

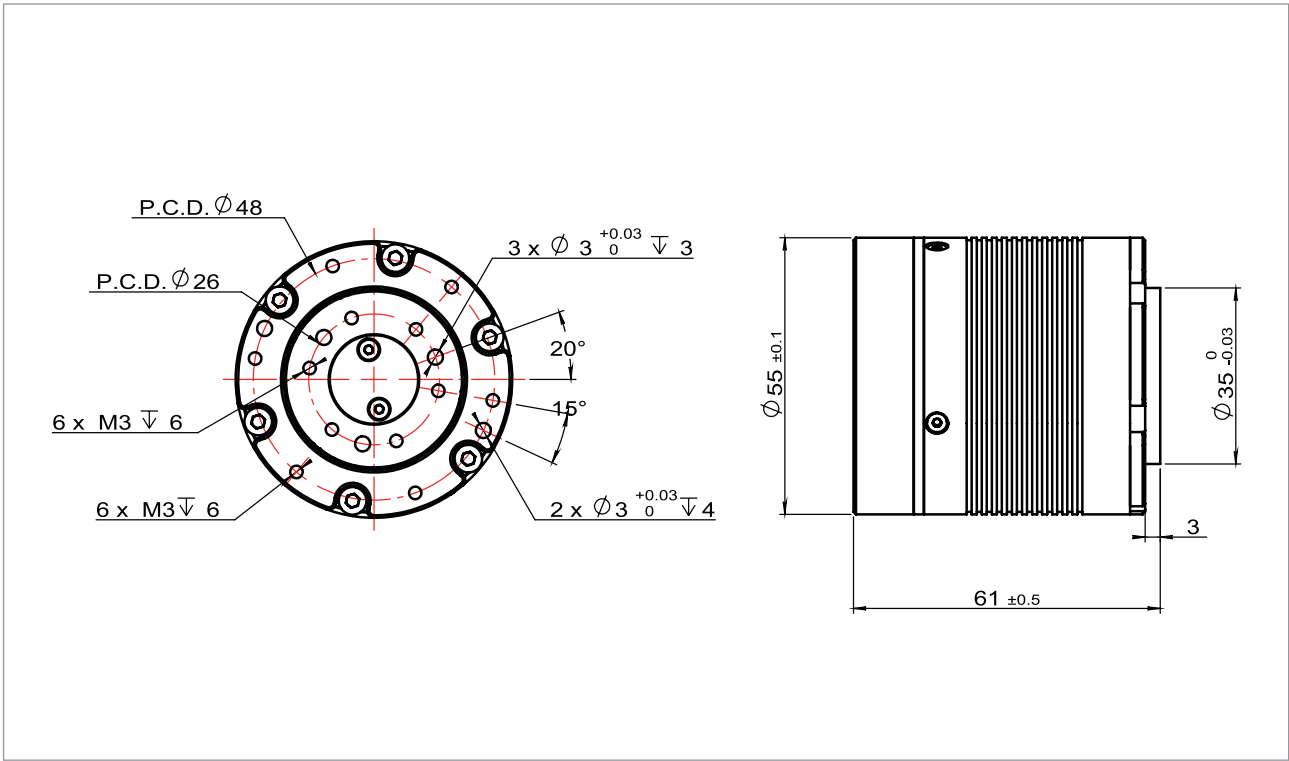
Series Name
RMD-X
Motor Simplified Name
X4-36



Dual encoder

Actuator Full Name	With Brake/Without Brake	Communication
RMD-X4-P36-36-E	N (without Brake)	EtherCAT & CAN BUS

Installation Drawing



Product Parameters

Parameters	Unit	X4-36
Gear Ratio	—	36
Input Voltage	V	24
No Load Speed	RPM	111
No-Load Input Current	A	0.9
Rated Speed	RPM	83
Rated Torque	N.m	10.5
Rated Output Power	W	100
Rated Phase Current	A(rms)	6.1
Peak Torque	N.m	34
Peak Phase Current	A(rms)	21.5
Efficiency	%	63.1
Motor Back-EMF Constant	Vdc/Krpm	6
Module Torque Constant	N.m/A	1.9
Motor Phase Resistance	Ω	0.39
Motor Phase Inductance	mH	0.07
Pole Pair	—	11
3 Phase Connection	—	Y
Back Drive Torque	N.m	1.14
Backlash	Arcmin	≤15
Output Bearing Type	—	Crossed Roller Bearings
Axial Load	Tensile load	KN
	Compressive load	KN
Radial Load	KN	1.5
Inertia	Kg.cm ²	0.3
Encoder Type & Interface	—	Dual Encoder ABS-17BIT (Input) / 18BIT (Output)
Control Accuracy	Degree	<0.01
Communication	—	EtherCAT & CAN BUS
Weight	Kg	0.36
Insulation Grade	—	F

Stall Torque Data

	Torque (N.m)	Temperature Rise (°C)	Stall Time (s)	Phase Current (Arms)
X4-36	17.25	30	15	9.2
	23	58	10	12.7
	28.75	41	5	16.3
	34.5	50	3	21.2