RF04-S  Rotary type / Sensor specification

■ Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>RF04</th>
<th>S</th>
</tr>
</thead>
<tbody>
<tr>
<td>Return-to-origin method</td>
<td>Standard (sensible rotation)</td>
<td></td>
</tr>
<tr>
<td>Torque type</td>
<td>Standard/High torque</td>
<td></td>
</tr>
<tr>
<td>Robot positioner</td>
<td>SH</td>
<td></td>
</tr>
<tr>
<td>Robot positioner</td>
<td>S</td>
<td></td>
</tr>
<tr>
<td>Robot positioner</td>
<td>TF</td>
<td></td>
</tr>
<tr>
<td>Bearing</td>
<td>Standard</td>
<td></td>
</tr>
<tr>
<td>Torque</td>
<td>Standard/High torque</td>
<td></td>
</tr>
<tr>
<td>Cable entry location</td>
<td>From the left</td>
<td></td>
</tr>
<tr>
<td>Rotation direction</td>
<td>CW</td>
<td></td>
</tr>
<tr>
<td>Cable length (mm)</td>
<td>100</td>
<td></td>
</tr>
</tbody>
</table>

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
- Step motor
Resolution (Pulse/rotation)
- 42000
Repeatability (°)
- ±0.05
Drive method
- Special warm gear + belt
Torque type
- Standard/High torque
Maximum speed (°/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 (kg\*mm²)
- 0.4/0.1
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 when 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

![Graph of Acceleration/deceleration](image)

■ Effective torque vs. speed

![Graph of Effective torque vs. speed](image)

■ Allowable load

<table>
<thead>
<tr>
<th>Allowable radial load (N)</th>
<th>Allowable thrust load (N)</th>
<th>Allowable moment (N*m)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Standard model</td>
<td>378</td>
<td>226</td>
</tr>
<tr>
<td>High-rigidity model</td>
<td>378</td>
<td>308</td>
</tr>
</tbody>
</table>

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.

RF04-SN  Sensor specification – Standard model

![Sensor specification diagram](image)

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

Note 1. This drawing is output under the conditions below.
Bearing<br>Torque...Standard/High torque
Weight (kg) 2.3
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.
RF04-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.

Controller  TS-S2  490  TS-SH  490