

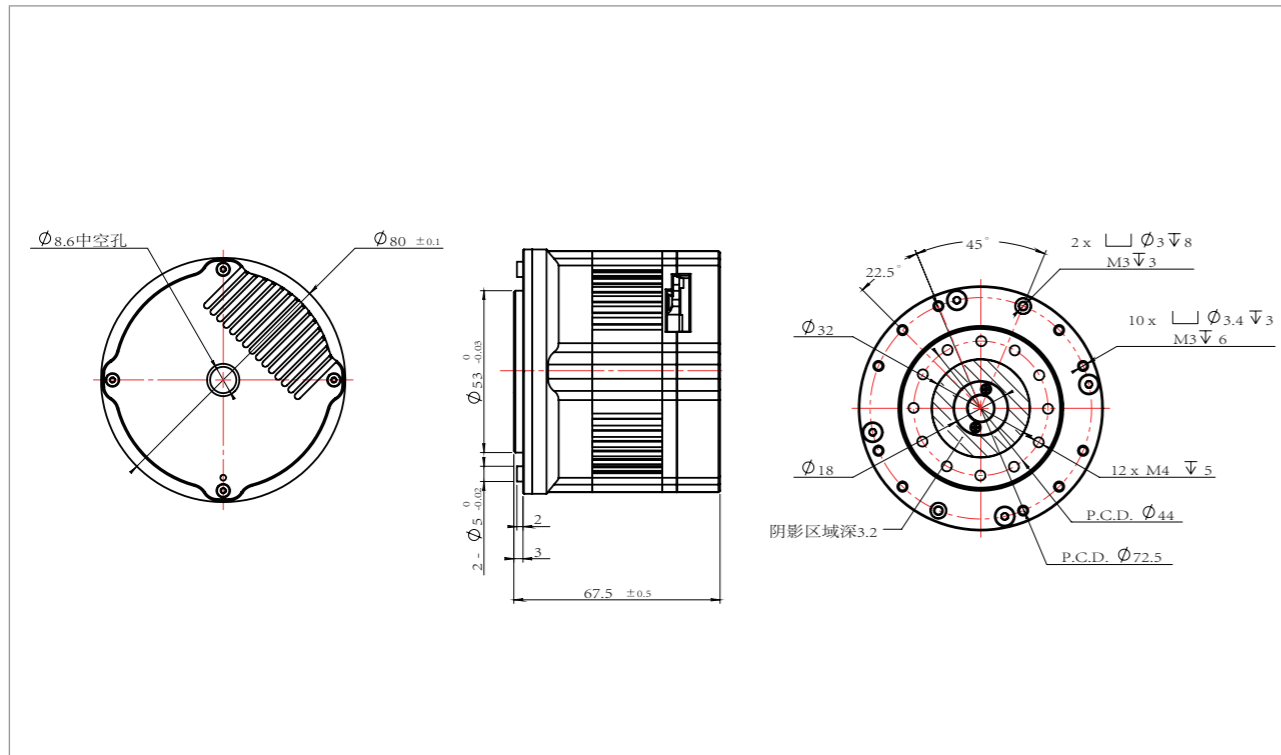
Series Name  
**RMD-X**  
Motor Simplified Name  
**X6-60**



Dual encoder

Actuator Full Name	With Brake/Without Brake	Communication
RMD-X6-P20-60-E	N (without Brake)	EtherCAT & CAN BUS

### Installation Drawing



### Product Parameters

Parameters	Unit	X6-60	
Gear Ratio	—	19.612	
Input Voltage	V	48	
No Load Speed	RPM	176	
No-Load Input Current	A	0.9	
Rated Speed	RPM	153	
Rated Torque	N.m	20	
Rated Output Power	W	320	
Rated Phase Current	A(rms)	9.5	
Peak Torque	N.m	60	
Peak Phase Current	A(rms)	29.1	
Efficiency	%	72.7	
Motor Back-EMF Constant	Vdc/Krpm	16	
Module Torque Constant	N.m/A	2.1	
Motor Phase Resistance	Ω	0.41	
Motor Phase Inductance	mH	0.51	
Pole Pair	—	10	
3 Phase Connection	—	Y	
Back Drive Torque	N.m	1.6	
Backlash	Arcmin	≤15	
Output Bearing Type	—	Crossed Roller Bearings	
Axial Load	Tensile load	KN	1.8
	Compressive load	KN	0.8
Radial Load	KN	2	
Inertia	Kg.cm <sup>2</sup>	0.66	
Encoder Type & Interface	—	Dual Encoder ABS-17BIT(Input) / 17BIT(Output)	
Control Accuracy	Degree	<0.01	
Communication	—	EtherCAT & CAN BUS	
Weight	Kg	0.82	
Insulation Grade	—	F	

### Stall Torque Data

	Torque (N.m)	Temperature Rise (°C)	Stall Time (s)	Phase Current (Arms)
X6-60	30	17	15	12.7
	40	29	10	17.7
	50	37	8	22.6
	60	24	5	28.3