ENGINEERING DOCUMENTATION

Micro Servo Electric Cylinder

Dimensional & Integration Guide

DOCUMENT	REVISION / ISSUE	STATUS
DIG-ES-LA-C00-S010-V002	DRAFT-08 / 25 Aug 2026	Engineering Integration Reference

Integration Overview

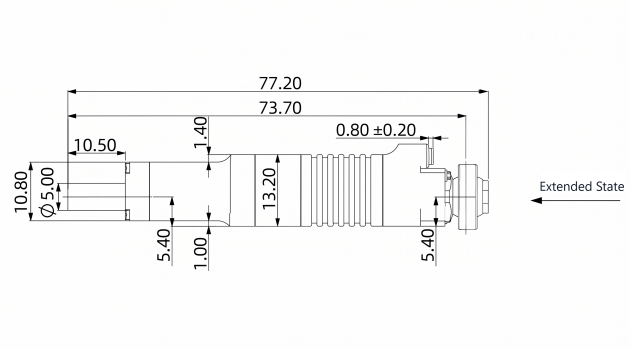
Compact electric actuator for robotic, medical and precision automation mechanisms. This guide supports mechanical-interface design, force and speed boundary , electrical and communication integration, cable routing, thermal and ingress and commissioning for ES-LA-C00-S010-V002.

Key Integration Facts

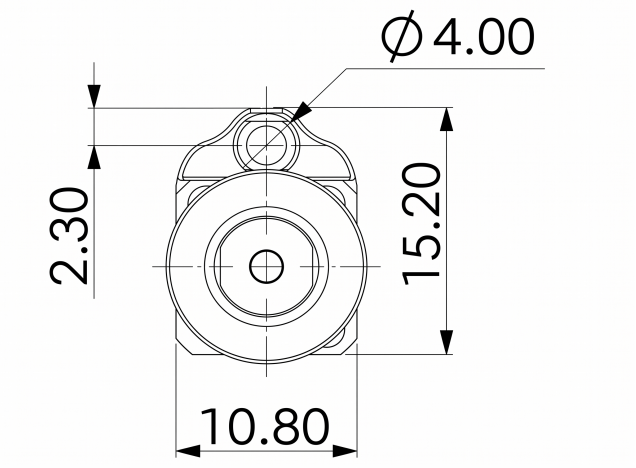
INTEGRATION ITEM	PUBLISHED VALUE
Maximum Push/Pull Force	56 N
Full-load Speed	16 mm/s
Stall Push/Pull Force	80 N
Maximum Self-locking Force	100 N
Electrical Interface	LVTTL serial interface
No-load Current	0.27 A
Mechanical Interface	Joint bearing
Speed Grade	03

Product Structure & Views

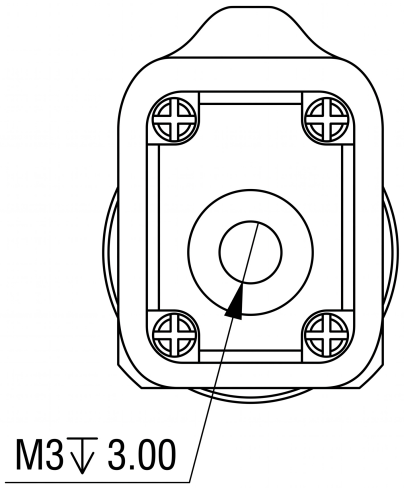
These views present the selected product structure, mounting interfaces and relevant integration geometry for this configuration.



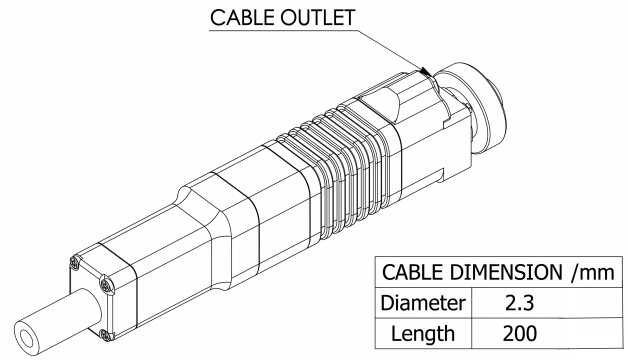
Mechanical View 1



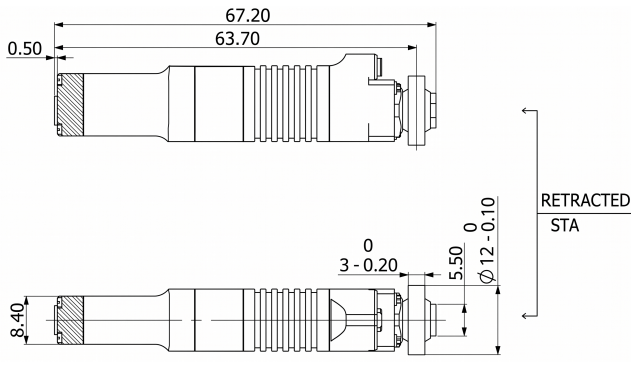
Mechanical View 2



Mechanical View 3



Mechanical View 4



Mechanical View 5

VIEW	FIELD	VALUE
Mechanical View 1	Overall length in extended state	Overall extended length 77.20 mm
	Extended state body length	Extended body length 73.70 mm
	End axial clearance or travel allowance	0.80 ± 0.20 mm
	Shoulder step offset	Step offset 1.40 mm
	Left shaft interface axial length	Left shaft interface length 10.50 mm
	Left shaft diameter	Diameter 5.00 mm
	Left end outer height	Outer height 10.80 mm
	Middle body outer height	Middle body outer height 13.20 mm
	State label	Extended state
	Left lower local height	Local height 5.40 mm
	Right end local height	Local height 5.40 mm
	Lower step offset	Lower step offset 1.00 mm
Mechanical View 2	Top small hole diameter	Diameter 4.00
	Left local vertical dimension	2.30
	Right overall vertical dimension	15.20
	Bottom width dimension	10.80
Mechanical View 3	M3 threaded hole depth	M3 thread, depth 3.00
Mechanical View 5	Retracted overall length	67.20
	Retracted internal length to end feature	63.70
	End offset dimension	0.50
	Retracted state label	Retracted state
	Joint bearing interface diameter with tolerance	Diameter 12, upper tolerance 0, lower tolerance -0.10
	Interface spacing dimension	5.50
	End step width with tolerance	3, upper tolerance 0, lower tolerance -0.20
	Left end height dimension	8.40

Overall Dimensions and Mounting Interface

PARAMETER	PUBLISHED VALUE	UNIT
Mechanical Interface	Joint bearing	

- 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	Joint bearing	

- 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	0.27	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	56	N
Full-load Speed	16	mm/s
Stall Push/Pull Force	80	N
Maximum Self-locking Force	100	N
Speed Grade	03	

- 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-S010-V002 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.