Note 1. See P.153 for grease gun nozzles.
Note 2. If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, refer to the manual.

**Basic specifications**

**Motor**
- Motor type: 42|1Step motor
- Resolution (Pulse/rotation): 2048/1
- Deceleration mechanism: Ball screw
- Ball screw lead: 5 mm
- Maximum speed (mm/sec): 1000
- Maximum payload (kg): 20
- Maximum stroke (mm): 1000
- Lead 12
- Encoder resolution: 20480
- Encoder: 42

**Motor installation (Space-saving model)**

- A type: Motor installed on right
- L type: Motor installed on left

**Speed vs. payload**

**Running life**

5000 km on models other than shown below. Running life of only the model shown below becomes shorter than 5000 km depending on the payload, so check the running life curve.

**Controller**

- Controller: TS-S2
- Operation method: I/O point trace / Remote command
- Controller: TS-SH
- Operation method: TS-SD

**Note 1**. It is possible to apply only the axial load.
**Note 2**. The orientation of the width across flat part is undefined in the base surface.
**Note 3**. Use the support guide together to maintain the straightness.
**Note 4**. When running the cables, secure cables so that any load is not applied to the rod.
**Note 5**. Remove the M4 hex. socket head cap set bolts and use them to secure the cables. (Effective screw thread depth 5)
**Note 6**. The cable’s minimum bend radius is R30.
**Note 7**. Models with a brake will be 0.2 kg heavier.
**Note 8**. Distance to mechanical stopper.

**Controller Information**

- Controller: TS-S2
- Controller: TS-SH
- Controller: TS-SD

**Note 4**. See P.522 for DIN rail mounting bracket.
**Note 5**. Remove the M4 hex. socket head cap set bolts and use them to secure the cables.

**Motor-less single-axis robots**

**Cartesian robots**

**XY-X**

**YK-X**

**Pick & place robots**

**YP-X**

**CLEAN CONTROLLER INFORMATION**

- Battery:
- Voltage:
- Capacity:
- CE compliance:
- Origin on the non-motor side is selectable

**Controller Operation method**

- Remote command
- Pulse train control
SR03 Space-saving model (motor installed on top)

Option: Horizontal installation plate (foot)
* Contents of option: Plate, 2 pcs. See our robot manuals for additional settings.

Option: Vertical installation plate (flange)
* Two bolts are required for one plate.

Hex. socket head cap bolt (M3×0.5), Length under head 10

* See the bottom installation tap position.

Note 1. It is possible to apply only the axial load. Use the external guide together so that any radial load is not applied to the rod.
Note 2. The orientation of the width across flat part is undefined to the base surface.
Note 3. Use the support guide together to maintain the straightness.
Note 4. When running the cables, secure cables so that any load is not applied to them.
Note 5. Remove the M4 hex. socket head cap set bolts and use them to secure the cables. (Effective screw thread depth 5)
Note 6. The cable’s minimum bend radius is R30.
Note 7. Models with a brake will be 0.2kg heavier.
Note 8. Distance to mechanical stopper.