### Ordering method

**F01H**

**Model**  
- YA  
- Linear conveyor modules (LCM100)  
- Compact single-axis robots (TRANSERVO, Motor-less single-axis robots (PHASER)  
- Cartesian robots (XY type)  
- SCARA robots (YK-X)  
- Pick & place robots (YP-X)  
- CLEAN CONTROLLER INFORMATION

**Note 1.** The model with a lead of 30mm cannot select specifications with brake (vertical specifications).

**Note 2.** If selecting 3mm lead specifications then the origin point cannot be changed to the non-motor side.

**Note 3.** The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.614 for details on robot cable.

**Note 4.** See P.522 for DIN rail mounting bracket.

**Note 5.** Select this selection when using the gateway function. For details, see P.66.

**Specifications**

- **AC servo motor output (W):** 200
- **Repeatability (mm):** ±0.01
- **Deceleration**  
  - Ball screw (R15)
  - Linear motor
- **Maximum speed (mm/ sec):** 1000 (closed loop), 1200 (open loop)
- **Maximum output (N):** 8
- **Rated thrust (N):** 100
- **Stroke (mm):** 630 (W), 341 (horizontal), 683 (vertical)
- **Vertical stroke: 355 (W), 100 (horizontal), 385 (vertical)
- **Overall length (mm):** 1130 (W), 1310 (horizontal), 1241 (vertical)
- **Overall width (mm):** 700 (W), 710 (horizontal), 741 (vertical)
- **Overall height (mm):** 1450 (W), 1465 (horizontal), 1465 (vertical)
- **Height (mm):** 1090 (W), 1100 (horizontal), 1090 (vertical)
- **Weight (kg):** 60 (W), 60 (horizontal), 60 (vertical)

**Table:**

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<th>Stroke (mm)</th>
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<th>1100</th>
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</tbody>
</table>

**Position detector (Resolution):**

- **Resolution (F/F):** 2
- **Position limit switch:** 10

**Note 1.** Positioning repeatability in one direction.

**Note 2.** If the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

**Note 3.** Positioning repeatability (incremental) are common to incremental and absolute specifications. If the controller has a backup function it will be absolute specifications.

**Note 6.** Service life is calculated for 600mm stroke models.

### Allowable overhang

- **Horizontal installation:** 1050 (W), 1100 (horizontal), 1150 (vertical)
- **Wall installation:** 1050 (W), 1100 (horizontal), 1150 (vertical)
- **Vertical installation:** 1050 (W), 1100 (horizontal), 1150 (vertical)

**Note:** Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 m.

**Note 1.** Service life is calculated for 600mm stroke models.

### Static loading moment

- **Moment of inertia (L, M, W):** 1500 (W), 1500 (horizontal), 1500 (vertical)
- **Maximum moment of inertia (K):** 2500 (W), 3000 (horizontal), 3500 (vertical)
- **Weight (kg):** 60 (W), 60 (horizontal), 60 (vertical)
- **Maximum speed (mm/sec):** 8.90 (W), 8.90 (horizontal), 8.90 (vertical)
- **Maximum load (W):** 500 (W), 500 (horizontal), 500 (vertical)
- **Maximum load (L):** 500 (W), 500 (horizontal), 500 (vertical)
- **Maximum load (M):** 500 (W), 500 (horizontal), 500 (vertical)
- **Maximum load (W):** 500 (W), 500 (horizontal), 500 (vertical)

- **Note 1.** No load position is determined by the mechanical stoppers at both ends.
- **Note 2.** When installing the units, the weight limit cannot be exceeded. Use E: CE marking R: With RG1 P: PNP (Incremental) DN: DeviceNet TM

### Controller

- **Controller Operation method:** SR1-X10, RCV20022, RCV20022, RCV20022
- **Programming:** I/O point / Remote command
- **Operating method:** Operation using RS-232C communication
- **Remote command:** TS-X210, SR1-X10, RBR1
- **Pulse train control:** RBR1

**Note:** When using the unit vertically, a regeneration unit is required.
**Articulated robots**

**YA**

**Linear conveyor modules**

**LCM100**

**Compact single-axis robots**

**TRANSERVO**

**Motor-less single axis actuator**

**Robonity**

**Single-axis robots**

**FLIP-X**

**Linear motor single-axis robots**

**PHASER**

**Cartesian robots**

**XY-X**

**SCARA robots**

**YK-X**

**Pick & place robots**

**YP-X**

**CLEAN CONTROLLER INFORMATION**

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**F10H**

High lead type: Lead 30

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**Controller**

SR1-X > 540

TS-X > 514

RDV-X > 528

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**Notes:**

1. Stop positions are determined by the mechanical stoppers at both ends.
2. When installing the unit, washers, etc., cannot be used in the \( \phi 9.5 \) counter bore hole.
3. Minimum bend radius of motor cable is \( R50 \).
4. When using this \( \phi 10 \) knock-pin hole to position the robot body, the knockpin must not protrude more than 10mm inside the robot body.
5. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table above.