

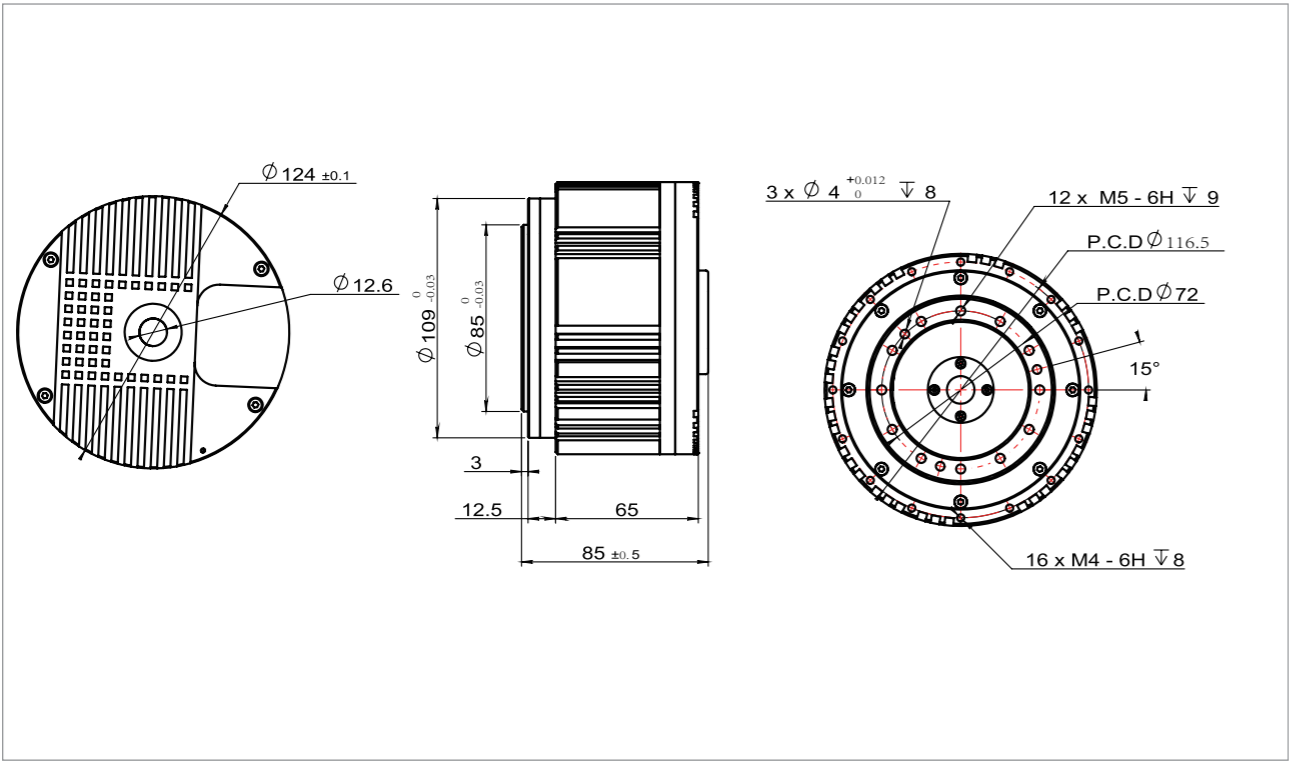
Series Name  
**RMD-X**  
Motor Simplified Name  
**X12-320**



Dual encoder

Actuator Full Name	With Brake/Without Brake	Communication
RMD-X12-P20-320-E	N (without Brake)	EtherCAT / CAN BUS

### Installation Drawing



### Product Parameters

Parameters	Unit	X12-320
Gear Ratio	—	20
Input Voltage	V	48
No Load Speed	RPM	125
No-Load Input Current	A	2.7
Rated Speed	RPM	100
Rated Torque	N.m	85
Rated Output Power	W	1000
Rated Phase Current	A(rms)	30
Peak Torque	N.m	320
Peak Phase Current	A(rms)	100
Efficiency	%	75
Motor Back-EMF Constant	Vdc/Krpm	17.9
Module Torque Constant	N.m/A	3.3
Motor Phase Resistance	Ω	0.12
Motor Phase Inductance	mH	0.05
Pole Pair	—	20
3 Phase Connection	—	Y
Back Drive Torque	N.m	3.8
Backlash	Arcmin	10
Output Bearing Type	—	Crossed Roller Bearings
Axial Load	Tensile load	KN
	Compressive load	KN
Radial Load	KN	5
Inertia	Kg.cm <sup>2</sup>	12.9
Encoder Type & Interface	—	Dual Encoder ABS-17BIT (Input) /17BIT (Output)
Control Accuracy	Degree	<0.01
Communication	—	485 / EtherCAT / CAN BUS
Weight	Kg	2.4
Insulation Grade	—	F

### Stall Torque Data

	Torque (N.m)	Temperature Rise (°C)	Stall Time (s)	Phase Current (Arms)
X12-320	150	13	10	37.5
	200	5	8	49.5
	250	7	7	61.5
	300	43	3	75.3