

Servo motor EMMT-AS-60-S-HS-RMB

Part number: 5242203

FESTO



 General operating condition

Data sheet

Feature	Value
Ambient temperature	-40 °C ... 40 °C
Note on ambient temperature	Up to 80°C with derating of -1.5% per degree Celsius
Max. installation height	4000 m
Note on max. installation height	As of 1,000 m: only with derating of -1.0% per 100 m
Storage temperature	-40 °C ... 70 °C
Relative air humidity	0 - 90%
Conforms to standard	IEC 60034
Temperature class as per EN 60034-1	F
Max. winding temperature	155 °C
Rating class as per EN 60034-1	S1
Temperature monitoring	Digital motor temperature transmission via EnDat® 2.2
Motor type to EN 60034-7	IM V1 IM V3
Mounting position	optional
Degree of protection	IP40
Note on degree of protection	IP67 for motor housing including connection components
Concentricity, coaxiality, axial runout to DIN SPEC 42955	N
Balance quality	G 2.5
Detent torque	<1.0% of peak torque
Bearing lifetime under nominal conditions	20000 h
Interface code, motor out	60P
Electrical connection 1, connection type	Hybrid plug
Electrical connection 1, connector system	M23x1
Electrical connection 1, number of connections/cores	15
Electrical connection 1, connection pattern	00995913
Pollution degree	2
Note on materials	RoHS-compliant
Corrosion resistance class CRC	0 - No corrosion stress
LABS (PWIS) conformity	VDMA24364 zone III
Vibration resistance	Transport application test with severity level 2 to FN 942017-4 and EN 60068-2-6
Shock resistance	Shock test with severity level 2 to FN 942017-5 and EN 60068-2-27
Approval	RCM trademark c UL us - Recognized (OL)
CE mark (see declaration of conformity)	To EU EMC Directive To EU Low Voltage Directive In accordance with EU RoHS Directive

Feature	Value
UKCA marking (see declaration of conformity)	To UK RoHS instructions To UK regulations for electrical equipment
Certificate issuing authority	UL E342973
Nominal operating voltage DC	680 V
Type of winding switch	Star inside
Number of pole pairs	5
Standstill torque	0.66 Nm
Nominal torque	0.6 Nm
Peak torque	1.6 Nm
Nominal rotary speed	3000 rpm
Max. rotational speed	15000 rpm
Max. mechanical speed	16000 rpm
Angular acceleration	$\leq 100000 \text{ rad/s}^2$
Nominal power rating of motor	190 W
Continuous stall current	1.6 A
Nominal motor current	1.4 A
Peak current	5.4 A
Motor constant	0.41 Nm/A
Standstill torque constant	0.49 Nm/A
Voltage constant, phase-to-phase	29.9 mVmin
Phase-phase winding resistance	11.7 Ohm
Phase-phase winding inductance	38 mH
Winding longitudinal inductivity Ld (phase)	15.5 mH
Winding cross inductivity Lq (phase)	19 mH
Electric time constant	2.1 ms
Thermal time constant	41 min
Thermal resistance	1.5 K/W
Measuring flange	250 x 250 x 15 mm, steel
Total mass moment of inertia of output	0.257 kgcm ²
Product weight	1500 g
Permissible axial shaft load	70 N
Permissible radial shaft load	350 N
Rotor position sensor	Absolute multi-turn encoder
rotor position sensor, manufacturer designation	EQI 1131
rotor position sensor, absolute detectable revolutions	4096
Rotor position encoder interface	EnDat® 22
Rotor position sensor, encoder measuring principle	Inductive
rotor position sensor, DC operating voltage	5 V
rotor position sensor, DC operating voltage range	3.6 V ... 14 V
rotor position sensor, position values per revolution	524288
Rotor position transducer resolution	19 bit
rotor position sensor, system accuracy of angle measurement	-120 arcsec ... 120 arcsec
Brake holding torque	2.5 Nm
Operating voltage DC for brake	24 V
Brake current consumption	0.46 A
Power consumption, brake	11 W
Brake coil resistance	52.4 Ohm
Brake coil inductivity	700 mH
Brake separation time	$\leq 35 \text{ ms}$
Brake closing time	10 ms
DC brake response delay	$\leq 2 \text{ ms}$
Max. brake no-load speed	10000 rpm
Max. friction per braking process	5600 J

Feature	Value
Number of emergency stops per hour	1
Total brake friction	615 kJ
Mass moment of inertia of brake	0.074 kgcm ²
Switching cycles holding brake	10 million idle actuations (without friction work!)
Mean time to failure (MTTF), subcomponent	190 years, rotor position sensor