

# RF04-N

## Rotary type / Limit rotation specification



- CE compliance
- Rotation range : 320°

### Ordering method

**RF04** - **N** - [ ] - [ ] - [ ] - [ ] - [ ] - [ ] - [ ] - [ ] - [ ] - [ ]

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length	Robot positioner	I/O	Battery
	N: Stroke end (Limit rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	R: From the right L: From the left	N: CCW Z: CW	Note 1 1L: 1m 3L: 3m 5L: 5m 10L: 10m	S2: TS-S2 SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ GW: No I/O board	Note 4 B: With battery (Absolute) N: None (Incremental)

**SD** - **1**

Robot driver	I/O cable
SD: TS-SD	t: 1m

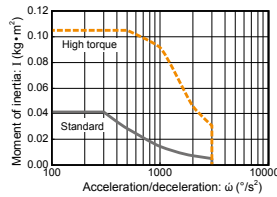
Note 1. The robot cable is flexible and resists bending.  
 Note 2. See P.446 for DIN rail mounting bracket.  
 Note 3. Select this selection when using the gateway function. For details, see P.439.  
 Note 4. Select whether or not the battery is provided only when using the TS-SH.

### Basic specifications

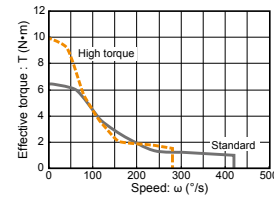
Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability Note 1 (°)	±0.05	
Drive method	Special worm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 (°/sec)	420	280
Rotating torque (N•m)	6.6	10
Max. pushing torque (N•m)	3.3	5
Backlash (°)	±0.5	
Max. moment of inertia Note 3 (kg•m <sup>2</sup> )	0.04	0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	320	

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.520.

### Moment of inertia Acceleration/deceleration



### Effective torque vs. speed



### Allowable load

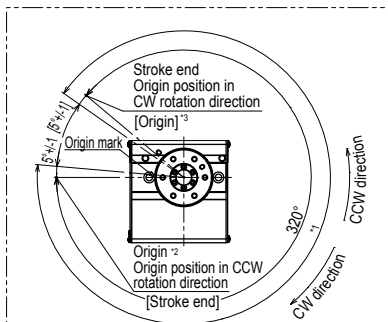
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
Standard model	High rigidity model	(a)		(b)		Standard model	High rigidity model
314	378	296	398	517	9.7	12.0	

### Controller

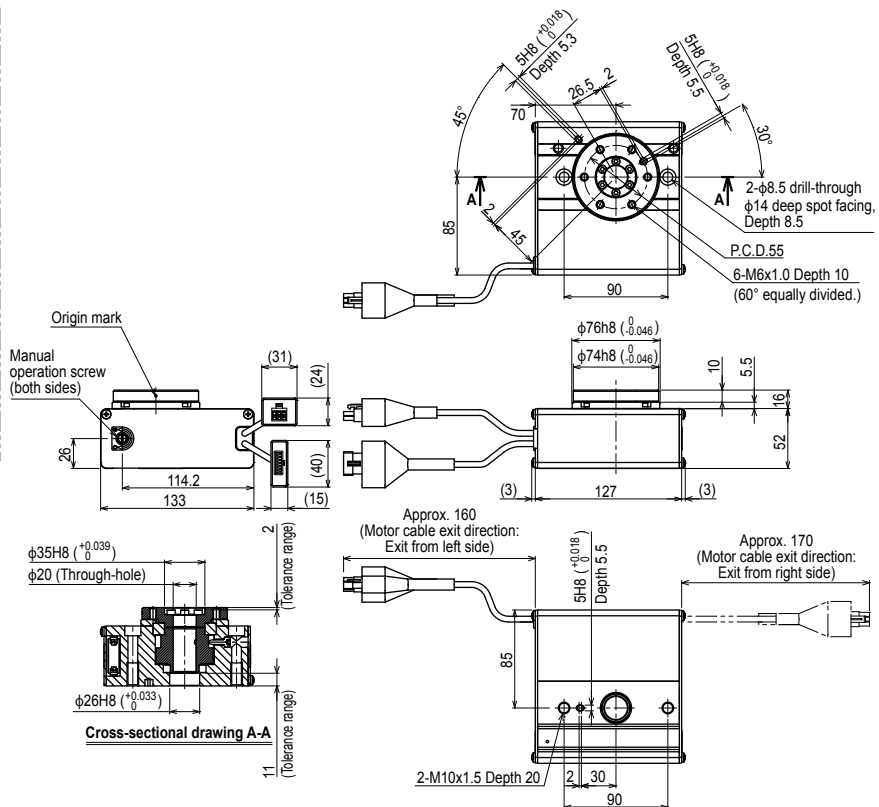
Controller	Operation method
TS-S2	I/O point trace / Remote command
TS-SH	Pulse train control

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 TRANSEURO Series User's Manual.

### RF04-NN Limit rotation specification – Standard model



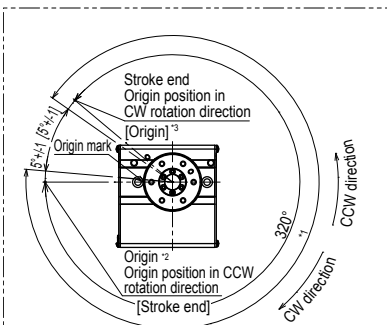
\*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.  
 \*2 Return-to-origin position  
 \*3 Values and characters in [ ] show those when the return-to-origin direction is changed.



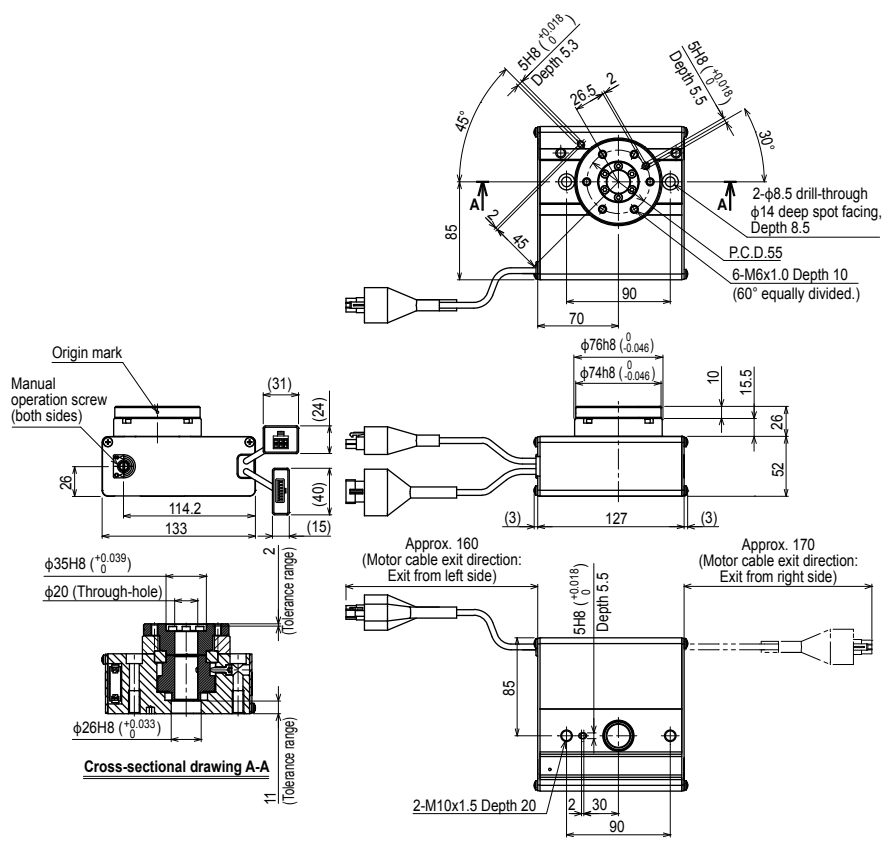
Weight (kg)	2.2
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Note1. This drawing is output under the conditions below.  
 Bearing..... Standard  
 Torque..... Standard/High torque  
 Note2. The minimum bending radius of the motor cable is R30.

RF04-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.



Weight (kg)	2.4
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Note1. This drawing is output under the conditions below.  
 Bearing..... High rigidity  
 Torque..... Standard/High torque  
 Note2. The minimum bending radius of the motor cable is R30.