

□ ẅ d ð Ր

Npmbsar Glqrpsarg

1 1
2 3
2.1 3
2.2 4
3 5
3.1 5
3.2 8
4 10
4.1 10
4.2 11
4.3 12
4.4 12
4.5 13
4.6 13
5 14
5.1 14
5.2 14
5.3 14
6 15

1



2

0 8mm

Z

+ ±0.1μm

2.1

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8mm

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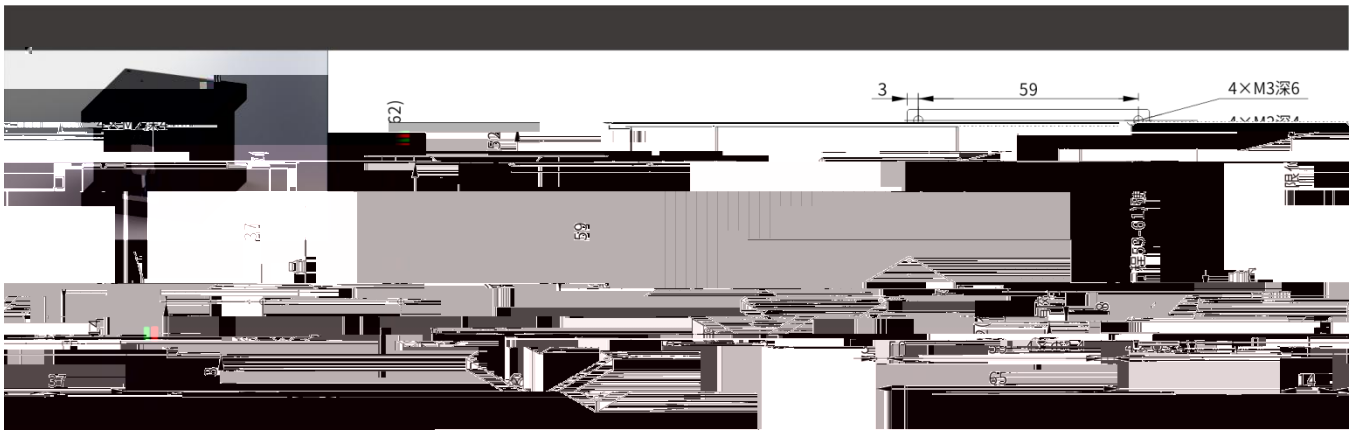
· SDK

Window Linux C/C++ C# Matlab LabVIEW

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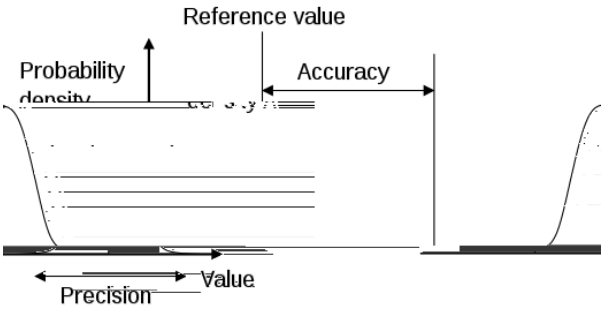
· EtherCAT

2.2



3

3.1



Y Y Z

Y (Straightness Z

(Flatness) 2

3.2

Model	
Travel(mm)	8
Load Capacity(Kg)[1]	0.5
Resolution(μm)	0.05
Min.Incremental Motion(μm)[2]	0.3
Undirection Repeatability[3]/Guaranteed(μm)[4]	±0.5 or 1
Undirection Repeatability/Typical(μm)	±0.2 or 0.4
Bi-Directional Repeatability/Guaranteed(μm)	±1 or 2
Bi-Directional Repeatability/Typical(μm)	±0.5 or 1
Accuracy[3]/Guaranteed(μm)	±2 or 4
Accuracy/Typical(μm)	±0.5 or 1
Max.Speed(mm/s)[5]	100
Straightness(μm)	5
Flatness(μm)	5
Continuous Force(N)	7.4
Peak Force(N)	29
Weight(kg)	0.6

4

4.1

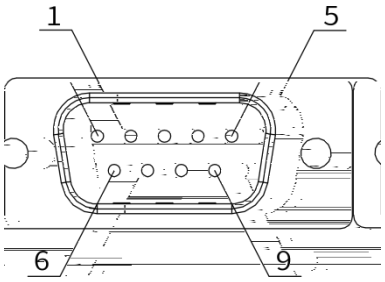
4.1.1

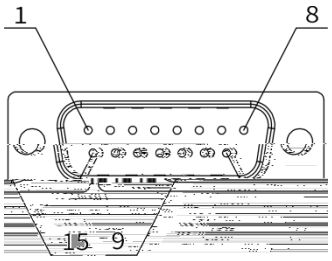
4.1.2

4.1.3

4.1.4

4.2

Motor wiring diagram		
 DB9		
	1	U
	2	/
	3	V
	4	/
	5	/
	6	/
	7	/
	8	/
	9	/

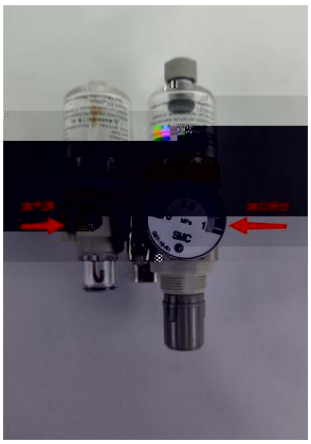
Encoder wiring diagram		
 DB15		
	1	5V+
	2	0V
	3	A+
	4	A-
	5	B+
	6	B-
	7	Z+
	8	Z-
	9	/

4.3

M3

(2.3)

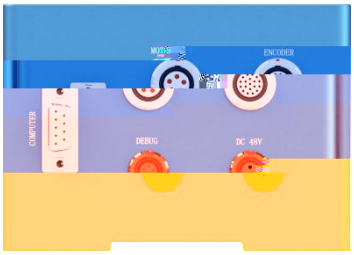
4.4



0Mpa

(0.5kg 0.2Mpa)

4.5

FMC04-MINI	
	

4.6

4.6.1

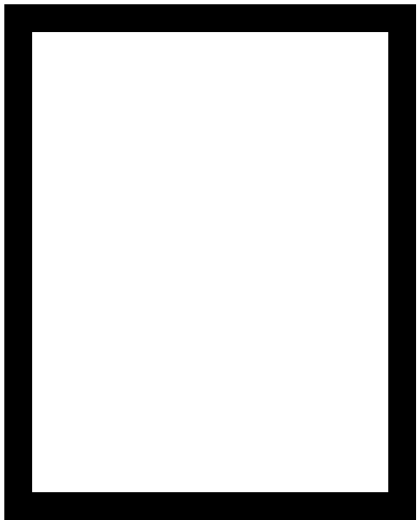
4.6.2

4.6.3

5

5.1

5.1.



6

6.1

A

B

C

D

E

F m"