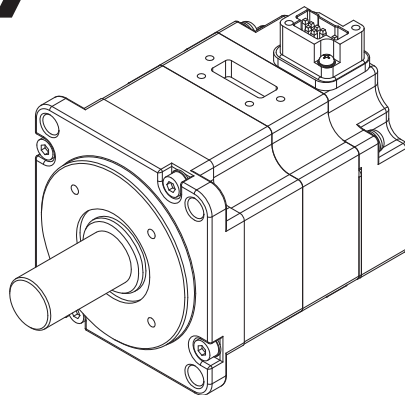


# $\Sigma$ -7-Series AC Servo Drive Rotary Servomotor Product Manual

Model: SGM7J/SGM7A/SGM7G



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## About this Manual

This manual provides information required to select, install, connect, and maintain Rotary Servomotors for  $\Sigma$ -7-Series AC Servo Drives.

Read and understand this manual to ensure correct usage of the  $\Sigma$ -7-Series AC Servo Drives.

Keep this manual in a safe place so that it can be referred to whenever necessary.

## Outline of Manual

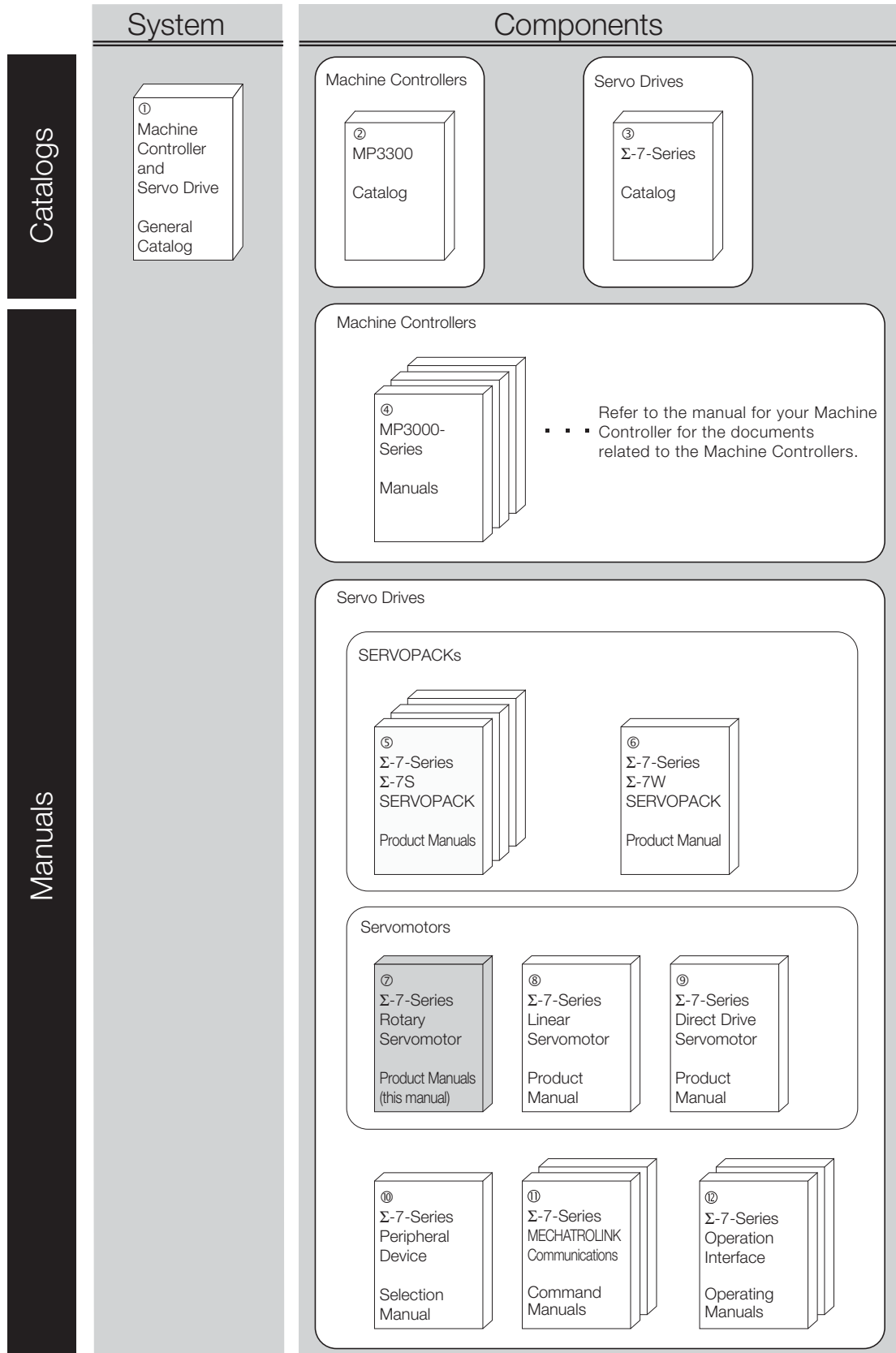
The contents of the chapters of this manual are described in the following table.

Refer to these chapters as required.

Chapter	Chapter Title	Contents
1	Basic Information on Servomotors	Provides basic information on Rotary Servomotors, including Servomotor part names and combinations with SERVOPACKs.
2	Capacity Selection	Describes calculation methods to use when selecting Servomotor capacities.
3	Specifications, Ratings, and External Dimensions of SGM7A Servomotors	Describes how to interpret the model numbers of SGM7A Servomotors and gives their specifications, ratings, and external dimensions.
4	Specifications, Ratings, and External Dimensions of SGM7J Servomotors	Describes how to interpret the model numbers of SGM7J Servomotors and gives their specifications, ratings, and external dimensions.
5	Specifications, Ratings, and External Dimensions of SGM7G Servomotors	Describes how to interpret the model numbers of SGM7G Servomotors and gives their specifications, ratings, and external dimensions.
6	Servomotor Installation	Describes the installation conditions, procedures, and precautions for Servomotors.
7	Connections between Servomotors and SERVOPACKs	Describes the cables that are used to connect the Servomotors and SERVOPACKs and provides related precautions.
8	Maintenance and Inspection	Describes the maintenance, inspection, and disposal of a Servomotor.
9	Appendices	Provide additional information on Servomotors with Gears and reference information on selecting Servomotor capacity.

# Related Documents

The relationships between the documents that are related to the Servo Drives are shown in the following figure. The numbers in the figure correspond to the numbers in the table on the following pages. Refer to these documents as required.



Classification	Document Name	Document No.	Description
① Machine Controller and Servo Drive General Catalog	Machine Controller and Servo Drive Solutions Catalog	KAEP S800001 22	Provides detailed information required to select MP3000-Series Machine Controllers and $\Sigma$ -7-Series AC Servo Drives.
② MP3300 Catalog	Machine Controller MP3300	KAEP C880725 03	Provides detailed information on MP3300 Machine Controllers, including features and specifications.
③ $\Sigma$ -7-Series Catalog	AC Servo Drives $\Sigma$ -7 Series	KAEP S800001 23	Provides detailed information on $\Sigma$ -7-Series AC Servo Drives, including features and specifications.
④ MP3000-Series Manuals	Machine Controller MP3000 Series MP3300 Product Manual	SIEP C880725 21	Describes the functions, specifications, operating methods, maintenance, inspections, and troubleshooting of the MP3000-series MP3300 Machine Controllers.
⑤ $\Sigma$ -7-Series $\Sigma$ -7S SERVOPACK Product Manuals	$\Sigma$ -7-Series AC Servo Drive $\Sigma$ -7S SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 28	Provide detailed information on selecting $\Sigma$ -7-Series SERVOPACKs and information on installing, connecting, setting, performing trial operation for, tuning, and monitoring the Servo Drives.
	$\Sigma$ -7-Series AC Servo Drive $\Sigma$ -7S SERVOPACK with MECHATROLINK-II Communications References Product Manual	SIEP S800001 27	
	$\Sigma$ -7-Series AC Servo Drive $\Sigma$ -7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual	SIEP S800001 26	
⑥ $\Sigma$ -7-Series $\Sigma$ -7W SERVOPACK Product Manual	$\Sigma$ -7-Series AC Servo Drive $\Sigma$ -7W SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 29	
⑦ $\Sigma$ -7-Series Rotary Servomotor Product Manual	$\Sigma$ -7-Series AC Servo Drive Rotary Servomotor Product Manual	This manual (SIEP S800001 36)	
⑧ $\Sigma$ -7-Series Linear Servomotor Product Manual	$\Sigma$ -7-Series AC Servo Drive Linear Servomotor Product Manual	SIEP S800001 37	Provide detailed information on selecting, installing, and connecting the $\Sigma$ -7-Series Servomotors.
⑨ $\Sigma$ -7-Series Direct Drive Servomotor Product Manual	$\Sigma$ -7-Series AC Servo Drive Direct Drive Servomotor Product Manual	SIEP S800001 38	

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Classification	Document Name	Document No.	Description
⑩ Σ-7-Series Peripheral Device Selection Manual	Σ-7-Series AC Servo Drive Peripheral Device Selection Manual	SIEP S800001 32	Describes the peripheral devices for a Σ-7-Series Servo System.
⑪ Σ-7-Series MECHATROLINK Communications Command Manuals	Σ-7-Series AC Servo Drive MECHATROLINK-II Communications Command Manual	SIEP S800001 30	Provides detailed information on the MECHATROLINK-II communi- cations commands that are used for a Σ-7-Series Servo System.
	Σ-7-Series AC Servo Drive MECHATROLINK-III Communications Standard Servo Profile Command Manual	SIEP S800001 31	Provides detailed information on the MECHATROLINK-III communi- cations standard servo profile com- mands that are used for a Σ-7- Series Servo System.
⑫ Σ-7-Series Operation Interface Operating Manuals	Σ-7-Series AC Servo Drive Digital Operator Operating Manual	SIEP S800001 33	Describes the operating proce- dures for a Digital Operator for a Σ-7-Series Servo System.
	AC Servo Drives Engineering Tool SigmaWin+ Online Manual Σ-7 Component	SIEP S800001 48	Provides detailed operating proce- dures for the SigmaWin+ Engineer- ing Tool for a Σ-7-Series Servo System.

# Using This Manual

## ◆ Technical Terms Used in This Manual

The following terms are used in this manual.


Term	Meaning
Servomotor	A $\Sigma$ -7-Series Rotary Servomotor, Direct Drive Servomotor, or Linear Servomotor.
SERVOPACK	A $\Sigma$ -7-Series $\Sigma$ -7S Servo Amplifier.
Servo Drive	The combination of a Servomotor and SERVOPACK.
Main Circuit Cable	One of the cables that connect to the main circuit terminals, including the Main Circuit Power Supply Cable, Control Power Supply Cable, and Servomotor Main Circuit Cable.

## ◆ Trademarks

- MECHATROLINK is a trademark of the MECHATROLINK Members Association.
- QR code is a trademark of Denso Wave Inc.
- Other product names and company names are the trademarks or registered trademarks of the respective company. "TM" and the ® mark do not appear with product or company names in this manual.


## ◆ Visual Aids

The following aids are used to indicate certain types of information for easier reference.



Important

Indicates precautions or restrictions that must be observed.  
Also indicates alarm displays and other precautions that will not result in machine damage.



Term

Indicates definitions of difficult terms or terms that have not been previously explained in this manual.

**Example** Indicates operating or setting examples.

**Information** Indicates supplemental information to deepen understanding or useful information.

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# Safety Precautions

## ◆ Safety Information

To prevent personal injury and equipment damage in advance, the following signal words are used to indicate safety precautions in this document. The signal words are used to classify the hazards and the degree of damage or injury that may occur if a product is used incorrectly. Information marked as shown below is important for safety. Always read this information and heed the precautions that are provided.

### **DANGER**

- Indicates precautions that, if not heeded, are likely to result in loss of life, serious injury, or fire.

### **WARNING**

- Indicates precautions that, if not heeded, could result in loss of life, serious injury, or fire.

### **CAUTION**

- Indicates precautions that, if not heeded, could result in relatively serious or minor injury, or in fire.

### **NOTICE**

- Indicates precautions that, if not heeded, could result in property damage.



## ◆ Safety Precautions That Must Always Be Observed

### ■ General Precautions



## DANGER

- Read and understand this manual to ensure the safe usage of the product.
- Keep this manual in a safe, convenient place so that it can be referred to whenever necessary. Make sure that it is delivered to the final user of the product.
- Do not remove covers, cables, connectors, or optional devices while power is being supplied to the SERVOPACK.  
There is a risk of electric shock, operational failure of the product, or burning.



## WARNING

- Connect the ground terminals on the SERVOPACK and Servomotor to ground poles according to local electrical codes (100  $\Omega$  or less for a SERVOPACK with a 100-VAC or 200-VAC power supply, and 10  $\Omega$  or less for a SERVOPACK with a 400-VAC power supply).  
There is a risk of electric shock or fire.
- Do not attempt to disassemble, repair, or modify the product.  
There is a risk of fire or failure.  
The warranty is void for the product if you disassemble, repair, or modify it.



## CAUTION

- The SERVOPACK heat sinks, regenerative resistors, Servomotors, and other components can be very hot while power is ON or soon after the power is turned OFF. Implement safety measures, such as installing covers, so that hands and parts such as cables do not come into contact with hot components.  
There is a risk of burn injury.
- Do not damage, pull on, apply excessive force to, place heavy objects on, or pinch cables.  
There is a risk of failure, damage, or electric shock.
- Do not use the product in an environment that is subject to water, corrosive gases, or flammable gases, or near flammable materials.  
There is a risk of electric shock or fire.

## NOTICE

- Do not attempt to use a SERVOPACK or Servomotor that is damaged or that has missing parts.
- Install external emergency stop circuits that shut OFF the power supply and stops operation immediately when an error occurs.
- Select the brake power supply for a Servomotor with a Holding Brake according to the power supply voltage and capacity required for the Servomotor model, as given in manuals and catalogs. Also confirm the input voltage to the holding brake.
- Always install a surge absorber as a protective device between the brake power supply and Servomotor.  
There is a risk of damage to the Servomotor.
- The time required for a holding brake to operate depends on the types of protective devices. The time required for a holding brake to operate will also change if holding brakes are connected in parallel. Always check the time required for a holding brake to operate on the actual machine before you operate a Servomotor.
- Always use a Servomotor and SERVOPACK in one of the specified combinations.
- Do not touch a SERVOPACK or Servomotor with wet hands.  
There is a risk of product failure.

## ■ Storage Precautions

### CAUTION

- Do not place an excessive load on the product during storage. (Follow all instructions on the packages.)  
There is a risk of injury or damage.

### NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiationIf you store or install the product in any of the above locations, the product may fail or be damaged.
- Although machined surfaces are covered with an anticorrosive coating, rust can develop due to storage conditions or the length of storage. If you store the product for more than six months, reapply an anticorrosive coating to machined surfaces, particularly the motor shaft.
- Consult with your Yaskawa representative if you have stored products for an extended period of time.

## ■ Transportation Precautions

### CAUTION

- Transport the product in a way that is suitable to the mass of the product.
- Do not hold onto the cables or motor shaft when you move a Servomotor.  
There is a risk of disconnection, damage, or injury.
- Do not use the eyebolts on a SERVOPACK or Servomotor to move the machine.  
There is a risk of damage or injury.
- When you handle a SERVOPACK or Servomotor, be careful of sharp parts, such as the corners.  
There is a risk of injury.
- Do not place an excessive load on the product during transportation. (Follow all instructions on the packages.)  
There is a risk of injury or damage.

## NOTICE

- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock. There is a risk of failure or damage.
- Do not subject connectors to shock. There is a risk of faulty connections or damage.
- If disinfectants or insecticides must be used to treat packing materials such as wooden frames, plywood, or pallets, the packing materials must be treated before the product is packaged, and methods other than fumigation must be used.  
Example: Heat treatment, where materials are kiln-dried to a core temperature of 56°C for 30 minutes or more.  
If the electronic products, which include stand-alone products and products installed in machines, are packed with fumigated wooden materials, the electrical components may be greatly damaged by the gases or fumes resulting from the fumigation process. In particular, disinfectants containing halogen, which includes chlorine, fluorine, bromine, or iodine can contribute to the erosion of the capacitors.
- Do not overtighten the eyebolts on a SERVOPACK or Servomotor. If you use a tool to overtighten the eyebolts, the tapped holes may be damaged.

### ■ Installation Precautions

## CAUTION

- Do not touch the key slot with your bare hands on the shaft end on a Servomotor with a Key Slot. There is a risk of injury.
- Securely mount the Servomotor to the machine. If the Servomotor is not mounted securely, it may come off the machine during operation.
- Install the Servomotor or SERVOPACK in a way that will support the mass given in technical documents.
- Install SERVOPACKs, Servomotors, and regenerative resistors on nonflammable materials. Installation directly onto or near flammable materials may result in fire.
- Do not step on or place a heavy object on the product. There is a risk of failure, damage, or injury.
- Do not allow any foreign matter to enter the SERVOPACK or Servomotor. There is a risk of failure or fire.
- Implement safety measures, such as installing a cover so that the rotating part of the Servomotor cannot be touched accidentally during operation.

## NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiationIf you store or install the product in any of the above locations, the product may fail or be damaged.
- Use the product in an environment that is appropriate for the product specifications.  
If you use the product in an environment that exceeds product specifications, the product may fail or be damaged.
- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock.  
There is a risk of failure or damage.
- A Servomotor is a precision device. Do not subject the output shaft or the main body of the Servomotor to strong shock.
- Design the machine so that the thrust and radial loads on the motor shaft during operation do not exceed the allowable values given in the catalog.
- When you attach the key to the motor shaft, do not subject the key slot to direct shock.
- Do not allow any foreign matter to enter a SERVOPACK or a Servomotor with a Cooling Fan and do not cover the outlet from the Servomotor's cooling fan.  
There is a risk of failure.
- If you use oil as the gear lubricant, always inject the specified oil before starting operation.
- You can install the Servomotor either horizontally or vertically. However, if you install a Servomotor with an Oil Seal with the output shaft facing upward, oil may enter the Servomotor depending on the operating conditions. Confirm the operating conditions sufficiently if you install a Servomotor with the output shaft facing upward. Some Servomotors with Gears have restrictions on the installation orientation. Refer to the relevant technical documents.
- If an installation orientation is specified for a Servomotor with a Gear, install the Servomotor in the specified orientation.  
There is a risk of failure due to oil leakage.
- For a Servomotor with an Oil Seal, use the Servomotor with the oil seal in a lubricated condition with only splashing of oil.  
If the Servomotor is used with the oil seal under the surface of the oil, oil may enter the Servomotor, possibly resulting in failure.
- The shaft opening of a Servomotor is not waterproof or oilproof. Implement measures in the machine to prevent water or cutting oil from entering the Servomotor.  
There is a risk of failure.
- In an application where the Servomotor would be subjected to large quantities of water or oil, implement measures to protect the Servomotor from large quantities of liquid, such as installing covers to protect against water and oil.
- In an environment with high humidity or oil mist, face Servomotor lead wires and connectors downward and provide cable traps.  
There is a risk of failure or fire due to insulation failure or accidents from short circuits.

### ■ Wiring Precautions



## DANGER

- Do not change any wiring while power is being supplied.  
There is a risk of electric shock or injury.



## WARNING

- **Wiring and inspections must be performed only by qualified engineers.**  
There is a risk of electric shock or product failure.
- **Check all wiring and power supplies carefully.**  
Incorrect wiring or incorrect voltage application to the output circuits may cause short-circuit failures. If a short-circuit failure occurs as a result of any of these causes, the holding brake will not work. This could damage the machine or cause an accident that may result in death or injury.



## CAUTION

- **Observe the precautions and instructions for wiring and trial operation precisely as described in this document.**  
Failures caused by incorrect wiring or incorrect voltage application in the brake circuit may cause the SERVOPACK to fail, damage the equipment, or cause an accident resulting in death or injury.
- **Check the wiring to be sure it has been performed correctly.**  
Connectors and pin layouts are sometimes different for different models. Always confirm the pin layouts in technical documents for your model before operation.  
There is a risk of failure or malfunction.
- **Connect wires to power supply terminals and motor connection terminals securely with the specified methods and tightening torque.**  
Insufficient tightening may cause wires and terminal blocks to generate heat due to faulty contact, possibly resulting in fire.
- **Use shielded twisted-pair cables or screened unshielded multi-twisted-pair cables for I/O Signal Cables and Encoder Cables.**
- **Observe the following precautions when wiring the SERVOPACK's main circuit terminals.**
  - Turn ON the power supply to the SERVOPACK only after all wiring, including the main circuit terminals, has been completed.
  - If a connector is used for the main circuit terminals, remove the main circuit connector from the SERVOPACK before you wire it.
  - Insert only one wire per insertion hole in the main circuit terminals.
  - When you insert a wire, make sure that the conductor wire (e.g., whiskers) does not come into contact with adjacent wires.

## NOTICE

- **Whenever possible, use the Cables specified by Yaskawa.**  
If you use any other cables, confirm the rated current and application environment of your model and use the wiring materials specified by Yaskawa or equivalent materials.
- **Securely tighten cable connector screws and lock mechanisms.**  
Insufficient tightening may result in cable connectors falling off during operation.
- **Do not bundle power lines (e.g., the Main Circuit Cable) and low-current lines (e.g., the I/O Signal Cables or Encoder Cables) together or run them through the same duct. If you do not place power lines and low-current lines in separate ducts, separate them by at least 30 cm.**  
If the cables are too close to each other, malfunctions may occur due to noise affecting the low-current lines.
- **For a motor with a cooling fan, check the rotation direction of the cooling fan after you wire the fan.**
- **Install a battery at either the host controller or on the Encoder Cable.**  
If you install batteries both at the host controller and on the Encoder Cable at the same time, you will create a loop circuit between the batteries, resulting in a risk of damage or burning.
- **When connecting a battery, connect the polarity correctly.**  
There is a risk of battery rupture or encoder failure.

## ■ Operation Precautions

### **WARNING**

- Before starting operation with a machine connected, change the settings of the switches and parameters to match the machine.  
Unexpected machine operation, failure, or personal injury may occur if operation is started before appropriate settings are made.
- Do not radically change the settings of the parameters.  
There is a risk of unstable operation, machine damage, or injury.
- Install limit switches or stoppers at the ends of the moving parts of the machine to prevent unexpected accidents.  
There is a risk of machine damage or injury.
- For trial operation, securely mount the Servomotor and disconnect it from the machine.  
There is a risk of injury.
- Forcing the motor to stop for overtravel is disabled when the Jog (Fn002), Origin Search (Fn003), or Easy FFT (Fn206) utility function is executed. Take necessary precautions.  
There is a risk of machine damage or injury.
- When an alarm occurs, the motor will coast to a stop or stop with the dynamic brake according to a setting in the SERVOPACK. The coasting distance will change with the moment of inertia of the load. Check the coasting distance during trial operation and implement suitable safety measures on the machine.
- Do not enter the machine's range of motion during operation.  
There is a risk of injury.
- Do not touch the moving parts of the Servomotor or machine during operation.  
There is a risk of injury.

### **CAUTION**

- Do not use the holding brake built into a Servomotor to stop the Servomotor. The holding brake is designed to hold the motor shaft. It is not designed as a stopping device to ensure machine safety. Provide an appropriate stopping device on the machine to ensure safety.  
There is a risk of brake failure due to wear, damage to the machine, or injury.
- Before you operate a Servomotor, supply power to the holding brake to release the holding brake. Refer to the timing charts in your Servomotor manual for details.
- During trial operation, confirm that the holding brake works correctly.
- When overtravel occurs, the power supply to the motor is turned OFF and the brake is released. If you use the Servomotor to drive a vertical load, set the Servomotor to enter a zero-clamped state after the Servomotor stops. Also, install safety devices (such as an external brake or counterweight) to prevent the moving parts of the machine from falling.
- Always turn OFF the servo before you turn OFF the power supply. If you turn OFF the main circuit power supply or control power supply during operation before you turn OFF the servo, the Servomotor will stop as follows:
  - If you turn OFF the main circuit power supply during operation without turning OFF the servo, the Servomotor will stop abruptly with the dynamic brake.
  - If you turn OFF the control power supply without turning OFF the servo, the stopping method that is used by the Servomotor depends on the model of the SERVOPACK. For details, refer to the manual for the SERVOPACK.

### **NOTICE**

- Always measure the vibration of the Servomotor with the Servomotor mounted to the machine and confirm that the vibration is within the allowable value.  
If the vibration is too large, the Servomotor will be damaged quickly and bolts may become loose.
- When you adjust the gain during system commissioning, use a measuring instrument to monitor the torque waveform and speed waveform and confirm that there is no vibration.  
If a high gain causes vibration, the Servomotor will be damaged quickly.
- An alarm or warning may occur if communications are performed with the host controller while the SigmaWin+ or Digital Operator is operating.  
If an alarm or warning occurs, it may interrupt the current process and stop the system.

## ■ Maintenance and Inspection Precautions



### DANGER

- Do not change any wiring while power is being supplied.  
There is a risk of electric shock or injury.



### WARNING

- Wiring and inspections must be performed only by qualified engineers.  
There is a risk of electric shock or product failure.
- If you replace a Servomotor with a Holding Brake, secure the machine before you replace the Servomotor.  
There is a risk of injury or equipment damage if the equipment falls.



### CAUTION

- Wait for six minutes after turning OFF the power supply and then make sure that the CHARGE indicator is not lit before starting wiring or inspection work. Do not touch the power supply terminals while the CHARGE lamp is lit after turning OFF the power supply because high voltage may still remain in the SERVOPACK.  
There is a risk of electric shock.
- Replace the Battery according to the correct procedure.  
If you remove the Battery or disconnect the Encoder Cable while the control power supply to the SERVOPACK is OFF, the absolute encoder data will be lost and position deviation may occur.

## ■ Troubleshooting Precautions



### WARNING

- The product may suddenly start to operate when the power supply is recovered after a momentary power interruption. Design the machine to ensure human safety when operation restarts.  
There is a risk of injury.



### CAUTION

- When an alarm occurs, remove the cause of the alarm and ensure safety. Then reset the alarm or turn the power supply OFF and ON again to restart operation.  
There is a risk of injury or machine damage.
- If the Servo ON signal is input to the SERVOPACK and an alarm is reset, the Servomotor may suddenly restart operation. Confirm that the servo is OFF and ensure safety before you reset an alarm.  
There is a risk of injury or machine damage.
- The holding brake on a Servomotor will not ensure safety if there is the possibility that an external force (including gravity) may move the current position and create a hazardous situation when power is interrupted or an error occurs. If an external force may cause movement, install an external braking mechanism that ensures safety.

## ■ Disposal Precautions

- When disposing of the product, treat it as ordinary industrial waste. However, local ordinances and national laws must be observed. Implement all labeling and warnings as a final product as required.

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## ■ General Precautions

- Figures provided in this document are typical examples or conceptual representations. There may be differences between them and actual wiring, circuits, and products.
- The products shown in illustrations in this document are sometimes shown without covers or protective guards. Always replace all covers and protective guards before you use the product.
- If you need a new copy of this document because it has been lost or damaged, contact your nearest Yaskawa representative or one of the offices listed on the back of this document.
- This document is subject to change without notice for product improvements, specifications changes, and improvements to the manual itself.  
We will update the document number of the document and issue revisions when changes are made.
- Any and all quality guarantees provided by Yaskawa are null and void if the customer modifies the product in any way. Yaskawa disavows any responsibility for damages or losses that are caused by modified products.



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# Warranty

## ◆ Details of Warranty

### ■ Warranty Period

The warranty period for a product that was purchased (hereinafter called the “delivered product”) is one year from the time of delivery to the location specified by the customer or 18 months from the time of shipment from the Yaskawa factory, whichever is sooner.

### ■ Warranty Scope

Yaskawa shall replace or repair a defective product free of charge if a defect attributable to Yaskawa occurs during the above warranty period.

This warranty does not cover defects caused by the delivered product reaching the end of its service life and replacement of parts that require replacement or that have a limited service life.

This warranty does not cover failures that result from any of the following causes.

- Improper handling, abuse, or use in unsuitable conditions or in environments not described in product catalogs or manuals, or in any separately agreed-upon specifications
- Causes not attributable to the delivered product itself
- Modifications or repairs not performed by Yaskawa
- Use of the delivered product in a manner in which it was not originally intended
- Causes that were not foreseeable with the scientific and technological understanding at the time of shipment from Yaskawa
- Events for which Yaskawa is not responsible, such as natural or human-made disasters

## ◆ Limitations of Liability

- Yaskawa shall in no event be responsible for any damage or loss of opportunity to the customer that arises due to failure of the delivered product.
- Yaskawa shall not be responsible for any programs (including parameter settings) or the results of program execution of the programs provided by the user or by a third party for use with programmable Yaskawa products.
- The information described in product catalogs or manuals is provided for the purpose of the customer purchasing the appropriate product for the intended application. The use thereof does not guarantee that there are no infringements of intellectual property rights or other proprietary rights of Yaskawa or third parties, nor does it construe a license.
- Yaskawa shall not be responsible for any damage arising from infringements of intellectual property rights or other proprietary rights of third parties as a result of using the information described in catalogs or manuals.

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## ◆ Suitability for Use

- It is the customer's responsibility to confirm conformity with any standards, codes, or regulations that apply if the Yaskawa product is used in combination with any other products.
- The customer must confirm that the Yaskawa product is suitable for the systems, machines, and equipment used by the customer.
- Consult with Yaskawa to determine whether use in the following applications is acceptable. If use in the application is acceptable, use the product with extra allowance in ratings and specifications, and provide safety measures to minimize hazards in the event of failure.
  - Outdoor use, use involving potential chemical contamination or electrical interference, or use in conditions or environments not described in product catalogs or manuals
  - Nuclear energy control systems, combustion systems, railroad systems, aviation systems, vehicle systems, medical equipment, amusement machines, and installations subject to separate industry or government regulations
  - Systems, machines, and equipment that may present a risk to life or property
  - Systems that require a high degree of reliability, such as systems that supply gas, water, or electricity, or systems that operate continuously 24 hours a day
  - Other systems that require a similar high degree of safety
- Never use the product for an application involving serious risk to life or property without first ensuring that the system is designed to secure the required level of safety with risk warnings and redundancy, and that the Yaskawa product is properly rated and installed.
- The circuit examples and other application examples described in product catalogs and manuals are for reference. Check the functionality and safety of the actual devices and equipment to be used before using the product.
- Read and understand all use prohibitions and precautions, and operate the Yaskawa product correctly to prevent accidental harm to third parties.

## ◆ Specifications Change

The names, specifications, appearance, and accessories of products in product catalogs and manuals may be changed at any time based on improvements and other reasons. The next editions of the revised catalogs or manuals will be published with updated code numbers. Consult with your Yaskawa representative to confirm the actual specifications before purchasing a product.

## Compliance with UL Standards, EU Directives, and Other Safety Standards

Certification marks for the standards for which the product has been certified by certification bodies are shown on nameplate. Products that do not have the marks are not certified for the standards.

### ◆ North American Safety Standards (UL)



Product	Model	UL Standards (UL File No.)
SERVOPACKs* <sup>1</sup>	SGD7S	UL 61800-5-1
Rotary Servomotors* <sup>1</sup>	<ul style="list-style-type: none"> <li>• SGM7A</li> <li>• SGM7J</li> <li>• SGM7P</li> <li>• SGM7G</li> </ul>	UL 1004-1 UL 1004-6
Direct Drive Servomotors* <sup>1</sup>	<ul style="list-style-type: none"> <li>• SGMCV</li> </ul>	
Linear Servomotors	<ul style="list-style-type: none"> <li>• SGLGW</li> <li>• SGLFW</li> <li>• SGLFW2*<sup>2</sup></li> <li>• SGLTW</li> </ul>	UL 1004 (E165827)

\*1. Certification is scheduled for April 2014.

\*2. Certification is scheduled for April 2015.

### ◆ European Directives



Product	Model	European Directive	Harmonized Standards
SERVOPACKs* <sup>1</sup>	SGD7S	Machinery Directive 2006/42/EC	EN ISO13849-1: 2008 EN 954-1
		EMC Directive 2004/108/EC	EN 55011 group 1, class A EN 61000-6-2 EN 61000-6-4 EN 61800-3
		Low Voltage Directive 2006/95/EC	EN 50178 EN 61800-5-1
Rotary Servomotors* <sup>1</sup>	<ul style="list-style-type: none"> <li>• SGM7A</li> <li>• SGM7J</li> <li>• SGM7P</li> <li>• SGM7G</li> </ul>	EMC Directive 2004/108/EC	EN 55011 group 1, class A EN 61000-6-2 EN 61800-3
		Low Voltage Directive 2006/95/EC	EN 60034-1 EN 60034-5
Direct Drive Servomotors	<ul style="list-style-type: none"> <li>• SGMCS- □□B, □□C, □□D, □□E (Small capacity, coreless)</li> <li>• SGMCV</li> </ul>	EMC Directive 2004/108/EC	EN 55011 group 1, class A EN 61000-6-2 EN 61800-3* <sup>2</sup>
		Low Voltage Directive 2006/95/EC	EN 60034-1 EN 60034-5
Linear Servomotors	<ul style="list-style-type: none"> <li>• SGLG</li> <li>• SGLF</li> <li>• SGLFW2*<sup>3</sup></li> <li>• SGLT</li> <li>• SGLC</li> </ul>	EMC Directive 2004/108/EC	EN 55011 group 1, class A EN 61000-6-2 EN 61000-6-4
		Low Voltage Directive 2006/95/EC	EN 60034-1

\*1. Certification is scheduled for April 2014.

\*2. Only the SGMCV is certified.

\*3. Certification is scheduled for April 2015.

## ◆ Safety Standards



Product	Model	Safety Standards	Standards
SERVOPACKs	SGD7S	Safety of Machinery	EN ISO13849-1: 2008 EN 954-1 IEC 60204-1
		Functional Safety	IEC 61508 series IEC 62061 IEC 61800-5-2
		EMC	IEC 61326-3-1

Note: Certification is scheduled for April 2014.

## ◆ Safe Performance

Item	Standards	Performance Level
Safety Integrity Level	IEC 61508	SIL3
	IEC 62061	SILCL3
Performance Level	EN ISO 13849-1	PLe (Category 3)
Stop Category	IEC 60204-1	Stop category 0
Safety Function	IEC 61800-5-2	STO

Note: Certification is scheduled for April 2014.

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### Revision History



# Basic Information on Servomotors

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# 1

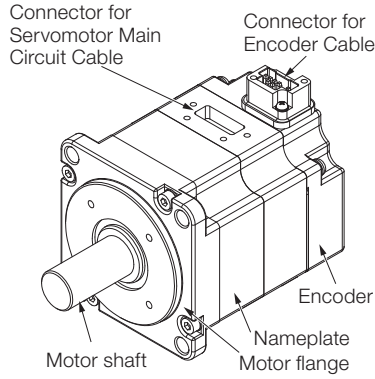
This chapter provides basic information on Rotary Servomotors, including Servomotor part names and combinations with SERVOPACKs.

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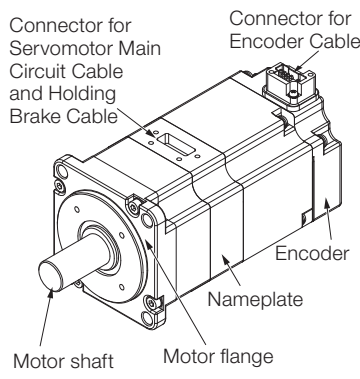
# 1.1 Servomotor Part Names

## 1.1.1 SGM7J and SGM7A Servomotor Up to 1.0 kW

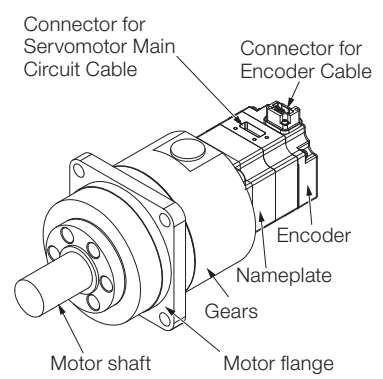
• Standard Servomotors



• Servomotors with Brakes

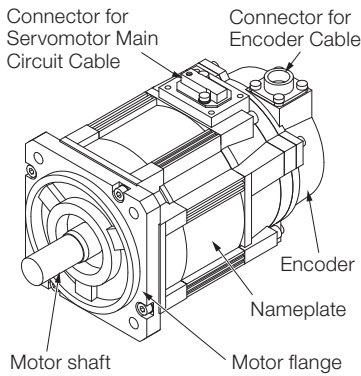


• Servomotors with Gears

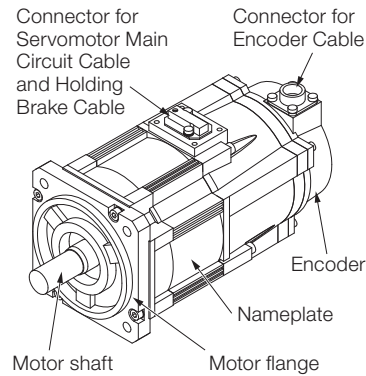


## 1.1.2 SGM7G Servomotors Up to 450 W

• Standard Servomotors

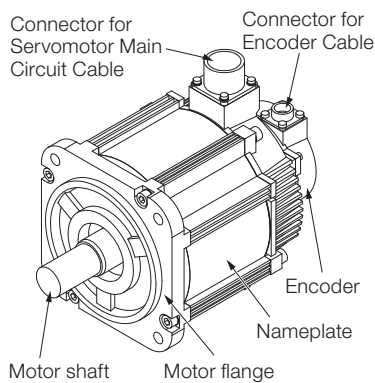


• Servomotors with Brakes

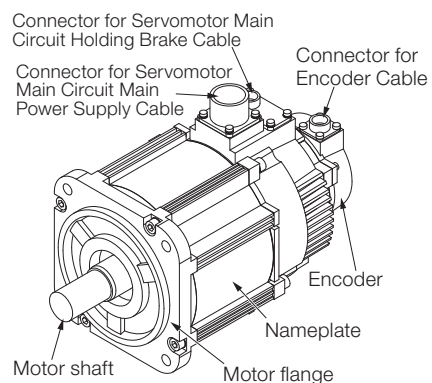


## 1.1.3 SGM7A Servomotors of 1.5 kW and Higher and SGM7G Servomotors of 850 W and Higher

• Standard Servomotors



• Servomotors with Brakes

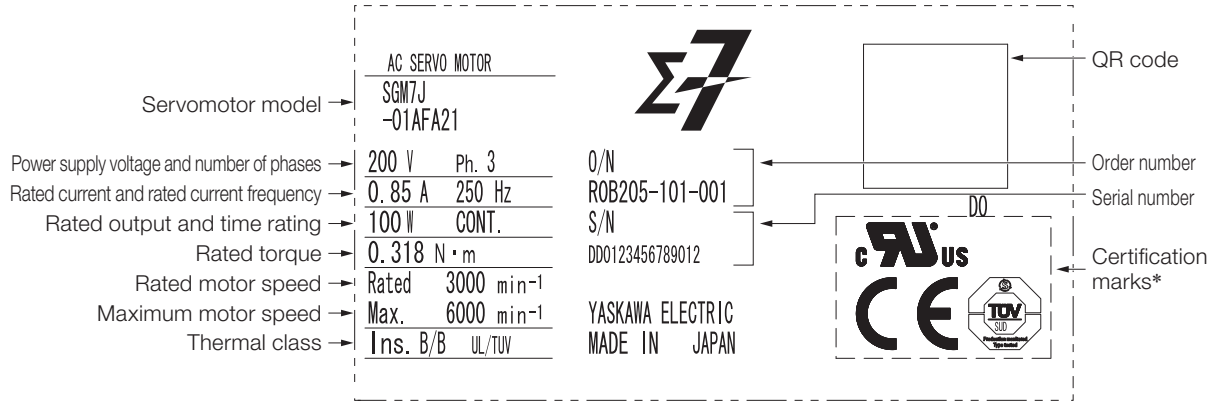


## 1.2 Interpreting the Nameplates

The following basic information is provided on the nameplate.

The nameplate is printed on the Servomotor.

The layout of the nameplate depends somewhat on the model of the Servomotor.



\* Certification marks for the standards for which the Servomotor has been certified by certification bodies are shown on the product.

# 1.3 Outline of Model Designations

## 1.3.1 Servomotor

This section outlines the model numbers of  $\Sigma$ -7-Series Servomotors. For details, refer to the chapter for your type of Servomotor.



Code	Specifications	Reference
SGM7J	Medium inertia, high speed	Chapter 3
SGM7A	Low inertia, high speed	Chapter 4
SGM7G	Medium inertia, low speed, high torque	Chapter 5

- Series**  $\Sigma$ -7-Series Servomotors
- 1st+2nd digits** Rated Output
- 3rd digit** Power Supply Voltage
  - 200 VAC
- 4th digit** Serial Encoder Specification
  - 24-bit absolute encoder
  - 24-bit incremental encoder
- 5th digit** Design Revision Order
- 6th digit** Shaft End Specification
  - Straight
  - With key and tap
  - With two flat seats
- 7th digit** Options
  - With 24-V holding brake
  - With oil seal

## 1.3.2 SERVOPACKs

This section outlines the model numbers of  $\Sigma$ -7-Series SERVOPACKs. For details, refer to the manual for your SERVOPACK.

- Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
- Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)
- Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)
- Σ-7-Series Σ-7W SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 29)



Code	Specification
SGD7S	Single-axis SERVOPACKs
SGD7W	Two-axis SERVOPACKs

- Series**  $\Sigma$ -7-Series SERVOPACKs
- 1st+2nd+3rd digits** Maximum Applicable Motor Capacity
  - 0.05 kW to 1.5 kW
- 4th digit** Power Supply Voltage
  - 200 VAC
- 5th+6th digits** Interface
  - Analog voltage/pulse train reference
  - MECHATROLINK-II communications reference
  - MECHATROLINK-III communications reference
- 7th digit** Design Revision Order
- 8th+9th+10th digits** Options
  - Rack-mounted installation
  - Varnished

## 1.4

## Combinations of Servomotors and SERVOPACKs

Rotary Servomotor Model		Capacity	SERVOPACK Model	
			SGD7S-□□□□	SGD7W-□□□□
SGM7A Models (Low Inertia, High Speed), 3,000 min <sup>-1</sup>	SGM7A-A5A	50 W	R70A	1R6A
	SGM7A-01A	100 W	R90A	
	SGM7A-C2A	150 W	1R6A	
	SGM7A-02A	200 W	1R6A	
	SGM7A-04A	400 W	2R8A	
	SGM7A-06A	600 W	5R5A	
	SGM7A-08A	750 W	5R5A	
	SGM7A-10A	1.0 kW	120A	-
	SGM7A-15A	1.5 kW		
	SGM7A-20A	2.0 kW	180A	
	SGM7A-25A	2.5 kW	200A	
	SGM7A-30A	3.0 kW		
SGM7J Models (Medium Inertia, High Speed), 3,000 min <sup>-1</sup>	SGM7J-A5A	50 W	R70A	
	SGM7J-01A	100 W	R90A	
	SGM7J-C2A	150 W	1R6A	
	SGM7J-02A	200 W	1R6A	
	SGM7J-04A	400 W	2R8A	
	SGM7J-06A	600 W	5R5A	
	SGM7J-08A	750 W	5R5A	
SGM7G Models (Medium Inertia, Low Speed, High Torque), 1,500 min <sup>-1</sup>	SGM7G-03A	300 W	3R8A	5R5A
	SGM7G-05A	450 W		
	SGM7G-09A	850 W	7R6A	
	SGM7G-13A	1.3 kW	120A	-
	SGM7G-20A	1.8 kW	180A	

# Capacity Selection

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This chapter describes calculation methods to use when selecting Servomotor capacities.

## **2.1** Selecting the Servomotor Capacity . . . . . 2-2

- 2.1.1 Capacity Selection Example for a Rotary Servomotor: For Speed Control . . . . . 2-2
- 2.1.2 Capacity Selection Example for a Rotary Servomotor: For Position Control . . . . . 2-4

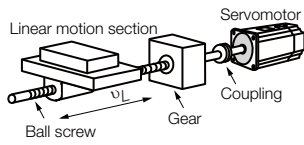
# 2.1 Selecting the Servomotor Capacity

Use Yaskawa's SigmaJunmaSize+, an AC servo drive capacity selection program, to select the Servomotor capacity. With the SigmaJunmaSize+, you can find the optimum Servomotor capacity by simply selecting and entering information according to instructions from a wizard.

Refer to the following selection examples to select Servomotor capacities with manual calculations rather than with the above software.

## 2.1.1 Capacity Selection Example for a Rotary Servomotor: For Speed Control

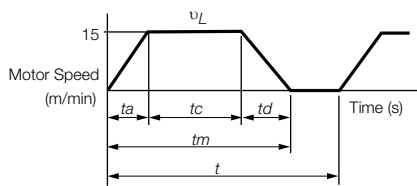
### 1. Mechanical Specifications



Item	Code	Value
Load Speed	$v_L$	15 m/min
Linear Motion Section Mass	$m$	250 kg
Ball Screw Length	$l_B$	1.0 m
Ball Screw Diameter	$d_B$	0.02 m
Ball Screw Lead	$P_B$	0.01 m
Ball Screw Material Density	$\rho$	$7.87 \times 10^3 \text{ kg/m}^3$
Gear Ratio	$R$	2 (gear ratio: 1/2)
External Force on Linear Motion Section	$F$	0 N

Item	Code	Value
Gear and Coupling Moment of Inertia	$J_G$	$0.40 \times 10^{-4} \text{ kg}\cdot\text{m}^2$
Number of Feeding Operations	$n$	40 rotations/min
Feeding Distance	$l$	0.275 m
Feeding Time	$tm$	1.2 s max.
Friction Coefficient	$\mu$	0.2
Mechanical Efficiency	$\eta$	0.9 (90%)

### 2. Operation Pattern



$$t = \frac{60}{n} = \frac{60}{40} = 1.5 \text{ (s)}$$

If  $t_a = t_d$ ,

$$t_a = t_m - \frac{60 \cdot l}{v_L} = 1.2 - \frac{60 \times 0.275}{15} = 1.2 - 1.1 = 0.1 \text{ (s)}$$

$$t_c = 1.2 - 0.1 \times 2 = 1.0 \text{ (s)}$$

### 3. Motor Speed

- Load shaft speed  $n_L = \frac{v_L}{P_B} = \frac{15}{0.01} = 1,500 \text{ (min}^{-1}\text{)}$
- Motor shaft speed  $n_M = n_L \cdot R = 1,500 \times 2 = 3,000 \text{ (min}^{-1}\text{)}$

### 4. Load Torque

$$T_L = \frac{(9.8 \cdot \mu \cdot m + F) \cdot P_B}{2\pi R \cdot \eta} = \frac{(9.8 \times 0.2 \times 250 + 0) \times 0.01}{2\pi \times 2 \times 0.9} = 0.43 \text{ (N}\cdot\text{m)}$$

**5. Load Moment of Inertia**

- Linear motion section

$$J_{L1} = m \left( \frac{P_B}{2\pi R} \right)^2 = 250 \times \left( \frac{0.01}{2\pi \times 2} \right)^2 = 1.58 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$$

- Ball screw

$$J_B = \frac{\pi}{32} \rho \cdot l_B \cdot d_B^4 \cdot \frac{1}{R^2} = \frac{\pi}{32} \times 7.87 \times 10^3 \times 1.0 \times (0.02)^4 \cdot \frac{1}{2^2} = 0.31 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$$

- Coupling  $J_G = 0.40 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$
- Load moment of inertia at motor shaft

$$J_L = J_{L1} + J_B + J_G = (1.58 + 0.31 + 0.40) \times 10^{-4} = 2.29 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$$

**6. Load Moving Power**

$$P_O = \frac{2\pi n_M \cdot T_L}{60} = \frac{2\pi \times 3,000 \times 0.43}{60} = 135 \text{ (W)}$$

**7. Load Acceleration Power**

$$P_a = \left( \frac{2\pi}{60} n_M \right)^2 \frac{J_L}{t_a} = \left( \frac{2\pi}{60} \times 3,000 \right)^2 \times \frac{2.29 \times 10^{-4}}{0.1} = 226 \text{ (W)}$$

**8. Servomotor Provisional Selection****① Selection Conditions**

- $T_L \leq$  Motor rated torque
- $\frac{(P_O + P_a)}{2} <$  Provisionally selected Servomotor rated output  $< (P_O + P_a)$
- $n_M \leq$  Rated motor speed
- $J_L \leq$  Allowable load moment of inertia

The following Servomotor meets the selection conditions.

- SGM7J-02A Servomotor

**② Specifications of the Provisionally Selected Servomotor**

Item	Value
Rated Output	200 (W)
Rated Motor Speed	3,000 (min <sup>-1</sup> )
Rated Torque	0.637 (N·m)
Instantaneous Maximum Torque	2.23 (N·m)
Motor Moment of Inertia	$0.263 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$
Allowable Load Moment of Inertia	$0.263 \times 10^{-4} \times 15 = 3.94 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$

**9. Verification of the Provisionally Selected Servomotor**

- Verification of required acceleration torque:
 
$$T_P = \frac{2\pi n_M (J_M + J_L)}{60 t_a} + T_L = \frac{2\pi \times 3,000 \times (0.263 + 2.29) \times 10^{-4}}{60 \times 0.1} + 0.43$$

$$\approx 1.23 \text{ (N}\cdot\text{m)} < \text{Maximum instantaneous torque...Satisfactory}$$
- Verification of required deceleration torque:
 
$$T_S = \frac{2\pi n_M (J_M + J_L)}{60 t_d} - T_L = \frac{2\pi \times 3,000 \times (0.263 + 2.29) \times 10^{-4}}{60 \times 0.1} - 0.43$$

$$\approx 0.37 \text{ (N}\cdot\text{m)} < \text{Maximum instantaneous torque...Satisfactory}$$



2.1 Selecting the Servomotor Capacity

2.1.2 Capacity Selection Example for a Rotary Servomotor: For Position Control

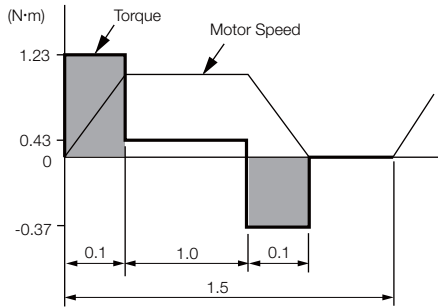
• Verification of effective torque value:

$$T_{rms} = \sqrt{\frac{T_P^2 \cdot ta + T_L^2 \cdot tc + Ts^2 \cdot td}{t}} = \sqrt{\frac{(1.23)^2 \times 0.1 + (0.43)^2 \times 1.0 + (0.37)^2 \times 0.1}{1.5}}$$

$$\approx 0.483 \text{ (N}\cdot\text{m)} < \text{Rated torque...Satisfactory}$$

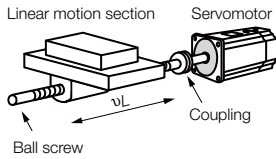
10. Result

It has been verified that the provisionally selected Servomotor is applicable. The torque diagram is shown below.



## 2.1.2 Capacity Selection Example for a Rotary Servomotor: For Position Control

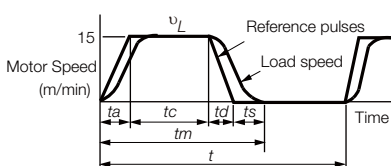
1. Mechanical Specifications



Item	Code	Value
Load Speed	$v_L$	15 m/min
Linear Motion Section Mass	$m$	80 kg
Ball Screw Length	$\ell_B$	0.8 m
Ball Screw Diameter	$d_B$	0.016 m
Ball Screw Lead	$P_B$	0.005 m
Ball Screw Material Density	$\rho$	$7.87 \times 10^3 \text{ kg/m}^3$
External Force on Linear Motion Section	$F$	0 N
Coupling Mass	$m_C$	0.3 kg

Item	Code	Value
Coupling Outer Diameter	$d_C$	0.03 m
Number of Feeding Operations	$n$	40 rotation/min
Feeding Distance	$\ell$	0.25 m
Feeding Time	$tm$	1.2 s max.
Electrical Stopping Precision	$\delta$	$\pm 0.01 \text{ mm}$
Friction Coefficient	$\mu$	0.2
Mechanical Efficiency	$\eta$	0.9 (90%)

2. Speed Diagram



$$t = \frac{60}{n} = \frac{60}{40} = 1.5 \text{ (s)}$$

If  $ta = td$  and  $ts = 0.1 \text{ (s)}$ ,

$$ta = tm - ts - \frac{60 \ell}{v_L} = 1.2 - 0.1 - \frac{60 \times 0.25}{15} = 0.1 \text{ (s)}$$

$$tc = 1.2 - 0.1 - 0.1 \times 2 = 0.9 \text{ (s)}$$

**3. Motor Speed**

- Load shaft speed  $n_L = \frac{v_L}{P_B} = \frac{15}{0.005} = 3,000 \text{ (min}^{-1}\text{)}$
- Motor shaft speed Direct coupling gear ratio  $1/R = 1/1$   
Therefore,  $n_M = n_L \cdot R = 3,000 \times 1 = 3,000 \text{ (min}^{-1}\text{)}$

**4. Load Torque**

$$T_L = \frac{(9.8 \mu \cdot m + F) \cdot P_B}{2\pi R \cdot \eta} = \frac{(9.8 \times 0.2 \times 80 + 0) \times 0.005}{2\pi \times 1 \times 0.9} = 0.139 \text{ (N}\cdot\text{m)}$$

**5. Load Moment of Inertia**

- Linear motion section

$$J_{L1} = m \left( \frac{P_B}{2\pi R} \right)^2 = 80 \times \left( \frac{0.005}{2\pi \times 1} \right)^2 = 0.507 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$$

- Ball screw  $J_B = \frac{\pi}{32} \rho \cdot l_B \cdot d_B^4 = \frac{\pi}{32} \times 7.87 \times 10^3 \times 0.8 \times (0.016)^4 = 0.405 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$

- Coupling  $J_C = \frac{1}{8} m_C \cdot d_C^2 = \frac{1}{8} \times 0.3 \times (0.03)^2 = 0.338 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$

- Load moment of inertia at motor shaft

$$J_L = J_{L1} + J_B + J_C = 1.25 \times 10^{-4} \text{ (kg}\cdot\text{m}^2\text{)}$$

**6. Load Moving Power**

$$P_O = \frac{2\pi n_M \cdot T_L}{60} = \frac{2\pi \times 3,000 \times 0.139}{60} = 43.7 \text{ (W)}$$

**7. Load Acceleration Power**

$$P_a = \left( \frac{2\pi}{60} n_M \right)^2 \frac{J_L}{t_a} = \left( \frac{2\pi}{60} \times 3,000 \right)^2 \times \frac{1.25 \times 10^{-4}}{0.1} = 123.4 \text{ (W)}$$

**8. Servomotor Provisional Selection****① Selection Conditions**

- $T_L \leq$  Motor rated torque
- $\frac{(P_O + P_a)}{2} <$  Provisionally selected Servomotor rated output  $< (P_O + P_a)$
- $n_M \leq$  Rated motor speed
- $J_L \leq$  Allowable load moment of inertia

The following Servomotor meets the selection conditions.

- SGM7J-01A Servomotor

**② Specifications of the Provisionally Selected Servomotor**

Item	Value
Rated Output	100 (W)
Rated Motor Speed	3,000 (min <sup>-1</sup> )
Rated Torque	0.318 (N·m)
Instantaneous Maximum Torque	1.11 (N·m)
Motor Moment of Inertia	0.0659 × 10 <sup>-4</sup> (kg·m <sup>2</sup> )
Allowable Load Moment of Inertia	0.0659 × 10 <sup>-4</sup> × 35 = 2.31 × 10 <sup>-4</sup> (kg·m <sup>2</sup> )
Encoder Resolution	16,777,216 (pulses/rev) (24 bits)

### 9. Verification of the Provisionally Selected Servomotor

- Verification of required acceleration torque:  

$$T_P = \frac{2\pi n_M (J_M + J_L)}{60ta} + T_L = \frac{2\pi \times 3,000 \times (0.0659 + 1.25) \times 10^{-4}}{60 \times 0.1} + 0.139$$

$$\approx 0.552 \text{ (N}\cdot\text{m)} < \text{Maximum instantaneous torque...Satisfactory}$$
- Verification of required deceleration torque:  

$$T_S = \frac{2\pi n_M (J_M + J_L)}{60td} - T_L = \frac{2\pi \times 3,000 \times (0.0659 + 1.25) \times 10^{-4}}{60 \times 0.1} - 0.139$$

$$\approx 0.274 \text{ (N}\cdot\text{m)} < \text{Maximum instantaneous torque...Satisfactory}$$
- Verification of effective torque value:  

$$T_{rms} = \sqrt{\frac{T_P^2 \cdot ta + T_L^2 \cdot tc + T_S^2 \cdot td}{t}} = \sqrt{\frac{(0.552)^2 \times 0.1 + (0.139)^2 \times 0.9 + (0.274)^2 \times 0.1}{1.5}}$$

$$\approx 0.192 \text{ (N}\cdot\text{m)} < \text{Rated torque...Satisfactory}$$

It has been verified that the provisionally selected Servomotor is applicable in terms of capacity. Position control is considered next.

### 10. Positioning Resolution

The electrical stopping precision  $\delta$  is  $\pm 0.01$  mm, so the positioning resolution  $\Delta_\ell$  is 0.01 mm. The ball screw lead  $P_B$  is 0.005 m, so the number of pulses per motor rotation is calculated with the following formula.

$$\text{Number of pulses per rotation (pulses)} = \frac{P_B}{\Delta_\ell} = \frac{5 \text{ mm/rev}}{0.01 \text{ mm}} = 500 \text{ (P/rev)} < \text{Encoder resolution (16,777,216 (pulses/rev))}$$

The number of pulses per motor rotation is less than the encoder resolution (pulses/rev), so the provisionally selected motor can be used.

### 11. Reference Pulse Frequency

The load speed  $v_L$  is 15 m/min, or  $1,000 \times 15/60$  mm/s and the positioning resolution (travel distance per pulse) is 0.01 mm/pulse, so the reference pulse frequency is calculated with the following formula.

$$v_s = \frac{1,000 v_L}{60 \times \Delta_\ell} = \frac{1,000 \times 15}{60 \times 0.01} = 25,000 \text{ (pps)}$$

The reference pulse frequency is less than the maximum input pulse frequency,\* so the provisionally selected Servomotor can be used.

\*Refer to the specifications in the SERVOPACK manual for the maximum input pulse frequency.

It has been verified that the provisionally selected Servomotor is applicable for position control.

# Specifications, Ratings, and External Dimensions of SGM7A Servomotors

## 3

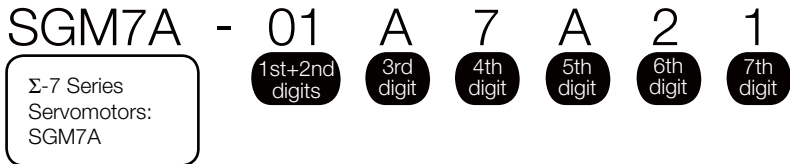
This chapter describes how to interpret the model numbers of SGM7A Servomotors and gives their specifications, ratings, and external dimensions.

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# 3.1 Model Designations

## 3.1.1 Without Gears



**1st+2nd digits** Rated Output

Code	Specification
A5	50 W
01	100 W
C2	150 W
02	200 W
04	400 W
06	600 W
08	750 W
10	1.0 kW
15	1.5 kW
20	2.0 kW
25	2.5 kW
30	3.0 kW

**3rd digit** Power Supply Voltage

Code	Specification
A	200 VAC

**4th digit** Serial Encoder

Code	Specification
7	24-bit absolute
F	24-bit incremental

**5th digit** Design Revision Order

A

**6th digit** Shaft End

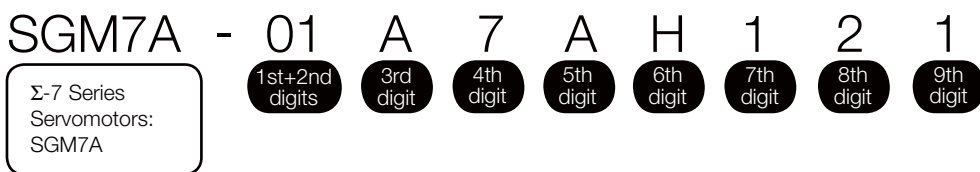
Code	Specification
2	Straight without key
6	Straight with key and tap
B*	With two flat seats

\* Code B is not supported for models with a rated output of 1.5 kW or higher.

**7th digit** Options

Code	Specification
1	Without options
C	With holding brake (24 VDC)
E	With oil seal and holding brake (24 VDC)
S	With oil seal

## 3.1.2 With Gears



**1st+2nd digits** Rated Output

Code	Specification
A5	50 W
01	100 W
C2	150 W
02	200 W
04	400 W
06	600 W
08	750 W
10	1.0 kW

**3rd digit** Power Supply Voltage

Code	Specification
A	200 VAC

**4th digit** Serial Encoder

Code	Specification
7	24-bit absolute
F	24-bit incremental

**5th digit** Design Revision Order

A

**6th digit** Gear Type

Code	Specification
H	HDS planetary low-backlash gear

**7th digit** Gear Ratio

Code	Specification
B	1/11 <sup>*1</sup>
C	1/21
1	1/5
2	1/9 <sup>*2</sup>
7	1/33

\*1. This specification is not supported for models with a rated output of 50 W.

\*2. This specification is supported only for models with a rated output of 50 W.

**8th digit** Shaft End

Code	Specification
0	Flange output
2	Straight without key
6	Straight with key and tap

**9th digit** Options

Code	Specification
1	Without options
C	With holding brake (24 VDC)

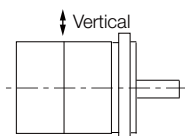
# 3.2 Specifications and Ratings

## 3.2.1 Specifications

Voltage		200 V
Model SGM7A-		A5A to 30A
Time Rating	Continuous	
Thermal Class	B: A5A to 10A F: 15A to 30A	
Insulation Resistance	500 VDC, 10 MΩ min.	
Withstand Voltage	1,500 VAC for 1 minute	
Excitation	Permanent magnet	
Mounting	Flange-mounted	
Drive Method	Direct drive	
Rotation Direction	Counterclockwise (CCW) for forward reference when viewed from the load side	
Vibration Class*1	V15	
Environmental Conditions	Surrounding Air Temperature	0°C to 40°C (With derating, usage is possible between 40°C and 60°C.)*4
	Surrounding Air Humidity	20% to 80% relative humidity (with no condensation)
	Installation Site	<ul style="list-style-type: none"> <li>• Must be indoors and free of corrosive and explosive gases.</li> <li>• Must be well-ventilated and free of dust and moisture.</li> <li>• Must facilitate inspection and cleaning.</li> <li>• Must have an altitude of 1,000 m or less. (With derating, usage is possible between 1,000 m and 2,000 m.)*5</li> <li>• Must be free of strong magnetic fields.</li> </ul>
	Storage Environment	Store the Servomotor in the following environment if you store it with the power cable disconnected. Storage Temperature: -20°C to 60°C (with no freezing) Storage Humidity: 20% to 80% relative humidity (with no condensation)
Shock Resistance*2	Impact Acceleration Rate at Flange	490 m/s <sup>2</sup>
	Number of Impacts	2 times
Vibration Resistance*3	Vibration Acceleration Rate at Flange	49 m/s <sup>2</sup> (Models 15A to 30A: 24.5 m/s <sup>2</sup> front to back)
Applicable SERVOPACKs	Refer to 1.4 Combinations of Servomotors and SERVOPACKs on page 1-5.	

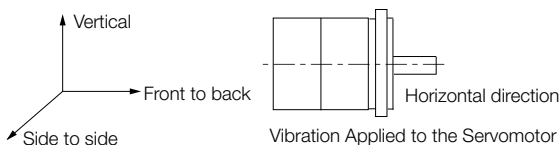
\*1. A vibration class of V15 indicates a vibration amplitude of 15 μm maximum on the Servomotor without a load at the rated motor speed.

\*2. The shock resistance for shock in the vertical direction when the Servomotor is mounted with the shaft in a horizontal position is given in the above table.



Shock Applied to the Servomotor

\*3. The vertical, side-to-side, and front-to-back vibration resistance for vibration in three directions when the Servomotor is mounted with the shaft in a horizontal position is given in the above table. The strength of the vibration that the Servomotor can withstand depends on the application. Always check the vibration acceleration rate that is applied to the Servomotor with the actual equipment.



\*4. If the ambient temperature will exceed 40°C, refer to the following section.

3.2.11 Applications Where the Ambient Temperature of the Servomotor Exceeds 40 °C on page 3-15

\*5. If the altitude will exceed 1,000 m, refer to the following section.


3.2.12 Applications Where the Altitude of the Servomotor Exceeds 1,000 m on page 3-15

## 3.2.2 Ratings of Servomotors without Gears

Voltage		200 V								
Model SGM7A-		A5A	01A	C2A	02A	04A	06A	08A	10A	
Rated Output* <sup>1</sup>	W	50	100	150	200	400	600	750	1000	
Rated Torque* <sup>1, *2</sup>	N·m	0.159	0.318	0.477	0.637	1.27	1.91	2.39	3.18	
Instantaneous Maximum Torque* <sup>1</sup>	N·m	0.557	1.11	1.67	2.23	4.46	6.69	8.36	11.1	
Rated Current* <sup>1</sup>	Arms	0.57	0.89	1.5	1.5	2.4	4.5	4.4	6.4	
Instantaneous Maximum Current* <sup>1</sup>	Arms	2.1	3.2	5.6	5.9	9.3	16.9	16.8	23.2	
Rated Motor Speed* <sup>1</sup>	min <sup>-1</sup>	3000								
Maximum Motor Speed* <sup>1</sup>	min <sup>-1</sup>	6000								
Torque Constant	N·m/Arms	0.304	0.384	0.332	0.458	0.576	0.456	0.584	0.541	
Motor Moment of Inertia	×10 <sup>-4</sup> kg·m <sup>2</sup>	0.0217 (0.0297)	0.0337 (0.0417)	0.0458 (0.0538)	0.139 (0.209)	0.216 (0.286)	0.315 (0.385)	0.775 (0.955)	0.971 (1.15)	
Rated Power Rate* <sup>1</sup>	kW/s	11.7 (8.51)	30.0 (24.2)	49.7 (42.2)	29.2 (19.4)	74.7 (56.3)	115 (94.7)	73.7 (59.8)	104 (87.9)	
Rated Angular Acceleration Rate* <sup>1</sup>	rad/s <sup>2</sup>	73200 (53500)	94300 (76200)	104000 (88600)	45800 (30400)	58700 (44400)	60600 (49600)	30800 (25000)	32700 (27600)	
Derating Rate for Servomotor with Oil Seal	%	80	90			95				
Heat Sink Size	mm	200 × 200 × 6		250 × 250 × 6			300 × 300 × 12* <sup>7</sup>	250 × 250 × 6	300 × 300 × 12	
Protective Structure* <sup>3</sup>	Totally enclosed, self-cooled, IP67									
Holding Brake Specifications* <sup>4</sup>	Rated Voltage	V	24 VDC±10%							
	Capacity	W	5.5			6		6.5		
	Holding Torque	N·m	0.159	0.318	0.477	0.637	1.27	1.91	2.39	3.18
	Coil Resistance	Ω (at 20°C)	104.8±10%			96±10%		88.6±10%		
	Rated Current	A (at 20°C)	0.23			0.25		0.27		
	Time Required to Release Brake	ms	60					80		
	Time Required to Brake	ms	100							
Allowable Load Moment of Inertia (Motor Moment of Inertia Ratio)			40 times		30 times	20 times		20 times		
	With External Regenerative Resistor and Dynamic Brake Resistor							30 times		
Allowable Shaft Loads* <sup>5</sup>	LF	mm	20		25		35			
	Allowable Radial Load	N	78		245		392			
	Allowable Thrust Load	N	54		74		147			

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

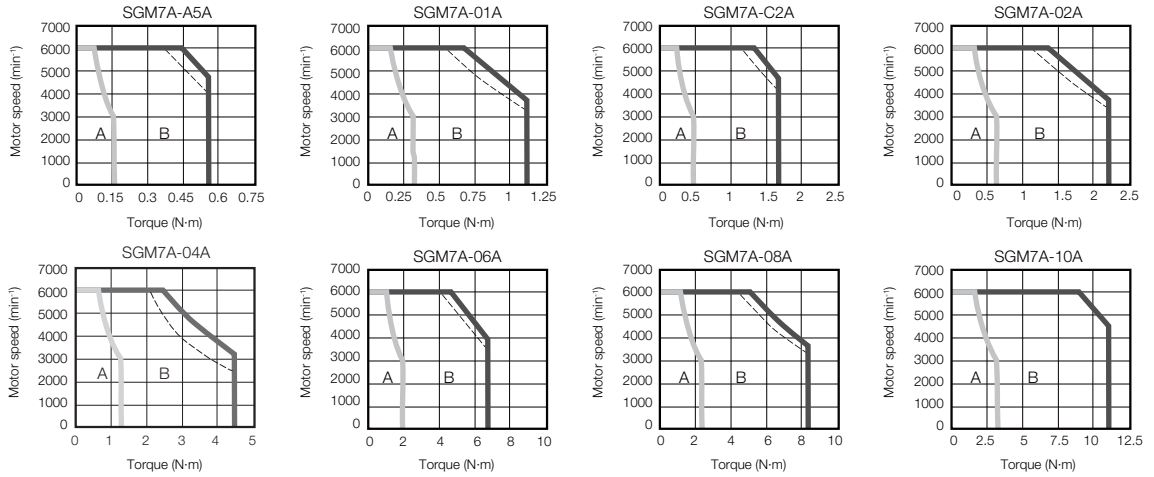
2. Refer to the following section for footnotes \*1 to \*7.

 ◆ Notes for Ratings of Servomotor without Gears and Servomotor Ratings on page 3-8



## 3.2.3 Torque-Motor Speed Characteristics

**A** : Continuous duty zone      — (solid lines): With three-phase 200-V or single-phase 230-V input  
**B** : Intermittent duty zone      - - - (dotted lines): With single-phase 200-V input




- Note: 1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 100°C. These are typical values.
2. The characteristics in the intermittent duty zone depend on the power supply voltage.
3. If the effective torque is within the allowable range for the rated torque, the Servomotor can be used within the intermittent duty zone.
4. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.

## 3.2.4 Servomotor Ratings

Voltage		200 V			
Model SGM7A-		15A	20A	25A	30A
Rated Output* <sup>6</sup>	kW	1.5	2.0	2.5	3.0
Rated Torque* <sup>2, *6</sup>	N·m	4.90	6.36	7.96	9.80
Instantaneous Maximum Torque* <sup>6</sup>	N·m	14.7	19.1	23.9	29.4
Rated Current* <sup>6</sup>	Arms	9.3	12.1	15.6	17.9
Instantaneous Maximum Current* <sup>6</sup>	Arms	28	42	51	56
Rated Motor Speed* <sup>6</sup>	min <sup>-1</sup>	3000			
Maximum Motor Speed* <sup>6</sup>	min <sup>-1</sup>	6000			
Torque Constant	N·m/Arms	0.590	0.561	0.538	0.582
Motor Moment of Inertia	×10 <sup>-4</sup> kg·m <sup>2</sup>	2.00 (2.25)	2.47 (2.72)	3.19 (3.44)	7.00 (9.20)
Rated Power Rate* <sup>6</sup>	kW/s	120 (106)	164 (148)	199 (184)	137 (104)
Rated Angular Acceleration Rate* <sup>6</sup>	rad/s <sup>2</sup>	24500 (21700)	25700 (23300)	24900 (23100)	14000 (10600)
Heat Sink Size	mm	300 × 300 × 12			400 × 400 × 20
Protective Structure* <sup>3</sup>		Totally enclosed, self-cooled, IP67			
Holding Brake Specifications* <sup>4</sup>	Rated Voltage	V	24 VDC <sup>+10%</sup> <sub>0</sub>		
	Capacity	W	12		10
	Holding Torque	N·m	7.84		10
	Coil Resistance	Ω (at 20°C)	48		59
	Rated Current	A (at 20°C)	0.5		0.41
	Time Required to Release Brake	ms	170		100
	Time Required to Brake	ms	80		
Allowable Load Moment of Inertia (Motor Moment of Inertia Ratio)		10 times			5 times
	With External Regenerative Resistor and Dynamic Brake Resistor	20 times			15 times
Allowable Shaft Loads* <sup>5</sup>	LF	mm	45		63
	Allowable Radial Load	N	686		980
	Allowable Thrust Load	N	196		392

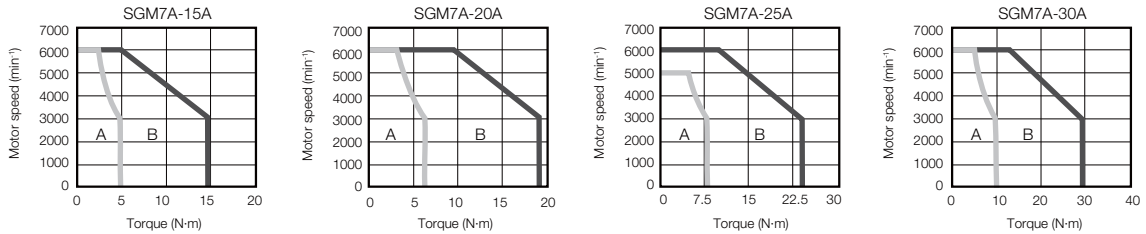
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Refer to the following section for footnotes \*2 to \*6.

 ◆ Notes for Ratings of Servomotor without Gears and Servomotor Ratings on page 3-8

## 3.2.5 Torque-Motor Speed Characteristics for Three-phase, 200 V

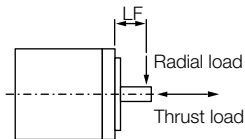
- A** : Continuous duty zone
- B** : Intermittent duty zone



- Note: 1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 20°C. These are typical values.
2. The characteristics in the intermittent duty zone depend on the power supply voltage.
3. If the effective torque is within the allowable range for the rated torque, the Servomotor can be used within the intermittent duty zone.
4. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.

### ◆ Notes for Ratings of Servomotor without Gears and Servomotor Ratings

- \*1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 100°C. The values for other items are at 20°C. These are typical values.
- \*2. The rated torques are the continuous allowable torque values at 40°C with an aluminum heat sink of the dimensions given in the table.
- \*3. This does not apply to the shaft opening. Protective structure specifications apply only when the special cable is used.
- \*4. Observe the following precautions if you use a Servomotor with a Holding Brake.
  - The holding brake cannot be used to stop the Servomotor.
  - The time required to release the brake and the time required to brake depend on which discharge circuit is used.
 Confirm that the operation delay time is appropriate for the actual equipment.
  - The 24-VDC power supply is not provided by Yaskawa.
- \*5. The allowable shaft loads are illustrated in the following figure. Design the mechanical system so that the thrust and radial loads applied to the Servomotor shaft end during operation do not exceed the values given in the table.



- \*6. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 20°C. These are typical values.
- \*7. If the heat sink is 250 mm × 250 mm × 6 mm, the rated output is 550 W and the rated torque is 1.75 N·m. Refer to the following section for details.

3.2.10 Servomotor Heat Dissipation Conditions on page 3-14

## 3.2.6 Ratings of Servomotors with Gears

All Models	Gear Mechanism		Protective Structure			Lost Motion [arc-min]				
	Planetary gear mechanism		Totally enclosed, self-cooled, IP55 (except for shaft opening)			3 max.				
Servomotor Model SGM7A-	Servomotor					Gear Output				
	Rated Output [W]	Rated Motor Speed [min <sup>-1</sup> ]	Maximum Motor Speed [min <sup>-1</sup> ]	Rated Torque [N·m]	Instantaneous Maximum Torque [N·m]	Gear Ratio	Rated Torque/Efficiency* <sup>1</sup> [N·m/%]	Instantaneous Maximum Torque [N·m]	Rated Motor Speed [min <sup>-1</sup> ]	Maximum Motor Speed [min <sup>-1</sup> ]
A5A□AH1□	50	3000	6000	0.159	0.557	1/5	0.433/64* <sup>2</sup>	2.37	600	1200
A5A□AH2□						1/9	1.12/78	3.78* <sup>3</sup>	333	667
A5A□AHC□						1/21	2.84/85	10.6	143	286
A5A□AH7□						1/33	3.68/70	15.8	91	182
01A□AH1□	100	3000	6000	0.318	1.11	1/5	1.06/78* <sup>2</sup>	4.96	600	1200
01A□AHB□						1/11	2.52/72	10.7	273	545
01A□AHC□						1/21	5.35/80	20.8	143	286
01A□AH7□						1/33	7.35/70	32.7	91	182
C2A□AH1□	150	3000	6000	0.477	1.67	1/5	1.68/83* <sup>2</sup>	7.80	600	1200
C2A□AHB□						1/11	3.53/79* <sup>2</sup>	16.9	273	545
C2A□AHC□						1/21	6.30/70* <sup>2</sup>	31.0	143	286
C2A□AH7□						1/33	11.2/79* <sup>2</sup>	49.7	91	182
02A□AH1□	200	3000	6000	0.637	2.23	1/5	2.39/75	9.80	600	1200
02A□AHB□						1/11	5.74/82	22.1	273	545
02A□AHC□						1/21	10.2/76	42.1	143	286
02A□AH7□						1/33	17.0/81	67.6	91	182
04A□AH1□	400	3000	6000	1.27	4.46	1/5	5.35/84	20.1	600	1200
04A□AHB□						1/11	11.5/82	45.1	273	545
04A□AHC□						1/21	23.0/86	87.0	143	286
04A□AH7□						1/33	34.0/81	135	91	182
06A□AH1□	600	3000	6000	1.91	6.69	1/5	7.54/79	30.5	600	1200
06A□AHB□						1/11	18.1/86	68.6	273	545
06A□AHC□						1/21	32.1/80	129	143	286
06A□AH7□						1/33	53.6/85	206	91	182
08A□AH1□	750	3000	6000	2.39	8.36	1/5	10.0/84	38.4	600	1200
08A□AHB□						1/11	23.1/88	86.4	273	545
08A□AHC□						1/21	42.1/84	163	143	286
08A□AH7□						1/33	69.3/88	259	91	182
10A□AH1□	1000	3000	6000	3.18	11.1	1/5	13.7/86	52.5	600	1200
10A□AHB□						1/11	29.1/83	111	273	545
10A□AHC□						1/21	58.2/87	215	143	286
10A□AH7□						1/33	94.5/90	296* <sup>3</sup>	91	182

\*1. The gear output torque is expressed by the following formula.

$$\text{Gear output torque} = \text{Servomotor output torque} \times \frac{1}{\text{Gear ratio}} \times \text{Efficiency}$$

The gear efficiency depends on operating conditions such as the output torque, motor speed, and temperature. The values in the table are typical values for the rated torque, rated motor speed, and a surrounding air temperature of 25°C. They are reference values only.

\*2. When using an SGM7A-A5A, SGM7A-01A, or SGM7A-C2A Servomotor with a gear ratio of 1/5 or an SGM7A-C2A Servomotor with a gear ratio of 1/11, maintain an 85% maximum effective load ratio. For an SGM7A-C2A Servomotor with a gear ratio of 1/21 or 1/33, maintain a 90% maximum effective load ratio. The values in the table take the effective load ratio into consideration.

\*3. The instantaneous maximum torque is 300% of the rated torque.

## 3.2 Specifications and Ratings

### 3.2.6 Ratings of Servomotors with Gears

- Note: 1. The gears that are mounted to Yaskawa Servomotors have not been broken in. Break in the Servomotor if necessary. First, operate the Servomotor at low speed with no load. If no problems occur, gradually increase the speed and load.
2. The no-load torque for a Servomotor with a Gear is high immediately after the Servomotor starts, and it then decreases and becomes stable after a few minutes. This is a common phenomenon caused by grease circulation in the gears and it does not indicate faulty gears.
3. Contact your Yaskawa representative for information on Servomotor with Gears with a rated output of 1.5 kW or higher.
4. Other specifications are the same as those for Servomotors without Gears.



Important

The SERVOPACK speed control range is 5,000:1. If you use Servomotors at extremely low speeds ( $0.02 \text{ min}^{-1}$  or lower at the gear output shaft), if you use Servomotors with a one-pulse feed reference for extended periods, or under some other operating conditions, the gear bearing lubrication may be insufficient. That may cause deterioration of the bearing or increase the load ratio. Contact your Yaskawa representative if you use a Servomotor under these conditions.

Servomotor Model SGM7A-	Moment of Inertia [ $\times 10^{-4} \text{ kg}\cdot\text{m}^2$ ]				With Gears			Reference Diagram
	Shaft Output		Flange Output		Allowable Radial Load [N]	Allowable Thrust Load [N]	LF [mm]	
	Motor* + Gear	Gear	Motor* + Gear	Gear				
A5A□AH1□	0.0277	0.006	0.0267	0.005	95	431	37	
A5A□AH2□	0.0247	0.003	0.0247	0.003	113	514	37	
A5A□AHC□	0.0257	0.004	0.0257	0.004	146	663	37	
A5A□AH7□	0.0667	0.045	0.0667	0.045	267	1246	53	
01A□AH1□	0.0397	0.006	0.0387	0.005	95	431	37	
01A□AHB□	0.0937	0.060	0.0927	0.059	192	895	53	
01A□AHC□	0.0837	0.050	0.0837	0.050	233	1087	53	
01A□AH7□	0.0987	0.065	0.0977	0.064	605	2581	75	
C2A□AH1□	0.0518	0.006	0.0508	0.005	95	431	37	
C2A□AHB□	0.106	0.060	0.105	0.059	192	895	53	
C2A□AHC□	0.156	0.110	0.154	0.108	528	2254	75	
C2A□AH7□	0.111	0.065	0.110	0.064	605	2581	75	
02A□AH1□	0.346	0.207	0.340	0.201	152	707	53	
02A□AHB□	0.332	0.193	0.331	0.192	192	895	53	
02A□AHC□	0.629	0.490	0.627	0.488	528	2254	75	
02A□AH7□	0.589	0.450	0.588	0.449	605	2581	75	
04A□AH1□	0.423	0.207	0.417	0.201	152	707	53	
04A□AHB□	0.786	0.570	0.776	0.560	435	1856	75	
04A□AHC□	0.706	0.490	0.704	0.488	528	2254	75	
04A□AH7□	0.836	0.620	0.826	0.610	951	4992	128	
06A□AH1□	1.02	0.700	0.975	0.660	343	1465	75	
06A□AHB□	0.885	0.570	0.875	0.560	435	1856	75	
06A□AHC□	1.16	0.840	1.14	0.820	830	4359	128	
06A□AH7□	0.935	0.620	0.925	0.610	951	4992	128	
08A□AH1□	1.48	0.700	1.44	0.660	343	1465	75	
08A□AHB□	1.38	0.600	1.37	0.590	435	1856	75	
08A□AHC□	3.78	3.00	3.76	2.98	830	4359	128	
08A□AH7□	3.58	2.80	3.57	2.79	951	4992	128	
10A□AH1□	1.67	0.700	1.63	0.660	343	1465	75	
10A□AHB□	4.37	3.40	4.31	3.34	684	3590	128	
10A□AHC□	3.97	3.00	3.95	2.98	830	4359	128	
10A□AH7□	3.77	2.80	3.76	2.79	951	4992	128	

\* The moment of inertia for the Servomotor and gear is the value without a holding brake. You can calculate the moment of inertia for a Servomotor with a Gear and Holding Brake with the following formula.  
 Motor moment of inertia for a Servomotor with a Holding Brake from 3.2.2 Ratings of Servomotors without Gears on page 3-5 + Moment of inertia for the gear from the above table.



Important

During operation, the gear generates the loss at the gear mechanism and oil seal. The loss depends on the torque and motor speed conditions. The temperature rise depends on the loss and heat dissipation conditions. For the heat dissipation conditions, always refer to the following table and check the gear and motor temperatures with the actual equipment. If the temperature is too high, implement the following measures.

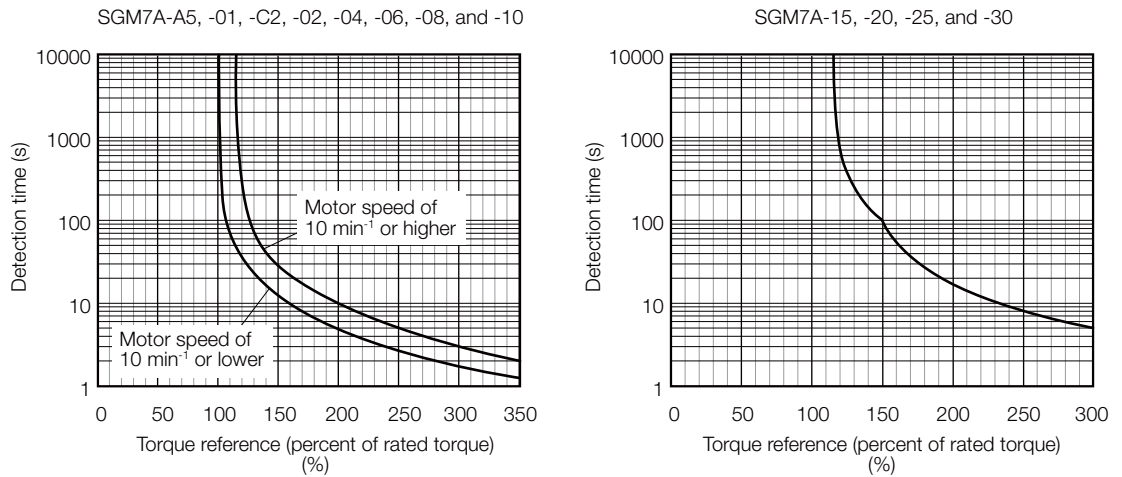
- Decrease the load ratio.
- Change the heat dissipation conditions.
- Use forced-air cooling for the motor with a cooling fan or other means.

Model	Heat Sink Size			
	1/5	1/9 or 1/11	1/21	1/33
SGM7A-A5	A			
SGM7A-01	B			
SGM7A-C2				
SGM7A-02				
SGM7A-04	C			
SGM7A-06				
SGM7A-08				
SGM7A-10A				

- A: 250 mm × 250 mm × 6 mm, aluminum plate
- B: 300 mm × 300 mm × 12 mm, aluminum plate
- C: 350 mm × 350 mm × 12 mm, aluminum plate

## 3.2.7 Servomotor Overload Protection Characteristics

The overload detection level is set for hot start conditions with a Servomotor ambient temperature of 40°C.



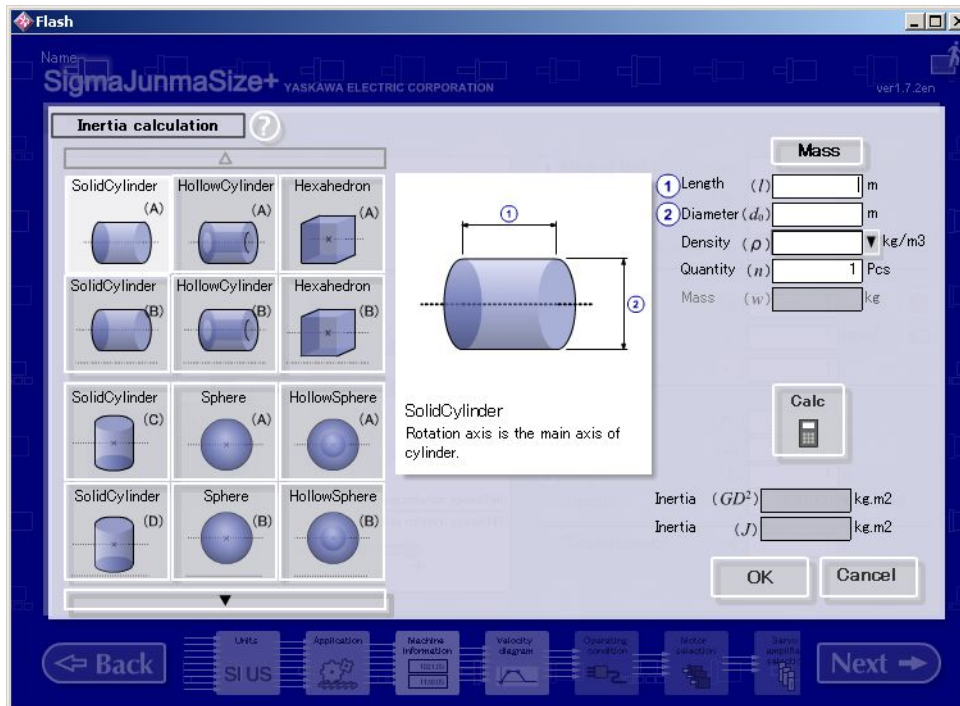
Note: The above overload protection characteristics do not mean that you can perform continuous duty operation with an output of 100% or higher. Use the Servomotor so that the effective torque remains within the continuous duty zone given in 3.2.3 *Torque-Motor Speed Characteristics* on page 3-6 or in 3.2.5 *Torque-Motor Speed Characteristics for Three-phase, 200 V* on page 3-8.

## 3.2.8 Load Moment of Inertia

The load moment of inertia indicates the inertia of the load. The larger the load moment of inertia, the worse the response. If the moment of inertia is too large, operation will become unstable.

The allowable size of the load moment of inertia ( $J_L$ ) for the Servomotor is restricted. Refer to 3.2.2 *Ratings of Servomotors without Gears* on page 3-5 or to 3.2.4 *Servomotor Ratings* on page 3-7. This value is provided strictly as a guideline and results depend on Servomotor driving conditions.

Use the SigmaJunmaSize+ AC Servo Drive Capacity Selection Program to check the driving conditions. Contact your Yaskawa representative for information on the SigmaJunmaSize+.



An Overvoltage Alarm (A.400) is likely to occur during deceleration if the load moment of inertia exceeds the allowable load moment of inertia. SERVOPACKs with a built-in regenerative resistor may generate a Regenerative Overload Alarm (A.320). Perform one of the following steps if this occurs.

- Reduce the torque limit.
- Reduce the deceleration rate.
- Reduce the maximum motor speed.
- Install an external regenerative resistor if the alarm cannot be cleared using the above steps.

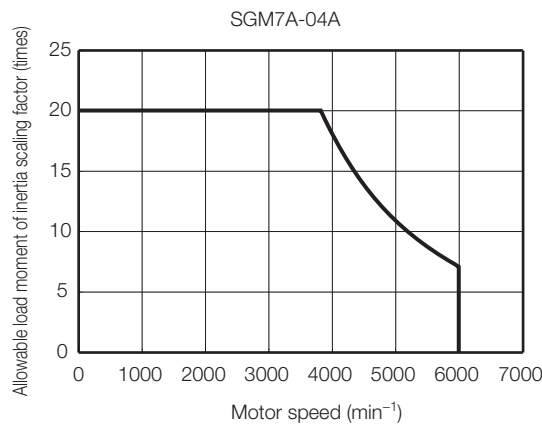
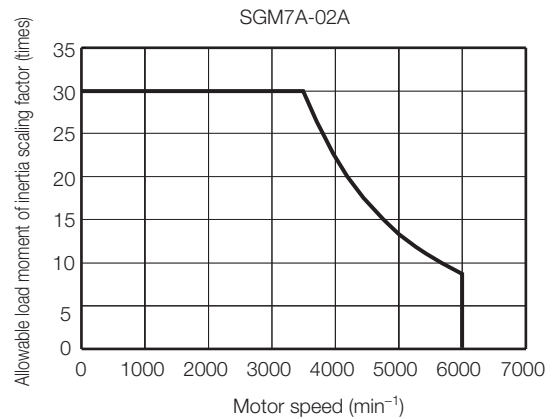
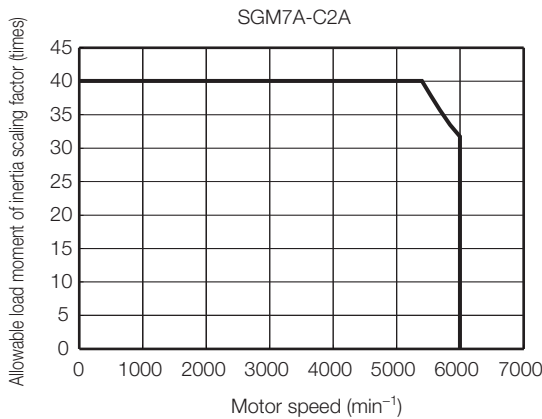
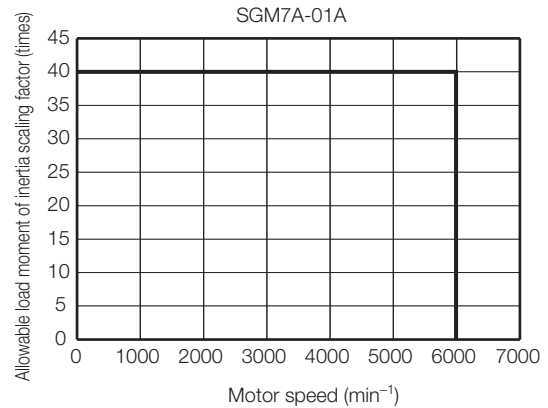
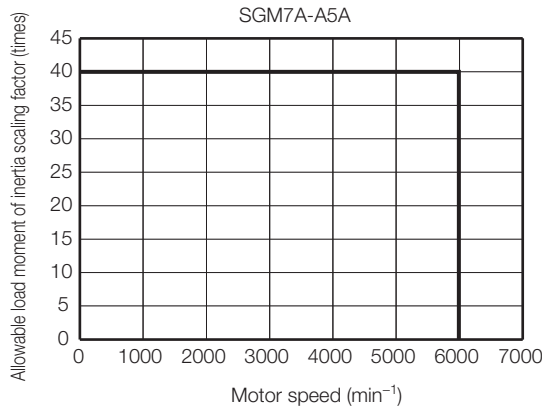
Regenerative resistors are not built into SERVOPACKs for 400-W Servomotors or smaller Servomotors. Even for SERVOPACKs with built-in regenerative resistors, an external regenerative resistor is required if the energy that results from the regenerative driving conditions exceeds the allowable loss capacity (W) of the built-in regenerative resistor.

## 3.2.9 Allowable Load Moment of Inertia Scaling Factor for SERVOPACKs without Built-in Regenerative Resistors

The following graphs show the allowable load moment of inertia scaling factor of the motor speed for SERVOPACKs\* without built-in regenerative resistors when an External Regenerative Resistor is not connected.

If the Servomotor exceeds the allowable load moment of inertia, an overvoltage alarm may occur in the SERVOPACK.

These graphs provide reference data for deceleration at the rated torque or higher with a 200-VAC power supply input.




\* Applicable SERVOPACK models: SGD7S-R70A, -R90A, -1R6A, or -2R8A



## 3.2.10 Servomotor Heat Dissipation Conditions

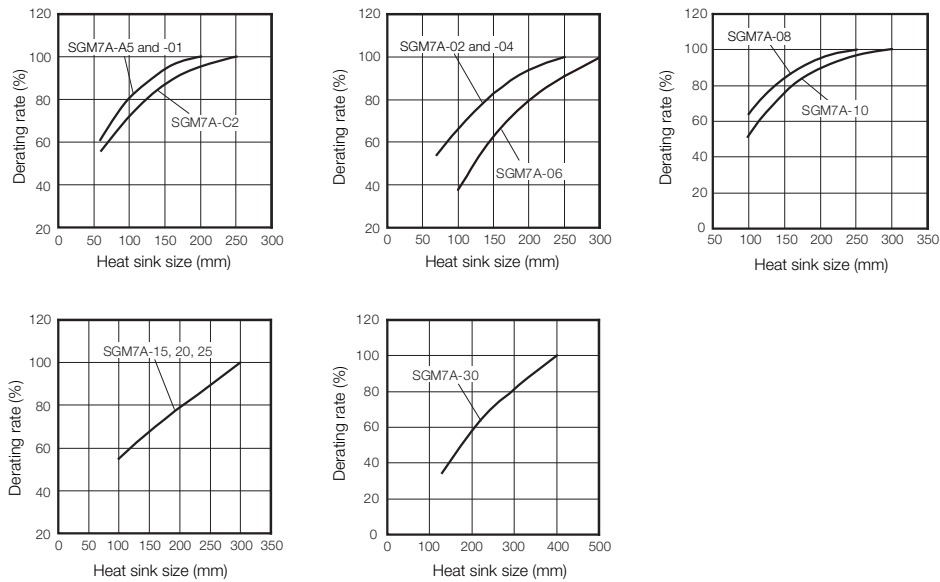
The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C when a heat sink is installed on the Servomotor. If the Servomotor is mounted on a small device component, the Servomotor temperature may rise considerably because the surface for heat dissipation becomes smaller. Refer to the following graphs for the relation between the heat sink size and derating rate.

Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



Important

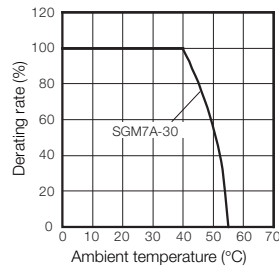
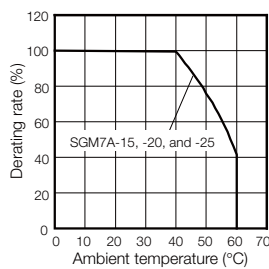
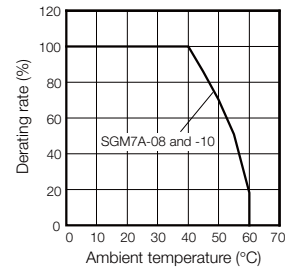
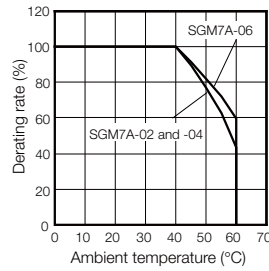
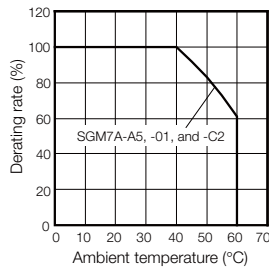
The actual temperature rise depends on how the heat sink (i.e., the Servomotor mounting section) is attached to the installation surface, what material is used for the Servomotor mounting section, and the motor speed. Always check the Servomotor temperature with the actual equipment.



### 3.2.11 Applications Where the Ambient Temperature of the Servomotor Exceeds 40°C

The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C. If you use a Servomotor at an ambient temperature that exceeds 40°C (60°C max.), apply a suitable derating rate from the following graphs.

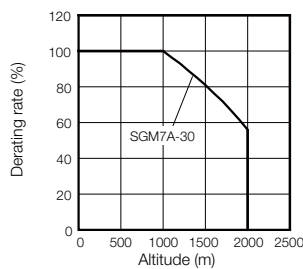
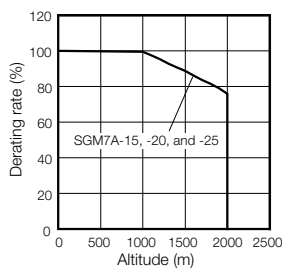
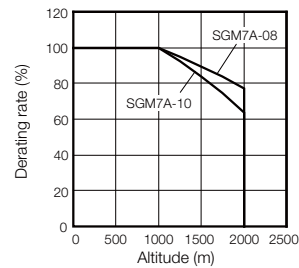
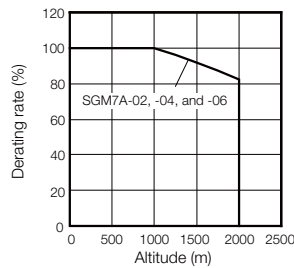
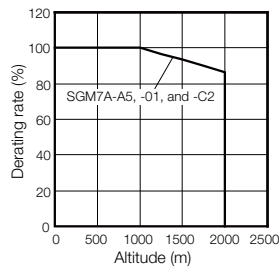
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



### 3.2.12 Applications Where the Altitude of the Servomotor Exceeds 1,000 m

The Servomotor ratings are the continuous allowable values at an altitude of 1,000 m or less. If you use a Servomotor at an altitude that exceeds 1,000 m (2,000 m max.), the heat dissipation effect of the air is reduced. Apply the appropriate derating rate from the following graphs.

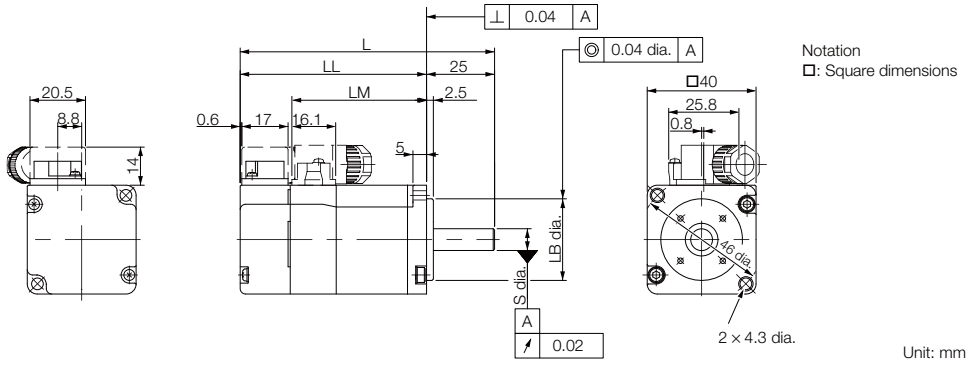
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



# 3.3 External Dimensions

## 3.3.1 Servomotors without Gears

### SGM7A-A5, -01, and -C2



Model SGM7A-	L	LL	LM	LB	S	Approx. Mass [kg]
A5A□A2□	81.5 (122)	56.5 (97)	37.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.3 (0.6)
01A□A2□	93.5 (134)	68.5 (109)	49.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.4 (0.7)
C2A□A2□	105.5 (153.5)	80.5 (128.5)	61.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.5 (0.8)

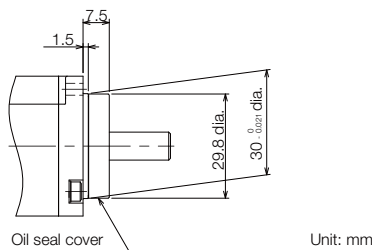
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Refer to the following section for detailed shaft end specifications.

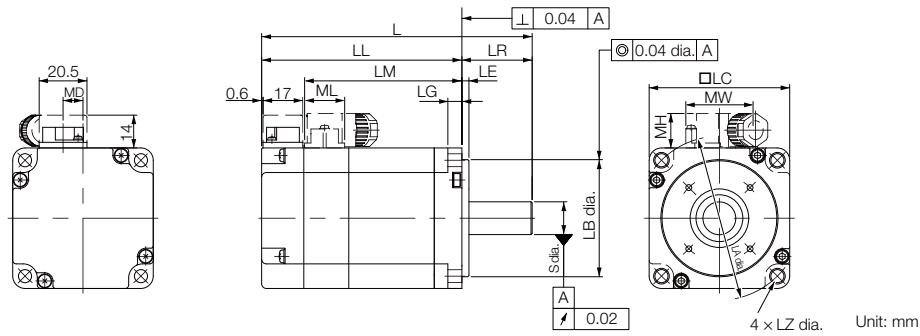
☞ 3.3.2 Shaft End Specifications for SGM7A-A5 to -10 on page 3-18

### ◆ Specifications of Options

- Oil Seal



## SGM7A-02 to -10



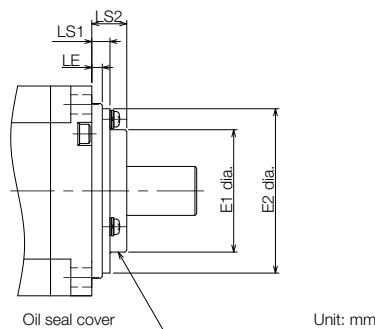
Model SGM7A-	L	LL	LM	Flange Dimensions							S
				LR	LE	LG	LC	LA	LB	LZ	
02A□A2□	99.5 (140)	69.5 (110)	51.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
04A□A2□	115.5 (156)	85.5 (126)	67.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
06A□A2□	137.5 (191.5)	107.5 (161.5)	89.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
08A□A2□	137 (184)	97 (144)	78.5	40	3	8	80	90	70 <sup>0</sup> <sub>-0.030</sub>	7	19 <sup>0</sup> <sub>-0.013</sub>
10A□A2□	162 (209)	122 (169)	103.5	40	3	8	80	90	70 <sup>0</sup> <sub>-0.030</sub>	7	19 <sup>0</sup> <sub>-0.013</sub>

Model SGM7A-	MD	MW	MH	ML	Approx. Mass [kg]
02A□A2□	8.5	28.7	14.7	17.1	0.8 (1.4)
04A□A2□	8.5	28.7	14.7	17.1	1.2 (1.8)
06A□A2□	8.5	28.7	14.7	17.1	1.6 (2.2)
08A□A2□	13.6	38	14.7	19.3	2.3 (2.9)
10A□A2□	13.6	38	14.7	19.3	3.1 (3.7)

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.  
 2. Refer to the following section for detailed shaft end specifications.  
 📖 3.3.2 Shaft End Specifications for SGM7A-A5 to -10 on page 3-18

### ◆ Specifications of Options

- Oil Seal



Model SGM7A-	Dimensions with Oil Seal			
	E1	E2	LS1	LS2
02A, 04A, 06A	35	47	5.2	10
08A, 10A	47	61	5.5	11

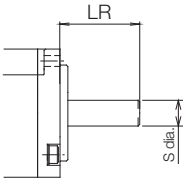
## 3.3.2 Shaft End Specifications for SGM7A-A5 to -10

### SGM7A-□□□□□□□□

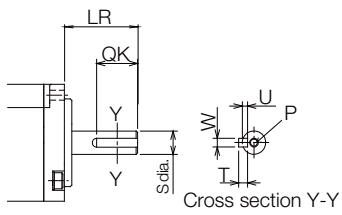
Code	Specification
2	Straight without key
6	Straight with key and tap for one location (Key slot is JIS B1301-1996 fastening type.)
B	With two flat seats

Shaft End Details	Servomotor Model SGM7A-							
	A5	01	C2	02	04	06	08	10

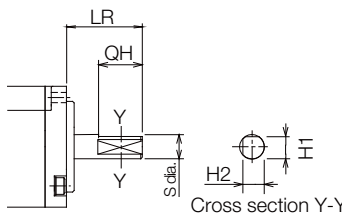
Code: 2 (Straight without Key)

	LR	25	30	40
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$

Code: 6 (Straight with Key and Tap)

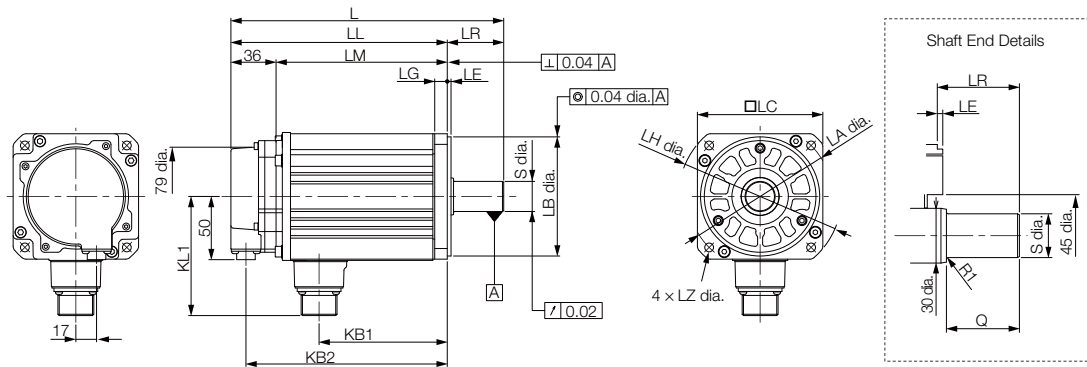
	LR	25	30	40
	QK	14	14	22
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$
	W	3	5	6
	T	3	5	6
	U	1.8	3	3.5
	P	M3 × 6L	M5 × 8L	M6 × 10L

Code: B (with Two Flat Seats)

	LR	25	30	40
	QH	15	15	22
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$
	H1	7.5	13	18
	H2	7.5	13	18

### 3.3.3 Servomotors without Gears and without Holding Brakes

## SGM7A-15, -20, and -25



Refer to 3.3.5 Shaft End Specifications for SGM7A-15 to -30 on page 3-21 for details.

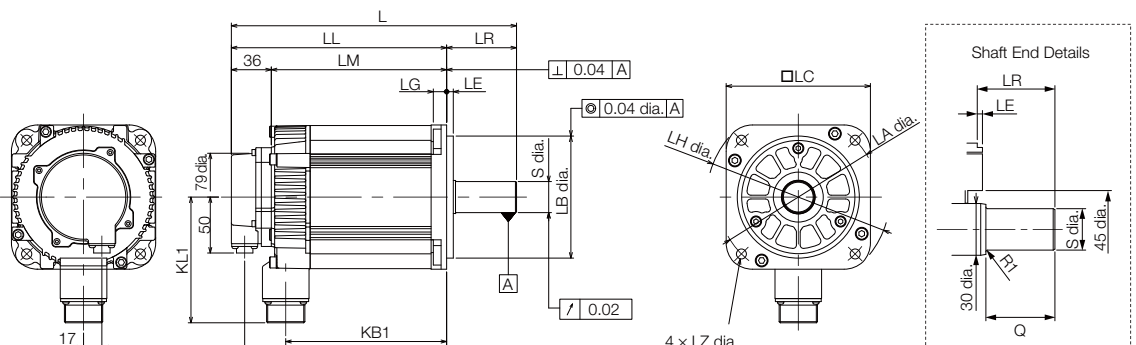
Unit: mm

Model SGM7A-	L	LL	LM	LR	KB1	KB2	KL1
15A□A21	202	157	121	45	86	145	96
20A□A21	218	173	137	45	102	161	96
25A□A21	241	196	160	45	125	184	96

Model SGM7A-	Flange Surface Dimensions							Shaft End Dimensions		Approx. Mass [kg]
	LA	LB	LC	LE	LG	LH	LZ	S	Q	
15A□A21	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	4.6
20A□A21	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	5.4
25A□A21	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	6.8

Note: Servomotors with Oil Seals have the same dimensions.

## SGM7A-30



Refer to 3.3.5 Shaft End Specifications for SGM7A-15 to -30 on page 3-21 for details.

Unit: mm

Model SGM7A-	L	LL	LM	LR	KB1	KB2	KL1
30A□A21	257	194	158	63	145	182	114

Model SGM7A-	Flange Surface Dimensions							Shaft End Dimensions		Approx. Mass [kg]
	LA	LB	LC	LE	LG	LH	LZ	S	Q	
30A□A21	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	28 <sup>0</sup> <sub>-0.013</sub>	55	10.5

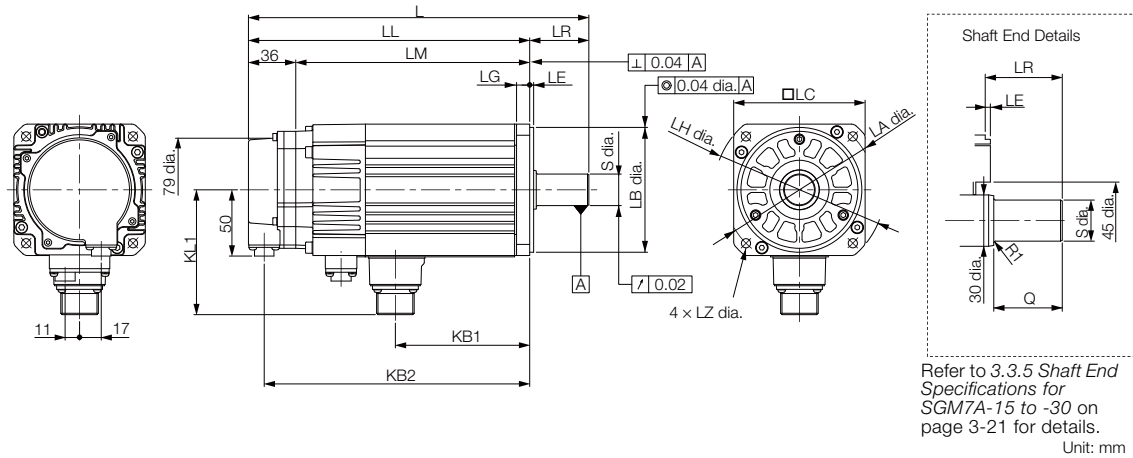
Note: Servomotors with Oil Seals have the same dimensions.

Refer to the following section for information on connectors.

☞ SGM7A-15 to -30 without Holding Brakes on page 3-28

## 3.3.4 Servomotors without Gears and with Holding Brakes

### SGM7A-15 to -30



Model SGM7A-	L	LL	LM	LR	KB1	KB2	KL1
15A□A2C	243	198	162	45	77	186	102
20A□A2C	259	214	178	45	93	202	102
25A□A2C	292	247	211	45	116	225	102
30A□A2C	295	232	196	63	114	220	119

Model SGM7A-	Flange Surface Dimensions							Shaft End Dimensions		Approx. Mass [kg]
	LA	LB	LC	LE	LG	LH	LZ	S	Q	
15A□A2C	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	6.0
20A□A2C	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	6.8
25A□A2C	115	95 <sup>0</sup> <sub>-0.035</sub>	100	3	10	130	7	24 <sup>0</sup> <sub>-0.013</sub>	40	8.7
30A□A2C	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	28 <sup>0</sup> <sub>-0.013</sub>	55	13

Note: Servomotors with Oil Seals have the same dimensions.

Refer to the following section for information on connectors.

👉 SGM7A-15 to -30 with Holding Brakes on page 3-28

### 3.3.5 Shaft End Specifications for SGM7A-15 to -30

#### SGM7A-□□□□□□

Code	Specification
2	Straight without key
6	Straight with key and tap for one location (Key slot is JIS B1301-1996 fastening type.)

Shaft End Details	Servomotor Model SGM7A-			
	15	20	25	30

Code: 2 (Straight without Key)

	LR	45	63
	Q	40	55
	S	$24^{0}_{-0.013}$	$28^{0}_{-0.013}$

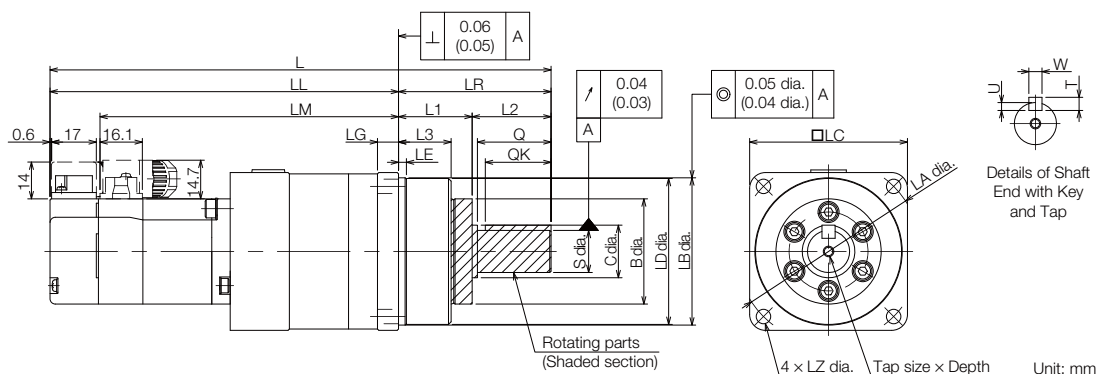
Code: 6 (Straight with Key and Tap)

	LR	45	63
	Q	40	55
	QK	32	50
	S	$24^{0}_{-0.013}$	$28^{0}_{-0.013}$
	W	8	
	T	7	
	U	4	
P	M8 screw, Depth: 16		



## 3.3.6 Servomotors with Gears

### SGM7A-A5, -01, and -C2



Model SGM7A-	Gear Ratio	L	LL	LM	Flange Surface Dimensions									
					LR	LE	LG	B	LD	LB	LC	LA	LZ	
A5A□AH1	1/5	138	96	77.4										
A5A□AH2	1/9	(178.5)	(136.5)		42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4	
A5A□AHC	1/21	147	105	86.4										
A5A□AH7	1/33	178.5	120.5	101.9	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5	
01A□AH1	1/5	150	108	89.4	42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4	
01A□AHB	1/11	190.5	132.5	113.9	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5	
01A□AHC	1/21	(231)	(173)											
01A□AH7	1/33	215	135	116.4	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9	
C2A□AH1	1/5	162	120	101.4	42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4	
C2A□AHB	1/11	202.5	144.5	125.9	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5	
C2A□AHC	1/21	227	147	128.4	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9	
C2A□AH7	1/33	(275)	(195)											

Model SGM7A-	Flange Surface Dimensions			Q	C	S	Tap Size × Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
A5A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.6
A5A□AH2												0.7
A5A□AHC												1.0
A5A□AH7	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.3
01A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.7
01A□AHB	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.4
01A□AHC												1.7
01A□AH7	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	2.8
C2A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.8
C2A□AHB	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.5
C2A□AHC	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	1.8
C2A□AH7												3.2

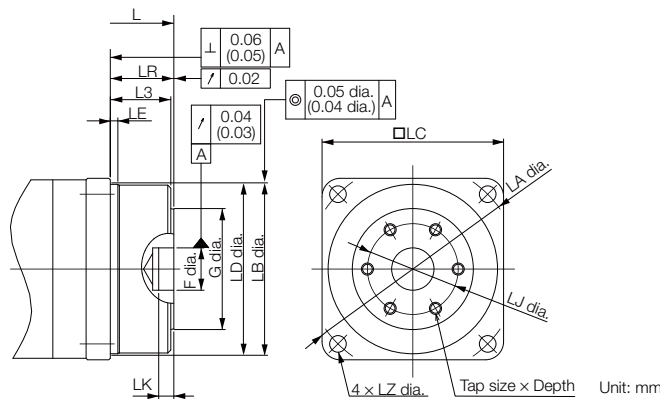
\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation.

If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.

◆ Flange Output Face




Note: The geometric tolerance in parentheses is the value for LC = 40.

Model SGM7A-	Gear Ratio	L	LR	LJ	F	G	LK	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
A5A□AH10□	1/5	111 (151.5)	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	3	3 × M4 × 6L	0.6 (0.9)
A5A□AH20□	1/9								
A5A□AHC0□	1/21	120 (160.5)							
A5A□AH70□	1/33	141.5 (182)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	5	6 × M4 × 7L	1.2 (1.5)
01A□AH10□	1/5	123 (163.5)	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	3	3 × M4 × 6L	0.7 (1.0)
01A□AHB0□	1/11	153.5 (194)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	5	3 × M4 × 7L	1.3 (1.6)
01A□AHC0□	1/21							6 × M6 × 10L	2.4 (2.7)
01A□AH70□	1/33	162 (202.5)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59			
02A□AH10□	1/5	135 (183)	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	3	3 × M4 × 6L	0.8 (1.1)
02A□AHB0□	1/11	165.5 (213.5)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	5	6 × M4 × 7L	1.4 (1.7)
02A□AHC0□	1/21	174 (222)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	5	6 × M6 × 10L	2.5 (2.8)
02A□AH70□	1/33								

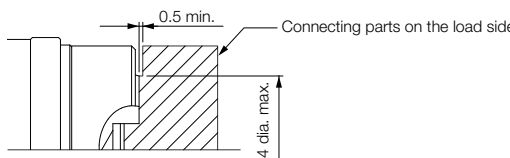
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

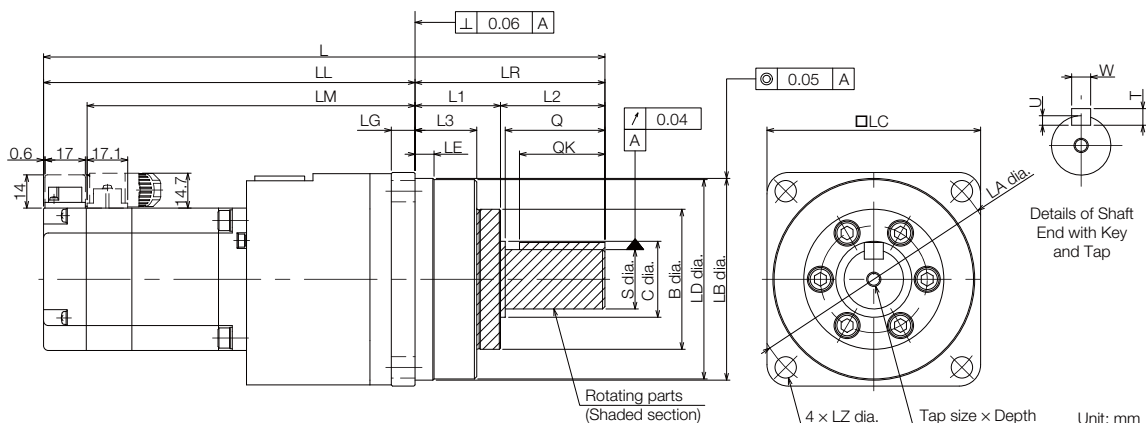


Important

For a Servomotor with a flange output that has square gear flange dimensions (□LC) of 40 mm, we recommend that you design the Servomotor with the dimensions shown in the following figure in order to secure a gap between the gear oil seal and the connecting parts on the load side.



### SGM7A-02, -04, and -06



Model SGM7A-	Gear Ratio	L	LL	LM	Flange Surface Dimensions								
					LR	LE	LG	B	LD	LB	LC	LA	LZ
02A□AH1 □□	1/5	191.5	133.5	115.2	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5
02A□AH2 □□	1/11	(232)	(174)										
02A□AHC □□	1/21	220.5	140.5	122.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
02A□AH7 □□	1/33	(261)	(181)										
04A□AH1 □□	1/5	207.5	149.5	131.2	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5
04A□AHB □□	1/11	236.5	156.5	138.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
04A□AHC □□	1/21	(277)	(197)										
04A□AH7 □□	1/33	322.5	189.5	171.2	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
06A□AH1 □□	1/5	258.5	178.5	160.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
06A□AHB □□	1/11	(312.5)	(232.5)										
06A□AHC □□	1/21	344.5	211.5	193.2	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
06A□AH7 □□	1/33	(398.5)	(265.5)										

Model SGM7A-	Flange Surface Dimensions			Q	C	S	Tap Size × Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
02A□AH1 □□	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.8 (2.4)
02A□AH2 □□												1.9 (2.5)
02A□AHC □□	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	3.7 (4.3)
02A□AH7 □□												
04A□AH1 □□	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	2.1 (2.7)
04A□AHB □□												
04A□AHC □□	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	4.0 (4.6)
04A□AH7 □□												
06A□AH1 □□	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	8.6 (9.2)
06A□AHB □□												4.3 (4.9)
06A□AHC □□	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 × 20L	70	5	12	8	4.5 (5.1)
06A□AH7 □□												9.1 (9.7)

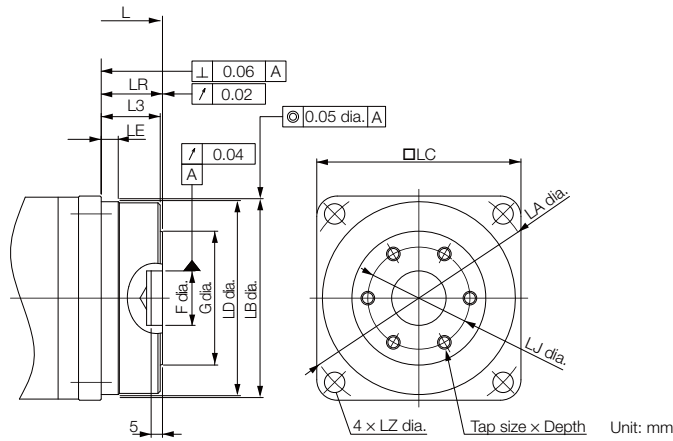
\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation.

If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.

◆ Flange Output Face

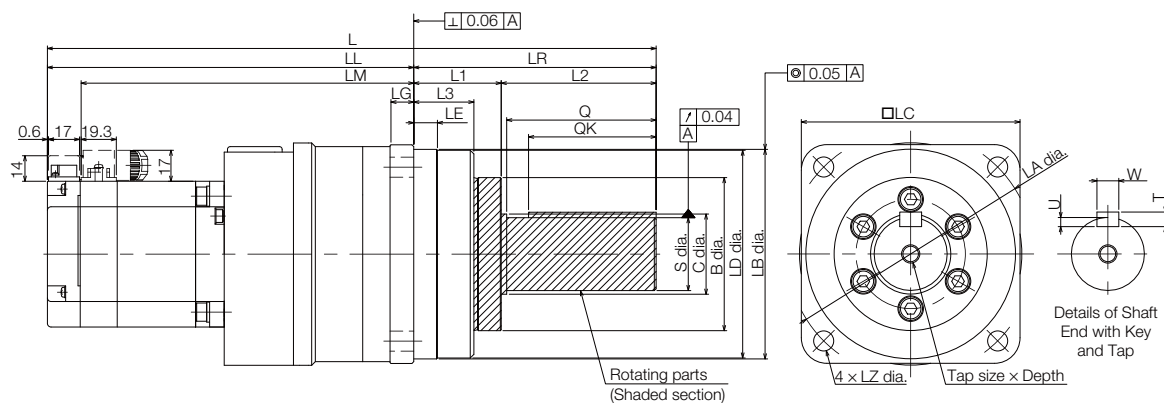


Model SGM7A-	Gear Ratio	L	LR	LJ	F	G	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
02A□AH10□	1/5	154.5 (195)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	6 × M4 × 7L	1.7 (2.3)
02A□AH20□	1/11							1.8 (2.4)
02A□AHC0□	1/21	167.5 (208)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.3 (3.9)
02A□AH70□	1/33							
04A□AH10□	1/5	170.5 (211)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	6 × M4 × 7L	2.0 (2.6)
04A□AHB0□	1/11	183.5 (224)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.6 (4.2)
04A□AHC0□	1/21							
04A□AH70□	1/33	224.5 (265)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	7.2 (7.8)
06A□AH10□	1/5	205.5 (259.5)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.9 (4.5)
06A□AHB0□	1/11							4.1 (4.7)
06A□AHC0□	1/21	246.5 (300.5)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	7.7 (8.3)
06A□AH70□	1/33							

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

### SGM7A-08 and -10



Unit: mm

Model SGM7A-	Gear Ratio	L	LL	LM	Flange Surface Dimensions								
					LR	LE	LG	B	LD	LB	LC	LA	LZ
08A□AH1 □□	1/5	255	175	156.5	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
08A□AHB □□	1/11	(302)	(222)										
08A□AHC □□	1/21	334	201	182.5	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
08A□AH7 □□	1/33	(381)	(248)										
10A□AH1 □□	1/5	280	200	181.5	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
10A□AHB □□	1/11	359	226										
10A□AHC □□	1/21	(406)	(273)	207.5	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
10A□AH7 □□	1/33												

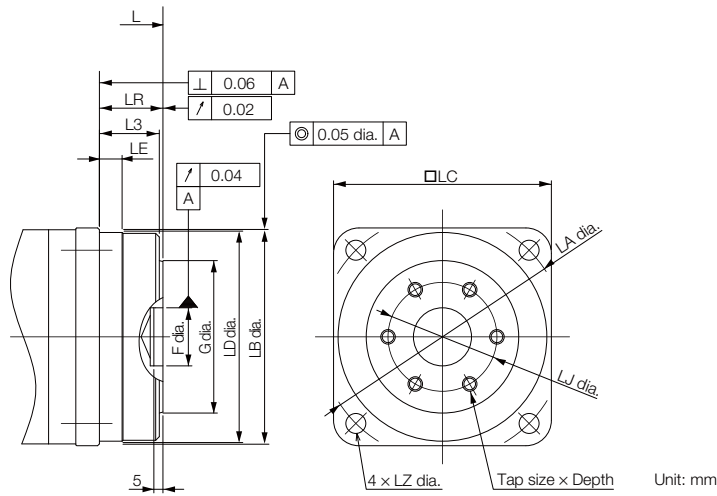
Model SGM7A-	Flange Surface Dimensions			Q	C	S	Tap Size x Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
08A□AH1 □□	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 x 12L	36	4	8	7	4.9 (5.8)
08A□AHB □□												5.1 (6.0)
08A□AHC □□	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 x 20L	70	5	12	8	9.8 (10.7)
08A□AH7 □□												
10A□AH1 □□	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 x 12L	36	4	8	7	6.0 (6.6)
10A□AHB □□												
10A□AHC □□	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 x 20L	70	5	12	8	10.9 (11.5)
10A□AH7 □□												

\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation. If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.

◆ Flange Output Face



Model SGM7A-	Gear Ratio	L	LR	LJ	F	G	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
08A□AH10□	1/5	202 (249)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	4.7 (5.3)
08A□AHB0□	1/11							4.9 (5.5)
08A□AHC0□	1/21	236 (283)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	8.6 (9.2)
08A□AH70□	1/33							
10A□AH10□	1/5	227 (274)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	5.6 (6.3)
10A□AHB0□	1/11	261 (308)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	9.5 (10.1)
10A□AHC0□	1/21							
10A□AH70□	1/33							

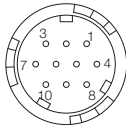
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

## 3.3.7 Connector Specifications

### SGM7A-15 to -30 without Holding Brakes

- Encoder Connector Specifications (24-bit Encoder)



Receptacle: CM10-R10P-D

Applicable plug: Not provided by Yaskawa.

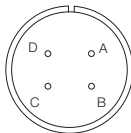
Plug: CM10-AP10S-□-D for Right-angle Plug  
 CM10-SP10S-□-D for Straight Plug  
 (□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT (+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT (-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

- Servomotor Connector Specifications

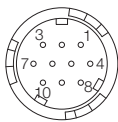


Manufacturer: DDK Ltd.

A	Phase U
B	Phase V
C	Phase W
D	FG (frame ground)

### SGM7A-15 to -30 with Holding Brakes

- Encoder Connector Specifications (24-bit Encoder)



Receptacle: CM10-R10P-D

Applicable plug: Not provided by Yaskawa.

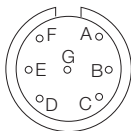
Plug: CM10-AP10S-□-D for Right-angle Plug  
 CM10-SP10S-□-D for Straight Plug  
 (□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT (+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT (-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

- Servomotor Connector Specifications



Manufacturer: Japan Aviation Electronics Industry, Ltd.

A	Phase U
B	Phase V
C	Phase W
D	FG (frame ground)
E	Brake terminal
F	Brake terminal
G	-

Note: There is no voltage polarity for the brake terminals.

# Specifications, Ratings, and External Dimensions of SGM7J Servomotors

# 4

This chapter describes how to interpret the model numbers of SGM7J Servomotors and gives their specifications, ratings, and external dimensions.

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# 4.1 Model Designations

## 4.1.1 Without Gears



Σ-7 Series Servomotors: SGM7J

1st+2nd digits Rated Output

Code	Specification
A5	50 W
01	100 W
C2	150 W
02	200 W
04	400 W
06	600 W
08	750 W

3rd digit Power Supply Voltage

Code	Specification
A	200 VAC

4th digit Serial Encoder

Code	Specification
7	24-bit absolute
F	24-bit incremental

5th digit Design Revision Order

A

6th digit Shaft End

Code	Specification
2	Straight without key
6	Straight with key and tap
B	With two flat seats

7th digit Options

Code	Specification
1	Without options
C	With holding brake (24 VDC)
E	With oil seal and holding brake (24 VDC)
S	With oil seal

## 4.1.2 With Gears



Σ-7 Series Servomotors: SGM7J

1st+2nd digits Rated Output

Code	Specification
A5	50 W
01	100 W
C2	150 W
02	200 W
04	400 W
06	600 W
08	750 W

3rd digit Power Supply Voltage

Code	Specification
A	200 VAC

4th digit Serial Encoder

Code	Specification
7	24-bit absolute
F	24-bit incremental

5th digit Design Revision Order

A

6th digit Gear Type

Code	Specification
H	HDS planetary low-backlash gear

7th digit Gear Ratio

Code	Specification
B	1/11*1
C	1/21
1	1/5
2	1/9*2
7	1/33

\*1. This specification is not supported for models with a rated output of 50 W.

\*2. This specification is supported only for models with a rated output of 50 W.

8th digit Shaft End

Code	Specification
0	Flange output
2	Straight without key
6	Straight with key and tap

9th digit Options

Code	Specification
1	Without options
C	With holding brake (24 VDC)

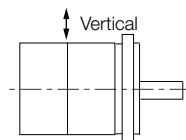
## 4.2 Specifications and Ratings

### 4.2.1 Specifications

Voltage		200 V						
Model SGM7J-		A5A	01A	C2A	02A	04A	06A	08A
Time Rating		Continuous						
Thermal Class		B						
Insulation Resistance		500 VDC, 10 M $\Omega$ min.						
Withstand Voltage		1,500 VAC for 1 minute						
Excitation		Permanent magnet						
Mounting		Flange-mounted						
Drive Method		Direct drive						
Rotation Direction		Counterclockwise (CCW) for forward reference when viewed from the load side						
Vibration Class* <sup>1</sup>		V15						
Environmental Conditions	Surrounding Air Temperature	0°C to 40°C (With derating, usage is possible between 40°C and 60°C.)* <sup>4</sup>						
	Surrounding Air Humidity	20% to 80% relative humidity (with no condensation)						
	Installation Site	<ul style="list-style-type: none"> <li>• Must be indoors and free of corrosive and explosive gases.</li> <li>• Must be well-ventilated and free of dust and moisture.</li> <li>• Must facilitate inspection and cleaning.</li> <li>• Must have an altitude of 1,000 m or less. (With derating, usage is possible between 1,000 m and 2,000 m.)*<sup>5</sup></li> <li>• Must be free of strong magnetic fields.</li> </ul>						
	Storage Environment	Store the Servomotor in the following environment if you store it with the power cable disconnected. Storage Temperature: -20°C to 60°C (with no freezing) Storage Humidity: 20% to 80% relative humidity (with no condensation)						
Shock Resistance* <sup>2</sup>	Impact Acceleration Rate at Flange	490 m/s <sup>2</sup>						
	Number of Impacts	2 times						
Vibration Resistance* <sup>3</sup>	Vibration Acceleration Rate at Flange	49 m/s <sup>2</sup>						
Applicable SERVOPACKs		Refer to 1.4 <i>Combinations of Servomotors and SERVOPACKs</i> on page 1-5.						

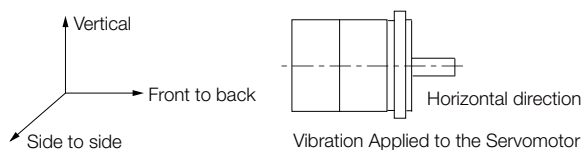
\*1. A vibration class of V15 indicates a vibration amplitude of 15  $\mu$ m maximum on the Servomotor without a load at the rated motor speed.

\*2. The shock resistance for shock in the vertical direction when the Servomotor is mounted with the shaft in a horizontal position is given in the above table.



Shock Applied to the Servomotor

\*3. The vertical, side-to-side, and front-to-back vibration resistance for vibration in three directions when the Servomotor is mounted with the shaft in a horizontal position is given in the above table. The strength of the vibration that the Servomotor can withstand depends on the application. Always check the vibration acceleration rate that is applied to the Servomotor with the actual equipment.



Vibration Applied to the Servomotor

\*4. If the ambient temperature will exceed 40°C, refer to the following section.

☞ 4.2.9 *Applications Where the Ambient Temperature of the Servomotor Exceeds 40 °C* on page 4-12

\*5. If the altitude will exceed 1,000 m, refer to the following section.

☞ 4.2.10 *Applications Where the Altitude of the Servomotor Exceeds 1,000 m* on page 4-13

## 4.2.2 Ratings of Servomotors without Gears

Voltage		200 V							
Model SGM7J-		A5A	01A	C2A	02A	04A	06A	08A	
Rated Output* <sup>1</sup>	W	50	100	150	200	400	600	750	
Rated Torque* <sup>1, *2</sup>	N·m	0.159	0.318	0.477	0.637	1.27	1.91	2.39	
Instantaneous Maximum Torque* <sup>1</sup>	N·m	0.557	1.11	1.67	2.23	4.46	6.69	8.36	
Rated Current* <sup>1</sup>	Arms	0.55	0.85	1.6	1.6	2.5	4.2	4.4	
Instantaneous Maximum Current* <sup>1</sup>	Arms	2.0	3.1	5.7	5.8	9.3	15.3	16.9	
Rated Motor Speed* <sup>1</sup>	min <sup>-1</sup>	3000							
Maximum Motor Speed* <sup>1</sup>	min <sup>-1</sup>	6000							
Torque Constant	N·m/Arms	0.316	0.413	0.321	0.444	0.544	0.493	0.584	
Motor Moment of Inertia	×10 <sup>-4</sup> kg·m <sup>2</sup>	0.0395 (0.0475)	0.0659 (0.0739)	0.0915 (0.0995)	0.263 (0.333)	0.486 (0.556)	0.800 (0.870)	1.59 (1.77)	
Rated Power Rate* <sup>1</sup>	kW/s	6.40 (5.32)	15.3 (13.6)	24.8 (22.8)	15.4 (12.1)	33.1 (29.0)	45.6 (41.9)	35.9 (32.2)	
Rated Angular Acceleration Rate* <sup>1</sup>	rad/s <sup>2</sup>	40200 (33400)	48200 (43000)	52100 (47900)	24200 (19100)	26100 (22800)	23800 (21900)	15000 (13500)	
Derating Rate for Servomotor with Oil Seal	%	80	90			95			
Heat Sink Size	mm	200 × 200 × 6			250 × 250 × 6				
Protective Structure* <sup>3</sup>	Totally enclosed, self-cooled, IP67								
Holding Brake Specifications* <sup>4</sup>	Rated Voltage	V	24 VDC±10%						
	Capacity	W	5.5			6		6.5	
	Holding Torque	N·m	0.159	0.318	0.477	0.637	1.27	1.91	2.39
	Coil Resistance	Ω (at 20°C)	104.8±10%			96±10%		88.6±10%	
	Rated Current	A (at 20°C)	0.23			0.25		0.27	
	Time Required to Release Brake	ms	60					80	
	Time Required to Brake	ms	100						
Allowable Load Moment of Inertia (Motor Moment of Inertia Ratio)		35 times			15 times	10 times	20 times	12 times	
	With External Regenerative Resistor and Dynamic Brake Resistor				25 times			15 times	
Allowable Shaft Loads* <sup>5</sup>	LF	mm	20			25		35	
	Allowable Radial Load	N	78			245		392	
	Allowable Thrust Load	N	54			74		147	

Note: The values in parentheses are for Servomotors with Holding Brakes.

\*1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 100°C. The values for other items are at 20°C. These are typical values.

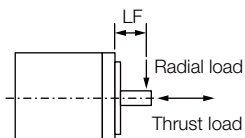
\*2. The rated torques are the continuous allowable torque values at 40°C with an aluminum heat sink of the dimensions given in the table.

\*3. This does not apply to the shaft opening. Protective structure specifications apply only when the special cable is used.

\*4. Observe the following precautions if you use a Servomotor with a Holding Brake.

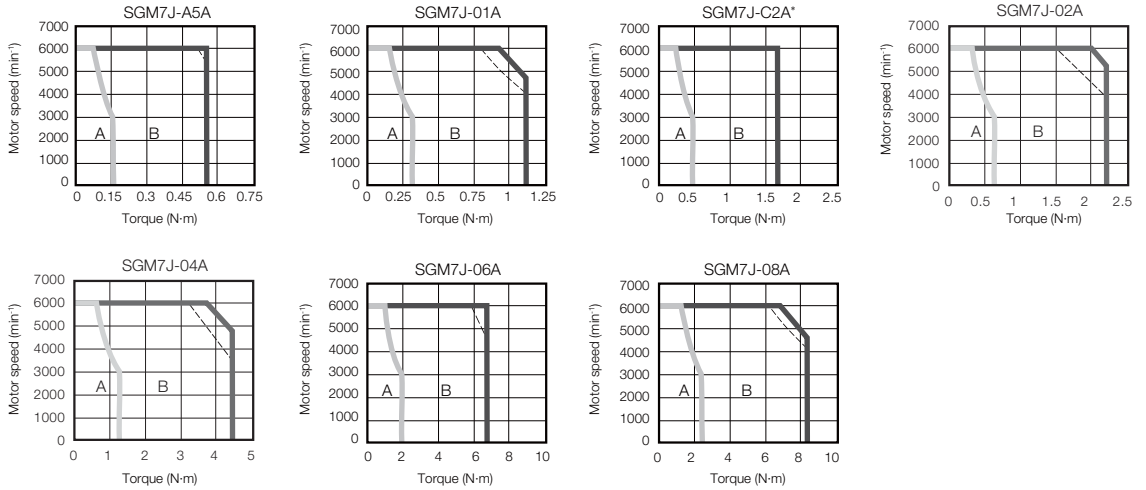
- The holding brake cannot be used to stop the Servomotor.
- The time required to release the brake and the time required to brake depend on which discharge circuit is used. Confirm that the operation delay time is appropriate for the actual equipment.
- The 24-VDC power supply is not provided by Yaskawa.

\*5. The allowable shaft loads are illustrated in the following figure. Design the mechanical system so that the thrust and radial loads applied to the Servomotor shaft end during operation do not exceed the values given in the table.



## 4.2.3 Torque-Motor Speed Characteristics

A : Continuous duty zone      — (solid lines): With three-phase 200-V or single-phase 230-V input  
B : Intermittent duty zone      - - - - (dotted lines): With single-phase 200-V input



\* The characteristics are the same for three-phase 200 V and single-phase 200 V.

Note: 1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 100°C. These are typical values.

2. The characteristics in the intermittent duty zone depend on the power supply voltage.
3. If the effective torque is within the allowable range for the rated torque, the Servomotor can be used within the intermittent duty zone.
4. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.

## 4.2.4 Ratings of Servomotors with Gears

All Models	Gear Mechanism	Protective Structure	Lost Motion [arc-min]
	Planetary gear mechanism	Totally enclosed, self-cooled, IP55 (except for shaft opening)	3 max.

Servomotor Model SGM7J-	Servomotor					Gear Output				
	Rated Output [W]	Rated Motor Speed [min <sup>-1</sup> ]	Maximum Motor Speed [min <sup>-1</sup> ]	Rated Torque [N·m]	Instantaneous Maximum Torque [N·m]	Gear Ratio	Rated Torque/Efficiency <sup>*1</sup> [N·m/%]	Instantaneous Maximum Torque [N·m]	Rated Motor Speed [min <sup>-1</sup> ]	Maximum Motor Speed [min <sup>-1</sup> ]
A5A□AH1□	50	3000	6000	0.159	0.557	1/5	0.433/64 <sup>*2</sup>	2.37	600	1200
A5A□AH2□						1/9	1.12/78	3.78 <sup>*3</sup>	333	667
A5A□AHC□						1/21	2.84/85	10.6	143	286
A5A□AH7□						1/33	3.68/70	15.8	91	182
01A□AH1□	100	3000	6000	0.318	1.11	1/5	1.06/78 <sup>*2</sup>	4.96	600	1200
01A□AHB□						1/11	2.52/72	10.7	273	545
01A□AHC□						1/21	5.35/80	20.8	143	286
01A□AH7□						1/33	7.35/70	32.7	91	182
C2A□AH1□	150	3000	6000	0.477	1.67	1/5	1.68/83 <sup>*2</sup>	7.80	600	1200
C2A□AHB□						1/11	3.53/79 <sup>*2</sup>	16.9	273	545
C2A□AHC□						1/21	6.30/70 <sup>*2</sup>	31.0	143	286
C2A□AH7□						1/33	11.2/79 <sup>*2</sup>	49.7	91	182
02A□AH1□	200	3000	6000	0.637	2.23	1/5	2.39/75	9.80	600	1200
02A□AHB□						1/11	5.74/82	22.1	273	545
02A□AHC□						1/21	10.2/76	42.1	143	286
02A□AH7□						1/33	17.0/81	67.6	91	182
04A□AH1□	400	3000	6000	1.27	4.46	1/5	5.35/84	20.1	600	1200
04A□AHB□						1/11	11.5/82	45.1	273	545
04A□AHC□						1/21	23.0/86	87.0	143	286
04A□AH7□						1/33	34.0/81	135	91	182
06A□AH1□	600	3000	6000	1.91	6.69	1/5	7.54/79	30.5	600	1200
06A□AHB□						1/11	18.1/86	68.6	273	545
06A□AHC□						1/21	32.1/80	129	143	286
06A□AH7□						1/33	53.6/85	206	91	182
08A□AH1□	750	3000	6000	2.39	8.36	1/5	10.0/84	38.4	600	1200
08A□AHB□						1/11	23.1/88	86.4	273	545
08A□AHC□						1/21	42.1/84	163	143	286
08A□AH7□						1/33	69.3/88	259	91	182

\*1. The gear output torque is expressed by the following formula.

$$\text{Gear output torque} = \text{Servomotor output torque} \times \frac{1}{\text{Gear ratio}} \times \text{Efficiency}$$

The gear efficiency depends on operating conditions such as the output torque, motor speed, and temperature. The values in the table are typical values for the rated torque, rated motor speed, and a surrounding air temperature of 25°C. They are reference values only.

\*2. When using an SGM7J-A5A, SGM7J-01A, or SGM7J-C2A Servomotor with a gear ratio of 1/5 or an SGM7J-C2A Servomotor with a gear ratio of 1/11, maintain an 85% maximum effective load ratio. For an SGM7J-C2A Servomotor with a gear ratio of 1/21 or 1/33, maintain a 90% maximum effective load ratio. The values in the table take the effective load ratio into consideration.

\*3. The instantaneous maximum torque is 300% of the rated torque.

Note: 1. The gears that are mounted to Yaskawa Servomotors have not been broken in.

Break in the Servomotor if necessary. First, operate the Servomotor at low speed with no load. If no problems occur, gradually increase the speed and load.

2. The no-load torque for a Servomotor with a Gear is high immediately after the Servomotor starts, and it then decreases and becomes stable after a few minutes.

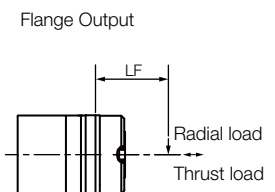
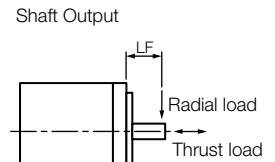
This is a common phenomenon caused by grease circulation in the gears and it does not indicate faulty gears.

3. Other specifications are the same as those for Servomotors without Gears.



The SERVOPACK speed control range is 5,000:1. If you use Servomotors at extremely low speeds ( $0.02 \text{ min}^{-1}$  or lower at the gear output shaft), if you use Servomotors with a one-pulse feed reference for extended periods, or under some other operating conditions, the gear bearing lubrication may be insufficient. That may cause deterioration of the bearing or increase the load ratio. Contact your Yaskawa representative if you use a Servomotor under these conditions.

Servomotor Model SGM7J-	Moment of Inertia [ $\times 10^{-4} \text{ kg}\cdot\text{m}^2$ ]				With Gears			Reference Diagram
	Shaft Output		Flange Output		Allowable Radial Load [N]	Allowable Thrust Load [N]	LF [mm]	
	Motor* + Gear	Gear	Motor* + Gear	Gear				
A5A□AH1□	0.0455	0.006	0.0445	0.005	95	431	37	
A5A□AH2□	0.0425	0.003	0.0425	0.003	113	514	37	
A5A□AHC□	0.0435	0.004	0.0435	0.004	146	663	37	
A5A□AH7□	0.0845	0.045	0.0845	0.045	267	1246	53	
01A□AH1□	0.0719	0.006	0.0709	0.005	95	431	37	
01A□AHB□	0.126	0.060	0.125	0.059	192	895	53	
01A□AHC□	0.116	0.050	0.116	0.050	233	1087	53	
01A□AH7□	0.131	0.065	0.130	0.064	605	2581	75	
C2A□AH1□	0.0975	0.006	0.0965	0.005	95	431	37	
C2A□AHB□	0.152	0.060	0.151	0.059	192	895	53	
C2A□AHC□	0.202	0.110	0.200	0.108	528	2254	75	
C2A□AH7□	0.157	0.065	0.156	0.064	605	2581	75	
02A□AH1□	0.470	0.207	0.464	0.201	152	707	53	
02A□AHB□	0.456	0.193	0.455	0.192	192	895	53	
02A□AHC□	0.753	0.490	0.751	0.488	528	2254	75	
02A□AH7□	0.713	0.450	0.712	0.449	605	2581	75	
04A□AH1□	0.693	0.207	0.687	0.201	152	707	53	
04A□AHB□	1.06	0.570	1.05	0.560	435	1856	75	
04A□AHC□	0.976	0.490	0.974	0.488	528	2254	75	
04A□AH7□	1.11	0.620	1.10	0.610	951	4992	128	
06A□AH1□	1.50	0.700	1.46	0.660	343	1465	75	
06A□AHB□	1.37	0.570	1.36	0.560	435	1856	75	
06A□AHC□	1.64	0.840	1.62	0.820	830	4359	128	
06A□AH7□	1.42	0.620	1.41	0.610	951	4992	128	
08A□AH1□	2.29	0.700	2.25	0.660	343	1465	75	
08A□AHB□	2.19	0.600	2.18	0.590	435	1856	75	
08A□AHC□	4.59	3.00	4.57	2.98	830	4359	128	
08A□AH7□	4.39	2.80	4.37	2.78	951	4992	128	



\* The moment of inertia for the Servomotor and gear is the value without a holding brake. You can calculate the moment of inertia for a Servomotor with a Gear and Holding Brake with the following formula.  
 Motor moment of inertia for a Servomotor with a Holding Brake from 4.2.2 Ratings of Servomotors without Gears on page 4-4 + Moment of inertia for the gear from the above table.

## 4.2 Specifications and Ratings

### 4.2.4 Ratings of Servomotors with Gears



Important

During operation, the gear generates the loss at the gear mechanism and oil seal. The loss depends on the torque and motor speed conditions. The temperature rise depends on the loss and heat dissipation conditions. For the heat dissipation conditions, always refer to the following table and check the gear and motor temperatures with the actual equipment. If the temperature is too high, implement the following measures.

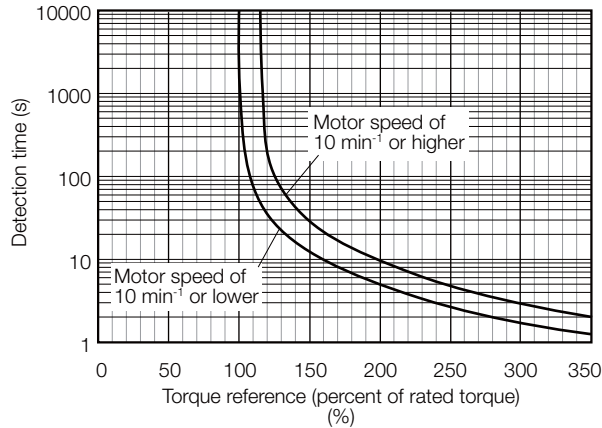
- Decrease the load ratio.
- Change the heat dissipation conditions.
- Use forced-air cooling for the motor with a cooling fan or other means.

Model	Heat Sink Size			
	1/5	1/9 or 1/11	1/21	1/33
SGM7J-A5	A			
SGM7J-01	B			C
SGM7J-C2				
SGM7J-02	C			
SGM7J-04				
SGM7J-06				
SGM7J-08				

- A: 250 mm × 250 mm × 6 mm, aluminum plate
- B: 300 mm × 300 mm × 12 mm, aluminum plate
- C: 350 mm × 350 mm × 12 mm, aluminum plate

## 4.2.5 Servomotor Overload Protection Characteristics

The overload detection level is set for hot start conditions with a Servomotor ambient temperature of 40°C.



Note: The above overload protection characteristics do not mean that you can perform continuous duty operation with an output of 100% or higher.

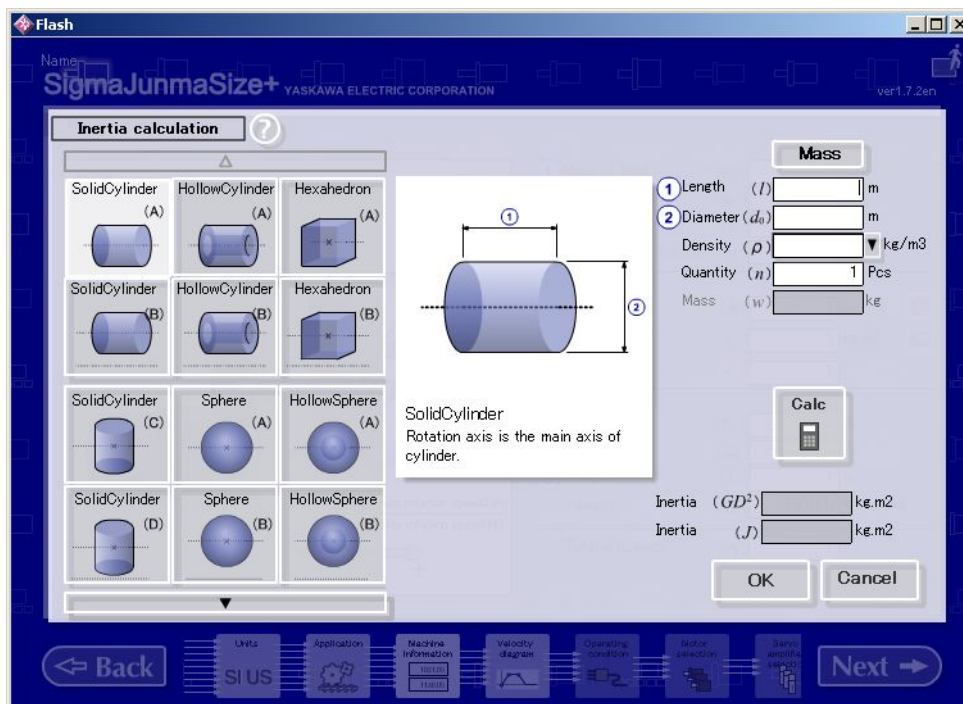
Use the Servomotor so that the effective torque remains within the continuous duty zone given in 4.2.3 *Torque-Motor Speed Characteristics* on page 4-5.

## 4.2.6 Load Moment of Inertia

The load moment of inertia indicates the inertia of the load. The larger the load moment of inertia, the worse the response. If the moment of inertia is too large, operation will become unstable.

The allowable size of the load moment of inertia ( $J_L$ ) for the Servomotor is restricted. Refer to 4.2.2 *Ratings of Servomotors without Gears* on page 4-4. This value is provided strictly as a guideline and results depend on Servomotor driving conditions.

Use the SigmaJunmaSize+ AC Servo Drive Capacity Selection Program to check the driving conditions. Contact your Yaskawa representative for information on the SigmaJunmaSize+.





### 4.2.6 Load Moment of Inertia

An Overvoltage Alarm (A.400) is likely to occur during deceleration if the load moment of inertia exceeds the allowable load moment of inertia. SERVOPACKs with a built-in regenerative resistor may generate a Regenerative Overload Alarm (A.320). Perform one of the following steps if this occurs.

- Reduce the torque limit.
- Reduce the deceleration rate.
- Reduce the maximum motor speed.
- Install an external regenerative resistor if the alarm cannot be cleared using the above steps.

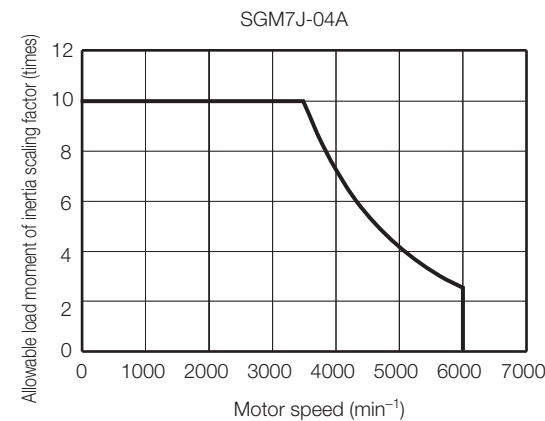
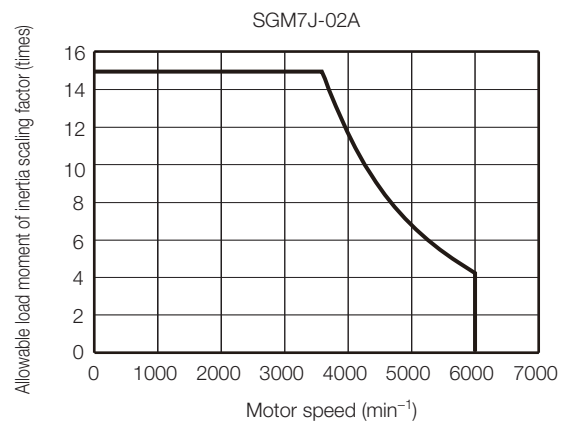
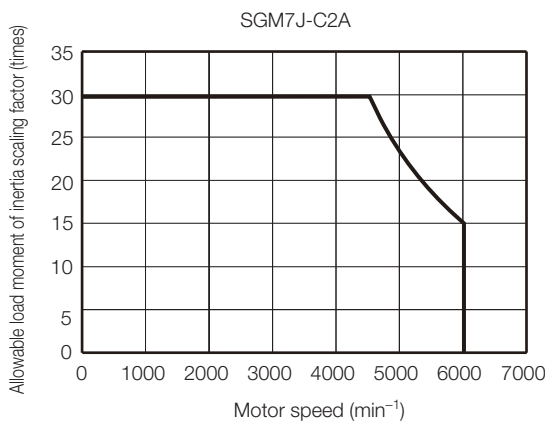
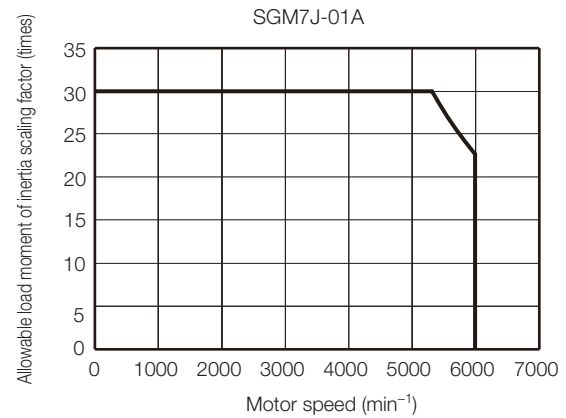
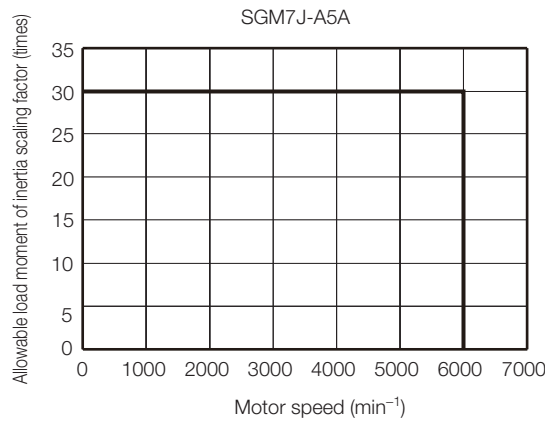
Regenerative resistors are not built into SERVOPACKs for 400-W Servomotors or smaller Servomotors. Even for SERVOPACKs with built-in regenerative resistors, an external regenerative resistor is required if the energy that results from the regenerative driving conditions exceeds the allowable loss capacity (W) of the built-in regenerative resistor.

## 4.2.7 Allowable Load Moment of Inertia Scaling Factor for SERVOPACKs without Built-in Regenerative Resistors

The following graphs show the allowable load moment of inertia scaling factor of the motor speed for SERVOPACKs\* without built-in regenerative resistors when an External Regenerative Resistor is not connected.

If the Servomotor exceeds the allowable load moment of inertia, an overvoltage alarm may occur in the SERVOPACK.

These graphs provide reference data for deceleration at the rated torque or higher with a 200-VAC power supply input.




\* Applicable SERVOPACK models: SGD7S-R70A, -R90A, -1R6A, or -2R8A

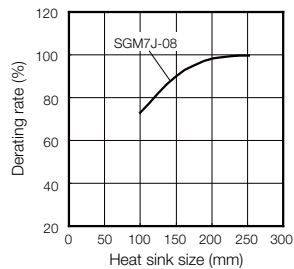
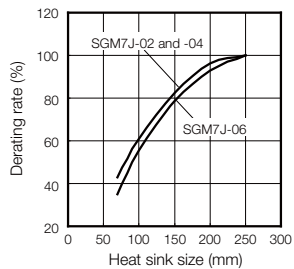
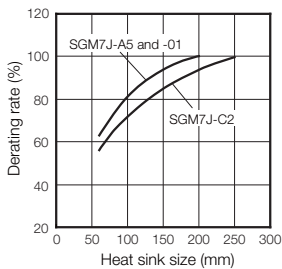
## 4.2.8 Servomotor Heat Dissipation Conditions

The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C when a heat sink is installed on the Servomotor. If the Servomotor is mounted on a small device component, the Servomotor temperature may rise considerably because the surface for heat dissipation becomes smaller. Refer to the following graphs for the relation between the heat sink size and derating rate.

Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



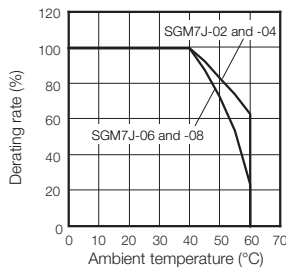
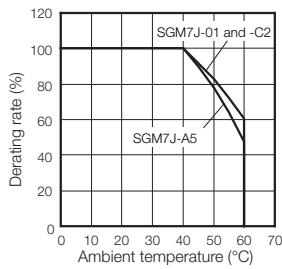
The actual temperature rise depends on how the heat sink (i.e., the Servomotor mounting section) is attached to the installation surface, what material is used for the Servomotor mounting section, and the motor speed. Always check the Servomotor temperature with the actual equipment.



## 4.2.9 Applications Where the Ambient Temperature of the Servomotor Exceeds 40°C

The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C. If you use a Servomotor at an ambient temperature that exceeds 40°C (60°C max.), apply a suitable derating rate from the following graphs.

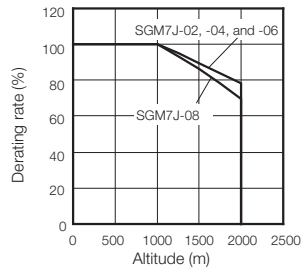
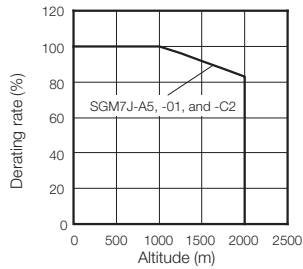
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



## 4.2.10 Applications Where the Altitude of the Servomotor Exceeds 1,000 m

The Servomotor ratings are the continuous allowable values at an altitude of 1,000 m or less. If you use a Servomotor at an altitude that exceeds 1,000 m (2,000 m max.), the heat dissipation effect of the air is reduced. Apply the appropriate derating rate from the following graphs.

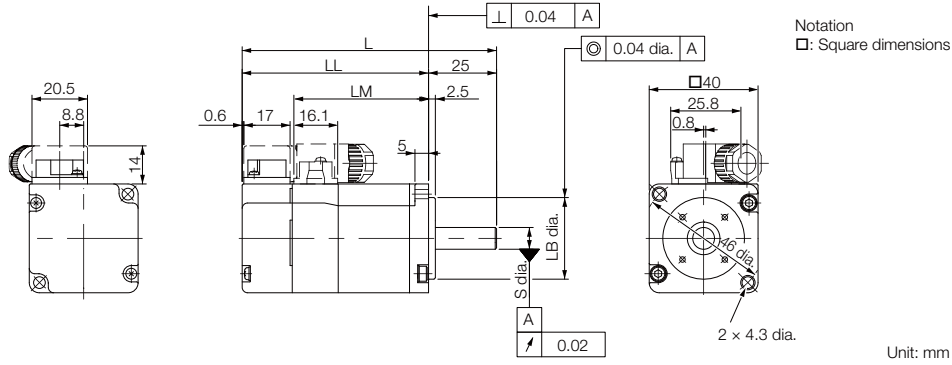
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



# 4.3 External Dimensions

## 4.3.1 Servomotors without Gears

### SGM7J-A5, -01, and -C2

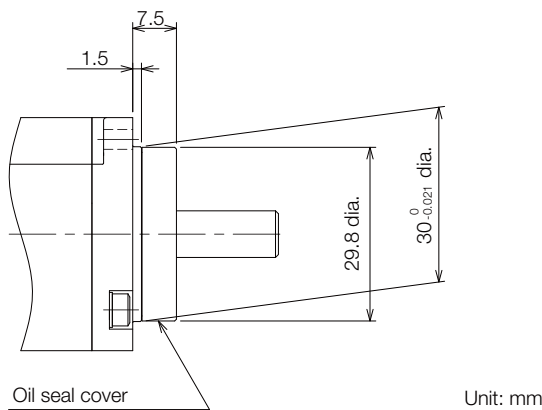


Model SGM7J-	L	LL	LM	LB	S	Approx. Mass [kg]
A5A□A2□	81.5 (122)	56.5 (97)	37.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.3 (0.6)
01A□A2□	93.5 (134)	68.5 (109)	49.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.4 (0.7)
C2A□A2□	105.5 (153.5)	80.5 (128.5)	61.9	30 <sup>0</sup> <sub>-0.021</sub>	8 <sup>0</sup> <sub>-0.009</sub>	0.5 (0.8)

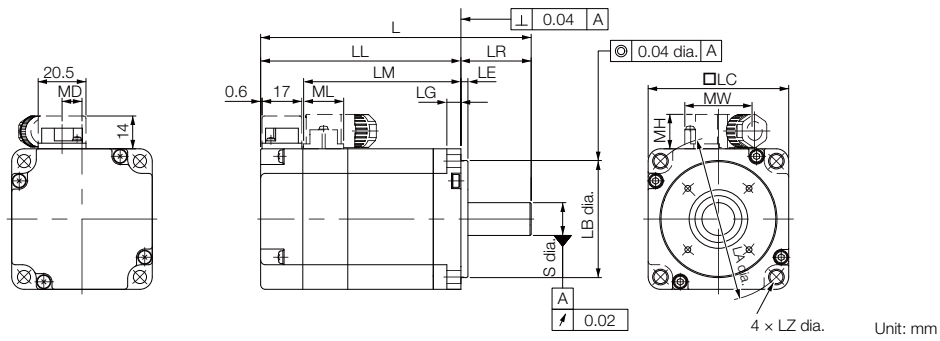
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.  
 2. Refer to the following section for detailed shaft end specifications.  
 ■ 4.3.2 Shaft End Specifications on page 4-16

### ◆ Specifications of Options

- Oil Seal



## SGM7J-02, -04, -06, and -08



Model SGM7J-	L	LL	LM	Flange Dimensions							S
				LR	LE	LG	LC	LA	LB	LZ	
02A□A2□	99.5 (140)	69.5 (110)	51.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
04A□A2□	115.5 (156)	85.5 (126)	67.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
06A□A2□	137.5 (191.5)	107.5 (161.5)	89.2	30	3	6	60	70	50 <sup>0</sup> <sub>-0.025</sub>	5.5	14 <sup>0</sup> <sub>-0.011</sub>
08A□A2□	137 (184)	97 (144)	78.5	40	3	8	80	90	70 <sup>0</sup> <sub>-0.030</sub>	7	19 <sup>0</sup> <sub>-0.013</sub>

Model SGM7J-	MD	MW	MH	ML	Approx. Mass [kg]
02A□A2□	8.5	28.7	14.7	17.1	0.8 (1.4)
04A□A2□	8.5	28.7	14.7	17.1	1.1 (1.7)
06A□A2□	8.5	28.7	14.7	17.1	1.6 (2.2)
08A□A2□	13.6	38	14.7	19.3	2.2 (2.8)

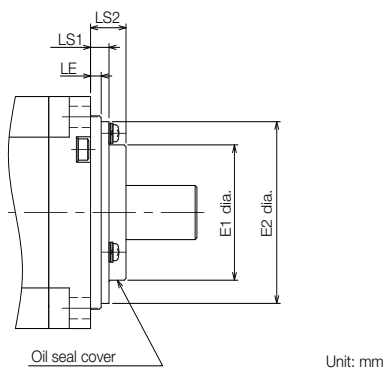
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Refer to the following section for detailed shaft end specifications.

☞ 4.3.2 Shaft End Specifications on page 4-16

### ◆ Specifications of Options

- Oil Seal



Model SGM7J-	Dimensions with Oil Seal			
	E1	E2	LS1	LS2
02A, 04A, 06A	35	47	5.2	10
08A	47	61	5.5	11

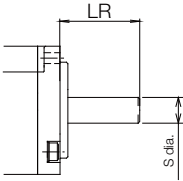
## 4.3.2 Shaft End Specifications

### SGM7J-□□□□□□□□

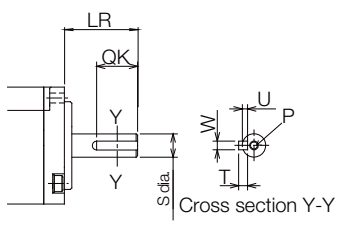
Code	Specification
2	Straight without key
6	Straight with key and tap for one location (Key slot is JIS B1301-1996 fastening type.)
B	With two flat seats

Shaft End Details	Servomotor Model SGM7J-						
	A5	01	C2	02	04	06	08

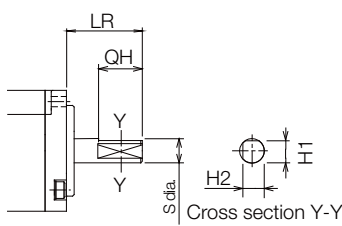
Code: 2 (Straight without Key)

	LR	25	30	40
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$

Code: 6 (Straight with Key and Tap)

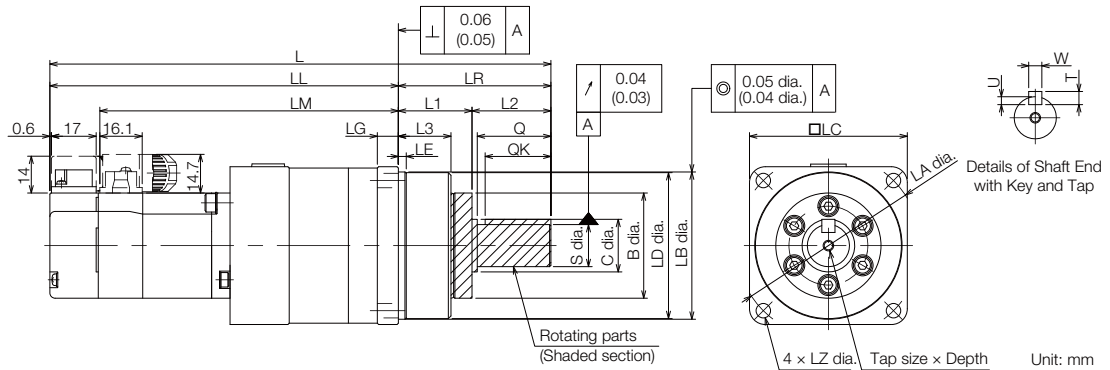
	LR	25	30	40
	QK	14	14	22
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$
	W	3	5	6
	T	3	5	6
	U	1.8	3	3.5
	P	M3 × 6L	M5 × 8L	M6 × 10L

Code: B (with Two Flat Seats)

	LR	25	30	40
	QH	15	15	22
	S	$8^{0}_{-0.009}$	$14^{0}_{-0.011}$	$19^{0}_{-0.013}$
	H1	7.5	13	18
	H2	7.5	13	18

## 4.3.3 Servomotors with Gears

### SGM7J-A5, -01, and -C2



Model SGM7J-	Gear Ratio	L	LL	LM	Flange Surface Dimensions								
					LR	LE	LG	B	LD	LB	LC	LA	LZ
A5A□AH1	1/5	138	96	77.4	42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4
A5A□AH2	1/9	(178.5)	(136.5)										
A5A□AHC	1/21	147	105										
A5A□AH7	1/33	178.5	120.5	101.9	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5
01A□AH1	1/5	150	108	89.4	42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4
01A□AHB	1/11	190.5	132.5										
01A□AHC	1/21	(231)	(173)										
01A□AH7	1/33	215	135	116.4	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
C2A□AH1	1/5	162	120	101.4	42	2.2	5	29	39.5	40 <sup>0</sup> <sub>-0.025</sub>	40	46	3.4
C2A□AHB	1/11	202.5	144.5										
C2A□AHC	1/21	(250.5)	(192.5)										
C2A□AH7	1/33	227	147	128.4	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9

Model SGM7J-	Flange Surface Dimensions			Q	C	S	Tap Size × Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
A5A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.6
A5A□AH2												(0.9)
A5A□AHC												0.7
A5A□AH7	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.3
01A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.7
01A□AHB	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.4
01A□AHC												(1.7)
01A□AH7	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	2.8
C2A□AH1	22	20	14.6	-	-	10 <sup>0</sup> <sub>-0.015</sub>	M3 × 6L	15	2.5	4	4	0.8
C2A□AHB	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.5
C2A□AHC	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	2.9
C2A□AH7												(3.2)

\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation. If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

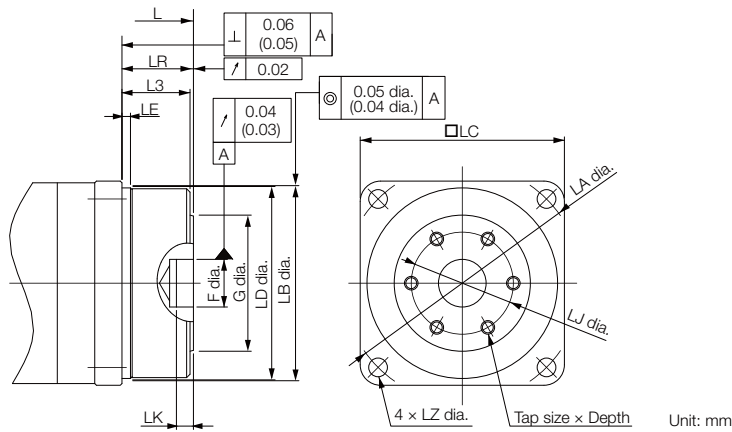
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.  
2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.



4.3 External Dimensions

4.3.3 Servomotors with Gears

◆ Flange Output Face




Note: The geometric tolerance in parentheses is the value for LC = 40.

Model SGM7J-	Gear Ratio	L	LR	LJ	F	G	LK	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
A5A□AH10□	1/5	111	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	3	3 × M4 × 6L	0.6 (0.9)
A5A□AH20□	1/9	(151.5)							
A5A□AHC0□	1/21	120 (160.5)							
A5A□AH70□	1/33	141.5 (182)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	5	6 × M4 × 7L	1.2 (1.5)
01A□AH10□	1/5	123 (163.5)	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	5	3 × M4 × 6L	0.7 (1.0)
01A□AHB0□	1/11	153.5 (194)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40		3 × M4 × 7L	1.3 (1.6)
01A□AHC0□	1/21								
01A□AH70□	1/33	162 (202.5)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59		6 × M6 × 10L	2.4 (2.7)
C2A□AH10□	1/5	135 (183)	15	18	5 <sup>+0.012</sup> <sub>0</sub>	24	3	3 × M4 × 6L	0.8 (1.1)
C2A□AHB0□	1/11	165.5 (213.5)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	5	6 × M4 × 7L	1.4 (1.7)
C2A□AHC0□	1/21	174	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	5	6 × M6 × 10L	2.5 (2.8)
C2A□AH70□	1/33	(222)							

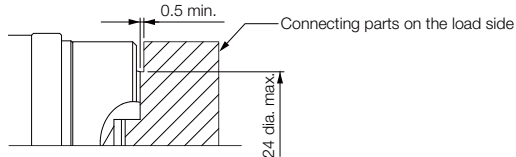
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

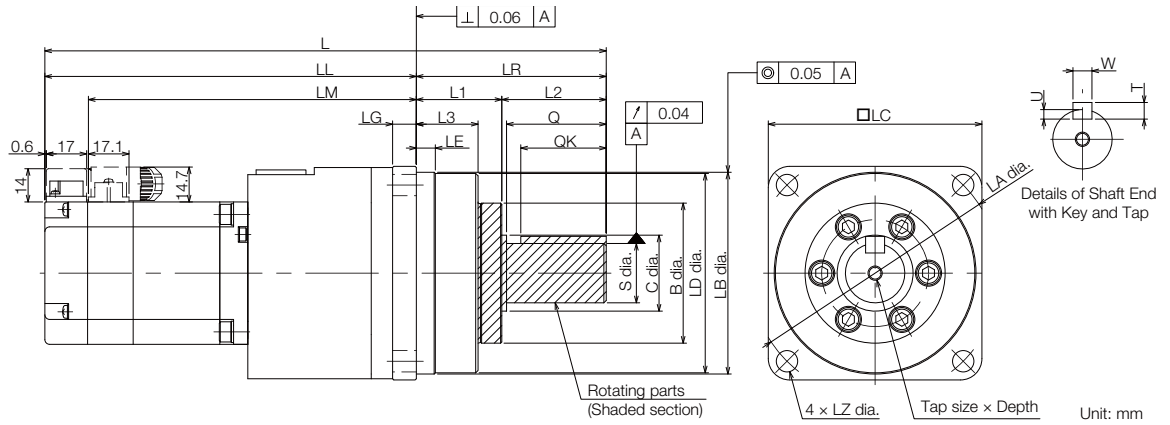


Important

For a Servomotor with a flange output that has square gear flange dimensions (□LC) of 40 mm, we recommend that you design the Servomotor with the dimensions shown in the following figure in order to secure a gap between the gear oil seal and the connecting parts on the load side.



## SGM7J-02, -04, and -06



Model SGM7J-	Gear Ratio	L	LL	LM	Flange Surface Dimensions								
					LR	LE	LG	B	LD	LB	LC	LA	LZ
02A□AH1	1/5	191.5	133.5	115.2	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5
02A□AH2	1/11	(232)	(174)										
02A□AHC	1/21	220.5	140.5	122.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
02A□AH7	1/33	(261)	(181)										
04A□AH1	1/5	207.5	149.5	131.2	58	2.5	8	40	55.5	56 <sup>0</sup> <sub>-0.030</sub>	60	70	5.5
04A□AHB	1/11	236.5	156.5	138.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
04A□AHC	1/21	(277)	(197)										
04A□AH7	1/33	322.5	189.5	171.2	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
06A□AH1	1/5	258.5	178.5	160.2	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
06A□AHB	1/11	(312.5)	(232.5)										
06A□AHC	1/21	344.5	211.5	193.2	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
06A□AH7	1/33	(398.5)	(265.5)										

Model SGM7J-	Flange Surface Dimensions			Q	C	S	Tap Size × Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
02A□AH1	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	1.8
02A□AH2												1.9
02A□AHC	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	3.7
02A□AH7												4.3
04A□AH1	28	30	20	28	20	16 <sup>0</sup> <sub>-0.018</sub>	M4 × 8L	25	3	5	5	2.1
04A□AHB												2.7
04A□AHC	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	4.0
04A□AH7												4.6
06A□AH1	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 × 20L	70	5	12	8	8.6
06A□AHB												9.2
06A□AHC	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	4.3
06A□AH7												4.5
06A□AHC	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 × 20L	70	5	12	8	9.1
06A□AH7												9.7

\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation.  
If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

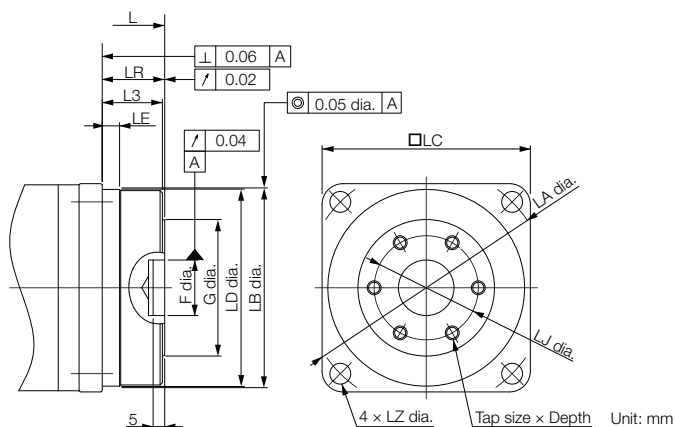
Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.

### 4.3 External Dimensions

#### 4.3.3 Servomotors with Gears

#### ◆ Flange Output Face

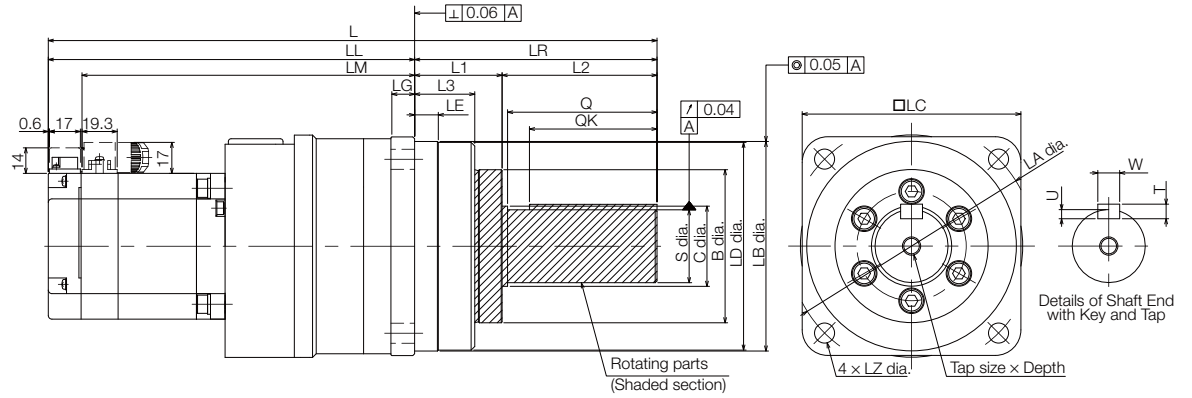


Model SGM7J-	Gear Ratio	L	LR	LJ	F	G	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
02A□AH10□	1/5	154.5 (195)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	6 × M4 × 7L	1.7 (2.3)
02A□AH20□	1/11							1.8 (2.4)
02A□AHC0□	1/21	167.5 (208)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.3 (3.9)
02A□AH70□	1/33							
04A□AH10□	1/5	170.5 (211)	21	30	14 <sup>+0.018</sup> <sub>0</sub>	40	6 × M4 × 7L	2.0 (2.6)
04A□AHB0□	1/11	183.5 (224)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.6 (4.2)
04A□AHC0□	1/21							
04A□AH70□	1/33	224.5 (265)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	7.2 (7.8)
06A□AH10□	1/5	205.5 (259.5)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	3.9 (4.5)
06A□AHB0□	1/11							4.1 (4.7)
06A□AHC0□	1/21	246.5 (300.5)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	7.7 (8.3)
06A□AH70□	1/33							

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

## SGM7J-08



Unit: mm

Model SGM7J-	Gear Ratio	L	LL	LM	Flange Surface Dimensions								
					LR	LE	LG	B	LD	LB	LC	LA	LZ
08A□AH1	1/5	255	175	156.5	80	7.5	10	59	84	85 <sup>0</sup> <sub>-0.035</sub>	90	105	9
08A□AHB	1/11	(302)	(222)										
08A□AHC	1/21	334	201	182.5	133	12.5	13	84	114	115 <sup>0</sup> <sub>-0.035</sub>	120	135	11
08A□AH7	1/33	(381)	(248)										

Model SGM7J-	Flange Surface Dimensions			Q	C	S	Tap Size × Depth	Key Dimensions				Approx. Mass [kg]
	L1	L2	L3					QK	U	W	T	
08A□AH1	36	44	26	42	32	25 <sup>0</sup> <sub>-0.021</sub>	M6 × 12L	36	4	8	7	5.1 (5.7)
08A□AHB												5.3 (5.9)
08A□AHC	48	85	33	82	44	40 <sup>0</sup> <sub>-0.025</sub>	M10 × 20L	70	5	12	8	10 (10.6)
08A□AH7												

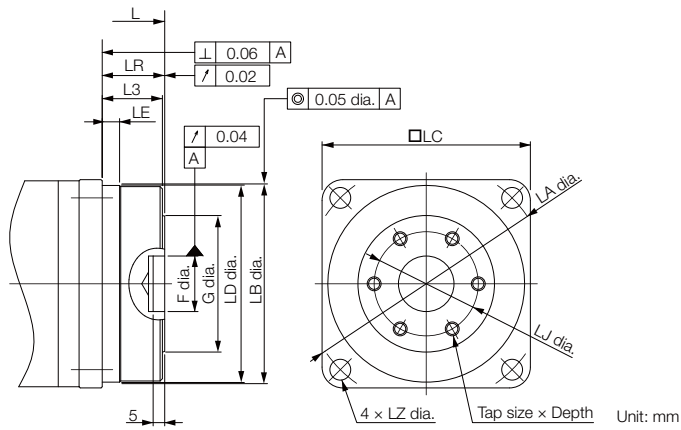
\* The asterisk (\*) is replaced by shaft end code 6 (straight with key and tap) for the 8th digit of the model designation.

If a key and tap are not necessary, specify shaft end code 2 (without key and tap).

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Gear dimensions are different from those of the Σ, Σ-II, and Σ-III Series.

◆ Flange Output Face



Model SGM7J-	Gear Ratio	L	LR	LJ	F	G	No. of Taps × Tap Size × Depth	Approx. Mass [kg]
08A□AH101	1/5	202 (249)	27	45	24 <sup>+0.021</sup> <sub>0</sub>	59	6 × M6 × 10L	4.7 (5.3)
08A□AHB01	1/11							4.9 (5.5)
08A□AHC01	1/21	236 (283)	35	60	32 <sup>+0.025</sup> <sub>0</sub>	84	6 × M8 × 12L	8.6 (9.2)
08A□AH701	1/33							

Note: 1. The values in parentheses are for Servomotors with Holding Brakes.

2. Dimensions not found in the above table are the same as those in the table on the previous page.

# Specifications, Ratings, and External Dimensions of SGM7G Servomotors

# 5

This chapter describes how to interpret the model numbers of SGM7G Servomotors and gives their specifications, ratings, and external dimensions.

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# 5.1 Model Designations

SGM7G - 03 A 7 A 2 1

1st+2nd digits
3rd digit
4th digit
5th digit
6th digit
7th digit

Σ-7 Series  
Servomotors:  
SGM7G

**1st+2nd digits** Rated Output

Code	Specification
03	300 W
05	450 W
09	850 W
13	1.3 kW
20	1.8 kW

**3rd digit** Power Supply Voltage

Code	Specification
A	200 VAC

**4th digit** Serial Encoder

Code	Specification
7	24-bit absolute
F	24-bit incremental

**5th digit** Design Revision Order

A

**6th digit** Shaft End

Code	Specification
2	Straight without key
6	Straight with key and tap

**7th digit** Options

Code	Specification
1	Without options
C	With holding brake (24 VDC)
E	With oil seal and holding brake (24 VDC)
S	With oil seal

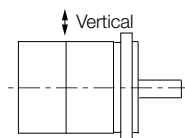
## 5.2 Specifications and Ratings

### 5.2.1 Specifications

Voltage		200 V				
Model SGM7G-		03A	05A	09A	13A	20A
Time Rating		Continuous				
Thermal Class		F				
Insulation Resistance		500 VDC, 10 M $\Omega$ min.				
Withstand Voltage		1,500 VAC for 1 minute				
Excitation		Permanent magnet				
Mounting		Flange-mounted				
Drive Method		Direct drive				
Rotation Direction		Counterclockwise (CCW) for forward reference when viewed from the load side				
Vibration Class* <sup>1</sup>		V15				
Environmental Conditions	Surrounding Air Temperature	0°C to 40°C (With derating, usage is possible between 40°C and 60°C.)* <sup>4</sup>				
	Surrounding Air Humidity	20% to 80% relative humidity (with no condensation)				
	Installation Site	<ul style="list-style-type: none"> <li>• Must be indoors and free of corrosive and explosive gases.</li> <li>• Must be well-ventilated and free of dust and moisture.</li> <li>• Must facilitate inspection and cleaning.</li> <li>• Must have an altitude of 1,000 m or less. (With derating, usage is possible between 1,000 m and 2,000 m.)*<sup>5</sup></li> <li>• Must be free of strong magnetic fields.</li> </ul>				
	Storage Environment	Store the Servomotor in the following environment if you store it with the power cable disconnected. Storage Temperature: -20°C to 60°C (with no freezing) Storage Humidity: 20% to 80% relative humidity (with no condensation)				
Shock Resistance* <sup>2</sup>	Impact Acceleration Rate at Flange	490 m/s <sup>2</sup>				
	Number of Impacts	2 times				
Vibration Resistance* <sup>3</sup>	Vibration Acceleration Rate at Flange	49 m/s <sup>2</sup> (24.5 m/s <sup>2</sup> front to back)				
Applicable SERVOPACKs		Refer to 1.4 <i>Combinations of Servomotors and SERVOPACKs</i> on page 1-5.				

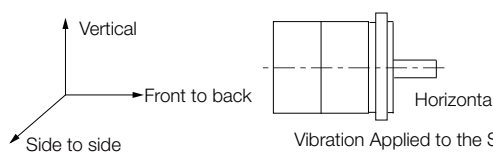
\*1. A vibration class of V15 indicates a vibration amplitude of 15  $\mu\text{m}$  maximum on the Servomotor without a load at the rated motor speed.

\*2. The shock resistance for shock in the vertical direction when the Servomotor is mounted with the shaft in a horizontal position is given in the above table.



Shock Applied to the Servomotor

\*3. The vertical, side-to-side, and front-to-back vibration resistance for vibration in three directions when the Servomotor is mounted with the shaft in a horizontal position is given in the above table. The strength of the vibration that the Servomotor can withstand depends on the application. Always check the vibration acceleration rate that is applied to the Servomotor with the actual equipment.



Vibration Applied to the  $\xi$

\*4. If the ambient temperature will exceed 40°C, refer to the following section.

☞ 5.2.7 *Applications Where the Ambient Temperature of the Servomotor Exceeds 40 °C* on page 5-7

\*5. If the altitude will exceed 1,000 m, refer to the following section.

☞ 5.2.8 *Applications Where the Altitude of the Servomotor Exceeds 1,000 m* on page 5-8



## 5.2.2 Servomotor Ratings

Voltage		200 V				
Model SGM7G-		03A	05A	09A	13A	20A
Rated Output* <sup>1</sup>	kW	0.3	0.45	0.85	1.3	1.8
Rated Torque* <sup>1, *2</sup>	N·m	1.96	2.86	5.39	8.34	11.5
Instantaneous Maximum Torque* <sup>1</sup>	N·m	5.88	8.92	14.2	23.3	28.7
Rated Current* <sup>1</sup>	Arms	2.8	3.8	6.9	10.7	16.7
Instantaneous Maximum Current* <sup>1</sup>	Arms	8.0	11	17	28	42
Rated Motor Speed* <sup>1</sup>	min <sup>-1</sup>	1500				
Maximum Motor Speed* <sup>1</sup>	min <sup>-1</sup>	3000				
Torque Constant	N·m/Arms	0.776	0.854	0.859	0.891	0.748
Motor Moment of Inertia	×10 <sup>-4</sup> kg·m <sup>2</sup>	2.48 (2.73)	3.33 (3.58)	13.9 (16.0)	19.9 (22.0)	26.0 (28.1)
Rated Power Rate* <sup>1</sup>	kW/s	15.5 (14.1)	24.6 (22.8)	20.9 (18.2)	35.0 (31.6)	50.9 (47.1)
Rated Angular Acceleration Rate* <sup>1</sup>	rad/s <sup>2</sup>	7900 (7180)	8590 (7990)	3880 (3370)	4190 (3790)	4420 (4090)
Heat Sink Size	mm	250 × 250 × 6 (aluminum)		400 × 400 × 20 (steel)		
Protective Structure* <sup>3</sup>		Totally enclosed, self-cooled, IP67				
Holding Brake Specifications* <sup>4</sup>	Rated Voltage	V	24 VDC <sup>+10%</sup> <sub>0</sub>			
	Capacity	W	10			
	Holding Torque	N·m	4.5	12.7	19.6	
	Coil Resistance	Ω (at 20°C)	56	59		
	Rated Current	A (at 20°C)	0.43	0.41		
	Time Required to Release Brake	ms	100			
	Time Required to Brake	ms	80			
Allowable Load Moment of Inertia (Motor Moment of Inertia Ratio)		15 times	15 times	5 times		
With External Regenerative Resistor and Dynamic Brake Resistor		10 times				
Allowable Shaft Loads* <sup>5</sup>	LF	mm	40		58	
	Allowable Radial Load	N	490		686	980
	Allowable Thrust Load	N	98		343	392

Note: The values in parentheses are for Servomotors with Holding Brakes.

\*1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 20°C. These are typical values.

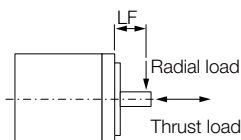
\*2. The rated torques are the continuous allowable torque values at 40°C with an aluminum or steel heat sink of the dimensions given in the table.

\*3. This does not apply to the shaft opening. Protective structure specifications apply only when the special cable is used.

\*4. Observe the following precautions if you use a Servomotor with a Holding Brake.

- The holding brake cannot be used to stop the Servomotor.
- The time required to release the brake and the time required to brake depend on which discharge circuit is used. Confirm that the operation delay time is appropriate for the actual equipment.
- The 24-VDC power supply is not provided by Yaskawa.

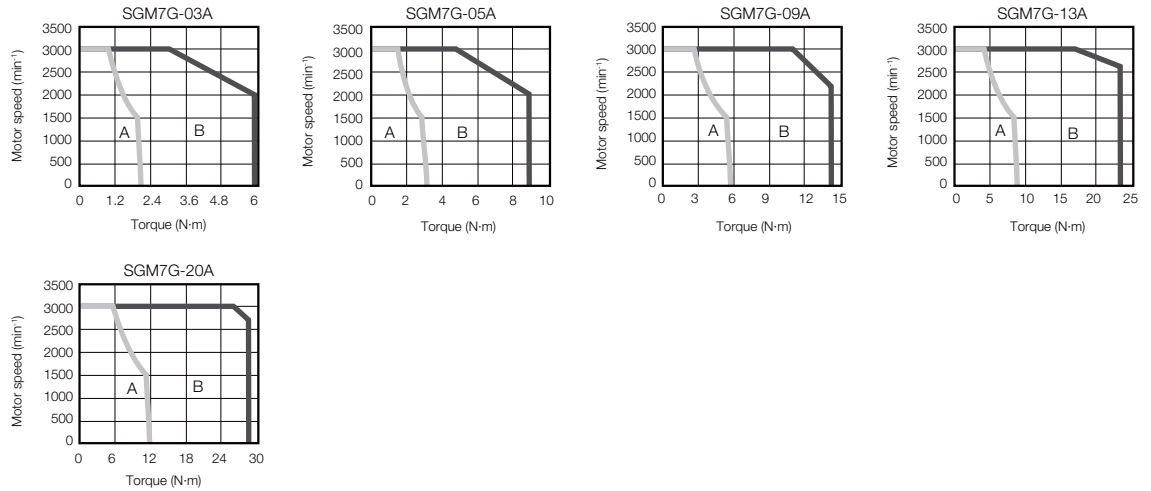
\*5. The allowable shaft loads are illustrated in the following figure. Design the mechanical system so that the thrust and radial loads applied to the Servomotor shaft end during operation do not exceed the values given in the table.



## 5.2.3 Torque-Motor Speed Characteristics for Three-phase, 200 V

**A** : Continuous duty zone

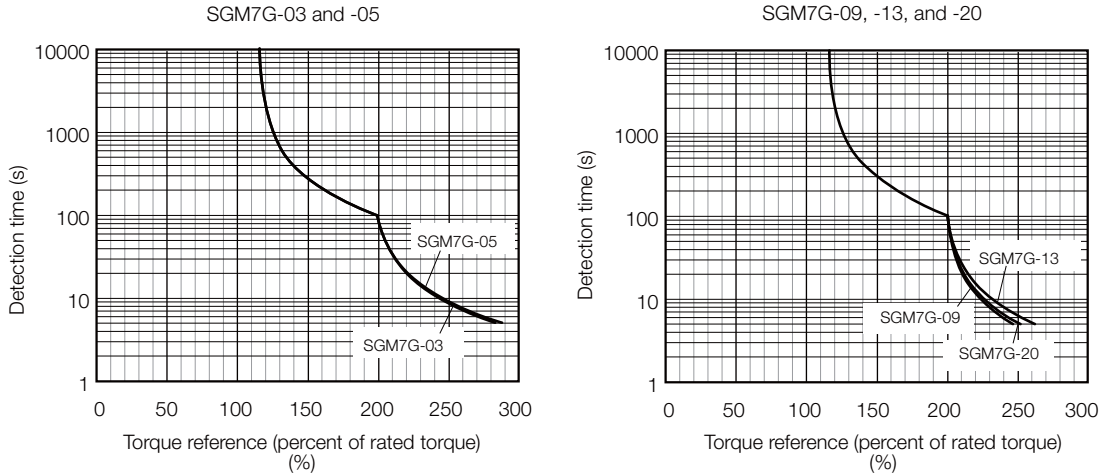
**B** : Intermittent duty zone



- Note: 1. These values are for operation in combination with a SERVOPACK when the temperature of the armature winding is 20°C. These are typical values.
2. The characteristics in the intermittent duty zone depend on the power supply voltage.
3. If the effective torque is within the allowable range for the rated torque, the Servomotor can be used within the intermittent duty zone.
4. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.

## 5.2.4 Servomotor Overload Protection Characteristics

The overload detection level is set for hot start conditions with a Servomotor ambient temperature of 40°C.



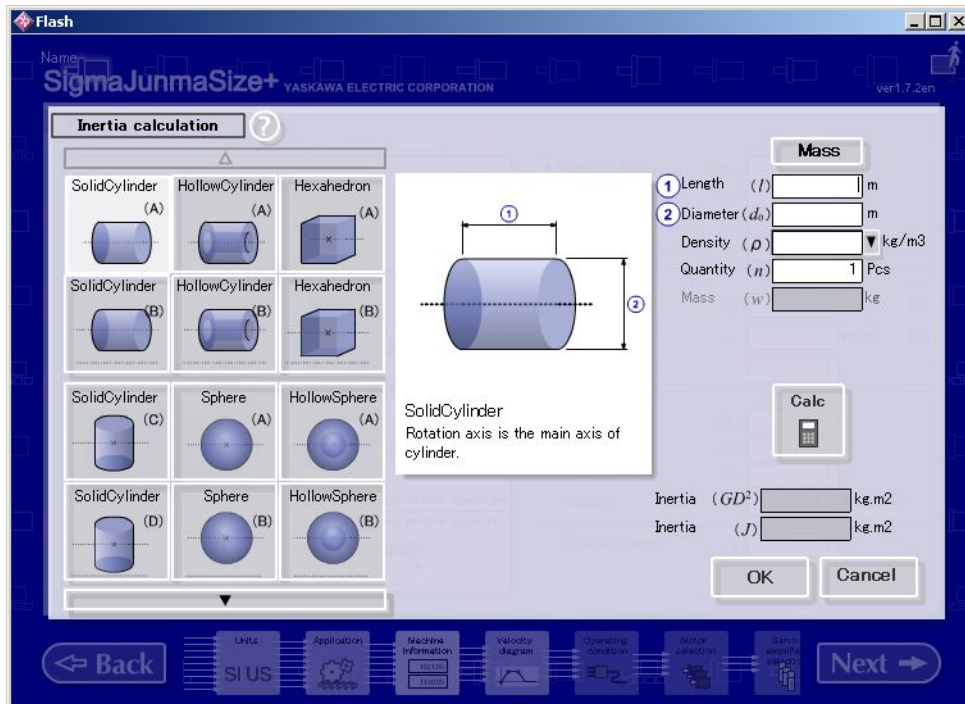
Note: The above overload protection characteristics do not mean that you can perform continuous duty operation with an output of 100% or higher. Use the Servomotor so that the effective torque remains within the continuous duty zone given in 5.2.3 *Torque-Motor Speed Characteristics for Three-phase, 200 V* on page 5-5.

## 5.2.5 Load Moment of Inertia

The load moment of inertia indicates the inertia of the load. The larger the load moment of inertia, the worse the response. If the moment of inertia is too large, operation will become unstable.

The allowable size of the load moment of inertia ( $J_L$ ) for the Servomotor is restricted. Refer to 5.2.2 *Servomotor Ratings* on page 5-4. This value is provided strictly as a guideline and results depend on Servomotor driving conditions.

Use the SigmaJunmaSize+ AC Servo Drive Capacity Selection Program to check the driving conditions. Contact your Yaskawa representative for information on the SigmaJunmaSize+.



An Overvoltage Alarm (A.400) is likely to occur during deceleration if the load moment of inertia exceeds the allowable load moment of inertia. SERVOPACKs with a built-in regenerative resistor may generate a Regenerative Overload Alarm (A.320). Perform one of the following steps if this occurs.

- Reduce the torque limit.
- Reduce the deceleration rate.
- Reduce the maximum motor speed.
- Install an external regenerative resistor if the alarm cannot be cleared using the above steps.

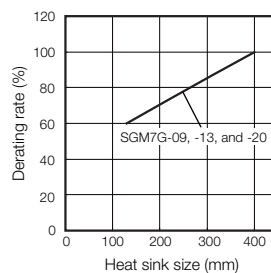
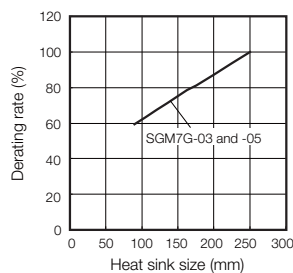
## 5.2.6 Servomotor Heat Dissipation Conditions

The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C when a heat sink is installed on the Servomotor. If the Servomotor is mounted on a small device component, the Servomotor temperature may rise considerably because the surface for heat dissipation becomes smaller. Refer to the following graphs for the relation between the heat sink size and derating rate.

Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



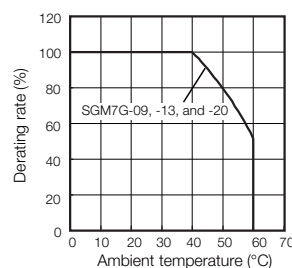
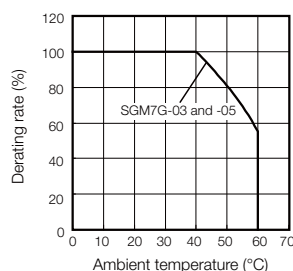
The actual temperature rise depends on how the heat sink (i.e., the Servomotor mounting section) is attached to the installation surface, what material is used for the Servomotor mounting section, and the motor speed. Always check the Servomotor temperature with the actual equipment.



## 5.2.7 Applications Where the Ambient Temperature of the Servomotor Exceeds 40°C

The Servomotor ratings are the continuous allowable values at an ambient temperature of 40°C. If you use a Servomotor at an ambient temperature that exceeds 40°C (60°C max.), apply a suitable derating rate from the following graphs.

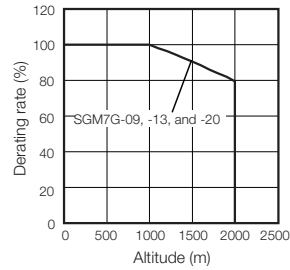
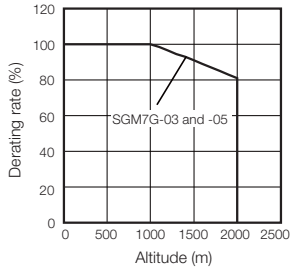
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



## 5.2.8 Applications Where the Altitude of the Servomotor Exceeds 1,000 m

The Servomotor ratings are the continuous allowable values at an altitude of 1,000 m or less. If you use a Servomotor at an altitude that exceeds 1,000 m (2,000 m max.), the heat dissipation effect of the air is reduced. Apply the appropriate derating rate from the following graphs.

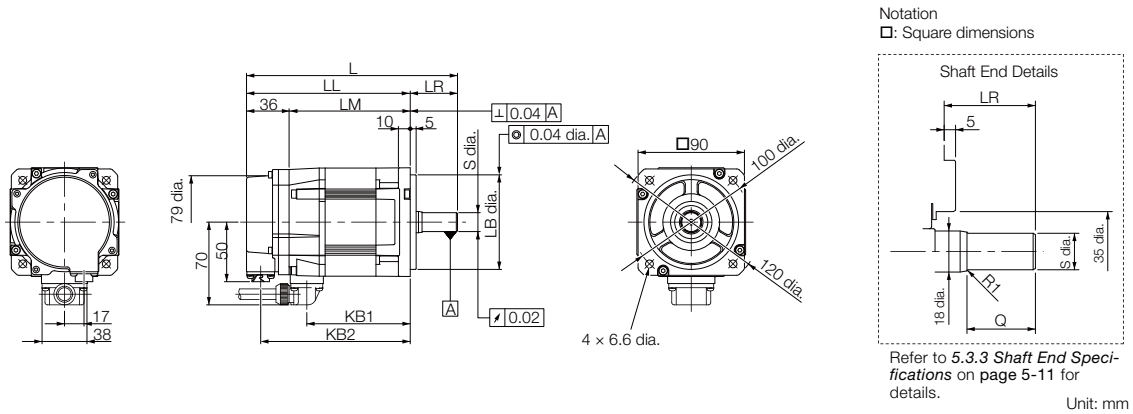
Note: The derating rates are applicable only when the average motor speed is less than or equal to the rated motor speed. If the average motor speed exceeds the rated motor speed, consult with your Yaskawa representative.



# 5.3 External Dimensions

## 5.3.1 Servomotors without Holding Brakes

### SGM7G-03 and -05



Model SGM7G-	L	LL	LM	LR	KB1	KB2	LB	Shaft End Dimensions		Approx. Mass [kg]
								S	Q	
03A□A21	166*	126	90	40*	75	114	80 <sup>0</sup> <sub>-0.030</sub>	16 <sup>0</sup> <sub>-0.011</sub> *	30*	2.6
05A□A21	179	139	103	40	88	127	80 <sup>0</sup> <sub>-0.030</sub>	16 <sup>0</sup> <sub>-0.011</sub>	30	3.2

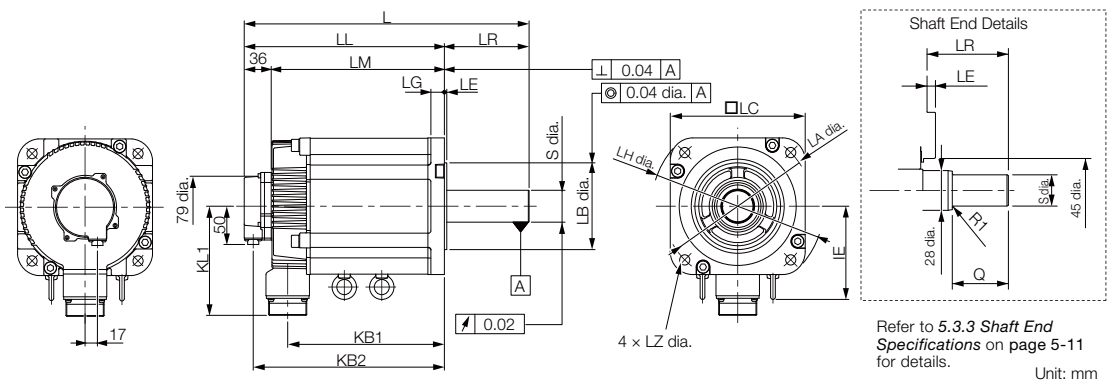
Note: Servomotors with Oil Seals have the same dimensions.

\* The L, LR, S, and Q dimensions of these Servomotors are different from those of the Σ-V-series SGMGV Servomotors. Models that have the same installation dimensions as the SGMGV Servomotors are also available. Contact your Yaskawa representative for details.

Refer to the following section for information on connectors.

☞ SGM7G-03 and -05 without Holding Brakes on page 5-12

### SGM7G-09, -13, and -20



Model SGM7G-	L	LL	LM	LR	KB1	KB2	IE	KL1	Flange Surface Dimensions						Shaft End Dimensions		Approx. Mass [kg]	
									LA	LB	LC	LE	LG	LH	LZ	S		Q
09A□A21	195	137	101	58	83	125	-	104	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub> *	40	5.5
13A□A21	211	153	117	58	99	141	-	104	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub> *	40	7.1
20A□A21	229	171	135	58	117	159	-	104	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub>	40	8.6

Note: Servomotors with Oil Seals have the same dimensions.

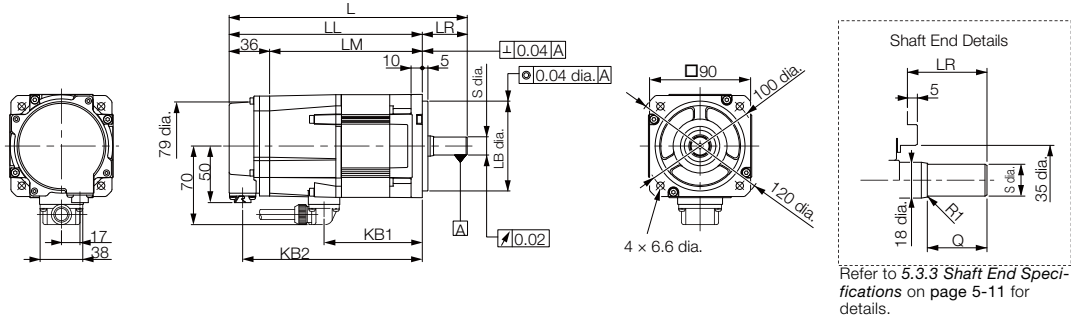
\* The S dimensions of these Servomotors are different from those of the Σ-V-series SGMGV Servomotors. Models that have the same installation dimensions as the SGMGV Servomotors are also available. Contact your Yaskawa representative for details.

Refer to the following section for information on connectors.

☞ SGM7G-09, -13, and -20 without Holding Brakes on page 5-12

## 5.3.2 Servomotors with Holding Brakes

### SGM7G-03 and -05



Unit: mm

Model SGM7G-	L	LL	LM	LR	KB1	KB2	LB	Shaft End Dimensions		Approx. Mass [kg]
								S	Q	
03A□A2C	199*	159	123	40*	75	147	80 <sup>0</sup> <sub>-0.030</sub>	16 <sup>0</sup> <sub>-0.011</sub> *	30*	3.6
05A□A2C	212	172	136	40	88	160	80 <sup>0</sup> <sub>-0.030</sub>	16 <sup>0</sup> <sub>-0.011</sub>	30	4.2

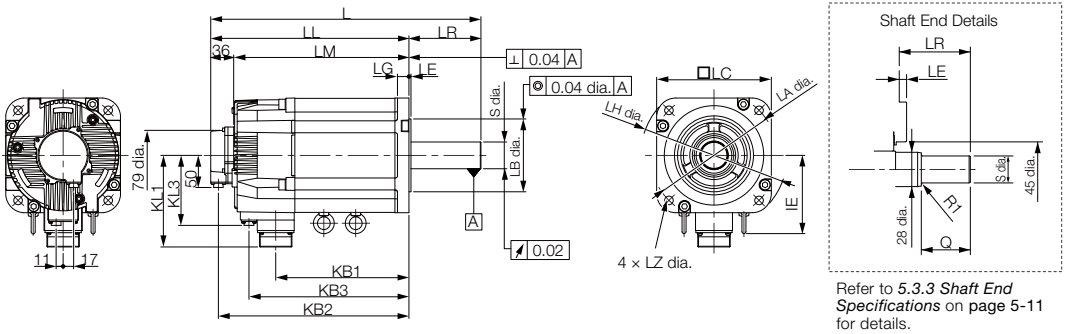
Note: Servomotors with Oil Seals have the same dimensions.

\* The L, LR, S, and Q dimensions of these Servomotors are different from those of the Σ-V-series SGMGV Servomotors. Models that have the same installation dimensions as the SGMGV Servomotors are also available. Contact your Yaskawa representative for details.

Refer to the following section for information on connectors.

☞ SGM7G-03 and -05 with Holding Brakes on page 5-13

### SGM7G-09, -13, and -20



Unit: mm

Model SGM7G-	L	LL	LM	LR	KB1	KB2	KB3	IE	KL1	KL3	Flange Surface Dimensions						Shaft End Dimensions		Approx. Mass [kg]	
											LA	LB	LC	LE	LG	LH	LZ	S		Q
09A□A2C	231	173	137	58	83	161	115	-	104	80	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub> *	40	7.5
13A□A2C	247	189	153	58	99	177	131	-	104	80	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub> *	40	9.0
20A□A2C	265	207	171	58	117	195	149	-	104	80	145	110 <sup>0</sup> <sub>-0.035</sub>	130	6	12	165	9	24 <sup>0</sup> <sub>-0.013</sub>	40	11.0

Note: Servomotors with Oil Seals have the same dimensions.

\* The S dimensions of these Servomotors are different from those of the Σ-V-series SGMGV Servomotors. Models that have the same installation dimensions as the SGMGV Servomotors are also available. Contact your Yaskawa representative for details.

Refer to the following section for information on connectors.

☞ SGM7G-09, -13, and -20 with Holding Brakes on page 5-13

## 5.3.3 Shaft End Specifications

### SGM7G-□□□□□□□□

Code	Specification
2	Straight without key
6	Straight with key and tap for one location (Key slot is JIS B1301-1996 fastening type.)

Shaft End Details	Servomotor Model SGM7G-					
	03	05	09	13	20	
Code: 2 (Straight without Key)						
	LR	40*	40	58	58	58
	Q	30*	30	40	40	40
	S	$16^{0}_{-0.011}$ *	$16^{0}_{-0.011}$	$24^{0}_{-0.013}$ *	$24^{0}_{-0.013}$ *	$24^{0}_{-0.013}$
Code: 2 (Straight without Key)						
	LR	40*	40	58	58	58
	Q	30*	30	40	40	40
	QK	20*	20	25	25	25
	S	$16^{0}_{-0.011}$ *	$16^{0}_{-0.011}$	$24^{0}_{-0.013}$ *	$24^{0}_{-0.013}$ *	$24^{0}_{-0.013}$
	W	5	5	8*	8*	8
	T	5	5	7*	7*	7
	U	3	3	4*	4*	4
	P	M5 screw, Depth: 12				

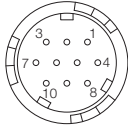
\* The shaft end dimensions of these Servomotors are different from those of the  $\Sigma$ -V-series SGMGV Servomotors. Models that have the same installation dimensions as the SGMGV Servomotors are also available. Contact your Yaskawa representative for details.



## 5.3.4 Connector Specifications

### SGM7G-03 and -05 without Holding Brakes

- Encoder Connector Specifications (24-bit Encoder)



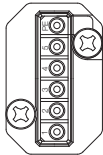
Receptacle: CM10-R10P-D  
 Applicable plug: Not provided by Yaskawa.  
 Plug: CM10-AP10S-□-D for Right-angle Plug  
 CM10-SP10S-□-D for Straight Plug  
 (□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT(+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT(-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

- Servomotor Connector Specifications

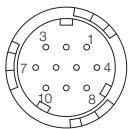


Manufacturer: Japan Aviation Electronics Industry, Ltd.

PE	FG (frame ground)
5	-
4	-
3	Phase U
2	Phase V
1	Phase W

### SGM7G-09, -13, and -20 without Holding Brakes

- Encoder Connector Specifications (24-bit Encoder)



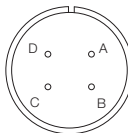
Receptacle: CM10-R10P-D  
 Applicable plug: Not provided by Yaskawa.  
 Plug: CM10-AP10S-□-D for Right-angle Plug  
 CM10-SP10S-□-D for Straight Plug  
 (□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT(+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT(-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

- Servomotor Connector Specifications

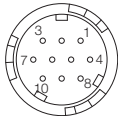


Manufacturer: DDK Ltd.

A	Phase U
B	Phase V
C	Phase W
D	FG (frame ground)

## SGM7G-03 and -05 with Holding Brakes

### • Encoder Connector Specifications (24-bit Encoder)



Receptacle: CM10-R10P-D

Applicable plug: Not provided by Yaskawa.

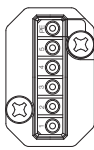
Plug: CM10-AP10S-□-D for Right-angle Plug  
CM10-SP10S-□-D for Straight Plug  
(□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT(+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT(-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

### • Servomotor Connector Specifications

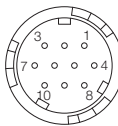


Manufacturer: Japan Aviation Electronics Industry, Ltd.

PE	FG (frame ground)
5	Brake terminal
4	Brake terminal
3	Phase U
2	Phase V
1	Phase W

## SGM7G-09, -13, and -20 with Holding Brakes

### • Encoder Connector Specifications (24-bit Encoder)



Receptacle: CM10-R10P-D

Applicable plug: Not provided by Yaskawa.

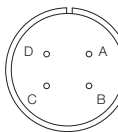
Plug: CM10-AP10S-□-D for Right-angle Plug  
CM10-SP10S-□-D for Straight Plug  
(□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	PS	6*	BAT(+)
2	/PS	7	-
3	-	8	-
4	PG5V	9	PG0V
5*	BAT(-)	10	FG (frame ground)

\* A battery is required only for an absolute encoder.

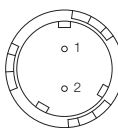
### • Servomotor Connector Specifications



Manufacturer: DDK Ltd.

A	Phase U
B	Phase V
C	Phase W
D	FG (frame ground)

### • Brake Connector Specifications



Receptacle: CM10-R2P-D

Applicable plug: Not provided by Yaskawa.

Plug: CM10-AP2S-□-D for Right-angle Plug  
CM10-SP2S-□-D for Straight Plug  
(□ depends on the applicable cable size.)

Manufacturer: DDK Ltd.

1	Brake terminal
2	Brake terminal

Note: There is no voltage polarity for the brake terminals.

# Servomotor Installation

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# 6

This chapter describes the installation conditions, procedures, and precautions for Servomotors.

<b>6.1</b>	<b>Installation Conditions</b>	<b>6-2</b>
6.1.1	Installation Precautions	6-2
6.1.2	Installation Environment	6-3
6.1.3	Installation Orientation	6-3
6.1.4	Using Servomotors with Oil Seals	6-3
6.1.5	Using Servomotors with Holding Brakes	6-4
<b>6.2</b>	<b>Coupling to the Machine</b>	<b>6-5</b>
6.2.1	Using a Coupling	6-5
6.2.2	Using a Belt	6-6
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<b>6.4</b>	<b>Servomotor Temperature Increase</b>	<b>6-9</b>

## 6.1 Installation Conditions

The service life of a Servomotor will be shortened or unexpected problems will occur if the Servomotor is installed incorrectly or in an inappropriate environment or location. Always observe the following installation instructions.

### 6.1.1 Installation Precautions

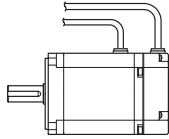
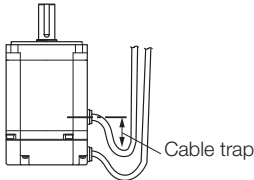
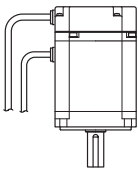
- Use the lifting bolts on the Servomotor to move only the Servomotor. Never use the lifting bolts on the Servomotor to move the Servomotor while it is installed on the machine. There is a risk of damage to the Servomotor or injury.
- Do not over-tighten the lifting bolts. If you use a tool to over-tighten the lifting bolts, the tapped holes may be damaged.
- Do not hold onto the cables or motor shaft when you move the Servomotor. Doing so may result in injury or damage.
- Do not install the Servomotor in the following locations. Doing so may result in fire, electric shock, or damage.
  - Outdoors or in locations subject to direct sunlight
  - Locations subject to condensation as the result of extreme changes in temperature
  - Locations subject to corrosive or flammable gases or near flammable objects
  - Locations subject to dust, salts, or iron dust
  - Locations subject to oil drops or chemicals
  - Locations subject to shock or vibration
  - Locations that would make it difficult to inspect or clean the Servomotor
- Mount the Servomotor to the machine so that the cables and connectors are not subjected to stress.
- Implement suitable countermeasures, such as attaching a cover, if the Servomotor is used in an application where it is subject to excessive water or oil drops. We recommend that you keep the connectors facing downward.
- Do not connect a Servomotor with an Absolute Encoder in a location where there is a magnetic field with a magnetic flux density of 0.01 tesla (100 gauss) or higher.
- Mount the Servomotor securely to the machine. If the Servomotor is not mounted securely, the machine may be damaged or injury may occur.
- Do not step on or place a heavy object on the Servomotor. Doing so may result in injury.
- Do not allow any foreign matter to enter the Servomotor.
- For a Servomotor with a Cooling Fan, provide at least 200 mm of space around the fan inlet.
- To prevent electric shock, ground the Servomotor securely.
- Servomotors are precision devices. Never drop the Servomotor or subject it to strong shock.
- Implement safety measures, such as installing a cover, so that the motor shaft and other rotating parts of the Servomotor cannot be touched during operation.
- Continuous operation in one direction, such as for a fan, may damage the bearings due to electrolytic corrosion. Contact your Yaskawa representative if you use a Servomotor for this type of application.
- A Servomotor that has been stored for a long period of time must be inspected before it is used. Contact your Yaskawa representative for more information.
- Using a Servomotor for oscillating rotation may reduce the service life of the bearings. (Oscillating rotation is defined as a continuous forward-reverse operation within a 150° rotation angle of the motor shaft.) Rotate the Servomotor one full turn or more at least once a day.
- Never attempt to disassemble or modify a Servomotor.

## 6.1.2 Installation Environment

Refer to the specifications for each type of Servomotor for the mechanical specifications, protective structure, and environmental conditions related to Servomotor installation.

## 6.1.3 Installation Orientation

You can install the Servomotor either horizontally or vertically.

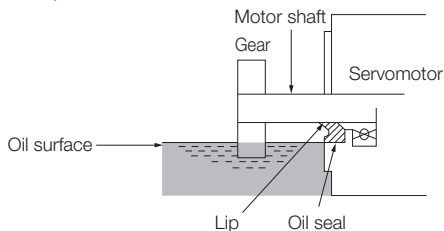
Installation Orientation	Figure	Precautions
Horizontal		If you are using a Servomotor with an Oil Seal, refer to the following section as well. ☞ 6.1.4 Using Servomotors with Oil Seals on page 6-3
Vertical	Shaft end up 	<ul style="list-style-type: none"> <li>You cannot use a Servomotor with an Oil Seal in this orientation.</li> <li>Provide a cable trap so that water drops will not run into the Servomotor.</li> <li>Implement countermeasures in the machine so that oil, e.g., from a gear box, does not enter the Servomotor.</li> </ul>
	Shaft end down 	If you are using a Servomotor with an Oil Seal, refer to the following section as well. ☞ 6.1.4 Using Servomotors with Oil Seals on page 6-3

**Information** If you attach a gear to the Servomotor, observe the installation orientation specified by the manufacturer of the gear.

## 6.1.4 Using Servomotors with Oil Seals

This section gives the operating conditions for using Servomotors with Oil Seals.

- Keep the oil surface below the oil seal lip.



- Use the oil seal in favorably lubricated condition with only splashing of oil.
- Do not allow oil to collect in the oil seal lip.
- Do not use the Servomotor where the oil seal would be below the oil surface. If you do, oil will enter the Servomotor, which may damage the Servomotor.

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## 6.1.5 Using Servomotors with Holding Brakes

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This section gives precautions for using Servomotors with Holding Brakes

- The holding brakes have a limited service life. Although the quality and reliability of a holding brake has been sufficiently confirmed, stress factors, such as emergency braking, can result in problems in the holding operation. In applications in which safety is a concern, such as for a load falling on a vertical axis, determine if safety measures are required on the machine, such as adding a redundant fall-prevention mechanism.
- For a Servomotor with a Holding Brake, there is a small amount of rotational play in the motor shaft (1.5° max. initially) because of the backlash in the holding brake, even when the brake power is OFF.
- For a Servomotor with a Holding Brake, the brake's rotating disc may sometimes generate murmur from friction during acceleration, stopping, and low-speed operation.

## 6.2 Coupling to the Machine

You can couple the Servomotor to the machine with either a coupling or a belt. Use the following procedures.

### 6.2.1 Using a Coupling



Important

- Use a flexible coupling that is designed for Servomotors. We recommend that you use a double-spring coupling, which provides some tolerance in eccentricity and deflection.
- Select a suitable size of coupling for the operating conditions. An inappropriate coupling may cause damage.

1. Wipe off all of the anticorrosive coating from the motor shaft.
2. If you are using a Servomotor with a Key, attach the key enclosed with the Servomotor or the specified size of key to the shaft.

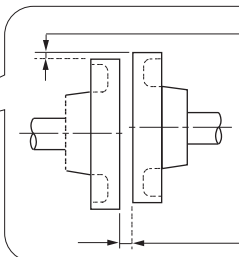
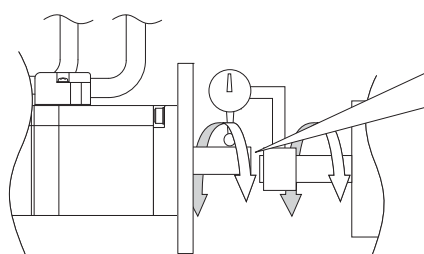


Important

When you attach the key to the motor shaft, do not subject the key groove or shaft to direct shock.

3. Confirm that the centering accuracy is within the specified range using a dial gauge or other means.

If a dial gauge is not available, slide the coupling along both shafts and make adjustments so that it does not catch.




- Centering Accuracy

Measure this distance at four different positions on the circumference. The difference between the maximum and minimum measurements must be 0.03 mm or less. Even within this range, make adjustments to increase centering accuracy as much as possible.

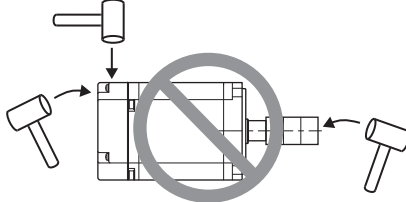
Note: When making the measurements, turn the coupling and motor shaft together.

- Align the shaft of the Servomotor with the shaft of the machine, and then connect the shafts with the coupling.




Important

- When you couple the shafts, make sure that the required centering accuracy is achieved. Vibration will damage the bearings and encoders if the shafts are not properly centered.
- When you attach the coupling, do not subject the shaft to direct shock. Also, do not subject the area around the encoder to shock. Shock may damage the encoder.



- If the coupling makes any abnormal noise, center the shafts again until the noise is eliminated.
- Make sure that the thrust load and radial load are within specifications. Refer to the specifications for each type of Servomotor for the thrust load and radial load.


## 6.2.2 Using a Belt



Note

Select a coupling belt that is suitable for the allowable radial load of the Servomotor and the Servomotor output. When the Servomotor accelerates or decelerates, the counterforce from the acceleration/deceleration torque adds tension to the initial belt tension. Take this additional tension into consideration when you select the coupling belt.

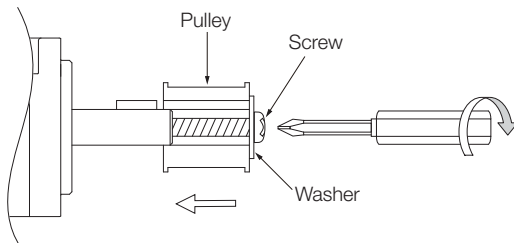
- Wipe off all of the anticorrosive coating from the motor shaft.
- If you are using a Servomotor with a Key, attach the key enclosed with the Servomotor or the specified size of key to the shaft.



Important

When you attach the key to the motor shaft, do not subject the key groove or shaft to direct shock.

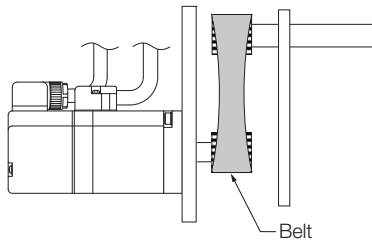
- If you need to attach a pulley to the Servomotor with a Key, use a screwdriver to tighten the screw in the end of the motor shaft to press in and attach the pulley.





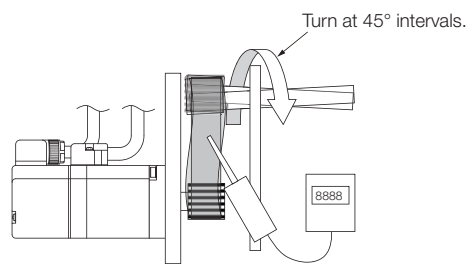
**4. Couple the Servomotor to the machine with a belt.**

When you attach the belt, adjust the belt tension so that the allowable radial load given in the Servomotor specifications is not exceeded. For details, refer to the catalog of the belt manufacturer.



Important

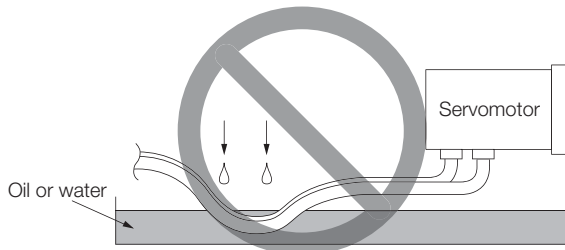
Adjust the belt tension to adjust the radial load. Measure the belt tension at 45° intervals of the machine shaft. Turn the shaft and take measurements with a belt tension meter at each point.



## 6.3 Oil and Water Countermeasures

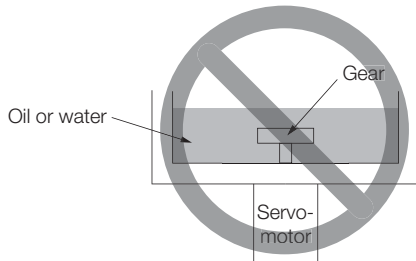
Observe the following instructions so that water, oil, or other foreign matter will not enter the Servomotor.

- Do not allow the cables to be in oil or water.



If contact with oil or water is unavoidable, use oil-resistant cables. Oil-resistant cables are not provided by Yaskawa.

- If you install the Servomotor with the end of the shaft facing up, do not use the Servomotor where oil or water from the machine, a gear box, or other source would come into contact with the Servomotor.



If contact with oil or water is unavoidable, implement countermeasures in the machine so that oil from the gear box does not enter the Servomotor.

- Do not use the Servomotor where it would come into contact with cutting fluids. Depending on the type of cutting fluid, sealing materials, packing, cables, or other parts may be adversely affected.
- Do not use the Servomotor where it would be continuously in contact with oil mist, water vapor, oil, water, or grease. If usage under the above conditions is unavoidable, implement countermeasures in the machine to protect against dirt and water.

## 6.4 Servomotor Temperature Increase

This section describes measures to suppress temperature increases in the Servomotor.

- When you install the Servomotor, observe the cooling conditions (heat sink sizes) that are given in the specifications for each type of Servomotor.  
The Servomotor generates heat when it operates. The heat generated by the Servomotor radiates to the heat sink through the motor mounting surface. Therefore, if the surface area of the heat sink is too small, the temperature of the Servomotor may increase abnormally.
- If the operating environment makes it difficult to use a large heat sink, or if the surrounding air temperature or altitude given in the specifications is exceeded, implement the following measures.
  - Derate the Servomotor.  
Refer to the specifications for each type of Servomotor for information on derating. Consider derating when you select the capacity of the Servomotor.
  - Use external forced-air cooling for the Servomotor with a cooling fan or other means.



Important

Do not place packing or any other insulating material between the Servomotor and heat sink. Doing so will cause the motor temperature to increase, affect resistance to noise, and may cause motor failure.

# Connections between Servomotors and SERVOPACKs



This chapter describes the cables that are used to connect the Servomotors and SERVOPACKs and provides related precautions.

## **7.1 Cables for the SGM7A and SGM7J Servomotors . . . 7-2**

- 7.1.1 System Configurations . . . . . 7-2
- 7.1.2 Servomotor Main Circuit Cables . . . . . 7-3
- 7.1.3 Encoder Cables of 20 m or Less . . . . . 7-7
- 7.1.4 Relay Encoder Cable of 30 m to 50 m . . . . . 7-8

## **7.2 Cables for the SGM7G Servomotors . . . . . 7-9**

- 7.2.1 System Configurations . . . . . 7-9
- 7.2.2 Servomotor Main Circuit Cables . . . . . 7-10
- 7.2.3 Encoder Cables of 20 m or Less . . . . . 7-12
- 7.2.4 Relay Encoder Cables of 30 m to 50 m . . . . . 7-12

## **7.3 Wiring Servomotors and SERVOPACKs . . 7-13**

- 7.3.1 Wiring Precautions . . . . . 7-13
- 7.3.2 Wiring Procedure . . . . . 7-16

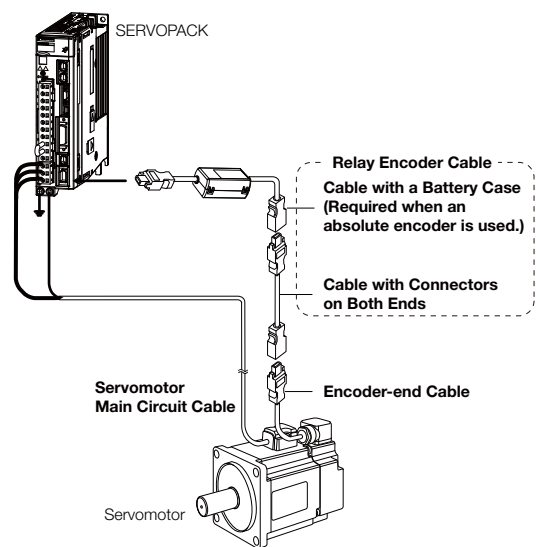
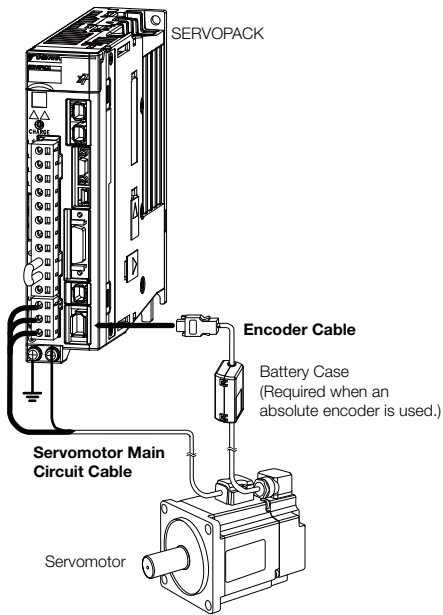
# 7.1 Cables for the SGM7A and SGM7J Servomotors

## 7.1.1 System Configurations


The cables shown below are required to connect a Servomotor to a SERVOPACK.

Encoder Cable of 20 m or Less

Encoder Cable of 30 m to 50 m (Relay Cable)



- Note:
1. Cables with connectors on both ends that are compliant with an IP67 protective structure and European Safety Standards are not available from Yaskawa for the SGM7A-15A to SGM7A-30A Servomotors. You must make such a cable yourself. Use the Connectors specified by Yaskawa for these Servomotors. (These Connectors are compliant with the standards.) Yaskawa does not specify what wiring materials to use.
  2. If the cable length exceeds 20 m, be sure to use a Relay Encoder Cable.
  3. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.
  4. Refer to the *Σ-7-Series Peripheral Device Selection Manual* (Manual No.: SIEP S800001 32) for the following information.
    - Cable dimensional drawings and cable connection specifications
    - Order numbers and specifications of individual connectors for cables
    - Order numbers and specifications for wiring materials

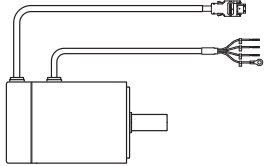


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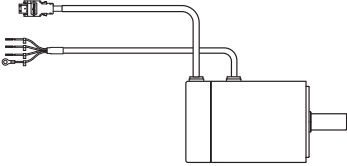
For the following Servomotor models, there are different order numbers for the Servomotor Main Circuit Cables and Encoder Cables depending on the cable installation direction. Confirm the order numbers before you order.

- All SGM7J models
- SGM7A models SGM7A-A5 to SGM7A-10

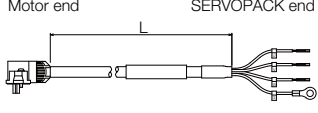

Cable Installed toward Load



Cable Installed away from Load



## 7.1.2 Servomotor Main Circuit Cables

Servomotor Model	Name	Length	Order Number		Appearance
			Standard Cable	Flexible Cable*	
SGM7J-A5 to -C2 SGM7A-A5 to -C2  50 W to 150 W	For Servo- motors with- out Holding Brakes  Cable installed toward load	3 m	JZSP-C7M10F-03-E	JZSP-C7M12F-03-E	
		5 m	JZSP-C7M10F-05-E	JZSP-C7M12F-05-E	
		10 m	JZSP-C7M10F-10-E	JZSP-C7M12F-10-E	
		15 m	JZSP-C7M10F-15-E	JZSP-C7M12F-15-E	
		20 m	JZSP-C7M10F-20-E	JZSP-C7M12F-20-E	
		30 m	JZSP-C7M10F-30-E	JZSP-C7M12F-30-E	
		40 m	JZSP-C7M10F-40-E	JZSP-C7M12F-40-E	
50 m		JZSP-C7M10F-50-E	JZSP-C7M12F-50-E		
SGM7J-02 to -06 SGM7A-02 to -06  200 W to 600 W		3 m	JZSP-C7M20F-03-E	JZSP-C7M22F-03-E	
		5 m	JZSP-C7M20F-05-E	JZSP-C7M22F-05-E	
		10 m	JZSP-C7M20F-10-E	JZSP-C7M22F-10-E	
		15 m	JZSP-C7M20F-15-E	JZSP-C7M22F-15-E	
		20 m	JZSP-C7M20F-20-E	JZSP-C7M22F-20-E	
		30 m	JZSP-C7M20F-30-E	JZSP-C7M22F-30-E	
		40 m	JZSP-C7M20F-40-E	JZSP-C7M22F-40-E	
50 m		JZSP-C7M20F-50-E	JZSP-C7M22F-50-E		
SGM7J-08 SGM7A-08 and -10  750 W, 1.0 kW		3 m	JZSP-C7M30F-03-E	JZSP-C7M32F-03-E	
		5 m	JZSP-C7M30F-05-E	JZSP-C7M32F-05-E	
		10 m	JZSP-C7M30F-10-E	JZSP-C7M32F-10-E	
		15 m	JZSP-C7M30F-15-E	JZSP-C7M32F-15-E	
		20 m	JZSP-C7M30F-20-E	JZSP-C7M32F-20-E	
	30 m	JZSP-C7M30F-30-E	JZSP-C7M32F-30-E		
	40 m	JZSP-C7M30F-40-E	JZSP-C7M32F-40-E		
50 m	JZSP-C7M30F-50-E	JZSP-C7M32F-50-E			
SGM7J-A5 to -C2 SGM7A-A5 to -C2  50 W to 150 W	For Servo- motors with- out Holding Brakes  Cable installed away from load	3 m	JZSP-C7M10G-03-E	JZSP-C7M12G-03-E	
		5 m	JZSP-C7M10G-05-E	JZSP-C7M12G-05-E	
		10 m	JZSP-C7M10G-10-E	JZSP-C7M12G-10-E	
		15 m	JZSP-C7M10G-15-E	JZSP-C7M12G-15-E	
		20 m	JZSP-C7M10G-20-E	JZSP-C7M12G-20-E	
		30 m	JZSP-C7M10G-30-E	JZSP-C7M12G-30-E	
		40 m	JZSP-C7M10G-40-E	JZSP-C7M12G-40-E	
50 m		JZSP-C7M10G-50-E	JZSP-C7M12G-50-E		
SGM7J-02 to -06 SGM7A-02 to -06  200 W to 600 W		3 m	JZSP-C7M20G-03-E	JZSP-C7M22G-03-E	
		5 m	JZSP-C7M20G-05-E	JZSP-C7M22G-05-E	
		10 m	JZSP-C7M20G-10-E	JZSP-C7M22G-10-E	
		15 m	JZSP-C7M20G-15-E	JZSP-C7M22G-15-E	
		20 m	JZSP-C7M20G-20-E	JZSP-C7M22G-20-E	
		30 m	JZSP-C7M20G-30-E	JZSP-C7M22G-30-E	
		40 m	JZSP-C7M20G-40-E	JZSP-C7M22G-40-E	
50 m		JZSP-C7M20G-50-E	JZSP-C7M22G-50-E		
SGM7J-08 SGM7A-08 and -10  750 W, 1.0 kW		3 m	JZSP-C7M30G-03-E	JZSP-C7M32G-03-E	
		5 m	JZSP-C7M30G-05-E	JZSP-C7M32G-05-E	
		10 m	JZSP-C7M30G-10-E	JZSP-C7M32G-10-E	
		15 m	JZSP-C7M30G-15-E	JZSP-C7M32G-15-E	
		20 m	JZSP-C7M30G-20-E	JZSP-C7M32G-20-E	
	30 m	JZSP-C7M30G-30-E	JZSP-C7M32G-30-E		
	40 m	JZSP-C7M30G-40-E	JZSP-C7M32G-40-E		
50 m	JZSP-C7M30G-50-E	JZSP-C7M32G-50-E			

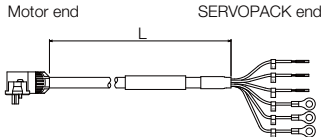
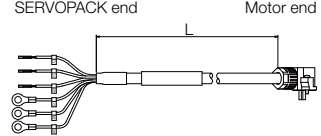
\* Use Flexible Cables for moving parts of machines, such as robots.

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7.1 Cables for the SGM7A and SGM7J Servomotors

7.1.2 Servomotor Main Circuit Cables

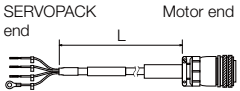
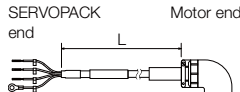
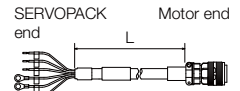
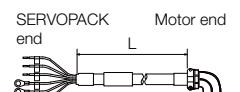
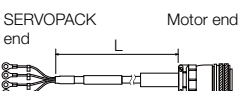
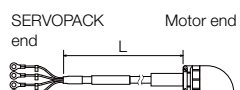
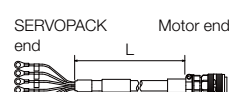
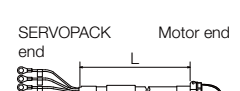
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Servomotor Model	Name	Length	Order Number		Appearance
			Standard Cable	Flexible Cable*	
SGM7J-A5 to -C2 SGM7A-A5 to -C2  50 W to 150 W		3 m	JZSP-C7M13F-03-E	JZSP-C7M14F-03-E	
		5 m	JZSP-C7M13F-05-E	JZSP-C7M14F-05-E	
		10 m	JZSP-C7M13F-10-E	JZSP-C7M14F-10-E	
		15 m	JZSP-C7M13F-15-E	JZSP-C7M14F-15-E	
		20 m	JZSP-C7M13F-20-E	JZSP-C7M14F-20-E	
		30 m	JZSP-C7M13F-30-E	JZSP-C7M14F-30-E	
		40 m	JZSP-C7M13F-40-E	JZSP-C7M14F-40-E	
For Servo- motors with Holding Brakes  200 W to 600 W	Cable installed toward load	3 m	JZSP-C7M23F-03-E	JZSP-C7M24F-03-E	
		5 m	JZSP-C7M23F-05-E	JZSP-C7M24F-05-E	
		10 m	JZSP-C7M23F-10-E	JZSP-C7M24F-10-E	
		15 m	JZSP-C7M23F-15-E	JZSP-C7M24F-15-E	
		20 m	JZSP-C7M23F-20-E	JZSP-C7M24F-20-E	
		30 m	JZSP-C7M23F-30-E	JZSP-C7M24F-30-E	
		40 m	JZSP-C7M23F-40-E	JZSP-C7M24F-40-E	
SGM7J-08 SGM7A-08 and -10  750 W, 1.0 kW		3 m	JZSP-C7M33F-03-E	JZSP-C7M34F-03-E	
		5 m	JZSP-C7M33F-05-E	JZSP-C7M34F-05-E	
		10 m	JZSP-C7M33F-10-E	JZSP-C7M34F-10-E	
		15 m	JZSP-C7M33F-15-E	JZSP-C7M34F-15-E	
		20 m	JZSP-C7M33F-20-E	JZSP-C7M34F-20-E	
		30 m	JZSP-C7M33F-30-E	JZSP-C7M34F-30-E	
		40 m	JZSP-C7M33F-40-E	JZSP-C7M34F-40-E	
SGM7J-A5 to -C2 SGM7A-A5 to -C2  50 W to 150 W		3 m	JZSP-C7M13G-03-E	JZSP-C7M14G-03-E	
		5 m	JZSP-C7M13G-05-E	JZSP-C7M14G-05-E	
		10 m	JZSP-C7M13G-10-E	JZSP-C7M14G-10-E	
		15 m	JZSP-C7M13G-15-E	JZSP-C7M14G-15-E	
		20 m	JZSP-C7M13G-20-E	JZSP-C7M14G-20-E	
		30 m	JZSP-C7M13G-30-E	JZSP-C7M14G-30-E	
		40 m	JZSP-C7M13G-40-E	JZSP-C7M14G-40-E	
For Servo- motors with Holding Brakes  200 W to 600 W	Cable installed away from load	3 m	JZSP-C7M23G-03-E	JZSP-C7M24G-03-E	
		5 m	JZSP-C7M23G-05-E	JZSP-C7M24G-05-E	
		10 m	JZSP-C7M23G-10-E	JZSP-C7M24G-10-E	
		15 m	JZSP-C7M23G-15-E	JZSP-C7M24G-15-E	
		20 m	JZSP-C7M23G-20-E	JZSP-C7M24G-20-E	
		30 m	JZSP-C7M23G-30-E	JZSP-C7M24G-30-E	
		40 m	JZSP-C7M23G-40-E	JZSP-C7M24G-40-E	
SGM7J-08 SGM7A-08 and -10  750 W, 1.0 kW		3 m	JZSP-C7M33G-03-E	JZSP-C7M34G-03-E	
		5 m	JZSP-C7M33G-05-E	JZSP-C7M34G-05-E	
		10 m	JZSP-C7M33G-10-E	JZSP-C7M34G-10-E	
		15 m	JZSP-C7M33G-15-E	JZSP-C7M34G-15-E	
		20 m	JZSP-C7M33G-20-E	JZSP-C7M34G-20-E	
		30 m	JZSP-C7M33G-30-E	JZSP-C7M34G-30-E	
		40 m	JZSP-C7M33G-40-E	JZSP-C7M34G-40-E	
50 m	JZSP-C7M33G-50-E	JZSP-C7M34G-50-E			

\* Use Flexible Cables for moving parts of machines, such as robots.

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Servo-motor Model	Name	Connector Specifications	Length	Order Number		Appearance
				Standard Cable	Flexible Cable*	
SGM7A-15A 1.5 kW	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA101-03-E	JZSP-UVA121-03-E	
			5 m	JZSP-UVA101-05-E	JZSP-UVA121-05-E	
			10 m	JZSP-UVA101-10-E	JZSP-UVA121-10-E	
			15 m	JZSP-UVA101-15-E	JZSP-UVA121-15-E	
		Right-angle	3 m	JZSP-UVA102-03-E	JZSP-UVA122-03-E	
			5 m	JZSP-UVA102-05-E	JZSP-UVA122-05-E	
			10 m	JZSP-UVA102-10-E	JZSP-UVA122-10-E	
			15 m	JZSP-UVA102-15-E	JZSP-UVA122-15-E	
	For Servomotors with Holding Brakes	Straight	3 m	JZSP-UVA151-03-E	JZSP-UVA161-03-E	
			5 m	JZSP-UVA151-05-E	JZSP-UVA161-05-E	
			10 m	JZSP-UVA151-10-E	JZSP-UVA161-10-E	
			15 m	JZSP-UVA151-15-E	JZSP-UVA161-15-E	
		Right-angle	3 m	JZSP-UVA152-03-E	JZSP-UVA162-03-E	
			5 m	JZSP-UVA152-05-E	JZSP-UVA162-05-E	
			10 m	JZSP-UVA152-10-E	JZSP-UVA162-10-E	
			15 m	JZSP-UVA152-15-E	JZSP-UVA162-15-E	
SGM7A-20A 2.0 kW	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA301-03-E	JZSP-UVA321-03-E	
			5 m	JZSP-UVA301-05-E	JZSP-UVA321-05-E	
			10 m	JZSP-UVA301-10-E	JZSP-UVA321-10-E	
			15 m	JZSP-UVA301-15-E	JZSP-UVA321-15-E	
		Right-angle	3 m	JZSP-UVA302-03-E	JZSP-UVA322-03-E	
			5 m	JZSP-UVA302-05-E	JZSP-UVA322-05-E	
			10 m	JZSP-UVA302-10-E	JZSP-UVA322-10-E	
			15 m	JZSP-UVA302-15-E	JZSP-UVA322-15-E	
	For Servomotors with Holding Brakes	Straight	3 m	JZSP-UVA351-03-E	JZSP-UVA361-03-E	
			5 m	JZSP-UVA351-05-E	JZSP-UVA361-05-E	
			10 m	JZSP-UVA351-10-E	JZSP-UVA361-10-E	
			15 m	JZSP-UVA351-15-E	JZSP-UVA361-15-E	
		Right-angle	3 m	JZSP-UVA352-03-E	JZSP-UVA362-03-E	
			5 m	JZSP-UVA352-05-E	JZSP-UVA362-05-E	
			10 m	JZSP-UVA352-10-E	JZSP-UVA362-10-E	
			15 m	JZSP-UVA352-15-E	JZSP-UVA362-15-E	
			20 m	JZSP-UVA352-20-E	JZSP-UVA362-20-E	

\* Use Flexible Cables for moving parts of machines, such as robots.

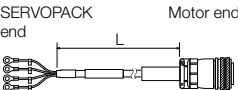
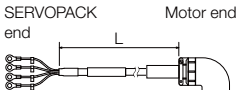
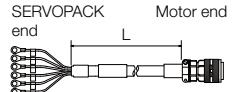

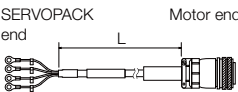
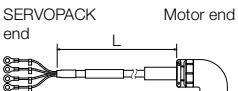
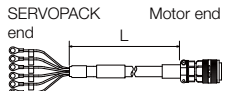
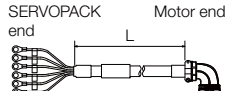
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7.1 Cables for the SGM7A and SGM7J Servomotors

7.1.2 Servomotor Main Circuit Cables

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Servo-motor Model	Name	Connector Specifications	Length	Order Number		Appearance
				Standard Cable	Flexible Cable*	
SGM7A-25A	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA501-03-E	JZSP-UVA521-03-E	
			5 m	JZSP-UVA501-05-E	JZSP-UVA521-05-E	
			10 m	JZSP-UVA501-10-E	JZSP-UVA521-10-E	
			15 m	JZSP-UVA501-15-E	JZSP-UVA521-15-E	
			20 m	JZSP-UVA501-20-E	JZSP-UVA521-20-E	
		Right-angle	3 m	JZSP-UVA502-03-E	JZSP-UVA522-03-E	
			5 m	JZSP-UVA502-05-E	JZSP-UVA522-05-E	
			10 m	JZSP-UVA502-10-E	JZSP-UVA522-10-E	
			15 m	JZSP-UVA502-15-E	JZSP-UVA522-15-E	
			20 m	JZSP-UVA502-20-E	JZSP-UVA522-20-E	
2.5 kW	For Servomotors with Holding Brakes	Straight	3 m	JZSP-UVA551-03-E	JZSP-UVA561-03-E	
			5 m	JZSP-UVA551-05-E	JZSP-UVA561-05-E	
			10 m	JZSP-UVA551-10-E	JZSP-UVA561-10-E	
			15 m	JZSP-UVA551-15-E	JZSP-UVA561-15-E	
			20 m	JZSP-UVA551-20-E	JZSP-UVA561-20-E	
		Right-angle	3 m	JZSP-UVA552-03-E	JZSP-UVA562-03-E	
			5 m	JZSP-UVA552-05-E	JZSP-UVA562-05-E	
			10 m	JZSP-UVA552-10-E	JZSP-UVA562-10-E	
			15 m	JZSP-UVA552-15-E	JZSP-UVA562-15-E	
			20 m	JZSP-UVA552-20-E	JZSP-UVA562-20-E	
SGM7A-30A	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA601-03-E	JZSP-UVA621-03-E	
			5 m	JZSP-UVA601-05-E	JZSP-UVA621-05-E	
			10 m	JZSP-UVA601-10-E	JZSP-UVA621-10-E	
			15 m	JZSP-UVA601-15-E	JZSP-UVA621-15-E	
			20 m	JZSP-UVA601-20-E	JZSP-UVA621-20-E	
		Right-angle	3 m	JZSP-UVA602-03-E	JZSP-UVA622-03-E	
			5 m	JZSP-UVA602-05-E	JZSP-UVA622-05-E	
			10 m	JZSP-UVA602-10-E	JZSP-UVA622-10-E	
			15 m	JZSP-UVA602-15-E	JZSP-UVA622-15-E	
			20 m	JZSP-UVA602-20-E	JZSP-UVA622-20-E	
3.0 kW	For Servomotors with Holding Brakes	Straight	3 m	JZSP-UVA651-03-E	JZSP-UVA661-03-E	
			5 m	JZSP-UVA651-05-E	JZSP-UVA661-05-E	
			10 m	JZSP-UVA651-10-E	JZSP-UVA661-10-E	
			15 m	JZSP-UVA651-15-E	JZSP-UVA661-15-E	
			20 m	JZSP-UVA651-20-E	JZSP-UVA661-20-E	
		Right-angle	3 m	JZSP-UVA652-03-E	JZSP-UVA662-03-E	
			5 m	JZSP-UVA652-05-E	JZSP-UVA662-05-E	
			10 m	JZSP-UVA652-10-E	JZSP-UVA662-10-E	
			15 m	JZSP-UVA652-15-E	JZSP-UVA662-15-E	
			20 m	JZSP-UVA652-20-E	JZSP-UVA662-20-E	

\* Use Flexible Cables for moving parts of machines, such as robots.

## 7.1.3 Encoder Cables of 20 m or Less

Servomotor Model	Name	Length	Order Number		Appearance	
			Standard Cable	Flexible Cable* <sup>1</sup>		
SGM7J-A5 to -08 50 W to 750 W	For incremental encoder	3 m	JZSP-C7PI0D-03-E	JZSP-C7PI2D-03-E		
		5 m	JZSP-C7PI0D-05-E	JZSP-C7PI2D-05-E		
	Cable installed toward load	10 m	JZSP-C7PI0D-10-E	JZSP-C7PI2D-10-E		
		15 m	JZSP-C7PI0D-15-E	JZSP-C7PI2D-15-E		
		20 m	JZSP-C7PI0D-20-E	JZSP-C7PI2D-20-E		
		For incremental encoder	3 m	JZSP-C7PI0E-03-E		JZSP-C7PI2E-03-E
	5 m		JZSP-C7PI0E-05-E	JZSP-C7PI2E-05-E		
	10 m		JZSP-C7PI0E-10-E	JZSP-C7PI2E-10-E		
	15 m		JZSP-C7PI0E-15-E	JZSP-C7PI2E-15-E		
	Cable installed away from load	20 m	JZSP-C7PI0E-20-E	JZSP-C7PI2E-20-E		
		For absolute encoder: With Battery Case* <sup>2</sup>	3 m	JZSP-C7PA0D-03-E	JZSP-C7PA2D-03-E	
			5 m	JZSP-C7PA0D-05-E	JZSP-C7PA2D-05-E	
			10 m	JZSP-C7PA0D-10-E	JZSP-C7PA2D-10-E	
	15 m		JZSP-C7PA0D-15-E	JZSP-C7PA2D-15-E		
	Cable installed toward load	20 m	JZSP-C7PA0D-20-E	JZSP-C7PA2D-20-E		
		For absolute encoder: With Battery Case* <sup>2</sup>	3 m	JZSP-C7PA0E-03-E	JZSP-C7PA2E-03-E	
			5 m	JZSP-C7PA0E-05-E	JZSP-C7PA2E-05-E	
			10 m	JZSP-C7PA0E-10-E	JZSP-C7PA2E-10-E	
	15 m		JZSP-C7PA0E-15-E	JZSP-C7PA2E-15-E		
	Cable installed away from load	20 m	JZSP-C7PA0E-20-E	JZSP-C7PA2E-20-E		
For incremental encoder		3 m	JZSP-CVP01-03-E	JZSP-CVP11-03-E		
		5 m	JZSP-CVP01-05-E	JZSP-CVP11-05-E		
		10 m	JZSP-CVP01-10-E	JZSP-CVP11-10-E		
	15 m	JZSP-CVP01-15-E	JZSP-CVP11-15-E			
Cable installed toward load	20 m	JZSP-CVP01-20-E	JZSP-CVP11-20-E			
	For incremental encoder	3 m	JZSP-CVP02-03-E	JZSP-CVP12-03-E		
		5 m	JZSP-CVP02-05-E	JZSP-CVP12-05-E		
		10 m	JZSP-CVP02-10-E	JZSP-CVP12-10-E		
15 m		JZSP-CVP02-15-E	JZSP-CVP12-15-E			
Cable installed toward load	20 m	JZSP-CVP02-20-E	JZSP-CVP12-20-E			
	For absolute encoder: With Battery Case* <sup>2</sup>	3 m	JZSP-CVP06-03-E		JZSP-CVP26-03-E	
		5 m	JZSP-CVP06-05-E		JZSP-CVP26-05-E	
		10 m	JZSP-CVP06-10-E		JZSP-CVP26-10-E	
15 m		JZSP-CVP06-15-E	JZSP-CVP26-15-E			
Cable installed toward load	20 m	JZSP-CVP06-20-E	JZSP-CVP26-20-E			
	For absolute encoder: With Battery Case* <sup>2</sup>	3 m	JZSP-CVP07-03-E		JZSP-CVP27-03-E	
		5 m	JZSP-CVP07-05-E		JZSP-CVP27-05-E	
		10 m	JZSP-CVP07-10-E		JZSP-CVP27-10-E	
15 m		JZSP-CVP07-15-E	JZSP-CVP27-15-E			
Cable installed toward load	20 m	JZSP-CVP07-20-E	JZSP-CVP27-20-E			

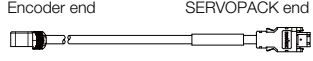
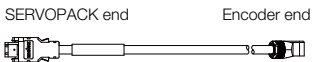
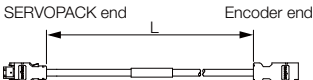
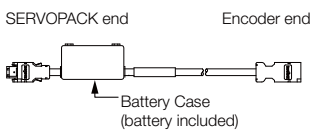


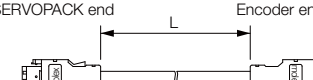
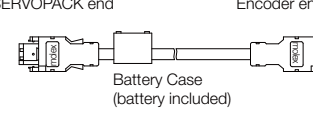
\*1. Use Flexible Cables for moving parts of machines, such as robots.

\*2. If a battery is connected to the host controller, the Battery Case is not required. If so, use a cable for incremental encoders.

7.1 Cables for the SGM7A and SGM7J Servomotors

7.1.4 Relay Encoder Cable of 30 m to 50 m

## 7.1.4 Relay Encoder Cable of 30 m to 50 m

Servomotor Model	Name	Length	Order Number	Appearance
SGM7J-A5 to -08 50 W to 750 W	Encoder-end Cable (for incremental or absolute encoder) Cable installed toward load	0.3 m	JZSP-C7PRCD-E	
	Encoder-end Cable (for incremental or absolute encoder) Cable installed away from load	0.3 m	JZSP-C7PRCE-E	
	Cables with Connectors on Both Ends (for incremental or absolute encoder)	30 m	JZSP-UCMP00-30-E	
		40 m	JZSP-UCMP00-40-E	
50 m		JZSP-UCMP00-50-E		
	Cable with a Battery Case (Required when an absolute encoder is used.*)	0.3 m	JZSP-CSP12-E	
SGM7A-15 to -30 1.5 kW to 3.0 kW	Encoder-end Cable (for incremental or absolute encoder)	0.3 m	JZSP-CVP01-E	
			JZSP-CVP02-E	
	Cables with Connectors on Both Ends (for incremental or absolute encoder)	30 m	JZSP-UCMP00-30-E	
		40 m	JZSP-UCMP00-40-E	
		50 m	JZSP-UCMP00-50-E	
	Cable with a Battery Case (Required when an absolute encoder is used.*)	0.3 m	JZSP-CSP12-E	

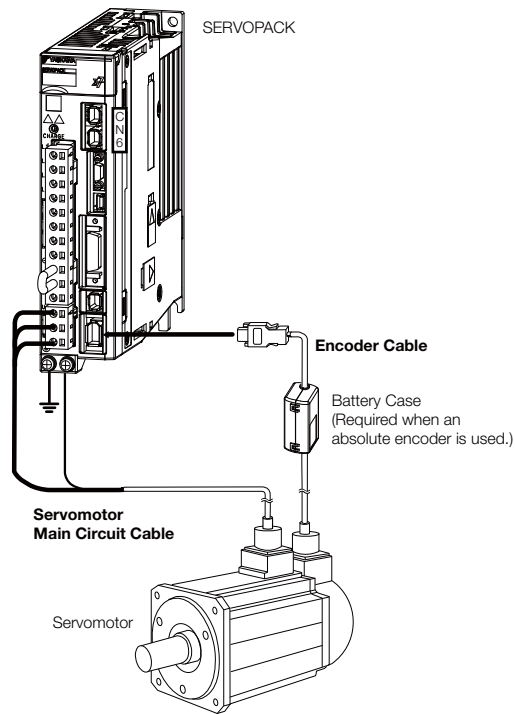
\* This Cable is not required if a battery is connected to the host controller.

## 7.2 Cables for the SGM7G Servomotors

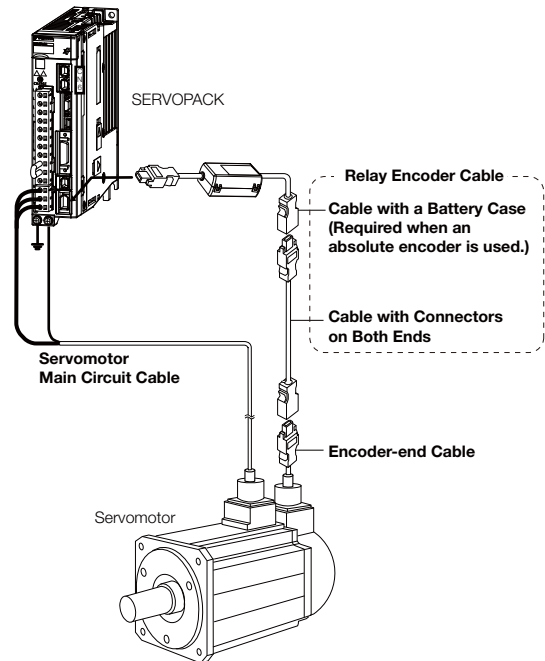
### 7.2.1 System Configurations

The cables shown below are required to connect a Servomotor to a SERVOPACK.

Encoder Cable of 20 m or Less



Encoder Cable of 30 m to 50 m (Relay Cable)



- Note: 1. Cables with connectors on both ends that are compliant with an IP67 protective structure and European Safety Standards are not available from Yaskawa for the SGM7G Servomotors. You must make such a cable yourself. Use the Connectors specified by Yaskawa for these Servomotors. (These Connectors are compliant with the standards.) Yaskawa does not specify what wiring materials to use.
2. If the cable length exceeds 20 m, be sure to use a Relay Encoder Cable.
3. If you use a Servomotor Main Circuit Cable that exceeds 20 m, the intermittent duty zone in the torque-motor speed characteristics will become smaller because the voltage drop increases.
4. Refer to the *Σ-7-Series Peripheral Device Selection Manual* (Manual No.: SIEP S800001 32) for the following information.
- Cable dimensional drawings and cable connection specifications
  - Order numbers and specifications of individual connectors for cables
  - Order numbers and specifications for wiring materials

## 7.2.2 Servomotor Main Circuit Cables

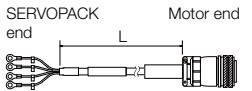
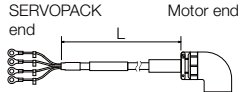
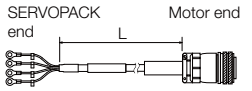
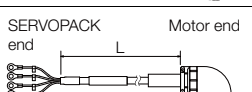
Servomotor Model	Name	Length	Order Number*	Appearance
SGM7G-03 to -05  0.3 kW 0.45 kW	For Servomotors without Holding Brakes	3 m	JZSP-CVM21-03-E	
		5 m	JZSP-CVM21-05-E	
		10 m	JZSP-CVM21-10-E	
		15 m	JZSP-CVM21-15-E	
		20 m	JZSP-CVM21-20-E	
		30 m	JZSP-CVM21-30-E	
		40 m	JZSP-CVM21-40-E	
	For Servomotors with Holding Brakes	3 m	JZSP-CVM41-03-E	
		5 m	JZSP-CVM41-05-E	
		10 m	JZSP-CVM41-10-E	
		15 m	JZSP-CVM41-15-E	
		20 m	JZSP-CVM41-20-E	
		30 m	JZSP-CVM41-30-E	
		40 m	JZSP-CVM41-40-E	
50 m	JZSP-CVM41-50-E			

\* Flexible cables are provided as a standard feature.

Servomotor Model	Name	Connector Specifications	Length	Order Number		Appearance
				Standard Cable	Flexible Cable	
SGM7G-09, -13  850 W, 1.3 kW	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA101-03-E	JZSP-UVA121-03-E	
			5 m	JZSP-UVA101-05-E	JZSP-UVA121-05-E	
			10 m	JZSP-UVA101-10-E	JZSP-UVA121-10-E	
			15 m	JZSP-UVA101-15-E	JZSP-UVA121-15-E	
			20 m	JZSP-UVA101-20-E	JZSP-UVA121-20-E	
		Right-angle	3 m	JZSP-UVA102-03-E	JZSP-UVA122-03-E	
			5 m	JZSP-UVA102-05-E	JZSP-UVA122-05-E	
			10 m	JZSP-UVA102-10-E	JZSP-UVA122-10-E	
			15 m	JZSP-UVA102-15-E	JZSP-UVA122-15-E	
			20 m	JZSP-UVA102-20-E	JZSP-UVA122-20-E	
	For Servomotors with Holding Brakes	Straight*1	3 m	JZSP-UVA131-03-E	JZSP-UVA141-03-E	
			5 m	JZSP-UVA131-05-E	JZSP-UVA141-05-E	
			10 m	JZSP-UVA131-10-E	JZSP-UVA141-10-E	
			15 m	JZSP-UVA131-15-E	JZSP-UVA141-15-E	
			20 m	JZSP-UVA131-20-E	JZSP-UVA141-20-E	
		Right-angle*2	3 m	JZSP-UVA132-03-E	JZSP-UVA142-03-E	
			5 m	JZSP-UVA132-05-E	JZSP-UVA142-05-E	
			10 m	JZSP-UVA132-10-E	JZSP-UVA142-10-E	
Note: Set of two cables (Main Power Supply Cable and Holding Brake Cable)		Right-angle*2	15 m	JZSP-UVA132-15-E	JZSP-UVA142-15-E	
20 m	JZSP-UVA132-20-E		JZSP-UVA142-20-E			
20 m	JZSP-UVA132-20-E		JZSP-UVA142-20-E			

\*1. The order number for the Main Power Supply Cable is JZSP-UVA101-□□-E (standard cable) or JZSP-UVA121-□□-E (flexible cable). The order number for the Holding Brake Cable is JZSP-CVB9-SMC3-E.

\*2. The order number for the Main Power Supply Cable is JZSP-UVA102-□□-E (standard cable) or JZSP-UVA122-□□-E (flexible cable). The order number for the Holding Brake Cable is JZSP-CVB9-AMC3-E.

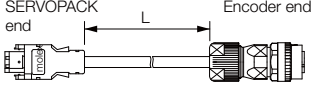
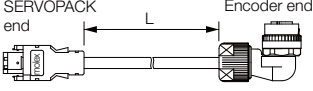
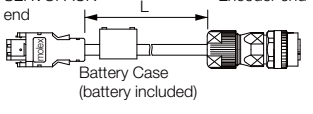
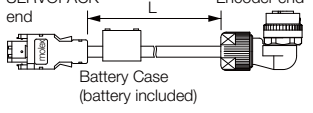
Servo- motor Model	Name	Conne- tor Spec- ifications	Length	Order Number		Appearance
				Standard Cable	Flexible Cable	
SGM7G- 20  1.8 kW	For Servomotors without Holding Brakes	Straight	3 m	JZSP-UVA301-03-E	JZSP-UVA321-03-E	
			5 m	JZSP-UVA301-05-E	JZSP-UVA321-05-E	
			10 m	JZSP-UVA301-10-E	JZSP-UVA321-10-E	
			15 m	JZSP-UVA301-15-E	JZSP-UVA321-15-E	
			20 m	JZSP-UVA301-20-E	JZSP-UVA321-20-E	
		Right-angle	3 m	JZSP-UVA302-03-E	JZSP-UVA322-03-E	
			5 m	JZSP-UVA302-05-E	JZSP-UVA322-05-E	
			10 m	JZSP-UVA302-10-E	JZSP-UVA322-10-E	
			15 m	JZSP-UVA302-15-E	JZSP-UVA322-15-E	
			20 m	JZSP-UVA302-20-E	JZSP-UVA322-20-E	
	For Servomotors with Holding Brakes  Note: Set of two cables (Main Power Sup- ply Cable and Holding Brake Cable)	Straight* <sup>1</sup>	3 m	JZSP-UVA331-03-E	JZSP-UVA341-03-E	
			5 m	JZSP-UVA331-05-E	JZSP-UVA341-05-E	
			10 m	JZSP-UVA331-10-E	JZSP-UVA341-10-E	
			15 m	JZSP-UVA331-15-E	JZSP-UVA341-15-E	
			20 m	JZSP-UVA331-20-E	JZSP-UVA341-20-E	
		Right-angle * <sup>2</sup>	3 m	JZSP-UVA332-03-E	JZSP-UVA342-03-E	
			5 m	JZSP-UVA332-05-E	JZSP-UVA342-05-E	
			10 m	JZSP-UVA332-10-E	JZSP-UVA342-10-E	
			15 m	JZSP-UVA332-15-E	JZSP-UVA342-15-E	
			20 m	JZSP-UVA332-20-E	JZSP-UVA342-20-E	

Note: If you need a Cable with a length of 20 m to 50 m, consider the operating conditions and specify a suitable length.

\*1. The order number for the Main Power Supply Cable is JZSP-UVA301-□□-E (standard cable) or JZSP-UVA321-□□-E (flexible cable). The order number for the Holding Brake Cable is JZSP-CVB9-SMC3-E.

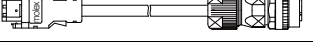
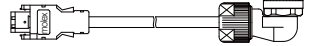
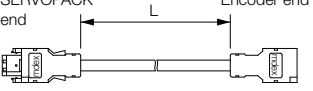
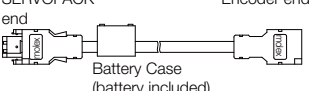
\*2. The order number for the Main Power Supply Cable is JZSP-UVA302-□□-E (standard cable) or JZSP-UVA322-□□-E (flexible cable). The order number for the Holding Brake Cable is JZSP-CVB9-AMC3-E.

## 7.2.3 Encoder Cables of 20 m or Less

Servomotor Model	Name	Length	Order Number		Appearance	
			Standard Cable	Flexible Cable*		
SGM7G-03 to -20 300 W to 1.8 kW	Cables with Connectors on Both Ends (for incremental encoder)	3 m	JZSP-CVP01-03-E	JZSP-CVP11-03-E		
		5 m	JZSP-CVP01-05-E	JZSP-CVP11-05-E		
		10 m	JZSP-CVP01-10-E	JZSP-CVP11-10-E		
		15 m	JZSP-CVP01-15-E	JZSP-CVP11-15-E		
		20 m	JZSP-CVP01-20-E	JZSP-CVP11-20-E		
		3 m	JZSP-CVP02-03-E	JZSP-CVP12-03-E		
		5 m	JZSP-CVP02-05-E	JZSP-CVP12-05-E		
		10 m	JZSP-CVP02-10-E	JZSP-CVP12-10-E		
	15 m	JZSP-CVP02-15-E	JZSP-CVP12-15-E			
	Cables with Connectors on Both Ends (for absolute encoder: With Battery Case)	3 m	JZSP-CVP06-03-E	JZSP-CVP26-03-E		
		5 m	JZSP-CVP06-05-E	JZSP-CVP26-05-E		
		10 m	JZSP-CVP06-10-E	JZSP-CVP26-10-E		
		15 m	JZSP-CVP06-15-E	JZSP-CVP26-15-E		
		3 m	JZSP-CVP07-03-E	JZSP-CVP27-03-E		
		5 m	JZSP-CVP07-05-E	JZSP-CVP27-05-E		
		10 m	JZSP-CVP07-10-E	JZSP-CVP27-10-E		
15 m		JZSP-CVP07-15-E	JZSP-CVP27-15-E			
20 m	JZSP-CVP07-20-E	JZSP-CVP27-20-E				

\* Use Flexible Cables for moving parts of machines, such as robots.

## 7.2.4 Relay Encoder Cables of 30 m to 50 m

Servomotor Model	Name	Length	Order Number for Standard Cable	Appearance
SGM7G-03 to -20 300 W to 1.8 kW	Encoder-end Cable (for incremental or absolute encoder)	0.3 m	JZSP-CVP01-E	
			JZSP-CVP02-E	
	Cables with Connectors on Both Ends (for incremental or absolute encoder)	30 m	JZSP-UCMP00-30-E	
		40 m	JZSP-UCMP00-40-E	
		50 m	JZSP-UCMP00-50-E	
	Cable with a Battery Case (Required only if an absolute encoder is used.)*	0.3 m	JZSP-CSP12-E	

\* This Cable is not required if a battery is connected to the host controller.

## 7.3

## Wiring Servomotors and SERVOPACKs

## 7.3.1 Wiring Precautions

**CAUTION**

- Do not connect the Servomotor directly to an industrial power supply. Doing so will destroy the Servomotor. You cannot operate a Servomotor without a SERVOPACK that is designed for it

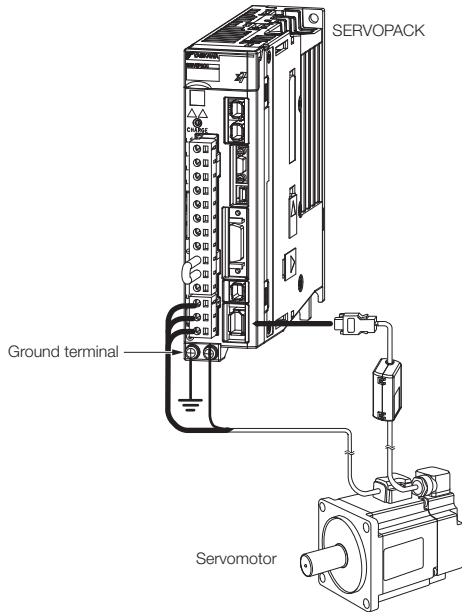
**General Precautions**

- Wiring Procedure
- Always connect the Servomotor Main Circuit Cable before you connect the Encoder Cable. If you connect the Encoder Cable first, the encoder may be damaged due to the difference in electrical potential from the FG.
- Never touch the connector pins on the Servomotor directly with your hands. Particularly the encoder may be damaged by static electricity.
- For the following Servomotor models, use the screws to secure the cable connectors to the Servomotor. Make sure that they are securely attached.
  - SGM7J Servomotors
  - SGM7A Servomotors up to 1.0 kW
  - SGM7G Servomotors up to 450 W
 If they are not securely attached, the protective structure specifications may not be satisfied.
- Do not remove rubber packings or O-rings. Also, make sure that rubber packings and O-rings do not come off. If the rubber packings or O-rings are not securely attached, the protective structure specifications may not be satisfied.
- Separate the Servomotor Main Circuit Cable from the I/O Signal Cables and Encoder Cable by at least 30 cm.
- Do not connect magnetic contactors, reactors, or other devices on the cables that connect the SERVOPACK and Servomotor. Failure to observe this caution may result in malfunction or damage.
- Do not subject the cables to excessive bending stress or tension. The conductors in the Encoder Cable and Servomotor Main Circuit Cable are as thin as 0.2 mm<sup>2</sup> or 0.3 mm<sup>2</sup>. Wire them so that they are not subjected to excessive stress.
- If you secure the cables with cable ties, protect the cables with cushioning material.
- If the cable will be bent repeatedly, e.g., if the Servomotor will move in the machine, use Flexible Cables. If you do not use Flexible Cables, the cables may break.
- Before you connect the wires, make sure that there are no mistakes in the wiring.
- Always use the connectors specified by Yaskawa and insert them correctly.
- When you connect a connector, check it to make sure there is no foreign matter, such as metal clippings, inside.
- The connectors are made of resin. To prevent damage, do not apply any strong impact.
- Perform all wiring so that stress is not applied to the connectors. The connectors may break if they are subjected to stress.
- If you move the Servomotor while the cables are connected, always hold onto the main body of the Servomotor. If you lift the Servomotor by the cables when you move it, the connectors may be damaged or the cables may be broken.



## Grounding Precautions

The ground terminal on the SERVOPACK is used to ground the Servomotor.



## Precautions for Standard Cables

Do not use standard cables in applications that required a high degree of flexibility, such as twisting and turning, or in which the cables themselves must move. When you use Standard Cables, observe the recommended bending radius given in the following table and perform all wiring so that stress is not applied to the cables. Use the cables so that they are not repeatedly bent.

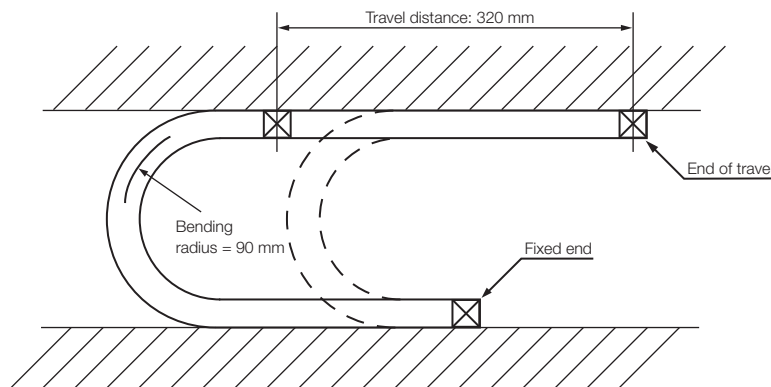
Cable Diameter	Recommended Bending Radius [R]
Less than 8 mm	15 mm min.
8 mm	20 mm min.
Over 8 mm	Cable diameter × 3 mm min.

## Precautions for Flexible Cables

- The Flexible Cables have a service life of 10,000,000 operations minimum when used at the recommended bending radius of 90 mm or larger under the following test conditions. The service life of a Flexible Cable is reference data under special test conditions. The service life of a Flexible Cable greatly depends on the amount of mechanical shock, how the cable is attached, and how the cable is secured.

### Test Conditions

- One end of the cable is repeatedly moved forward and backward for 320 mm using the test equipment shown in the following figure.
- The lead wires are connected in parallel, and the number of cable return operations until a lead wire breaks are counted. One round trip is counted as one bend.



Note: The service life of a Flexible Cable indicates the number of bends while the lead wires are electrically charged for which no cracks or damage that affects the performance of the cable sheathing occur. Breaking of the shield wire is not considered.

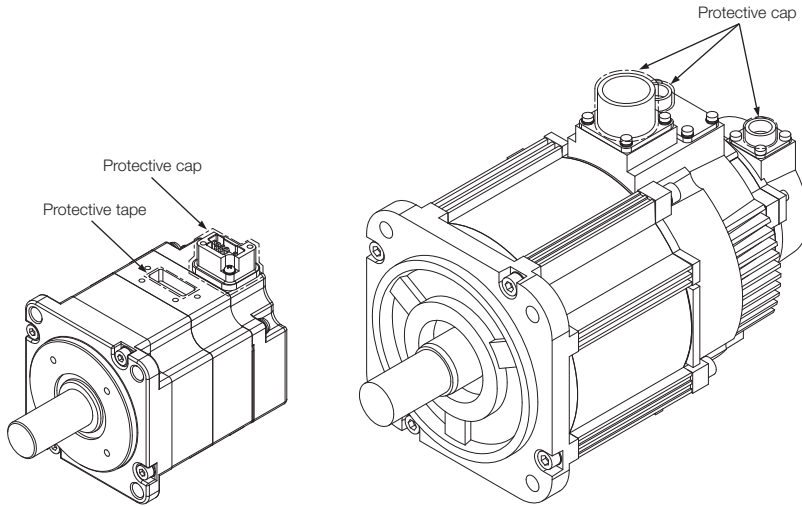
- Straighten out the Flexible Cable when you connect it. If the cable is connected while it is twisted, it will break faster. Check the indication on the cable surface to make sure that the cable is not twisted.
- Do not secure the portions of the Flexible Cable that move. Stress will accumulate at the point that is secured, and the cable will break faster. Secure the cable in as few locations as possible.
- If a Flexible Cable is too long, looseness will cause it to break faster. If the Flexible Cable is too short, stress at the points where it is secured will cause it to break faster. Adjust the cable length to the optimum value.
- Do not allow Flexible Cables to interfere with each other. Interference will restrict the motion of the cables, causing them to break faster. Separate the cables sufficiently, or provide partitions between them when wiring.

## 7.3.2 Wiring Procedure

This manual provides the wiring procedure only for the Servomotors. Refer to the SERVOPACK manual for information on wiring the SERVOPACKs.

**1. Remove the protective cap and protective tape from the Servomotor connectors.**

- Information**
  - Some models of Servomotors do not have protective tape.
  - The number of connectors depends on the model of the Servomotor.

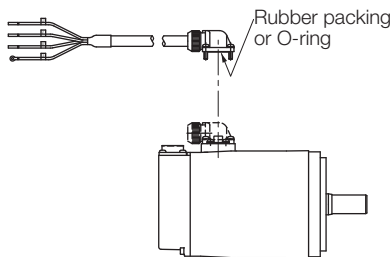


**2. Attach the Servomotor Main Circuit Cable and tighten the screws.**

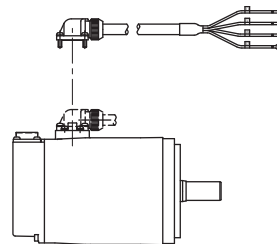
Pay attention to the orientation of the cable (i.e., load or non-load side) when you attach it. Refer to the following table for the tightening torque.

Servomotor Model	Tightening Torque	Servomotor Model	Tightening Torque
SGM7J-A5 to -06	0.15 N·m	SGM7A-A5 to -06	0.15 N·m
SGM7J-08	0.33 N·m	SGM7A-08 to -10	0.33 N·m
		SGM7G-03, -05	0.44 N·m

- Leads on Non-load Side



- Leads on Load Side



- Information**
  - There are two Servomotor Main Circuit Cables for the SGM7G-09, SGM7G-13, or SGM7G-20 Servomotor (the Main Power Supply Cable and the Holding Brake Cable). Attach both of them.

**3. Attach the Encoder Cable and tighten the screws. Pay attention to the orientation of the cable (i.e., load or non-load side) when you attach it.**

- Tightening torque:  
SGM7J and SGM7A Servomotors up to 1.0 kW: 0.15 N·m

To extend the Encoder Cable to from 30 to 50 m, proceed to step 4.

**4. Connect a Cable with Connectors on Both Ends to the Encoder Cable.**

**5. If necessary, connect a Cable with a Battery Case to the Cable with Connectors on Both Ends.**

# Maintenance and Inspection

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This section describes the maintenance, inspection, and disposal of a Servomotor.

<b>8.1</b>	<b>Periodic Inspections . . . . .</b>	<b>8-2</b>
<b>8.2</b>	<b>Service Lives of Parts . . . . .</b>	<b>8-3</b>
<b>8.3</b>	<b>Disposing of Servomotors . . . . .</b>	<b>8-4</b>

## 8.1 Periodic Inspections

The following table gives the periodic inspection items for a Servomotor. The inspection periods given in the table are guidelines. Determine the optimum inspection periods based on the application conditions and environment.

### CAUTION

- Before you perform any maintenance or inspection work, turn OFF the power supply, confirm that the CHARGE indicator on the front of the SERVOPACK has gone out, and then use a tester to check the voltage between the positive and negative terminals on the SERVOPACK. Start inspection work only after you have confirmed that the main circuit voltage has dropped.  
If there is any main circuit voltage left, the risk of electric shock still exists. Do not touch the Servomotor or any wiring.
- All inspection and maintenance work must be performed only by qualified engineers.  
There is a risk of electric shock or injury.
- Contact your Yaskawa representative for help with failures, repairs, or part replacement.

Item	Inspection Period	Basic Inspection and Maintenance Procedure	Remarks
Check the coupling between the Servomotor and the machine.	Before starting operation	<ul style="list-style-type: none"> <li>• Make sure that there are no loose mounting screws between the Servomotor and machine.</li> <li>• Make sure that there is no looseness in the coupling between the Servomotor and machine.</li> <li>• Make sure that there is no misalignment.</li> </ul>	–
Check for vibration and noise.	Daily	Inspect by touching and by listening.	There should be no more vibration or noise than normal.
Exterior	Check for dirt and grime.	Clean off the dirt and grime with a cloth or pressurized air.	–
Measure the insulation resistance.	At least once a year	Disconnect the Servomotor from the SERVOPACK and measure the insulation resistance at 500 V with an insulation resistance meter. (Measurement method: Measure the resistance between phase U, V, or W on the Servomotor's power line and FG.) The insulation is normal if the resistance is 10 MΩ or higher.	If the resistance is less than 10 MΩ, contact your Yaskawa representative.
Replace the oil seal.	At least once every 5,000 hours	Contact your Yaskawa representative.	This inspection applies only to Servomotors with Oil Seals.
Overhaul	At least once every 5 years or every 20,000 hours	Contact your Yaskawa representative.	–

## 8.2 Service Lives of Parts

The following table gives the standard service lives of the parts of the Servomotor. Contact your Yaskawa representative using the following table as a guide. After an examination of the part in question, we will determine whether the part should be replaced. Even if the service life of a part has not expired, replacement may be required if abnormalities occur. The standard service lives in the table are only for reference. The actual service lives will depend on the application conditions and environment.

Part	Standard Service Life	Remarks
Bearing	20,000 hours	The service life is affected by operating conditions. Check for abnormal sounds and vibration during inspections.
Oil Seal	5,000 hours	The service life is affected by operating conditions. Check for oil leaks during inspections.
Holding Brake	20,000 hours	The service life is affected by operating conditions. Check for abnormal sounds and vibration during inspections. Confirm that the brake is released when power is supplied and check for any changes in the operating time of the brake.

## 8.3 Disposing of Servomotors

When disposing of a Servomotor, treat it as ordinary industrial waste. However, local ordinances and national laws must be observed. Implement all labeling and warnings as a final product as required.

# Appendices

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# 9

The appendices provide additional information on Servomotors with Gears and reference information on selecting Servomotor capacity.

## **9.1 Terminology and Data for Servomotors with Gears . . . 9-2**

- 9.1.1 Terminology for Servomotors with Low-backlash Gears . . . . . 9-2
- 9.1.2 Noise Data . . . . . 9-2
- 9.1.3 Efficiency . . . . . 9-3

## **9.2 Reference Information for Servomotor Capacity Selection . . . . 9-4**

- 9.2.1 Formulas Required to Select the Servomotor Capacity . . . . . 9-4
- 9.2.2  $GD^2$  for Simple Diagrams . . . . . 9-5
- 9.2.3 Conversions between Engineering Units and SI Units . . . . . 9-6
- 9.2.4 Application Examples by Type of Application . . . 9-7

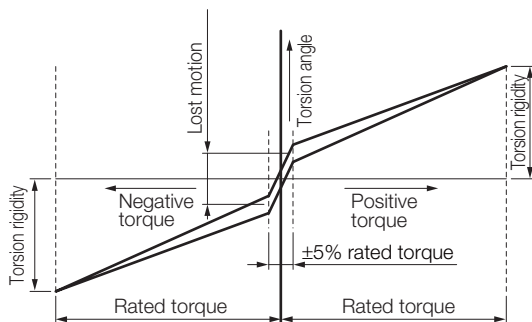


# 9.1 Terminology and Data for Servomotors with Gears

## 9.1.1 Terminology for Servomotors with Low-backlash Gears

Item	Measurement Method and Definition	Typical Value for Low-Backlash Gear
Rated Torque (N·m)	The rated output torque of the Servomotor is the input torque to the gear. The rated torque is this value multiplied by the inverse of the gear ratio and efficiency.	-
Lost Motion (arc-min)	The difference in the torsion angle with a $\pm 5\%$ rated torque load (maximum value at any four positions during output).	3 max.
Torsion Rigidity (arc-min)	Higher torsion angle value on one side with a $\pm$ rated torque load.	10 max.
Angle Transmission Deviation Accuracy (arc-min)	The difference between the absolute accuracy and the accuracy for one rotation under no-load conditions during output.	6 max.

Refer to the following graph for lost motion and torsion rigidity.

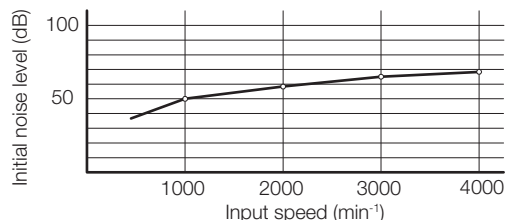


## 9.1.2 Noise Data

The following noise data for Servomotors with Gears is only for reference. The data may vary slightly depending on the capacity and gear ratio of the Servomotor.

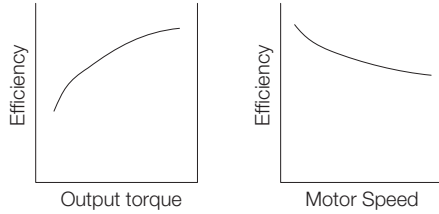
Measurement Conditions

- Scale A: 50 cm
- Ground noise: 28 dB



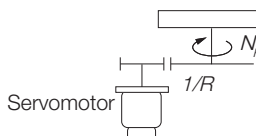
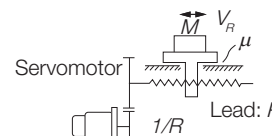
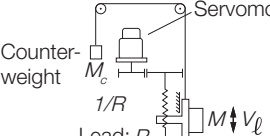
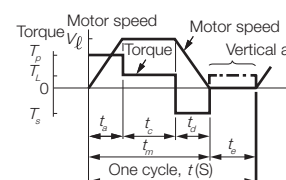
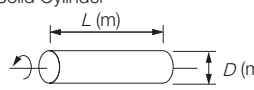
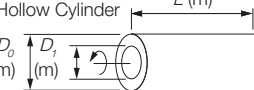
## 9.1.3 Efficiency

The output torque and motor speed produce the following trends in efficiency. The values in the tables of ratings and specifications for Servomotors with Gears are given at the rated motor torque and rated motor speed.



# 9.2 Reference Information for Servomotor Capacity Selection

## 9.2.1 Formulas Required to Select the Servomotor Capacity

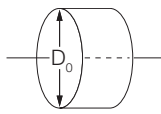
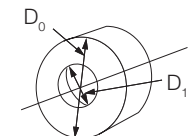
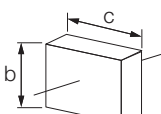
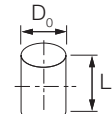
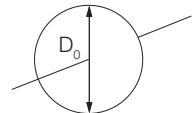
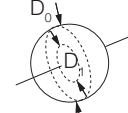
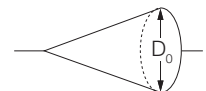
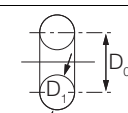
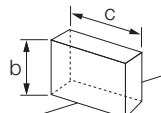
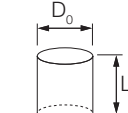
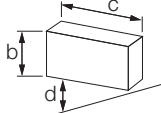
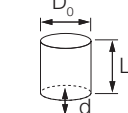
Type of Motion	Rotary Motion	Linear Motion	
		Horizontal Axis	Vertical Axis
Machine Configuration			
	$N_l$ : Load shaft speed ( $\text{min}^{-1}$ ) $V_l$ : Load speed ( $\text{m}/\text{min}$ ) $T_l$ : Load torque calculated at load shaft ( $\text{N}\cdot\text{m}$ ) $\mu$ : Friction coefficient	$P_B$ : Ball screw lead (m) $M$ : Linear motion section mass (kg) $M_c$ : Counterweight mass (kg)	$1/R$ : Gear ratio $\eta$ : Mechanical efficiency $T_{PM}$ : Servomotor instantaneous maximum torque ( $\text{N}\cdot\text{m}$ )
Speed Diagram			
Travel distance (m)	$R = \frac{V_l}{60} \cdot \frac{t_a + 2t_c + t_d}{2} \quad \left( t_a = \text{If...}t_d, R... = \frac{V_l}{60} (t_m - t_a) \right)$		
Load Shaft Speed ( $\text{min}^{-1}$ )	$N_l$	$N_l = \frac{V_l}{P_B}$	
Motor Shaft Speed ( $\text{min}^{-1}$ )	$N_M = N_l \cdot R$		
Load Torque Calculated at Motor Shaft ( $\text{N}\cdot\text{m}$ )	$T_L = \frac{T_l}{R \cdot \eta}$	$T_L = \frac{9.8 \times \mu \cdot M \cdot P_B}{2\pi \cdot R \cdot \eta}$	$T_L = \frac{9.8 \times (M - M_c) P_B}{2\pi \cdot R \cdot \eta}$
Load Moment of Inertia Calculated at Motor Shaft ( $\text{kg}\cdot\text{m}^2$ )	$J_L = J_{L1} + J_{L2} + J_{L3}$		
Linear Motion Section	-	$J_{L1} = M \cdot \left( \frac{P_B}{2\pi R} \right)^2$	$J_{L1} = (M + M_c) \cdot \left( \frac{P_B}{2\pi R} \right)^2$
Rotary Motion Section	<ul style="list-style-type: none"> <li>Solid Cylinder                              </li> <li>Hollow Cylinder                              </li> </ul>	$J_k = \frac{1}{8} M_k \cdot D^2$ OR $J_k = \frac{\pi}{32} \rho \cdot L \cdot D^4$ $M_k$ : Solid cylinder mass (kg) $\rho$ : Density ( $\text{kg}/\text{m}^3$ )...Iron $\rho = 7.87 \times 10^3$ ( $\text{kg}/\text{m}^3$ ) ...Aluminum $\rho = 2.70 \times 10^3$ ( $\text{kg}/\text{m}^3$ )	$J_k = \frac{1}{8} M_k (D_o^2 + D_i^2)$ OR $J_k = \frac{\pi}{32} \rho \cdot L (D_o^4 - D_i^4)$
	Moment of Inertia of Rotary Motion Section Calculated at Motor Shaft Rotary motion section at gear input shaft $J_{L2} = J_k$ Rotary motion section at gear output shaft $J_{L3} = \frac{J_k}{R^2}$		
Minimum Starting Time (s)	$t_{am} = \frac{2\pi \cdot N_M (J_M + J_L)}{60 (T_{PM} - T_L)}$		

Continued on next page.

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Type of Motion	Rotary Motion	Linear Motion	
		Horizontal Axis	Vertical Axis
Minimum Braking Time (s)		$t_{dm} = \frac{2\pi \cdot N_M (J_M + J_L)}{60 (T_{PM} + T_L)}$	
Load Moving Power (W)		$P_o = \frac{2\pi \cdot N_M \cdot T_L}{60}$	
Load Acceleration Power (W)		$P_a = \left(\frac{2\pi \cdot N_M}{60}\right)^2 \frac{J_L}{t_a}$	$(t_a \geq t_{am})$
Required Starting Torque (N·m)		$T_p = \frac{2\pi \cdot N_M (J_M + J_L)}{60 \times t_a} + T_L$	$(t_a \geq t_{am})$
Required Braking Torque (N·m)		$T_s = \frac{2\pi \cdot N_M (J_M + J_L)}{60 \times t_d} - T_L$	$(t_d \geq t_{dm})$
Effective Torque Value (N·m)		$T_{rms} = \sqrt{\frac{T_p^2 \cdot t_a + T_L^2 \cdot t_c + T_s^2 \cdot t_d}{t}}$	$T_{rms} = \sqrt{\frac{T_p^2 \cdot t_a + T_L^2 (t_c + t_d) + T_s^2 \cdot t_d}{t}}$

## 9.2.2 GD<sup>2</sup> for Simple Diagrams

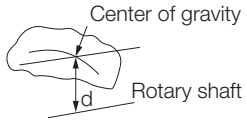
When Rotary Shaft Is Aligned with Center Line of Cylinder	Solid cylinder ( $D^2 = D_o^2/2$ )  (OR $GD^2 = 125\pi \rho L D^4$ $\rho$ : Density (g/cm <sup>3</sup> )...Copper: 7.866 $L$ : Length (m) $D$ : Diameter (m))		Hollow cylinder $D^2 = (D_o^2 + D_i^2)/2$  (OR $GD^2 = 125\pi \rho L (D_o^4 + D_i^4)$ $\rho$ : Density (g/cm <sup>3</sup> ) $L$ : Length (m) $D_o, D_i$ : Diameter (m))	
	Rectangular solid $D^2 = (b^2 + c^2)/3$		Cylindrical body $D^2 = L^2/3 + D_o^2/4$	
When Rotary Shaft Runs Through Gravitational Center	Sphere $D^2 = \frac{2}{5} D_o^2$		Hollow sphere $D^2 = \frac{2}{5} \cdot \frac{D_o^5 - D_i^3}{D_o^3 - D_i^3}$	
	Cone $D^2 = \frac{3}{10} D_o^2$		Wheel $D^2 = D_o^2 + \frac{3}{4} D_i^2$	
When Rotary Shaft Is on One End	Rectangular solid $D^2 = (4b^2 + C^2)/3$		Cylindrical body $D^2 = \frac{4}{3} L^2 + \frac{D_o^2}{4}$	
When Rotary Shaft Is Outside Rotating Body	Rectangular solid $D^2 = \frac{4b^2 + C^2}{3} + 4(bd + d^2)$		Cylindrical body $D^2 = \frac{4}{3} L^2 + \frac{D_o^2}{4} + 4(dL + d^2)$	

Continued on next page.

9.2 Reference Information for Servomotor Capacity Selection

9.2.3 Conversions between Engineering Units and SI Units

Continued from previous page.

<p>General Formula When Rotary Shaft Is outside Rotating Body</p>	<p>General formula for diameter of rotation when rotary shaft is outside rotating body</p> $D_2^2 = D_1^2 + 4 d^2$ <p><math>D_1</math> : Diameter of rotation when shaft that is parallel to rotary shaft and runs through center of gravity virtually operates as a rotary shaft</p>	
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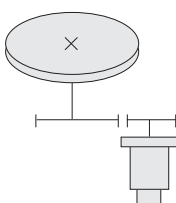
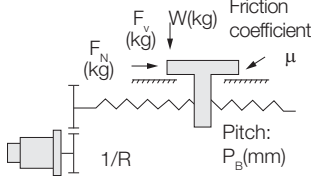
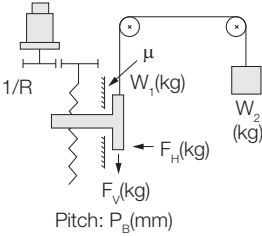
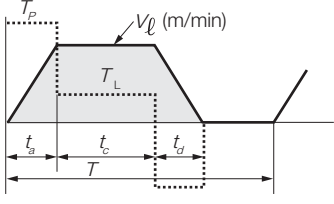
**Information**  $GD^2 = \text{Weight} \times (\text{Diameter of rotation})^2$

## 9.2.3 Conversions between Engineering Units and SI Units

The following table provides the conversion rates between engineering units and SI units for typical physical quantities required for capacity selection.

Quantity	Engineering Unit	SI Unit	Conversion Factor
Force or load	kgf	N	1 kgf = 9.80665 N
Weight	kgf	-	The numerical values are the same for mass in the traditional unit and the SI unit. (The mass SI unit Wkg is used for objects in the Wkgf traditional unit.)
Mass	kgf·s <sup>2</sup> /m	kg	
Torque	kgf·m	N·m	1 kgf·m = 9.80665 N·m
Inertia (moment of inertia)	gf·cm·s <sup>2</sup>	kg·m <sup>2</sup>	1 gf·cm·s <sup>2</sup> = 0.980665 × 10 <sup>-4</sup> kg·m <sup>2</sup>
GD <sup>2</sup>	kgf·m <sup>2</sup>	kg·m <sup>2</sup>	Relationship between GD <sup>2</sup> (kgf·m <sup>2</sup> ) and moment of inertia $J$ (kg·m <sup>2</sup> ) $J = \frac{GD^2}{4}$

## 9.2.4 Application Examples by Type of Application

Machine Configuration		Rotating Body	Horizontal Ball Screw	Vertical Ball Screw
				
Load Speed, $N_\ell$ ( $\text{min}^{-1}$ )		$N_\ell$	Load speed (m/min) $\frac{1000 \times V_\ell}{P_B}$	Load speed (m/min) $\frac{1000 \times V_\ell}{P_B}$
Speed Calculated at Motor Shaft, $N_M$ ( $\text{min}^{-1}$ )		$R \times N_\ell$	$R \times N_\ell$	$R \times N_\ell$
Linear Motion Section, $GD_2$ ( $\text{kg} \cdot \text{m}^2$ )	$GD^2_\ell$ Calculated at Load Shaft	-	$W \cdot \left(\frac{P_B}{1000\pi}\right)^2$	$W \cdot \left(\frac{P_B}{1000\pi}\right)^2$ [However, $W=W_1 + W_2$ ]
	$GD^2_L$ Calculated at Motor Shaft	$GD^2_L \times \left(\frac{1}{R}\right)^2$	$GD^2_L \times \left(\frac{1}{R}\right)^2$ [OR $W \cdot \left(\frac{V_\ell}{\pi \cdot N_M}\right)^2$ ]	$GD^2_L \times \left(\frac{1}{R}\right)^2$ [OR $W \cdot \left(\frac{V_\ell}{\pi \cdot N_M}\right)^2$ ] [However, $W=W_1 + W_2$ ]
Load Torque ( $\text{kg} \cdot \text{m}$ )	$T_\ell$ Calculated at Load Shaft	$T_\ell$	$\{\mu \cdot (W + F_v) + F_H\} \cdot \frac{P_B}{2000\pi}$	$\{\mu \cdot F_H + W_1 - W_2 + F_v\} \cdot \frac{P_B}{2000\pi}$
	$T_L$ Calculated at Motor Shaft	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ Mechanical efficiency	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ ← Mechanical efficiency [OR $\frac{\{\mu \cdot (W + F_v) + F_H\} \cdot V_\ell}{2\pi \cdot N_M \cdot \eta}$ ]	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ ← Mechanical efficiency [OR $\frac{\{\mu \cdot F_H + W_1 - W_2 + F_v\} \cdot V_\ell}{2\pi \cdot N_M \cdot \eta}$ ]
Load Moving Power, $P_O$ (kW)		$\frac{T_\ell \cdot N_\ell}{973 \times \eta}$	$\frac{\{\mu \cdot (W + F_v) + F_H\} \cdot V_\ell}{6120 \times \eta}$	$\frac{\{\mu \cdot F_H + W_1 - W_2 + F_v\} \cdot V_\ell}{6120 \times \eta}$
Load Acceleration Power		$\frac{GD^2_\ell \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ Acceleration time (s)	$\frac{GD^2_\ell \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ Acceleration time (s)	$\frac{GD^2_\ell \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ Acceleration time (s)
Starting Torque, $T_P$ ( $\text{kg} \cdot \text{m}$ ) Deceleration Torque, $T_S$ ( $\text{kg} \cdot \text{m}$ ) Effective Torque Value, $T_{rms}$ ( $\text{kg} \cdot \text{m}$ )			$T_P = \frac{(GD^2_M + GD^2_L) \cdot N_M}{375 \cdot t_a} + T_L$ $T_S = \frac{(GD^2_M + GD^2_L) \cdot N_M}{375 \cdot t_d} - T_L$ $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot t_c + T_S^2 \cdot t_d}{T}}$ <p>[When a load torque is applied while stopped for a vertical ball screw:</p> $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot (T - t_a - t_d) + T_S^2 \cdot t_d}{T}}$	
System Remarks		-	<ul style="list-style-type: none"> <li>The gear backlash is a problem.</li> <li>Effective for applications for which increasing system speed is not required.</li> <li>A large torque can be generated by a small motor.</li> </ul>	<ul style="list-style-type: none"> <li>Falling when <math>W_1 \neq W_2</math></li> <li>Brake timing</li> </ul>

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9.2 Reference Information for Servomotor Capacity Selection

9.2.4 Application Examples by Type of Application

Continued from previous page.

Machine Configuration		Roll Feeder	Rack and Pinion
Load Speed, $N_\ell$ ( $\text{min}^{-1}$ )	$\frac{1000 \times V_\ell}{P_B}$ <p>[However, <math>P_B = \pi \cdot d_p</math>]</p>	$\frac{1000 \times V_\ell}{P_B}$ <p>[However, <math>P_B = \pi \cdot d_p</math> OR <math>P_B = Z_p \cdot L_p</math>]</p>	
Speed Calculated at Motor Shaft, $N_M$ ( $\text{min}^{-1}$ )	$R \times N_\ell$	$R \times N_\ell$	
Linear Motion Section, $GD_2$ ( $\text{kg} \cdot \text{m}^2$ )	$GD_\ell^2$ Calculated at Load Shaft	$W \cdot \left(\frac{d_p}{1000}\right)^2$	$W \cdot \left(\frac{d_p}{1000}\right)^2$
	$GD_L^2$ Calculated at Motor Shaft	$GD_L^2 \times \left(\frac{1}{R}\right)^2$ [OR $W \cdot \left(\frac{V_\ell}{\pi \cdot N_M}\right)^2$ ]	$GD_L^2 \times \left(\frac{1}{R}\right)^2$ [OR $W \cdot \left(\frac{V_\ell}{\pi \cdot N_M}\right)^2$ ]
Load Torque ( $\text{kg} \cdot \text{m}$ )	$T_\ell$ Calculated at Load Shaft	$(F_t + \mu_1 W + \mu_2 N) \cdot \frac{d_p}{2000}$	$\{\mu \cdot (W + F_v) + F_h\} \cdot \frac{d_p}{2000}$
	$T_L$ Calculated at Motor Shaft	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ ← Mechanical efficiency [OR $\frac{(F_t + \mu_1 W + \mu_2 N) \cdot V_\ell}{2\pi \cdot N_M \cdot \eta}$ ]	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ ← Mechanical efficiency [OR $\frac{\{\mu \cdot (W + F_v) + F_h\} \cdot V_\ell}{2\pi \cdot N_M \cdot \eta}$ ]
Load Moving Power, $P_O$ (kW)	$\frac{(F_t + \mu_1 W + \mu_2 N) \cdot V_\ell}{6120 \times \eta}$	$\frac{\{\mu \cdot (W + F_v) + F_h\} \cdot V_\ell}{6120 \times \eta}$	
Load Acceleration Power	$\frac{GD_\ell^2 \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ ← Acceleration time (s)	$\frac{GD_\ell^2 \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ ← Acceleration time (s)	
Starting Torque, $T_P$ ( $\text{kg} \cdot \text{m}$ ) Deceleration Torque, $T_S$ ( $\text{kg} \cdot \text{m}$ ) Effective Torque Value, $T_{rms}$ ( $\text{kg} \cdot \text{m}$ )		$T_P = \frac{(GD_M^2 + GD_L^2) \cdot N_M}{375 \cdot t_a} + T_L$ $T_S = \frac{(GD_M^2 + GD_L^2) \cdot N_M}{375 \cdot t_d} - T_L$ $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot t_c + T_S^2 \cdot t_d}{T}}$ <p>[When a load torque is applied while stopped for a vertical ball screw:]</p> $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot (T - t_a - t_d) + T_S^2 \cdot t_d}{T}}$	
System Remarks	<ul style="list-style-type: none"> <li>Feeding of coiled and sheet materials</li> <li>Roller slipping affects accuracy.</li> <li>A measuring roller pulse generator may also be installed separately.</li> </ul>	<ul style="list-style-type: none"> <li>Can be used for positioning with long travel distances.</li> <li>A separate pulse generator is often installed.</li> </ul>	

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Machine Configuration		Chains and Timing Belts	Dollies
Load Speed, $N_\ell$ ( $\text{min}^{-1}$ )	$\frac{1000 \times V_\ell}{P_B}$ Load speed (m/min) [ However, $P_B = \pi \cdot d_p$ ] [ OR $P_B = Z_p \cdot L_p$ ]		$\frac{1000 \times V_\ell}{P_B}$ Load speed (m/min) [However, $P_B = \pi \cdot d_p$ ]
	$R \times N_\ell$		$R \times N_\ell$
Linear Motion Section, $GD_2$ ( $\text{kg} \cdot \text{m}^2$ )	$W \cdot \left( \frac{d_p}{1000} \right)^2$		$W \cdot \left( \frac{d_p}{1000} \right)^2$
	$GD_L^2 \times \left( \frac{1}{R} \right)^2$ [OR $W \cdot \left( \frac{V_\ell}{\pi \cdot N_M} \right)^2$ ]		$GD_L^2 \times \left( \frac{1}{R} \right)^2$ [OR $W \cdot \left( \frac{V_\ell}{\pi \cdot N_M} \right)^2$ ]
Load Torque ( $\text{kg} \cdot \text{m}$ )	$\{ \mu \cdot (W + F_v) + F_H \} \cdot \frac{d_p}{2000}$		$C \cdot W \cdot \frac{d_p}{2 \times 10^6}$
	$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ Mechanical efficiency [OR $\frac{\{ \mu \cdot (W + F_v) + F_H \} \cdot V_\ell}{2\pi \cdot N_M \cdot \eta}$ ]		$T_\ell \times \frac{1}{R} \times \frac{1}{\eta}$ Mechanical efficiency [OR $\frac{C \cdot W \cdot V_\ell}{2 \times 10^3 \times \pi \times N_M \cdot \eta}$ ]
Load Moving Power, $P_O$ (kW)		$\frac{\{ \mu \cdot (W + F_v) + F_H \} \cdot V_\ell}{6120 \times \eta}$	$\frac{C \cdot W \cdot V_\ell}{6120 \times 10^3 \times \eta}$
Load Acceleration Power		$\frac{GD^2 \ell \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ Acceleration time (s)	$\frac{GD^2 \ell \cdot N_\ell^2}{365 \times 10^3 \times t_a}$ Acceleration time (s)
Starting Torque, $T_P$ ( $\text{kg} \cdot \text{m}$ ) Deceleration Torque, $T_S$ ( $\text{kg} \cdot \text{m}$ ) Effective Torque Value, $T_{rms}$ ( $\text{kg} \cdot \text{m}$ )			$T_P = \frac{(GD_M^2 + GD_L^2) \cdot N_M}{375 \cdot t_a} + T_L$ $T_S = \frac{(GD_M^2 + GD_L^2) \cdot N_M}{375 \cdot t_d} - T_L$ $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot t_c + T_S^2 \cdot t_d}{T}}$ (When a load torque is applied while stopped for a vertical ball screw: $T_{rms} = \sqrt{\frac{T_P^2 \cdot t_a + T_L^2 \cdot (T - t_a - t_d) + T_S^2 \cdot t_d}{T}}$
System Remarks		<ul style="list-style-type: none"> <li>Positioning of conveyors</li> <li>Chain looseness, movement, and pitch error are problems (not suitable for frequent use).</li> <li>Radial load for overtightened belt chains</li> </ul>	<ul style="list-style-type: none"> <li>Dolly slipping</li> </ul>



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The revision dates and numbers of the revised manuals are given on the bottom of the back cover.

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# Σ-7-Series AC Servo Drive Rotary Servomotor Product Manual

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