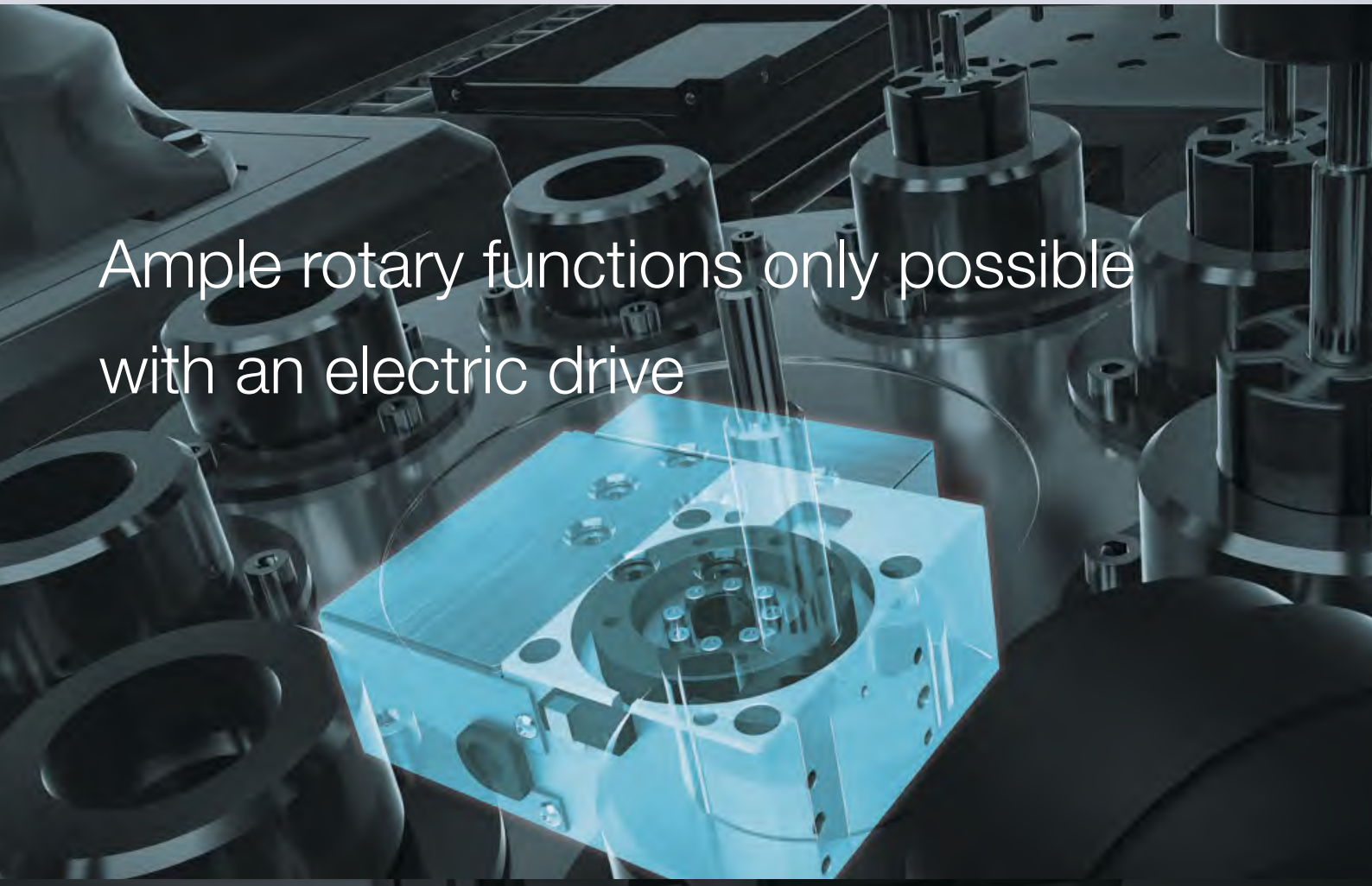
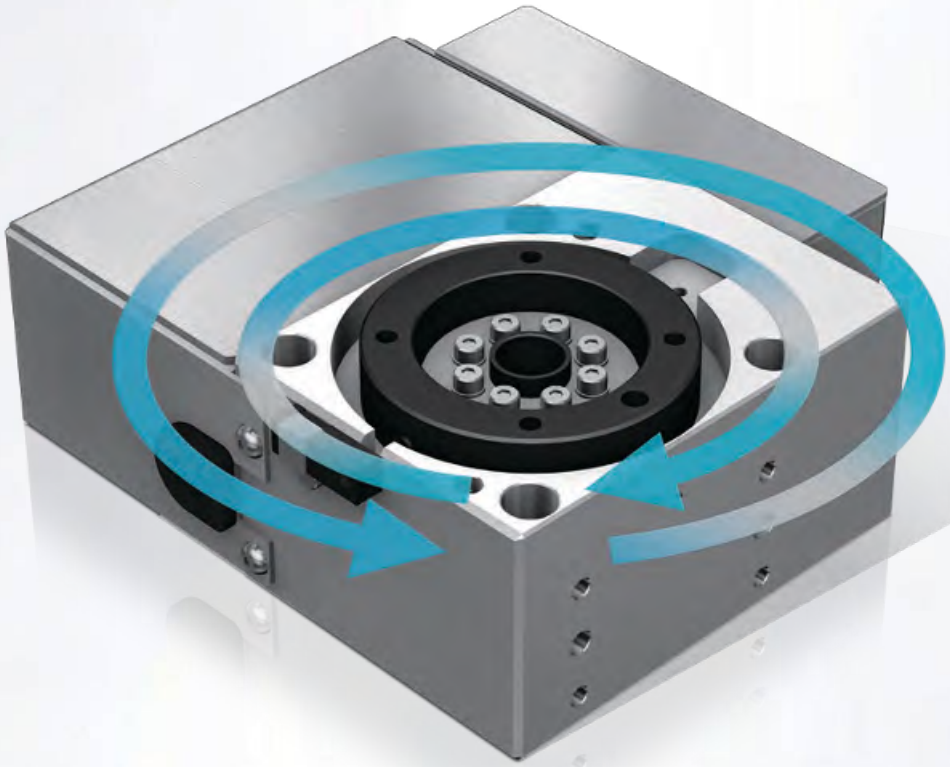
Thin Electric Turntable **ET**

High-precision multi-point positioning
with superior rotary performance


Ample rotary functions only possible
with an electric drive

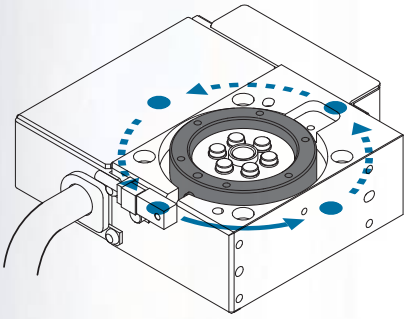

Consistent movement at
any installation angle

Thin Electric Turntable ET

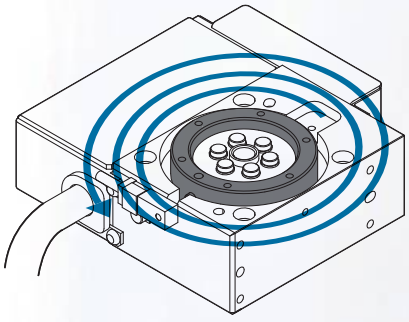


Multi-point positioning, multi-rotation control (speed can also be adjusted)

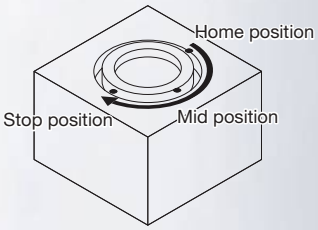
The combination of an electric drive with position control makes it possible to easily set three or more positions without stoppers.
Capable of multiple movements, including clockwise and counterclockwise rotation control, speed control, and continuous rotation.



Multi-point positioning



Continuous rotation in one direction



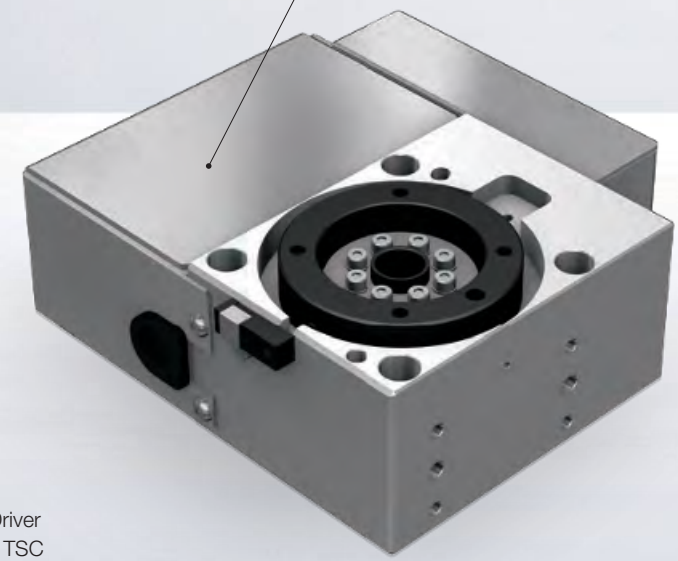
Up to three stop positions with pneumatics

ET

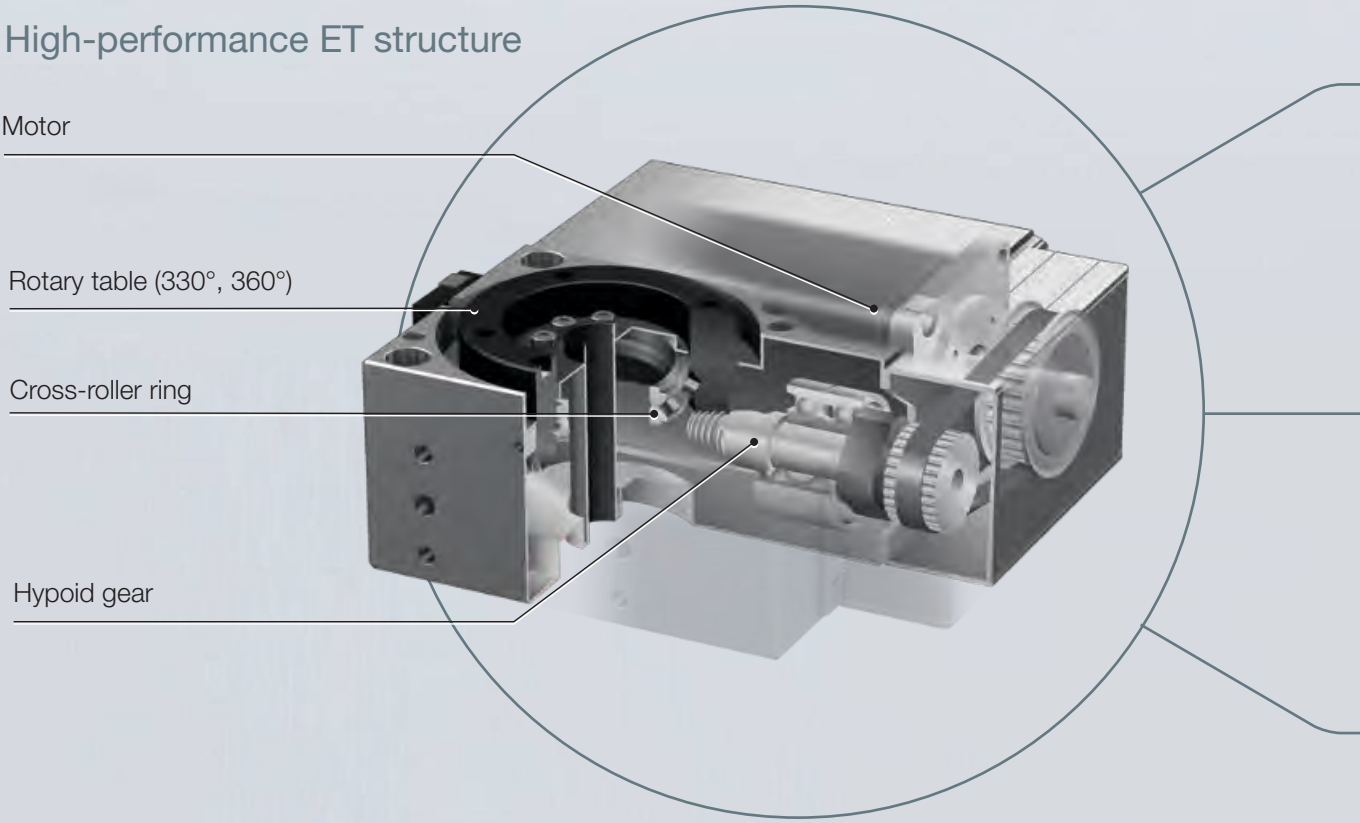
Multi-point positioning
Continuous rotation in one direction
Rotation speed control
Freely set at any angle
Positioning repeatability: ±0.04 degrees

TSC specifications

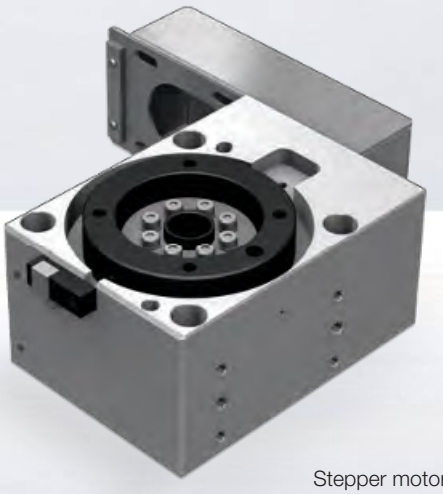
Stepper Driver
Controller TSC



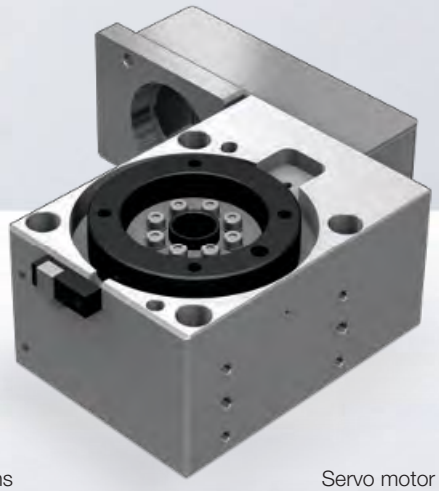
High-performance ET structure



Without motor



Stepper motor specifications

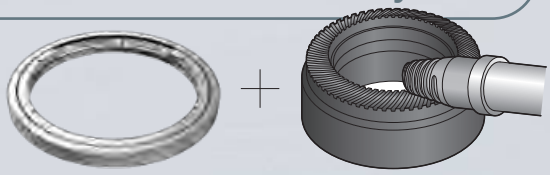


Servo motor specifications

Choose from 330° (mechanical homing type) or 360° (sensor homing type) to match your control application.

A mechanism that achieves high rotational accuracy

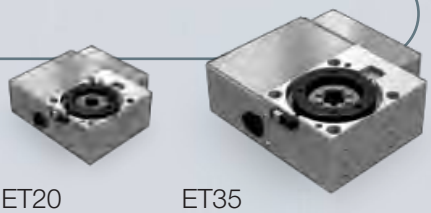
The rotary structure combines
a THK cross-roller ring and hypoid gear.



Cross-roller ring　　Hypoid gear

Thin structure

Product height is reduced by providing a compact rotary table and motor and integrating the cross-roller ring and hypoid gear. This helps equipment take up less space.



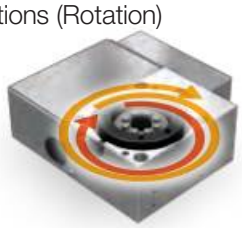
ET20　　ET35

Different varieties are available for purchase

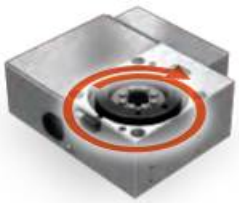
This product can come with a motor that pairs with the THK controller, a motor that you specify, or no motor installed.

Applications

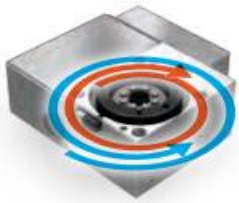
Basic Applications (Rotation)



330°/360° stroke rotation

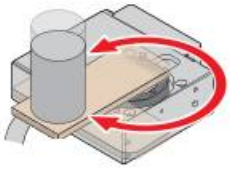


Continuous rotation in one direction

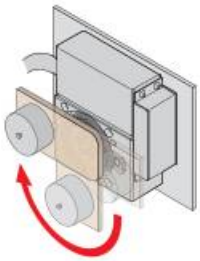


Clockwise/counterclockwise rotation

Diversified Applications



Applied moment



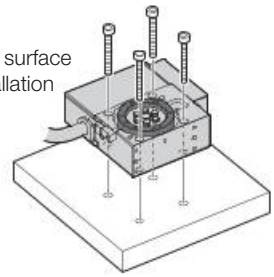
No speed fluctuations from varying loads

Suspended installation

Mounting Methods

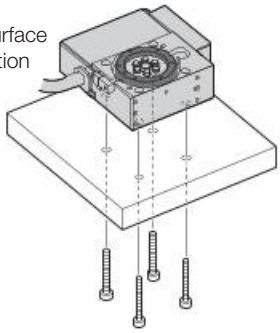
This product can be mounted from any surface, making it easy to install anywhere.

Upper surface installation

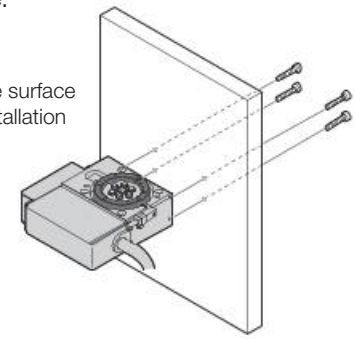


Note) This product cannot be installed with the pulley facing downward. See the instruction manual for details.

Lower surface installation



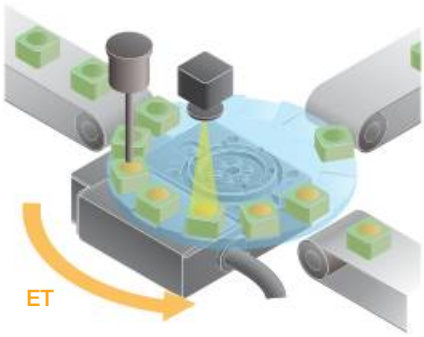
Side surface installation



Example Applications

General industry

Index table



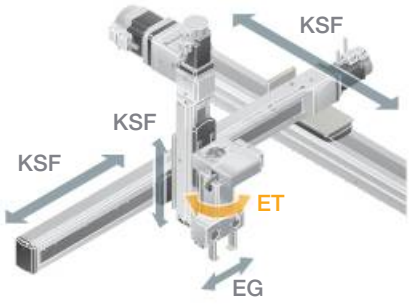
The ET is used in the parts that rotate the table. The rotary mechanism combines a cross-roller ring and a hypoid gear to achieve highly accurate indexing.

Model used

θ axis: ET

General industry

Orthogonal-axis robot



The ET is used in the hand rotary mechanism of the orthogonal-axis robot. The reduced weight of the thin structure allows for a decreased load on the lower axis.

Models used

θ axis: ET
Hand: EG
X, Y, and Z axis: KSF

General Specifications

Two sizes are available: ET20 and ET35. The reduction ratio and motor size for each are given below.

TSC specifications

ET20

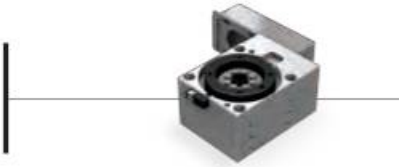
Reduction ratio | 45: 1/45
Motor size: 40×40

ET35

Reduction ratio | 20: 1/20 30: 1/30
Motor size: 35×35

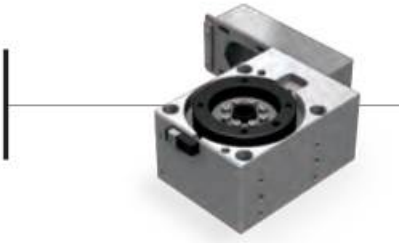
Without motor: Stepper motor specifications

ET20



Reduction ratio | 45: 1/45
Motor size: 40×40

ET35



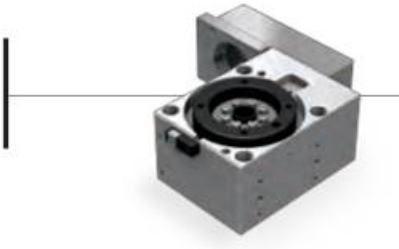
Reduction ratio | 20: 1/20 30: 1/30
Motor size: 35×35

Without motor: Servo motor specifications

ET20

Reduction ratio | 45: 1/45
Motor size: 25×25

ET35

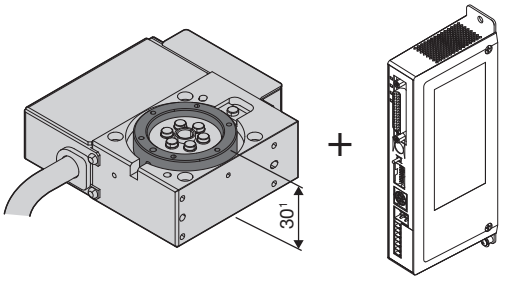
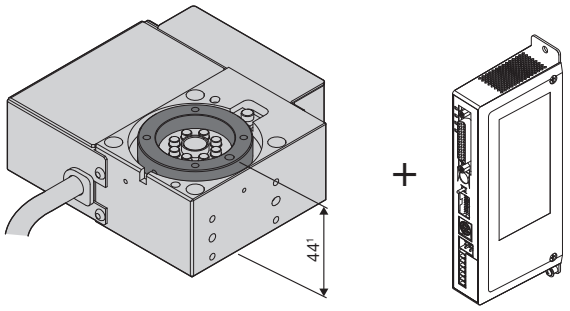


Reduction ratio | 20: 1/20 30: 1/30
Motor size: 40×40

ET (with Stepper Driver Controller TSC)

Combination with dedicated driver controller

Lineup

ET20+TSC	ET35+TSC
	

Users can select a reduction ratio.

[1] This dimension represents the distance from the bottom surface of the base to the top surface of the table.

Model Number Coding

Model ①	Reduction ratio ②	Stroke ③	Control device ④	Options ⑤	Motor size ⑥	Home position ⑦	Cable length ⑧
ET20 –	45 –	330 –	TS –		/ 20P –	D00 –	S3
ET20	20: 1/20	330: 330°	TS: Stepper Driver Controller TSC	No symbol: None	20P: Stepper motor 20×20	No symbol: Multi-rotation specifications	No symbol: None
ET35	30: 1/30	360: Multi-rotation specifications[2]		U: Sensor	35P: Stepper motor 35×35	D00: Counter-clockwise movement	S3: Standard 3 m
	45: 1/45					R00: Clockwise movement	S5: Standard 5 m
							SA: Standard 10 m

Controller must be procured separately. → p. 20

[2] There are conditions for using the product under TSC specifications in continuous rotation in one direction. Please contact THK for more information.

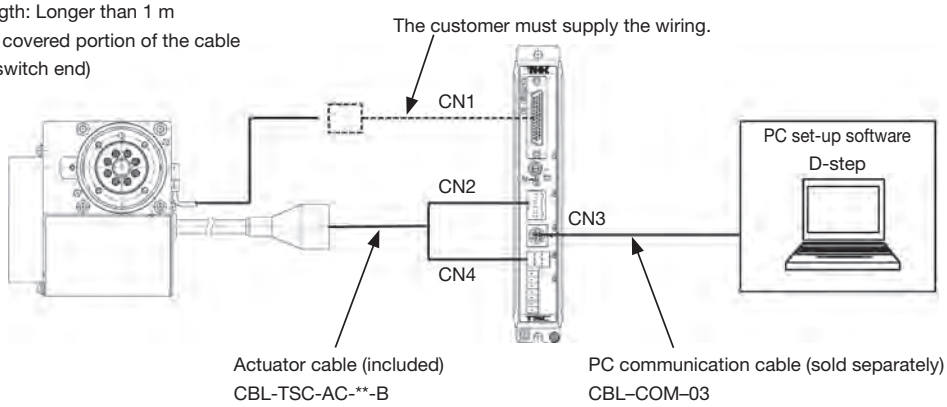
The available motor options vary based on the model.
ET20: 20P
ET35: 35P

D00 and R00 use mechanical homing.

System Configuration

The system configuration is as follows when “360: Multirotation specifications” is selected.
Magnetic proximity switch: AH003 (ASA ELECTRONICS INDUSTRY CO., LTD.)

- Cable ends: multi-conductor cable
- Cable length: Longer than 1 m (length of covered portion of the cable from the switch end)



Cable List

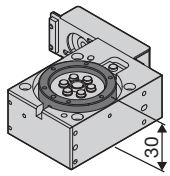
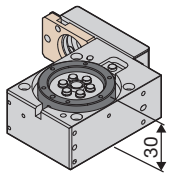
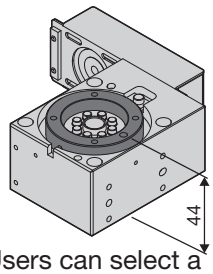
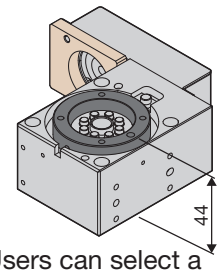
Cable	Quantity	Notes
Actuator cable for TSC	1	Comes with compatible actuator
I/O cable	1	Sold separately (I/O connector for TSC side only comes with TSC)
PC communication cable	1	Sold separately

Note) When using a 10 m actuator cable, please insert a noise filter in the TSC power source.
We recommend the RSAN-2003 noise filter from the TDK-Lambda Corporation.

ET (Without Motor)

Main actuator unit only or equipped with motor specified by customer

Lineup

ET20		ET35	
Stepper motor specifications	Servo motor specifications	Stepper motor specifications	Servo motor specifications
		 Users can select a reduction ratio.	 Users can select a reduction ratio.

Model Number Coding

Model		Reduction ratio		Stroke		With/without motor		Motor bracket		Options
①		②		③		④		⑤		⑥
ET20	–	45	–	360	–	0	–	A	–	U
ET20		20: 1/20		330: 330°		0: Without motor		A: Stepper motor		No symbol: None
ET35		30: 1/30		360: Multi-rotation specifications		1: With motor (THK will purchase and mount the motor you specify)		B: Servo motor		U: Sensor
		45: 1/45								

ET20

Turn table type | Stepper motor 20×20 | Motor wrap | Servo motor 20 W | Servo motor 30 W | Body height 30 mm

Model Number Coding

If "TS" is selected for ④ With or without motor/controller type, selections must be made for ⑦ to ⑨.

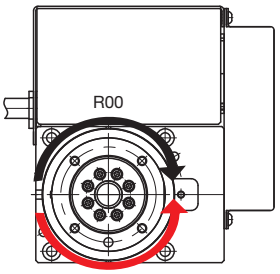
Model ①	Reduction ratio ②	Stroke ③	With or without motor/controller type ④	Motor bracket ⑤	Sensor ⑥	Motor size ⑦	Home position ⑧	Cable length ⑨
ET20	45	360	0	A	U	20P	D00	S3
ET20	45: 1/45	330: 330° 360: Multi-rotation specifications[1]	TS: Stepper Driver Controller TSC 0: Without motor 1: With motor (THK will purchase and mount the motor you specify)	No symbol: None A: Stepper motor type B: Servo motor type	No symbol: None U: Sensor	20P: Stepper motor 20×20	No symbol: Multi-rotation specifications D00: Counter-clockwise movement R00: Clockwise movement	No symbol: None S3: Standard 3 m S5: Standard 5 m SA: Standard 10 m

[1] There are conditions for using the product under TSC specifications in continuous rotation in one direction. Please contact THK for more information.

The available sensor options vary based on the stroke.
330: No Symbol
360: U

360° stroke (multi-rotation) uses a homing sensor (1 m cable).

D00 and R00 use mechanical homing.



Selection Information

Controller Specification

Control device	TSC
Motor size	20×20
Reduction ratio	1/45
Max. output torque[2] (N·m)	0.3
Max. permissible moment of inertia (kg·m^2)	0.0057

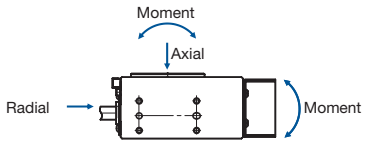
[2] Varies based on angular velocity. See p. 10 "Angular Velocity versus Output Torque" graph for details.

Basic Specifications

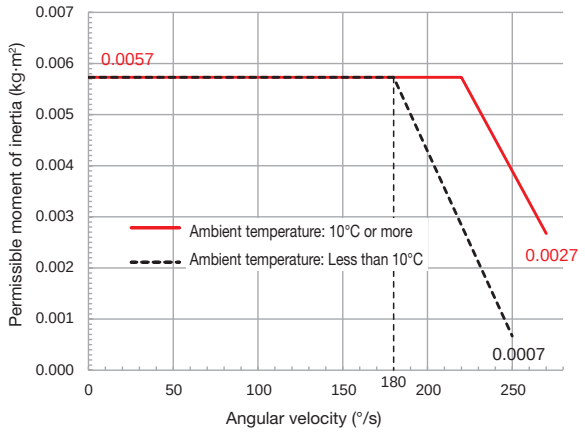
Motor size	20×20
Stroke (one side) (°)	330 or 360
Drive system	Hypoid gear
Output shaft bearing	Cross-roller ring
Reduction ratio	1/45
Max. permissible load torque (N·m)	0.3
Max. permissible moment of inertia (kg·m^2)	0.0057
Max. angular velocity (°/s)	270
Max. angular acceleration (°/s)	2000
Positioning repeatability (°)	±0.04
Backlash[3] (°)	0.2
Permissible axial load[4, 5] (N)	30
Permissible radial load[4, 5] (N)	13.2
Permissible moment[4, 5] (N·m)	3.6
Permissible input torque (N·m)	0.039
Mass[6] (kg)	0.52 (0.35)

[3] Depending on usage conditions, minor wear to the hypoid gear may cause increased backlash.
[4] Please use with a safety margin of 1.5 or greater.
[5] This is the permissible value when loaded in one direction.
[6] Values in parentheses are for no motor specifications.

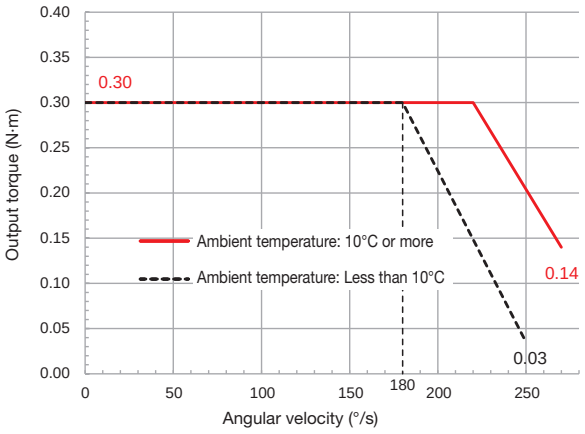
Permissible Load and Permissible Moment



Angular Velocity versus Permissible Moment of Inertia

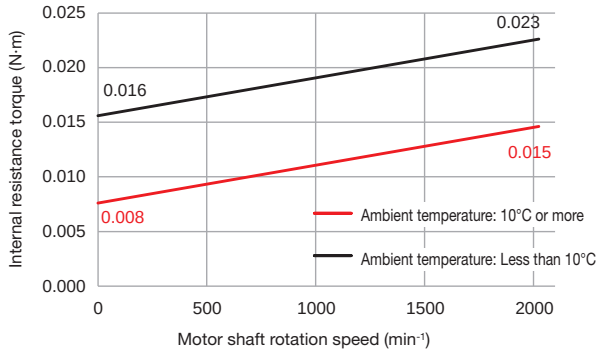


Angular Velocity versus Output Torque



Note 1) This graph represents cases where the angular acceleration is 2000°/s^2.
Note 2) When the ambient temperature is low (below 10°C), the permissible moment of inertia will decrease in the high angular velocity range.
Note 3) When the ambient temperature is low (below 10°C), the output torque will decrease in the high angular velocity range.
Note 4) Please use a safety margin of 1.5 or higher for the output torque.

Motor Shaft Rotation Speed versus Internal Resistance Torque



Note 5) Internal resistance torque increases in low-temperature environments (10°C and below).
Therefore, it is recommended to use a higher safety margin when selecting a product.

Motor Selection Information

Reduction ratio	Unit mass (with motor) (kg)	Unit mass (without motor) (kg)	Moving part mass (kg)	Unit inertia (kg·cm^2)	Efficiency	Timing pulley	Timing belt
1/45	0.52	0.35	0.07	0.004	0.47	P26-1.5GT-3-33F (Manufactured by Gates Unitta Asia Company)	100.5-1.5GT-3 (Manufactured by Gates Unitta Asia Company)

Compatible Motors

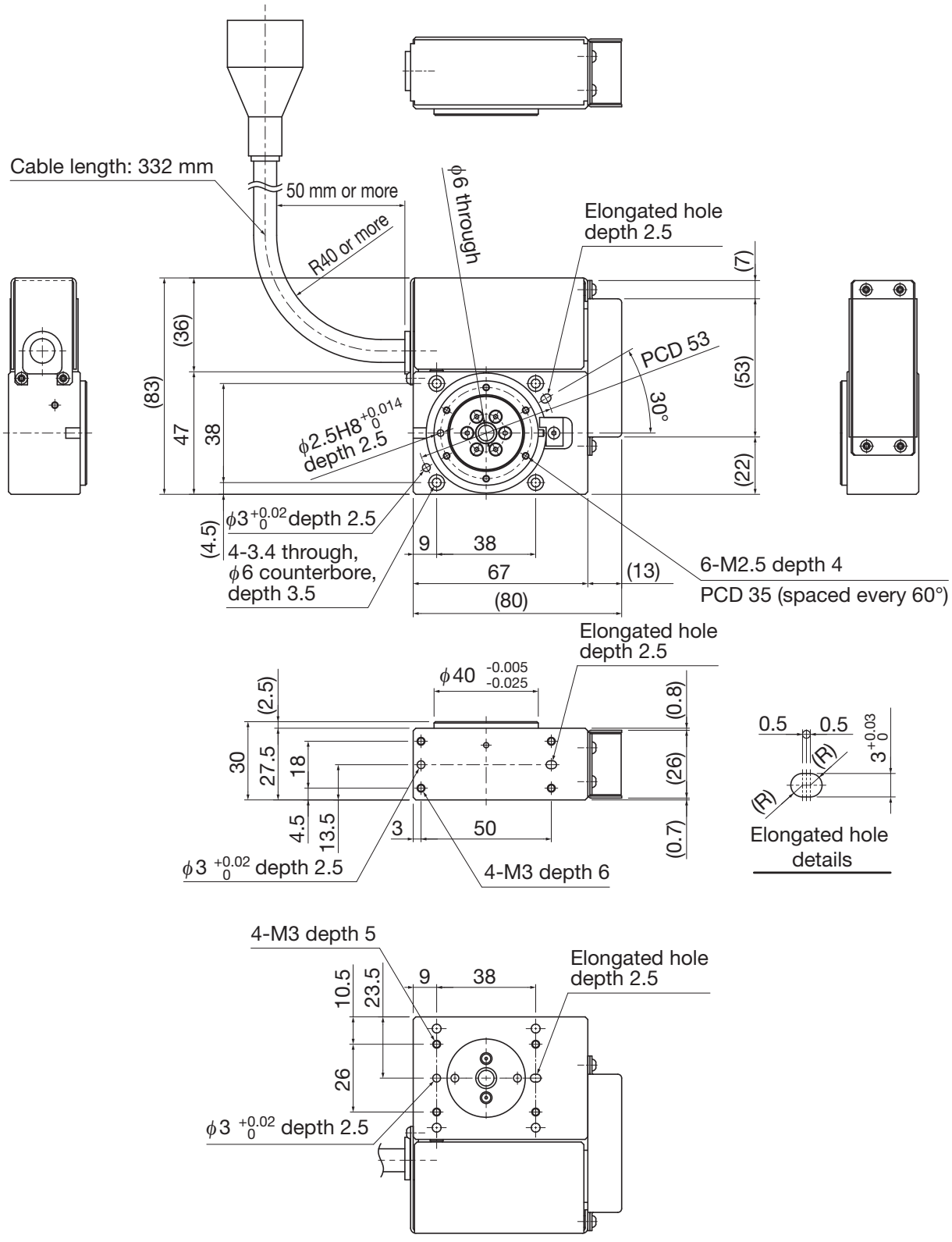
AC servo motor				Motor rated output (W)	Flange size	Motor bracket
YASKAWA Electric Corporation	Σ-Vmini		SGMMV–A2	20	25×25	B
			SGMMV–A3	30		
Mitsubishi Electric Corporation	MELSERVO	J4	HG–AK0236	20	25×25	B
			HG–AK0336	30		

Stepper motor			Flange size	Motor bracket
ORIENTAL MOTOR CO., LTD.	2-phase	PKP214D06*	20×20	A

Note 6) Please select and use a motor that is suited to the usage conditions. The table shows only a portion of the model numbers for motors. For details regarding model numbers, please see the catalog for each respective motor manufacturer.
Note 7) If the maximum torque of the installed motor will exceed the permissible input torque (p. 9), please consider a safety measure to limit the torque.
Note 8) Please select a D-cut type motor output shaft.
Note 9) Installation may not be possible depending on the motor options, so please verify in advance.

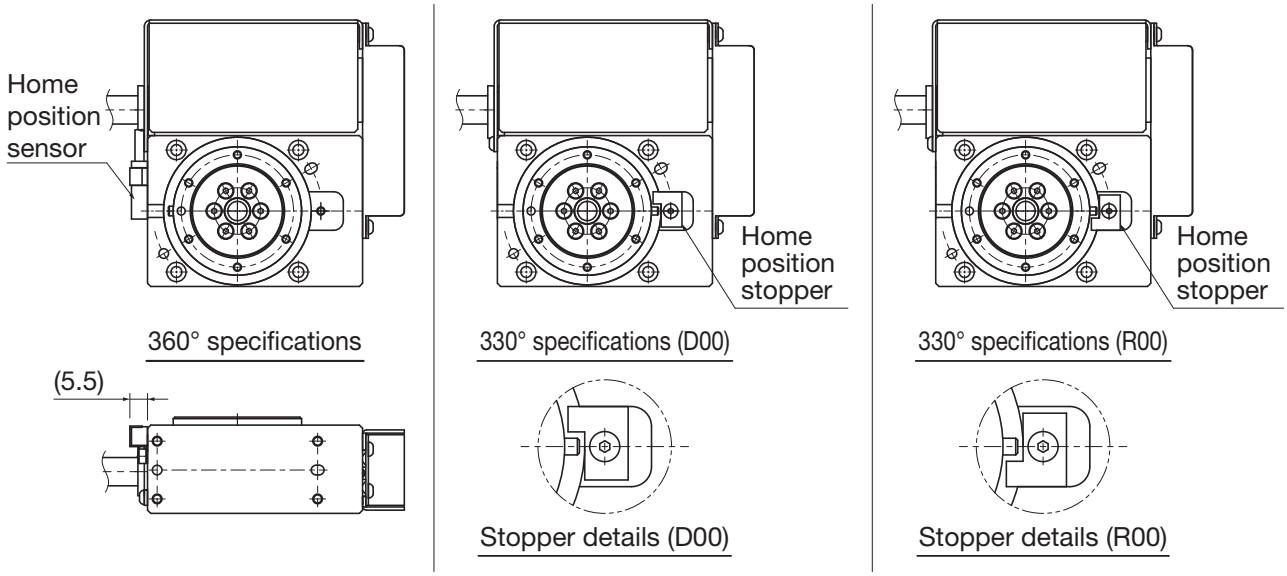
Dimensions

TSC Specifications

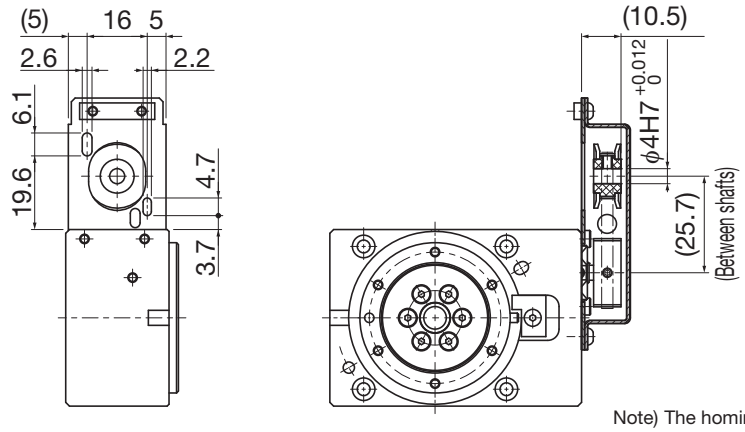


Dimensions

Homing Specifications

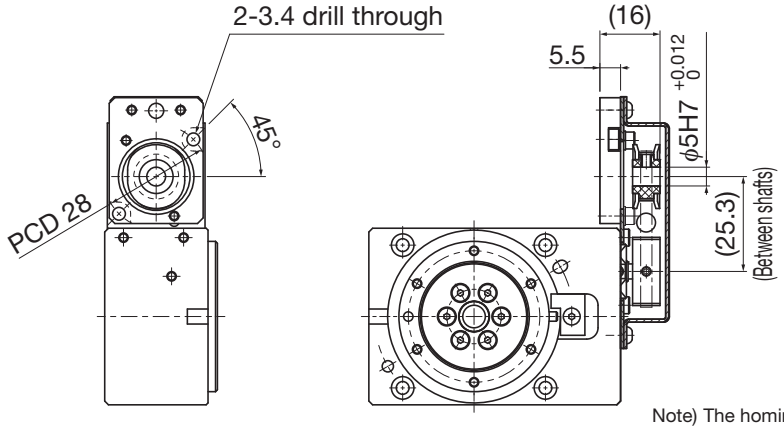


Without Motor (Stepper Motor Specifications)



Note) The homing stopper is for detecting the home position. If a stopper is necessary to prevent overrun, please prepare one separately.

Without Motor (Servo Motor Specifications)



Note) The homing stopper is for detecting the home position. If a stopper is necessary to prevent overrun, please prepare one separately.

ET35

Turn table type | Stepper motor 35×35 | Motor wrap | Servo motor 50 W | Servo motor 80 W | Servo motor 100 W | Body height 44 mm

Model Number Coding

If "TS" is selected for ④ With or without motor/controller type, selections must be made for ⑦ to ⑨.

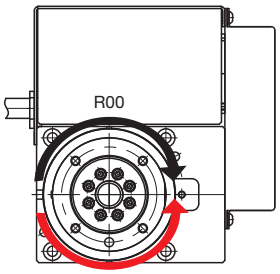
Model ①	Reduction ratio ②	Stroke ③	With or without motor/ controller type ④	Motor bracket ⑤	Sensor ⑥	Motor size ⑦	Home position ⑧	Cable length ⑨
ET35	20	360	TS	U	35P	D00	S3
ET35	20: 1/20 30: 1/30	330: 330° 360: Multi-rotation specifications[1]	TS: Stepper Driver Controller TSC 0: Without motor 1: With motor (THK will purchase and mount the motor you specify)	No symbol: None A: Stepper motor type B: Servo motor type	No symbol: None U: Sensor	35P: Stepper motor 35×35	No symbol: Multi-rotation specifications D00: Counter-clockwise movement R00: Clockwise movement	No symbol: None S3: Standard 3 m S5: Standard 5 m SA: Standard 10 m

[1] There are conditions for using the product under TSC specifications in continuous rotation in one direction. Please contact THK for more information.

The available sensor options vary based on the stroke.
330: No Symbol
360: U

360° stroke (multi-rotation) uses a homing sensor (1 m cable).

D00 and R00 use mechanical homing.



Selection Information

Controller Specifications

Control device	TSC	
Motor size	35×35	
Reduction ratio	1/20	1/30
Max. output torque[2] (N·m)	2.2	3.3
Max. permissible moment of inertia (kg·m^2)	0.028	0.042

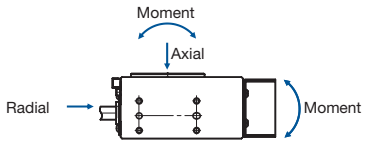
[2] Varies based on angular velocity. See p. 14 "Angular Velocity versus Output Torque" graph for details.

Basic Specifications

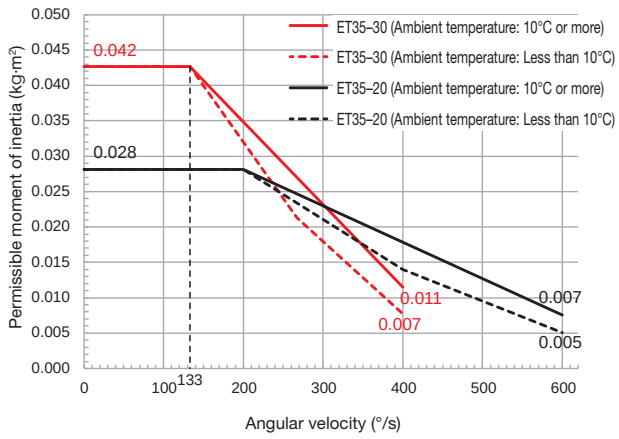
Motor size	35×35	
Stroke (one side) (°)	330 or 360	
Drive system	Hypoid gear	
Output shaft bearing	Cross-roller ring	
Reduction ratio	1/20	1/30
Max. permissible load torque (N·m)	2.2	3.3
Max. permissible moment of inertia (kg·m^2)	0.028	0.042
Max. angular velocity (°/s)	600	400
Max. angular acceleration (°/s)	3000	
Positioning repeatability (°)	±0.04	
Backlash[3] (°)	0.2	
Permissible axial load[4, 5] (N)	200	
Permissible radial load[4, 5] (N)	88	
Permissible moment[4, 5] (N·m)	17.7	
Permissible input torque (N·m)	0.248	
Mass[6] (kg)	1.2 (0.8)	

[3] Depending on usage conditions, minor wear to the hypoid gear may cause increased backlash.
[4] Please use with a safety margin of 1.5 or greater.
[5] This is the permissible value when loaded in one direction.
[6] Values in parentheses are for no motor specifications.

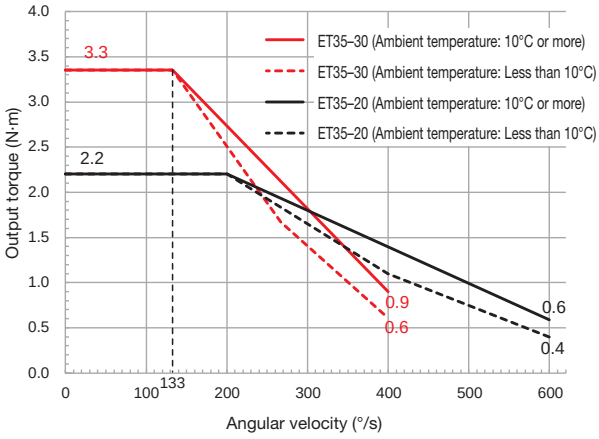
Permissible Load and Permissible Moment



Angular Velocity versus Permissible Moment of Inertia

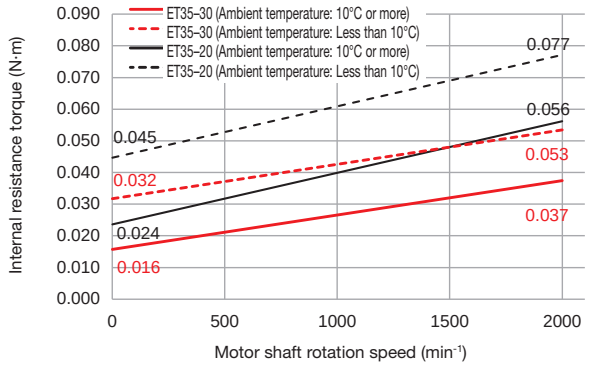


Angular Velocity versus Output Torque



Note 1) This graph represents cases where the angular acceleration is 3000°/s^2.
Note 2) Please use a safety margin of 1.5 or higher for the output torque.

Motor Shaft Rotation Speed versus Internal Resistance Torque



Note 3) Internal resistance torque increases in low-temperature environments (10°C and below). Therefore, it is recommended to use a higher safety margin when selecting a product.

Motor Selection Information

Reduction ratio	Unit mass (with motor) (kg)	Unit mass (without motor) (kg)	Moving part mass (kg)	Unit inertia (kg·cm^2)	Efficiency	Timing pulley	Timing belt
1/20	1.2	0.8	0.17	0.012	0.72	P26-2GT-6-33F (Manufactured by Gates Unitta Asia Company)	134-2GT-6 (Manufactured by Gates Unitta Asia Company)
1/30	1.2	0.8	0.17	0.015	0.71	P26-2GT-6-33F (Manufactured by Gates Unitta Asia Company)	148-2GT-6 (Manufactured by Gates Unitta Asia Company)

Compatible Motors

AC servo motor				Motor rated output (W)	Flange size	Motor bracket
YASKAWA Electric Corporation	Σ-V		SGMJV–A5	50	40×40	B
			SGMJV-01	100		
			SGMAV–A5	50		
			SGMAV-01	100		
	Σ–7		SGM7J–A5	50	40×40	B
			SGM7J-01	100		
			SGM7A–A5	50		
			SGM7A-01	100		
	Σ-X		SGMXJ–A5	50	40×40	B
			SGMXJ-01	100		
			SGMXA–A5	50		
			SGMXA-01	100		
Mitsubishi Electric Corporation	MELSERVO	J4	HG–KR053	50	40×40	B
			HG-KR13	100		
			HG–MR053	50		
			HG-MR13	100		
		J5	HK–KT053W	50	40×40	B
			HK-KT13W	100		

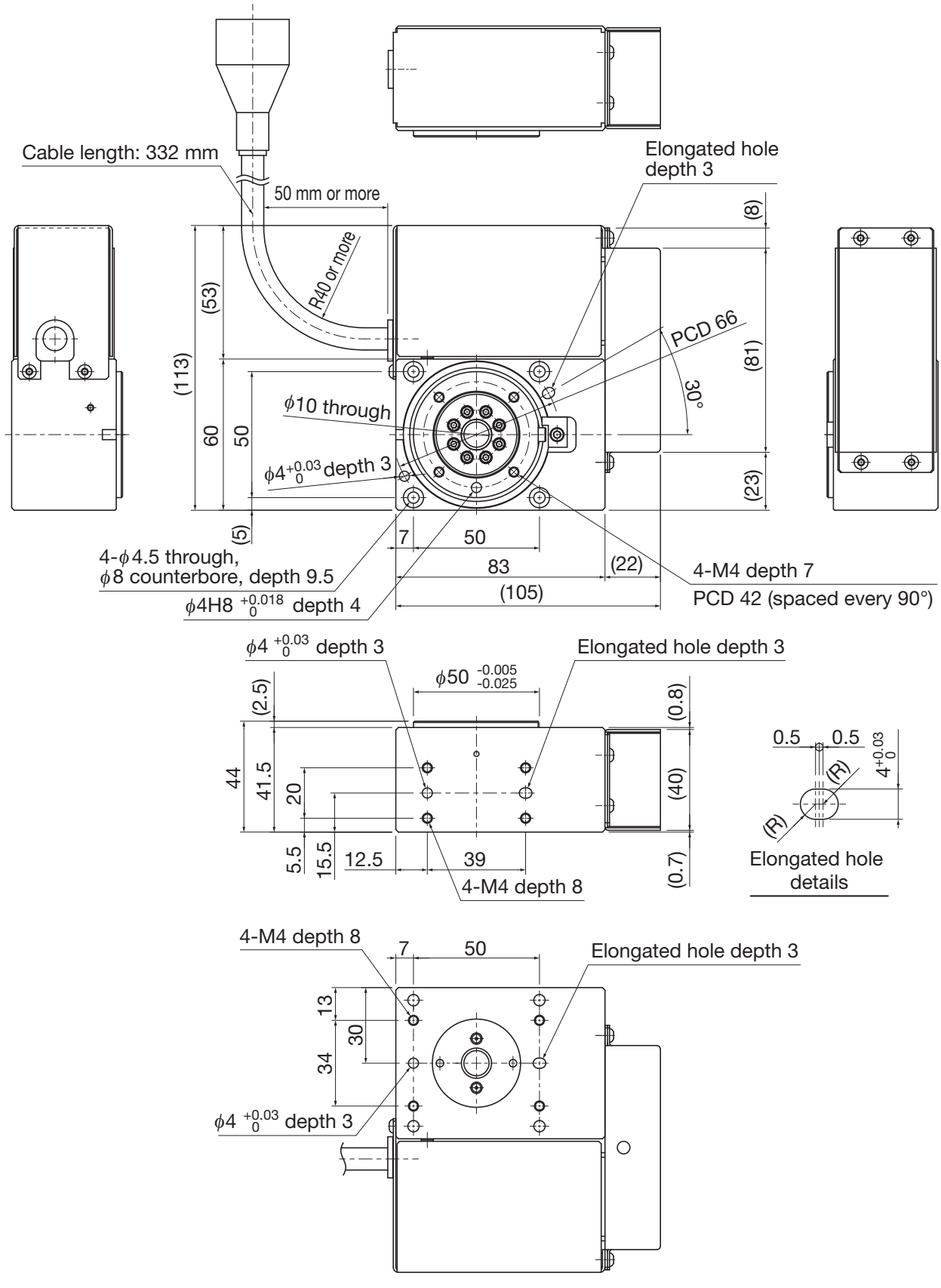
AC servo motor			Motor rated output (W)	Flange size	Motor bracket
TAMAGAWA SEIKI CO., LTD.	TBL-iⅡ	TS4602	50	40 × 40	B
		TS4603	100		
	TBL-iⅣ	TSM3102	50	40×40	B
		TSM3104	100		
SANYO DENKI CO., LTD.	SANMOTION R	R2*A04005	50	40×40	B
		R2EA04008	80		
		R2AA04010	100		

Stepper motor			Flange size	Motor bracket
ORIENTAL MOTOR CO., LTD.	2-phase	PKP235*	35×35	A

Note 4) Please select and use a motor that is suited to the usage conditions. The table shows only a portion of the model numbers for motors. For details regarding model numbers, please see the catalog for each respective motor manufacturer.
Note 5) If the maximum torque of the installed motor will exceed the permissible input torque (p. 13), please consider a safety measure to limit the torque.
Note 6) Please select a D-cut type motor output shaft.
Note 7) Installation may not be possible depending on the motor options, so please verify in advance.

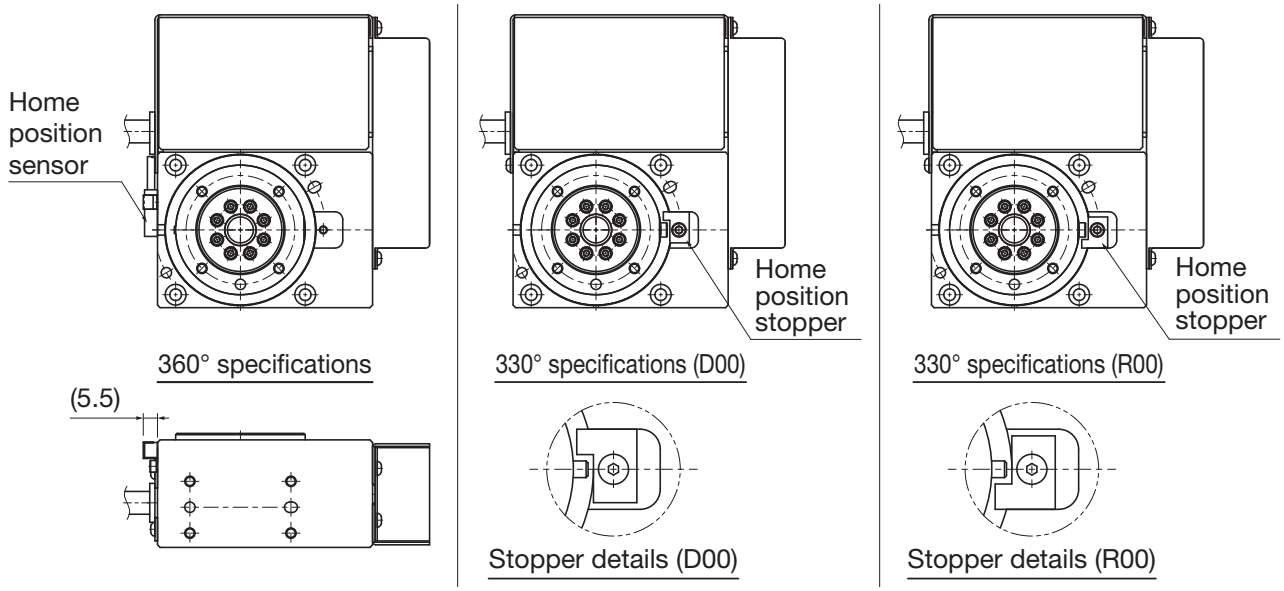
Dimensions

TSC Specifications

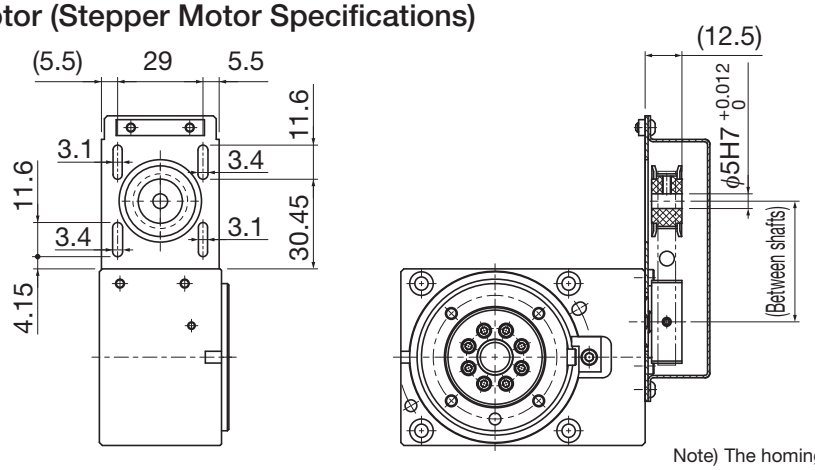


Dimensions

Homing Specifications



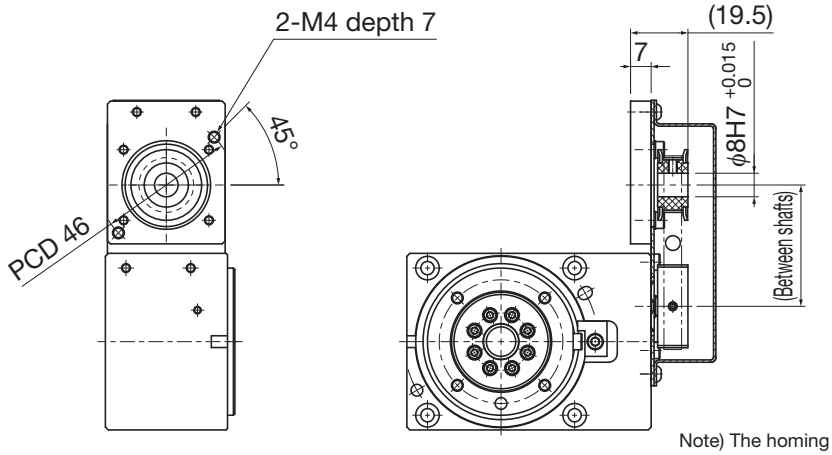
Without Motor (Stepper Motor Specifications)



Reduction ratio	(Between shafts)
1/20	41
1/30	41.3

Note) The homing stopper is for detecting the home position. If a stopper is necessary to prevent overrun, please prepare one separately.

Without Motor (Servo Motor Specifications)



Reduction ratio	(Between shafts)
1/20	41
1/30	41.3

Note) The homing stopper is for detecting the home position. If a stopper is necessary to prevent overrun, please prepare one separately.

Selection Method

When selecting a rotary shaft, calculate the moment of inertia and load torque for the usage conditions and make a selection where the permissible moment of inertia and maximum output torque will not be exceeded.
Refer to the formula below as a representative example and calculate the moment of inertia for the workpiece and mounting jigs you will be using.

Selection Procedure

● Calculating the moment of inertia

Confirm whether or not the calculated moment of inertia satisfies the requirements for the permissible moment of inertia for the model.

If the calculated moment of inertia is less than the permissible moment of inertia, the product may be used.

If the calculated moment of inertia is greater than or equal to the permissible moment of inertia, the product may not be used. Please select a different model or reduce the mass or rotational radius.

For the permissible moment of inertia for each model, please consult the "Angular Velocity versus Permissible Moment of Inertia" graph.

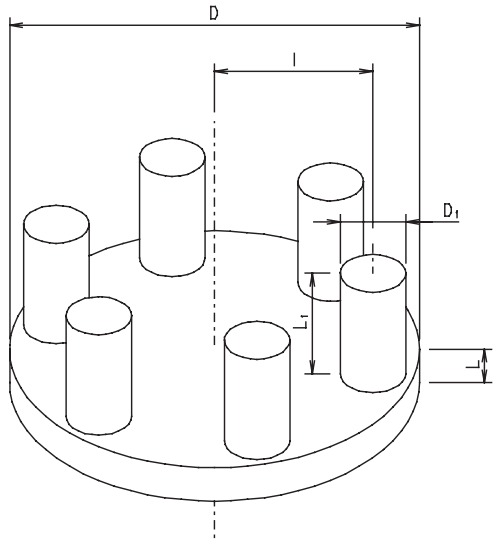
Confirm whether or not the calculated torque satisfies the requirements for the maximum output torque for the model.

If the calculated torque is less than the maximum output torque, the product can be used.

If the calculated torque is greater than or equal to the maximum output torque, the product cannot be used. Please select a different model or reduce the mass or rotational radius.

For the maximum output torque for each model, please consult the "Angular Velocity versus Output Torque" graph.

(Reference) Moment of Inertia for Multiple Cylindrical Columns Combined



$$I_X = \frac{1}{8}m \cdot D^2 + \frac{1}{8}n \cdot m \cdot (D_1{}^2 + 8l^2)\ [\mathrm{kg \cdot m^2}]$$

$$m:\ \frac{\pi}{4}\rho \cdot L \cdot D^2$$

$$m_1:\ \frac{\pi}{4}\rho \cdot L_1 \cdot D_1{}^2$$

Table

Diameter: D (m) Height: L (m)

Mass: m (kg)

Workpiece

Diameter: D_1 (m) Height: L_1 (m)

Mass: m_1 (kg) Quantity: n (pieces)

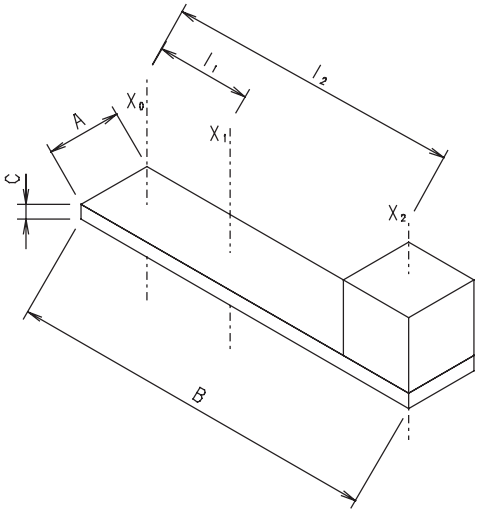
Density: ρ (kg/m^3)

(Notes)

・All workpieces are considered to be of the same shape and mass.

・All workpieces are considered to be at the same distance from the center point.

(Reference) Moment of Inertia for Multiple Rectangular Solids Combined



$$I_X = \frac{1}{12}m_1(A^2 + B^2 + 12 \cdot l_1^2) + \frac{1}{12}m_2(2 \cdot A^2 + 12 \cdot l_2^2)\ [\mathrm{kg \cdot m^2}]$$

m_1 : $\rho \cdot A \cdot B \cdot C$

m_2 : $\rho \cdot A^3$

l_1 : *Distance between X_0 and X_1 (center of rotation X_0)* (m)

l_2 : *Distance between X_0 and X_2 (center of rotation X_0)* (m)

Rectangular solid:

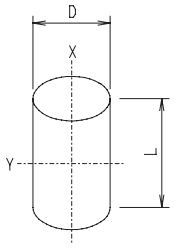
Depth A (m), height B (m), width C (m), mass m_1 (kg)

Cube:

Depth A (m), height A (m), width A (m), mass m_2 (kg)

Density: ρ (kg/m^3)

Moment of Inertia for a Cylinder

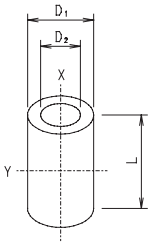


$$I_X = \frac{1}{8} m \cdot D^2 = \frac{\pi}{32} \rho \cdot L \cdot D^4 \, [\mathrm{kg \cdot m^2}]$$

$$I_Y = \frac{1}{4} m \left(\frac{D^2}{4} + \frac{L^2}{3} \right) [\mathrm{kg \cdot m^2}]$$

Outer diameter: D (m)
Length: L (m)
Mass: m (kg)
Density: ρ (kg/m^3)

Moment of Inertia for a Hollow Cylinder

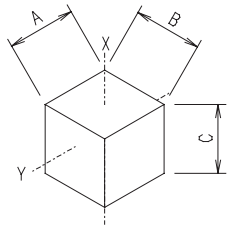


$$I_X = \frac{1}{8} m(D_1^2 + D_2^2) = \frac{\pi}{32} \rho \cdot L \cdot (D_1^4 - D_2^4) \, [\mathrm{kg \cdot m^2}]$$

$$I_Y = \frac{1}{4} m \left(\frac{D_1^2 + D_2^2}{4} + \frac{L^2}{3} \right) [\mathrm{kg \cdot m^2}]$$

Outer diameter: D_1 (m)
Inner diameter: D_2
Length: L (m)
Mass: m (kg)
Density: ρ (kg/m^3)

Moment of Inertia for a Rectangular Solid

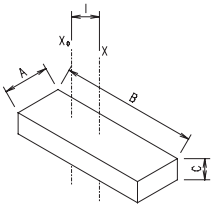


$$I_X = \frac{1}{12} m(A^2 + B^2) = \frac{1}{12} \rho \cdot A \cdot B \cdot C \cdot (A^2 + B^2) \, [\mathrm{kg \cdot m^2}]$$

$$I_Y = \frac{1}{12} m(B^2 + C^2) = \frac{1}{12} \rho \cdot A \cdot B \cdot C \cdot (B^2 + C^2) \, [\mathrm{kg \cdot m^2}]$$

Depth: A (m) Width: B (m)
Height: C (m) Mass: m (kg)
Density: ρ (kg/m^3)

Moment of Inertia for an Object with Different Centers of Rotation and Gravity



$$I_X = \frac{1}{12} m(A^2 + B^2 + 12 \cdot l^2) \, [\mathrm{kg \cdot m^2}]$$

m: $\rho \cdot A \cdot B \cdot C$

l: *Distance between X and X_0 (center of rotation X_0)* (m)

Rectangular solid:
Depth A (m), height B (m), width C (m), mass m (kg)
Cube:
Depth A (m), height A (m), width A (m), mass m (kg)
Density: ρ (kg/m^3)

If I is less than the permissible moment of inertia, the product can be used.

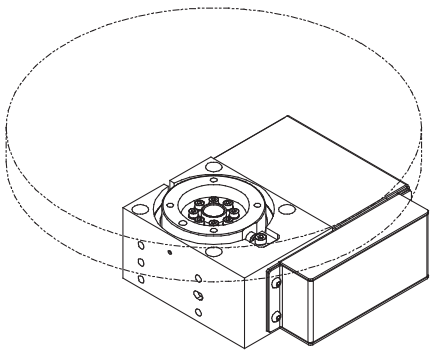
If I is greater than or equal to the permissible moment of inertia, the product cannot be used. Please select a different model or reduce the mass or rotational radius.

For the permissible moment of inertia for each model, please consult the "Angular Velocity versus Permissible Moment of Inertia" graph.

Calculating Torque in Horizontal Applications (Installed from the Bottom Surface)

$$T_1 = (I \times \omega' + \textit{external torque}) \times \textit{safety margin}$$

I: Moment of inertia (kg·m^2)
ω': Angular acceleration (rad/s^2)
Please ensure a safety margin of 1.5 or greater.



Example) External torque (friction torque)
External torque = $\mu \cdot m \cdot g \cdot r$

m: Workpiece mass (kg)		g: Gravitational acceleration (m/s^2)	
μ: Friction coefficient	ET20: 0.020	r: Rotary table radius	ET20: 29 (mm)
	ET35: 0.017		ET25: 34 (mm)

Confirm whether or not the calculated torque satisfies the requirements for the maximum output torque for the model.

If T_1 is less than the maximum output torque, the product can be used.

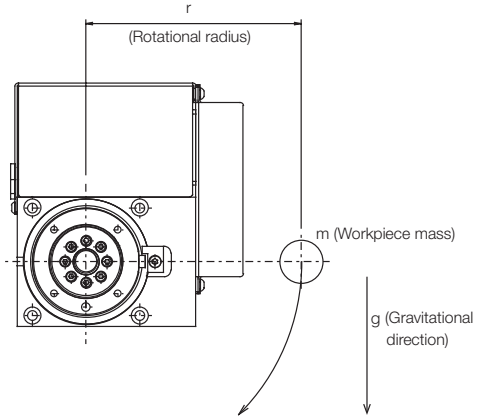
If T_1 is greater than or equal to the maximum output torque, the product cannot be used. Please select a different model or reduce the mass or rotational radius.

For the maximum output torque for each model, please consult the "Angular Velocity versus Output Torque" graph.

Calculating Torque in Horizontal Applications (Installed from a Side Surface)

$$T_2 = (m \cdot g \cdot r + I\omega' + \textit{external torque}) \times \textit{safety margin}$$

m: Workpiece mass (kg) g: Gravitational acceleration (m/s^2)
r: Radius (m) I: Moment of inertia (kg·m^2)
ω': Angular acceleration (rad/s^2)
Please ensure a safety margin of 1.5 or greater.



Confirm whether or not the calculated torque satisfies the requirements for the maximum output torque for the model.

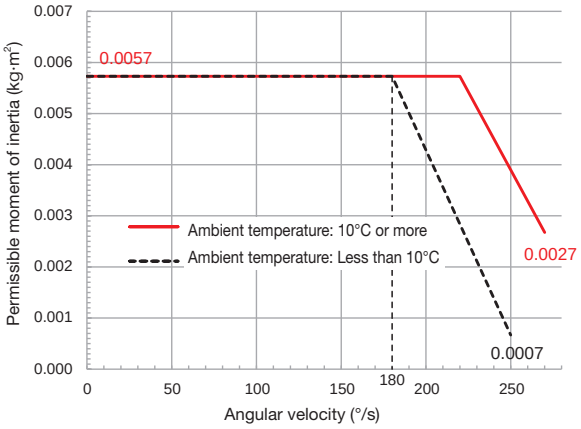
If T_2 is less than the maximum output torque, the product can be used.

If T_2 is greater than or equal to the maximum output torque, the product cannot be used.
Please select a different model or reduce the mass or rotational radius.

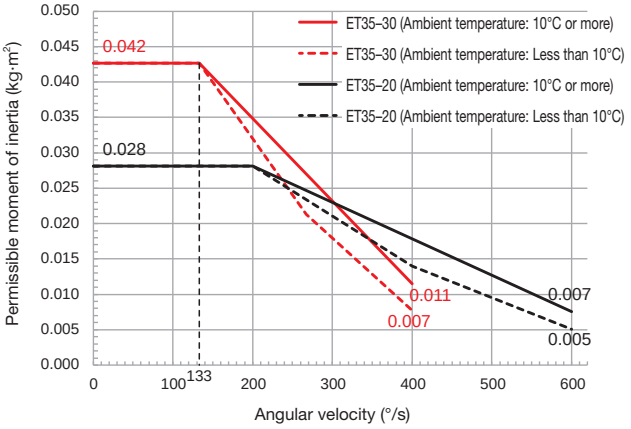
For the maximum output torque for each model, please consult the "Angular Velocity versus Output Torque" graph.

Angular Velocity versus Permissible Moment of Inertia

ET20

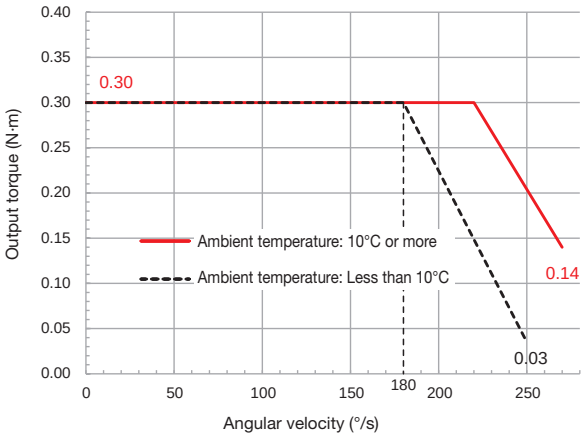


ET35

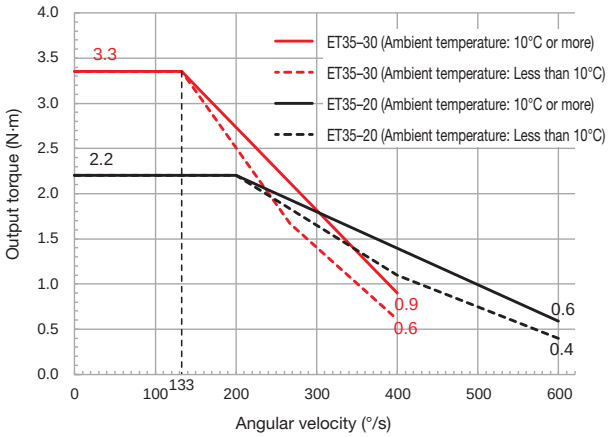


Angular Velocity versus Output Torque

ET20

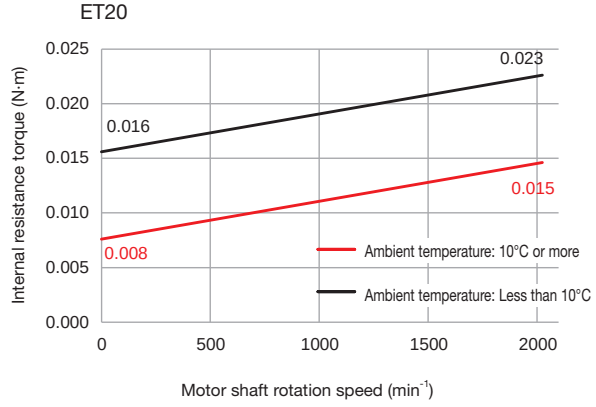


ET35

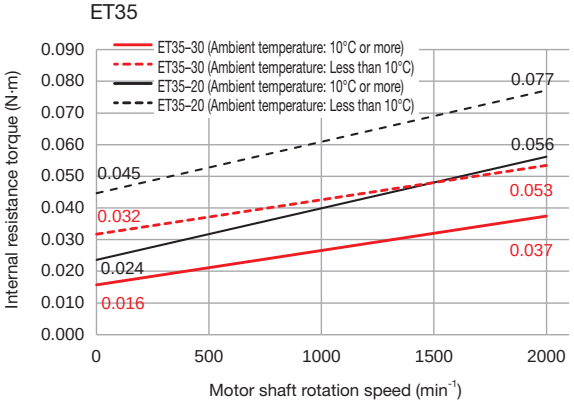


Motor Shaft Rotation Speed versus Internal Resistance Torque

ET20



ET35



Note) Internal resistance torque increases in low-temperature environments (10°C and below).
Therefore, it is recommended to use a higher safety margin when selecting a product.