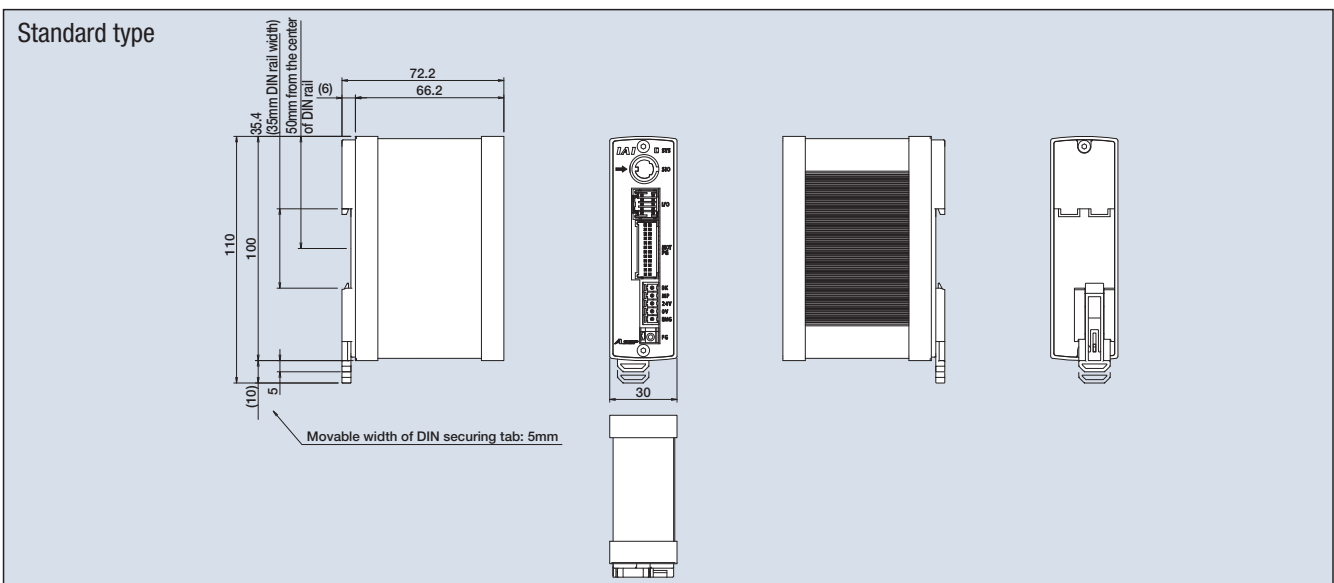
(\*6) The max. value of current can be detected in the magnetic pole detection process or during collision or constraint. The condition continues for up to 10 seconds in the magnetic pole detection process. In this process the above current is required.

(\*7) The bottom surface is excluded.

Names



Outer dimensions



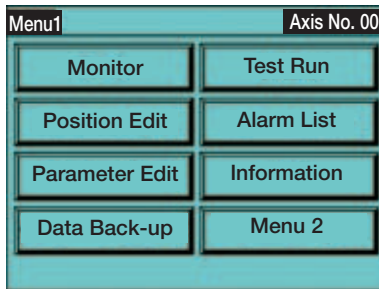
- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor

Option

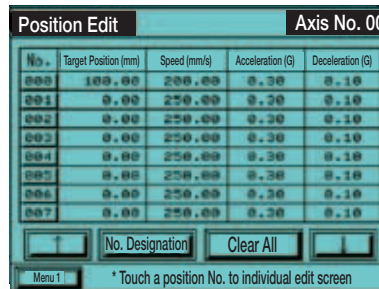


### Touch Panel Teaching Pendant for Position Controller

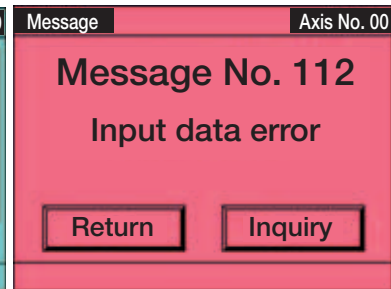
- Feature 1** A data input device with an intuitive touch panel menu screen that is easy to operate, even for first-time users. You can use it to configure settings such as home / end positions, intermediate position, speed, and pushing force, or to run an adjustment operation such as jogging, inching, and moving to a specified position.
- Feature 2** Intuitive and interactive touch panel menus allow for easy configuration, even for first-time users.



Large, easy to read display



Easy configuration with the touch panel



Backlight color changes when an error occurs

### Model & Specifications

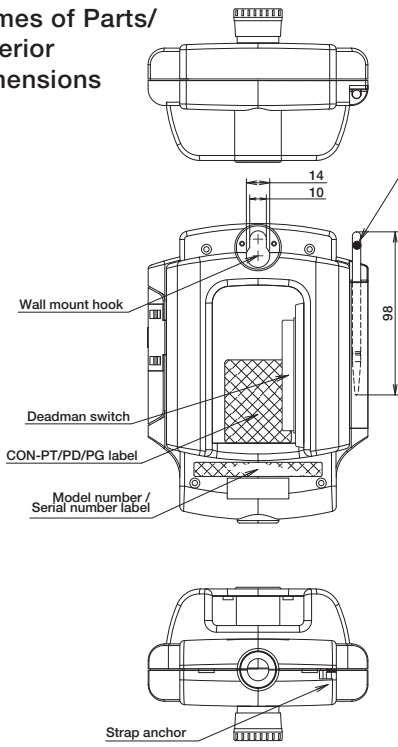
Item	Description		
Model	CON-PT-M-ENG	CON-PD-M-ENG	CON-PG-M-S-ENG
Type	Standard type	Deadman switch type	Safety compliant type
Connectible controllers	PSEP/PCON/RPCON ASEP/ACON/RACON SCON/ERC2 (*)		
3-position deadman switch	-	○	○
Functions	Input and edit position data Movement functions (move to specified position, jog, inch) Test input and output signals Edit parameters		
Display	3-color LED with backlight		
Operating ambient temp./Humidity	0~50°C 20~85% RH (non-condensing)		
Environmental resistance	IP40		
Weight (incl. 5m cable)	Approx. 750g	Approx. 780g	Approx. 780g
Accessories	• Touch pen	• Touch pen	• TP Adapter (Model: RCB-LB-TG) • Dummy Plug (Model: DP-4) • Controller connection cable (Model: CB-CON-LB005) • Touch pen

(\*) If an ERC2 type controller does not have "4904" on the serial number label, it cannot be connected.

**Caution:** If you have a "CON" type controller (i.e. PCON, RPCON, ACON, RACON, SCON, ERC2) and an "SEP" type controller (PSEP or ASEP) linked together, you cannot connect the teaching pendant to it.

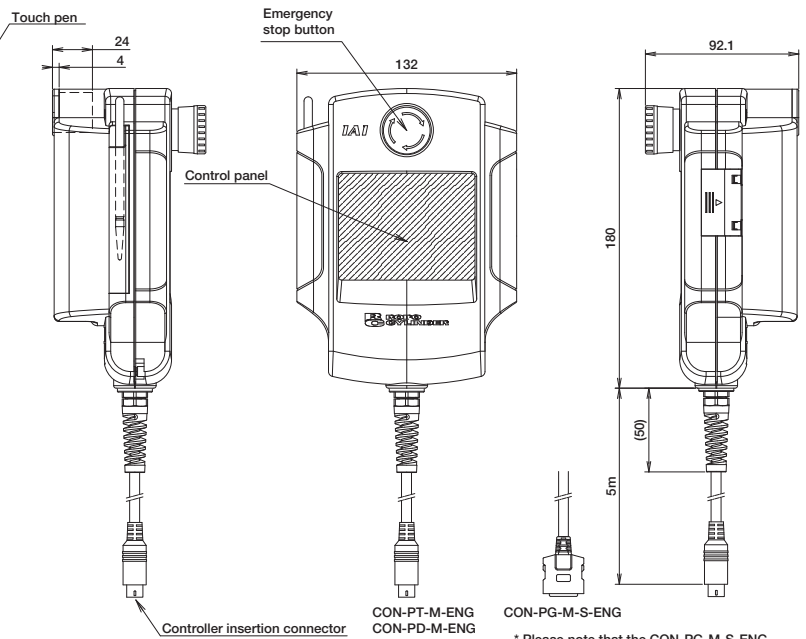
Absolute battery unit for SEP controllers

Names of Parts/ Exterior Dimensions



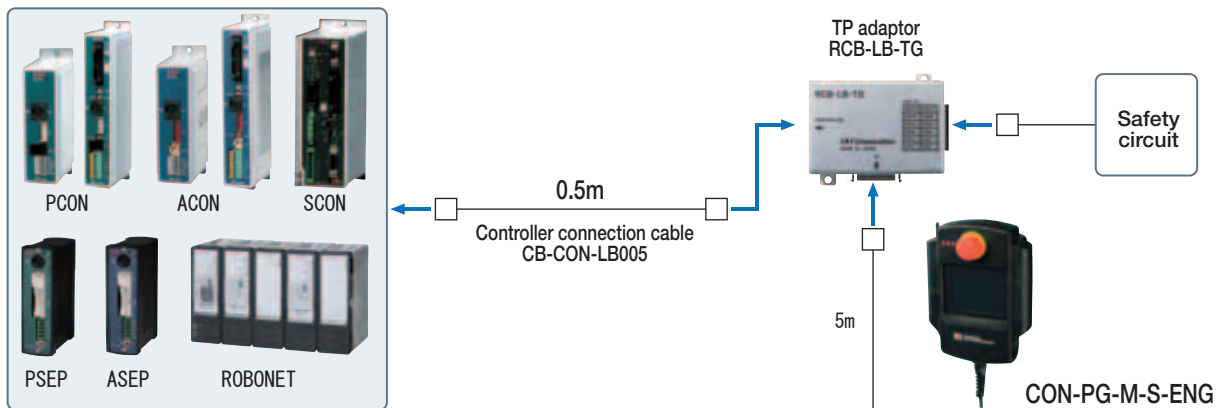
Option

- Strap Model STR-1



\* Please note that the CON-PG-M-S-ENG has a controller insertion connector that is different from the other models.

CON-PG-M-S-ENG Wiring Drawing



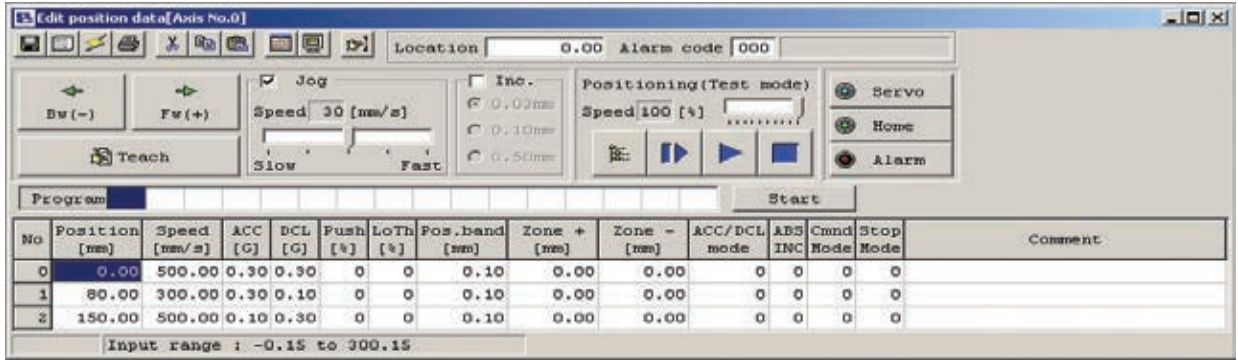
- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL

- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor

## Option

### PC Software (Windows Only)

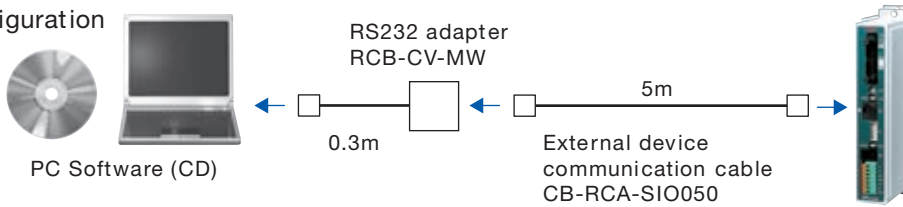
- **Features** A startup support software for inputting positions, performing test runs, and monitoring. With enhancements for adjustment functions, the startup time is shortened.



- **Model RCM-101-MW-ENG**  
(External device communication cable + RS232 conversion unit)



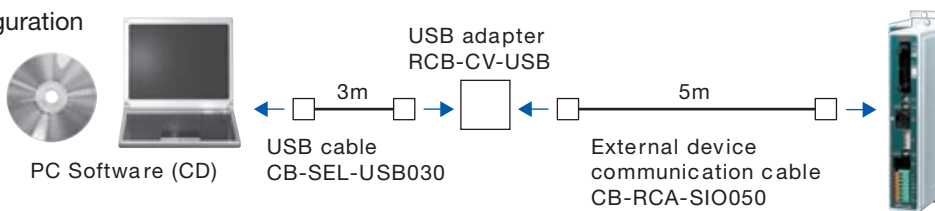
#### Configuration



- **Model RCM-101-USB-ENG**  
(External device communication cable + USB adapter + USB cable)



#### Configuration



Absolute battery unit for SEP controllers

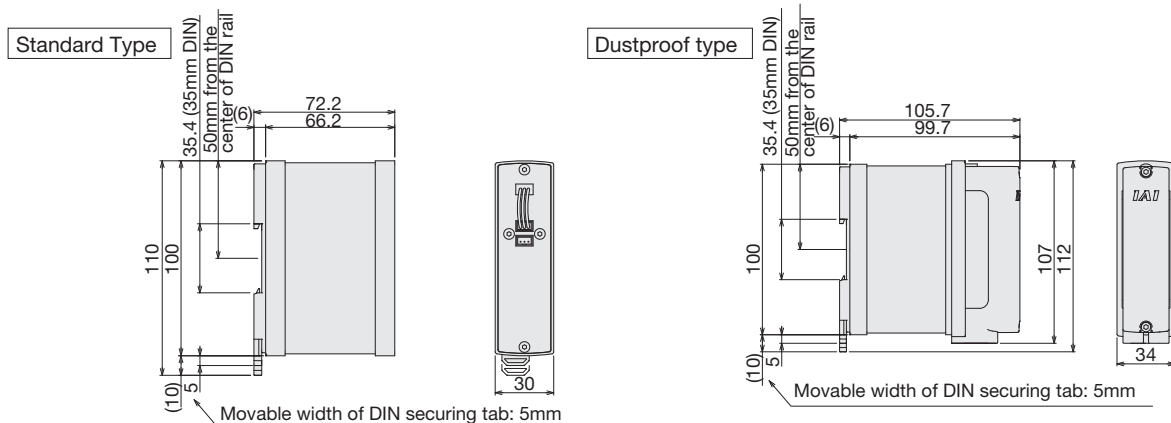
**Description** Supplied with the PSEP and ASEP simple absolute controllers.  
This is a battery unit used for backing up the current position data.

**Model** **SEP-ABUM (standard type)**  
**SEP-ABUM-W (dustproof type)**

**Specifications**

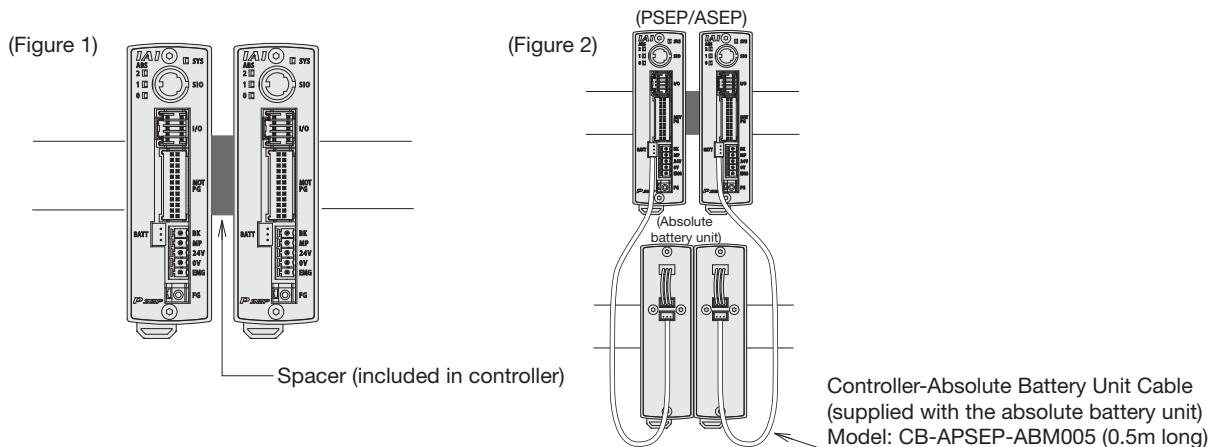
Item	Specifications			
Ambient operating temp./Humidity	0~40°C (around 20°C preferred), 95% RH or below (non-condensing)			
Ambient operating environment	No corrosive gases			
Absolute battery (*1)	Model: AB-7 (Ni-MH battery/Approx. 3-year life)			
Controller-absolute battery unit cable (*1)	Model: CB-APSEP-ABM005 (0.5m long)			
Weight	Standard type: Approx. 230g; Dustproof type: Approx. 260g			
Allowable encoder RPM during data retention (*2)	800rpm	400rpm	200rpm	100rpm
Position data retention duration (*2)	120h	240h	360h	480h

(\*1) The absolute battery unit comes with a cable to connect the controller and the absolute battery unit.  
(\*2) Position data retention time changes with the allowable encoder RPMs during data retention.  
(800rpm→120h, 400rpm→240h, 200rpm→360h, 100rpm→480h)



**Cautions on Controllers and Options**

- When mounting the controller to a DIN rail, use the supplied spacer between the controllers to prevent them from contacting each other, to deal with heat dissipation. (See Fig. 1)
  - When mounting the absolute battery units and controllers, place the absolute battery units below the controllers. (See Fig. 2)
- If there is not enough space below the controllers, mount the absolute battery units in such a way that the temperature around the absolute battery unit stays at 40°C or below.



- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor



## Spare parts

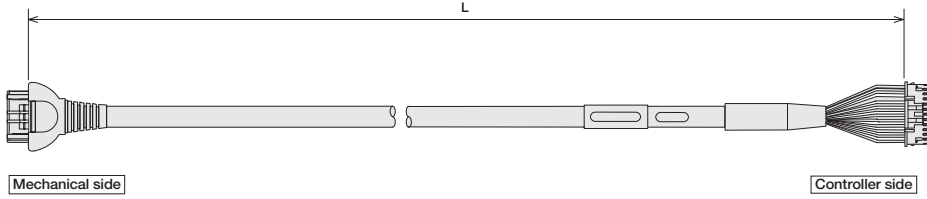
When you need spare parts after purchasing the product, such as when replacing a cable, refer to the list of models below.

### Motor/P3-A3-encoder integrated cable for connecting [RCP3/RCP2 (for specific models\*)/RCA2/RCL] and [PSEP/ASEP]

Model **CB-APSEP-MPA**

\* Enter the cable length (L) into    . Compatible to a maximum of 20 meters.  
Ex. 080 = 8m

\* For RCP2-GRSS/GRLS/GRST/GRHM/GRHB/SRA4R/SRGS4R/SRGD4R



Mechanical side

Controller side

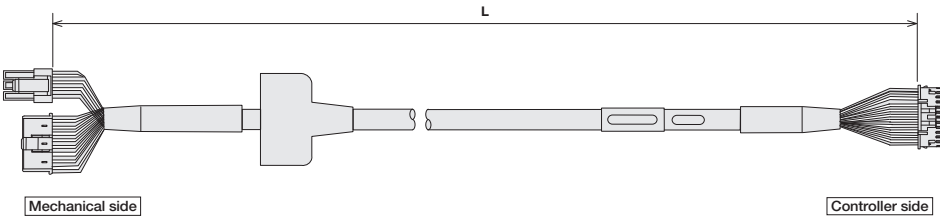
Min. bend radius r = 68 mm or larger (when movable type is used)

Mechanical side Pin number	[PCON] (ACON)	Controller side Pin number
A1	Black (ΦA)(U)	1
B1	White [VMM](V)	2
A2	Brown (Φ/A)(W)	3
B2	Green (ΦB)(-)	4
A3	Yellow [VMM](-)	5
B3	Red (Φ/B)(-)	6
A4	Orange (LS+)(BK+)	7
B4	Gray (LS-)(BK-)	8
A5	White (-)(A+)	9
B5	Yellow (-)(A-)	10
A7	Red (A+)(B+)	13
B7	Green (A-)(B-)	14
A8	Black (B+)(Z+)	15
B8	Brown (B-)(Z-)	16
A5	Black (label) (BK+)(LS+)	9
B5	Brown (label) (BK-)(LS-)	10
A9	Green (label) (GNDLS)(GNDLS)	20
B9	Red (label) (VPS)(VPS)	18
A10	White (label) (VCC)(VCC)	17
B10	Yellow (label) (GND)(GND)	19
A11	NC	21
B11	Shield (FG)(FG)	24
	NC	22
	NC	23

### Motor/P3-encoder cable for connecting [RCP2] and [PSEP]

Model **CB-PSEP-MPA**

\* Enter the cable length (L) into    . Compatible to a maximum of 20 meters.  
Ex. 080 = 8m



Mechanical side

Controller side

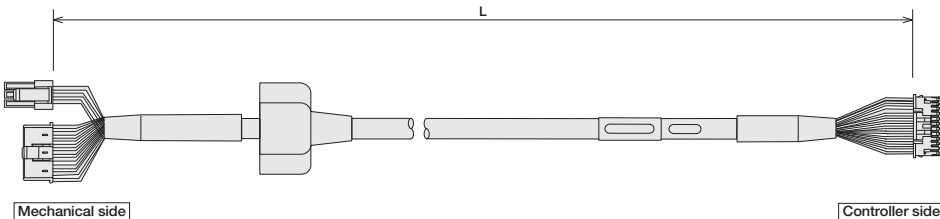
Min. bend radius r = 68 mm or larger (when movable type is used)

Mechanical side Pin number		Controller side Pin number
1	Black (ΦA)	2
2	White [VMM]	3
4	Red (ΦB)	4
5	Green [VMM]	5
3	Brown (Φ/A)	6
6	Yellow (Φ/B)	9
16	Orange [BK+]	10
17	Gray [BK-]	11
5	NC	12
6	NC	7
13	Black [LS+]	8
14	Brown [LS-]	13
1	White [A+]	14
2	Yellow [A-]	15
3	Red [B+]	16
4	Green [B-]	17
10	White (label) [VCC]	18
11	Yellow (label) [VPS]	19
9	Red (label) [GND]	20
12	Green (label) [spare]	21
15	NC	22
7	NC	23
8	NC	24
18	Shield [FG]	

### Motor/A3-encoder cable for connecting [RCA] and [ASEP]

Model **CB-ASEP-MPA**

\* Enter the cable length (L) into    . Compatible to a maximum of 20 meters.  
Ex. 080 = 8m



Mechanical side

Controller side

Min. bend radius r = 68 mm or larger (when movable type is used)

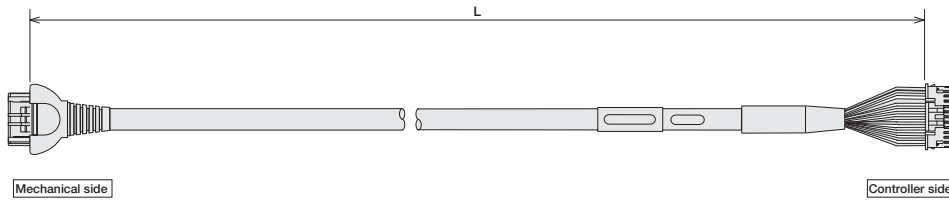
Mechanical side Pin number		Controller side Pin number
1	Red [U]	1
2	Yellow [V]	2
	NC	3
3	Black [W]	4
	NC	5
	NC	6
18	Orange [BK+]	7
17	Gray [BK-]	8
7	Black [LS+]	9
16	Brown [LS-]	10
1	White [A+]	11
2	Yellow [A-]	12
3	Red [B+]	13
4	Green [B-]	14
10	Black (label) [Z+]	15
11	Brown (label) [Z-]	16
14	White (label) [VCC]	17
9	Yellow (label) [VPS]	18
13	Red (label) [GND]	19
15	Green (label) [spare]	20
6	NC	21
5	NC	22
8	NC	23
12	NC	24
9	Shield [FG]	



Motor/P3-encoder cable for connecting [RCP2 mini rotary] and [PSEP]

Model **CB-RPSEP-MPA**

\* Enter the cable length (L) into    . Compatible to a maximum of 20 meters.  
Ex. 080 = 8m



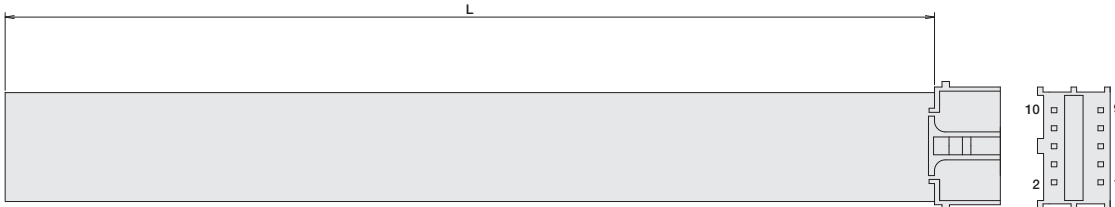
Min. bend radius r = 68 mm or larger (when movable type is used)

Mechanical side Pin number		Controller side Pin number
A1	Black (0A)	1
B1	White (VMM)	2
A2	Brown (0/A)	5
B2	Green (0/B)	3
A3	Yellow (VMM)	4
B3	Red (0/B)	6
A6	Orange (LS-)	7
B6	Gray (LS-)	8
A7	Red (A+)	13
B7	Green (A-)	14
A8	Black (A+)	15
B8	Brown (B-)	16
A4	NC	7
B4	NC	8
A5	Black (label) [BK-]	9
B5	Brown (label) [BK-]	10
A9	Green (label) [GNDLS]	19
B9	Red (label) [VPS]	18
A10	White (label) [VCC]	17
B10	Yellow (label) [GND]	19
A11	NC	21
B11	Shield (FG) (FG)	24
	NC	22
	NC	23

I/O cable for PSEP-C/ASEP-C

Model **CB-APSEP-PIO**

\* Enter the cable length (L) into    . Compatible to a maximum of 10 meters.  
Ex. 080 = 8m

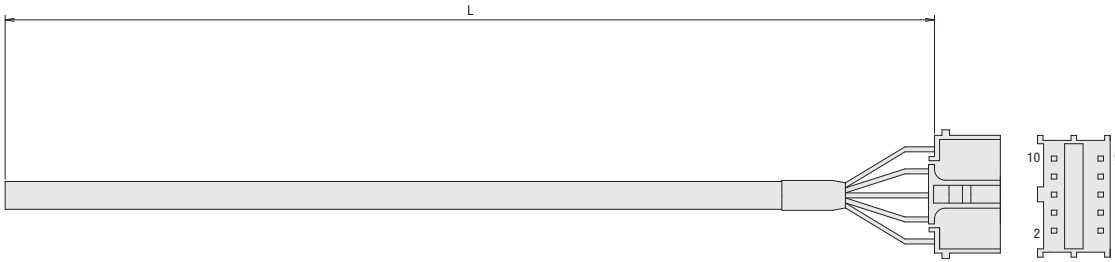


51353-1000 (MOLEX)			
No.	Signal	Color	Wire
1	24V	Brown	Flat cable (crimped)
2	0V	Red	
3	IN0	Orange	
4	IN1	Yellow	
5	IN2	Green	
6	IN3	Blue	
7	OUT0	Purple	
8	OUT1	Gray	
9	OUT2	White	
10	OUT3	Black	

I/O cable for PSEP-CW/ASEP-CW

Model **CB-APSEPW-PIO**

\* Enter the cable length (L) into    . Compatible to a maximum of 10 meters.  
Ex. 080 = 8m



51353-1000 (MOLEX)			
No.	Signal	Color	Wire
1	24V	Brown	Cable (crimped)
2	0V	Brown-White	
3	IN0	Red	
4	IN1	Red-White	
5	IN2	Yellow	
6	IN3	Yellow-White	
7	OUT0	Green	
8	OUT1	Green-White	
9	OUT2	Black	
10	OUT3	Black-White	

- Slider Type
- Mini
- Standard
- Controllers Integrated
- Rod Type
- Mini
- Standard
- Controllers Integrated
- Table/Arm /Flat Type
- Mini
- Standard
- Gripper/ Rotary Type
- Linear Motor Type
- Cleanroom Type
- Splash-Proof
- Controllers
- PMEC /AMEC
- PSEP /ASEP
- ROBO NET
- ERC2
- PCON
- ACON
- SCON
- PSEL
- ASEL
- SSEL
- XSEL
- Pulse Motor
- Servo Motor (24V)
- Servo Motor (230V)
- Linear Motor