RF02-S \hspace{2cm} Rotary type / Sensor specification

### Ordering method

#### RF02

- **Model**
  - RF02
  - L
  - S

#### S2

- **Robot positioner**
  - Standard
  - High-rigidity
  - High torque
  - Standard

#### SH

- **Robot positioner**
  - TS-S2

### Basic specifications

- **Motor**
  - 20 [Step motor]

- **Resolution (Pulse/rotation)**
  - 4096

- **Repeatability**
  - +/- 0.05°

- **Drive method**
  - Special warm gear + belt

- **Torque type**
  - Standard
  - High torque

- **Maximum speed**
  - 420°/sec

- **Rotating torque**
  - 0.22 N•m

- **Max. pushing torque**
  - 0.32 N•m

- **Backlash**
  - +/- 0.5°

- **Max. moment of inertia**
  - 0.0015 kg•m²

- **Cable length (m)**
  - Standard: 1
  - Option: 3, 5, 10

### Moment of inertia Acceleration/deceleration

#### Effective torque vs. speed

### Allowable load

#### Cross-sectional drawing A-A

#### RF02-SN Sensor specification – Standard model

**Note 1.** The robot cable is flexible and resists bending.
**Note 2.** The maximum speed may vary depending on the "Moment of inertia vs. Acceleration/Deceleration" graph and the "Effective torque vs. speed" graph (reference).
**Note 3.** Select this selection when using the gateway function. For details, see P.60.

**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.604.

**Note 1.** This drawing is output under the conditions below.
**Note 2.** The minimum bending radii of the motor cable and sensor cable are R30.
**Note 3.** For details, please refer to the TRANSERVO Series User’s Manual.

**Controller**

- **Controller**
  - TS-S2
  - TS-SHS

**Operation method**

- I/O point trace / Remote command
RF02-S  Sensor specification – High rigidity model

1. Table movable range by return-to-origin operation. Be careful not to interfere with the workplace 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

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.

Controller TS-S2 > 490 TS-SH > 490