



T STANDALONE AXIS

ASME-RTMBi1401003R#S0000

Data sheet

Version 2.0

ETEL

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1) RTMBi140-100 with connectors
and AccurET Modular 300VDC

2) RTMBi140-100-3RAS with free leads
and AccurET Modular 400/600VDC or third party controller 300/600VDC

3) RTMBi140-100-3RBS with free leads
and AccurET Modular 400/600VDC or third party controller 300/600VDC

AXIS DESIGNATION		
Number of controlled axes		1
Axes name		Theta
Thrust transmitter: DD (direct drive) or ID (indirect drive)		DD

TESTING CONDITIONS	UNIT	
Position controller	-	AccurET Modular 300 07/15A
Motion controller	-	none
Rated payload	kg	2.3
Rated inertia	kg.m ²	0.025
Tool point position	mm	centered on the table. 18.4 mm above rotor's interface
Ambient temperature	°C	22±1

DIMENSIONAL DATA	UNIT	
Outside diameter	mm	166
Inside diameter	mm	25
Height	mm	165
Total stroke	°	Unlimited
Total mass (without payload)	kg	15.5
Rotor inertia (without payload)	kg.m ²	3.36E-03

TORQUE CAPABILITIES (1)	UNIT	RTMBi140-100-3RAS	RTMBi140-100-3RBS
Peak torque	Nm	104	76.3
Continuous torque (2)	Nm	26.3	26.3
Standstill torque	Nm	19.9	19.9
Max. detent torque (average to peak)	Nm	0.96	0.96
Static friction (maximal value)	Nm	0.65	0.65
Dynamic friction (maximal value)	Nm/(rad/s)	0.012	0.012

LOAD CAPACITIES	UNIT	
Maximum moment load (3)	Nm	15
Maximum axial load	N	120
Maximum axial load in upside down configuration	N	120

DYNAMIC PERFORMANCE	UNIT	
Maximum speed (4)	rad/s	62.9
Maximum acceleration	rad/s ²	10000
Typical position stability at 2kHz (5)	arcsec	±1.5

STAGE ACCURACY	UNIT	
Positioning accuracy (without mapping)	arcsec	±20
Positioning accuracy (with mapping)	arcsec	±6
Unidirectional repeatability	arcsec	±2
Bidirectional repeatability	arcsec	±3
Radial runout	µm	20
Total axial error at 41 [mm] radius	µm	20

ENCODER CHARACTERISTICS	UNIT	
Encoder and signal type	-	Optical - Incremental
Output signal	-	1 Vpp
Line count	period/turn	5000
Reference mark	-	1
Power supply	V	5±10%

WORKING ENVIRONMENT	
IP protection grade	IP40
Standard compliance	SEMI S22

ELECTRICAL SPECIFICATIONS (1)		UNIT	Ironcore	Ironcore
	Motor type	-	TMB0140-100-3RAS	TMB0140-100-3RBS
	Motor model	-	3	3
	Number of phases	-	12.1	6.03
Kt	Force constant	Nm/Arms	6.97	3.48
Ku	Back EMF constant (6)	Vrms/(rad/s)	2.37	2.37
Km	Motor constant	Nm/√W	17.3	4.33
R20	Electrical resistance at 20°C (6)	Ohm	101 / 112	25.2 / 28.0
Ld/Lq	Electrical inductance (6)	mH	11.5	15.0
Ip	Peak current	Arms	2.40	4.81
Ic	Continuous current (2)	Arms	1.82	3.64
Is	Standstill current	Arms	0.0019	0.0019
ns	Standstill speed	rad/s	326	326
Udc	Nominal input voltage	VDC	196	196
Pc	Max. cont. power dissipation (2)	W	22	22
2p	Number of poles	-		

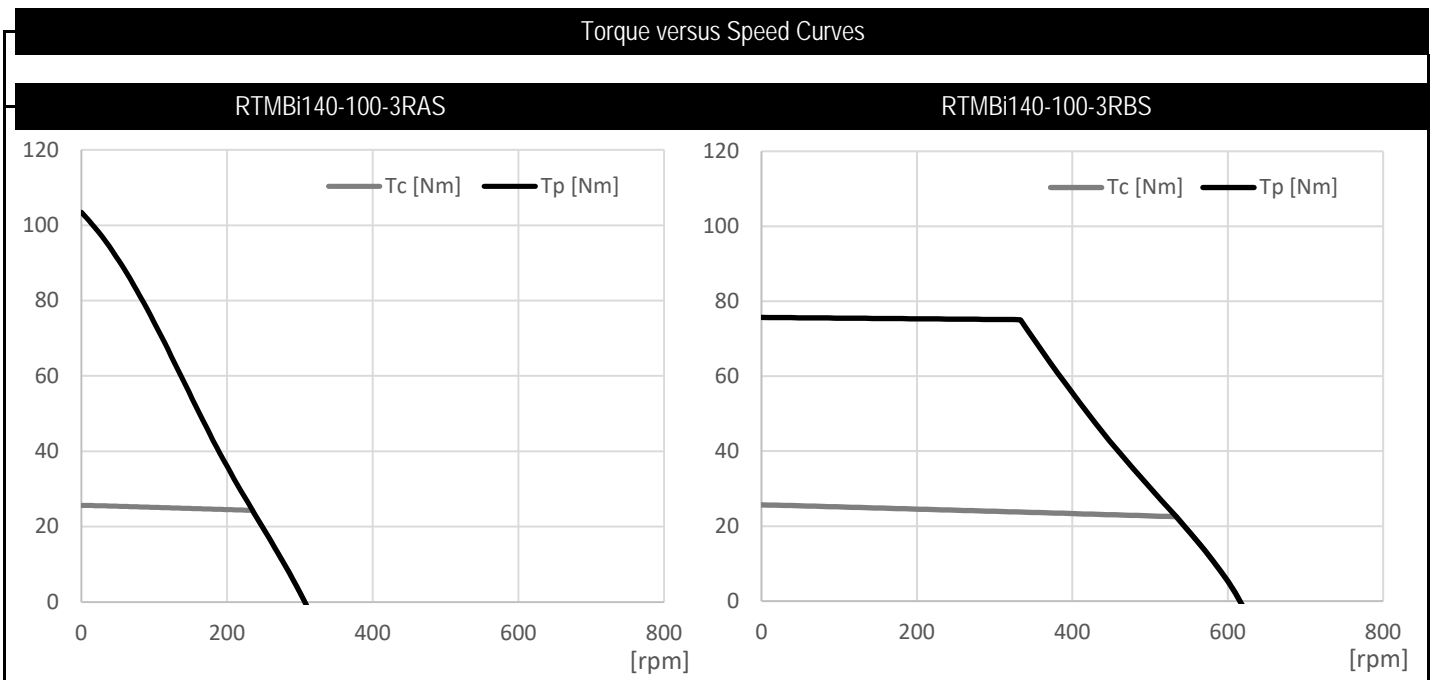
GUIDING ELEMENTS	
Type	Ball bearing

MATERIAL AND FINISH	
Baseplate	Stainless steel
Shaft	Stainless steel

According to the Machinery Directive 2006/42/EC, the system presently described falls into the "partly completed machinery" category and fully complies with it as long as the system is operated according to the working conditions described in the corresponding manual. Customer is responsible for setting safeties/limitations that will keep the motor in its safe operating area. ETEL cannot be held responsible if the system is used in an improper way.

Notes: The specifications given may be mutually exclusive. Unless stated otherwise, all measurements are made within the testing conditions.

- (1) Tolerances on electrical parameters are available on request.
- (2) Coils at 100°C with additional surface of 0.012m² fixed on the base and 0.018m² on the rotor made of black anodized aluminum.
- (3) At the fastening holes of the rotor.
- (4) See torque vs speed curve to check if the specification can be reached based on selected winding.
- (5) Specification given at encoder level without any additional load fixed to the customer interface. This specification is reduced when an additional mass is fixed to the customer interface.
- (6) Terminal to terminal.



AXIS DESIGNATION		
Number of controlled axes		1
Axes name		Theta
Thrust transmitter: DD (direct drive) or ID (indirect drive)		DD

TESTING CONDITIONS	UNIT	AccurET Modular 400 15/40A	AccurET Modular 600 15/40A	Third party 300 VDC no current limit	Third party 600 VDC no current limit
Position controller	-				
Motion controller	-	none			
Rated payload	kg	2.3			
Rated inertia	kg.m ²	0.025			
Tool point position	mm	centered on the table. 18.4 mm above rotor's interface			
Ambient temperature	°C	22±1			

DIMENSIONAL DATA	UNIT	
Outside diameter	mm	166
Inside diameter	mm	25
Height	mm	165
Total stroke	°	Unlimited
Total mass (without payload)	kg	15.5
Rotor inertia (without payload)	kg.m ²	3.36E-03

TORQUE CAPABILITIES (1)	UNIT				
Peak torque	Nm	118	131	98.4	131
Continuous torque (2)	Nm	26.3			
Standstill torque	Nm	19.9			
Max. detent torque (average to peak)	Nm	0.96			
Static friction (maximal value)	Nm	0.65			
Dynamic friction (maximal value)	Nm/(rad/s)	0.012			

LOAD CAPACITIES	UNIT	
Maximum moment load (3)	Nm	15
Maximum axial load	N	120
Maximum axial load in upside down configuration	N	120

DYNAMIC PERFORMANCE	UNIT	
Maximum speed (4)	rad/s	57.6
Maximum acceleration	rad/s ²	10000
Typical position stability at 2kHz (5)	arcsec	±1.5

STAGE ACCURACY	UNIT	
Positioning accuracy (without mapping)	arcsec	±20
Positioning accuracy (with mapping)	arcsec	±6
Unidirectional repeatability	arcsec	±2
Bidirectional repeatability	arcsec	±3
Radial runout	µm	20
Total axial error at 41 [mm] radius	µm	20

ENCODER CHARACTERISTICS	UNIT	
Encoder and signal type	-	Optical - Incremental
Output signal	-	1 Vpp
Line count	period/turn	5000
Reference mark	-	1
Power supply	V	5±10%

WORKING ENVIRONMENT	
IP protection grade	IP40
Standard compliance	SEMI S22

ELECTRICAL SPECIFICATIONS (1)		UNIT	AccurET Modular 400 15/40A	AccurET Modular 600 15/40A	Third party 300 VDC no current limit	Third party 600 VDC no current limit
Motor type	-	Ironcore				
Motor model	-	TMB0140-100-3RAS				
Number of phases	-	3				
Kt Force constant	Nm/Arms	12.1	12.1	12.1	12.1	
Ku Back EMF constant (6)	Vrms/(rad/s)	6.97	6.97	6.97	6.97	
Km Motor constant	Nm/ \sqrt{W}	2.37	2.37	2.37	2.37	
R20 Electrical resistance at 20°C (6)	Ohm	17.3	17.3	17.3	17.3	
Ld/Lq Electrical inductance (6)	mH	101 / 112	101 / 112	101 / 112	101 / 112	
Ip Peak current	Arms	13.9	16.9	10.6	16.9	
Ic Continuous current (2)	Arms	2.40	2.40	2.40	2.40	
Is Standstill current	Arms	1.82	1.82	1.82	1.82	
ns Standstill speed	rad/s	0.0019	0.0019	0.0019	0.0019	
Udc Nominal input voltage	VDC	395	565	300	600	
Pc Max. cont. power dissipation (2)	W	196	196	196	196	
2p Number of poles	-	22				

GUIDING ELEMENTS	
Type	Ball bearing

MATERIAL AND FINISH	
Baseplate	Stainless steel
Shaft	Stainless steel

According to the Machinery Directive 2006/42/EC, the system presently described falls into the "partly completed machinery" category and fully complies with it as long as the system is operated according to the working conditions described in the corresponding manual. Customer is responsible for setting safeties/limitations that will keep the motor in its safe operating area. ETEL cannot be held responsible if the system is used in an improper way.

Notes: The specifications given may be mutually exclusive. Unless stated otherwise, all measurements are made within the testing conditions.

(1) Tolerances on electrical parameters are available on request.

(2) Coils at 100°C with additional surface of 0.12m² fixed on the base and 0.018m² on the rotor made of black anodized aluminum.

(3) At the fastening holes of the rotor.

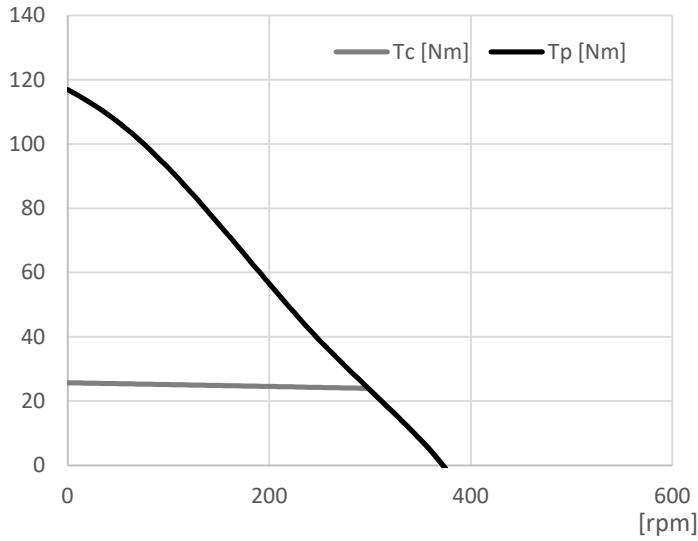
(4) See torque vs speed curve to check if the specification can be reached based on selected DC bus voltage limitation.

(5) Specification given at encoder level without any additional load fixed to the customer interface. This specification is reduced when an additional mass is fixed to the customer interface.

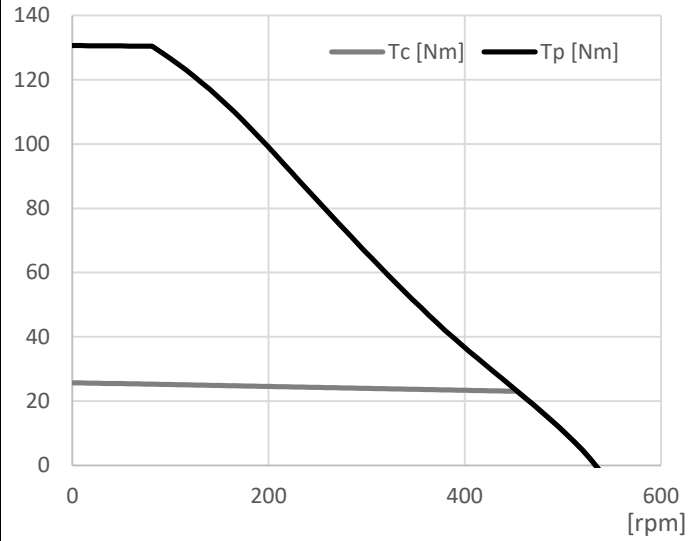
(6) Terminal to terminal.

Torque versus Speed Curves for RTMBi140-100-3RAS

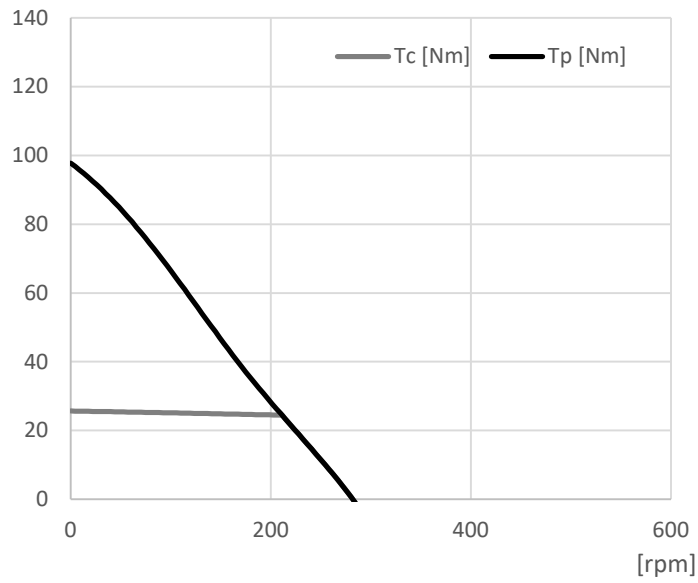
AccurET 400



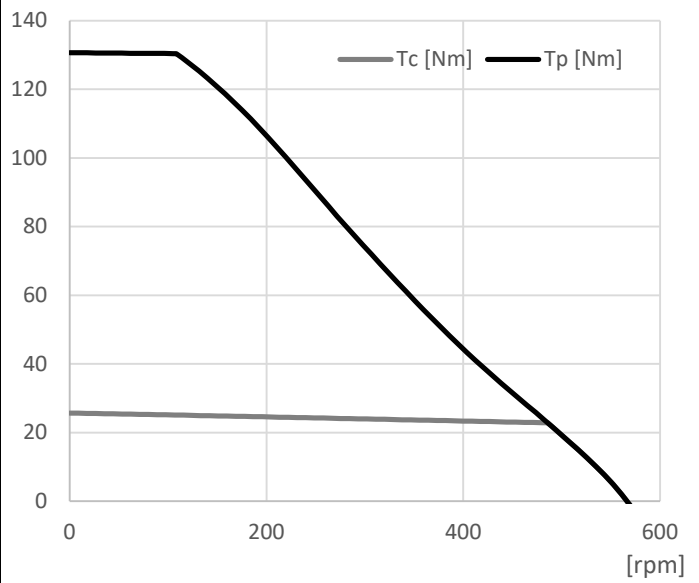
AccurET 600



Third party 300 V



Third party 600 V



AXIS DESIGNATION	
Number of controlled axes	1
Axes name	Theta
Thrust transmitter: DD (direct drive) or ID (indirect drive)	DD

TESTING CONDITIONS	UNIT	AccurET Modular 400 15/40A	AccurET Modular 600 15/40A	Third party 300 VDC no current limit	Third party 600 VDC no current limit
Position controller	-				
Motion controller	-	none			
Rated payload	kg	2.3			
Rated inertia	kg.m ²	0.025			
Tool point position	mm	centered on the table. 18.4 mm above rotor's interface			
Ambient temperature	°C	22±1			

DIMENSIONAL DATA	UNIT	
Outside diameter	mm	166
Inside diameter	mm	25
Height	mm	165
Total stroke	°	Unlimited
Total mass (without payload)	kg	15.5
Rotor inertia (without payload)	kg.m ²	3.36E-03

TORQUE CAPABILITIES (1)	UNIT	
Peak torque	Nm	131
Continuous torque (2)	Nm	26.3
Standstill torque	Nm	19.9
Max. detent torque (average to peak)	Nm	0.96
Static friction (maximal value)	Nm	0.65
Dynamic friction (maximal value)	Nm/(rad/s)	0.012

LOAD CAPACITIES	UNIT	
Maximum moment load (3)	Nm	15
Maximum axial load	N	120
Maximum axial load in upside down configuration	N	120

DYNAMIC PERFORMANCE	UNIT	
Maximum speed (4)	rad/s	117.2
Maximum acceleration	rad/s ²	10000
Typical position stability at 2kHz (5)	arcsec	±1.5

STAGE ACCURACY	UNIT	
Positioning accuracy (without mapping)	arcsec	±20
Positioning accuracy (with mapping)	arcsec	±6
Unidirectional repeatability	arcsec	±2
Bidirectional repeatability	arcsec	±3
Radial runout	µm	20
Total axial error at 41 [mm] radius	µm	20

ENCODER CHARACTERISTICS	UNIT	
Encoder and signal type	-	Optical - Incremental
Output signal	-	1 Vpp
Line count	period/turn	5000
Reference mark	-	1
Power supply	V	5±10%

WORKING ENVIRONMENT	
IP protection grade	IP40
Standard compliance	SEMI S22

ELECTRICAL SPECIFICATIONS (1)		UNIT	AccurET Modular 400 15/40A	AccurET Modular 600 15/40A	Third party 300 VDC no current limit	Third party 600 VDC no current limit	
Motor type	-	Ironcore					
Motor model	-	TMB0140-100-3RBS					
Number of phases	-	3					
Kt Force constant	Nm/Arms	6.03	6.03	6.03	6.03		
Ku Back EMF constant (6)	Vrms/(rad/s)	3.48	3.48	3.48	3.48		
Km Motor constant	Nm/ \sqrt{W}	2.37	2.37	2.37	2.37		
R20 Electrical resistance at 20°C (6)	Ohm	4.33	4.33	4.33	4.33		
Ld/Lq Electrical inductance (6)	mH	25.2 / 28.0	25.2 / 28.0	25.2 / 28.0	25.2 / 28.0		
Ip Peak current	Arms	33.8	33.8	33.8	33.8		
Ic Continuous current (2)	Arms	4.81	4.81	4.81	4.81		
Is Standstill current	Arms	3.64	3.64	3.64	3.64		
ns Standstill speed	rad/s	0.0019	0.0019	0.0019	0.0019		
Udc Nominal input voltage	VDC	395	565	300	600		
Pc Max. cont. power dissipation (2)	W	196	196	196	196		
2p Number of poles	-	22					

GUIDING ELEMENTS	
Type	Ball bearing

MATERIAL AND FINISH	
Baseplate	Stainless steel
Shaft	Stainless steel

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(3) At the fastening holes of the rotor.

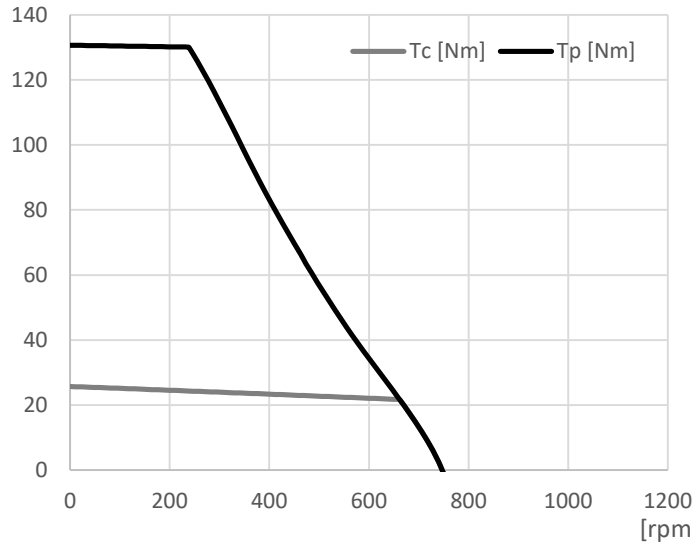
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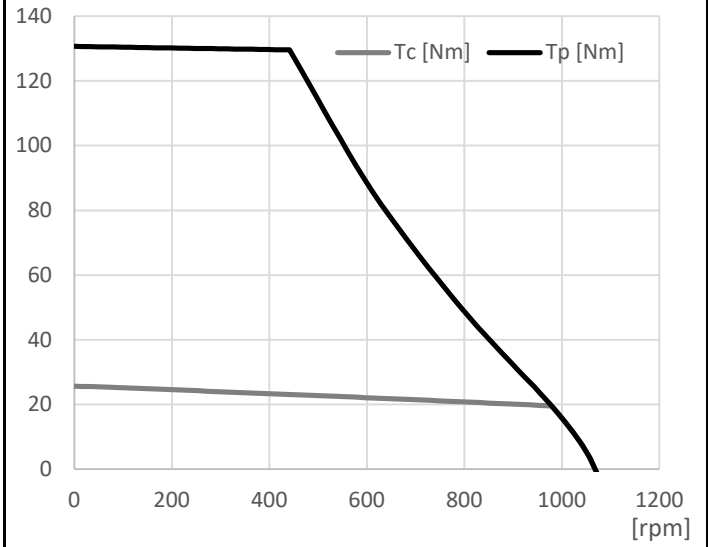
(6) Terminal to terminal.

Torque versus Speed Curves for RTMBi140-100-3RBS

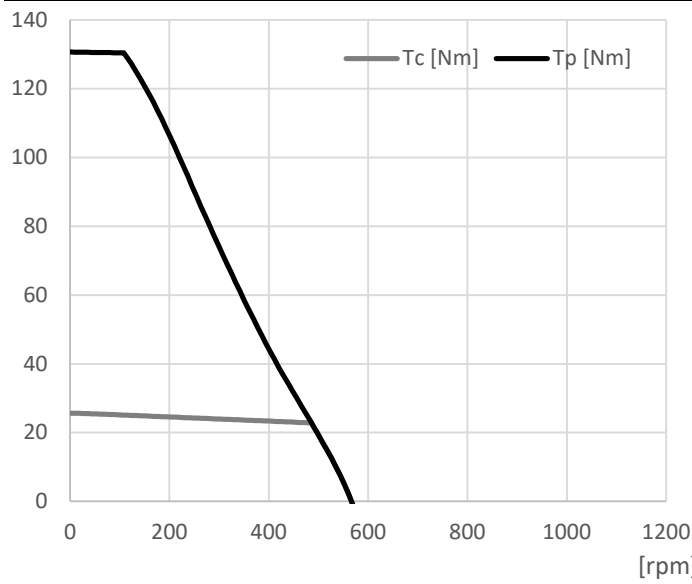
AccurET 400



AccurET 600



Third party 300 V



Third party 600 V

