

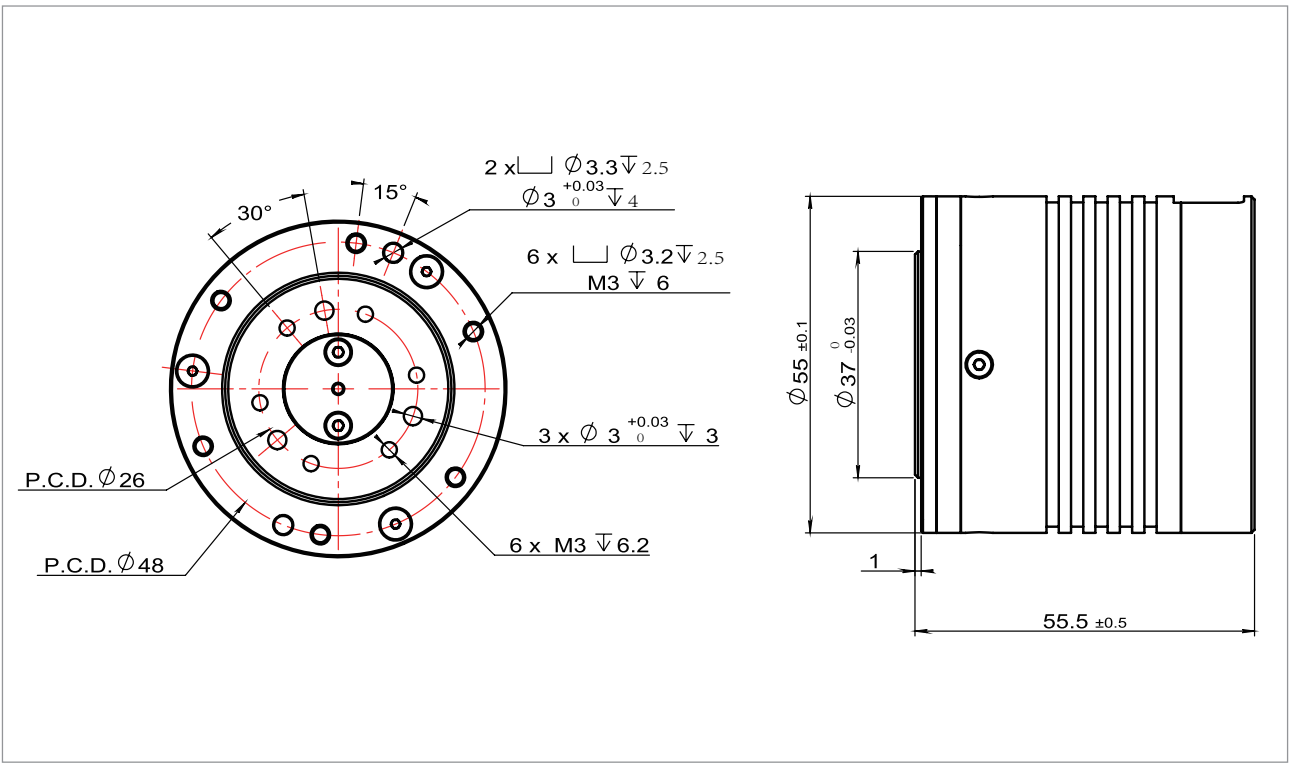
Series Name
RMD-X
Motor Simplified Name
X4-10



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
Voltage Range	V	20-55
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
Line Resistance	Ω	0.32
Line Inductance	mH	0.14
Pole Pairs	—	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
	Compressive load	KN
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

Note:

- The maximum operating voltage of the motor is 55V. It is recommended that customers add an external capacitor to regulate voltage, so as to ensure stable battery power supply and protect the PCB from damage caused by voltage fluctuations.
- If voltage exceeds the rated value, the operating speed must not exceed the motor's rated speed.

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