ENGINEERING DOCUMENTATION

Micro Servo Electric Cylinder

Dimensional & Integration Guide

DOCUMENT	REVISION / ISSUE	STATUS
DIG-ES-LA-C00-S007-V006	DRAFT-08 / 25 Aug 2026	Engineering Integration Reference

Integration Overview

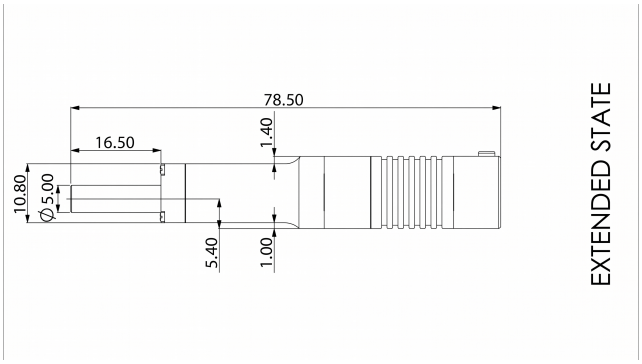
Compact electric actuator for robotic, medical and precision automation mechanisms. This guide supports mechanical-interface design, force and speed boundary , electrical and communication integration, cable routing, thermal and ingress and commissioning for ES-LA-C00-S007-V006.

Key Integration Facts

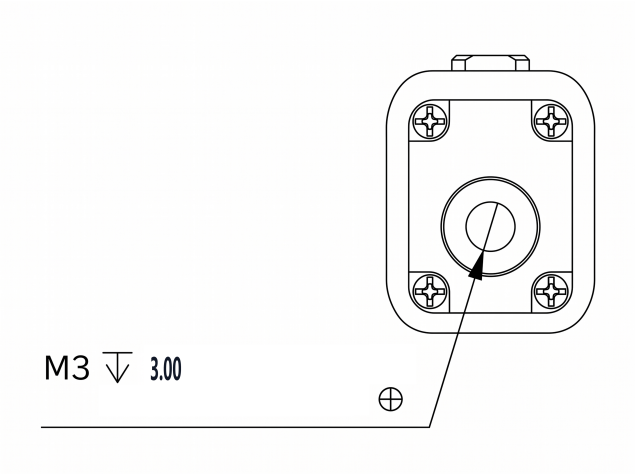
INTEGRATION ITEM	PUBLISHED VALUE
Maximum Push/Pull Force	42 N
Full-load Speed	21 mm/s
Stall Push/Pull Force	60 N
Maximum Self-locking Force	50 N
Electrical Interface	LVTTL serial interface
No-load Current	0.50 A
Mechanical Interface	Octagonal interface
Speed Grade	07

Product Structure & Views

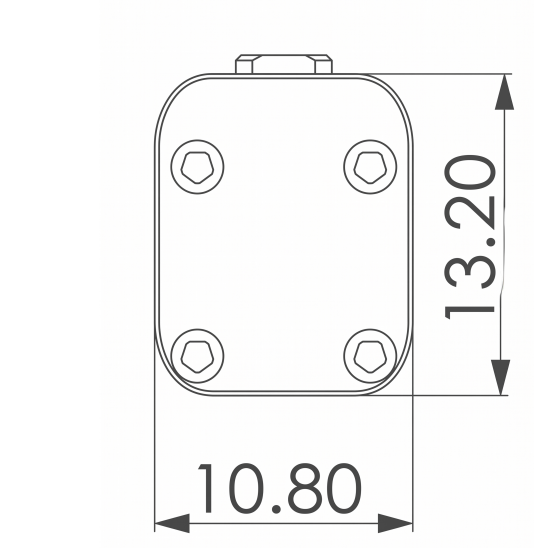
These views present the selected product structure, mounting interfaces and relevant integration geometry for this configuration.



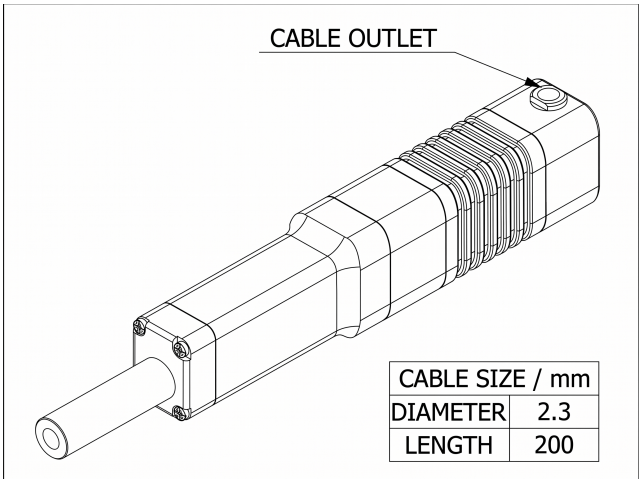
Mechanical View 1



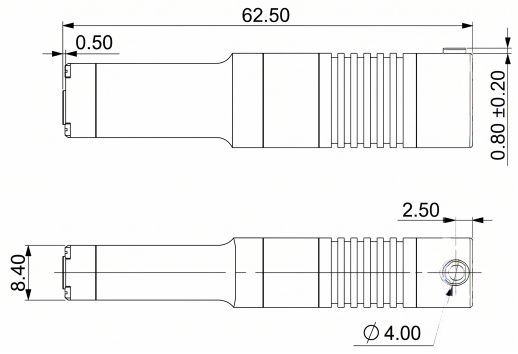
Mechanical View 2



Mechanical View 3



Mechanical View 4



Mechanical View 5

VIEW	FIELD	VALUE
Mechanical View 1	Total length in extended state	78.50 mm
	Front section partial length (extended end)	16.50 mm
	Neck / transition section width	1.40 mm
	Output shaft diameter	Φ5.00 mm
	Body outer diameter (visible in extended state)	10.80 mm
	View state label	Extended state
	Left step section axial length (lower dimension line)	5.40 mm
	Center step section axial length	1.00 mm
	Right step section axial length (lower dimension line)	5.40 mm
Mechanical View 2	Mounting face height (vertical)	13.20 mm
	Inner span width (smaller horizontal dimension)	10.80 mm
	Middle span width (intermediate horizontal dimension)	11.40 mm
	Overall width (largest horizontal dimension)	16.40 mm
Mechanical View 3	Shaft-end tapped hole specification and depth	M3 tapped hole, depth 3.00 mm
Mechanical View 4	Overall length (retracted)	62.50 mm
	End protrusion / step length	0.50 mm
	Threaded hole depth tolerance	0.80 ±0.20 mm
	Thread specification and depth	M1.60, depth 2.50 mm
	Right-end segment length	5.00 mm
	View state label	Retracted Position
	Output shaft diameter	Φ4.00 mm
	Right-end segment length (lower view)	2.50 mm
	Left-end feature length	8.40 mm
	Output shaft small-end diameter	Φ3.20 mm
	Output shaft diameter with tolerance	Φ3 -0.01/-0.03 mm

Overall Dimensions and Mounting Interface

PARAMETER	PUBLISHED VALUE	UNIT
Mechanical Interface	Octagonal interface	

- Confirm the selected series configuration and exact SKU before using dimensions or interface geometry.
- Keep mounting faces flat, clean and free of burrs, raised holes, debris and coating buildup.
- Reserve assembly, cable, inspection and removal access around the actuator and linkage interface.

Mechanical Load Path and Joint Interface

PARAMETER	PUBLISHED VALUE	UNIT
Mechanical Interface	Octagonal interface	

- Route axial force through the specified joint interface, adapter and host structure; include offset, side load, acceleration, shock and emergency-stop cases.
- Validate axial, radial and moment loads with the linkage, guide and host stiffness; do not infer system capacity from the actuator envelope alone.
- Protect the joint interface from binding, impact, uncontrolled bending and misalignment throughout the stroke.

Power, Communication and Cable Integration

PARAMETER	PUBLISHED VALUE	UNIT
Electrical Interface	LVTTL serial interface	
No-load Current	0.50	A

- Use the published supply range and current boundary for this SKU, with suitable protection for normal, peak and fault conditions.
- Verify the selected communication interface, electrical levels, address or protocol settings and control-cycle compatibility before motion.
- Provide cable slack, bend radius and strain relief across the complete actuator and host motion envelope.
- Separate power, communication and low-level sensing paths according to the system EMC and grounding architecture.

Force, Position and Motion Validation

PARAMETER	PUBLISHED VALUE	UNIT
Maximum Push/Pull Force	42	N
Full-load Speed	21	mm/s
Stall Push/Pull Force	60	N
Maximum Self-locking Force	50	N
Speed Grade	07	

- Treat the published force-sensor detection range as a measurement boundary, not as complete actuator thrust or machine safety approval.
- Commission in stages with linkage, limits, guards and cable routing installed; verify each boundary before increasing speed or load.
- At low energy, verify position direction, command polarity, travel limits, communication status and force-signal mapping.

Thermal, Ingress and Maintenance Conditions

- Validate temperature using the installed voltage, peak current, load cycle, mounting heat path, ambient condition and enclosure.
- Treat IP40 as a product-boundary condition; validate connectors, cable entry, linkage and complete host protection separately.
- Prevent chips, fibers, cleaning residue and moisture from entering interfaces, cable exits and moving joints.
- Stop and inspect after binding, impact, abnormal noise, rising temperature, unexpected friction, communication loss or protection damage.

Commissioning and Safety

- Commission in stages with linkage, limits, guards and cable routing installed; verify each boundary before increasing speed or load.
- Before full-power operation, verify polarity, end limits, emergency stop, fault response and safe recovery behavior.
- Stop and inspect after binding, impact, abnormal noise, rising temperature, unexpected friction, communication loss or protection damage.

Integration Checklist

01	Confirm the drawing, published parameters and applicable wiring data identify this SKU.
02	Verify mechanical interface, joint bearing, adapter, orientation and service clearance.
03	Establish and validate the complete axial, side-load and moment load path.
04	Confirm supply range, peak current, communication interface, polarity and controller compatibility.
05	Provide cable slack, bend radius and strain relief across the full motion envelope.
06	Separate power, communication and low-level sensor paths according to the EMC architecture.
07	Treat force-sensor range as a measurement boundary and complete system-level load validation.
08	At low speed and low load verify position, direction, limits, communication and force-signal mapping.
09	Validate temperature, friction, noise, protection boundary and abnormal-stop behavior over the duty cycle.
10	Include specified 2D, STEP, wiring, commissioning and maintenance data in integration planning.

View SKU Product Datasheet **Request controlled 2D drawing** **Request controlled STEP review** **Request a Quote**

Engineering Use and Verification Notice

01. This Dimensional & Integration Guide applies only to EmbodyStack SKU ES-LA-C00-S007-V006 and is intended for dimensional evaluation and preliminary integration. It is not a applicable manufacturing drawing, actuator selection approval, force or safety approval, wiring final integration, machinery risk assessment, safety validation or integration planning document and must not be used as the sole basis for machining, linkage design, fastener selection, cable assembly, drive configuration or final integration. Before design freeze, assembly or commissioning, verify dimensions, interface geometry, load path, power, communication, polarity, cable routing, force and speed boundaries, temperature, ingress, limits, thermal behavior, maintenance and fault handling against the applicable EmbodyStack engineering data for this exact SKU. Where this guide and applicable product documentation differ, the applicable product documentation governs. Validate the complete actuator, linkage, drive, host structure, motion cycle, guarding, fault cases and applicable regulatory requirements under intended operating conditions.