

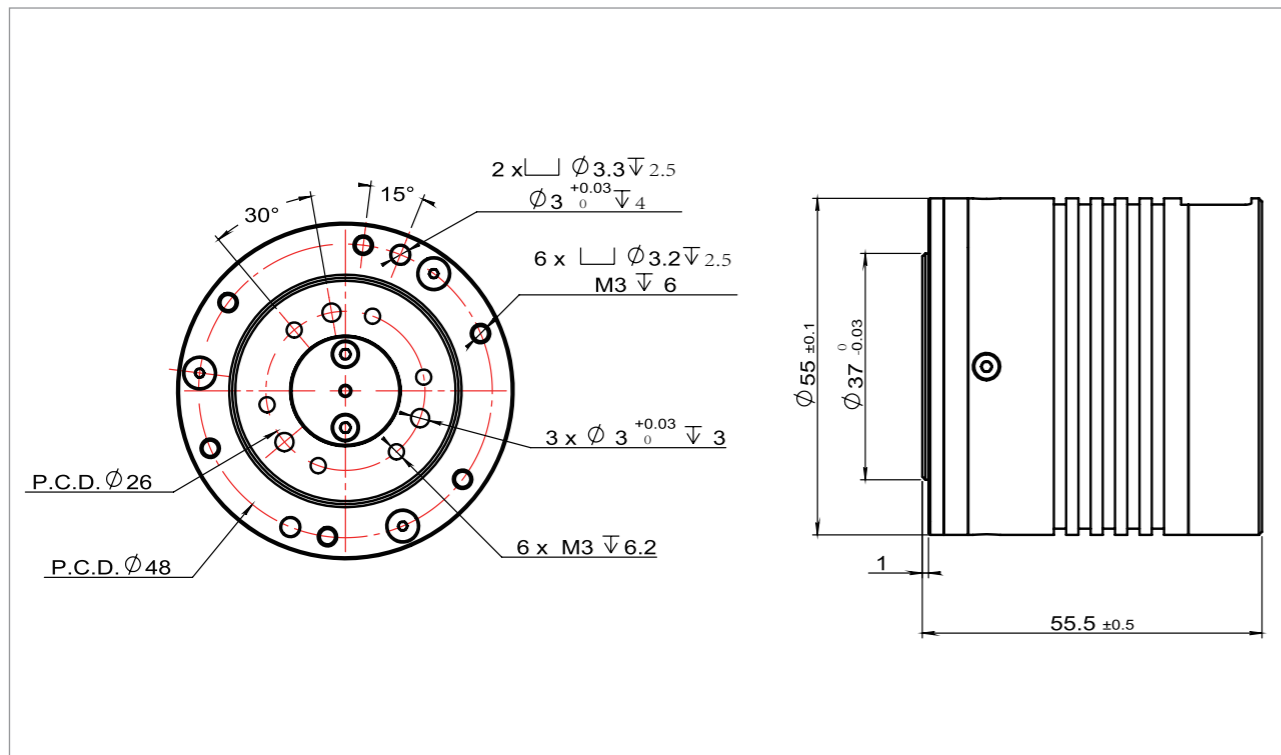
Series Name
RMD-X
Motor Simplified Name
X4-10



Dual encoder

Actuator Full Name	With Brake/Without Brake	Communication
RMD-X4-P12-10-E	N (without Brake)	EtherCAT & CAN BUS

Installation Drawing



Product Parameters

Parameters	Unit	X4-10	
Gear Ratio	—	12.5	
Input Voltage	V	24	
No Load Speed	RPM	317	
No-Load Input Current	A	1	
Rated Speed	RPM	238	
Rated Torque	N.m	4	
Rated Output Power	W	100	
Rated Phase Current	A(rms)	7.8	
Peak Torque	N.m	10	
Peak Phase Current	A(rms)	19.5	
Efficiency	%	69.5	
Motor Back-EMF Constant	Vdc/Krpm	6	
Module Torque Constant	N.m/A	0.8	
Motor Phase Resistance	Ω	0.32	
Motor Phase Inductance	mH	0.14	
Pole Pair	—	13	
3 Phase Connection	—	Y	
Back Drive Torque	N.m	0.8	
Backlash	Arcmin	≤15	
Output Bearing Type	—	Deep Groove Ball Bearings	
Axial Load	Tensile load	KN	1.2
	Compressive load	KN	1.2
Radial Load	KN	1.2	
Inertia	Kg.cm ²	0.25	
Encoder Type & Interface	—	Dual Encoder ABS-17BIT (Input) / 18BIT (Output)	
Control Accuracy	Degree	<0.01	
Communication	—	EtherCAT & CAN BUS	
Weight	Kg	0.33	
Insulation Grade	—	F	

Stall Torque Data

	Torque (N.m)	Temperature Rise (°C)	Stall Time (s)	Phase Current (Arms)
X4-10	5.2	41	10	7.8
	6	16	8	9.1
	7.2	26	5	11
	8	30	3	12.1