Rotary type / Sensor specification

CE compliance Limitless rotation

■ Ordering method

RF04

N: Standard
H: High rigidity
N: Standard torque
H: High torque

314

378

Cable length N

S2 PN: PNF GW: No I/O board

SH

Standard model

9.7

3: With batt (Absolute) N: None (Incremental)

Controller Operation method

I/O point trace /

Remote command

Note 1. The robot cable is flexible and resists bending.

Note 2. See P.498 for DIN rail mounting bracket.

Note 3. Select this selection when using the gateway function. For details, see P.60.

Basic specifications Motor 42 Step motor Resolution (Pulse/rotation) Repeatability Note 1 (°) +/-0.05 **Drive method** Special warm gear + belt Torque type Standard High torque Maximum speed Note 2 (°/sec) 420 280 Rotating torque (N•m) 6.6 10 Max. pushing torque (N•m) 3.3 5 Backlash (°) +/-0.5 Max. moment of inertia Note 3 (kg·m²) 0.04 0.1 Cable length (m) Standard: 1 / Option: 3, 5, 10

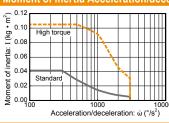
Note 1. Positioning repeatability in one direction.

Rotation range (°)

Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/ deceleration" graph and the "Effective torque vs. speed" graph (reference).

Note 3. For moment of inertia and effective torque details, see P.604.

Moment of inertia Acceleration/deceleration





Allowable load (a) 🕴 👃 (b) Allowable moment (N•m) Allowable radial load (N) (a)

398

517

TS-S2S TS-SHS

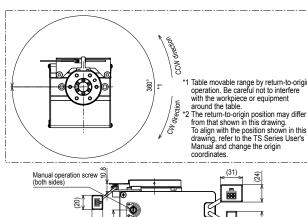
12.0

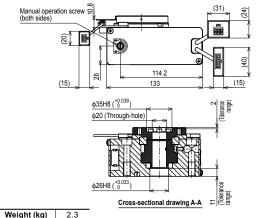
Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective

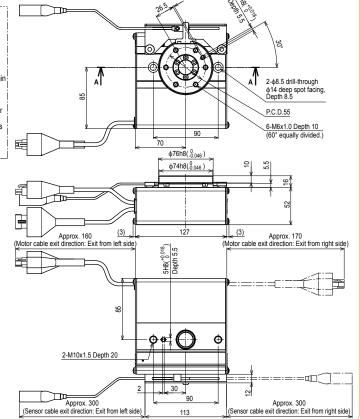
296

For details, please refer to the TRANSERVO Series User's Manual.

RF04-SN Sensor specification - Standard model







Note 1. This drawing is output under the conditions below

Bearing Standard Standard
Torque Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.

