



● CE compliance ● Rotation range : 320°

Ordering method

RF04	N			L			S2	
Model	Return-to-origin method N: Stroke end (Limit rotation)	Bearing N: Standard H: High rigidity	Torque N: Standard torque H: High torque	Cable entry location L: From the left	Rotation direction N: CCW Z: CW	Cable length ^{Note 1} 1L: 1m 3L: 3m 5L: 5m 10L: 10m	Controller S2: TS-S2	I/O selection NP: NPN PN: PNP CC: CC-Link DN: DeviceNet EP: EtherNet/IP

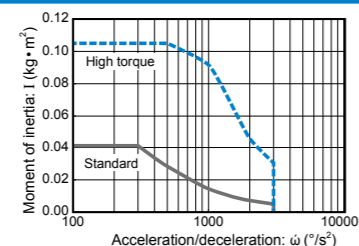
Note 1. The robot cable is flexible and resists bending.

Basic specifications

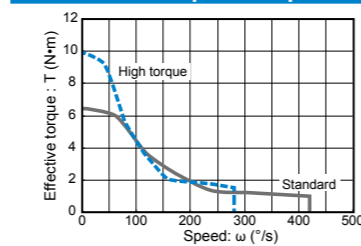
Motor	42 □ Step motor
Resolution (Pulse/rotation)	20480
Repeatability ^{Note 1} (°)	+/-0.05
Drive method	Special worm gear + belt
Torque type	Standard High torque
Maximum speed ^{Note 2} (°/sec)	420 280
Rotating torque (N·m)	6.6 10
Max. pushing torque (N·m)	3.3 5
Backlash (°)	+/-0.5
Max. moment of inertia ^{Note 3} (kg·m ²)	0.04 0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10
Rotation range (°)	320

Note 1. Positioning repeatability in one direction.
 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.???

Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load

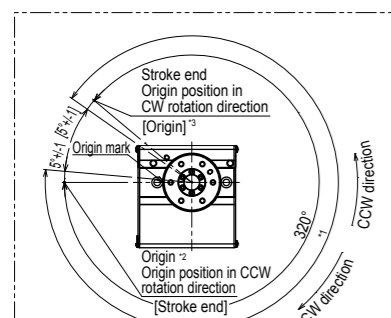
Allowable radial load (N)	Allowable thrust load (N)				Allowable moment (N·m)	
	(a)	(b)	(a)	(b)	Standard model	High rigidity model
Standard model	314	378	296	398	9.7	12.0
High rigidity model				517		

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs. For details, please refer to the TRANSERVO Series User's Manual.

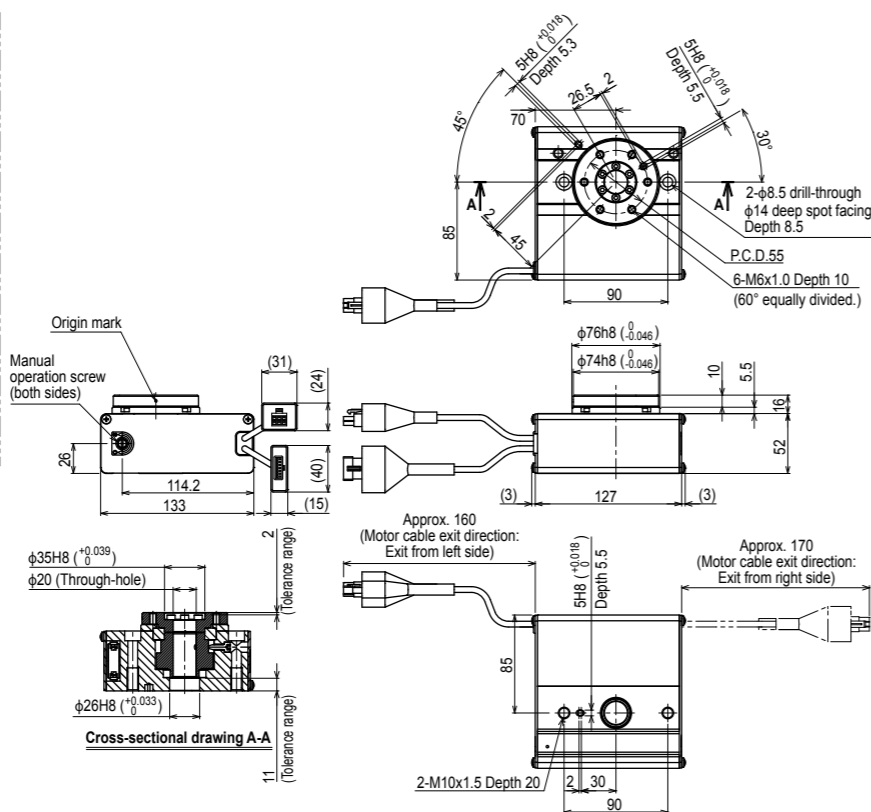
Controller

Controller	Operation method
TS-S2	I/O point trace / Remote command

RF04-NN Limit rotation specification – Standard model



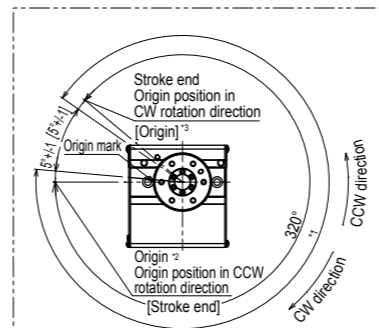
*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
 *2 Return-to-origin position
 *3 Values and characters in [] show those when the return-to-origin direction is changed.



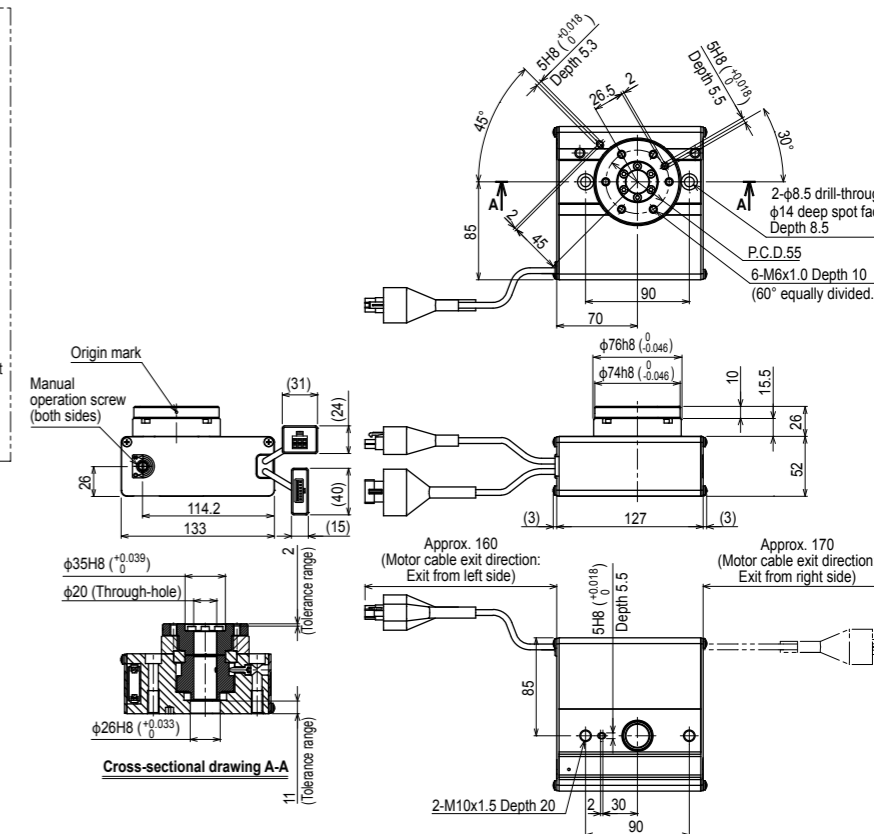
Weight (kg) 2.2

Note1. This drawing is output under the conditions below.
 Bearing Standard
 Torque Standard/High torque
 Note2. The minimum bending radius of the motor cable is R30.

RF04-NH Limit rotation specification – High rigidity model



*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
 *2 Return-to-origin position
 *3 Values and characters in [] show those when the return-to-origin direction is changed.



Weight (kg) 2.4

Note1. This drawing is output under the conditions below.
 Bearing High rigidity
 Torque Standard/High torque
 Note2. The minimum bending radius of the motor cable is R30.

● CE compliance ● Limitless rotation

Ordering method

RF04	S						S2	S	
Model	Return-to-origin method S: Sensor (Limitless rotation)	Bearing N: Standard H: High rigidity	Torque N: Standard torque H: High torque	Cable entry location R: From the right L: From the left	Rotation direction N: CCW Z: CW	Cable length ^{Note 1} 1L: 1m 3L: 3m 5L: 5m 10L: 10m	Controller S2: TS-S2	Type S: Sensor	I/O selection NP: NPN PN: PNP CC: CC-Link DN: DeviceNet EP: EtherNet/IP

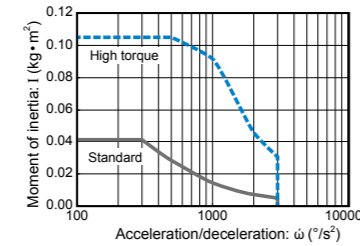
Note 1. The robot cable is flexible and resists bending.

Basic specifications

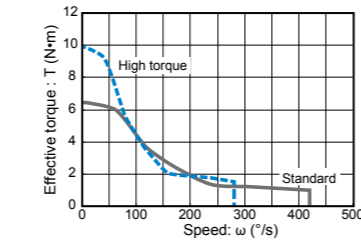
Motor	42 □ Step motor
Resolution (Pulse/rotation)	20480
Repeatability ^{Note 1} (°)	+/-0.05
Drive method	Special worm gear + belt
Torque type	Standard High torque
Maximum speed ^{Note 2} (°/sec)	420 280
Rotating torque (N·m)	6.6 10
Max. pushing torque (N·m)	3.3 5
Backlash (°)	+/-0.5
Max. moment of inertia ^{Note 3} (kg·m ²)	0.04 0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10
Rotation range (°)	360

Note 1. Positioning repeatability in one direction.
 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.???

Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load

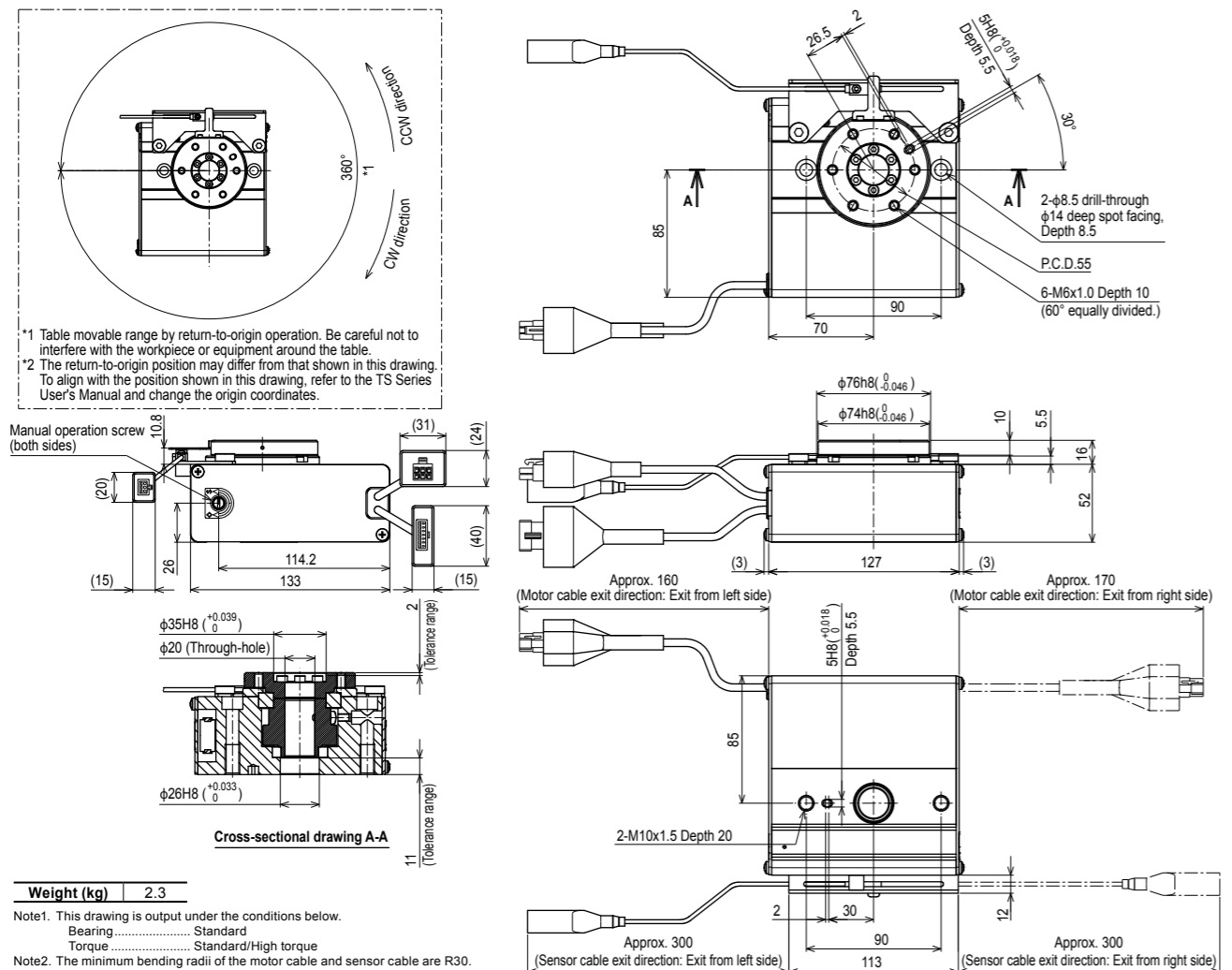
Allowable radial load (N)	Allowable thrust load (N)				Allowable moment (N·m)	
	(a)		(b)		Standard model	High rigidity model
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	
314	378	296	398	517	9.7	12.0

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs. For details, please refer to the TRANSERVO Series User's Manual.

Controller

Controller	Operation method
TS-S2S	I/O point trace / Remote command

RF04-SN Sensor specification – Standard model



RF04-SH Sensor specification – High rigidity model

