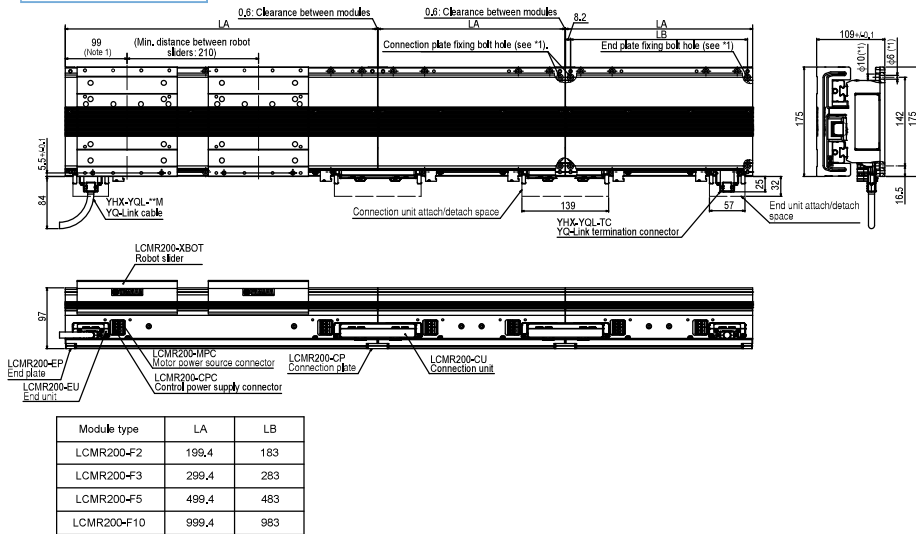


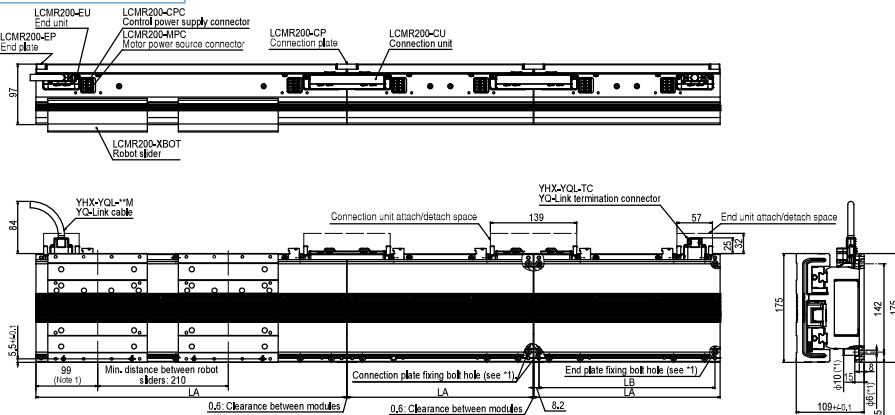
External view

LCMR200 Module connection and installation

Front* cable extraction

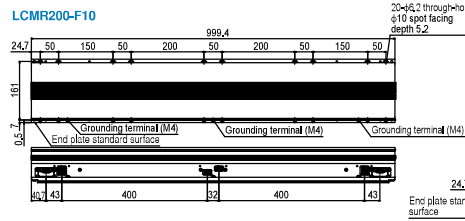
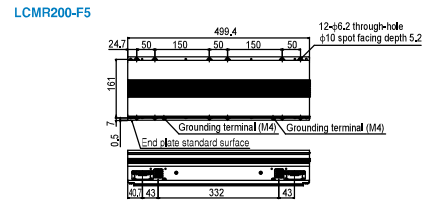
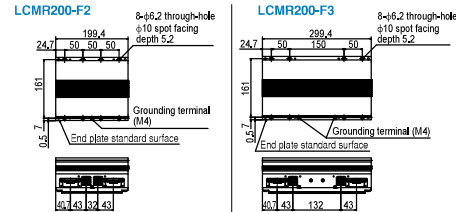


Rear* cable extraction

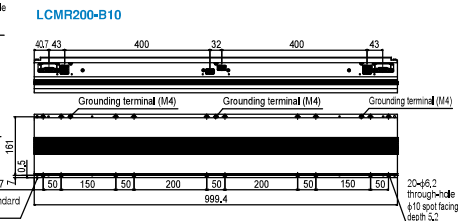
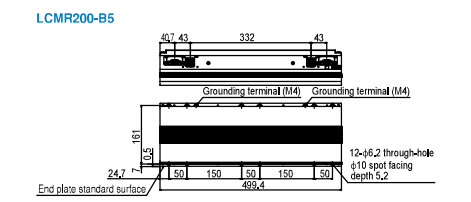
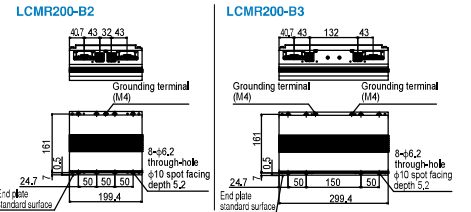


- Note 1. A robot slider is unable to stop in an area 99 mm from both ends of the line. The robot slider stopper juts out from the ends, which could cause collision. (The dimensions refer to the robot slider center.)
- Note 2. A module type can be freely combined on the same line after aligning the front/rear of the cable extraction direction.
- Note 3. The control power source and motor power source can be passed and received by the jumper connector. See the manual for detail of passing and receiving.
- Note 4. For the YQ-Link cable connection, always supply from the end unit that moving coordinate value is smaller. When passing with signal between lines, connect the YQ-Link cable to the end part end unit that moving coordinate value is larger, and connect to the end unit that moving coordinate value of the other line is smaller.
- Note 5. When not connecting the YQ-Link to other lines from the line end, attach the YQ-Link terminal connector.
- Note 6. Sixty-four robot sliders can be installed in a system connected by the YQ-Link cables* (depending on the number of robots that are controlled by the same controller).
- Note 7. Where modules are connected with the connection plate, the clearance between the adjacent modules is 0.6 mm.
- Note 8. The minimum pitch of each slider at the stopping state is 210 mm; however, when they start at the same time, they may collide due to operation conditions, and conditions such as command timing from the upper PLC, programming with YHX, etc. In the case, it is necessary to adjust by securing more distance (pitch) between the sliders, changing the start timing (sequential start), etc.
- Note 9. There is no mechanical stopper due to the nature of the product. Please install a mechanical stopper by the customer as needed.
- Note 10. For connection between modules, use a connection plate and connection unit, and for the line end, use an end plate and end unit.
- * It may differ depending on the system configuration.

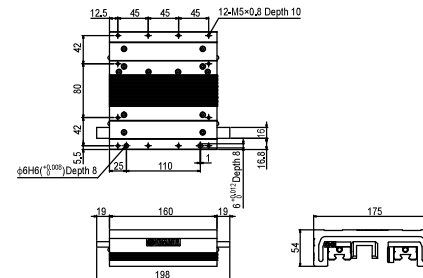
Linear module (Front* cable extraction)



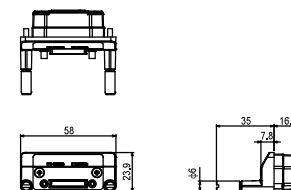
Linear module (Rear* cable extraction)



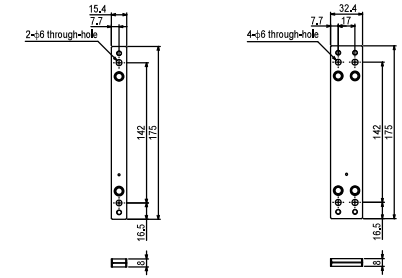
Robot slider



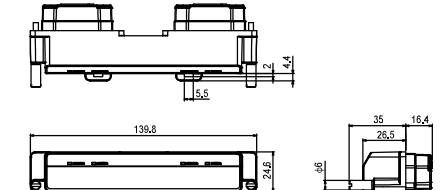
End unit



End plate



Connection unit



* The direction for the order of the driver numbers.