

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	5.17
Rated torque	N.m	1.1
Peak current	A	33.1
Nominal current	A	5.8
Nominal voltage	V	24
Nominal power (source rating)	W	139.2
Outer diameter	mm	89 +/-0.1
Nominal speed	rpm	954
Body height	mm	38 +/-0.1
Motor weight	g	534
Motor Parameters		
Number of pole pairs	Pair	21
Phase resistance	Ohm	0.33
Phase inductance (source unit: Mh)	Mh	0.23
Torque constant	N.m/A	0.19
Speed constant	rpm/V	47.8
Control Parameters		
No-load maximum speed	rpm	1146
Encoder type		Single-turn absolute
Control resolution	bit	14
Dynamic and Operating Parameters		
Rotor inertia	g*cm^2	2574
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	4.11
Rated torque	N.m	1.26
Peak current	A	6.6
Nominal current	A	2.1
Nominal voltage	V	36
Nominal power (source rating)	W	75.6
Outer diameter	mm	89 +/-0.1
Nominal speed	rpm	372
Body height	mm	38 +/-0.1
Motor weight	g	534
Motor Parameters		
Number of pole pairs	Pair	21
Phase resistance	Ohm	3.89
Phase inductance (source unit: Mh)	Mh	3.14
Torque constant	N.m/A	0.67
Speed constant	rpm/V	14.8
Control Parameters		
No-load maximum speed	rpm	534
Encoder type		Single-turn absolute
Control resolution	bit	14
Dynamic and Operating Parameters		
Rotor inertia	g*cm^2	2574
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