RF03-N
Rotary type / Limit rotation specification

Ordering method

Motor
- Resolution (Pulse/rotation): 40/0.06
- Repeatability (°): ±0.05
- Drive method: Special warm gear + belt
- Torque type: Standard (High torque)
- Maximum speed (°/sec): 420 / 280
- Rotating torque (Nm): 0.8 / 1.2
- Max. pushing torque (Nm): 0.4 / 0.6
- Max. moment of inertia (kgm): 0.012 / 0.027
- Cable length (m): 320

Ordering method

Model:
- RF03-N
- Return-to-origin method: Return to origin at end (Limit rotation)
- Bearing: Standard / High rigidity
- Torque: Standard / High torque
- Cable entry location: From the left
- Rotation direction: CW
- Cable length: 1.2m

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
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Effective torque vs. speed

- Acceleration/deceleration:
  - Standard
  - High torque

Effective torque vs. speed

- Effective torque vs. speed graph

Allowable load

- Allowable radial load (N):
  - Standard: 1 / Option: 3, 5, 10
- Allowable thrust load (N): 0.4 / 0.6
- Allowable moment (Nm): 0.010 / 0.015
- Allowable radial load (N):
  - Standard: 1 / Option: 3, 5, 10
- Allowable thrust load (N): 0.4 / 0.6
- Allowable moment (Nm): 0.010 / 0.015

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.

RF03-NN
Limit rotation specification - Standard model

- Stroke end
- Origin position in CW rotation direction
- Origin position in CCW rotation direction
- CCW direction
- Origin mark
- Manual operation screw (both sides)
- 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 radius of the motor cable is R30.

Controller

- Operation method:
  - TS-S2: I/O point trace / Remote command
  - TS-SH: Pulse train control
  - TS-SD: Pulse train control

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.
RF03-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.

Note 1. This drawing is output under the conditions below.
   Bearing: High rigidity
   Torque: Standard/High torque

Note 2. The minimum bending radius of the motor cable is R30.