

# SYSMAC CS-series MECHATROLINK-II-compatible Motion Control Unit

# CS1W-MCH71

CSM\_CS1W-MCH71\_DS\_E\_3\_1

## Improve Equipment Design Efficiency and Shorten Tact Time

- Control Servos for up to 16 axes in a motion network with one Position Control Unit that supports MECHATROLINK-II \*.

\* MECHATROLINK-II is a registered trademark of the MECHATROLINK Members Association.

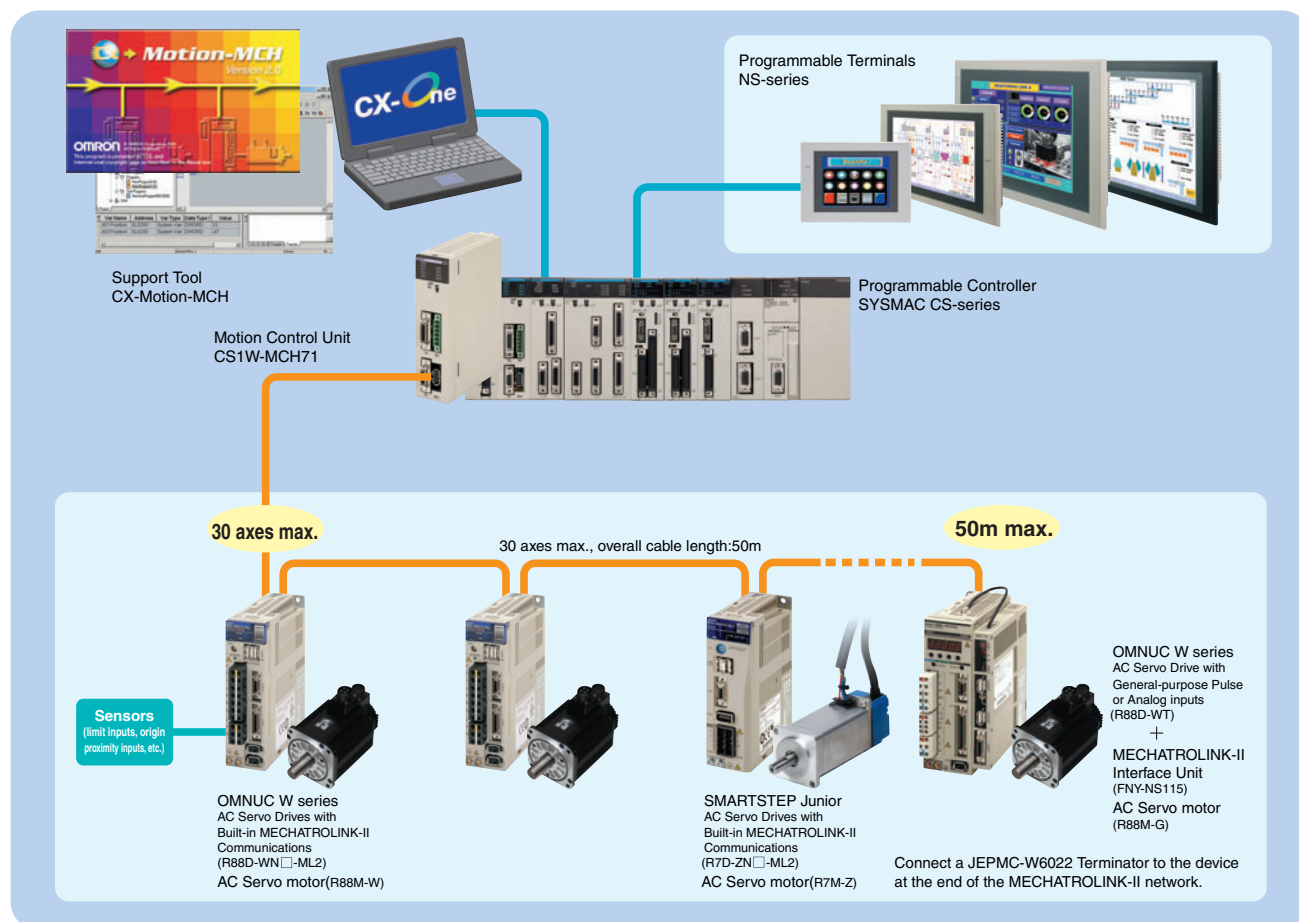


CS1W-MCH71

## Features

- High-precision motion control with less wiring using MECHATROLINK-II Servo communications with superior concurrency.
- Many synchronization and axis control commands are supported to aid existing synchronized control applications and improve motion control tact time.
- Program control commands (such as branching commands) and various arithmetic operations are supported for maximum motion programming efficiency.

## System Configuration




**Note:** OMNUC G5 series and G series cannot be connected with CS1W-MCH71.

## Ordering Information

### International Standards

- The standards are abbreviated as follows: U: UL, U1: UL(Class I Division 2 Products for Hazardous Locations), C: CSA, UC: cULus, UC1: cULus (Class I Division 2 Products for Hazardous Locations), CU: cUL, N: NK, L: Lloyd, and CE: EC Directives.
- Contact your OMRON representative for further details and applicable conditions for these standards.

### CS-series

Unit type	Product Name	Specifications	No. of unit numbers allocated	Current consumption (A)		Model	Standards
				5 V system	26 V system		
CS1 CPU Bus Unit	<b>MECHATROLINK-II-compatible Motion Control Unit</b> 	Control modes: Position, speed, or torque control via MECHSTROLINK-II Control axes: 32 axes max. (30 physical axes, 2 virtual axes) Internal programming language: Special motion control language	1	0.80	—	CS1W-MCH71	UC1, CE

### Support Software

Product name	Specifications	Number of licenses	Media	Model	Standards
<b>FA Integrated Tool Package CX-One Ver. 4.□</b>	The CX-One is a comprehensive software package that integrates Support Software for OMRON PLCs and components. CX-One runs on the following OS. OS: Windows XP (Service Pack 3 or higher), Vista or 7 <b>Note:</b> Except for Windows XP 64-bit version CX-One Ver. 4.□ includes CX-Motion-MCH Ver. 2.□. For details, refer to the CX-One catalog (Cat. No. R134).	1 license *1	DVD *2	CXONE-AL01D-V4	—
<b>CAM Data Creation Tool</b>	Windows 98SE/Me/NT4.0 (Service Pack 6a)/ 2000 (Service Pack 3a or higher), or XP	1 licence	CD	WS02-MOPC2	—

\*1. Multi licenses are available for the CX-One (3, 10, 30, or 50 licenses).

\*2. The CX-One is also available on CD (CXONE-AL□□C-V4).

### MECHATROLINK-related Devices and Cables (Manufactured by Yaskawa Corporation)

Name		OMRON model number	Yaskawa model number
MECHATROLINK-II Interface Unit	For W-series Servo Driver	FNY-NS115	JUSP-NS115
24-VDC I/O Module	Input : 64 Output : 64	FNY-IO2310	JEPMC-IO2310
Counter Module	Reversing Counter 2CH	FNY-PL2900	JEPMC-PL2900
Pulse Output Module	Pulse Positioning 2CH	FNY-PL2910	JEPMC-PL2910
MECHATROLINK-II Cables (with ring core and USB connector on both ends)	0.5 m	FNY-W6003-A5	JEPMC-W6003-A5
	1.0 m	FNY-W6003-01	JEPMC-W6003-01
	3.0 m	FNY-W6003-03	JEPMC-W6003-03
	5.0 m	FNY-W6003-05	JEPMC-W6003-05
	10.0 m	FNY-W6003-10	JEPMC-W6003-10
	20.0 m	FNY-W6003-20	JEPMC-W6003-20
	30.0 m	FNY-W6003-30	JEPMC-W6003-30
MECHATROLINK-II Terminating Resistor	Terminating resistance	FNY-W6022	JEPMC-W6022
MECHATROLINK-II Repeater	Communications Repeater	FNY-REP2000	JEPMC-REP2000

**Note:** MECHATROLINK-related Devices and Cables are manufactured by Yaskawa Corporation, but they can be ordered directly from OMRON using the OMRON model numbers. (Yaskawa-brand products will be delivered even when they are ordered from OMRON.)

### Accessories

None

## Mountable Racks

Model	CS1 system			CS1D system	
	CPU Rack	Expansion Backplane	Long-distance Expansion Racks	CPU Rack	Expansion Backplane
CS1W-MCH71	16 Units max. Per CPU Unit ( 9 Units per CPU Rack 10 Units per Expansion Backplane )			16 Units max. Per CPU Unit ( 9 Units per CPU Rack 10 Units per Expansion Backplane )	

## Specifications

### General Specifications

Item	Specifications
Model	CS1W-MCH71
Power supply voltage	5 VDC (from Backplane) 24 VDC (from external power supply)
Voltage fluctuation tolerance	4.75 to 5.25 VDC (from Backplane) 21.6 to 26.4 VDC (from external power supply)
Internal current consumption	5 VDC 0.8 A max.
Weight (Connectors excluded)	300 g max.
Safety standards	UL, CSA, C-TICK, and EC Directives.
Dimensions (mm)	130 (H) × 35 (W) × 100.5 (D) (single)
Altitude	At 2,000 m elevation or lower.

Specifications other than those shown above conform to the general specifications for the SYSMAC CS series.

### Functions and Performance Specifications

Item	Specifications
Applicable PLC	CS-series PLCs with CPU Units with lot number 030418 or later
Type of Unit	CPU Bus Unit
Mounting	CPU unit or expansion rack
Number of Units	One slot
Method for data transfer with CPU Unit	CIO Area for CPU Bus Unit
	Occupies the area for 1 unit (25 words) For units and tasks: 11 to 25 words (Depending on the number of motion tasks)
	DM Area for CPU Bus Unit
	Occupies the area for 1 unit (100 words) For units and tasks: 32 to 74 words (Depending on the number of motion tasks)
	Custom Bit Area
	For axes: 0-64 words (Depending on the greatest number of the axis used)
	Custom Data Area
	For axes: 0-128 words (Depending on the greatest number of the axis used)
	Custom Data Area
	For General I/O: 0-1280 words (Depending on setting)
Controlled Devices	MECHATROLINK-II below supported <ul style="list-style-type: none"> <li>W-series Servo Driver with built-in communications functions</li> <li>W-series Servo Driver (OMRON) + Communications I/F Unit (YASKAWA)</li> <li>Various I/O units (YASKAWA)</li> <li>SMARTSTEP Junior Servo Drive</li> </ul> Up to 30 nodes * When MECHATROLINK-II devices are connected up to 16 nodes (within 30 m) or 15 nodes (within 50m), a repeater unit is not required. A repeater unit is required to connect MECHATROLINK-II devices more than the cases described above.
Built-in program language	Dedicated motion control language
Control	Control method
	MECHATROLINK-II <ul style="list-style-type: none"> <li>Position commands, Speed commands, Torque commands</li> </ul>
	Number of controlled axes
	32 axes max. Physical axes/Virtual axes: 30 axes max. (Either can be selected for each axis) Dedicated for virtual axes: 2 axes
Operating modes	RUN mode, CPU mode, Tool mode/System (Depending on the tool)
Automatic/Manual Mode	Automatic mode: Executing built-in programs of MC Unit controls motion. Manual mode: Executing commands from CPU Unit (PC interface area) controls motion. <b>Note:</b> The Automatic or Manual Mode is set according to the PC Interface area of the CPU Unit.
Control unit	Minimum setting unit
	1, 0.1, 0.01, 0.001, 0.0001
	Units
	mm, inch, deg, pulse
Maximum position command value	-2147483647 to 2147483647 pulses (signed 32-bit) Mode for unlimited axes feeding is possible. Example: With 16-bit encoder (65536 pulse/rev), Minimum setting unit: 0.001 mm, 10 mm/rev, the position command value range will be from -327679999 to 327679999 command units.
Control operations based on commands from the CPU Unit	Servo lock/unlock
	Executes Servo driver lock or unlock
	Jogging
	Executes continuous feeding independently for each axis, by means of speed set in system parameter x override.
	STEP operation
	Feeds a specified distance for a specified axis.
	Origin search
	Defines the machines origin according to the search method set in the system parameters.
	Forced origin
	Forcibly sets the present position to 0 to establish it as the origin.
	Absolute origin setting
	Sets the origin when an absolute encoder is used. Offset value: Signed 32-bit (pulses)
	Error counter reset
	Forcibly resets the error counter to 0.
	Present position pre-set
	Sets the present position to a user-specified value.
	Machine lock
	Prohibits the output of motion commands to the axes.
	Single block
	Executes the motion program one block at a time.
	Auto/manual change
	Switches between auto mode and manual mode.

Item		Specifications
Control Operations according to motion program	Positioning (PTP)	Executes positioning independently for each axis at the speed set in the system parameters. Simultaneous specification: 8 axes max. /block Simultaneous execution: 32 blocks max. /unit
	Linear interpolation	Executes linear interpolation for up to 8 axes simultaneously at the specified interpolation speed. Simultaneous specification: 8 axes max. /block Simultaneous execution: 32 blocks max. /system
	Circular interpolation	Executes clockwise or counterclockwise circular interpolation for two axes at their specified interpolation speed. Simultaneous specification: 2 or 3 axes/block Simultaneous execution: 16 blocks max. /system
	Origin search	Defines the machine origin according to the search method set in the system parameters. An offset can be specified for the position after the origin search. The absolute encoder can also execute origin search.
	Interrupt feeding	By means of inputs to the servo driver, moves a specified axis for a specified travel distance to perform positioning.
	Time-specified Positioning	Executes positioning with time specified.
	Traverse function	Performs winding operation (traverse control) with two specified axes.
	Electronic Cam, Single Axis	Execute cam operation according to the specified cam table data with reference to elapse of time.
	Synchronous Electronic cam	Executes cam operation according to the specified cam table data with reference to the position of the specified axis.
	Link operation	Executes link operation according to set conditions with reference to the position of the specified axis.
	Electronic Shaft	Executes synchronous operation at a speed calculated with the speed of the specified axis and gear ratio.
	Trailing synchronous operation	Executes trailing + synchronous operations with reference to the position of the specified axis.
	Speed command	Outputs speed commands to the specified axis.
	Torque command	Outputs torque commands to the specified axis.
Acceleration/deceleration curve		Trapezoidal or S-shape
Acceleration/deceleration time	Acceleration/deceleration time	60000 ms max.
	S-shape time constant	30000 ms max.
External I/O	For high-speed servo communication bus	One port for MECHATROLINK-II
	Servo encoder	Incremental rotary encoder Absolute rotary encoder (Unlimited length ABS supported with some conditions)
	I/O	Deceleration stop input (or servo-OFF stop): 1 pt General input: 2 pts General output: 2 pts
	External power supply for I/O	24 V
Feed rate	Rapid feed rate	1 to 2147483647 [Command unit/min]
	Interpolation feed rate	1 to 2147483647 [Command unit/min]
	Override	Changes the operation speed by applying a given factor to the speed specified by the system parameters or the motion program. 0.00 to 327.67% (Setting unit: 0.01%, can be specified for each axis or task)
	Internal override (supported for unit version 3.1 and later)	The feed rate of the following commands can be set by the motion program. Command    Rate to which override is applied MOVE        Rapid feed rate DATUM       Origin return feed rate MOVEI       Rapid feed rate, external positioning rate MOVET       Rapid feed rate The actual feed rate is calculated using the following formula. Actual feed rate = Axis feed rate × (Axis override + Internal override)
Axis control	Backlash compensation	Compensates mechanical backlash (the mechanical play between driving and driven axes) with a value registered in advance. This function uses a parameter in the servo driver.
	In-position	This function is used whether a positioning is completed or not. This function uses a parameter in the servo driver.
	Position loop gain	This is the position loop gain of the servo driver. This function uses a parameter in the servo driver.
	Feed forward gain	The command values created in the MC Unit are multiplied by this feed forward gain. This function uses a parameter in the Servo Driver.

Item		Specifications
Program	Number of tasks	Motion task: 8 tasks max.
	Parallel branching in task	Motion task: 8 branches max.
	Number of programs	256 programs max. /unit The program Nos. used for programs are from 0000 to 0999.
	Program numbers	0000 to 0499: Main programs for motion tasks 0500 to 0999: Sub-programs for motion tasks
	Program capacity	2 Mbytes 8000 blocks max. /unit by motion program conversion.
	Number of blocks	800 blocks/program
	Position data capacity	10240 points/unit
	Sub-program nesting	5 levels max.
	Start	Starts program operation from program (of another task)
	Start mode	Motion task: Initial, continue, next
	Deceleration stop	Motion task: Executes deceleration stop regardless of block
	Block stop	Motion task: Executes deceleration stop at the end of the block currently being executed.
	Single-block mode	Motion task: the program is executed one block at a time.
	Breakpoints (supported for unit version 3.0 and later.)	Breakpoints can be set for any block using the Support Tool. When a breakpoint is set for a block, program execution will stop after that block has been executed.
Saving program data	MC Unit	Flash memory backup
Zones (supported for unit version 3.0 and later.)		The zone bit turns ON when any variable (including feedback present position, feedback speed, etc.) is within the set range, and OFF when outside of the set range. A maximum of 32 zones can be set.
Data tracing (supported for unit version 3.0 and later.)		A maximum of two groups can be simultaneously traced, with 1 to 16 data items in each group. <b>Note:</b> The items that can be traced are bits and data. These are each handled as a single item. The number of data samples that can be collected is 2,048 samples when 16 items are set for tracing to 32,768 when only 1 item is set for tracing.
Self-diagnostic function		Watchdog, FLASH-ROM check, RAM check, etc.
Error detection function		Deceleration stop input, unit number error, CPU Unit error, software limit over errors, etc.
Error log function		The error log is to be read from the CPU Unit by means of the IORD instructions as needed.
Alarm reset		Alarm reset
Program and CAM data read protection (supported for unit version 3.1 and later)		Third party access to program and CAM data can be restricted using the CX-Motion-MCH version 2.1 read protection function (password setting).

## Functions

### Electronic Shaft (Electronic Gear) (CONNECT)

This function synchronizes with the main axis at the specified gear ratio. It allows for reductions in mechanical functions and labor requirements for machinery maintenance.

### Electronic Cam (CAM, CAMBOX)

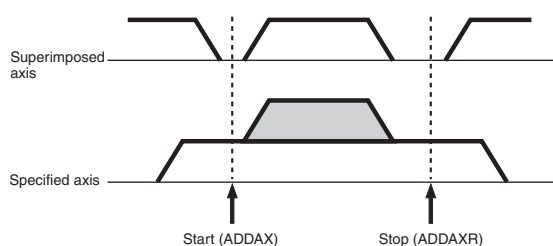
An independent electronic cam can be positioned according to execution times specified in the cam data, and a synchronized electronic cam can be operated according to a cam table in synchronization with a specified main axis. A total of 16,000 points for all Units combined can be included for the cam data, and 32 cam tables can be set, enabling complex operations.

### Virtual Axes

Any axis can be set as an axis performing an ideal movement. Setting it as the main axis for synchronized control simplifies design and debugging of programs and adjustment of synchronized operations. Also, when slippage occurs in motor operation and workpiece operation, the amount of compensation (for the amount of slippage) can be set as the target value for the virtual axis, and the compensation operation can be easily executed by means of the add axis travel function.

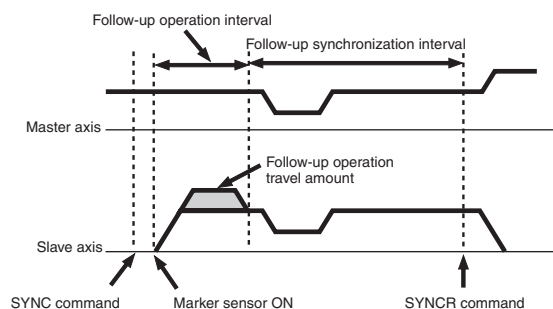
### Add Axis Travel (ADDAX, ADDAXR)

This function adds the operation of a superimposed axis to a specified axis, making it easy to perform compensation in feeder and synchronization operations.



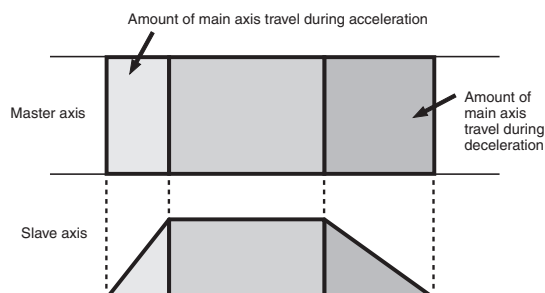
### Follow-up Synchronization (SYNC, SYNCR)

From standby status, this function starts follow-up operation when the marker sensor turns ON and executes follow-up synchronization with the main axis. This is ideal for applications that process workpieces without stopping the line.



### Electronic Links (SYNC)

This function enables the specified synchronized operation with acceleration at the start of synchronization, a ratio during synchronization, and deceleration at the end of synchronization. These specifications are specific for the actual application operation, enabling easy achievement of various types of synchronization operations.



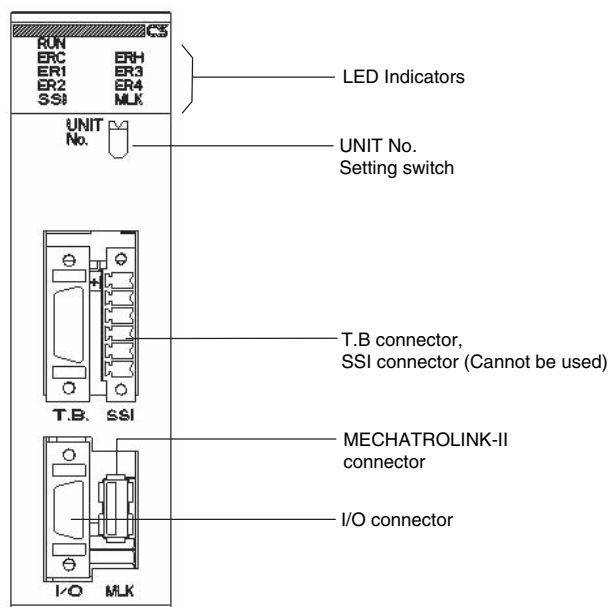
### Other Operations

Various applications are made possible by means of a wide range of commands, such as MOVE TIME (MOVET), CHANGE TARGET (MOVEMODI), LATCH (LATCH: With hardware latch and window functions), TRAVERSE (MOVETRAV), TORQUE (TORQUE, TORQUER), SPEED (SPEED, SPEEDR).

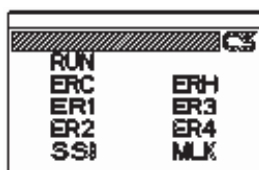
# Commands

Classification	Name	Command	Function
Axis movement	MOVE, LINEAR INTERPOLATION, CIRCULAR INTERPOLATION	MOVE, MOVEL, MOVEC	Moves axes individually, or using linear or circular interpolation.
	ORIGIN SEARCH	DATUM	Finds the machine origin according to input signals.
	INTERRUPT INCHING	MOVEI	Changes the position by inching according to input signals.
	MOVE TIME	MOVET	Positions according to a specified time.
	TRAVERSE	MOVETRAV	Executes a winding operation.
	INDEPENDENT ELECTRONIC CAM	CAM	Executes cam operations according to a table.
Starting and stopping axis operations	LINK	MOVELINK	Synchronizes with the main axis with acceleration and deceleration.
	SYNCHRONIZED ELECTRONIC CAM	CAMBOX	Executes a cam operation according to a table and main axis.
	ELECTRONIC SHAFT	CONNECT	Synchronizes at fixed rate to main axis.
	FOLLOW-UP SYNCHRONIZATION	SYNC	Follows and synchronizes with the main axis.
	STOP SYNCHRONIZATION	SYNCR	Stops MOVELINK, CAMBOX, CONNECT, and SYNC.
	ADD AXIS TRAVEL	ADDAX, ADDAXR	Starts and stops the accumulation of travel amounts between axes.
	START SPEED, END SPEED	SPEED, SPEEDR	Outputs and stops a speed reference.
	START TORQUE, END TORQUE	TORQUE, TORQUER	Outputs and stops a torque reference.
Settings	CHANGE TARGET	MOVEMODI	Changes the target position for the axis that is travelling.
	ABSOLUTE SPECIFICATION, INCREMENTAL SPECIFICATION	ABL, INC	Handles coordinates as absolute or incremental values.
	CHANGE PARAMETER	PARAM	Changes parameter values at one time.
	PASS MODE	PASSMODE	Specifies operations with interpolation blocks connected.
	STOP MODE	STOPMODE	Waits for the interpolation block to be in position.
	SELECT MACHINE COORDINATE SYSTEM, SELECT WORKPIECE COORDINATE SYSTEM	ORIGIN, WORK	Selects either the machine coordinate system or the workpiece coordinate system.
	CHANGE WORKPIECE ORIGIN OFFSET	OFFPOS	Changes the offset of the workpiece coordinate system.
	LATCH	LATCH	Latches the present position.
	IGNORE SINGLE BLOCK	NSTOP	Ignores single block mode.
Controls	PROGRAM START, PROGRAM END	PROG, END	Marks the beginning or end of a program.
	SUBPROGRAM CALL, SUBPROGRAM END	GOSUB, RETURN	Calls a subprogram or ends a subprogram and returns to the source of the call.
	DWELL, WAIT	DWELL, WAIT	Waits for a specified length of time or for a specified condition to be met and then executes the next block.
	OPTIONAL END	STOPOP	Stops the block being executed when a specified condition is met.
	Conditional Branching	IF, ELS, ENDIF	Branches according to conditions.
	WHILE Repeat Commands	WHILE, WEND	Repeats until any specified condition is met.
	FOR Repeat Commands	FOR, NEXT	Repeats until specified count (constant, variable, or immediate) is met.
	Parallel Execution	PARALLEL, JOINT, JWAIT	Executes in parallel for the specified interval.
	Selected Execution	SWITCH, CASE, BREAK, DEFAULT, SEND	Switches and executes the specified section according to conditions.
	NO OPERATION SINGLE, NO OPERATION MULTIPLE	NOPS, NOPM	Nothing is executed. (Single or multiple execution command)
Simple operations	SUBSTITUTION	=	Substitutes values for variables.
	Arithmetic Operations	+, −, *, / , ^	Performs addition, subtraction, multiplication, division, and power operations.
	REMAINDER	%	Finds the remainder in division operations.
Logical operations	OR/XOR/AND/NOT	, ., &, !	Performs logical OR, XOR, AND, and NOT operations.
Functions	ABSOLUTE	ABS	Finds the absolute value.
	SINE, COSINE, ASINE, ACOSINE	SIN, COS, ASIN, ACOS	Finds the sine, cosine, arcsine, or arccosine.
	TANGENT, ATANGENT	TAN, ATAN	Finds the tangent or arctangent.
	SQUARE ROOT, EXPONENT, LOGARITHM	SQR, EXP, LOG	Finds the square root, exponent, or logarithm.
	FRACTION	FRAC	Finds the decimal portion.
	SIGN	SGN	1 if greater than 0, and -1 if negative.
Bit operations	BIT ON, BIT OFF	SET, RESET	Turns a specified bit ON or OFF.
	RIGHT SHIFT, LEFT SHIFT	SFTR, SFTL	Shifts right or left for the specified number of bits.
Data operations	BCD → BIN/BIN → BCD	BIN, BCD	Converts from BCD to binary, or from binary to BCD.
	BLOCK TRANSFER, BLOCK CLEAR	XFER, CLEAR	Transfers or clears a block of data.

## External Interface



## LED Indicators



Name	Color	Status	Content
RUN (RUN)	Green	Lit	Motion Control Unit is operating normally.
		Not lit	Not recognized by PLC, or MC Unit is broken.
ERC (MC Unit Error)	Red	Lit	An error has occurred in the MC Unit.
		Not lit	MC Unit is operating normally.
ERH (CPU Unit Error)	Red	Lit	An error has occurred in the CPU Unit.
		Not lit	CPU Unit is operating normally.
ER1 * (Internal error status)	Yellow	Lit	An internal error has occurred.
		Not lit	MC Unit is operating normally.
ER2 * (Internal error status)	Yellow	Lit	An internal error has occurred.
		Not lit	MC Unit is operating normally.
ER3 * (Internal error status)	Yellow	Lit	An internal error has occurred.
		Not lit	MC Unit is operating normally.
ER4 * (Internal error status)	Yellow	Lit	An internal error has occurred.
		Not lit	MC Unit is operating normally.
SSI	Yellow	Lit	Not used.
		Not lit	Not used.
MLK (MECHATROLINK-II)	Yellow	Lit	MLK is operating normally.
		Not lit	An error has occurred in the MLK.

\* When the ERC or ERH indicator is lit, these four indicators show the internal error status.

## Functions Supported by CS1W-MCH71 Units Version 2.0 or Later

Unit version		Pre-Ver. 2.0	Unit Ver. 2.0	Unit Ver. 3.0	Unit Ver. 3.1
Internal system software version		1.00 to 1.04	1.05	1.08	1.09
MC Unit model		CS1W-MCH71			
Functions	Jogging	—	Supported	Supported	Supported
	Communications levels	—	Supported	Supported	Supported
	Communications cycle and unit cycle	—	Supported	Supported	Supported
	LATCH command processing time	—	Supported	Supported	Supported
	Latch status refresh time	—	Supported	Supported	Supported
	Using interpolation commands during pass operation	—	Supported	Supported	Supported
	Acceleration/deceleration time during pass operation	—	Supported	Supported	Supported
	Deceleration time during pass operation	—	Supported	Supported	Supported
	Torque to position control switching	—	Supported	Supported	Supported
	Expanded allocations in Custom I/O Area	—	—	Supported *1	Supported *1
	Digital input values changed to improve noise immunity	—	—	Supported	Supported
	Faster unit cycle and communications cycle times	—	—	Supported	Supported
	Signed master axis MOVELINK command	—	—	Supported	Supported
	Indirect writing of position data	—	—	Supported	Supported
	Status of program start bit	—	—	Supported	Supported
	Re-execution of WAIT command	—	—	Supported	Supported
	Main power status	—	—	Supported	Supported
	Servo Driver status	—	—	Supported	Supported
	Increased precision of CAMBOX command	—	—	Supported	Supported
	Data tracing	—	—	Supported *1	Supported *1
	Debugging	—	—	Supported *1	Supported *1
	Zones	—	—	Supported *1	Supported *1
	Setting the number of parallel branches for each task	—	—	Supported *1	Supported *1
	Present position preset to establish origin	—	—	Supported *1	Supported *1
	Servo OFF for deceleration stop signal	—	—	Supported *1	Supported *1
	Improved restarting after restoration	—	—	—	Supported
	Expanded bank switching for interpolation acceleration/deceleration times	—	—	—	Supported
	Internal overrides	—	—	—	Supported
	Connecting to SMARTSTEP Junior Servo Drivers	—	—	—	Supported *2
	Improved backup and restore functions	—	—	—	Supported *2
	Program and CAM data read protection	—	—	—	Supported *2
Applicable Support Tool		CX-Motion-MCH • Functions for unit version 3.0 indicated by “*1” can be used with CX-Motion-MCH version 2.0 or higher. • Functions for unit version 3.1 indicated by “*2” can be used with CX-Motion-MCH version 2.1 or higher.			

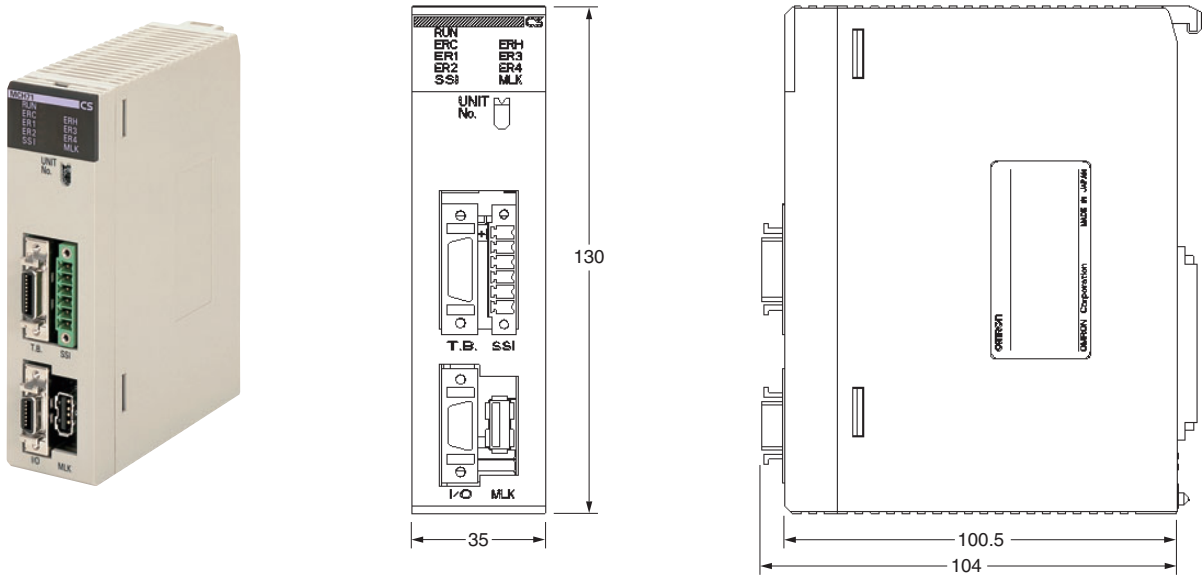
## CS1W-MCH71 Unit Versions and Manufacturing Dates/Lot Numbers

Classification	Type	Model	Manufacturing dates			
			From early June 2004	From July 2004	From March 2007	From early July 2007
CPU Bus Unit	MC Unit	CS1W-MCH71	Pre-Ver. 2.0	Unit version 2.0 (Lot No.: 040715 and later)	Unit version 3.0 (Lot No.: 070313 and later)	Unit version 3.1 (Lot No.: 070615 and later)

Dimensions

(Unit: mm)

CS1W-MCH71



Related Manual

English Cat. No.	Japanese Cat. No.	Model	Name
W435	SBCE-327	CS1W-MCH71/CJ1W-MCH71	CS1W-MCH71/CJ1W-MCH71 CS/CJ-series MECHATROLINK-II-compatible Motion Control Unit User's Manual
W448	SBCE-336	CXONE-AL□□C-V□/ CXONE-AL□□D-V□	CX-Motion-NCH Operation Manual
—	SBCE-046	CS1W-MCH71/CJ1W-MCH71	CS1W-MCH71/CJ1W-MCH71 Motion Control Unit (ONNUC W-series) Technical Guide

## Read and Understand This Catalog

Please read and understand this catalog before purchasing the products. Please consult your OMRON representative if you have any questions or comments.

## Warranty and Limitations of Liability

### WARRANTY

OMRON's exclusive warranty is that the products are free from defects in materials and workmanship for a period of one year (or other period if specified) from date of sale by OMRON.

OMRON MAKES NO WARRANTY OR REPRESENTATION, EXPRESS OR IMPLIED, REGARDING NON-INFRINGEMENT, MERCHANTABILITY, OR FITNESS FOR PARTICULAR PURPOSE OF THE PRODUCTS. ANY BUYER OR USER ACKNOWLEDGES THAT THE BUYER OR USER ALONE HAS DETERMINED THAT THE PRODUCTS WILL SUITABLY MEET THE REQUIREMENTS OF THEIR INTENDED USE. OMRON DISCLAIMS ALL OTHER WARRANTIES, EXPRESS OR IMPLIED.

### LIMITATIONS OF LIABILITY

OMRON SHALL NOT BE RESPONSIBLE FOR SPECIAL, INDIRECT, OR CONSEQUENTIAL DAMAGES, LOSS OF PROFITS OR COMMERCIAL LOSS IN ANY WAY CONNECTED WITH THE PRODUCTS, WHETHER SUCH CLAIM IS BASED ON CONTRACT, WARRANTY, NEGLIGENCE, OR STRICT LIABILITY.

In no event shall the responsibility of OMRON for any act exceed the individual price of the product on which liability is asserted.

IN NO EVENT SHALL OMRON BE RESPONSIBLE FOR WARRANTY, REPAIR, OR OTHER CLAIMS REGARDING THE PRODUCTS UNLESS OMRON'S ANALYSIS CONFIRMS THAT THE PRODUCTS WERE PROPERLY HANDLED, STORED, INSTALLED, AND MAINTAINED AND NOT SUBJECT TO CONTAMINATION, ABUSE, MISUSE, OR INAPPROPRIATE MODIFICATION OR REPAIR.

## Application Considerations

### SUITABILITY FOR USE

OMRON shall not be responsible for conformity with any standards, codes, or regulations that apply to the combination of products in the customer's application or use of the products.

At the customer's request, OMRON will provide applicable third party certification documents identifying ratings and limitations of use that apply to the products. This information by itself is not sufficient for a complete determination of the suitability of the products in combination with the end product, machine, system, or other application or use.

The following are some examples of applications for which particular attention must be given. This is not intended to be an exhaustive list of all possible uses of the products, nor is it intended to imply that the uses listed may be suitable for the products:

- Outdoor use, uses involving potential chemical contamination or electrical interference, or conditions or uses not described in this catalog.
- Nuclear energy control systems, combustion systems, railroad systems, aviation systems, medical equipment, amusement machines, vehicles, safety equipment, and installations subject to separate industry or government regulations.
- Systems, machines, and equipment that could present a risk to life or property.

Please know and observe all prohibitions of use applicable to the products.

NEVER USE THE PRODUCTS FOR AN APPLICATION INVOLVING SERIOUS RISK TO LIFE OR PROPERTY WITHOUT ENSURING THAT THE SYSTEM AS A WHOLE HAS BEEN DESIGNED TO ADDRESS THE RISKS, AND THAT THE OMRON PRODUCTS ARE PROPERLY RATED AND INSTALLED FOR THE INTENDED USE WITHIN THE OVERALL EQUIPMENT OR SYSTEM.

### PROGRAMMABLE PRODUCTS

OMRON shall not be responsible for the user's programming of a programmable product, or any consequence thereof.

## Disclaimers

### CHANGE IN SPECIFICATIONS

Product specifications and accessories may be changed at any time based on improvements and other reasons.

It is our practice to change model numbers when published ratings or features are changed, or when significant construction changes are made. However, some specifications of the products may be changed without any notice. When in doubt, special model numbers may be assigned to fix or establish key specifications for your application on your request. Please consult with your OMRON representative at any time to confirm actual specifications of purchased products.

### DIMENSIONS AND WEIGHTS

Dimensions and weights are nominal and are not to be used for manufacturing purposes, even when tolerances are shown.

### PERFORMANCE DATA

Performance data given in this catalog is provided as a guide for the user in determining suitability and does not constitute a warranty. It may represent the result of OMRON's test conditions, and the users must correlate it to actual application requirements. Actual performance is subject to the OMRON Warranty and Limitations of Liability.

### ERRORS AND OMISSIONS

The information in this document has been carefully checked and is believed to be accurate; however, no responsibility is assumed for clerical, typographical, or proofreading errors, or omissions.

2011.4

In the interest of product improvement, specifications are subject to change without notice.

**OMRON Corporation**  
Industrial Automation Company

<http://www.ia.omron.com/>

(c)Copyright OMRON Corporation 2011 All Right Reserved.