

RF02-S

Rotary type / Sensor specification



- CE compliance
- Limitless rotation

Ordering method

RF02-S-L

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length
S	S: Sensor (Limitless rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	L: From the left	N: CCW Z: CW	Note 1 1K: 1m 3K: 3m 5K: 5m 10K: 10m

Robot positioner	I/O
S2S: TS-S2S	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board

Robot positioner	I/O	Battery
SHS: TS-SHS	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board	B: With battery (Absolute) N: None (Incremental)

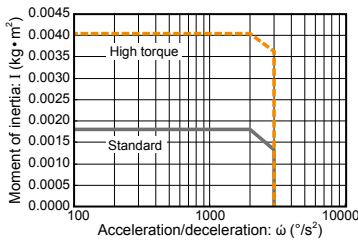
Note 1. The robot cable is flexible and resists bending.
 Note 2. See P.634 for DIN rail mounting bracket.
 Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

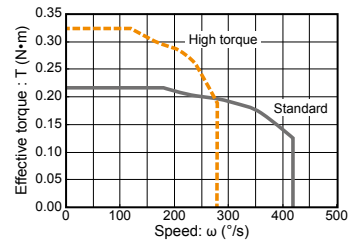
Motor	20 □ Step motor
Resolution (Pulse/rotation)	4096
Repeatability Note 1 (°)	+/-0.05
Drive method	Special warm gear + belt
Torque type	Standard High torque
Maximum speed Note 2 (°/sec)	420 280
Rotating torque (N•m)	0.22 0.32
Max. pushing torque (N•m)	0.11 0.16
Backlash (°)	+/-0.5
Max. moment of inertia Note 3 (kg•m ²)	0.0018 0.004
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.744.

Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load

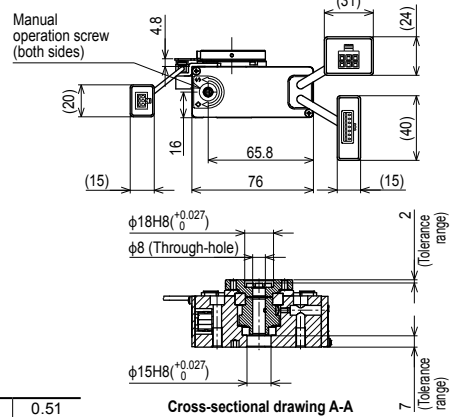
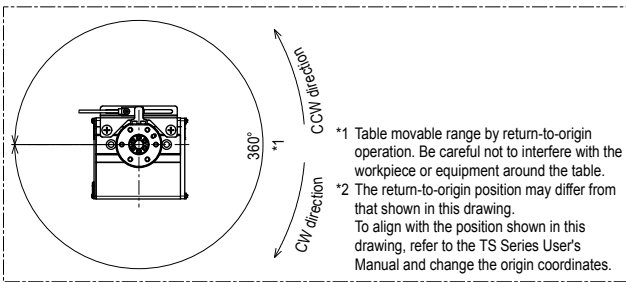
Standard model	High rigidity model	Allowable radial load (N)		Allowable thrust load (N)		Allowable moment (N•m)	
		(a)	(b)	(a)	(b)	Standard model	High rigidity model
78	86	74	78	107	2.4	2.9	

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.

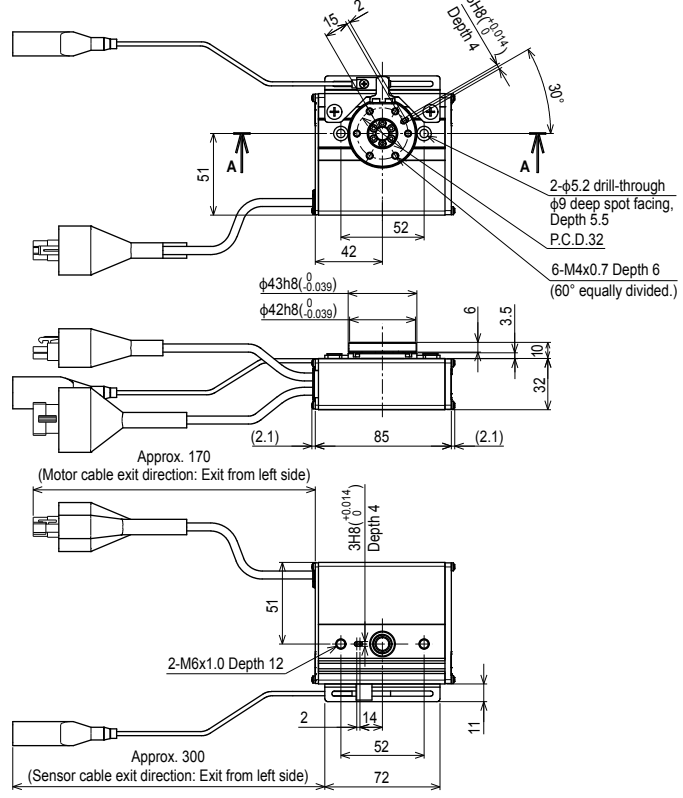
Controller

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

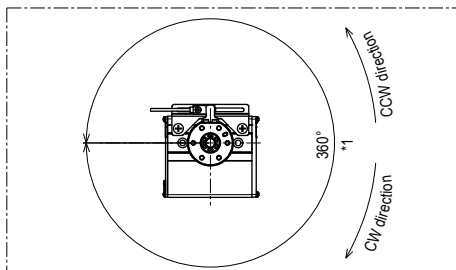
RF02-SN Sensor specification – Standard model



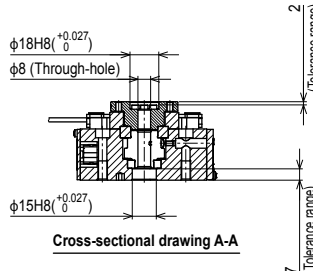
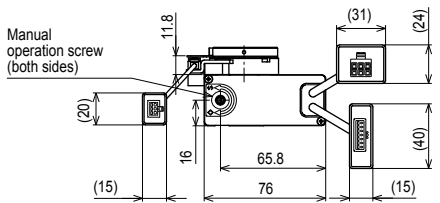
Weight (kg) 0.51
 Cross-sectional drawing A-A
 Note 1. This drawing is output under the conditions below.
 Bearing Standard
 Torque Standard/High torque
 Note 2. The minimum bending radii of the motor cable and sensor cable are R30.
 Note 3. The motor cable exit direction is only the left side.



RF02-SH Sensor 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 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.



Weight (kg)	0.55
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Note 1. This drawing is output under the conditions below.
 Bearing..... High rigidity
 Torque..... Standard/High torque
 Note 2. The minimum bending radii of the motor cable and sensor cable are R30.
 Note 3. The motor cable exit direction is only the left side.

