### Ordering method

<table>
<thead>
<tr>
<th>T4L</th>
<th>Load designation</th>
<th>Brake</th>
<th>Origin position change</th>
<th>Grease Type</th>
<th>Stroke</th>
<th>Cable length</th>
<th>Controller</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>Non-motor side</td>
<td>CC: Clean</td>
<td></td>
<td></td>
<td>ERCD</td>
</tr>
</tbody>
</table>

### Specifications

- **AC servo motor output (W)**: 30
- **Repeatability (mm)**: ±0.02
- **Deceleration mechanism**: Ball screw (8)
- **Ball screw lead (mm)**: 12
- **Maximum speed (mm/sec)**: 720
- **Maximum payload (kg)**: 6
- **Rated thrust (N)**: 32
- **Overall length (mm)**: 512
- **Maximum dimensions of cross section of main unit (mm)**: 84.5 × 103
- **Cable length (m)**: 16384
- **Linear guide type**: 2 rows of gothic arch grooves × 1 rail
- **Position detector**: Resolver
- **Resolution (Pulse/rotation)**: 16384

### Allowable overhang

- **Horizontal installation** (unit: mm): A: 2kg, B: 4.5kg, C: 7kg
- **Wall installation** (unit: mm): A: 2kg, B: 4.5kg, C: 7kg
- **Vertical installation** (unit: mm): A: 2.4kg, B: 5.7kg, C: 7.8kg

### Static loading moment

- **Controller**: Operation method
  - ERCD: Pulse train control / Programming / DO joint trace / Remote command / Operation using RS-232C communication

### Note

1. The robot cable is flexible and resists bending. See P.596 for details on robot cable.

### T4L

- **Approx. 250 (Motor cable length)**: 125.5 + 3
- **Effective stroke**: 72.5 + 3

### Controller

- **ERCD**: 512

### Cross-section B-B

- Note 1. Stop positions are determined by the mechanical stoppers at both ends.
- Note 2. Minimum bend radius of motor cable is 30mm.
- Note 3. Weight of models with no brake. The weight of brake-attached models is 0.2 kg heavier than the models with no brake shown in the table.
- Note 4. The under-head length of the hex socket-head bolt (M4×0.7) to be used for the installation work is 12mm or less.
- Note 5. External view of T4LH is identical to T4L.