F8L

- High lead: Lead 30
- Origin on the non-motor side is selectable

Ordering method

F8L – [ ] – [ ] – [ ] – [ ] – [ ] – [ ]

Model	Lead designation	Brake Note 1	Origin position change	Grease type	Stroke	Cable length Note 2
	30: 30mm 20: 20mm 10: 10mm 5: 5mm	No entry:No brakes BK:Brakes provided	None: Standard Z: Non-motor side	None: Standard GC: Clean	150 to 1050 (50mm pitch)	3L: 3.5m 5L: 5m 10L: 10m 3K/5K/10K (Flexible cable)

TSX

Positioner Note 2	Driver: Power-supply voltage / Power capacity	LCD monitor	I/O selection	Battery
TSX: TS-X	105: 100V/100W or less 205: 200V/100W or less	No entry: None L: With LCD	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 4	B: With battery (Absolute) N: None (Incremental)

SR1-X 05

Controller	Driver: Power capacity	Usable for CE	I/O selection	Battery
	05: 100W or less	No entry: Standard E: CE marking	N: NPN P: PNP CC: CC-Link DN: DeviceNet™ PB: PROFIBUS	B: With battery (Absolute) N: None (Incremental)

RDV-X 2 05 – RBR1

Driver	Power-supply voltage	Driver: Power capacity	Regenerative unit
	2: AC200V	05: 100W or less	

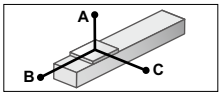
Note 1. The model with a lead of 30mm cannot select specifications with brake (vertical specifications).
Note 2. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.732 for details on robot cable.
Note 3. See P.634 for DIN rail mounting bracket.
Note 4. Select this selection when using the gateway function. For details, see P.96.

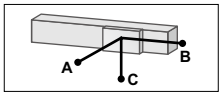
Specifications

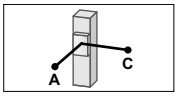
AC servo motor output (W)		100			
Repeatability Note 1 (mm)		+/-0.01			
Deceleration mechanism		Ball screw ϕ15			
Ball screw lead (mm)		30	20	10	5
Maximum speed Note 2 (mm/sec)		1800	1200	600	300
Maximum payload (kg)	Horizontal	7	20	40	50
	Vertical	–	4	8	16
Rated thrust (N)		56	84	169	339
Stroke (mm)		150 to 1050 (50mm pitch)			
Overall length (mm)	Horizontal	Stroke +300	Stroke+292		
	Vertical	–	Stroke+322		
Maximum dimensions of cross section of main unit (mm)		W80 × H65			
Cable length (m)		Standard: 3.5 / Option: 5,10			
Linear guide type		4 rows of circular arc grooves × 1 rail			
Position detector		Resolvers Note 3			
Resolution (Pulse/rotation)		16384			

Note 1. Positioning repeatability in one direction.
Note 2. When the stroke is longer than 650mm, 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. Position detectors (resolvers) are common to incremental and absolute specifications. If the controller has a backup function then it will be absolute specifications.

Allowable overhang Note







Horizontal installation (Unit: mm)

		A	B	C
Lead 30	5kg	112	80	80
Lead 20	7kg	78	43	49
	5kg	211	108	147
	10kg	116	45	69
	15kg	76	24	39
	20kg	58	14	26
Lead 10	10kg	251	56	122
	20kg	121	20	46
	30kg	74	8	20
	40kg	35	0	6
Lead 5	20kg	249	23	62
	30kg	170	10	29
	40kg	138	4	12
	50kg	51	0	0

Wall installation (Unit: mm)

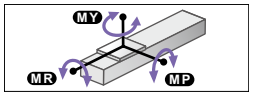
		A	B	C
Lead 30	5kg	55	57	77
Lead 20	7kg	21	19	34
	5kg	119	89	176
	10kg	38	26	69
	15kg	7	0	16
	20kg	0	0	0
Lead 10	10kg	85	39	202
	20kg	7	0	30
	30kg	0	0	0
	40kg	0	0	0
Lead 5	20kg	19	7	140
	30kg	0	0	0
	40kg	0	0	0
	50kg	0	0	0

Vertical installation (Unit: mm)

		A	C
Lead 20	2kg	236	240
	4kg	106	110
Lead 10	2kg	310	311
	4kg	141	143
	6kg	85	86
	8kg	57	58
Lead 5	5kg	123	124
	10kg	47	48
	15kg	22	22
	16kg	19	19

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

Static loading moment



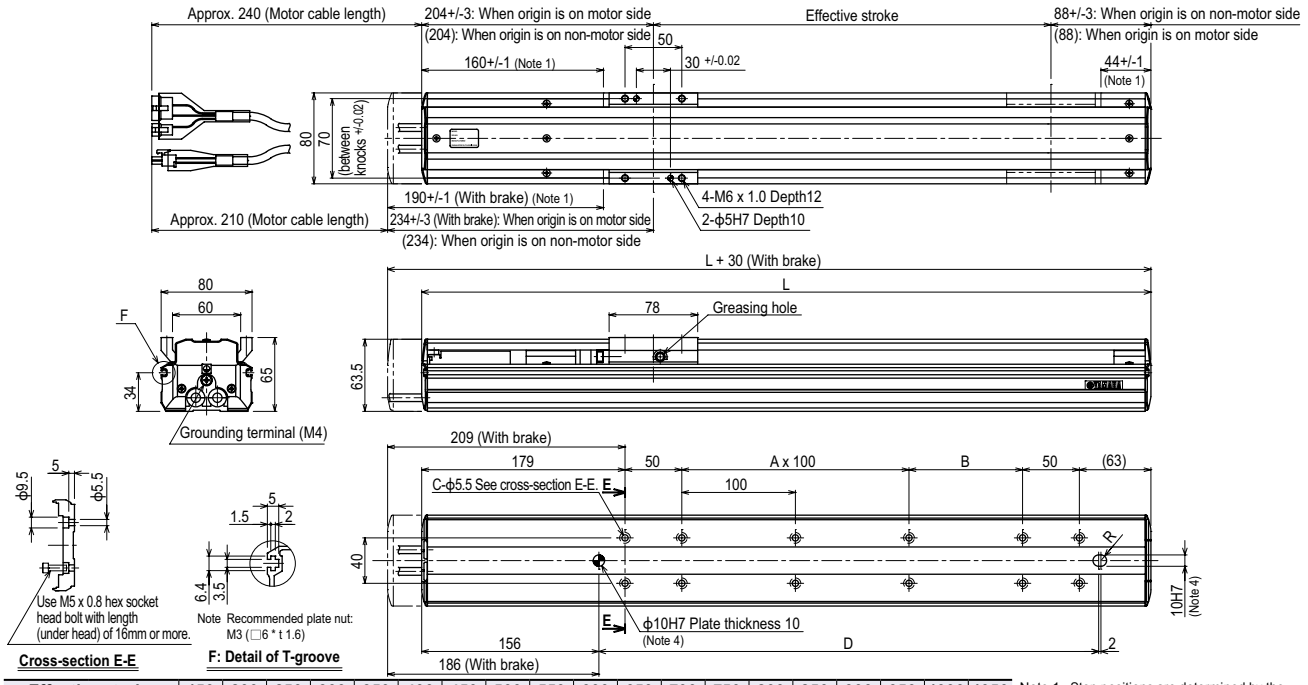
(Unit: N·m)

MY	MP	MR
70	95	110

Controller

Controller	Operation method
SR1-X05 RCX320 RCX221/222 RCX340	Programming / I/O point trace / Remote command / Operation using RS-232C communication
TS-X105 TS-X205	I/O point trace / Remote command
RDV-X205-RBR1	Pulse train control

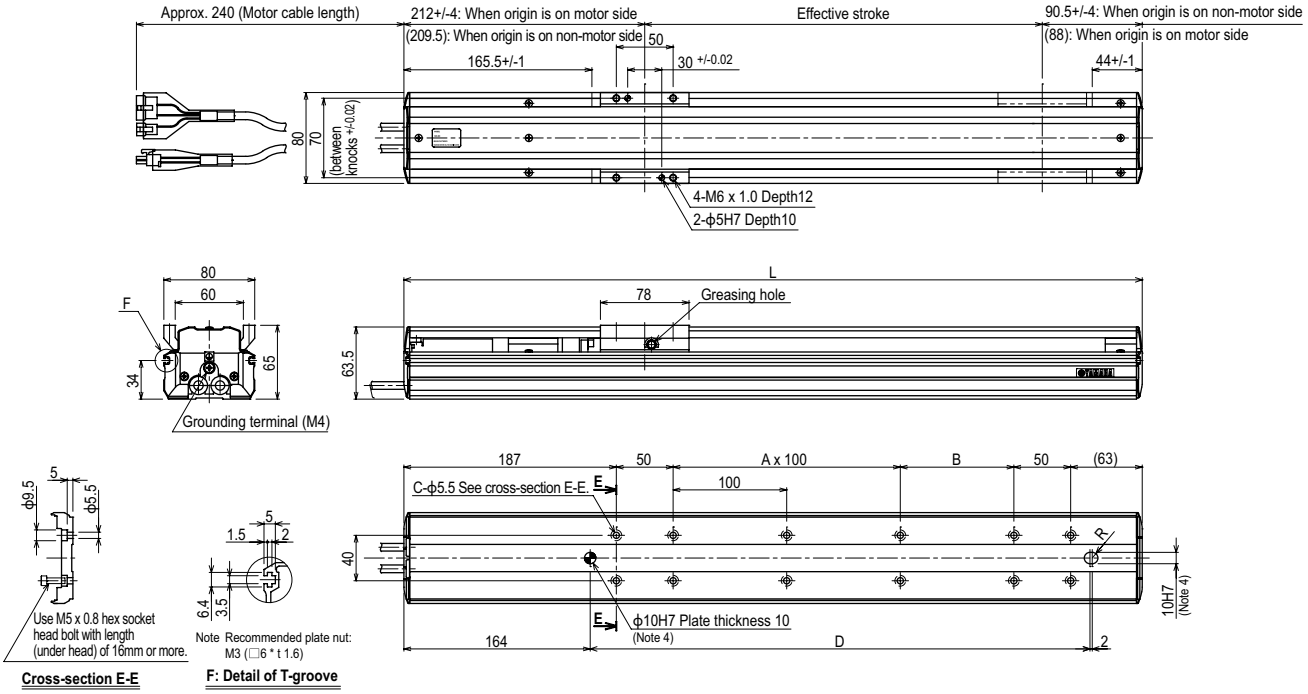
F8L



Effective stroke		150	200	250	300	350	400	450	500	550	600	650	700	750	800	850	900	950	1000	1050
L		442	492	542	592	642	692	742	792	842	892	942	992	1042	1092	1142	1192	1242	1292	1342
A		0	0	1	1	2	2	3	3	4	4	5	5	6	6	7	7	8	8	9
B		100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100
C		8	8	10	10	12	12	14	14	16	16	18	18	20	20	22	22	24	24	26
D		240	290	340	390	440	490	540	590	640	690	740	790	840	890	940	990	1040	1090	1140
Weight (kg) Note 5		3.9	4.2	4.5	4.8	5.1	5.4	5.7	6.1	6.4	6.7	7.0	7.3	7.6	7.9	8.2	8.5	8.8	9.2	9.5
Maximum speed Note 6 (mm/sec)	Lead 20	1200											1020	900	780	720	660	600	540	480
	Lead 10	600											510	450	390	360	330	300	270	240
	Lead 5	300											255	225	195	180	165	150	135	120
	Speed setting	–											85%	75%	65%	60%	55%	50%	45%	40%

Note 1. Stop positions are determined by the mechanical stoppers at both ends.
Note 2. When installing the robot, do not use washers inside the robot body.
Note 3. Minimum bend radius of motor cable is R50.
Note 4. When using this ϕ10 knock-pin hole to position the robot body, the knockpin must not protrude more than 10mm inside the robot body.
Note 5. Weight of models with no brake. The weight of brake-attached models is 0.3 kg heavier than the models with no brake shown in the table.
Note 6. When the stroke is longer than 650mm, 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.

F8L High lead type: Lead 30



Effective stroke		150	200	250	300	350	400	450	500	550	600	650	700	750	800	850	900	950	1000	1050
L		450	500	550	600	650	700	750	800	850	900	950	1000	1050	1100	1150	1200	1250	1300	1350
A		0	0	1	1	2	2	3	3	4	4	5	5	6	6	7	7	8	8	9
B		100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100	150	100
C		8	8	10	10	12	12	14	14	16	16	18	18	20	20	22	22	24	24	26
D		240	290	340	390	440	490	540	590	640	690	740	790	840	890	940	990	1040	1090	1140
Weight (kg)		3.9	4.2	4.5	4.8	5.1	5.4	5.7	6.1	6.4	6.7	7.0	7.3	7.6	7.9	8.2	8.5	8.8	9.2	9.5
Maximum speed (mm/sec) Note 5	Lead 30	1800											1530	1350	1170	1080	990	900	810	720
	Speed setting	–											85%	75%	65%	60%	55%	50%	45%	40%

Note 1. Stop positions are determined by the mechanical stoppers at both ends.
Note 2. When installing the robot, do not use washers inside the robot body.
Note 3. Minimum bend radius of motor cable is R50.
Note 4. When using this ϕ10 knock-pin hole to position the robot body, the knockpin must not protrude more than 10mm inside the robot body.

Note 5. When the stroke is longer than 650mm, 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.