

Air Servo Cylinder

IN-777

ø125, ø160, ø200, ø250, ø320

Produced upon receipt of order



How to Order

IN-777-**160**TF-**300**F**J**-**H****L**

Bore size

125	125 mm
160	160 mm
200	200 mm
250	250 mm
320	320 mm

Port thread type

TF	G
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Stroke [mm]

125	250
160	200, 300
200	200, 300
250	350, 450
320	200, 350, 530*1

*1 The models specified above are classified as Class-2 Pressure Vessels, as stipulated in the order for enforcement of the Industrial Safety and Health Act, and they are therefore not for use within Japan.

LED alarm display

L	With LED alarm display
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Communication protocol

H	4-20 mA/HART communication
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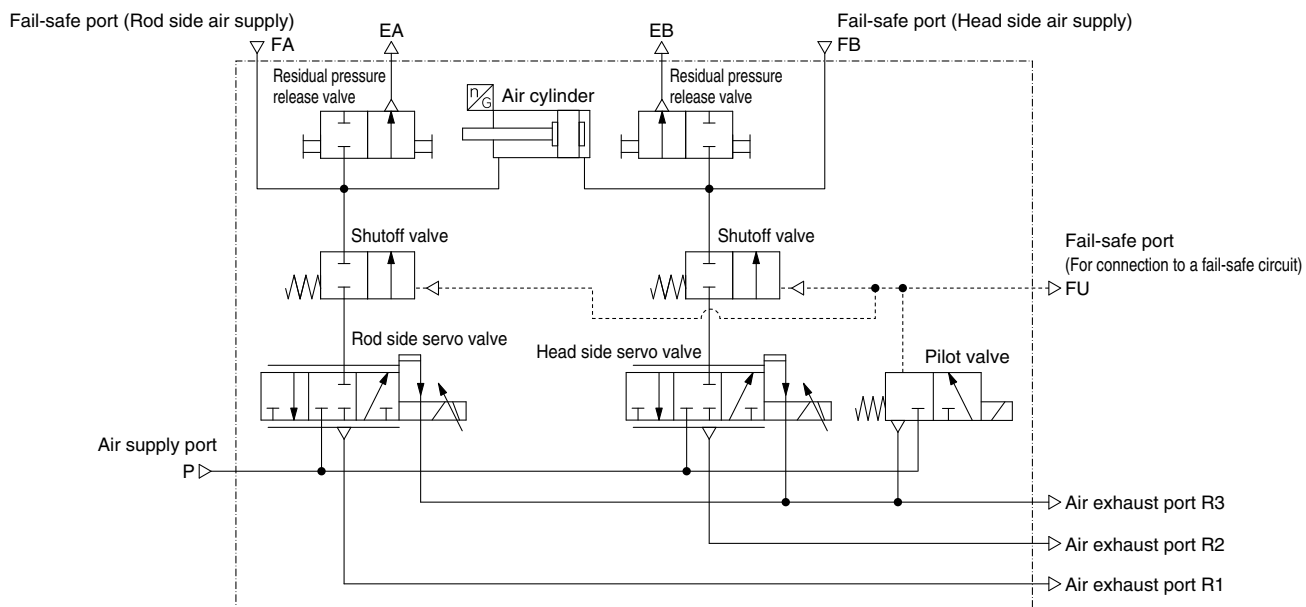
Rod boot

J	Silicone rubber material
Nil	Without rod boot

Mounting

F	With rod flange
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Pneumatic Circuit



Specifications

Mechanical Specifications

Action	Double acting, Single rod
Fluid	Air
Compressed air filtration	0.3 μm or less
Proof pressure	1.2 MPa
Operating pressure range	0.55 to 0.8 MPa
Positioning repeatability	±0.5 mm or less
Max. speed	ø125 to 250: 155 mm/s ø320: 80 mm/s
Ambient and fluid temperatures	-20°C to 60°C (No freezing)
Operating humidity	35 to 85% (No condensation)
Enclosure	IP67
Standards	CE, RoHS
Weight	Refer to Table 1 .
Lubrication	Non-lube
Mounting orientation	Vertical downward/Vertical upward
Vibration resistance	Total amplitude or acceleration: 1.5 mm or 3 G
	Vibration frequency: 5 to 100 Hz
	Vibration applying direction: 3 directions (X, Y, and Z) Sweep time/cycle: 12 min/10 cycles
Impact resistance	Acceleration: 15 G
	Pulse applying time/waveform: 11 ms/Sine wave
	Pulse applying direction: 3 times in each direction (X, Y, and Z axes)
Allowable lateral load	Refer to Table 2 .
Theoretical output/Work load	Refer to Table 3 .
Power supply connector (body)	M23 19-pin connector (Male): Refer to Table 4 .

Electrical Specifications

Power supply	Supply voltage: 24 VDC ±10%
Control system	Closed loop
Position sensor	Absolute
Analog input signal	4 to 20 mA DC
Analog input impedance	Approx. 250 Ω
Analog output signal	4 to 20 mA DC
Analog output impedance	500 Ω
Voltage between terminals	12 VDC (Equivalent to 600 Ω input resistance at 20 mA DC)
Switch input signal	4 inputs, Connect to +24 VDC ±10% Current consumption: 10 mA or less
Switch output signal	5 outputs, n-type MOSFET open source output Max. load current: 100 mA
Communication protocol	HART communication

Functional Specifications

- JOG operation
- No signal operation
- Self-diagnosis function (Allows for controller, valve, and position sensor error output when an abnormality is present)
- Fail-safe operation
- Calibration (Automatic/Manual)
- Emergency stop
- Residual pressure release valve mounted
- Target position operation
- Speed adjustment (10-level)

Table 1 Weight

Bore size [mm]	Stroke [mm]	Weight [kg]
125	250	24
	200	37
160	300	43
	200	53
200	300	61
	350	86
250	450	97
	200	100
320	350	129
	530	163

Table 2 Allowable Lateral Load

Bore size [mm]	Allowable lateral load [N]
125	70
160	90
200	140
250	160
320	230

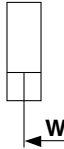
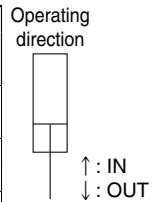


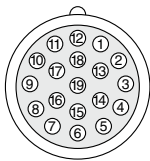
Table 3 Theoretical Output/Max. Work Load

Bore size [mm]	Operating direction	Theoretical output [N]		Max. work load [kg]*1
		Operating pressure [MPa]	Operating pressure [MPa]	
125	IN	0.55	0.8	160
	OUT	6,400	9,200	
160	IN	6,800	9,900	240
	OUT	10,400	15,100	
200	IN	11,100	16,100	240
	OUT	16,600	24,200	
250	IN	17,300	25,200	300
	OUT	26,000	37,700	
320	IN	27,000	39,300	300
	OUT	42,700	62,100	



*1 Based on SMC's specific testing conditions

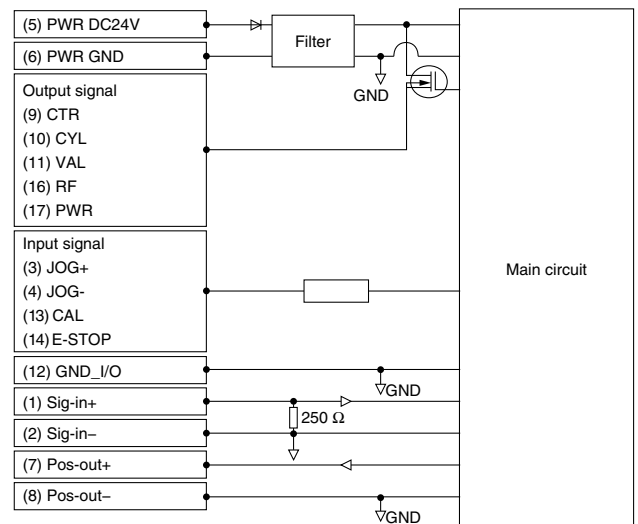
Table 4 Connector Pin Numbers (Body Side)



Pin no.	Signal name	IN/OUT	Description
1	Sig-in+	IN	Analog signal (4-20 mA(+)), HART communication signal input
2	Sig-in-	IN	Analog signal (4-20 mA(-)), HART communication signal input
3	JOG+	IN	JOG operation signal input (Moves to the rod side)
4	JOG-	IN	JOG operation signal input (Moves to the head side)
5	PWR DC24V		Power supply +24 VDC
6	PWR GND		Power supply GND
7	Pos-out+	OUT	Analog position signal (+) output
8	Pos-out-	OUT	Analog position signal (-) output
9	CTR	OUT	Controller signal output
10	CYL	OUT	Position sensor error signal output
11	VAL	OUT	Valve error signal output
12	GND I/O		Signal GND
13	CAL	IN	Calibration signal input
14	E-STOP	IN	Emergency stop signal input*1
15	—	—	—
16	RF	OUT	Rod friction error signal output
17	PWR	OUT	Power supply error signal output
18	—	—	—
19	—	—	—

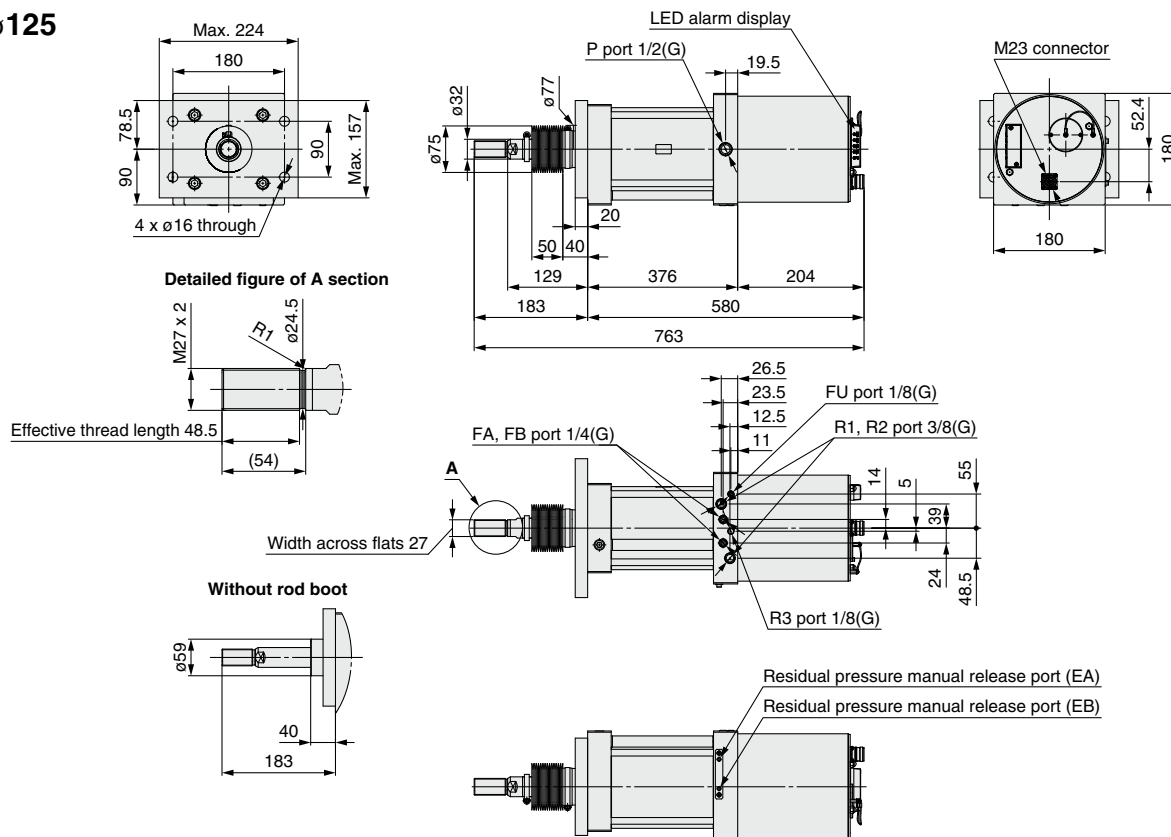
*1 When the signal is OFF, an emergency stop occurs. —: Cannot be connected

Wiring Diagram

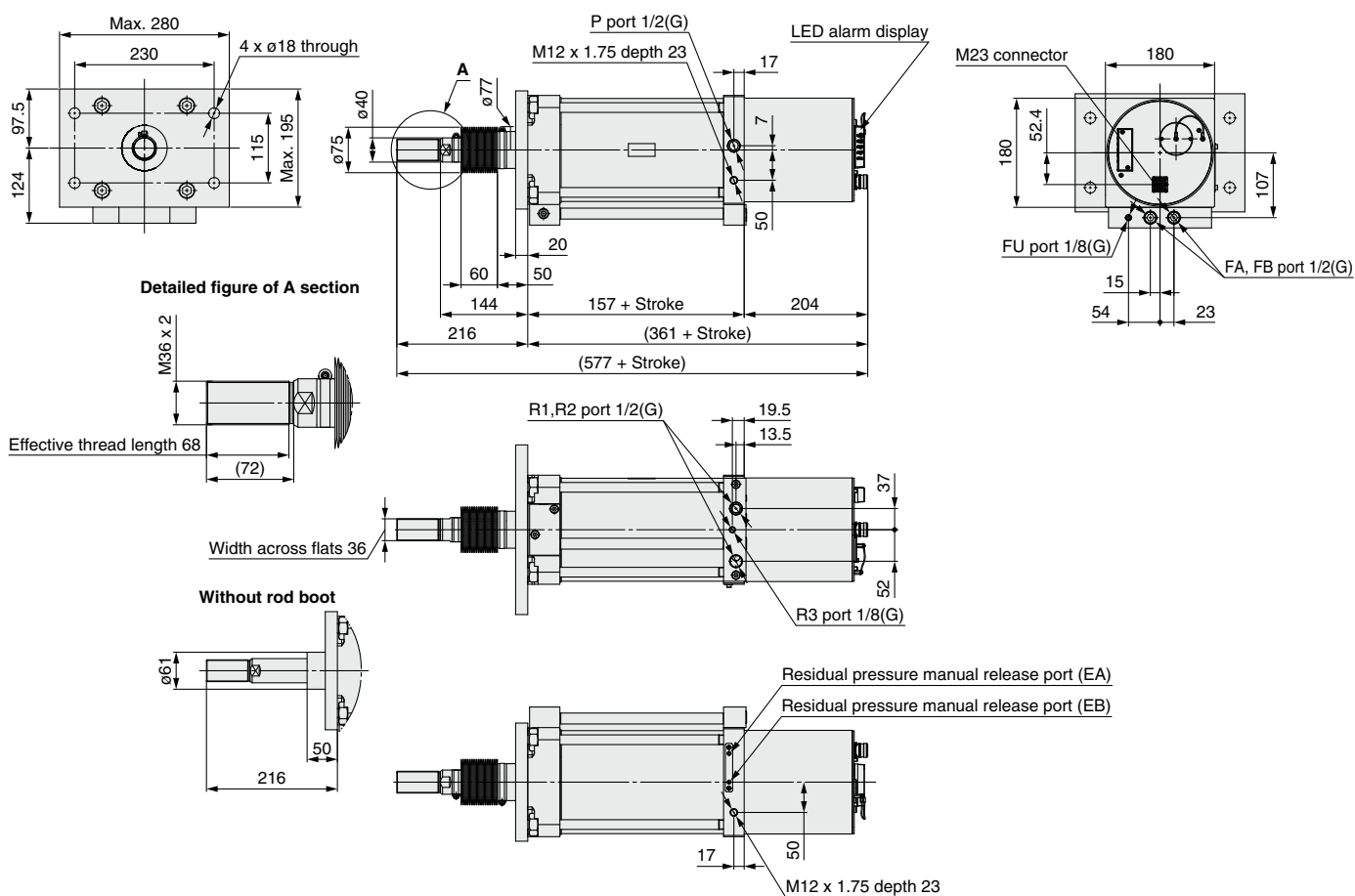


Dimensions

ø125

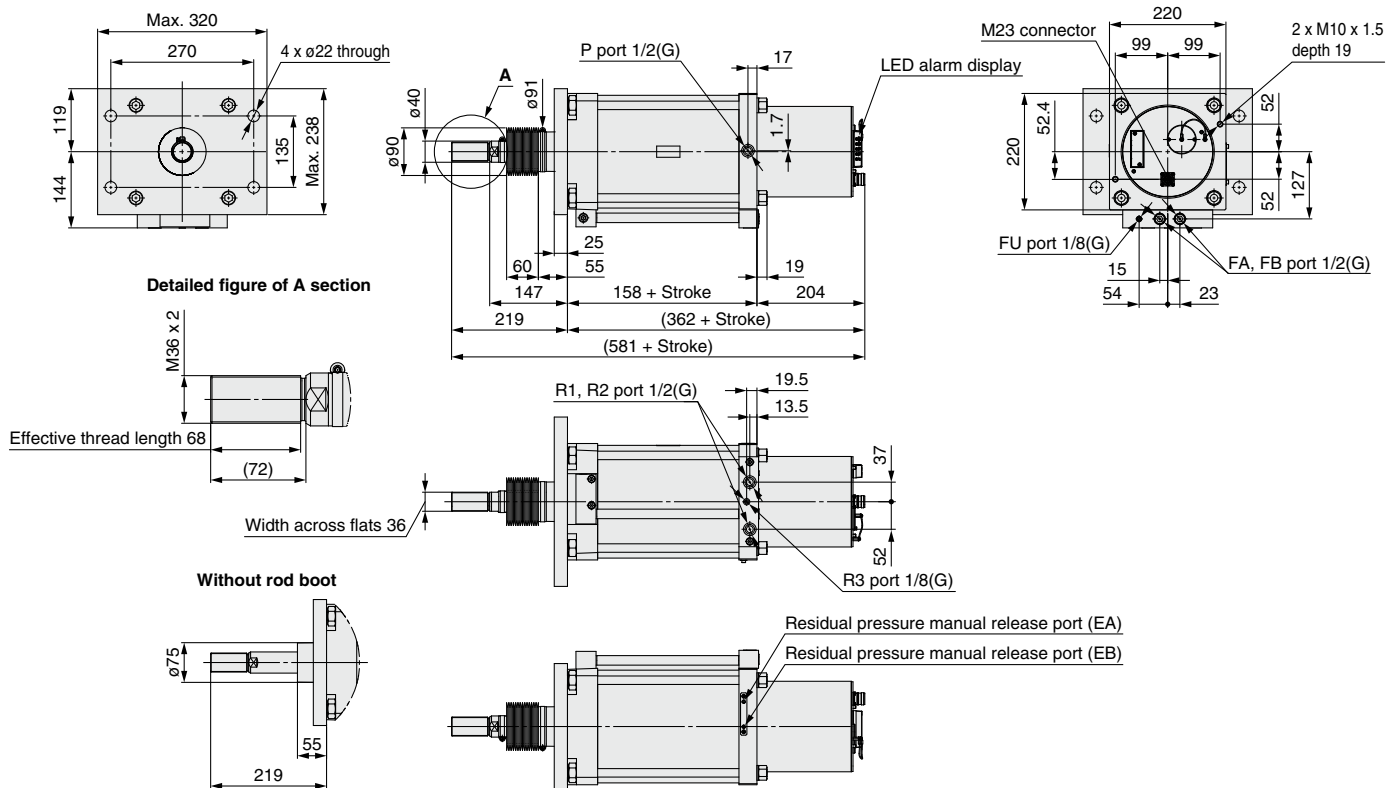


ø160

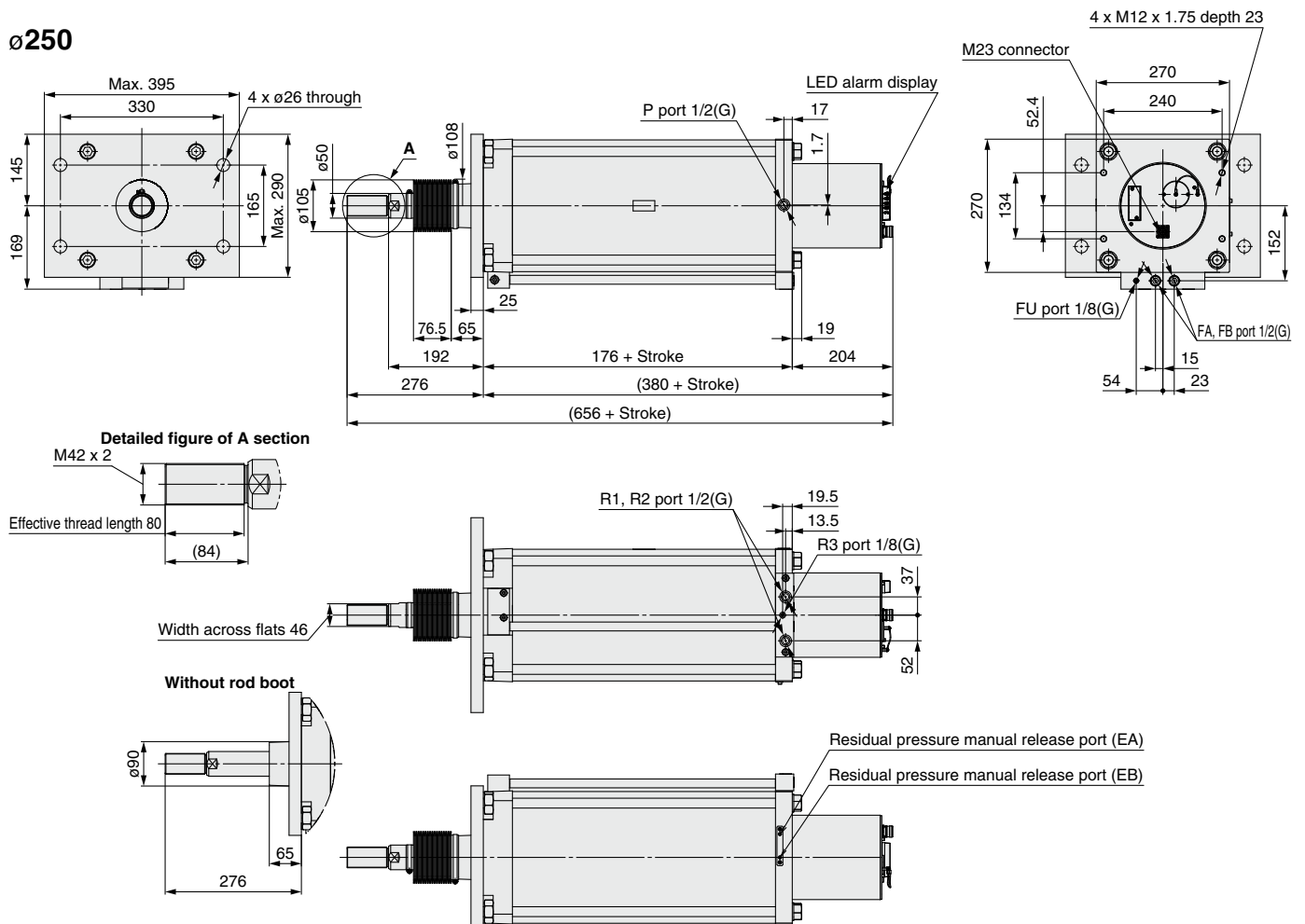


Dimensions

ø200

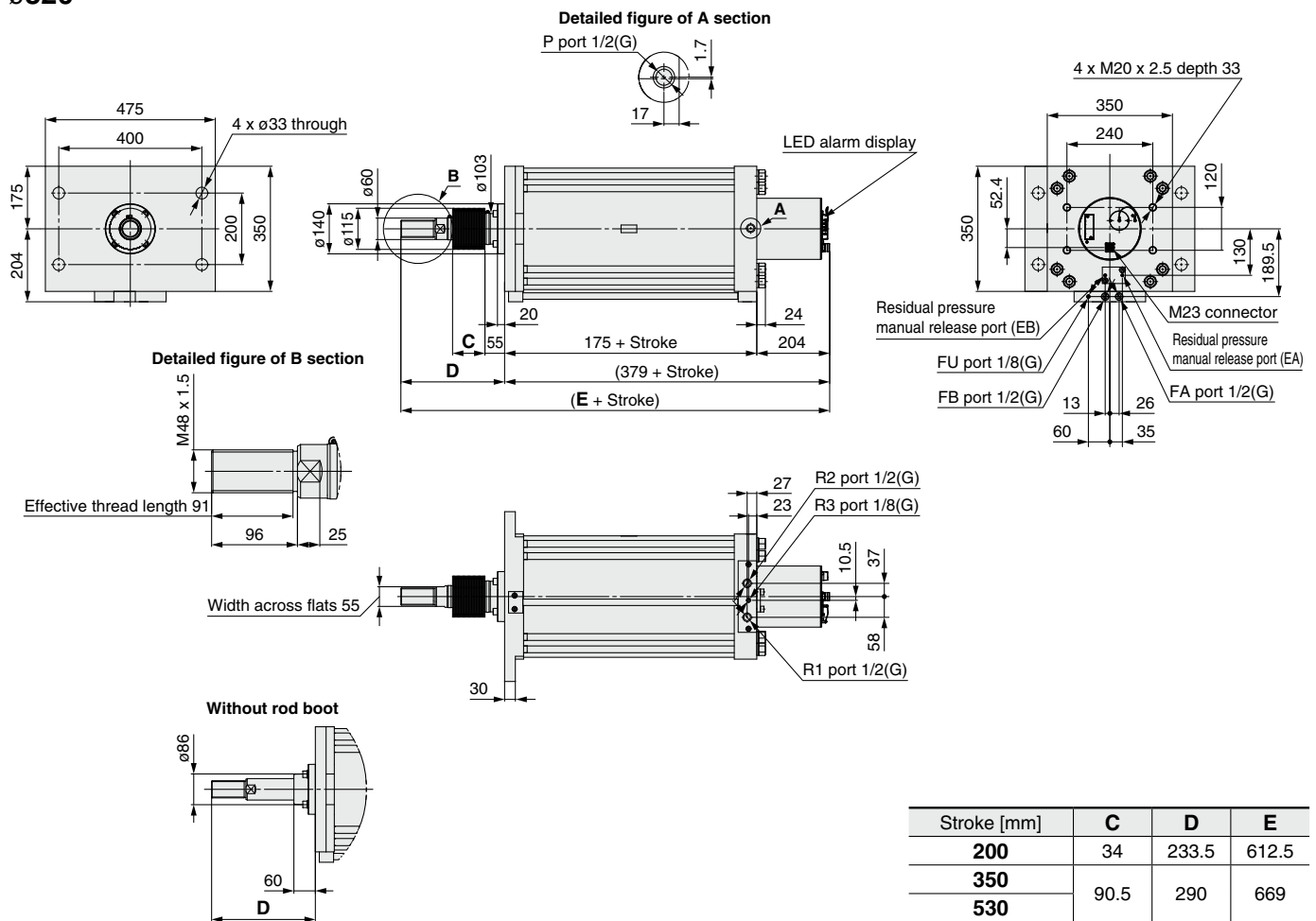


ø250



Dimensions

Ø320



Working Principle/Construction

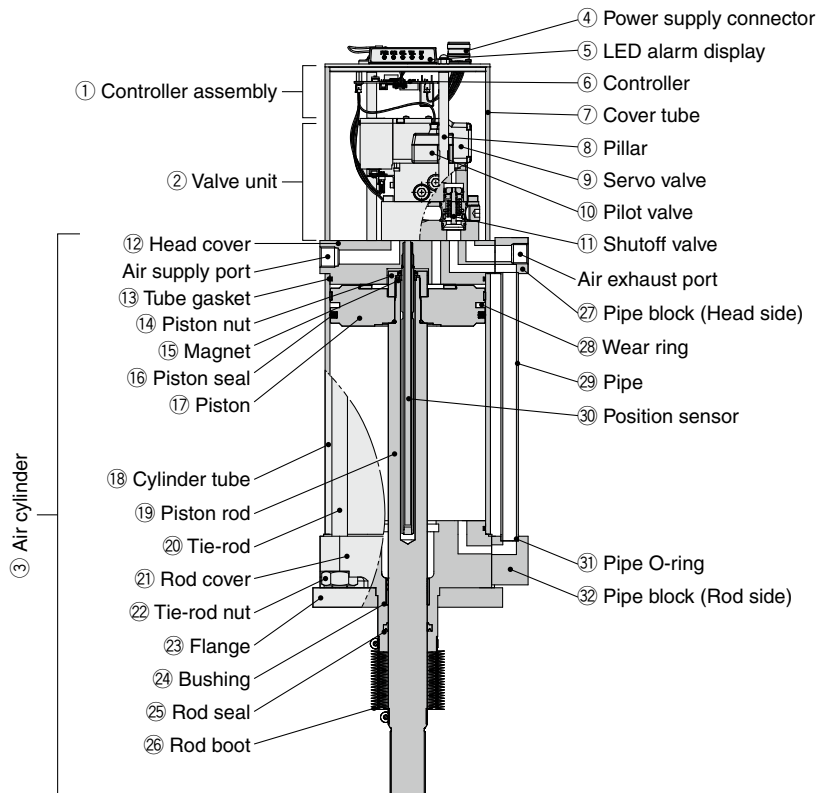
The ③ position sensor built in to the ③ air cylinder outputs the current position of the ⑱ piston rod to the ⑥ controller.

Next, the ⑥ controller outputs a command signal to the 2 ⑨ servo valves according to the target position signal sent from the host controller.

Then, according to the command signal sent from the ⑥ controller, the ⑨ servo valves control the ③ air cylinder air supply or exhaust to move the piston rod forwards or backwards, or to stop it at the target position.

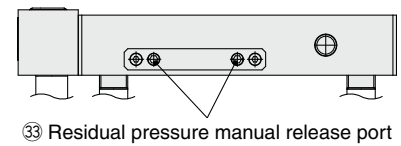
The opening and closing of the ⑪ shutoff valve is controlled by the ⑩ pilot valve connected to the ⑥ controller.

Two air-operated ⑪ shutoff valves (head side and rod side) are mounted along the air passage between the ⑨ servo valves and the ③ air cylinder. During an emergency stop (air or power supply cutoff, emergency stop signal input, etc.), the 2 ⑪ shutoff valves will close and ③ air cylinder operation will be stopped.

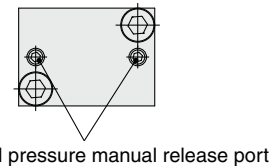


A 160 bore size, 200 mm stroke air cylinder is used in the drawings.

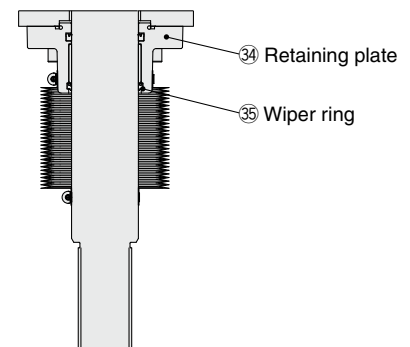
Back portion of ø125 to ø250 head covers



Top portion of ø320 head covers



Cross-section portion of ø320 rod ends



Component Parts

No.	Description	Material/Surface treatment	No.	Description	Material/Surface treatment
1	Controller assembly* ¹	Aluminum alloy/Anodized (Main parts)	20	Tie-rod	Stainless steel
2	Valve unit* ¹	—	21	Rod cover	ø160 to ø250: Aluminum die-cast/Chromated ø125 and ø320: Aluminum alloy/Anodized
3	Air cylinder	—	22	Tie-rod nut	Stainless steel
4	Power supply connector	—	23	Flange* ²	Steel/Zinc plating
5	LED alarm display	Aluminum alloy/Painted (Main parts)	24	Bushing	Bearing alloy
6	Controller	—	25	Rod seal* ¹	Low-temperature NBR
7	Cover tube	Aluminum alloy/Anodized	26	Rod boot (Option)* ¹	Silicone rubber material
8	Pillar	Aluminum alloy	27	Pipe block (Head side)* ³	Aluminum alloy/Anodized
9	Servo valve* ¹	—	28	Wear ring* ¹	Resin
10	Pilot valve* ¹	—	29	Pipe	Aluminum alloy/Anodized
11	Shutoff valve	—	30	Position sensor* ¹	—
12	Head cover	Aluminum alloy/Anodized	31	Pipe O-ring* ¹	Low-temperature NBR
13	Tube gasket* ¹	Low-temperature NBR	32	Pipe block (Rod side)* ⁴	Aluminum alloy/Anodized
14	Piston nut	Stainless steel	33	Residual pressure manual release port	—
15	Magnet	—	34	Retaining plate	Stainless steel
16	Piston seal* ¹	Low-temperature NBR	35	Wiper ring* ¹	Low-temperature NBR
17	Piston	Aluminum alloy/Chromated			
18	Cylinder tube	ø125 to ø250: Aluminum alloy/Anodized ø320: Carbon steel tube/Painted			
19	Piston rod	Stainless steel/Hard chrome plating			

*1 Refer to page 9 for maintenance parts and seal kit accessories.

*2 The rod cover is integrated for size ø320.

*3 The head cover is integrated for size ø125.

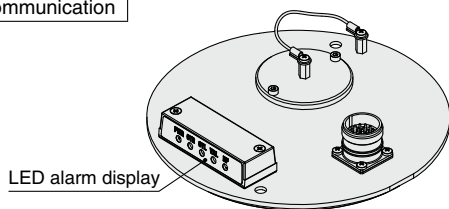
*4 The rod cover is integrated for size ø125.

Maintenance Parts

① Controller assembly

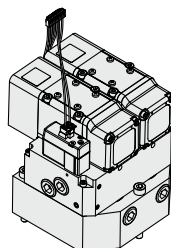
IN-777P-HL-410AS

Communication protocol	LED alarm display
H 4-20 mA/HART communication	L With LED alarm display



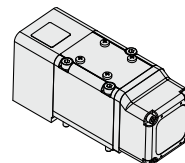
② Valve unit

IN-777P-010AS



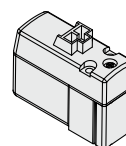
⑨ Servo valve

XT581-V-C-X001



⑩ Pilot valve

V211KT-5LOZ-X48



②⑥ Rod boot



Bore size [mm]	Stroke [mm]	Part number
125	250	C96A2G-1461V-R
160	200	C95A6G-471AQ-R
	300	
200	200	C95B0G-472AQ-R
	300	
250	350	C95B5G-533AQ-R
	450	
320	200	C1SC2G-1468V-R
	350	C1SC2G-1470V-R
	530	

③⑩ Position sensor unit

IN-777P-200-830AS



● Cylinder stroke

200	200 mm
250	250 mm
300	300 mm
350	350 mm
450	450 mm
530	530 mm

* For the position sensor unit, the cylinder stroke is the same for all tube sizes.

Seal kit

IN-777P-125-910AS

● Bore size

125	This set includes the following: ⑬Tube gasket (2 pcs.)
160	⑯Piston seal (1 pc.)
200	⑳Rod seal (1 pc.)
250	㉔Wear ring (1 pc.)
	㉑Pipe O-ring (2 pcs.)
320	This set includes the following: ⑬Tube gasket (2 pcs.)
	⑯Piston seal (1 pc.)
	⑳Rod seal (1 pc.)
	㉔Wear ring (1 pc.)
	㉑Pipe O-ring (2 pcs.)
	㉕Wiper ring (1 pc.)

* The seal kit includes a grease pack.

* The circled numbers correspond to the component numbers in the cross-section construction drawing on page 8.

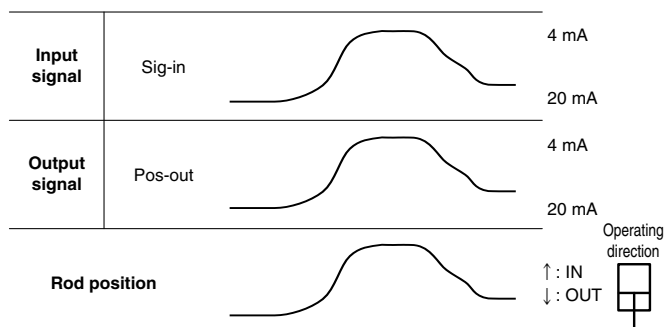
Operation Modes

■ Target position operation

The rod position is decided according to the Sig-in signal input by the master controller.

The rod position is then output as a Pos-out signal.

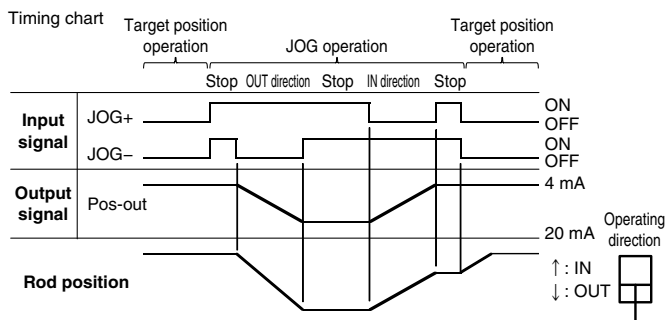
* Be sure to calibrate the product before use. If the set point has not yet been set, the rod will not move even during a target position operation. Refer to page 10 for calibration instructions.



* The operating direction can be changed.

■ JOG operation

The rod moves according to the JOG signal input by the master controller.



		JOG+	
		OFF	ON
JOG-	OFF	Target position operation	JOG operation (Moves in the OUT direction)
	ON	JOG operation (Moves in the IN direction)	JOG operation (Stops)

* The device will move to the target position input as the Sig-in and stop when changing from JOG operation to target position operation.

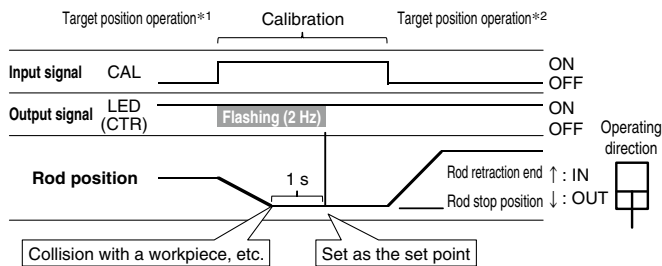
Operation Modes

■ Calibration

Set the rod position (set point) by inputting a CAL signal into the master controller and setting the Sig-in signal to 20 mA (default).
When changing the operation direction, the 4 mA rod position becomes the set point.
It is possible to change the operation mode from automatic to manual.

Automatic (Default)

When the CAL signal is turned ON, the rod will move in the OUT direction, and the position where the rod stops for 1 s will become the set point.
When the CAL signal is turned OFF, the rod will move in the IN direction, and the rod will stop at the retraction end.

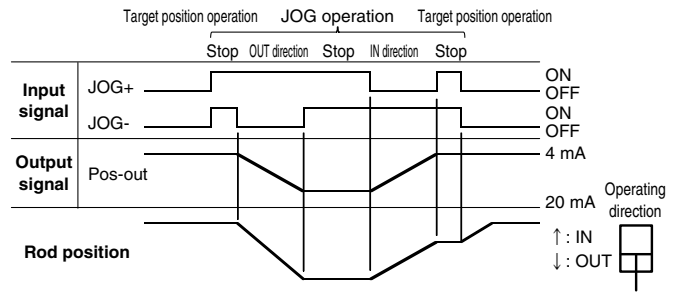


*1 If the set point has not yet been set, the rod will not move even during a target position operation.

*2 The target position may vary slightly before and after the set point has been set, even if the Sig-in signal is the same.

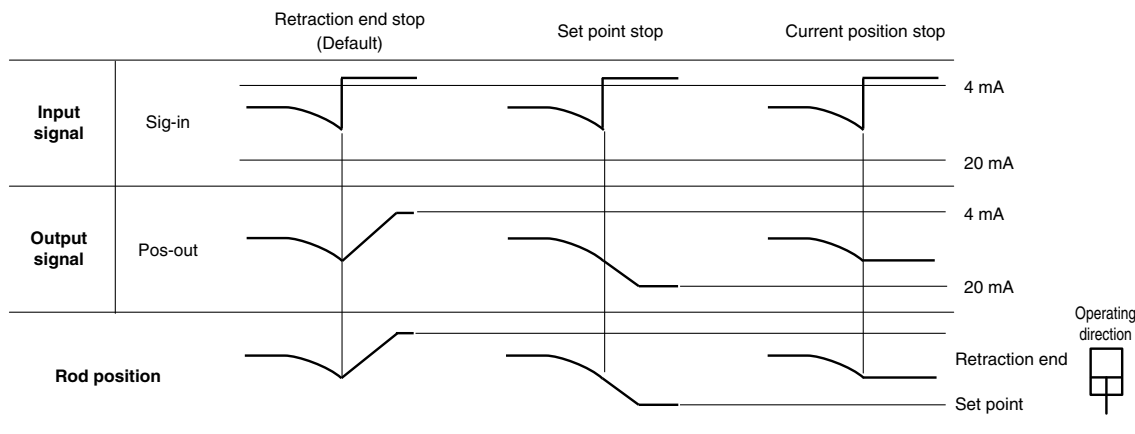
Manual

The rod will be moved by the JOG signal, and the position of the rod when the CAL signal is input will become the set point.



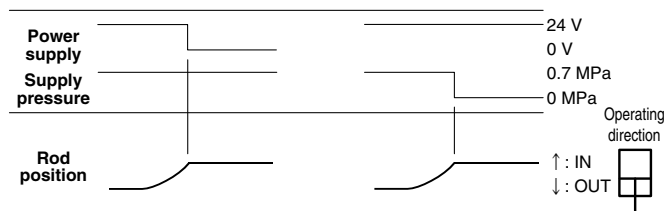
■ No signal operation

This is the operation mode used when the Sig-in signal input into the master controller is 4 mA or less.
The rod will move to the predetermined position and then stop.



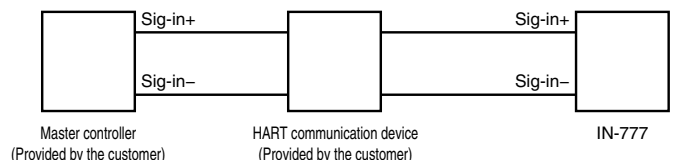
■ Emergency stop

When the air servo cylinder air or power supply is cut during use, the built-in shutoff valves will close, stopping the rod.
Air from the emergency tank can be supplied via the fail-safe port (FA/FB) in order to allow for the operation of the air cylinder rod.



■ HART (Highway Addressable Remote Transducer) communication

With this communication type, a digital signal is superimposed on the 4-20 mA Sig-in signal and then transmitted. Connect a HART communication device (provided by the customer) between the Sig-in + and the Sig-in -.



Main transmission contents
1. IN-777 information – confirmation and revision
2. HART communication settings – confirmation and revision
3. Cylinder operating conditions - setting and confirmation
4. Calibration - execution
5. Operating mode - setting and revision
6. JOG operation - execution
7. Operation status/Alarm confirmation