RF02-N

Rotary type / Limit rotation specification

CE compliance | Rotation range : 310°

Ordering method

RF02	N			L		
Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1
	N: Stroke end (Limit rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

Robot positioner	I/O
S2: TS-S2 Note2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SH

Robot positioner	I/O	Battery
SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3	B: With battery (Absolute) N: None (Incremental)

SD — **1**

Robot driver	I/O cable
SD: TS-SD	1: 1m

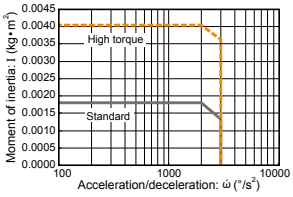
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

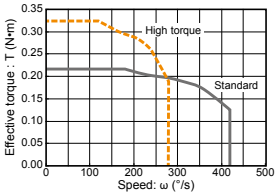
Motor	2 □ Step motor	
Resolution (Pulse/rotation)	4096	
Repeatability Note 1 (°)	±0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 (°/sec)	420	280
Rotating torque (N•m)	2.2	3.2
Max. pushing torque (N•m)	10	16
Backlash (°)	±0.5	
Max. moment of inertia Note 3 (kg•m²)	0.018	0.04
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	310	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

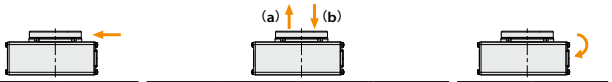
Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load



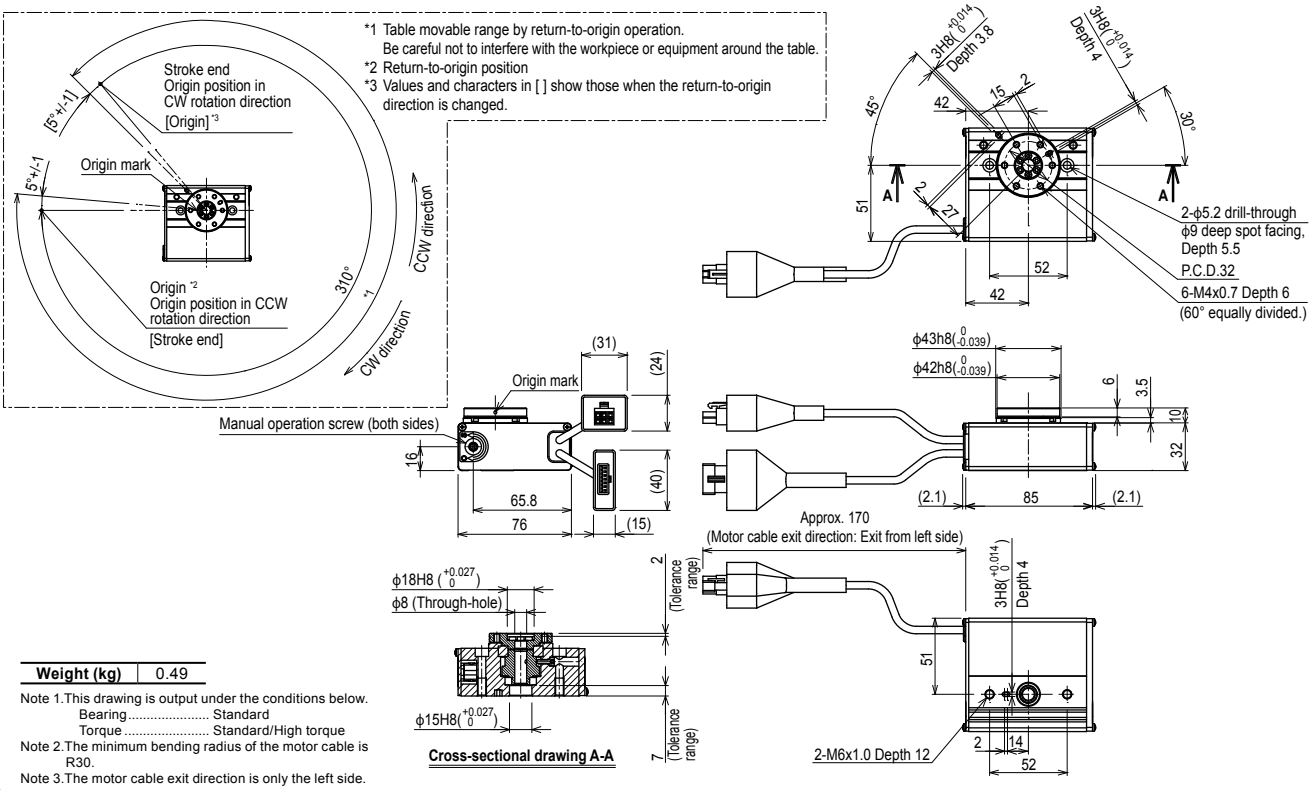
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
78	86	74		78	107	2.4	2.9

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

Controller

Controller	Operation method
TS-S2 TS-SH	I/O point trace / Remote command
TS-SD	Pulse train control

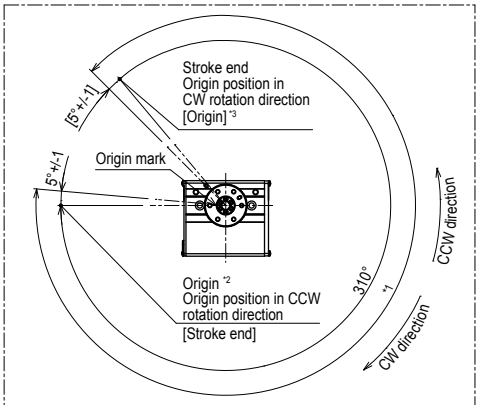
RF02-NN Limit rotation specification – Standard model



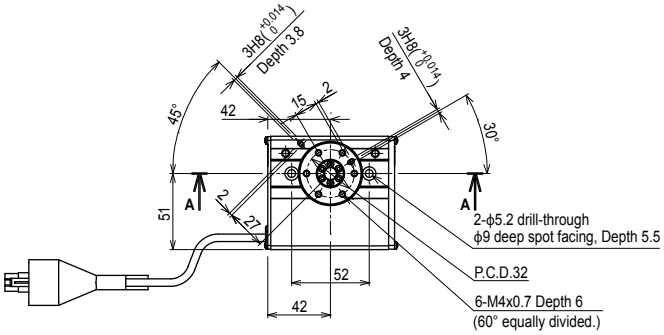
Weight (kg)	0.49

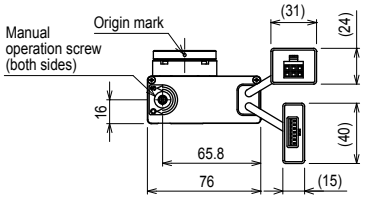
Note 1.This drawing is output under the conditions below.
Bearing..... Standard
Torque..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.
Note 3.The motor cable exit direction is only the left side.

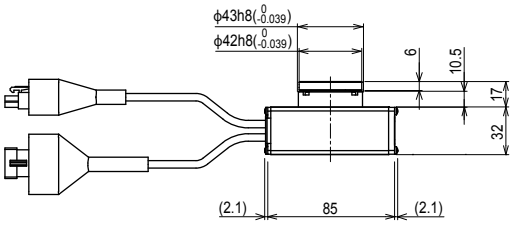
RF02-NH Limit rotation specification – High rigidity model

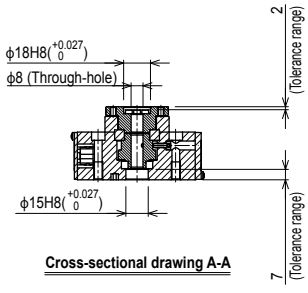


*1 Table movable range by return-to-origin operation.
Be careful not to interfere with the workpiece or equipment around the table.
*2 Return-to-origin position
*3 Values and characters in [ ] show those when the return-to-origin direction is changed.

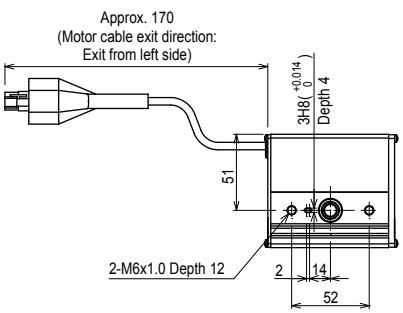








Cross-sectional drawing A-A



Weight (kg)	0.52

Note 1.This drawing is output under the conditions below.
Bearing..... High rigidity
Torque ..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.
Note 3.The motor cable exit direction is only the left side.

RF02-S

Rotary type / Sensor specification

CE compliance | Limitless rotation

Ordering method

RF02 – [S] – [ ] – [ ] – [L] – [ ] – [ ] – [ ]

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1
RF02	S: Sensor (Limitless rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2S

Robot positioner	I/O
S2S: TS-S2S Note 2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SHS

Robot positioner	I/O	Battery
SHS: TS-SHS	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3	B: With battery (Absolute) N: None (Incremental)

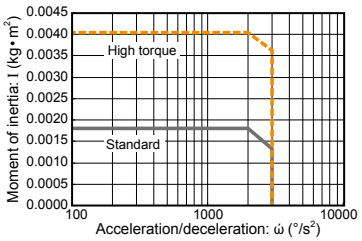
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

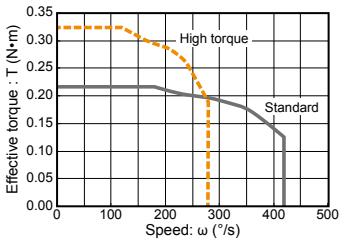
Motor	20 □ Step motor	
Resolution (Pulse/rotation)	4096	
Repeatability Note 1 (°)	+/-0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 (°/sec)	420	280
Rotating torque (N•m)	0.22	0.32
Max. pushing torque (N•m)	0.11	0.16
Backlash (°)	+/-0.5	
Max. moment of inertia Note 3 (kg•m²)	0.0018	0.004
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	360	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

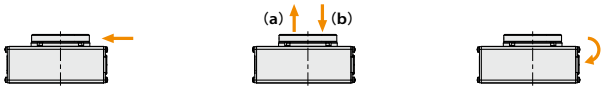
Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load



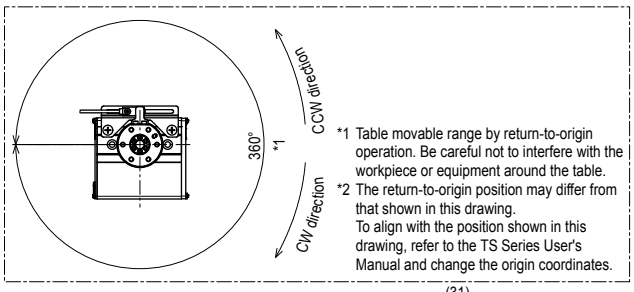
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
78	86	74		78	107	2.4	2.9

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

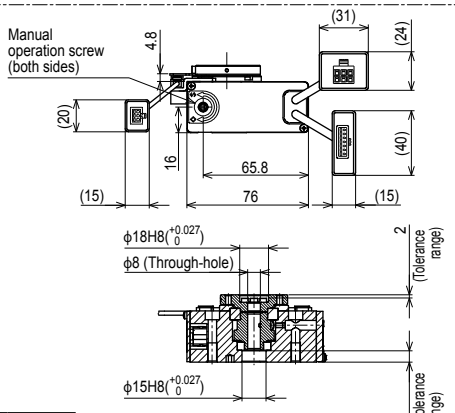
Controller

Controller	Operation method
TS-S2S	I/O point trace / Remote command
TS-SHS	

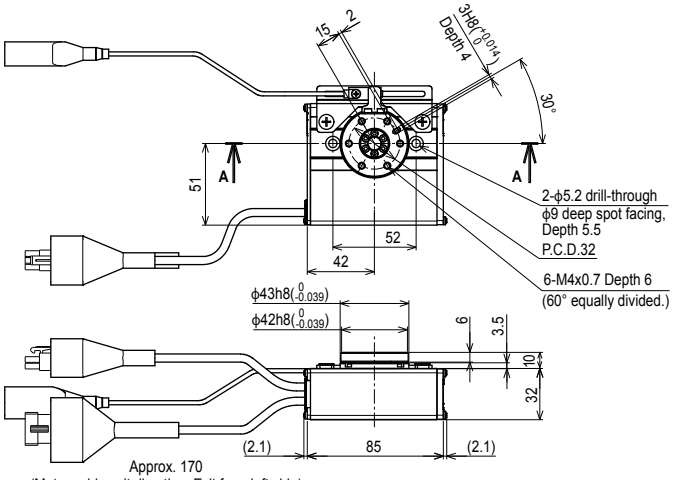
RF02-SN Sensor specification – Standard model

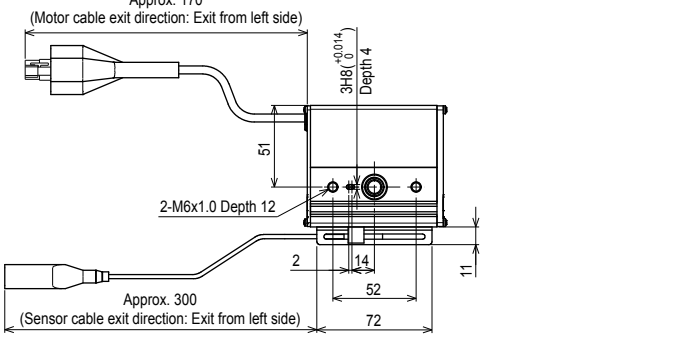


*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing.
To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.



Cross-sectional drawing A-A

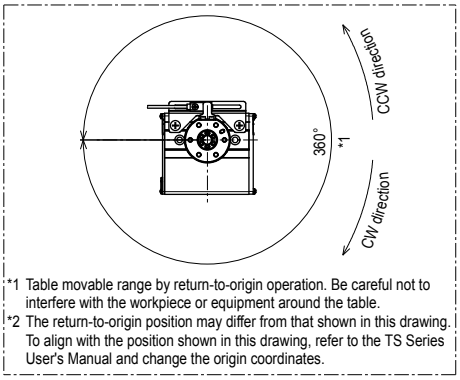




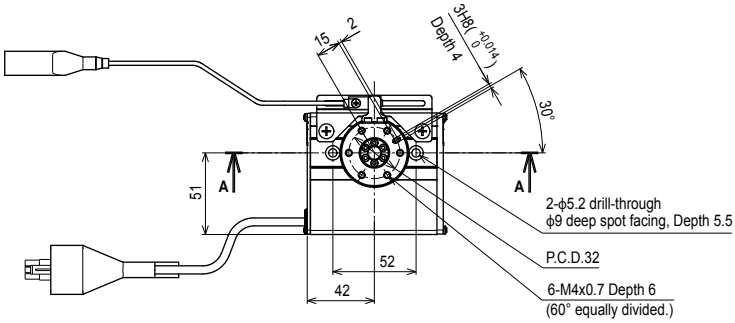
Weight (kg)	0.51

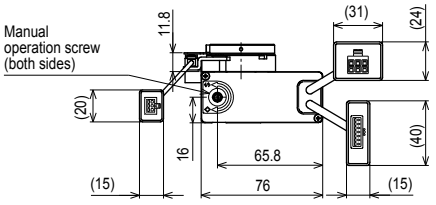
Note 1. This drawing is output under the conditions below.
Bearing..... Standard
Torque..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.
Note 3. The motor cable exit direction is only the left side.

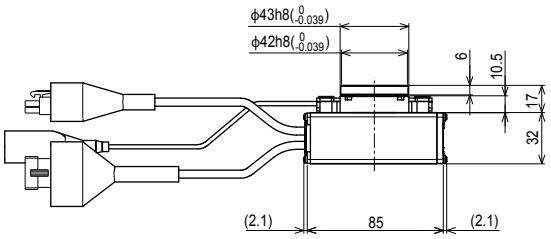
RF02-SH Sensor specification – High rigidity model

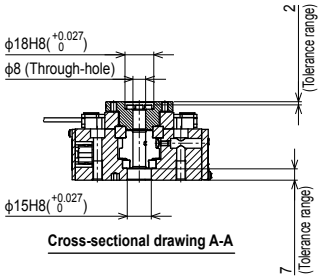


*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.

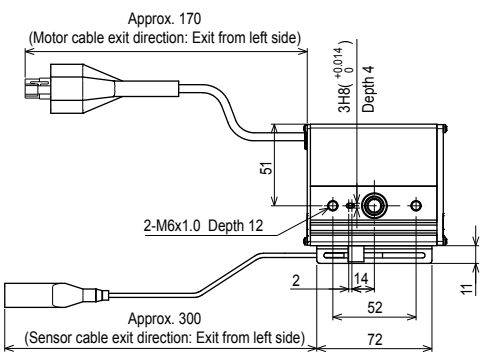








Cross-sectional drawing A-A



Weight (kg)	0.55

Note 1. This drawing is output under the conditions below.
Bearing..... High rigidity
Torque ..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.
Note 3. The motor cable exit direction is only the left side.

Controller TS-S2 ▶ 626 TS-SH ▶ 626

RF03-N

Rotary type / Limit rotation specification

CE compliance | Rotation range : 320°

Ordering method

RF03 – **N** – [ ] – [ ] – [ ] – [ ] – [ ] – [ ]

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1
RF03	N: Stroke end (Limit rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	R: From the right L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

Robot positioner	I/O
S2: TS-S2 Note2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SH

Robot positioner	I/O	Battery
SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3	B: With battery (Absolute) N: None (Incremental)

SD – **1**

Robot driver	I/O cable
SD: TS-SD	1: 1m

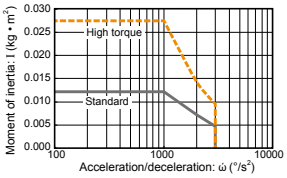
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

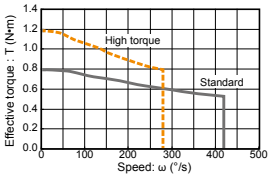
Motor	28 □ Step motor	
Resolution (Pulse/rotation)	4096	
Repeatability Note 1 **(°)**	+/-0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 **(°/sec)**	420	280
Rotating torque (N•m)	0.8	1.2
Max. pushing torque (N•m)	0.4	0.6
Backlash (°)	+/-0.5	
Max. moment of inertia Note 3 **(kg•m²)**	0.012	0.027
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	320	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

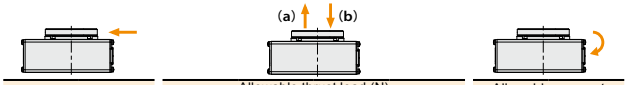
Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load



Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
196	233	197		363	398	5.3	6.4

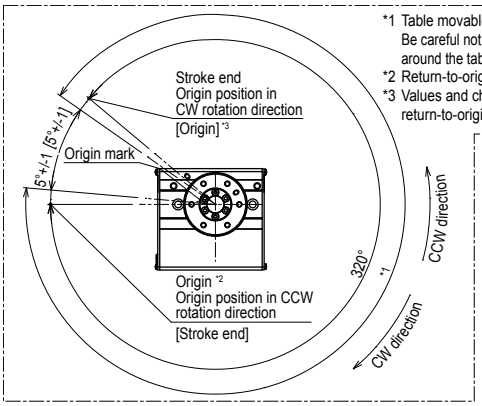
Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

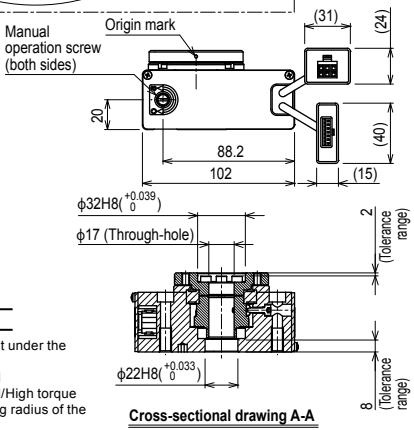
Controller

Controller	Operation method
TS-S2 TS-SH	I/O point trace / Remote command
TS-SD	Pulse train control

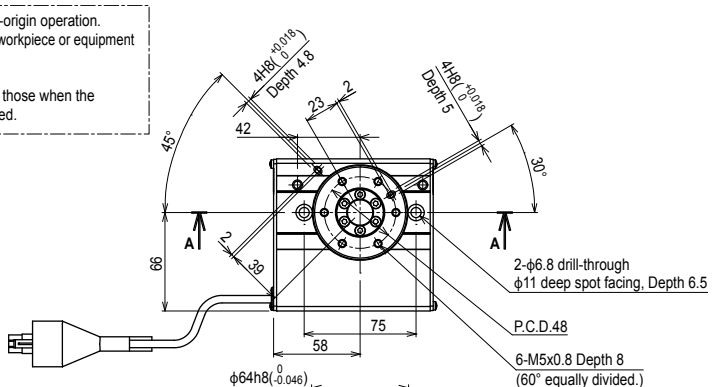
RF03-NN Limit rotation specification – Standard model

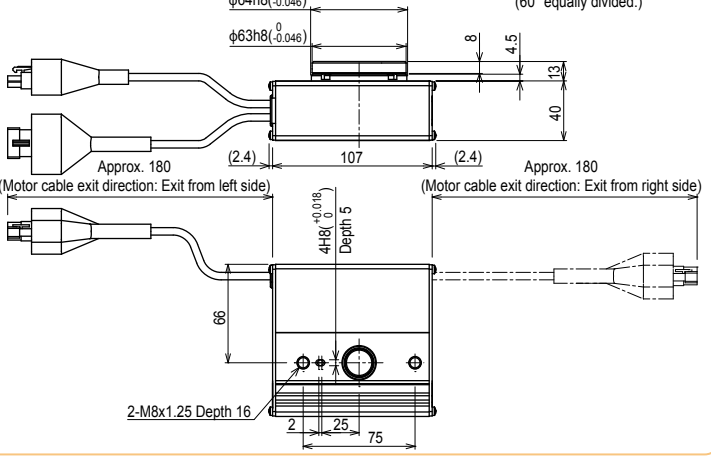
*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 Return-to-origin position
*3 Values and characters in [ ] show those when the return-to-origin direction is changed.





Cross-sectional drawing A-A

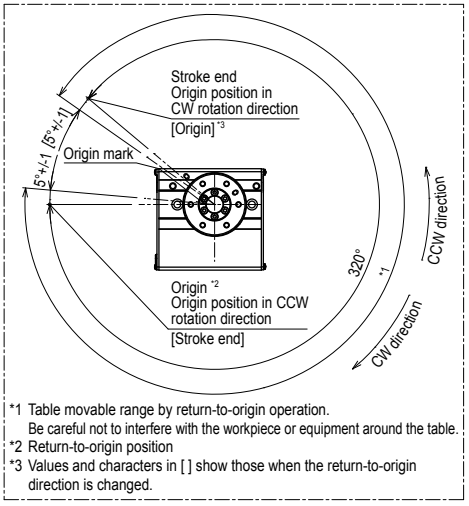




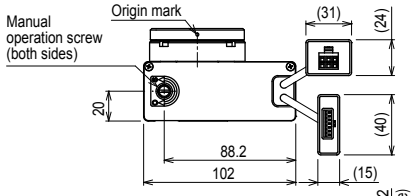
Weight (kg)	1.1

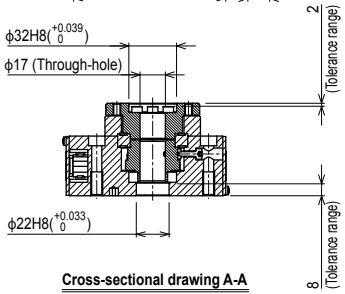
Note 1.This drawing is output under the conditions below.
Bearing ... Standard
Torque..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.

RF03-NH Limit rotation specification – High rigidity model

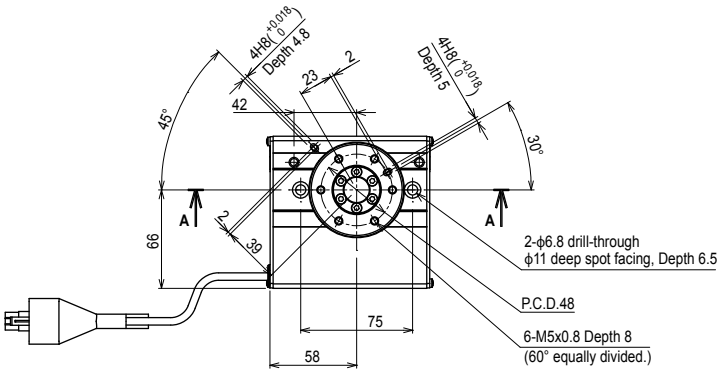


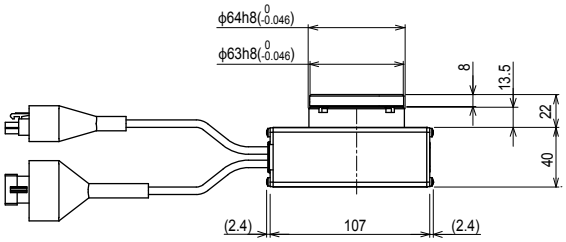
*1 Table movable range by return-to-origin operation.
Be careful not to interfere with the workpiece or equipment around the table.
*2 Return-to-origin position
*3 Values and characters in [ ] show those when the return-to-origin direction is changed.

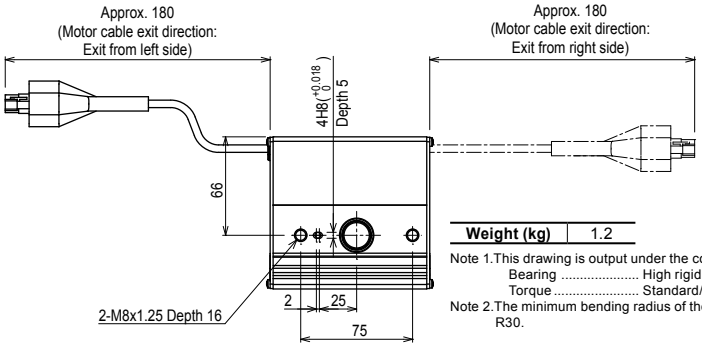




Cross-sectional drawing A-A







Weight (kg)	1.2

Note 1.This drawing is output under the conditions below.
Bearing ..... High rigidity
Torque ..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.

RF03-S

Rotary type / Sensor specification

CE compliance | Limitless rotation

Ordering method

RF03 – **S** – [ ] – [ ] – [ ] – [ ] – [ ] – [ ]

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1
RF03	S: Sensor (Limitless rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	R: From the right L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2S

Robot positioner	I/O
S2S: TS-S2S Note 2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SHS

Robot positioner	I/O	Battery
SHS: TS-SHS	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3	B: With battery (Absolute) N: None (Incremental)

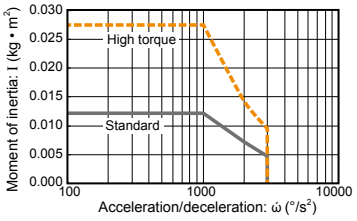
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

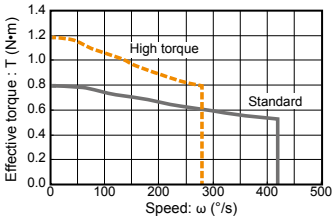
Motor	28 □ Step motor	
Resolution (Pulse/rotation)	4096	
Repeatability Note 1 **(°)**	+/-0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 **(°/sec)**	420	280
Rotating torque (N•m)	0.8	1.2
Max. pushing torque (N•m)	0.4	0.6
Backlash (°)	+/-0.5	
Max. moment of inertia Note 3 **(kg•m²)**	0.012	0.027
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	360	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

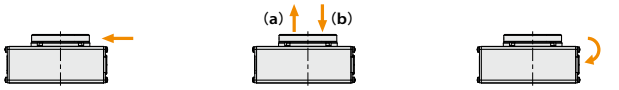
Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load



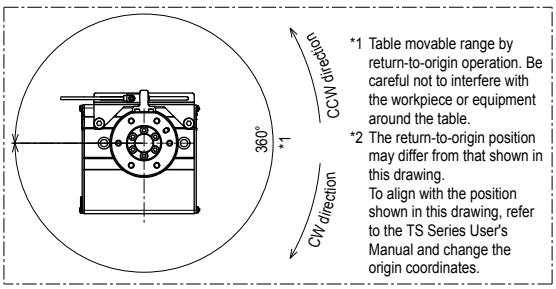
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
196	233	197		363	398	5.3	6.4

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

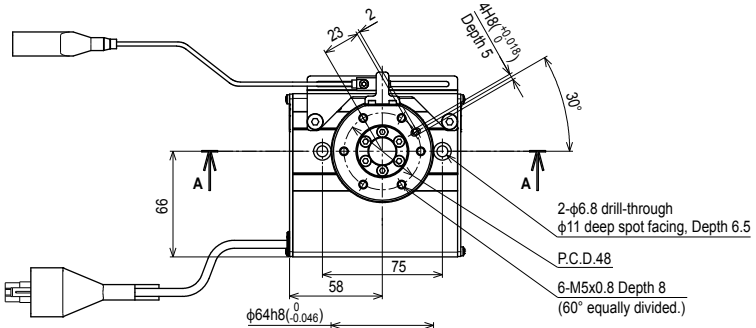
Controller

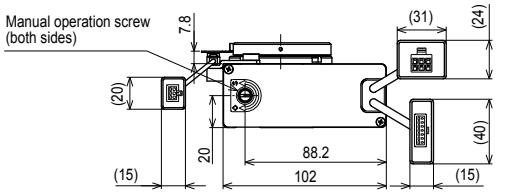
Controller	Operation method
TS-S2S	I/O point trace / Remote command
TS-SHS	

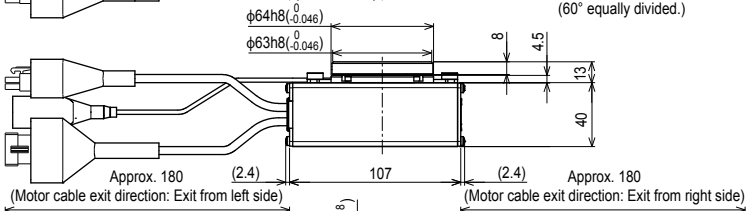
RF03-SN Sensor specification – Standard model

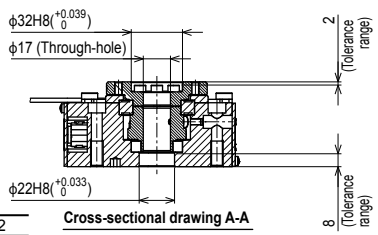


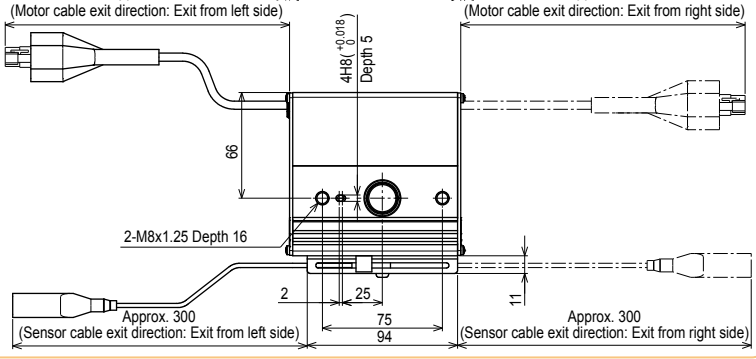
*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing.
To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.











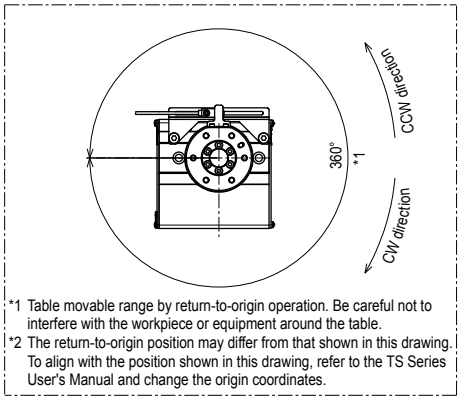
Weight (kg)	1.2

Cross-sectional drawing A-A

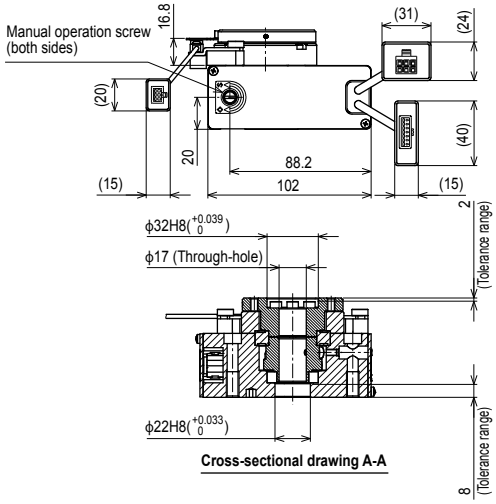
Note 1. This drawing is output under the conditions below.
Bearing..... Standard
Torque..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.

Controller TS-S2 ▶ 626 TS-SH ▶ 626

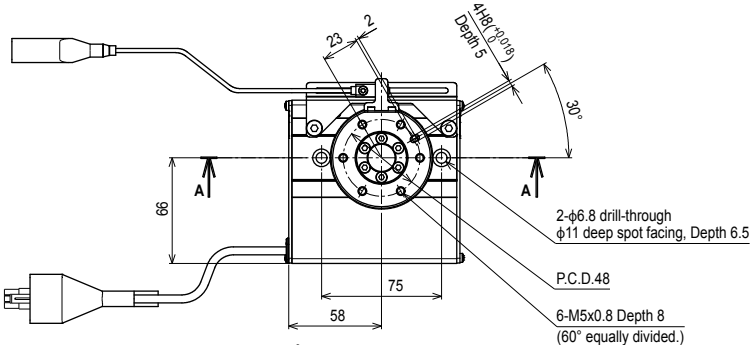
RF03-SH Sensor specification – High rigidity model

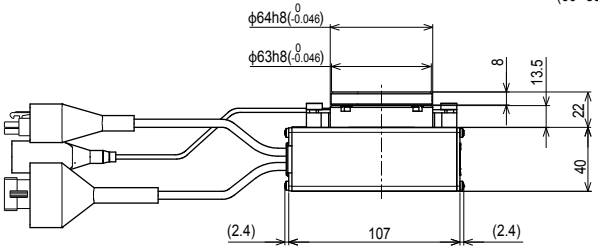


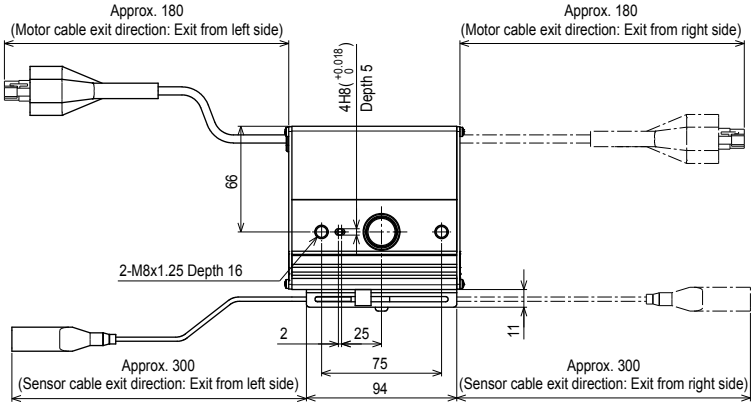
*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.



Cross-sectional drawing A-A





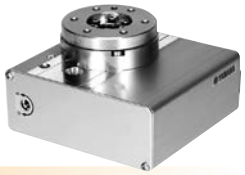


Weight (kg)	13

Note 1. This drawing is output under the conditions below.
Bearing ..... High rigidity
Torque ..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.

RF04-N

Rotary type / Limit rotation specification



- CE compliance
- Rotation range : 320°

Ordering method

RF04	N						
Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1	
	N: Stroke end (Limit rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	R:From the right L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m	

S2

Robot positioner	I/O
S2: TS-S2 Note2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note3

SH

Robot positioner	I/O	Battery
SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note3	B: With battery (Absolute) N: None (Incremental)

SD — **1**

Robot driver	I/O cable
SD: TS-SD	1: 1m

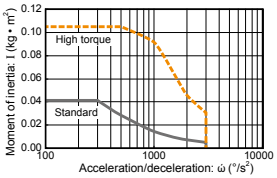
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

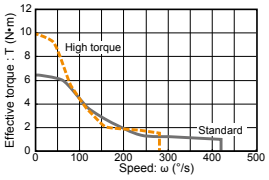
Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability Note 1 (°)	±0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 (°/sec)	420	280
Rotating torque (N•m)	6.6	10
Max. pushing torque (N•m)	33	5
Backlash (°)	±0.5	
Max. moment of inertia Note 3 (kg•m²)	0.04	0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	320	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load

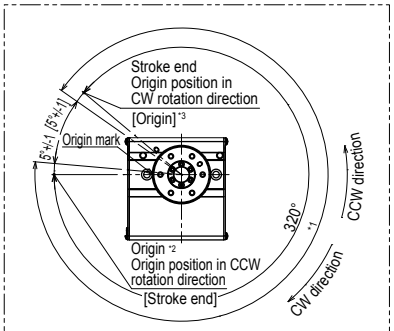
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
314	378	296		398	517	9.7	12.0

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

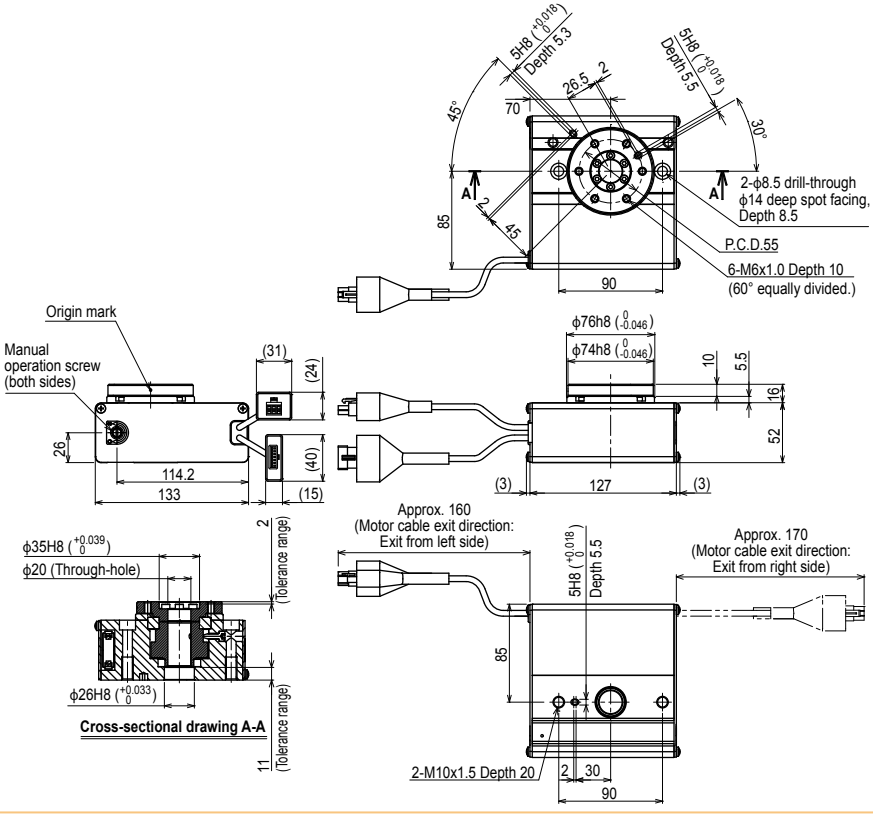
Controller

Controller	Operation method
TS-S2 TS-SH	I/O point trace / Remote command
TS-SD	Pulse train control

RF04-NN Limit rotation specification – Standard model



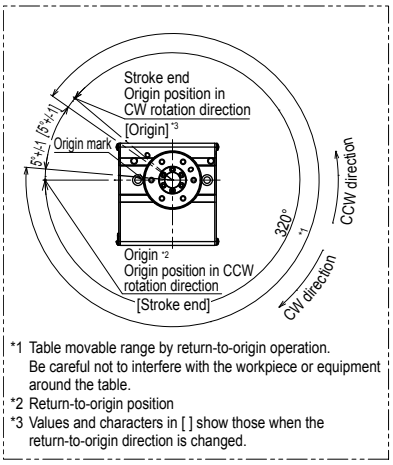
*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 Return-to-origin position
*3 Values and characters in [ ] show those when the return-to-origin direction is changed.



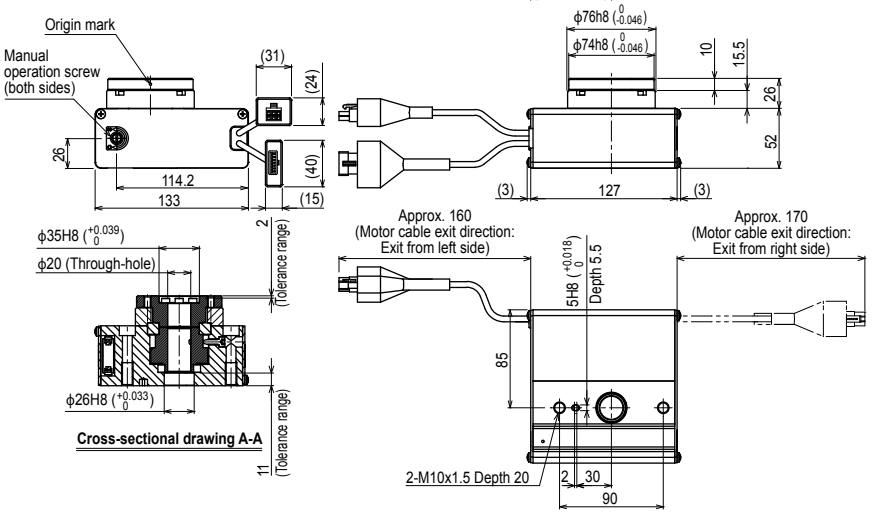
Weight (kg)	2.2

Note 1.This drawing is output under the conditions below.
Bearing..... Standard
Torque ..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.

RF04-NH Limit rotation specification – High rigidity model



*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 Return-to-origin position
*3 Values and characters in [ ] show those when the return-to-origin direction is changed.



Weight (kg)	2.4

Note 1.This drawing is output under the conditions below.
Bearing..... High rigidity
Torque ..... Standard/High torque
Note 2.The minimum bending radius of the motor cable is R30.

RF04-S

Rotary type / Sensor specification

CE compliance | Limitless rotation

Ordering method

RF04 – [S] – [ ] – [ ] – [ ] – [ ] – [ ] – [ ]

Model	Return-to-origin method	Bearing	Torque	Cable entry location	Rotation direction	Cable length Note 1
RF04	S: Sensor (Limitless rotation)	N: Standard H: High rigidity	N: Standard torque H: High torque	R: From the right L: From the left	N: CCW Z: CW	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2S

Robot positioner	I/O
S2S: TS-S2S Note 2	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3

SHS

Robot positioner	I/O	Battery
SHS: TS-SHS	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board Note 3	B: With battery (Absolute) N: None (Incremental)

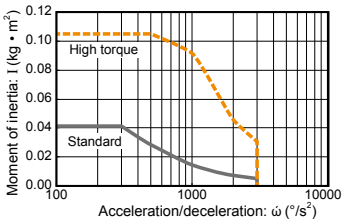
Note 1. The robot cable is flexible and resists bending.
Note 2. See P.634 for DIN rail mounting bracket.
Note 3. Select this selection when using the gateway function. For details, see P.96.

Basic specifications

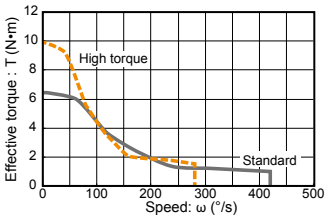
Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability Note 1 **(°)**	+/-0.05	
Drive method	Special warm gear + belt	
Torque type	Standard	High torque
Maximum speed Note 2 **(°/sec)**	420	280
Rotating torque (N•m)	6.6	10
Max. pushing torque (N•m)	3.3	5
Backlash (°)	+/-0.5	
Max. moment of inertia Note 3 **(kg•m²)**	0.04	0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10	
Rotation range (°)	360	

Note 1. Positioning repeatability in one direction.
Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/deceleration" graph and the "Effective torque vs. speed" graph (reference).
Note 3. For moment of inertia and effective torque details, see P.744.

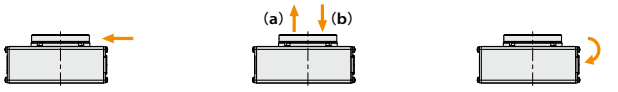
Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load



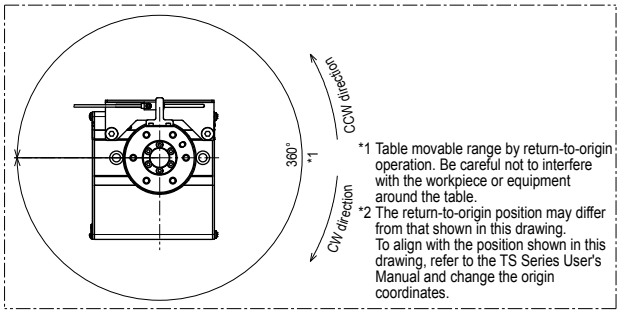
Allowable radial load (N)		Allowable thrust load (N)				Allowable moment (N•m)	
		(a)		(b)			
Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model	Standard model	High rigidity model
314	378	296		398	517	9.7	12.0

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs.
For details, please refer to the TRANSERVO Series User's Manual.

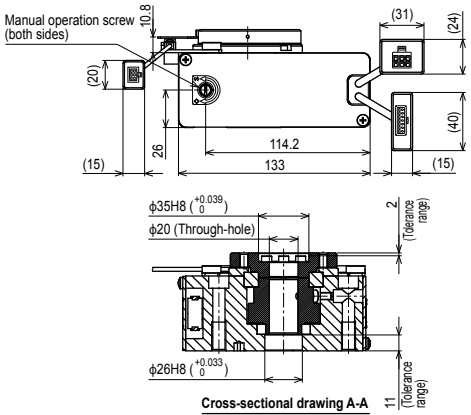
Controller

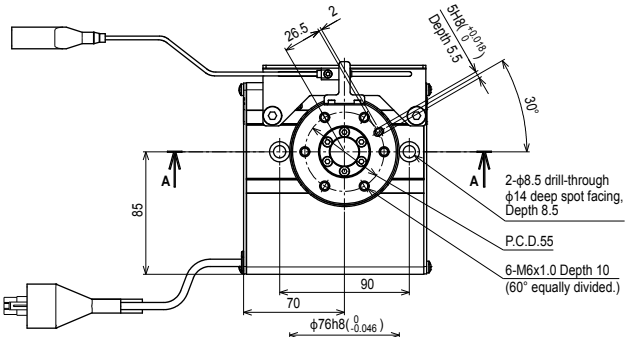
Controller	Operation method
TS-S2S	I/O point trace / Remote command
TS-SHS	

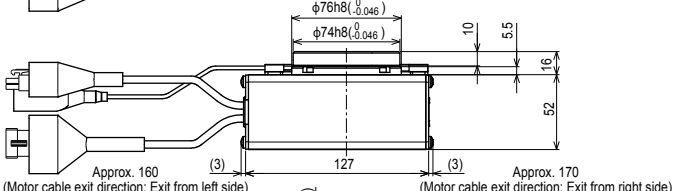
RF04-SN Sensor specification – Standard model

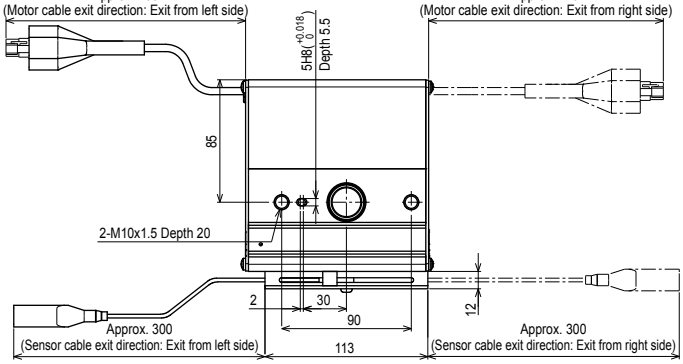


*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.





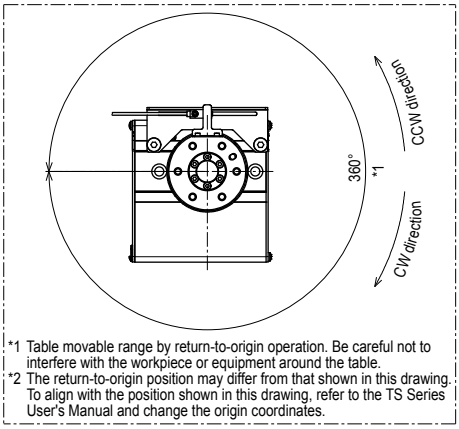




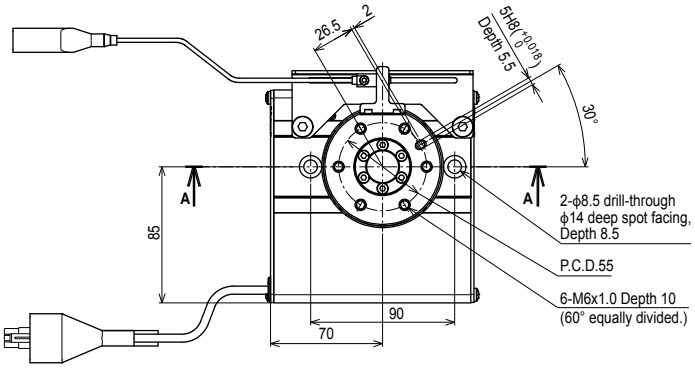
Weight (kg)	2.3

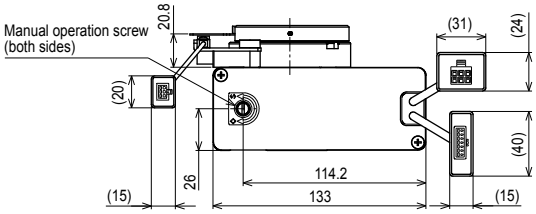
Note 1. This drawing is output under the conditions below.
Bearing..... Standard
Torque ..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.

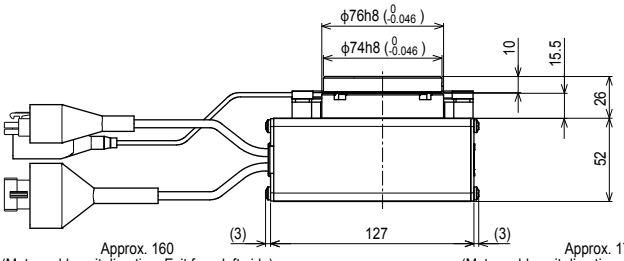
RF04-SH Sensor specification – High rigidity model

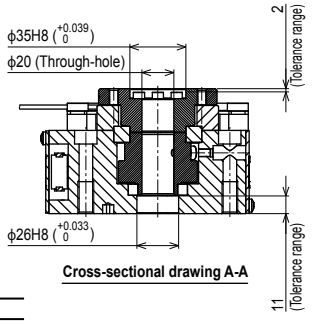


*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.

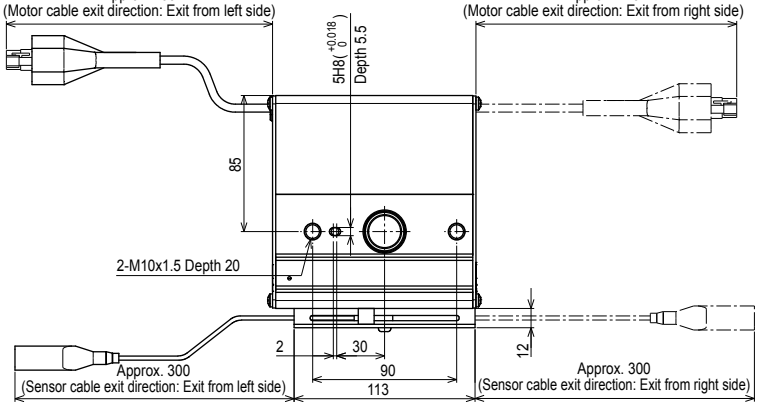








Cross-sectional drawing A-A



Weight (kg)	25

Note 1. This drawing is output under the conditions below.
Bearing..... High rigidity
Torque ..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.