ENGINEERING DOCUMENTATION

Rotary Servo Motor

Dimensional & Integration Guide

DOCUMENT	REVISION / ISSUE	STATUS
DIG-ES-SM-A02-060S-T0P64NM-200W-002	DRAFT-08 / 27 Aug 2026	Engineering Integration Reference

Integration Overview

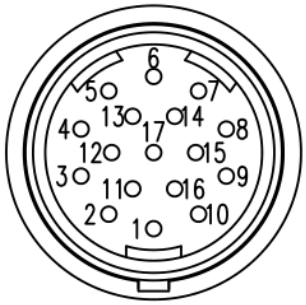
Closed-loop rotary servo motor for specified motion axes. This guide supports mechanical mounting, shaft and coupling integration, feedback and brake planning, cable routing, thermal validation and staged commissioning.

Key Integration Facts

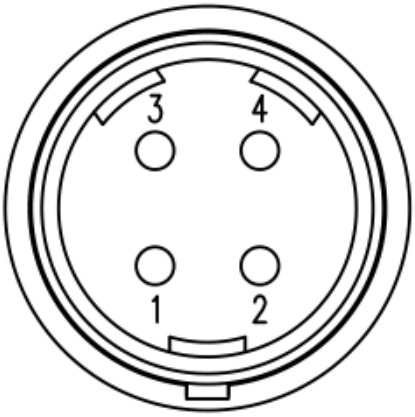
INTEGRATION ITEM	PUBLISHED VALUE
Rated Torque	0.64 N·m
Rated Speed	3000 rpm
Flange Size	60 mm

Product Structure & Views

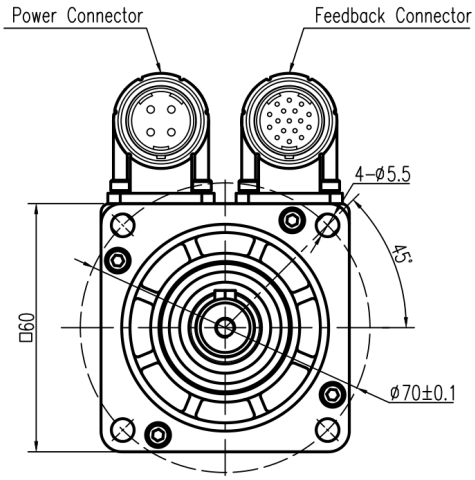
These views present product structure, mounting interfaces and relevant integration geometry for this SKU.



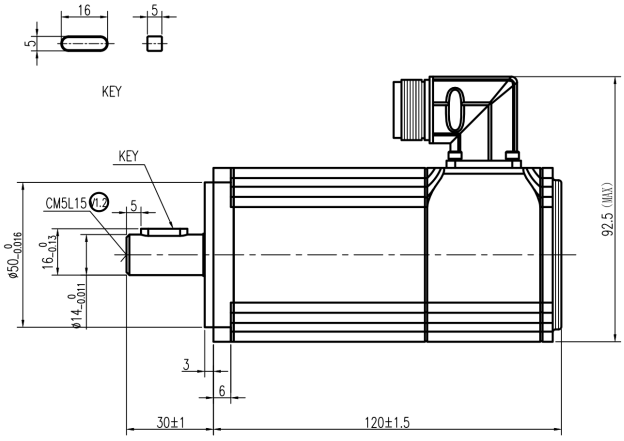
Mechanical View 2



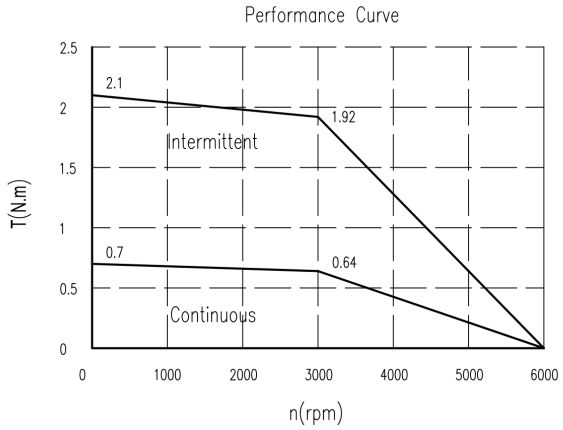
Mechanical View 4



Mechanical View 6



Mechanical View 7



Mechanical View 8

VIEW	FIELD	VALUE
Mechanical View 2	Connector pin label 1-17	Pin 1-17
Mechanical View 4	PINS	Pin 1~4
Mechanical View 6	Power Connector Label	Power Connector
	Feedback Connector Label	Feedback Connector
	Mounting Hole Diameter and Quantity	4 holes, Ø5.5 mm
	Mounting Hole Angular Position	45°
	Square Flange Side Length	60 mm × 60 mm square
	Mounting Hole Pitch Circle Diameter with Tolerance	Ø70 ±0.1 mm
Mechanical View 7	Keyway width	16 mm
	Keyway depth	5 mm
	Keyway width	5 mm
	Shaft diameter with tolerance	Φ50 0/-0.016 mm
	Keyway depth with tolerance	16 0/-0.13 mm
	Hole diameter with tolerance	Φ4 0/-0.011 mm
	Mounting spacing	3 mm
	Mounting spacing	6 mm
	Axial length with tolerance	30±1 mm
	Overall length with tolerance	120±1.5 mm
	Maximum height	92.5 mm (MAX)
Mechanical View 8	Performance Curve Title	Performance Curve
	Torque Axis Label	T(N.m)
	Speed Axis Label	n(rpm)
	Intermittent Operation Label	Intermittent
	Continuous Operation Label	Continuous
	Torque Grid Value 2.5 N.m	2.5 N.m
	Intermittent Starting Torque	2.1 N.m
	Torque Grid Value 2 N.m	2 N.m
	Intermittent Rated Torque at 3000 rpm	1.92 N.m @ 3000 rpm
	Torque Grid Value 1.5 N.m	1.5 N.m
	Continuous Starting Torque	0.7 N.m
	Continuous Rated Torque at 3000 rpm	0.64 N.m @ 3000 rpm
	Torque Grid Value 0.5 N.m	0.5 N.m
	Torque Zero Point	0 N.m
	Speed Zero Point	0 rpm
	Speed Grid Value 1000 rpm	1000 rpm

VIEW	FIELD	VALUE
Speed Grid Value 2000 rpm	2000 rpm	
Speed Grid Value 3000 rpm	3000 rpm	
Speed Grid Value 4000 rpm	4000 rpm	
Speed Grid Value 5000 rpm	5000 rpm	
Maximum Speed Value 6000 rpm	6000 rpm	
Torque Grid Value 1 N.m	1 N.m	

Overall Dimensions and Mounting Interface

PARAMETER	PUBLISHED VALUE	UNIT
Flange Size	60	mm

- Confirm the mounting face, locating feature, shaft geometry, fastener engagement and removal clearance against the applicable exact-SKU drawing.
- Mount the motor on a flat, rigid interface and avoid using fasteners to pull a misaligned assembly into position.

Shaft, Coupling and Load Path

PARAMETER	PUBLISHED VALUE	UNIT
Rotor Inertia	0.375	kg·cm²

- Align the driven shaft and coupling before tightening; validate radial, axial and moment loads against applicable bearing-load data.
- Do not hammer, uncontrolled press-fit or transmit installation force through the motor bearings.

Electrical, Feedback and Brake Integration

PARAMETER	PUBLISHED VALUE	UNIT
Position Feedback Device	2500 PPR incremental encoder	

- Use only the current winding, feedback, brake and connector definitions for this exact SKU.
- Verify drive compatibility, polarity, current limits, feedback direction and brake sequencing before enabling torque.

Thermal, Duty and Environmental Conditions

PARAMETER	PUBLISHED VALUE	UNIT
Rated Torque	0.64	N·m
Operating Temperature	20 40	°C

- Validate winding and housing temperature under the installed duty cycle, ambient condition, mounting heat path and enclosure airflow.
- Published peak values are transient boundaries and must not be treated as continuous operating ratings.

Cable Routing, Grounding and EMC

PARAMETER	PUBLISHED VALUE	UNIT
Position Feedback Device	2500 PPR incremental encoder	

- Provide strain relief and bend radius through the full machine motion envelope.
- Separate motor power, brake and feedback wiring and terminate shields according to the specified system grounding architecture.

Commissioning and Motion Validation

PARAMETER	PUBLISHED VALUE	UNIT
Rated Speed	3000	rpm
Rated Torque	0.64	N·m

- Commission at low energy with the transmission unloaded or safely restrained, then confirm direction, feedback polarity, brake final integration, current limit and fault response.
- Validate the complete axis through intended acceleration, speed, load, stop and fault cycles during integration planning.

Integration Checklist

01	Confirm the exact SKU, 2D drawing and applicable wiring data.
02	Verify mounting, shaft, coupling, alignment, fasteners and removal clearance.
03	Validate radial and axial loads, inertia, acceleration and credible shock cases.
04	Confirm drive, winding, feedback, brake and connector compatibility.
05	Set current, speed, acceleration and thermal limits from the installed duty cycle.
06	Verify cable routing, shielding, grounding, strain relief and bend radius.
07	Commission at low energy before validating the full machine cycle.

View SKU Product Datasheet **Request controlled 2D drawing** **Request controlled STEP review** **Request a Quote**

Engineering Use and Verification Notice

01. This Dimensional & Integration Guide applies only to EmbodyStack SKU ES-SM-A02-060S-T0P64NM-200W-002 and is intended for dimensional evaluation and preliminary integration. It is not a applicable manufacturing drawing, wiring definition, application approval, machinery risk assessment, safety validation or integration planning document. Before design freeze, machining, wiring or energization, verify all dimensions, tolerances, mounting and locating features, load boundaries, electrical interfaces, thermal conditions, cabling, grounding, protection, commissioning and applicable regulatory requirements against the applicable EmbodyStack engineering data for this exact SKU. Where this guide and applicable product documentation differ, the applicable product documentation governs. Validate the complete installed system under intended duty cycles, loads, accelerations, environmental conditions and credible fault cases.