



Torque Motor & Direct Drive Motor

Technical Information





Linear Motor Stage

- Automated transport / AOI application / Precision / Semiconductor
- With Iron-core
 - Coreless Type
 - Linear Turbo LMT
 - Planar Servo Motor
 - Air Bearing Platform
 - X-Y Stage
 - Gantry Systems



Linear Motor

- Machine tool / Touch panel industry / Semiconductor industry / Laser manufacturing machine / Glass cutting machine
- Ironcore linear motor-LMFA series, LMSA series, LMSC series
 - Ironless linear motor-LMC series, LMT series



Torque Motor & Direct Drive Motor

- Machine Tools
- Torque Motor--TMRW Series
- Inspection / Testing Equipment / Robot
- Direct Drive Motor--DMS, DMY, DMN Series



AC Servo Motor & Drive

- Semiconductor / Packaging machine / SMT / Food industry / LCD
- Drives-D1, D1-N, D2T
 - Motors-50W-2000W



Linear Actuator

- Hospital bed / Automatic window / Home care facility / Riveting / Press-fitting / Surface checks / Bending
- Servo Actuator-LAA series
 - LAM series
 - LAS series
 - LAN series
 - LAC series



Positioning Measurement System

- Cutting machines / Traditional gantry milling machines / Programmable drilling machines
- High Resolution
 - Signal Translator
 - High-precision Enclosed
 - High Efficiency Counter



Multi-Axis Robot

- Pick-and-place / Assembly / Array and packaging / Semiconductor / Electro-Optical industry / Automotive industry / Food industry
- Articulated Robot
 - Delta Robot
 - SCARA Robot
 - Wafer Robot
 - Electric Gripper
 - Integrated Electric Gripper
 - Rotary Joint



Single-Axis Robot

- Precision / Semiconductor / Medical / FPD
- KK, SK
 - KS, KA
 - KU, KE, KC



Torque Motor Rotary Table

- Aerospace / Medical / Automotive industry / Machine tools / Machinery industry
- RAB Series
 - RAS Series
 - RCV Series
 - RCH Series



Ballscrew






















- Precision Ground / Rolled
- Super S series
 - Super T series
 - Mini Roller
 - Ecological & Economical lubrication Module E2
 - Rotating Nut (R1)
 - Energy-Saving & Thermal-Controlling (C1)
 - Heavy Load Series (RD)
 - Ball Spline


















Linear Guideway
















- Automation / Semiconductor / Medical
- Ball Type--HG, EG, WE, MG, CG
 - Quiet Type--QH, QE, QW, QR
 - Other--RG, E2, PG, SE, RC




Direct Drive Motor

Type	Size (mm)	Peak Torque (Nm)																	Accuracy (arcsec)	Repeatability (arcsec)	Page	Drive		Motor Power Cable		Encoder Cable		Features	Applications
		4.2	9	12	18	24	30	40	45	60	75	90	120	150	180	225	300	450				Type	Page	Type	Page	Type	Page		
DMN	118x118																		±10/±45	± 2.5	15		D1-36-S2	LMACE□□AA LMACE□□AM (With Hall sensor)	· Low profile · Hollow shaft · External rotary table	· LED inspection/ processing · Semi-conductor transport, inspection/ porcessing · Each kind of Assembly machines			
	180x180																												
	230x230																												
DMY	Φ 110																	±30	± 3	9		D1-36-S4	LMACE□□AU	· External rotary table · High speed	· P&P · Turntable · Inspection machine · Automatic assembly machine · CD/DVD Mfg. system				
	Φ 170																	±30	± 3	10		DMYxxG: LMACE□□AA							
	Φ 270																		±30	± 3	11		DMYxx: LMACE□□AU						
DMS	Φ 110																		±10/±25	± 3	3		LMACE□□AA LMACE□□AM (With Hall sensor)	· Large torque · High precision	· P&P · Turntable · Index table · High-speed placement machine · Automatic assembly machine				
	Φ 150																												
	Φ 200																												
	Φ 300																												

TMRW Torque motor

	External diameter (mm)	Peak Torque (Nm)														Page		
		36	60	66	83	112	120	119	156	178	203	223	280	335	390		583	
Torque Motor	160	 TMRW13 TMRW13L	 TMRW15 TMRW15L		 TMRW17 TMRW17L			 TMRW1A TMRW1AL		 TMRW1F TMRW1FL								18
	198			 TMRW23 TMRW23L		 TMRW25 TMRW25L			 TMRW27 TMRW27L		 TMRW2A TMRW2AL		 TMRW2F TMRW2FL					20
	230						 TMRW43 TMRW43L				 TMRW45 TMRW45L		 TMRW47 TMRW47L		 TMRW4A TMRW4AL	 TMRW4F TMRW4FL		22

	External diameter (mm)	Peak Torque (Nm)														Page			
		275	456	490	640	750	810	910	1100	1230	1360	1600	1760	2400	2470		3600		
Torque Motor	310	 TMRW73 TMRW73L	 TMRW75 TMRW75L		 TMRW77 TMRW77L			 TMRW7A TMRW7AL			 TMRW7F TMRW7FL								24
	385			 TMRWA3 TMRWA3L			 TMRWA5 TMRWA5L		 TMRWA7 TMRWA7L		 TMRWAA TMRWAAL		 TMRWAF TMRWAF					26	
	485					 TMRWD3 TMRWD3L				 TMRWD5 TMRWD5L			 TMRWD7 TMRWD7L		 TMRWDA TMRWDAL	 TMRWDF TMRWDF		28	

	External diameter (mm)	Peak Torque (Nm)														Page	
														2360	3340		5020
Torque Motor	565													 TMRWG7 TMRWG7L	 TMRWGA TMRWGAL	 TMRWGF TMRWGFL	30

HIWIN[®]

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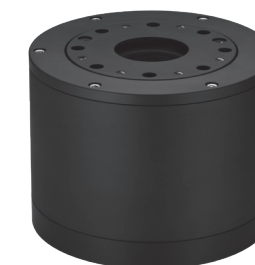


1. Direct Drive Motor

1.1 Product Overview and Applications

An extremely rigid connection between motor and load, and a servo-drive regulation ensures excellent acceleration capabilities and good uniformity of movement. HIWIN direct drive motors are especially well suited for tasks in automation due to the hollow shaft design. Media, cable systems or mechanical parts can be fed through without problems.

- No backlash
- Drive free of clearance
- Hollow shaft
- No gear transmission losses
- Maintenance free and compact
- Brush-free drive
- Extremely rigid support with cross-roller bearing
- IP65 available for DMS Series
- Integrated brake is available as an option
- Hall sensor is available as an option



Short and compact: HIWIN direct drive motors are optimized for high torques and robust dynamics.

Table 1.1 Applications

Classification	Application	Features and Applications					
		Accuracy	Speed	Rigidity	Compactness	Cleanliness	Maintenance Free
Production equipment	CVD, wafer cleaning, ion implantation	○			○	○	○
	Semi-conductor transport, inspection/processing	○			○	○	○
Assembly machines	Assembly machines for electric components	○	○		○	○	○
	High-speed assembly machines for electronic components	○	○		○	○	○
	Various assembly machines	○	○		○	○	○
Inspection/testing equipment	Machine part inspection	○			○		○
	Inspection of electric components	○			○		○
	Inspection of optical components	○			○		○
	Chemical analysis of liquids		○			○	○
	Various Inspection/testing equipment	○			○		○
Robots	Various assembly robots	○	○	○	○		○
	Various transport robots	○	○		○		○
	Inspection/Transport robots in clean rooms	○	○		○	○	○

1.2 DMS Series

The DMS series is designed with an integrated, high resolution feedback system optimized to achieve high dynamic motion, high torque and high precision. The DMS series is a perfect fit for industries that require high precision.

- Inner rotating structure
- Integrated incremental/absolute feedback system
- High dynamic, torque and precision
- Maximum torque: 9.3~450Nm
- Meets IP65 enclosure standards as an option
- Integrated brake is available as an option
- Hall sensor is available as an option



■ Model Numbers for DMS Series

	Motor specification					Function			
	DMS	3	2	L	G	H	B	P	C
Series	DMS : Internal rotary type								
Size	0 : External diameter Φ 110mm 1 : External diameter Φ 150mm 3 : External diameter Φ 200mm 7 : External diameter Φ 300mm								
Rotor height	2 : 20mm 3 : 30mm 4 : 40mm 6 : 60mm 8 : 80mm C : 120mm								
Wiring Code	: Standard L : Low Back emf								
Feedback system	G : Incremental								
Hall sensor	: Without Hall sensor H : With Hall sensor								
Brake	: Without brake B : With power-on brake (DMS1, DMS3, DMS7 Series)								
International Protection Standard	: IP40(Standard) P : IP65								
Optional Specifications	: Standard C : Customized								

1.2.1 DMS0 Series

DMS0 Dimensions

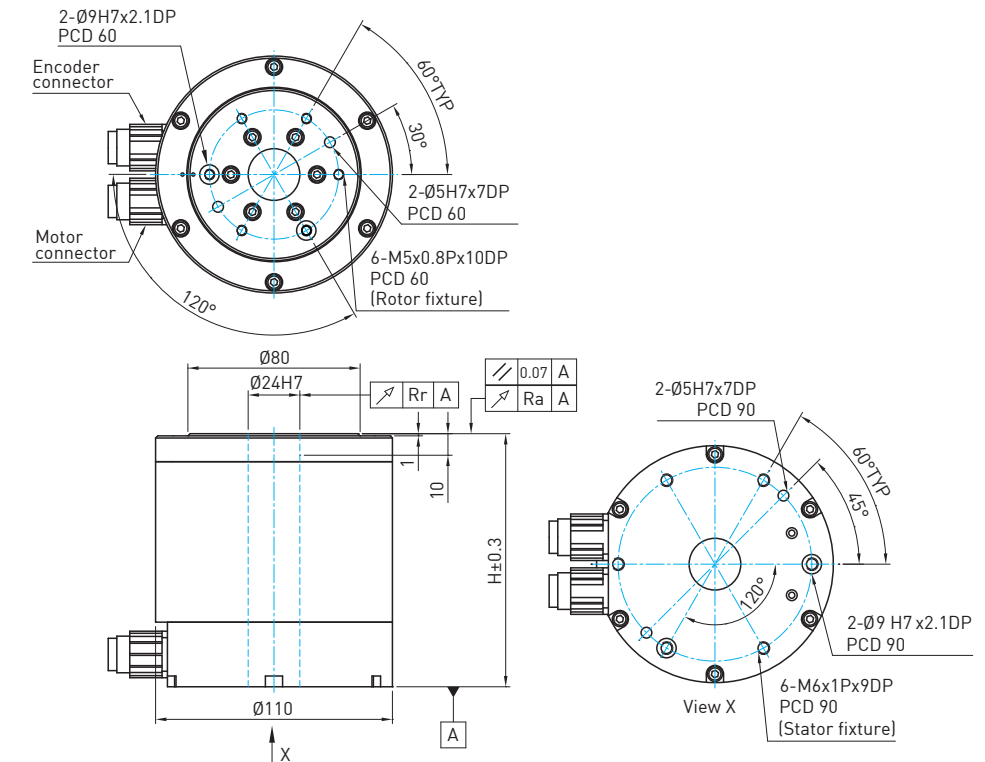


Table 1.2 DMS0 Specifications

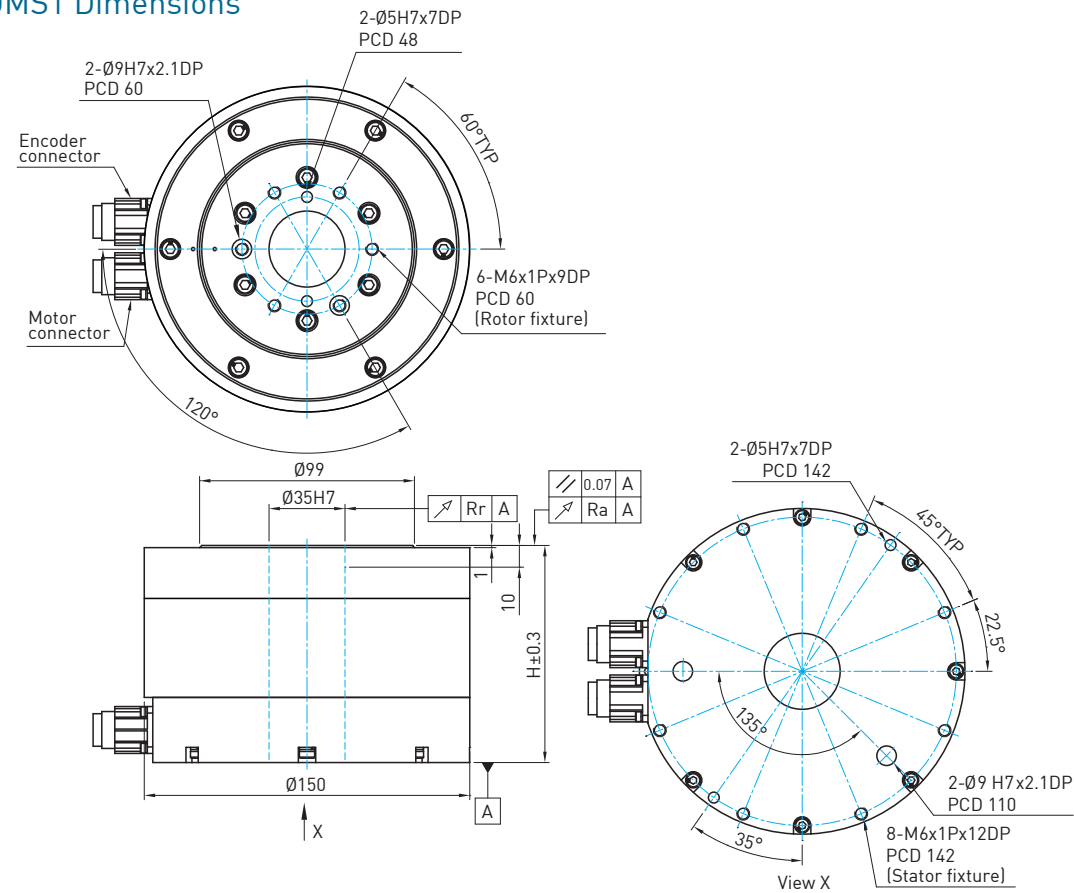
	Symbol	Unit	DMS03G	DMS07G
Continuous torque	T_c	Nm	3.1	6.2
Continuous current	I_c	A_{rms}	2	2
Peak torque (Within 1s.)	T_p	Nm	9.3	18.6
Peak current (Within 1s.)	I_p	A_{rms}	6	6
Torque constant	K_t	Nm/ A_{rms}	1.55	3.1
Electrical time constant	T_e	ms	1.9	2.1
Resistance (line to line at 25°C)	R_{25}	Ω	7.1	11.1
Inductance (line to line)	L	mH	13.8	23
Number of poles	$2p$		10	10
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	0.82	1.7
Motor constant (line to line at 25°C)	K_m	Nm/\sqrt{W}	0.5	0.8
Thermal resistance	R_{th}	K/W	1.76	1.13
Temperature sensor				PTC SNM100
Nominal input voltage		V_{DC}		500(600 ²⁾)
Inertia of rotating parts	J	kgm^2	0.003	0.006
Mass of motor	M_m	kg	4	7
Max. axial load	F_a	N	3700	3700
Max. moment load	M	Nm	40	40
Max. speed		rpm	700	700
Resolution		p/rev	4,325,376 (Incremental, sin/cos 1Vpp)	
Repeatability		arc-sec	± 3	
Accuracy		arc-sec	$\pm 45/\pm 10^{11}$	
Axial runout	R_a	mm	0.03(0.005 ²⁾)	
Radial runout	R_r	mm	0.03(0.015 ²⁾)	
Height	H	mm	117.5	150

Note : ¹⁾ After error mapping
²⁾ Optional

*All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.

1.2.2 DMS1 Series

DMS1 Dimensions



1.2.3 DMS3 Series

DMS3 Dimensions

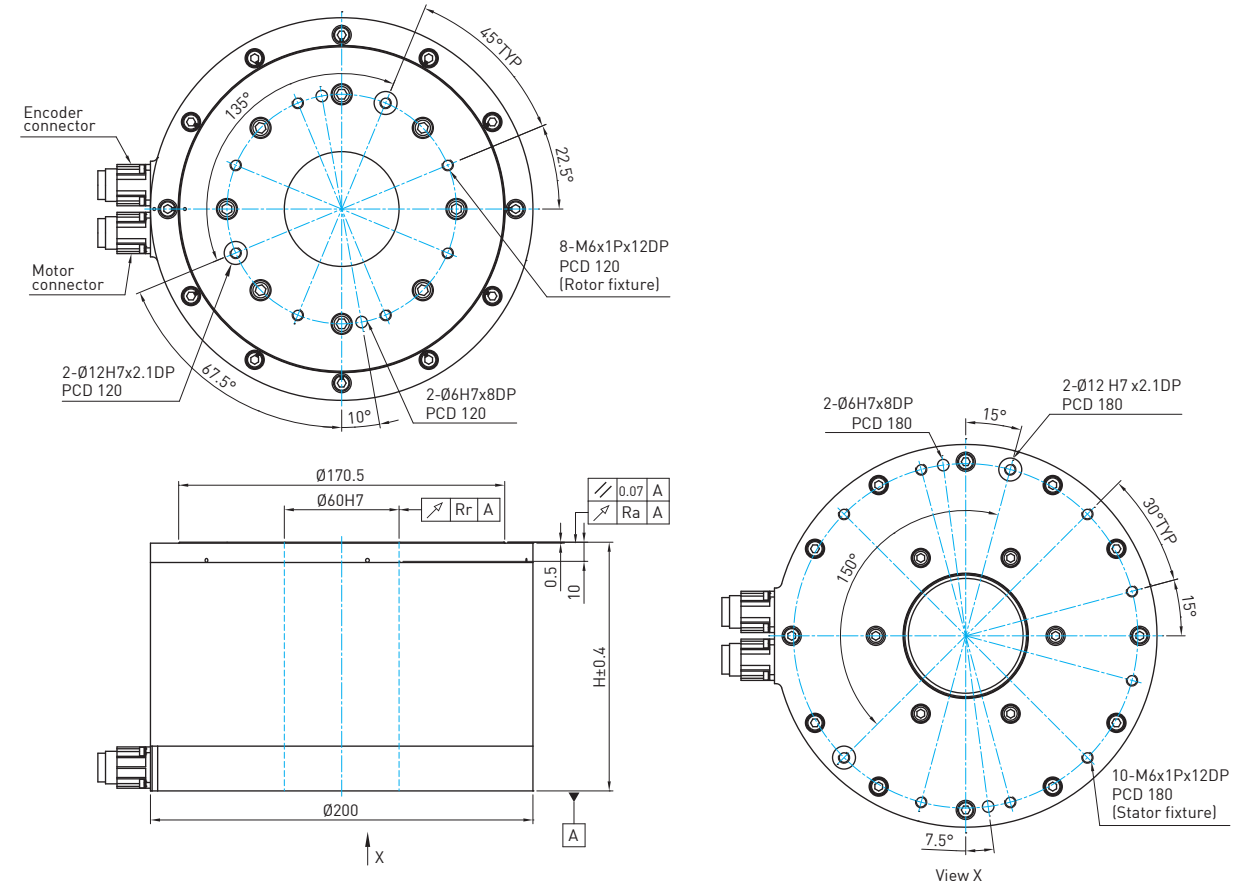


Table 1.3 DMS1 Specifications

	Symbol	Unit	DMS12G	DMS14G	DMS16G	DMS18G
Continuous torque	T _c	Nm	5	10	15	20
Continuous current	I _c	A _{rms}	4	4	4	4
Peak torque (Within 1s.)	T _p	Nm	15	30	45	60
Peak current (Within 1s.)	I _p	A _{rms}	12	12	12	12
Torque constant	K _t	Nm/A _{rms}	1.25	2.5	3.75	5
Electrical time constant	T _e	ms	3.2	3.6	3.8	4
Resistance (line to line at 25°C)	R ₂₅	Ω	2.6	3.9	5.2	6.5
Inductance (line to line)	L	mH	8.2	14	20	26
Number of poles	2 _p		22	22	22	22
Back emf constant (line to line)	K _v	V _{rms} /(rad/s)	0.6	1.2	1.8	2.4
Motor constant (line to line at 25°C)	K _m	Nm/√W	0.6	1	1.3	1.6
Thermal resistance	R _{th}	K/W	1.2	0.8	0.6	0.48
Temperature sensor			PTC SNM100			
Nominal input voltage	V _{dc}		500(600 ²)			
Inertia of rotating parts	J	kgm ²	0.006	0.0065	0.007	0.0075
Mass of motor	M _m	kg	7.2	8.5	9.8	11
Max. axial load	F _a	N	3700	3700	3700	3700
Max. moment load	M	Nm	60	60	60	60
Max. speed		rpm	600	600	600	500
Resolution		p/rev	4,320,000 (Incremental, sin/cos 1Vpp)			
Repeatability		arc-sec	±3			
Accuracy		arc-sec	±45/±10 ¹¹			
Axial runout	R _a	mm	0.03(0.005 ²)			
Radial runout	R _r	mm	0.03(0.015 ²)			
Height	H	mm	100	120	140	160

Note : ¹ After error mapping

² Optional

*All the specifications in the table are in ±10% of tolerance except dimensions.

Table 1.4 DMS3 Specifications

	Symbol	Unit	DMS32G	DMS34G	DMS34LG	DMS38G	DMS38LG	DMS3CG	DMS3CLG
Continuous torque	T _c	Nm	10	20	20	40	40	60	60
Continuous current	I _c	A _{rms}	3	3	6	3	6	3	6
Peak torque (Within 1s.)	T _p	Nm	30	60	60	120	120	180	180
Peak current (Within 1s.)	I _p	A _{rms}	9	9	18	9	18	9	18
Torque constant	K _t	Nm/A _{rms}	3.3	6.6	3.3	13.3	6.65	20	10
Electrical time constant	T _e	ms	4.7	4.8	4.4	5.3	4.5	5.1	5
Resistance (line to line at 25°C)	R ₂₅	Ω	5.8	8.4	1.7	13.6	2.9	18.8	3.9
Inductance (line to line)	L	mH	27	40	7.5	71.5	13	95	19.5
Number of poles	2 _p		22	22	22	22	22	22	22
Back emf constant (line to line)	K _v	V _{rms} /(rad/s)	1.6	3.2	1.6	6.4	3.2	9.6	4.8
Motor constant (line to line at 25°C)	K _m	Nm/√W	1.1	1.9	2.1	2.9	3.2	3.8	4.1
Thermal resistance	R _{th}	K/W	0.96	0.66	0.82	0.41	0.48	0.3	0.36
Temperature sensor			PTC SNM100						
Nominal input voltage	V _{dc}		500(600 ²)						
Inertia of rotating parts	J	kgm ²	0.014	0.02	0.02	0.026	0.026	0.035	0.035
Mass of motor	M _m	kg	14	17	17	22.5	22.5	28.5	28.5
Max. axial load	F _a	N	8000	8000	8000	8000	8000	8000	8000
Max. moment load	M	Nm	240	240	240	240	240	240	240
Max. speed		rpm	600	400	600	200	450	120	300
Resolution		p/rev	4,320,000 (Incremental, sin/cos 1Vpp)						
Repeatability		arc-sec	±2.5						
Accuracy		arc-sec	±25/±10 ¹¹						
Axial runout	R _a	mm	0.03(0.005 ²)						
Radial runout	R _r	mm	0.03(0.015 ²)						
Height	H	mm	130	150	150	190	190	230	230

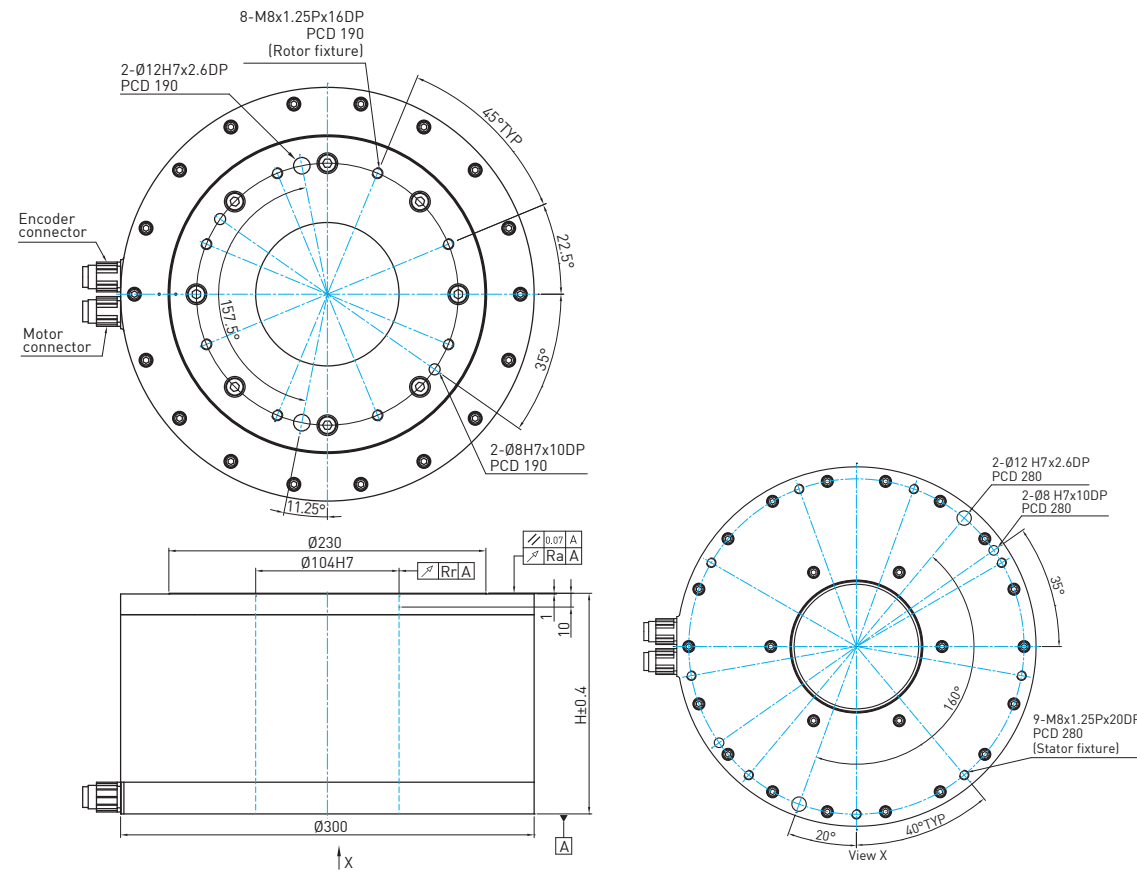
Note : ¹ After error mapping

² Optional

*All the specifications in the table are in ±10% of tolerance except dimensions.

1.2.4 DMS7 Series

DMS7 Dimensions



1.2.5 DMS Series T-N curves

(DC bus voltage=325Vdc)

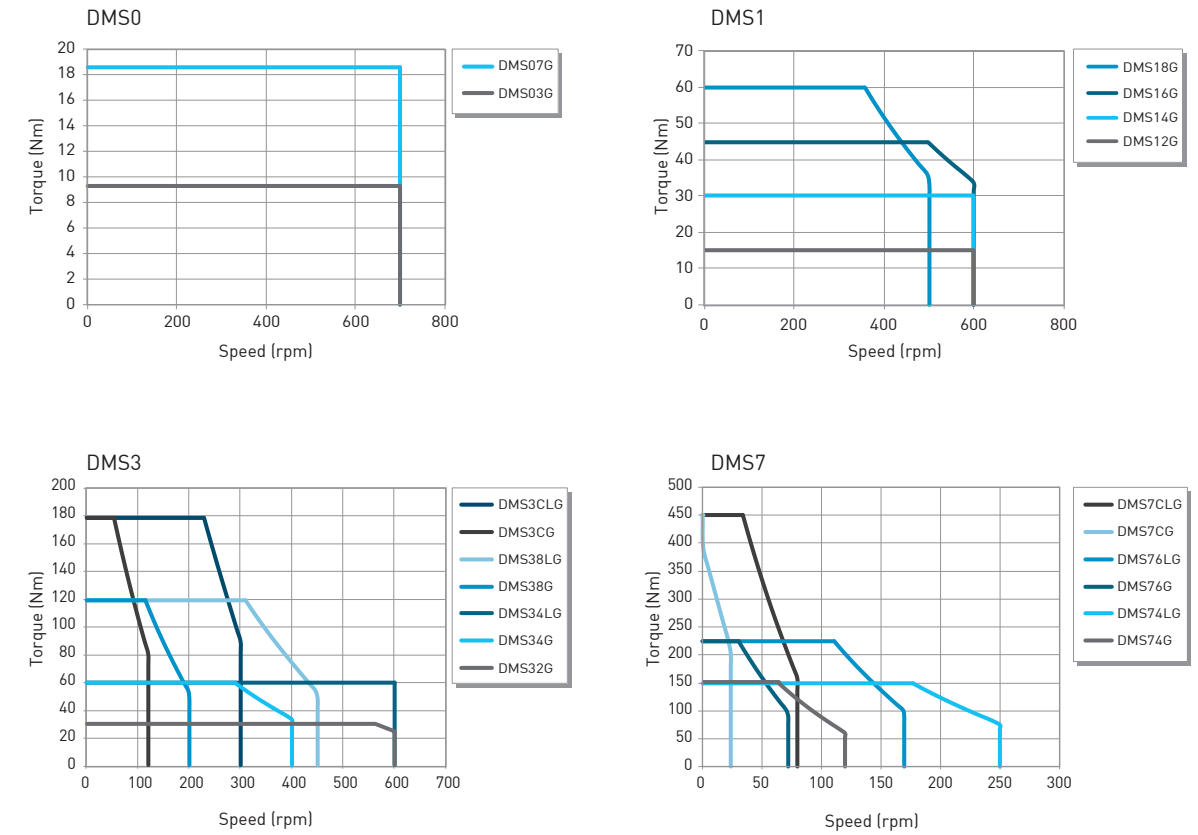


Table 1.5 DMS7 Specifications

	Symbol	Unit	DMS74G	DMS74LG	DMS76G	DMS76LG	DMS7CG	DMS7CLG
Continuous torque	T _c	Nm	50	50	75	75	150	150
Continuous current	I _c	A _{rms}	3	6	3	6	3	6
Peak torque (Within 1s.)	T _p	Nm	150	150	225	225	450	450
Peak current (Within 1s.)	I _p	A _{rms}	9	18	9	18	9	18
Torque constant	K _t	Nm/A _{rms}	16.7	8.35	25	12.5	50	25
Electrical time constant	T _e	ms	4.6	5	5.1	5	5.4	6
Resistance (line to line at 25°C)	R ₂₅	Ω	14	3.5	19	4.8	32.5	8.5
Inductance (line to line)	L	mH	64	17.5	96.5	27	176	50.6
Number of poles	2 _p		44	44	44	44	44	44
Back emf constant (line to line)	K _v	V _{rms} /(rad/s)	10.8	5.4	16.2	8.1	32.4	16.2
Motor constant (line to line at 25°C)	K _m	Nm/√W	3.6	3.6	4.7	4.7	7.2	7.0
Thermal resistance	R _{th}	K/W	0.4	0.4	0.29	0.29	0.17	0.16
Temperature sensor			PTC SNM100					
Nominal input voltage		V _{DC}	500(600 ²)					
Inertia of rotating parts	J	kgm ²	0.152	0.152	0.174	0.174	0.241	0.241
Mass of motor	M _m	kg	36	36	41	41	57	57
Max. axial load	F _a	N	8000	8000	8000	8000	8000	8000
Max. moment load	M	Nm	360	360	360	360	360	360
Max. speed		rpm	120	250	72	170	24	80
Resolution		p/rev	4,320,000 (Incremental, sin/cos 1Vpp)					
Repeatability		arc-sec	±2.5					
Accuracy		arc-sec	±25/±10 ¹¹					
Axial runout	R _a	mm	0.03(0.005 ²)					
Radial runout	R _r	mm	0.03(0.015 ²)					
Height	H	mm	160	160	180	180	240	240

Note : ¹ After error mapping

² Optional

*All the specifications in the table are in ±10% of tolerance except dimensions.

1.3 DMY Series

The DMY series is designed with an intergrated, high resolution feedback system which is optimized to achieve high dynamic motion, high torque and high precision. The DMY series is a perfect fit for industries that require high precision.

- Outer rotating structure
- Integrated high resolution incremental/absolute feedback system
- High dynamic, torque and precision
- Maximum torque: 12~300 Nm
- Compatible with special environments



Model Numbers for DMY Series

Motor specification				Function
DMY	6	3	G	C

Series	DMY : External rotary type
Size	4 : External diameter Φ 110mm 6 : External diameter Φ 170mm A : External diameter Φ 270mm
Rotor height	3 : 30mm 5 : 50mm 8 : 80mm A : 100mm
Feedback system	: Absolute G : Incremental
Optional Specifications	: Standard C : Customized

1.3.1 DMY4 Series

DMY4 Dimensions

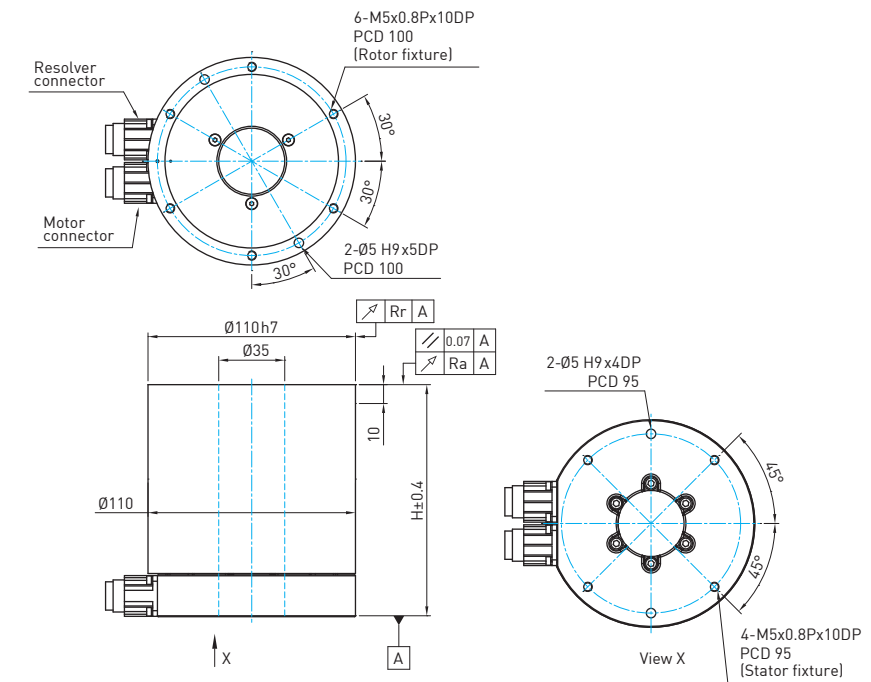


Table 1.6 DMY4 Specifications

	Symbol	Unit	DMY44	DMY48
Continuous torque	T _c	Nm	4	8
Continuous current	I _c	A _{rms}	2.6	2.6
Peak torque (Within 1s.)	T _p	Nm	12	24
Peak current (Within 1s.)	I _p	A _{rms}	7.8	7.8
Torque constant	K _t	Nm/A _{rms}	1.56	3.12
Electrical time constant	T _e	ms	5.2	5.4
Resistance (line to line at 25°C)	R ₂₅	Ω	2.57	4.5
Inductance (line to line)	L	mH	13.27	24.42
Number of poles	2 _p		14	14
Back emf constant (line to line)	K _v	V _{rms} /rad/s	0.9	1.8
Motor constant (line to line at 25°C)	K _m	Nm/ \sqrt{W}	0.8	1.2
Thermal resistance	R _{th}	K/W	2.9	1.6
Temperature sensor				PTC SNM100
Nominal input voltage		V _{DC}		500(600 ²⁾)
Inertia of rotating parts	J	kgm ²	0.0065	0.0085
Mass of motor	M _m	kg	5	7.5
Max. axial load	F _a	N	1000	1000
Max. moment load	M	Nm	30	30
Max. speed		rpm	300	300
Resolution		p/rev		920,000 (Absolute ¹⁾)
Repeatability		arc-sec		\pm 3
Accuracy		arc-sec		\pm 30
Axial runout	R _a	mm		0.03(0.005 ²⁾)
Radial runout	R _r	mm		0.03(0.015 ²⁾)
Height	H	mm	123	163

Note : ¹⁾ The motor should be matched with corresponding HIWIN drive.

²⁾ Optional

*All the specifications in the table are in \pm 10% of tolerance except dimensions.

1.3.2 DMY6 Series

DMY6 Dimensions

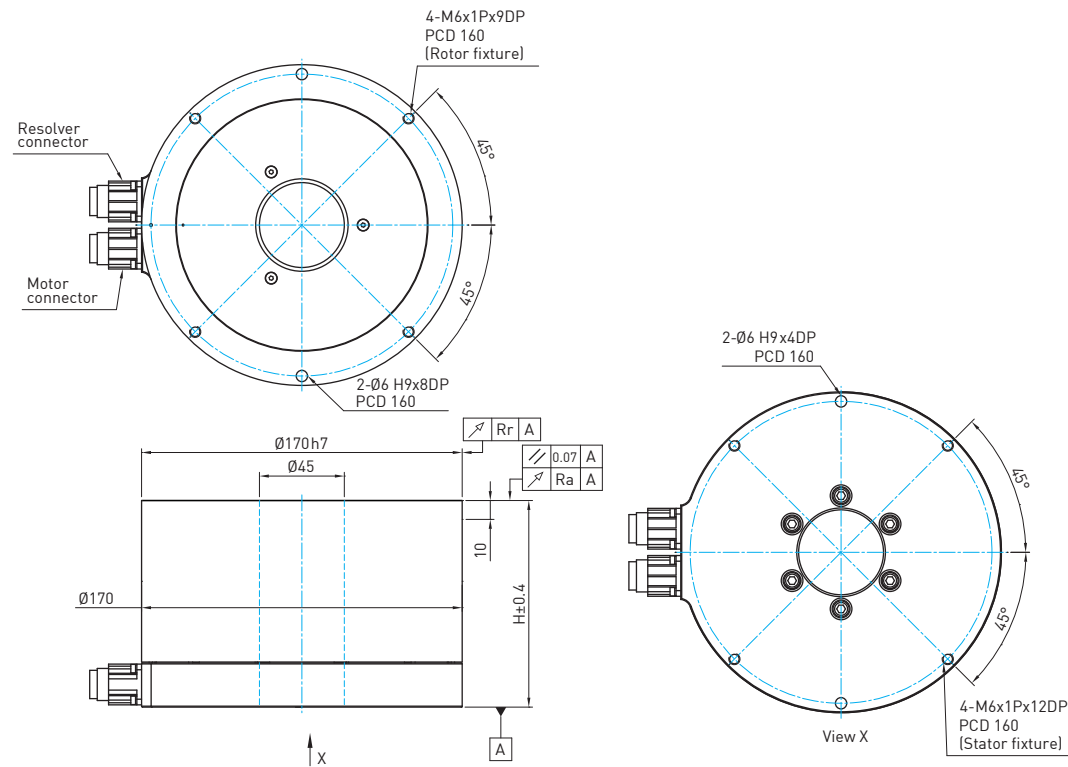


Table 1.7 DMY6 Specifications

	Symbol	Unit	DMY63G	DMY63	DMY65G	DMY65	DMY68G	DMY68
Continuous torque	T_c	Nm	8		16		24	
Continuous current	I_c	A_{rms}	3.8		3.8		3.8	
Peak torque (Within 1s.)	T_p	Nm	24		48		72	
Peak current (Within 1s.)	I_p	A_{rms}	12		12		12	
Torque constant	K_t	Nm/ A_{rms}	2.13		4.26		6.39	
Electrical time constant	T_e	ms	5.7		6.8		6.5	
Resistance (line to line at 25°C)	R_{25}	Ω	2		3.1		4.38	
Inductance (line to line)	L	mH	11.4		21		28.26	
Number of poles	$2p$		16		16		16	
Back emf constant (line to line)	K_v	$V_{rms}/(\text{rad/s})$	1.2		2.5		3.7	
Motor constant (line to line at 25°C)	K_m	Nm/\sqrt{W}	1.2		2		2.5	
Thermal resistance	R_{th}	K/W	1.7		1.1		0.8	
Temperature sensor			PTC SNM100					
Nominal input voltage	V_{dc}		500(600 ²)					
Inertia of rotating parts	J	kgm^2	0.019		0.026		0.033	
Mass of motor	M_m	kg	7.7		10.7		14.7	
Max. axial load	F_a	N	3700		3700		3700	
Max. moment load	M	Nm	60		60		60	
Max. speed		rpm	500	300	500	300	400	300
Resolution ¹⁾		p/rev	4,320,000	920,000	4,320,000	920,000	4,320,000	920,000
Repeatability		arc-sec	± 3					
Accuracy		arc-sec	± 30					
Axial runout	R_a	mm	0.03(0.005 ²⁾)					
Radial runout	R_r	mm	0.03(0.015 ²⁾)					
Height	H	mm	109.5		134.5		159.5	

Note : ¹⁾ Incremental type with sin/cos 1Vpp, absolute type should be matched with corresponding HIWIN drive.
²⁾ Optional
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.

1.3.3 DMYA Series

DMYA Dimensions

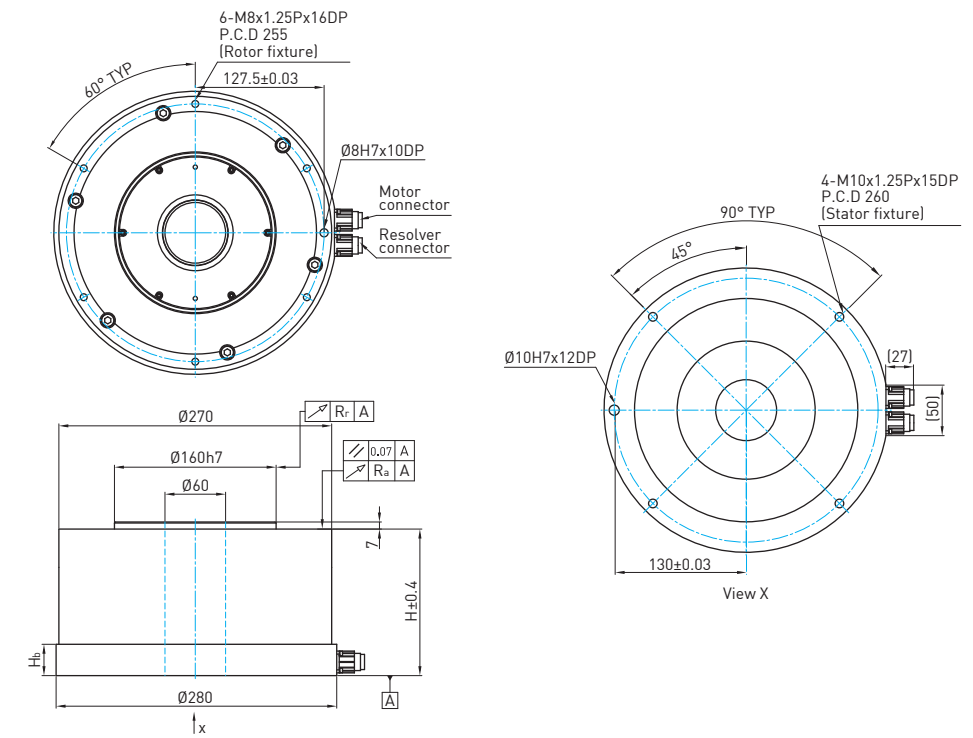


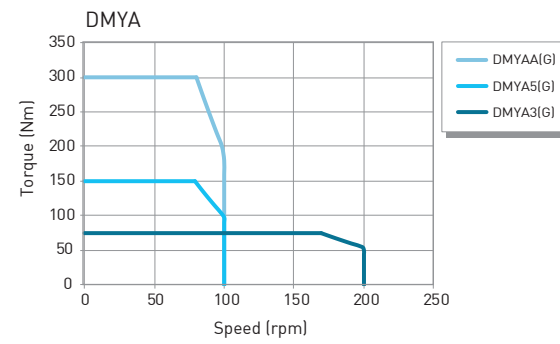
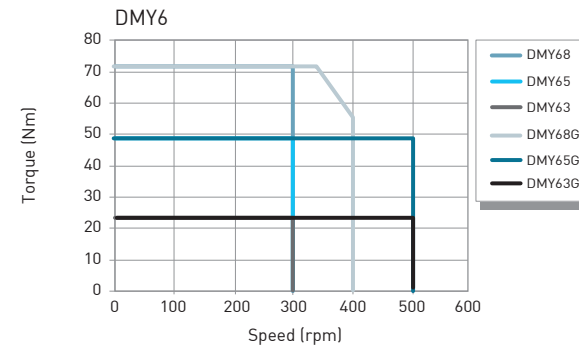
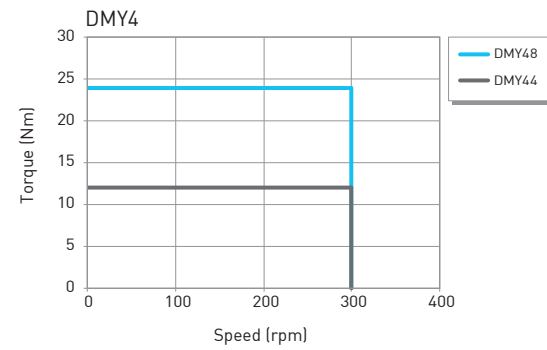
Table 1.8 DMYA Specifications

	Symbol	Unit	DMYA3G	DMYA5G	DMYA5	DMYAAG	DMYAA	
Continuous torque	T_c	Nm	25	50		100		
Continuous current	I_c	A_{rms}	2.2	2.2		4.4		
Peak torque (Within 1s.)	T_p	Nm	75	150		300		
Peak current (Within 1s.)	I_p	A_{rms}	6.6	6.6		13.2		
Torque constant	K_t	Nm/ A_{rms}	11.4	22.5		22.5		
Electrical time constant	T_e	ms	11.3	12.8		13.3		
Resistance (line to line at 25°C)	R_{25}	Ω	8.6	13.3		5.8		
Inductance (line to line)	L	mH	97	170		77		
Number of poles	$2p$		22	22		22		
Back emf constant (line to line)	K_v	$V_{rms}/(\text{rad/s})$	6.6	13		13		
Motor constant (line to line at 25°C)	K_m	Nm/\sqrt{W}	3.2	5		7.6		
Thermal resistance	R_{th}	K/W	1.2	0.8		0.4		
Temperature sensor			PTC SNM100					
Nominal input voltage	V_{dc}		500(600 ²)					
Inertia of rotating parts	J	kgm^2	0.254	0.32		0.44		
Mass of motor	M_m	kg	45	54		71		
Max. axial load	F_a	N	8000	8000		8000		
Max. moment load	M	Nm	240	240		240		
Max. speed		rpm	200	100		100		
Resolution ¹⁾		p/rev	4,320,000	4,320,000	920,000	4,320,000	920,000	
Repeatability		arc-sec	± 3					
Accuracy		arc-sec	± 30					
Axial runout	R_a	mm	0.03(0.005 ²⁾)					
Radial runout	R_r	mm	0.03(0.015 ²⁾)					
Height	H	mm	120	145		200		
Height of base	H_b	mm	31					

Note : ¹⁾ Incremental type with sin/cos 1Vpp, absolute type should be matched with corresponding HIWIN drive.
²⁾ Optional
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.

1.3.4 DMY Series T-N curves

(DC bus voltage=325V_{DC})



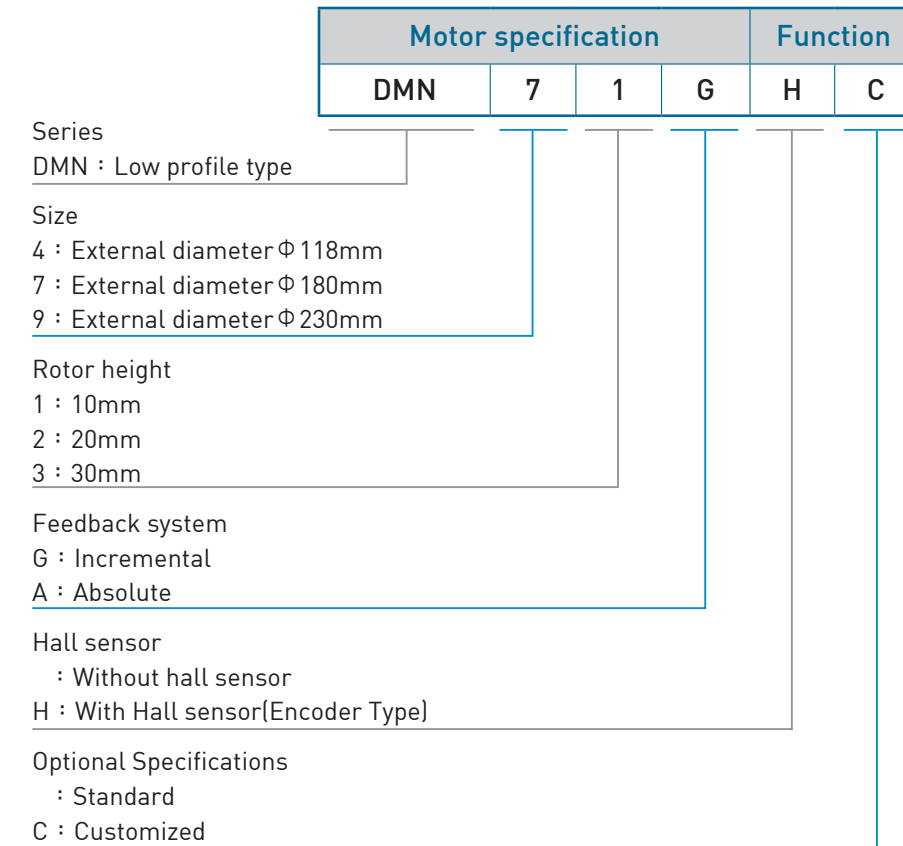
1.4 DMN Series

The DMN series is designed with an extremely low profile and a high resolution optical encoder optimized to achieve high dynamic motion, high torque and high precision. The DMN series is a perfect fit for industries that require high precision but less force.

- Outer rotating structure
- Space saving with Low profile design
- High resolution optical encoder
- Maximum torque: 4.2~39.6 Nm

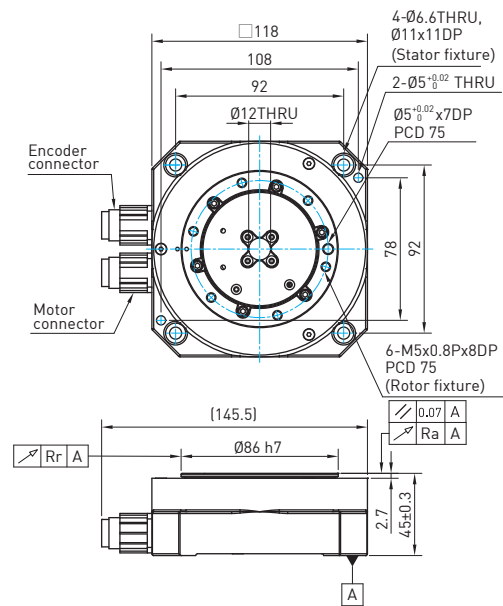


Model Numbers for DMN Series

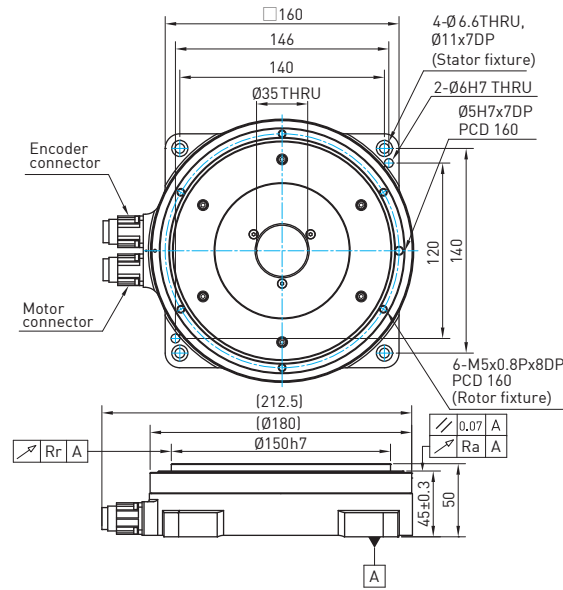


■ DMN Dimensions

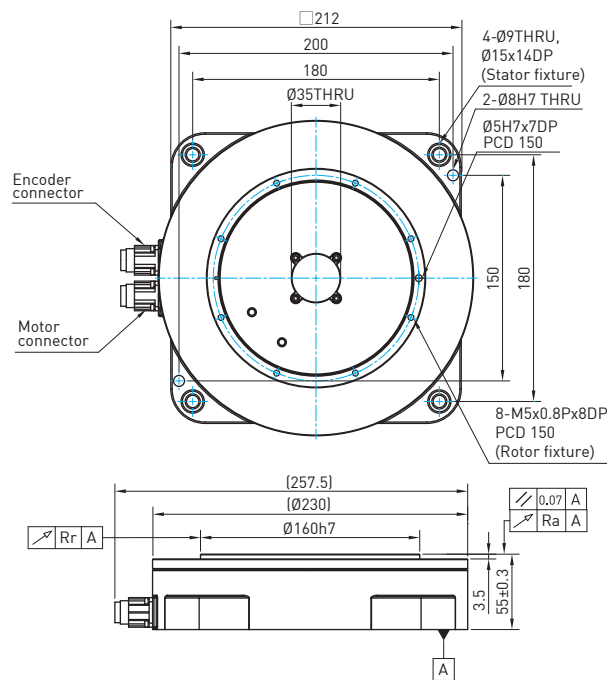
DMN42



DMN71



DMN93



1.4.1 DMN Incremental Series

Table 1.9 DMN Specifications

	Symbol	Unit	DMN42G	DMN71G	DMN93G
Continuous torque	T _c	Nm	1.4	3.7	13.2
Continuous current	I _c	A _{rms}	1.5	3.4	3.4
Peak torque (Within 1s.)	T _p	Nm	4.2	11.1	39.6
Peak current (Within 1s.)	I _p	A _{rms}	4.5	10.2	10.2
Torque constant	K _t	Nm/A _{rms}	0.97	1.09	3.9
Electrical time constant	T _e	ms	1.8	3.5	5.4
Resistance (line to line at 25°C)	R ₂₅	Ω	4.59	2.55	4.3
Inductance (line to line)	L	mH	8.18	9.02	23.2
Number of poles	2 _p		16	16	22
Back emf constant (line to line)	K _v	V _{rms} /[rad/s]	0.56	0.63	2.25
Motor constant(line to line at 25°C)	K _m	Nm/√W	0.4	0.6	1.5
Thermal resistance	R _{th}	K/W	4.84	1.95	1.01
Temperature sensor			PTC SNM100		
Nominal input voltage	V _{dc}		500(600 ²)		
Inertia of rotating parts	J	kgm ²	0.003	0.008	0.012
Mass of motor	M _m	kg	2	3.5	7.5
Max. axial load	F _a	N	600	1000	1000
Max. moment load	M	Nm	30	50	50
Max. speed		rpm	700	600	500
Resolution		p/rev	4,320,000	4,325,376	4,320,000
			(Incremental, sin/cos 1Vpp)		
Repeatability		arc-sec	±2.5	±2.5	±2.5
Accuracy		arc-sec	±45/±10 ¹⁾	±45/±10 ¹⁾	±45/±10 ¹⁾
Axial runout	R _a	mm	0.03(0.005 ²⁾)		
Radial runout	R _r	mm	0.03(0.015 ²⁾)		
Size	WxLxH	mm	118x118x45	160x160x50	212x212x55

Note : ¹⁾ After error mapping

²⁾ Optional

*All the specifications in the table are in ±10% of tolerance except dimensions.

1.4.2 DMN absolute Series

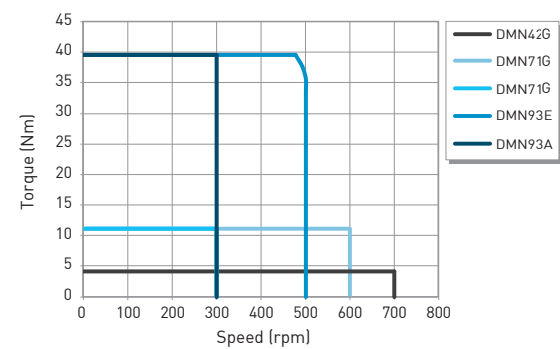
Table 1.10 DMN Specifications

	Symbol	Unit	DMN71A	DMN93A
Continuous torque	T _c	Nm	3.7	13.2
Continuous current	I _c	A _{rms}	3.4	3.4
Peak torque (Within 1s.)	T _p	Nm	11.1	39.6
Peak current (Within 1s.)	I _p	A _{rms}	10.2	10.2
Torque constant	K _t	Nm/A _{rms}	1.09	3.9
Electrical time constant	T _e	ms	4.1	5.4
Resistance (line to line at 25°C)	R ₂₅	Ω	2.22	4.3
Inductance (line to line)	L	mH	9.02	23.2
Number of poles	2 _p		16	22
Back emf constant (line to line)	K _v	V _{rms} /rad/s	0.63	2.25
Motor constant(line to line at 25°C)	K _m	Nm/√W	0.6	1.5
Thermal resistance	R _{th}	K/W	1.95	1.01
Temperature sensor			PTC SNM100	
Nominal input voltage		V _{DC}	500(600 ²⁾)	
Inertia of rotating parts	J	kgm ²	0.008	0.012
Mass of motor	M _m	kg	3.5	7.5
Max. axial load	F _a	N	1000	1000
Max. moment load	M	Nm	50	50
Max. speed		rpm	300	300
Resolution		p/rev	920,000 (Absolute ¹⁾)	
Repeatability		arc-sec	±2.5	±2.5
Accuracy		arc-sec	±30	±30
Axial runout	R _a	mm	0.03(0.005 ²⁾)	
Radial runout	R _r	mm	0.03(0.015 ²⁾)	
Size	WxLxH	mm	160x160x50	212x212x55

Note : ¹⁾ The motor should be matched with corresponding HIWIN drive.
²⁾ Optional
 *All the specifications in the table are in ±10% of tolerance except dimensions.

1.4.3 DMN Series T-N curves

(DC bus voltage=325V_{DC})



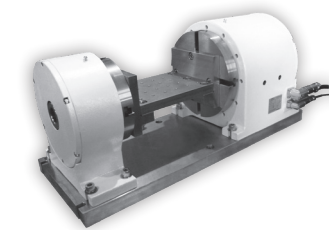
2. TMRW Torque Motor



The combination of a high torque stator and rotor meets the most demanding specifications in high precision industry. By using a water cooled design, high torque can be achieved.

- Water cooled
- Large hollow shaft
- Maximum torque up to 5020 Nm
- The concentricity of the stator and rotor will be calibrated before shipment

Example : Index table



Model Numbers for TMRW Series

Motor specification			Function		Winding Code
TMRW	4	7	L	C	XX

Series

TMRW : Water cooling type

External diameter of the stator's lamination stack

- 1 : Φ 140mm
- 2 : Φ 175mm
- 4 : Φ 210mm
- 7 : Φ 291mm
- A : Φ 360mm
- D : Φ 450mm
- G : Φ 530mm

Rotor height

- 3 : 30mm
- 5 : 50mm
- 7 : 70mm
- A : 100mm
- F : 150mm

Winding code

- : Standard
- L : Low Back emf

Optional Specifications

- : Standard
- C : Customized

: Standard

XX : Winding code

2.1 TMRW1 Series

2.1.1 TMRW1 Dimensions

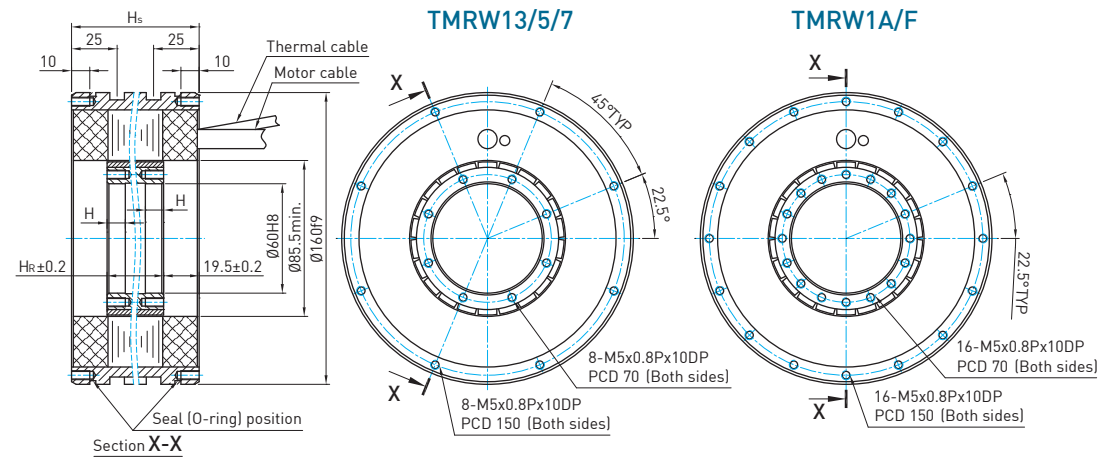
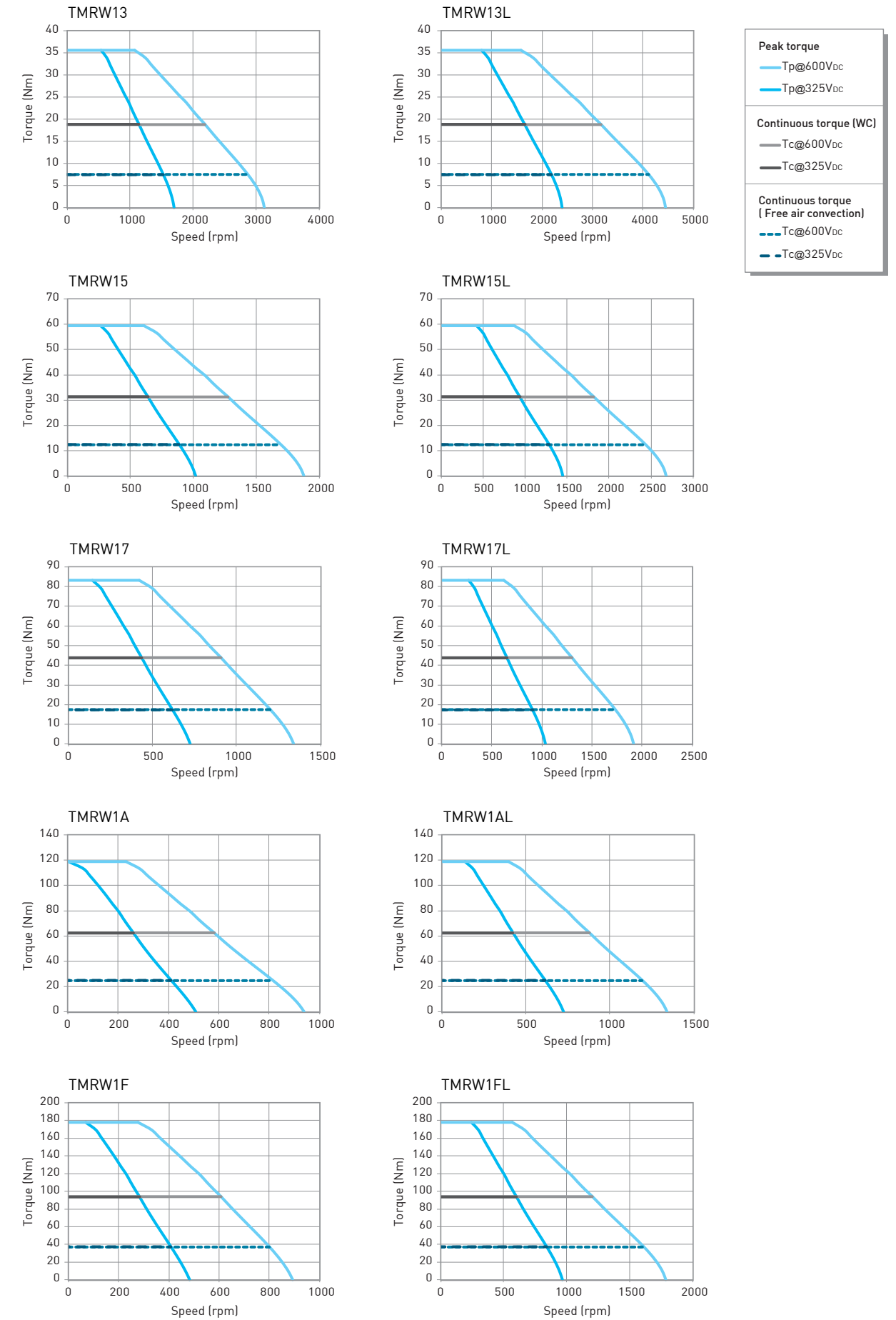


Table 2.1 TMRW1 Specifications

	Symbol	Unit	TMRW13	TMRW13L	TMRW15	TMRW15L	TMRW17	TMRW17L	TMRW1A	TMRW1AL	TMRW1F	TMRW1FL
Continuous torque	T_c	Nm	7.5	7.5	12.4	12.4	17.4	17.4	24.9	24.9	37.3	37.3
Continuous current	I_c	Arms	4	5.7	4	5.7	4	5.7	4	5.7	5.7	11.4
Continuous torque (WC)	T_{cw}	Nm	18.8	18.8	31.3	31.3	43.8	43.8	62.5	62.5	93.8	93.8
Continuous current (WC)	I_{cw}	Arms	10	14.4	10	14.4	10	14.4	10	14.4	14.4	28.8
Stall torque	T_s	Nm	5	5	9	9	12	12	17	17	26	26
Stall current	I_s	Arms	2.8	4	2.8	4	2.8	4	2.8	4	4	8
Stall torque (WC)	T_{sw}	Nm	13	13	22	22	31	31	44	44	66	66
Stall current (WC)	I_{sw}	Arms	7	10.1	7	10.1	7	10.1	7	10.1	10.1	20.2
Peak torque(Within 1s.)	T_p	Nm	35.6	35.6	59.4	59.4	83.1	83.1	118.8	118.8	178.1	178.1
Peak current(Within 1s.)	I_p	Arms	27	38.9	27	38.9	27	38.9	27	38.9	38.9	77.8
Torque constant	K_t	Nm/Arms	1.87	1.32	3.1	2.18	4.36	3.06	6.23	4.36	6.55	3.27
Electrical time constant	T_e	ms	3.2	3.2	3.6	3.4	3.6	4.1	4	4.1	3.9	4.3
Resistance (line to line at 25°C)	R_{25}	Ω	3.3	1.6	4.5	2.36	6.2	2.9	7.7	3.8	5.5	1.37
Inductance (line to line)	L	mH	10.5	5.1	16	8	22.5	11.9	31	15.5	21.7	5.9
Number of poles	$2p$		22									
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	1.08	0.76	1.8	1.26	2.52	1.76	3.6	2.52	3.78	1.89
Motor constant (at 25°C)	K_m	Nm/\sqrt{W}	0.84	0.85	1.19	1.16	1.43	1.46	1.83	1.83	2.28	2.28
Thermal resistance	R_{th}	K/W	1.2	1.22	0.88	0.83	0.64	0.67	0.51	0.51	0.35	0.36
Thermal resistance (WC)	R_{thw}	K/W	0.192	0.191	0.141	0.129	0.102	0.105	0.082	0.08	0.056	0.056
Thermal sensor			PTC SNM100+SNM120+Pt1000									
Max. DC BUS	V_{dc}		750									
Inertia of rotor	J	kgm^2	0.001	0.001	0.0016	0.0016	0.0023	0.0023	0.0033	0.0033	0.0049	0.0049
Max. speed at conti. Torque		rpm	2800	4000	1600	2400	1150	1700	800	1170	760	1600
Max. speed at conti. Torque (WC)		rpm	2200	3200	1200	1750	830	1300	580	870	540	1200
Max. speed at max. Torque		rpm	1000	1600	600	830	400	610	230	390	210	560
Rated speed	ω_n	rpm	820	820	820	820	820	820	820	820	800	820
Mass of rotor	M_r	kg	0.6	0.6	1	1	1.4	1.4	2	2	3	3
Mass of stator	M_s	kg	3.7	3.7	5.1	5.1	6.2	6.2	8.6	8.6	12.2	12.2
Height of stator	H_s	mm	70	70	90	90	110	110	140	140	190	190
Height of rotor	H_r	mm	31	31	51	51	71	71	101	101	151	151
Height	H	mm	10	10	15	15	15	15	15	15	15	15

Note : WC : water cooled
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.
¹⁾The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.

2.1.2 TMRW1 Series T-N curves



2.2 TMRW2 Series

2.2.1 TMRW2 Dimensions

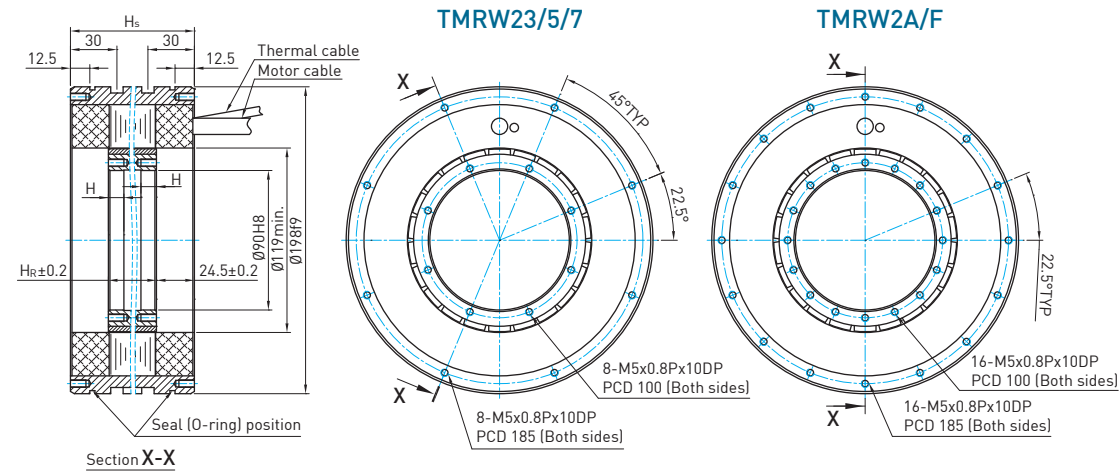
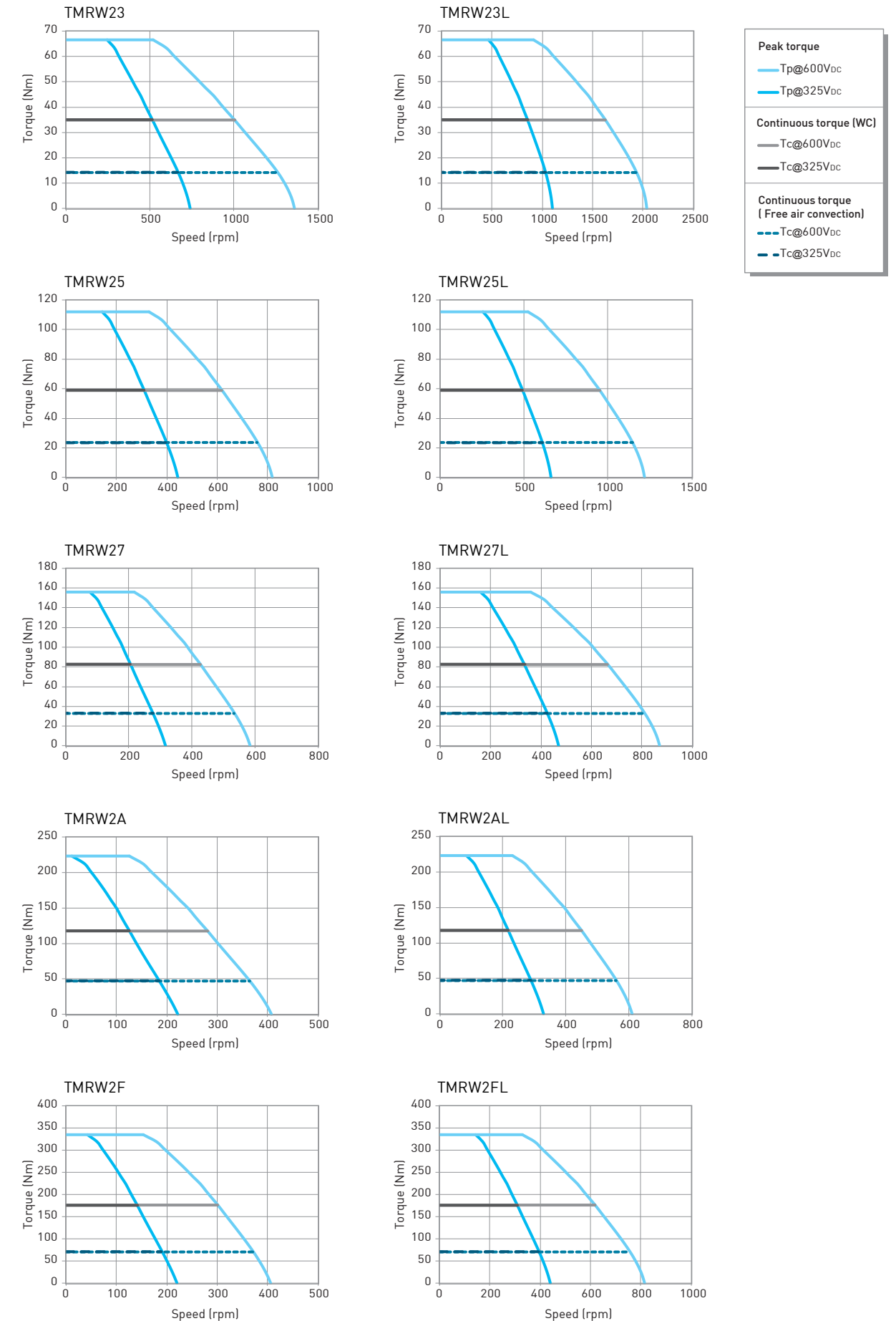


Table 2.2 TMRW2 Specifications

	Symbol	Unit	TMRW23	TMRW23L	TMRW25	TMRW25L	TMRW27	TMRW27L	TMRW2A	TMRW2AL	TMRW2F	TMRW2FL
Continuous torque	T_c	Nm	14.2	14.2	23.6	23.6	33	33	47.3	47.3	71	71
Continuous current	I_c	Arms	3.3	4.9	3.3	4.9	3.3	4.9	3.3	4.9	4.9	9.9
Continuous torque (WC)	T_{cw}	Nm	35	35	59	59	82.5	82.5	117.5	117.5	176	176
Continuous current (WC)	I_{cw}	Arms	8.3	12.3	8.3	12.3	8.3	12.3	8.3	12.3	12.3	24.6
Stall torque	T_s	Nm	10	10	17	17	23	23	33	33	50	50
Stall current	I_s	Arms	2.3	3.4	2.3	3.4	2.3	3.4	2.3	3.4	3.4	6.9
Stall torque (WC)	T_{sw}	Nm	25	25	41	41	58	58	82	82	123	123
Stall current (WC)	I_{sw}	Arms	5.8	8.6	5.8	8.6	5.8	8.6	5.8	8.6	8.6	17.2
Peak torque (Within 1s.)	T_p	Nm	66.5	66.5	112	112	156	156	223	223	334.5	334.5
Peak current (Within 1s.)	I_p	Arms	22.3	33.2	22.3	33.2	22.3	33.2	22.3	33.2	33.2	66.4
Torque constant	K_t	Nm/Arms	4.29	2.8	7.16	4.8	10.03	6.72	14.32	9.6	14.39	7.2
Electrical time constant	T_e	ms	6.4	6.1	6.8	6.5	6.5	6.5	7.4	7.4	7.8	6.9
Resistance (line to line at 25°C)	R_{25}	Ω	4.3	1.9	5.7	2.5	7.8	3.5	9.6	4.4	6	1.5
Inductance (line to line)	L	mH	27.5	11.5	39	16.23	50.7	22.72	70.8	32.46	47	10.4
Number of poles	$2p$		22									
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	2.48	1.6	4.13	2.77	5.79	3.88	8.27	5.54	8.31	4.15
Motor constant (at 25°C)	K_m	Nm/\sqrt{W}	1.68	1.72	2.45	2.49	2.92	2.94	3.78	3.76	4.83	4.78
Thermal resistance	R_{th}	K/W	1.35	1.39	1.02	1.06	0.75	0.75	0.61	0.53	0.44	0.43
Thermal resistance (WC)	R_{thw}	K/W	0.214	0.22	0.161	0.167	0.118	0.12	0.096	0.095	0.07	0.07
Thermal sensor			PTC SNM100+SNM120+Pt1000									
Max. DC BUS	V_{dc}		750									
Inertia of rotor	J	kgm^2	0.0027	0.0027	0.0045	0.0045	0.0063	0.0063	0.009	0.009	0.013	0.013
Max. speed at conti. Torque		rpm	1260	1900	750	1130	525	800	360	550	360	740
Max. speed at conti. Torque (WC)		rpm	1060	1600	610	950	420	660	280	440	275	610
Max. speed at max. Torque		rpm	590	900	330	525	210	360	125	225	120	330
Rated speed	ω_n	rpm	820	820	750	820	530	810	360	560	370	760
Mass of rotor	M_r	kg	0.95	0.95	1.6	1.6	2.2	2.2	3.2	3.2	4.8	4.8
Mass of stator	M_s	kg	6.1	6.1	8.4	8.4	10.2	10.2	14.2	14.2	20.1	20.1
Height of stator	H_s	mm	80	80	100	100	120	120	150	150	200	200
Height of rotor	H_r	mm	31	31	51	51	71	71	101	101	151	151
Height	H	mm	10	10	15	15	15	15	15	15	15	15

Note : WC : water cooled
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.
¹The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.

2.2.2 TMRW2 Series T-N curves



2.4 TMRW7 Series

2.4.1 TMRW7 Dimensions

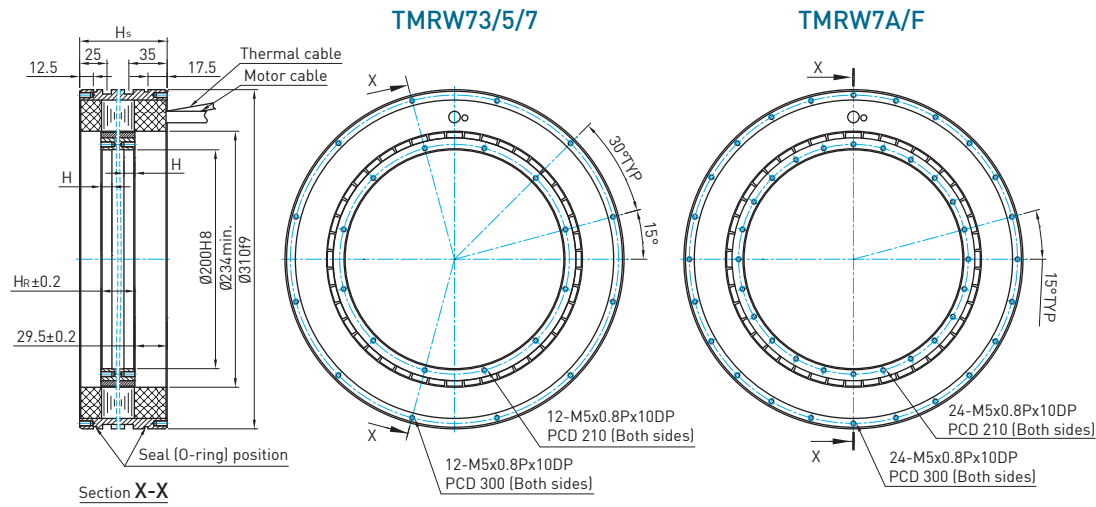
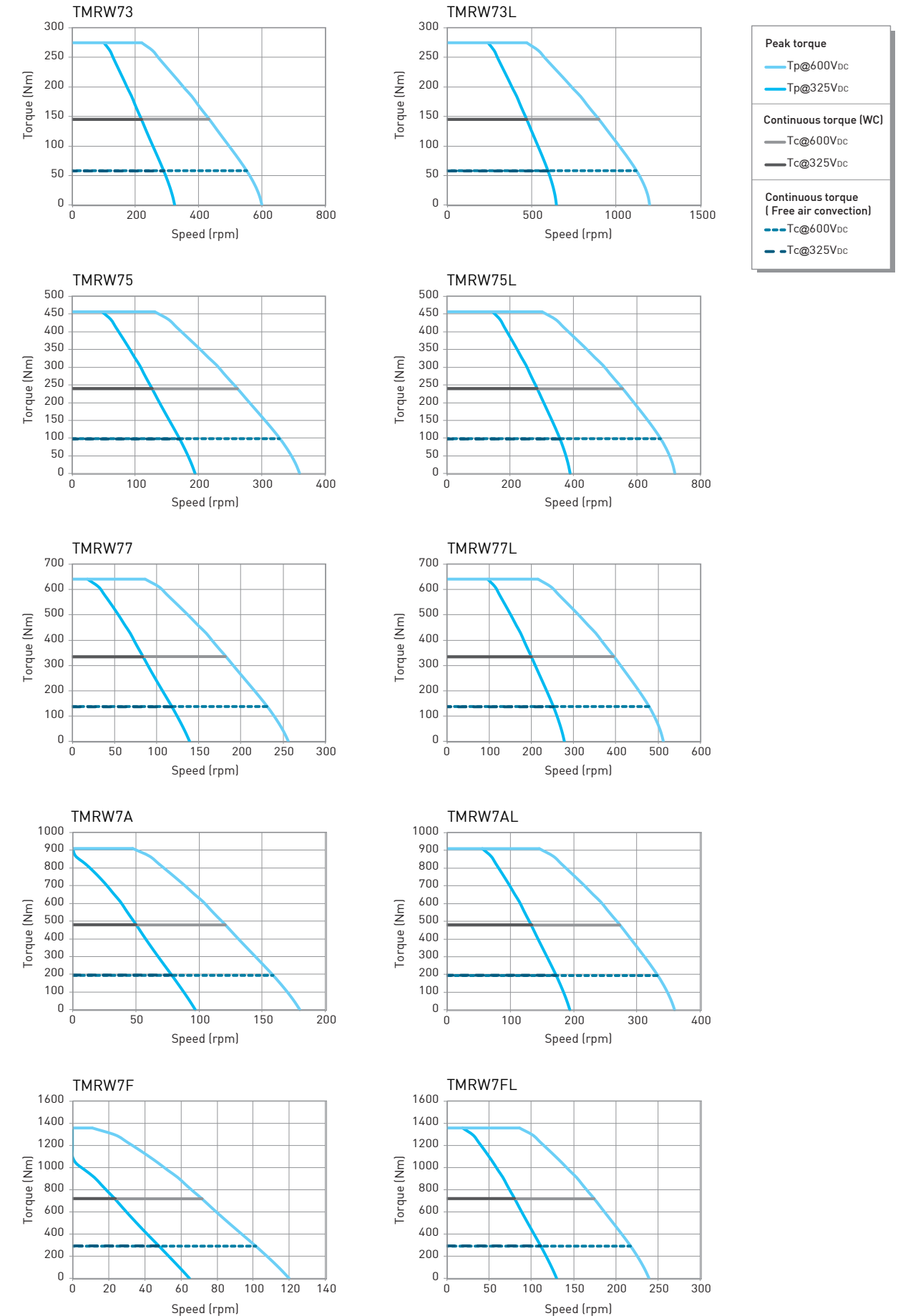


Table 2.4 TMRW7 Specifications

	Symbol	Unit	TMRW73	TMRW73L	TMRW75	TMRW75L	TMRW77	TMRW77L	TMRW7A	TMRW7AL	TMRW7F	TMRW7FL
Continuous torque	T_c	Nm	58	58	98	98	137	137	195	195	293	293
Continuous current	I_c	Arms	6	12	6	12	6	12	6	12	6	12
Continuous torque (WC)	T_{cw}	Nm	145	145	240	240	335	335	480	480	720	720
Continuous current (WC)	I_{cw}	Arms	15	30	15	30	15	30	15	30	15	30
Stall torque	T_s	Nm	41	41	69	69	96	96	137	137	205	205
Stall current	I_s	Arms	4.2	8.4	4.2	8.4	4.2	8.4	4.2	8.4	4.2	8.4
Stall torque (WC)	T_{sw}	Nm	102	102	168	168	235	235	336	336	504	504
Stall current (WC)	I_{sw}	Arms	10.5	21	10.5	21	10.5	21	10.5	21	10.5	21
Peak torque(Within 1s.)	T_p	Nm	275	275	456	456	640	640	910	910	1360	1360
Peak current(Within 1s.)	I_p	Arms	40.5	81	40.5	81	40.5	81	40.5	81	40.5	81
Torque constant	K_t	Nm/Arms	9.77	4.89	16.3	8.15	22.8	11.4	32.56	16.28	48.85	24.45
Electrical time constant	T_e	ms	5	4.9	5.6	5.6	5.6	5.6	5.6	6	5.8	
Resistance (line to line at 25°C)	R_{25}	Ω	3	0.81	4.19	1.05	5.52	1.38	7.52	1.88	10	2.5
Inductance (line to line)	L	mH	15	4	23.45	5.86	30.9	7.73	42.07	10.52	60	14.6
Number of poles	$2p$		44									
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	5.64	2.82	9.4	4.7	13.2	6.6	18.8	9.4	28.2	14.1
Motor constant (at 25°C)	K_m	Nm/\sqrt{W}	4.56	4.38	6.52	6.51	7.92	7.94	9.68	9.68	12.61	12.61
Thermal resistance	R_{th}	K/W	0.59	0.54	0.42	0.42	0.32	0.32	0.23	0.23	0.18	0.18
Thermal resistance (WC)	R_{thw}	K/W	0.094	0.087	0.067	0.067	0.051	0.051	0.037	0.037	0.028	0.028
Thermal sensor			PTC SNM100+SNM120+Pt1000									
Max. DC BUS	V_{dc}		750									
Inertia of rotor	J	kgm^2	0.023	0.023	0.039	0.039	0.059	0.059	0.079	0.079	0.11	0.11
Max. speed at conti. Torque		rpm	560	1110	325	675	225	475	160	325	100	210
Max. speed at conti. Torque (WC)		rpm	470	890	270	580	180	400	115	275	72	170
Max. speed at max. Torque		rpm	270	460	150	340	90	230	50	150	13	85
Rated speed	ω_n	rpm	410	410	320	410	230	410	150	330	100	210
Mass of rotor	M_r	kg	2.5	2.5	4.1	4.1	5.7	5.7	8.1	8.1	12.1	12.1
Mass of stator	M_s	kg	14.2	14.2	18.9	18.9	23.7	23.7	30.9	30.9	43.6	43.6
Height of stator	H_s	mm	80	80	100	100	120	120	150	150	200	200
Height of rotor	H_r	mm	31	31	51	51	71	71	101	101	151	151
Height	H	mm	10	10	15	15	15	15	15	15	15	15

Note : WC : water cooled
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.
¹⁾The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.

2.4.2 TMRW7 Series T-N curves



2.5 TMRWASeries

2.5.1 TMRWA Dimensions

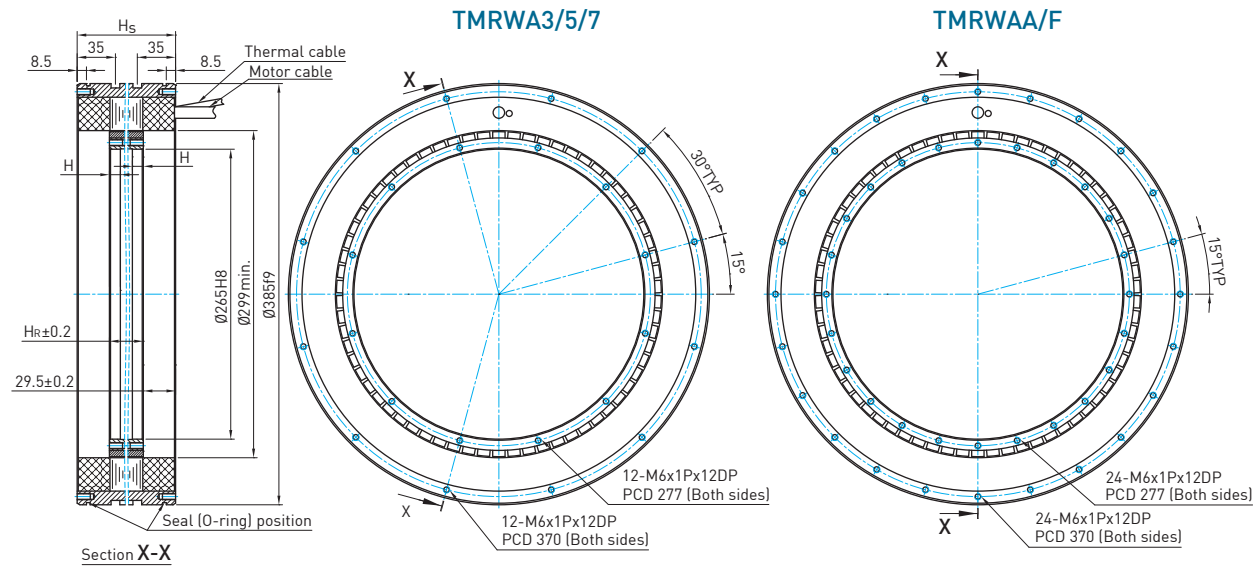


Table 2.5 TMRWA Specifications

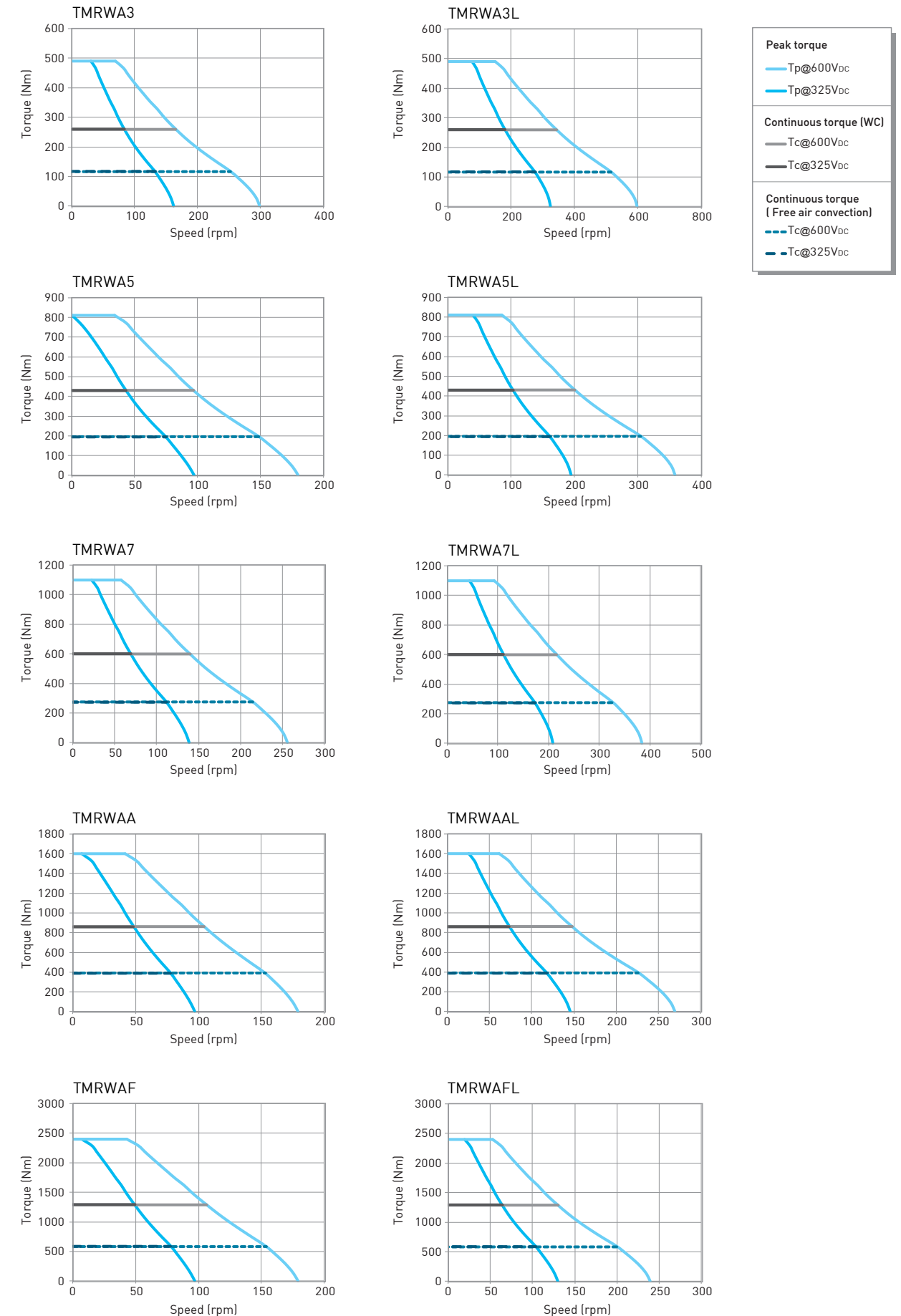
	Symbol	Unit	TMRWA3	TMRWA3L	TMRWA5	TMRWA5L	TMRWA7	TMRWA7L	TMRWAA	TMRWAAAL	TMRWAF	TMRWAFAL
Continuous torque	T_c	Nm	117	117	195	195	274	274	390	390	585	585
Continuous current	I_c	Arms	6	12	6	12	12	18	12	18	18	24
Continuous torque (WC)	T_{cw}	Nm	260	260	430	430	600	600	860	860	1290	1290
Continuous current (WC)	I_{cw}	Arms	15	30	15	30	30	45	30	45	45	60
Stall torque	T_s	Nm	82	82	137	137	192	192	273	273	410	410
Stall current	I_s	Arms	4.2	8.4	4.2	8.4	8.4	12.6	8.4	12.6	12.6	16.8
Stall torque (WC)	T_{sw}	Nm	182	182	301	301	420	420	602	602	903	903
Stall current (WC)	I_{sw}	Arms	10.5	21	10.5	21	21	31.5	21	31.5	31.5	42
Peak torque(Within 1s.)	T_p	Nm	490	490	810	810	1100	1100	1600	1600	2400	2400
Peak current(Within 1s.)	I_p	Arms	40.5	81	40.5	81	81	121.5	81	121.5	121.5	162
Torque constant	K_t	Nm/ Arms	19.57	9.79	32.6	16.32	22.84	15.23	32.63	21.75	32.63	24.45
Electrical time constant	T_e	ms	7.9	10	7.5	7.5	8.4	8.2	8.1	8	8.6	10
Resistance (line to line at 25°C)	R_{25}	Ω	4.8	0.89	7.1	1.78	2.2	0.98	2.97	1.32	1.98	1
Inductance (line to line)	L	mH	38.15	8.93	53.4	13.35	18.5	8	24.2	10.5	17	10
Number of poles	$2p$		66									
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	11.3	5.65	18.8	9.42	13.18	8.79	18.83	12.55	18.83	14.12
Motor constant (at 25°C)	K_m	Nm/\sqrt{W}	8.43	8.44	9.96	9.94	12.57	12.56	15.4	15.4	18.86	19.9
Thermal resistance	R_{th}	K/W	0.37	0.49	0.25	0.25	0.2	0.2	0.15	0.15	0.1	0.11
Thermal resistance (WC)	R_{thw}	K/W	0.059	0.079	0.04	0.04	0.032	0.032	0.024	0.024	0.016	0.018
Thermal sensor			PTC SNM100+SNM120+Pt1000									
Max. DC BUS	V_{dc}		750									
Inertia of rotor	J	kgm^2	0.065	0.065	0.1	0.1	0.15	0.15	0.21	0.21	0.32	0.32
Max. speed at conti. Torque		rpm	250	510	140	300	210	320	140	220	140	200
Max. speed at conti. Torque (WC)		rpm	160	340	90	200	135	210	90	140	92	125
Max. speed at max. Torque		rpm	65	150	35	80	55	90	35	60	35	50
Rated speed	ω_n	rpm	240	270	140	270	210	270	150	230	150	200
Mass of rotor	M_r	kg	3.1	3.1	5.1	5.1	7.1	7.1	10.2	10.2	15.3	15.3
Mass of stator	M_s	kg	20.1	20.1	26.8	26.8	34.5	34.5	44.9	44.9	63.1	63.1
Height of stator	H_s	mm	90	90	110	110	130	130	160	160	210	210
Height of rotor	H_r	mm	31	31	51	51	71	71	101	101	151	151
Height	H	mm	10	10	15	15	15	15	15	15	15	15

Note : WC : water cooled

*All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.

¹⁾The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.

2.5.2 TMRWA Series T-N curves



2.6 TMRWD Series

2.6.1 TMRWD Dimensions

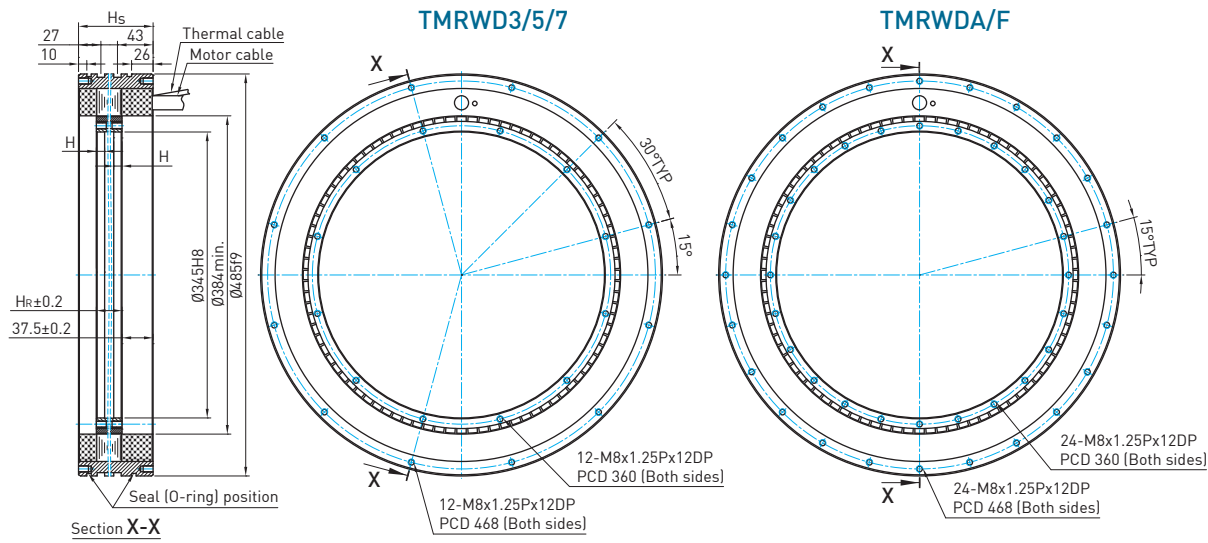
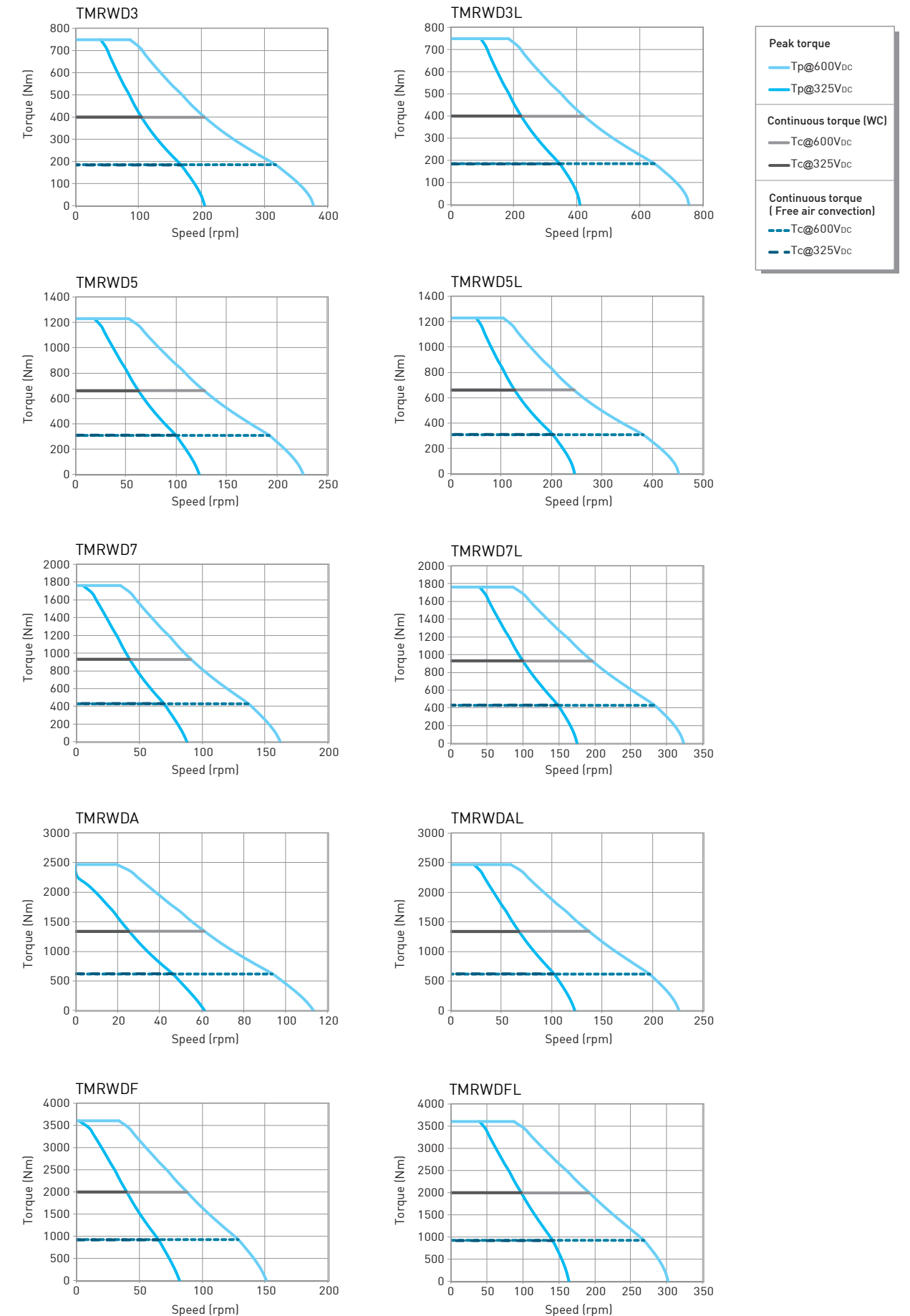


Table 2.6 TMRWD Specifications

	Symbol	Unit	TMRWD3	TMRWD3L	TMRWD5	TMRWD5L	TMRWD7	TMRWD7L	TMRWDA	TMRWDAL	TMRWDF	TMRWDFL
Continuous torque	T_c	Nm	185	185	310	310	430	430	619	619	925	925
Continuous current	I_c	Arms	12	24	12	24	12	24	12	24	24	48
Continuous torque (WC)	T_{cw}	Nm	400	400	660	660	930	930	1340	1340	2000	2000
Continuous current (WC)	I_{cw}	Arms	30	60	30	60	30	60	30	60	60	120
Stall torque	T_s	Nm	130	130	217	217	301	301	433	433	648	648
Stall current	I_s	Arms	8.4	16.8	8.4	16.8	8.4	16.8	8.4	16.8	16.8	33.6
Stall torque (WC)	T_{sw}	Nm	280	280	462	462	651	651	938	938	1400	1400
Stall current (WC)	I_{sw}	Arms	21	42	21	42	21	42	21	42	42	84
Peak torque (Within 1s.)	T_p	Nm	750	750	1230	1230	1760	1760	2470	2470	3600	3600
Peak current (Within 1s.)	I_p	Arms	81	162	81	162	81	162	81	162	162	324
Torque constant	K_t	Nm/Arms	15.48	7.74	25.8	12.9	36.11	18.1	51.6	25.8	38.7	19.35
Electrical time constant	T_e	ms	7.1	7.1	7.1	8.1	7.1	7.1	7	8.3	8.5	
Resistance (line to line at 25°C)	R_{25}	Ω	1.57	0.39	2.31	0.59	3.04	0.76	4.14	1.04	1.35	0.33
Inductance (line to line)	L	mH	11.13	2.78	16.3	4.78	21.5	5.38	29.3	7.33	11.2	2.8
Number of poles	$2p$		88									
Back emf constant (line to line)	K_v	$V_{rms}/(rad/s)$	8.94	4.47	14.9	7.45	20.85	10.43	29.8	14.9	22.35	11.18
Motor constant (at 25°C)	K_m	Nm/\sqrt{W}	10.05	10.08	13.88	13.73	16.78	16.78	20.7	20.65	27.08	27.39
Thermal resistance	R_{th}	K/W	0.28	0.28	0.19	0.19	0.14	0.14	0.11	0.11	0.08	0.08
Thermal resistance (WC)	R_{thw}	K/W	0.045	0.045	0.030	0.030	0.023	0.023	0.017	0.017	0.013	0.013
Thermal sensor			PTC SNM100+SNM120+Pt1000									
Max. DC BUS	V_{dc}		750									
Inertia of rotor	J	kgm^2	0.16	0.16	0.26	0.26	0.37	0.37	0.53	0.53	0.8	0.8
Max. speed at conti. Torque		rpm	300	630	180	390	130	275	90	190	125	260
Max. speed at conti. Torque (WC)		rpm	200	420	120	250	85	190	60	133	80	190
Max. speed at max. Torque		rpm	85	175	50	115	30	85	18	60	30	80
Rated speed	ω_n	rpm	200	200	190	200	130	200	90	190	120	200
Mass of rotor	M_r	kg	5.5	5.5	9.2	9.2	12.8	12.8	18.3	18.3	22	22
Mass of stator	M_s	kg	22.8	22.8	38	38	53.2	53.2	76	76	90	90
Height of stator	H_s	mm	90	90	110	110	130	130	160	160	210	210
Height of rotor	H_r	mm	31	31	51	51	71	71	101	101	151	151
Height	H	mm	10	10	15	15	15	15	15	15	15	15

Note : WC : water cooled
 *All the specifications in the table are in $\pm 10\%$ of tolerance except dimensions.
¹⁾The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.

2.6.2 TMRWD Series T-N curves



2.7 TMRWG Series

2.7.1 TMRWG Dimensions

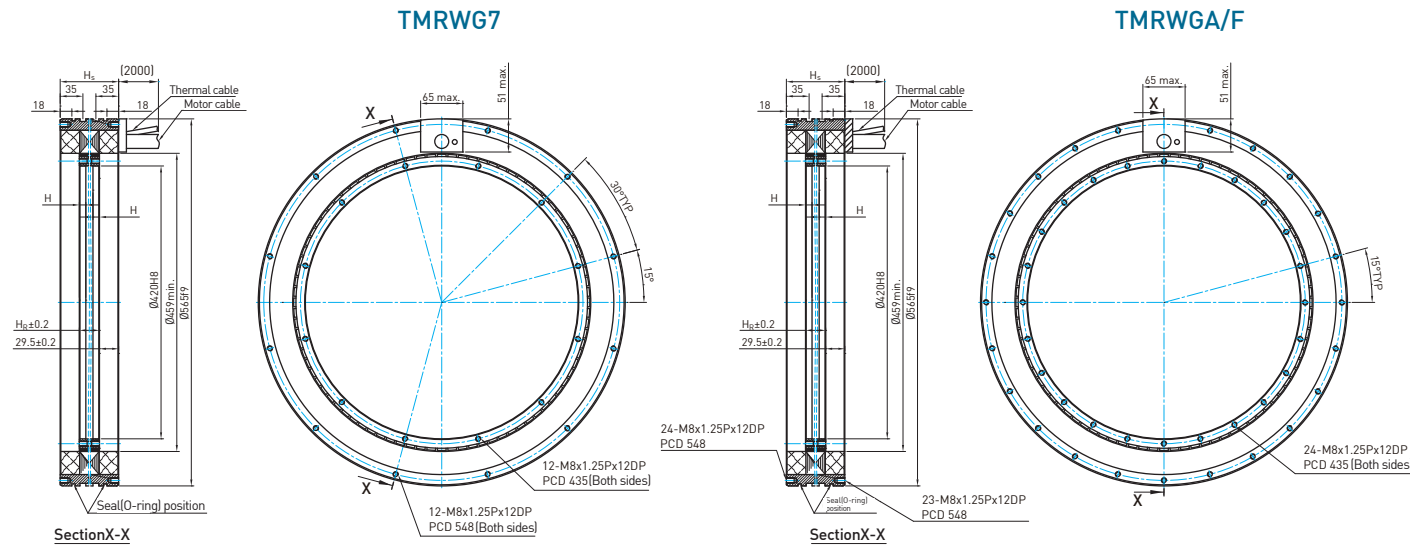


Table 2.7 TMRWG Specifications

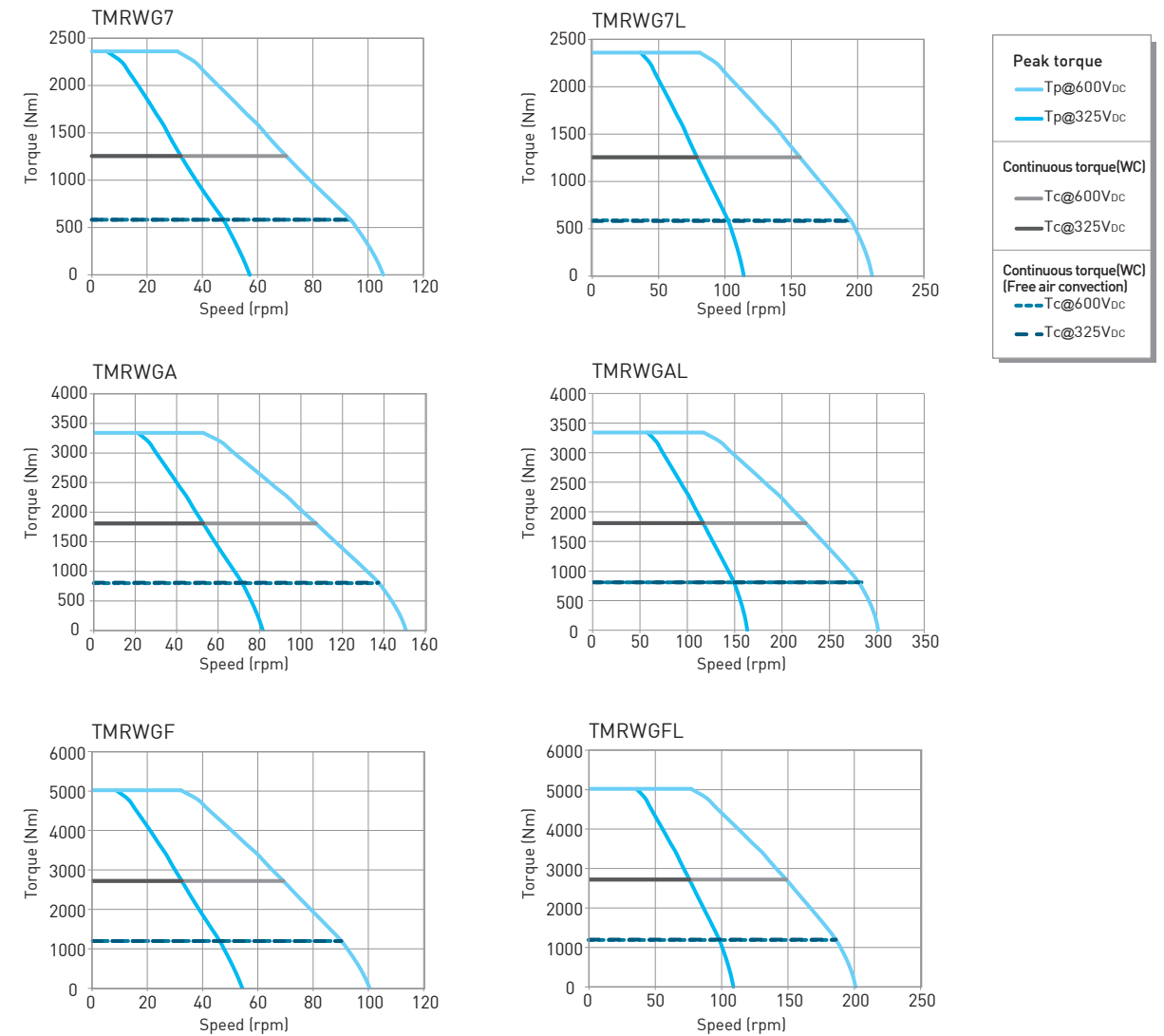
	Symbol	Unit	TMRWG7	TMRWG7L	TMRWGA	TMRWGA L	TMRWGF	TMRWGF L
Continuous torque	T _c	Nm	582	582	810	810	1200	1200
Continuous current	I _c	A _{rms}	10.5	21	21	42	21	42
Continuous torque (WC)	T _{cw}	Nm	1255	1255	1810	1810	2720	2720
Continuous current (WC)	I _{cw}	A _{rms}	26.3	52.5	52.5	105	52.5	105
Stall torque	T _s	Nm	407	407	567	567	840	840
Stall current	I _s	A _{rms}	7.4	14.7	14.7	29.4	14.7	29.4
Stall torque (WC)	T _{sw}	Nm	879	879	1267	1267	1904	1904
Stall current (WC)	I _{sw}	A _{rms}	18.4	36.8	36.8	73.5	36.8	73.5
Peak torque(for 1s)	T _p	Nm	2360	2360	3340	3340	5020	5020
Peak current(for 1s)	I _p	A _{rms}	71	142	142	284	142	284
Torque constant	K _t	Nm/A _{rms}	55.4	27.7	38.8	19.4	57	28.5
Electrical time constant	T _e	ms	7.8	7.2	8	8.3	8.9	8.8
Resistance (line to line at 25°C)	R ₂₅	Ω	3.3	0.83	1.06	0.27	1.46	0.37
Inductance (line to line)	L	mH	25.7	6	8.5	2.23	13	3.25
Number of poles	2 _p		88					
Back emf constant (line to line)	K _v	V _{rms} /rad/s	32	16	22.4	11.2	33.6	16.8
Motor constant (at 25°C)	K _m	Nm/√W	24.91	24.84	30.59	30.3	38.61	38.35
Thermal resistance	R _{th}	K/W	0.17	0.17	0.14	0.13	0.1	0.1
Thermal resistance (WC)	R _{thw}	K/W	0.028	0.028	0.022	0.021	0.016	0.016
Thermal sensor			PTC SNM100+SNM120+Pt1000					
Max. DC BUS	V _{dc}		750					
Inertia of rotor	J	kgm ²	0.619	0.619	0.904	0.904	1.38	1.38
Max. speed at conti. Torque		rpm	90	190	130	280	90	180
Max. speed at conti. Torque (WC)		rpm	70	150	100	220	60	140
Max. speed at max. Torque		rpm	30	80	50	110	30	70
Rated speed	ω _n	rpm	90	190	130	200	90	180
Mass of rotor	M _r	kg	13.3	13.3	19	19	28.3	28.3
Mass of stator	M _s	kg	61.1	61.1	75	75	107.5	107.5
Height of stator	H _s	mm	130	130	160	160	210	210
Height of rotor	H _r	mm	71	71	101	101	151	151
Height	H	mm	15	15	15	15	15	15

Note : WC : water cooled

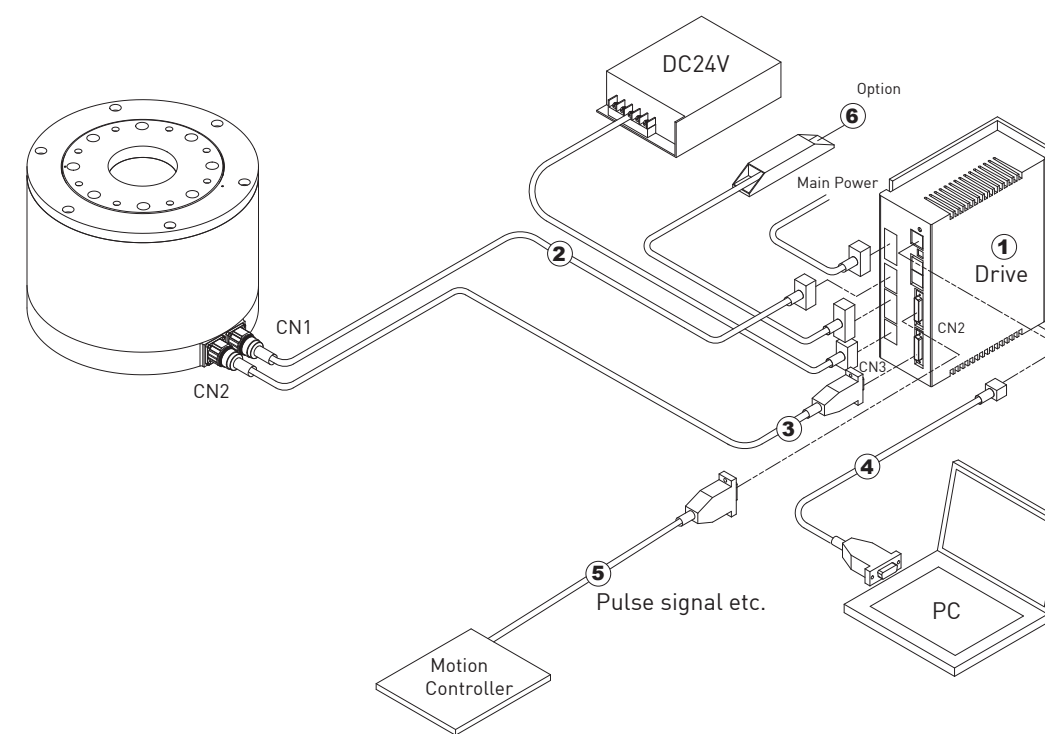
*All the specifications in the table are in ±10% of tolerance except dimensions.



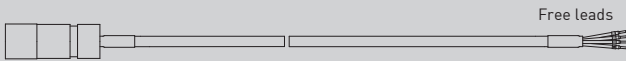
¹The rated speed is the maximum speed which the motor can run continuously without rest. More information please refer to Appendix B:Glossary.






2.7.2 TMRWG Series T-N curves



3. Drives and Accessories



Part name	Model	Connector	Description
① Drive	D1-36-S2		For Incremental feedback types 
	D1-36-S4		For absolute feedback types 
② Motor Power Cable	LMAC□□F	Motor Connects (U,V,W)	For Direct Drive motors  Intercontec Model:BSTA880FR0886201A000

Part name	Model	Connector	Description
③ Position Signal Cable	LMACE□□AA	CN3	For incremental feedback types  Intercontec Model : ASTA876FR1085200A000 Drive Connector(3M) Model : 10120-3000VE
	LMACE□□AM		For incremental feedback types with hall sensor  Intercontec Model : ASTA876FR1085200A000 Drive Connector(3M) Model : 10120-3000VE
	LMACE□□AU		For absolute feedback types  Intercontec Model : ASTA876FR1085200A000 Drive Connector(3M) Model : 10120-3000VE
④ RS-232 Cable	LMACR21D		To PC (about 2m long for mega-fabs drive)  D-SUB 9 Female Drive RS-232 RJ-11
⑤ Controller Pulse Cable	LMACK30R	CN2	To motion controller (about 3m long)  Drive Connector(3M) Model : 10126-3000VE
⑥ Regen Resistor	050100700001		Rated 100W, Peak 500W
D1 Drive Accessory	D1-CK1		All Connector (Not Include CN3)
	D1-CK2		All Connector (Include CN3)
EMC Accessory	D1-EMC1		Used in Single Phase AC Power
	D1-EMC2		Used in Three Phase AC Power
Heat Sink	D1-H1		Standard
	D1-H2		Low Profile

□□	03	04	05	06	07	08	09	10
Cable Length (m)	3	4	5	6	7	8	9	10

Note: User must prepare one 24 V_{DC} power supply for each drive.

3.1 Pin Assignment

LMACE□□AA

Function	8-10-0090 (Female)	Signal	Color (051400300069)	SCSI 20 (Male)
Power	4	5V	Blue	3
	5	5V	Blue	-
	6	0V	White	2
Incremental Signal	2	U ₂ ⁻	Red	19
	3	U ₁ ⁻	Brown	17
	9	U ₂ ⁺	Black	18
	10	U ₁ ⁺	Green	16
Reference Mark	1	U ₀ ⁻	Pink	9
	8	U ₀ ⁺	Grey	8
	Case	Shield	Outer Shield	1
Temperature Switch	11	T+	Purple	14
	12	T-	Yellow	15

LMACE□□AM

Function	8-10-0090 (Female)	Signal	Color (051400300069)	SCSI 20 (Male)
Power	4	5V	Blue	3
	5	5V	Blue	-
	6	0V	White	2
Incremental Signal	2	U ₂ ⁻	Red	19
	3	U ₁ ⁻	Brown	17
	9	U ₂ ⁺	Black	18
	10	U ₁ ⁺	Green	16
Reference Mark	1	U ₀ ⁻	Pink	9
	8	U ₀ ⁺	Grey	8
	Case	Shield	Outer Shield	1
Temperature Switch	11	T+	Purple	14
	12	T-	Yellow	15
Hall Sensor	13	Vcc	Blue	3
	14	Hall A	Brown/Green	11
	15	Hall B	White/Yellow	12
	16	Hall C	White/Green	13
	17	GND	White	10

LMACE□□AU

Function	8-10-0090 (Female)	Signal	Color (051400300069)	SCSI 20 (Male)
Resolver 1 (20/115)	1	VREF+	Brown	11
	4		White/Yellow	
	7	VREF-	White	3
	8		Yellow/Brown	
Resolver 2 (24/114)	2	SIN+	Green	16
	3	SIN-	Yellow	17
	9	COS+	Blue	18
	10	COS-	Red	19
	13	SIN+	Black	4
	14	SIN-	Purple	5
	15	COS+	Grey	6
	16	COS-	Pink	7
	12	Inner shield	Inner shield	15
	Case	Outer shield	Outer shield	1/Case
Temperature Switch	11	T+	Brown/Green	14
	12	T-	White/Green	15

Appendix A: Motor Sizing

Start Motor Sizing

The following contents describe how to choose proper motor according to speed, moving distance, and loading inertia. The basic process for sizing a motor is:

Requirement

- Operating environment
- Installation (horizontal or vertical)
- Driving method
- Load conditions (loading inertia, friction and cutting force)
- Speed condition (maximum acceleration and velocity)
- Duty cycle



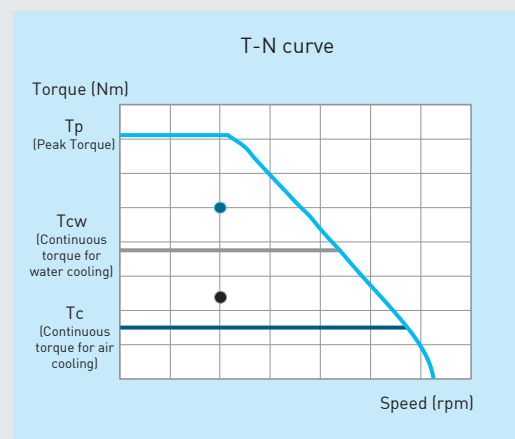
Torque calculation

- Calculate the torque corresponding to the speed under each operation condition
- Calculate equivalent torque



Motor sizing and T-N curve confirmation

- Select the appropriate motor from the HIWIN's catalogue in accordance with calculated maximum torque, equivalent torque and speed.
- Ensure the speed and the corresponding torque under all operating conditions are within the range of torque-speed curve of the motor.
- Confirm the equivalent torque is within the continuous torque of the motor.



Symbol :

- θ : Angular displacement (rad)
- t: Moving time(sec)
- α : Angular acceleration(rad/s²)
- ω : Angular velocity (rad/s)
- J: Load inertia (kgm²)
- J_m: Rotor inertia (kgm²)
- T_p: Peak torque (Nm)
- T_c: Continuous torque (Nm)
- T_i: Inertia torque (Nm)
- K_t: Torque constant (Nm/Arms)
- I_p: Peak current (Arms)
- I_e: Equivalent current (Arms)
- I_c: Continuous current (Arms)
- ω_0 : Initial angular velocity (rad/s)
- m: Loading Mass (kg)
- R: External diameter of loading Mass (m)
- r: Internal diameter of loading Mass (m)
- a, b: Side length of loading Mass (m)
- S: Distance from gravity center to rotary center (m)

STEP1 Requirement

In order to select the motor that meet user's needs, the following formula of load inertia motion must be understood prior to the selection.

Calculation of loading inertia

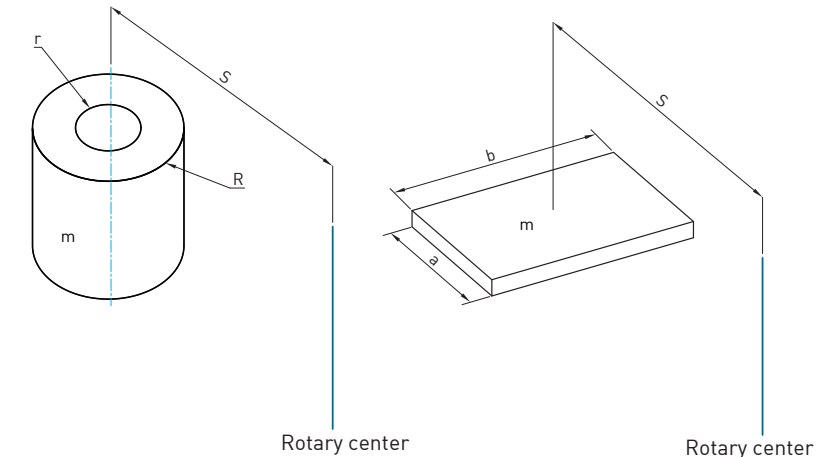
Loading inertia can be determined by 3D drawing software or according to the formula. The basic loading formula is as follows:

moment of inertia of a hollow cylinder

$$J = m \left(\frac{R^2 + r^2}{2} + S^2 \right)$$

moment of inertia of a rectangular

$$J = m \left(\frac{a^2 + b^2}{12} + S^2 \right)$$



Determine the motion speed and parameters

Motion equation

Basic kinematics equations are described as follows:

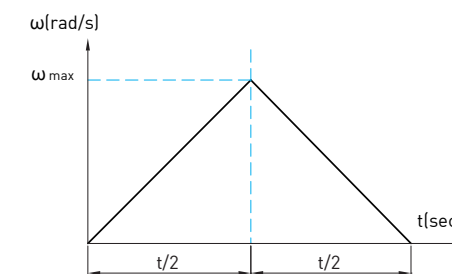
$$\omega = \omega_0 + \alpha t$$

$$\theta = \omega_0 t + \frac{1}{2} \alpha t^2$$

Where ω is angular velocity, α is angular acceleration, t is moving time and θ is angular displacement. User can choose two of the four parameters (ω , α , t and θ) as user's designed parameters, then the left two parameters can be calculated by above equations.

Motion velocity profile

The motion profiles for torque motor are usually classified as "Trapezoid Profile" and "Triangle Profile", where the Trapezoid Profile is frequently used for scan. The motion profiles are divided as acceleration, constant velocity and deceleration. The maximum angular acceleration can be determined by the basic kinematics equations above-mentioned; the Trapezoid Profile is usually used in point-to-point application. The motion profiles are divided as acceleration and deceleration, where the motion profile and formula can be simplified as follows:



$$\omega_{\max} = 2 \times \frac{\theta}{t} \quad \text{或} \quad \omega_{\max} = \sqrt{\alpha \times \theta}$$

$$\alpha_{\max} = \frac{4\theta}{t^2}$$

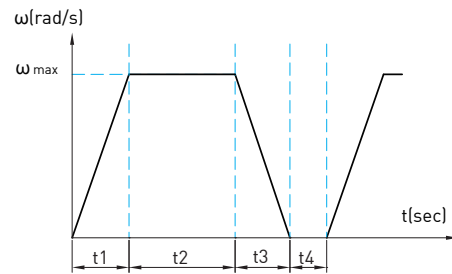
STEP 2 Torque calculation

The maximum torque can be calculated by the following equation

$$T_{max} = (J + J_m) \times \alpha_{max} + T_f = T_i + T_f$$

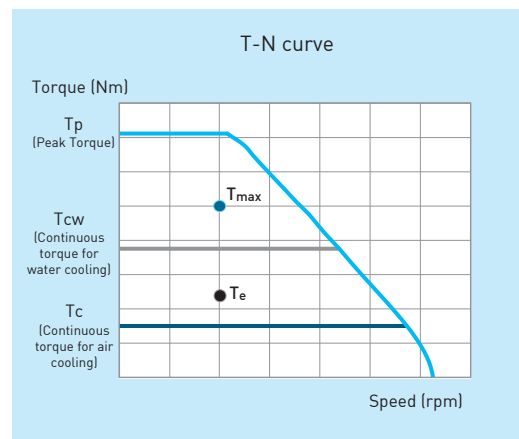
Where T_i is inertia torque, T_f is the torque which is caused by friction torque, cutting force or external force. In most cases, the motions are cyclic point-to-point movements. Assuming a cyclic motion shown in the following profile with a dwell time of t_4 second, the effective force can be calculated as follows:

$$T_e = \sqrt{\frac{[T_i + T_f]^2 \times t_1 + T_f^2 \times t_2 + [T_i - T_f]^2 \times t_3}{t_1 + t_2 + t_3 + t_4}}$$



STEP 3 Motor sizing and T-N curve confirmation

With the help of HIWIN's motor specification, users can select the appropriate motor from peak torque and equivalent torque, and ensure the speed and torque under all operating conditions is within the range of the T-N curve for the motor.



The motor sizing is determined as follows:

$$T_{max} < T_p$$

$$T_e < T_c$$

The user needs to consider the ratio of equivalent torque and continuous torque. Usually the ratio (T_e/T_c) is recommended within 0.7; continuous torque for TMRW series can be classified as air cooling and water cooling. If the motor is operated with water cooling, the comparison of equivalent torque can be based on water cooling continuous torque when selecting the motor.

The peak current I_{max} and effective current I_e can be calculated by bringing motor torque constant into the following equation (For K_t , please refer to Appendix B)

$$I_{max} = \frac{T_{max}}{K_t}$$

$$I_e = \frac{T_e}{K_t}$$

Example of motor sizing

Loading requirement: An aluminum disc with $\phi 500$ mm and 15mm thick without offset and weight is 12kg. There are eight jigs with 100x50x50mm on the aluminum disc at an interval of 45° . Each jig weighs 1 kg. The distance from the jig gravity center to the rotary center is 150mm, and the mechanical friction force is 2Nm. Speed requirement: Each position 45° is completed in 0.3 seconds, and rests for 1 second.

STEP1 Requirement confirmation

Calculation of loading inertia

Inertia of disc

$$J_1 = m \left(\frac{R^2 + r^2}{2} + S^2 \right) = 12 \left(\frac{0.25^2 + 0^2}{2} + 0^2 \right) = 0.375 \text{ kgm}^2$$

Inertia of jig

$$J_2 = m \left(\frac{a^2 + b^2}{12} + S^2 \right) = 1 \left(\frac{0.1^2 + 0.05^2}{12} + 0.15^2 \right) = 0.0235 \text{ kgm}^2$$

Total inertia

$$J = J_1 + 8 \times J_2 = 0.375 + 8 \times 0.0235 = 0.563 \text{ kgm}^2$$

Motion profile

It is a point-to-point application. The maximum angular velocity and the maximum angular acceleration are calculated as follows:

$$\theta = 45^\circ = \frac{45 \times \pi}{180} = 0.7854 \text{ rad}$$

$$\omega_{max} = 2 \times \frac{\theta}{t} = 2 \times \frac{0.7854}{0.3} = 5.236 \text{ rad/s} = 50 \text{ rpm}$$

$$\alpha_{max} = \frac{4\theta}{t^2} = \frac{4 \times 0.7854}{0.3^2} = 34.91 \text{ rad/s}^2$$

STEP 2 Torque calculation

It is recommended that the ratio loading inertia (J) over motor rotator inertia (J_m) be less than 50. It can be roughly estimated 30 in motor sizing. Since $J/30 = 0.563/30 = 0.019 \text{ kgm}^2$, user can select the DMS34 ($J_m = 0.02 \text{ kgm}^2$)

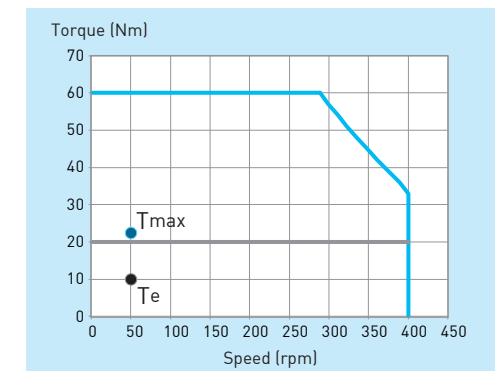
$$T_{max} = (J + J_m) \times \alpha_{max} + T_f = T_i + T_f = (0.563 + 0.02) \times 34.91 + 2 = 20.4 + 2 = 22.1 \text{ Nm}$$

Where $T_i = 20.4 \text{ Nm}$, $T_f = 2 \text{ Nm}$

$$T_e = \sqrt{\frac{[T_i + T_f]^2 \times t_1 + T_f^2 \times t_2 + [T_i - T_f]^2 \times t_3}{t_1 + t_2 + t_3 + t_4}} = \sqrt{\frac{[20.4 + 2]^2 \times 0.15 + 2^2 \times 0 + [20.4 - 2]^2 \times 0.15}{0.15 + 0 + 0.15 + 1}} = 9.9 \text{ Nm}$$

STEP 3 Motor sizing and T-N curve confirmation

Finally, DMS34G can be selected according to the T_{max} and T_e . The peak torque $T_p = 60 \text{ Nm}$, the continuous torque $T_c = 20 \text{ Nm}$, the torque constant $K_t = 6.6 \text{ Nm/Arms}$, and the speed and torque under all operating conditions are within the range of T-N curve for DMS34G.



Appendix B: Glossary

1. Back EMF constant(Line to Line): $K_v \left(\frac{V_{rms}}{rad/s} \right)$

The back EMF constant, K_v , is the ratio of the back emf voltage (V_{rms}) to the motor rotational speed (rad/s) when the magnet is at 25°C. It is created at the movement of the coil in the magnetic field of permanent magnets.

2. Continuous current: I_c/I_{cw} (Arms)

The continuous current, I_c , is the current that can be continuously supplied to the motor coils at the ambient temperature 25°C, and the final temperature of coil can't exceed 100°C (120°C for TMRW series). Under this condition, the motor reaches the rating continuous torque T_c ; in relation with the continuous current and coil temperature, TMRW/TMRI series will respond to I_c for air cooling and I_{cw} for water cooling.

3. Continuous torque: T_c/T_{cw} (Nm)

The continuous torque, T_c , is the maximum torque the motor is able to generate continuously at the ambient temperature 25°C and the final temperature of coil can't exceed 100°C (120°C for TMRW series). This continuous torque corresponds to I_c/I_{cw} supplied to the motor; in relation with the continuous current and coil temperature, TMRW/TMRI series will respond to T_c for air cooling and T_{cw} for water cooling.

4. Inductance (line-to-line): L (mH)

Inductance is defined as inductance measured between lines when the motor operates in continuous current I_c/I_{cw} .

5. Resistance at 25°C (line-to-line): R_{25} (Ω)

Resistance is defined as resistance measured between lines when the motor operates at the coil temperature 25°C.

6. Motor constant: $K_m \left(\frac{Nm}{\sqrt{W}} \right)$

The motor constant, K_m , is defined as the ratio of square root of motor output torque to consumption power when the coils and magnets are at 25°C. The larger motor constant represents the lower power loss when the motor outputs at the specific torque.

7. Number of poles: $2p$

$2p$ represents the number of poles of the rotor, where p is the number of poles pair.

8. Peak current: I_p (Arms)

The peak current, I_p , is the current corresponding to maximum torque output of the motor, and the motor temperature reached by current can't demagnetize magnet; generally speaking, peak current can be granted to supply 1 second when the motor is operating in the normal condition, and then need to ensure it reaches the normal temperature to supply peak current.

9. Peak torque: T_p (Nm)

The peak torque, T_p , is the maximum torque that the motor output less than 1 second. Peak current corresponding to the torque can't demagnetize magnet.

10. Rotor inertia: J (kgm^2)

The rotor inertia, J , is the rotary component resists any changes in its state of motion, including changes to its speed and direction. It is related with the shape and mass.

11. Stall current: I_s/I_{sw} (Arms)

The stall current, is the upper limit of current when the motor is at 25°C and in the stall condition; Depending on the heat dissipation, TMRW/TMRI series will correspond to I_s for air cooling and I_{sw} for water cooling.

12. Stall torque: T_s/T_{sw} (Nm)

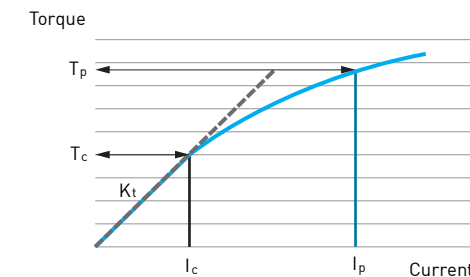
The stall current, T_s , is the upper limit of torque when the motor is at 25°C and in the stall condition; Depending on the heat dissipation, TMRW/TMRI series will correspond to T_s for air cooling and T_{sw} for water cooling.

13. Thermal resistance: R_{th}/R_{thw} (K/W)

The thermal resistance, R_{th} , is defined as the resistance suffered heat from motor coil to dissipate the environment (consider the natural convection and radiation for air cooling when ambient temperature is at 25°C, and the force water cooling for water cooling when the water is at 25°C); Higher thermal resistance represents the larger temperature difference between the coil and environment under the same heat source.

14. Torque constant: K_t (Nm/Arms)

The torque constant, K_t , is ratio between as the motor's output torque per RMS current. Except for TMRW/TMRI series, output torque and input current shows a linear relationship. The non-linear relationship is due to saturation in the lamination stack.



15. Maximum speed (RPM)

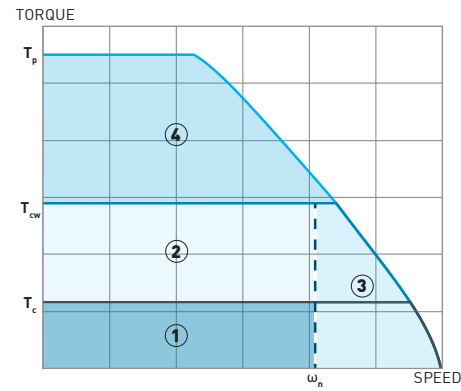
Maximum speed is defined as maximum speed provided under specific torque (usually continuous torque); if there is a bearing installed inside the motor, the maximum speed will be limited by the bearing's DN value; there are three conditions to define the maximum speed of water-cooling motor: maximum speed under air-cooling continuous torque, maximum speed under water-cooling continuous torque and maximum speed under peak torque.

16. Rated speed: ω_n (RPM)

The rated speed is defined as the speed at which when the motor is running continuously without break, the rotor does not suffer from excessive rotor temperature (>80 °C) due to iron loss; if the speed is exceeded, the duty cycle must be reduced or an additional rotor heat dissipation design must be done. Please refer to 17. T-N curve for details regarding motor operation range.

17. T-N Curve

The T-N curve is defined as the comparison chart of the torque and the speed that can be output under a certain input voltage of the motor. Considering the temperature rise of the motor, the figure can be divided into four operating ranges as shown below:



- ① When the motor is air-cooled and the torque is less than T_c , it can run continuously below ω_n without break.
- ①+② When the motor is water-cooled and the torque is less than T_{cw} , it can run continuously below ω_n without break.
- ③ When the motor is air-cooled and the torque is less than T_c or when it is water-cooled and the torque is less than T_{cw} , the speed is greater than ω_n , the duty cycle must be reduced or additional design on rotor heat dissipation must be provided to avoid overheating of the rotor.
- ④ When the motor is air-cooled and the torque is greater than T_c or when it is water-cooled and the torque is greater than T_{cw} , the duty cycle must be reduced. When T_p is reached, only 1 second output is allowed to avoid overheating of the stator.

18. Maximum Input Voltage (VDC):

Maximum input voltage is the maximum voltage for the motor operating in the normal environment.

19. Resolution: p/rev

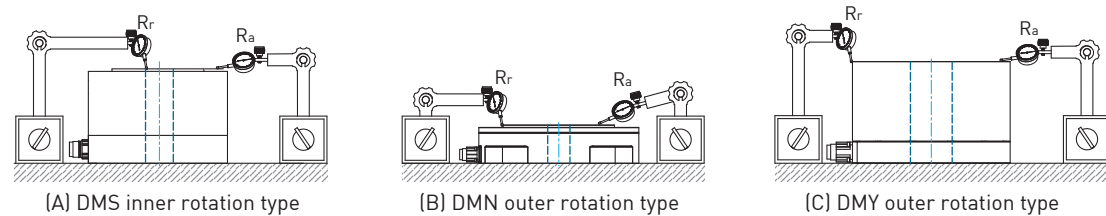
Resolution is the quantity of the motor feedback system divided in one turn.

20. Accuracy: arc-sec

Accuracy is the error between the target position and the actual position; in the HIWIN's definition, the motor is measured clockwise and counterclockwise twice per 22.5° to take the maximum error.

21. (Bi-) Repeatability: arc-sec

(Bi-)Repeatability is the repetition when the motor moves to the same angle.



22. Axial runout and radial runout:

Axial runout is the runout R_a by measuring the parallel direction between the installation end and rotary axis when the motor rotates; radial runout is defined as runout R_r by measuring the vertical direction between the installation end and the rotary axis when the motor rotates. Due to different types of motor, refer to the figure below for the measurement criteria.

23. Loading capacity:

The load of motor must be considered when it is operating. The load can be calculated by external force and the installation to identify the motor structure tolerates or not. The axial force applied to the motor in the calculation needs be less than the maximum axial load $F_i < F_a$, and can be used when the applied torque needs to be less than the maximum torque load $M_i < M$.

(A) External force= F

Axial force applied to the motor $F_1=F$ +loading weight W

Torque applied to the motor $M_1=0$

(B) External force= F

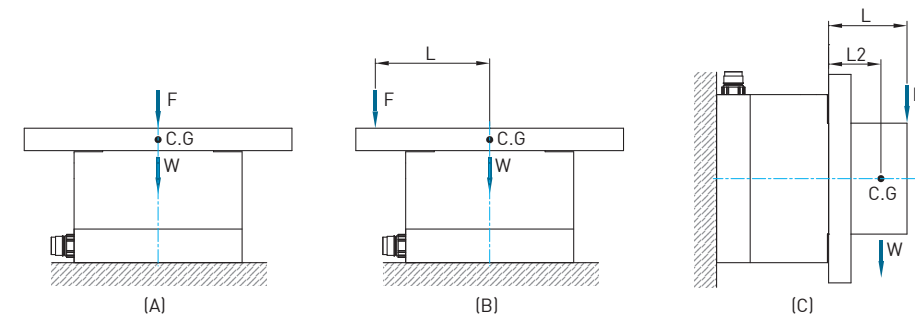
Axial force applied to the motor $F_2=F$ +loading weight W

Torque applied to the motor $M_2 = F \times L$

(C) External force= F

Axial force applied to the motor $F_3=F$ +loading weight W

Torque applied to the motor $M_3 = F \times (L+0.03m) + W \times (L_2+0.03m)$

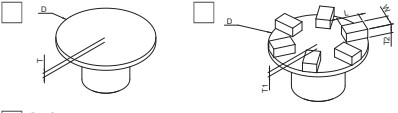
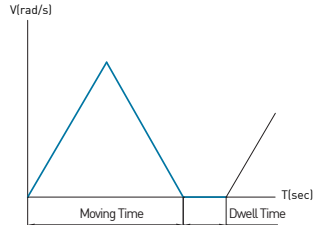


Appendix C: Environment

Operating Temperature	Temperature	+5 to +40°C
	Humidity	20 to 85% RH (no condensation)
Storage Temperature	Temperature	-10 to +50°C
	Humidity	20 to 85% RH (no condensation)
Atmosphere	Under 1000m, no corrosive gas, liquid and powder	

Appendix D : Motor Inquiry Form

Date:

Company Name:		Contact person:	
Email:		Title:	
Tel:	Fax:		
Industrial Environment	<input type="checkbox"/> Normal environment (25°C) <input type="checkbox"/> Clean room, Class _____ <input type="checkbox"/> Pollution environment ° <input type="checkbox"/> Other _____	Installation	<input type="checkbox"/> Horizontal <input type="checkbox"/> Laterally <input type="checkbox"/> (Upside Down)
Load Type	 <input type="checkbox"/> Other _____	Shaft runout	<input type="checkbox"/> Standard <input type="checkbox"/> High Precision Run out of output Shaft Surface (a) _____ μm
Load Conditions	<input type="checkbox"/> Total moment of inertia: _____ kgm ² , Size: _____ mm <input type="checkbox"/> Load1, Number _____ Mass: _____ kg or Material: _____ Size: _____ mm Offset of C.G. : _____ mm <input type="checkbox"/> Load2, Number _____ Mass: _____ kg or Material: _____ Size: _____ mm Offset of C.G. : _____ mm <input type="checkbox"/> Load3, Number _____ Mass: _____ kg or Material: _____ Size: _____ mm Offset of C.G. : _____ mm	Application	<input type="checkbox"/> Point to Point <input type="checkbox"/> Scan Moving Angle: _____ ° Moving Time: _____ sec Dwell Time: _____ sec
Force	<input type="checkbox"/> None <input type="checkbox"/> Yes: _____ kg, Offset of C.G. : _____ mm		
Repeatability	_____ arc-sec	Special requirement:	
Accuracy	_____ arc-sec		
Drive voltage	<input type="checkbox"/> 110V <input type="checkbox"/> 220V <input type="checkbox"/> Other _____ V		
Pulse format	<input type="checkbox"/> CW/CCW <input type="checkbox"/> A/B <input type="checkbox"/> STEP/DIR		
Brake	<input type="checkbox"/> None <input type="checkbox"/> Power Off Brake <input type="checkbox"/> Power On Brake		

The information below is to be filled out by our authorized agents.

Recommended specification:

Manager:

Engineer:

Salesperson:

Torque Motor & Direct Drive Motor Technical Information

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Global Sales And Customer Service Site

HIWIN GmbH

OFFENBURG, GERMANY
www.hiwin.de
www.hiwin.eu
info@hiwin.de

HIWIN JAPAN

KOBE · TOKYO · NAGOYA · NAGANO ·
TOHOKU · SHIZUOKA · HOKURIKU ·
HIROSHIMA · FUKUOKA · KUMAMOTO,
JAPAN
www.hiwin.co.jp
info@hiwin.co.jp

HIWIN USA

CHICAGO, U.S.A.
www.hiwin.com
info@hiwin.com

HIWIN Srl

BRUGHERIO, ITALY
www.hiwin.it
info@hiwin.it

HIWIN s.r.o.

BRNO, CZECH REPUBLIC
www.hiwin.cz
info@hiwin.cz

HIWIN SINGAPORE

SINGAPORE
www.hiwin.sg
info@hiwin.sg

HIWIN KOREA

SUWON · MASAN, KOREA
www.hiwin.kr
info@hiwin.kr

HIWIN CHINA

SUZHOU, CHINA
www.hiwin.cn
info@hiwin.cn

Mega-Fabs Motion Systems, Ltd.

HAIFA, ISRAEL
www.mega-fabs.com
info@mega-fabs.com

HIWIN MIKROSYSTEM CORP.

No.6, Jingke Central Rd.,
Taichung Precision Machinery Park,
Taichung 40852, Taiwan
Tel: +886-4-23550110
Fax: +886-4-23550123
www.hiwinmikro.tw
business@hiwinmikro.tw