

Nominal voltage: 24 V | Separate electrical configuration

Parameter	Unit	Value
Basic Parameters		
Motor type		Brushless torque servo motor
Voltage range	V	12~40
Peak torque	N.m	1.93
Rated torque	N.m	0.8
Peak current	A	16
Nominal current	A	3.1
Nominal voltage	V	24
Nominal power (source rating)	W	74.4
Outer diameter	mm	68 +/-0.1
Nominal speed	rpm	618
Body height	mm	31 +/-0.1
Motor weight	g	261
Motor Parameters		
Number of pole pairs	Pair	14
Phase resistance	Ohm	0.83
Phase inductance (source unit: Mh)	Mh	0.68
Torque constant	N.m/A	0.22
Speed constant	rpm/V	38.5
Control Parameters		
No-load maximum speed	rpm	924
Encoder type		Single-turn absolute
Control resolution	bit	14
Dynamic and Operating Parameters		
Rotor inertia	g*cm^2	672
Working temperature range	deg C	-20~80
Interface Parameters		
Communication interface		RS485 & CAN
Configuration interface		RS485
Supported modes (may vary with firmware version)		
Absolute position mode		Absolute target position control
Speed mode		Target speed and acceleration control
Current (torque) mode		Q-axis current control; torque estimated from current
Relative position mode		Relative displacement control
Status feedback		Position, speed, current and operating status

Nominal voltage: 36 V | Separate electrical configuration

Parameter	Unit	Value
Basic Parameters		
Motor type		Brushless torque servo motor
Voltage range	V	12~40
Peak torque	N.m	1.59
Rated torque	N.m	0.8
Peak current	A	2.7
Nominal current	A	1.3
Nominal voltage	V	36
Nominal power (source rating)	W	46.8
Outer diameter	mm	68 +/-0.1
Nominal speed	rpm	294
Body height	mm	31 +/-0.1
Motor weight	g	261
Motor Parameters		
Number of pole pairs	Pair	14
Phase resistance	Ohm	5.29
Phase inductance (source unit: Mh)	Mh	3.68
Torque constant	N.m/A	0.61
Speed constant	rpm/V	15.5
Control Parameters		
No-load maximum speed	rpm	564
Encoder type		Single-turn absolute
Control resolution	bit	14
Dynamic and Operating Parameters		
Rotor inertia	g*cm^2	672
Working temperature range	deg C	-20~80
Interface Parameters		
Communication interface		RS485 & CAN
Configuration interface		RS485
Supported modes (may vary with firmware version)		
Absolute position mode		Absolute target position control
Speed mode		Target speed and acceleration control
Current (torque) mode		Q-axis current control; torque estimated from current
Relative position mode		Relative displacement control
Status feedback		Position, speed, current and operating status