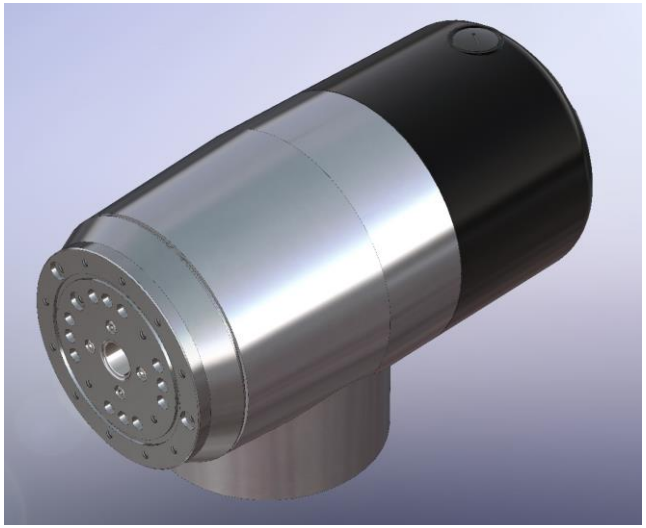
Technical Datasheet J-Actuator J17

J-Actuator is a rotary actuator with EtherCAT embedded motor control electronic board. It is composed by:

- 48V torque motor
- Harmonic gearbox
- Stationary brake
- Absolute encoder on motor axis or on both gearbox axes (optional)

It is available with different gear ratios and motor windings to customize the actuator according to the application requirements in terms of output torque, speed and power consumption.
The design of the J-Actuator is mainly developed in particular for robotic joints, but it could be used also as a rotary actuator with a very high density of torque capability. For a deep custom integration, it is available in the "naked" version without the external Aluminum alloy chassis.



Motor&Gear Specs		Mechanical Specs**		Electronics&Control Specs	
Ratio available	51-81-101-121	Permissible dynamic tilting moment [Nm]	105,4	Encoder	Absolute 20 bit + 16 bit multiturn
Rated motor speed [rpm]	3000	Permissible axial load [N]	1888	Stationary brake	Pin-lock
Max motor speed [rpm]	3500	Permissible radial load [N]	1266	Voltage [V]	48
Power	219	Weight [kg]	3,8	Fieldbus	EtherCAT - CiA 402
Rated Torque [Nm]	35 to 51*	Hollow shaft diameter [mm]	14	Electronic motor control board Safety Function	STO/SBC according to SIL 3, Pl e
Peak Torque [Nm]	44 to 70*	Operating Temperature [°C]	0-45		
*depending from gear ratio **referred to complete version with encoders on both gearbox axes and with external aluminum alloy chassis		Humidity	Max 90% non condensing		

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Complete version overall dimension and mounting: