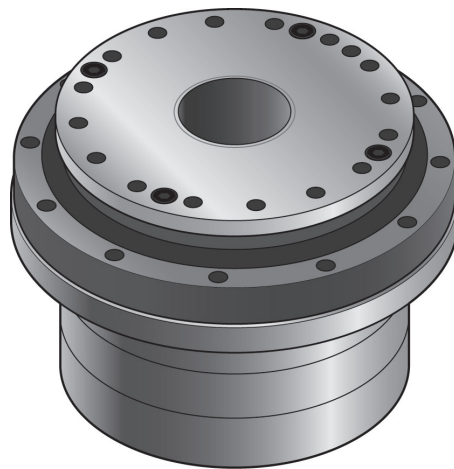


Harmonic Drive[®]

MECHATRONICS

AC Servo Actuator

S H A s e r i e s m a n u a l





Introduction

Thank you for purchasing our SHA series AC Servo Actuator.

Wrong handling or use of this product may result in unexpected accidents or shorter life of the product. Read this document carefully and use the product correctly so that the product can be used safely for many years.

Product specifications are subject to change without notice for improvement purposes.

Company names and product names in this document are generally registered trademarks or trademarks of their respective companies.

Keep this manual in a convenient location and refer to it whenever necessary in operating or maintaining the units.



The end user of the actuator should have a copy of this manual.

SAFETY GUIDE

To use this actuator safely and correctly, be sure to read SAFETY GUIDE and other parts of this document carefully and fully understand the information provided herein before using the actuator.

NOTATION

Important safety information you must note is provided herein. Be sure to observe these instructions.

| | |
|---|--|
|  WARNING | Indicates a potentially hazardous situation, which, if not avoided, could result in death or serious personal injury. |
|  CAUTION | Indicates a potentially hazardous situation, which, if not avoided, may result in minor or moderate personal injury and/or damage to the equipment. |
| Caution | Indicates what should be performed or avoided to prevent non-operation or malfunction of the product or negative effects on its performance or function. |

LIMITATION OF APPLICATIONS

The equipment listed in this document may not be used for the applications listed below:

- Space equipment
- Automobile, automotive parts
- Aircraft, aeronautic equipment
- Amusement equipment, sport equipment, game machines
- Nuclear equipment
- Machine or devices acting directly on the human body
- Household apparatus
- Instruments or devices to transport or carry people
- Vacuum equipment
- Apparatus or devices used in special environments

If the above list includes your intending application for our products, please consult us.



Safety measures are essential to prevent accidents resulting in death, injury or damage of the equipment due to malfunction or faulty operation.

SAFETY NOTE

ITEMS YOU SHOULD NOTE WHEN USING THE ACTUATOR

● CAUTIONS RELATED TO THE DESIGN



Always use under followings conditions.

The actuator is designed to be used indoors. Observe the following conditions:

- Ambient temperature: 0 to 40 °C
- Ambient humidity: 20 to 80 %RH (Non-condensation)
- Vibration: Max 25 m/s²
- No contamination by water, oil
- No corrosive or explosive gas

Follow exactly the instructions in the relating manuals to install the actuator in the equipment.

- Ensure exact alignment of the actuator center and the center of the corresponding machine by following the manual.
- Failure to observe this caution may lead to vibration, resulting in damage of output elements.

● CAUTIONS FOR USAGE



Keep limited torques of the actuator.

- Keep limited torques of the actuator.
- Be aware, that if arms attached to output element hits by accident an solid, the output element may be uncontrollable.

Never connect cables directly to a power supply socket.

- Each actuator must be operated with a proper driver.
- Failure to observe this caution may lead to injury, fire or damage of the actuator.

Do not apply impacts and shocks

- The actuator directly connects with the encoder so do not use a hammer during installation.
- Failure to observe this caution could damage the encoder and may cause uncontrollable operation.

Avoid handling of actuators by cables.

- Failure to observe this caution may damage the wiring, causing uncontrollable or faulty operation.

ITEMS YOU SHOULD NOTE WHEN USING THE DRIVER**● CAUTIONS RELATED TO THE DESIGN****Always use drivers under followings conditions.**

The driver generates heat. Use under the following conditions while paying careful attention to the heat radiation.

- Mount in a vertical position keeping sufficient clearance.
- 0 to 50 °C, 95 %RH or below (No condensation)
- No vibration or physical shock
- No dust, dirt, corrosive or inflammable gas

Use sufficient noise suppressing means and safe grounding.

Any noise generated on a signal wire will cause vibration or improper motion. Conform to the following conditions.

- Keep signal and power leads separated.
- Keep leads as short as possible.
- Ground actuator and driver at one single point, minimum ground resistance class: D (less than 100 ohms)
- Do not use a power line filter in the motor circuit.

Pay attention to negative torque by inverse load.

- Inverse load may cause damages of drivers.
- Please consult our sales office, if you intent to apply products for inverse load.

Use a fast-response type ground-fault detector designed for PWM inverters.

Do not use a time-delay-type ground-fault detector.

Safety measures are essential to prevent accidents resulting in death, injury or damage of the equipment due to malfunction or faulty operation.

● CAUTIONS FOR USAGE**Never change wiring while power is active.**

Make sure of power non-active before servicing the products. Failure to observe this caution may result in electric shock or personal injury.

Do not touch terminals or inspect products at least 5 minutes after turning OFF power.

- Otherwise residual electric charges may result in electric shock.
- Make installation of products not easy to touch their inner electric components.



Do not make a voltage resistance test.

- Failure to observe this caution may result in damage of the control unit.
- Please consult our sales office, if you intent to use a voltage resistance test.

Do not operate control units by means of power ON/OFF switching.

- Start/stop operation should be performed via input signals.
- Failure to observe this caution may result in deterioration of electronic parts.

DISPOSAL



All products or parts have to be disposed of as industrial waste.

Since the case or the box of drivers have a material indication, classify parts and dispose them separately.

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Related manual

The table below lists related manual. Check each item as necessary.

| Title | Description |
|---|--|
| AC Servo Driver HA-800 series manual | The specifications and characteristics of HA-800 series are explained. |
| AC Servo Driver HA-900 series manual | The specifications and characteristics of HA-900 series are explained. |
| | |
| | |

Conformance to overseas standards

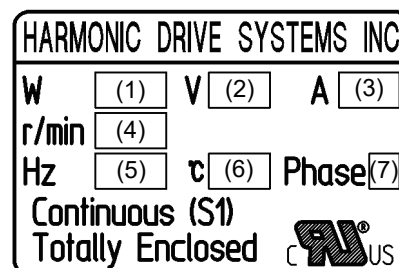
The SHA series actuator conforms to following overseas standards.

| | |
|---|--------------------------------------|
| UL Standard | UL1004-1,UL1004-6 (File No. E243316) |
| CSA Standard | C22.2 No.100 |
| European Low Voltage EC Directives | EN60034-1, EN60034-5 |

UL nameplate sticker

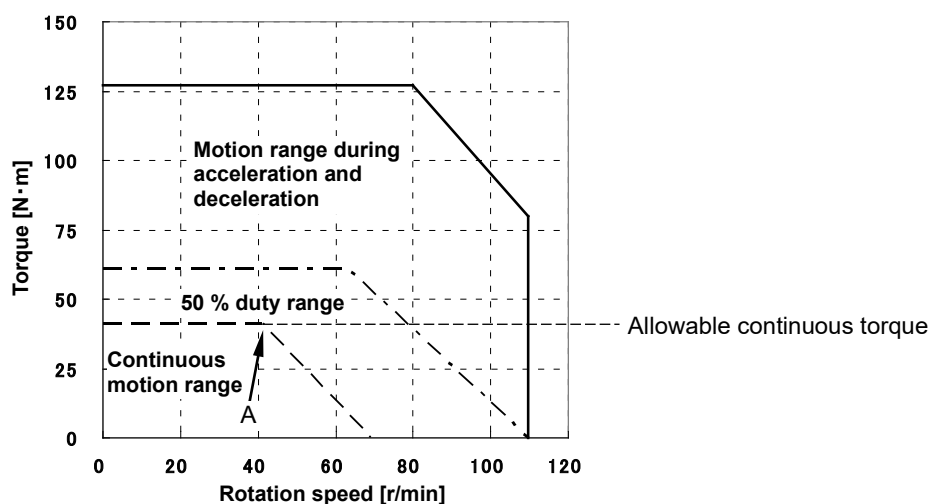
The following specifications of the SHA series actuators are shown based on the UL1004-1,UL1004-6 (File No. E243316) standards.

| Nameplate field | Explanation |
|-----------------|--|
| (1) | Output [W] at point A on the graph below |
| (2) | Voltage [V] between motor wires at point A on the graph below |
| (3) | Allowable continuous current [A] |
| (4) | Rotation speed [r/min] at point A on the graph below |
| (5) | Current fundamental frequency [Hz] at point A on the graph below |
| (6) | Allowable range temperature [°C] |
| (7) | Number of phase |



UL nameplate sticker

Aluminum radiation plate: 350×350×18 [mm]



The nameplate values of various models are shown below.

SG/HP type

| Item | Model | SHA20A | | | | |
|----------------------------------|-------|--------|-----|-----|-----|-----|
| | | 51 | 81 | 101 | 121 | 161 |
| (1) Output at point A | W | 99 | 109 | 109 | 106 | 86 |
| (2) Voltage at point A | V | 113 | 117 | 117 | 119 | 122 |
| (3) Allowable continuous current | A | 2.1 | 2.0 | 2.0 | 1.9 | 1.6 |
| (4) Speed at point A | r/min | 44 | 30 | 24 | 21 | 17 |
| (5) Frequency at point A | Hz | 187 | 203 | 202 | 212 | 228 |
| (6) Allowable range temperature | °C | 40 | | | | |
| (7) Number of phase | — | 3 | | | | |

| Item | Model | SHA25A (Motor input voltage 100 V) | | | | | SHA25A (Motor input voltage 200 V) | | | | | |
|----------------------------------|-------|---------------------------------------|-----|-----|-----|-----|---------------------------------------|-----|-----|------|-----|-----|
| | | 51 | 81 | 101 | 121 | 161 | 11 | 51 | 81 | 101 | 121 | 161 |
| | | (1) Output at point A | W | 165 | 188 | 190 | 178 | 127 | 133 | 175 | 203 | 207 |
| (2) Voltage at point A | V | 61 | 64 | 65 | 64 | 62 | 101 | 115 | 122 | 125 | 125 | 120 |
| (3) Allowable continuous current | A | 4.7 | 4.7 | 4.7 | 4.5 | 3.7 | 3.0 | 3.0 | 3.0 | 2.9 | 2.6 | 2.1 |
| (4) Speed at point A | r/min | 45 | 31 | 25 | 21 | 15 | 141 | 41 | 29 | 24.5 | 21 | 15 |
| (5) Frequency at point A | Hz | 191 | 209 | 210 | 212 | 201 | 129 | 174 | 196 | 206 | 212 | 201 |
| (6) Allowable range temperature | °C | 40 | | | | | | | | | | |
| (7) Number of phase | — | 3 | | | | | | | | | | |

| Item | Model | SHA32A | | | | | | SHA40A | | | | |
|----------------------------------|-------|--------|-----|-----|-----|------|------|--------|------|------|-----|-----|
| | | 11 | 51 | 81 | 101 | 121 | 161 | 51 | 81 | 101 | 121 | 161 |
| (1) Output at point A | W | 240 | 328 | 369 | 373 | 308 | 233 | 487 | 564 | 570 | 560 | 480 |
| (2) Voltage at point A | V | 97 | 110 | 114 | 118 | 116 | 115 | 109 | 115 | 115 | 116 | 122 |
| (3) Allowable continuous current | A | 6.0 | 6.0 | 6.0 | 5.7 | 5.0 | 4.1 | 9.0 | 9.0 | 9.0 | 8.8 | 7.2 |
| (4) Speed at point A | r/min | 115 | 34 | 23 | 20 | 16.5 | 12.5 | 29 | 20.5 | 16.5 | 14 | 12 |
| (5) Frequency at point A | Hz | 105 | 145 | 155 | 168 | 166 | 168 | 123 | 138 | 139 | 141 | 161 |
| (6) Allowable range temperature | °C | 40 | | | | | | | | | | |
| (7) Number of phase | — | 3 | | | | | | | | | | |

| Item | Model | SHA45A | | | | |
|----------------------------------|-------|--------|------|------|------|-----|
| | | 51 | 81 | 101 | 121 | 161 |
| (1) Output at point A | W | 456 | 534 | 543 | 551 | 537 |
| (2) Voltage at point A | V | 103 | 108 | 108 | 109 | 112 |
| (3) Allowable continuous current | A | 10.0 | 10.0 | 10.0 | 10.0 | 9.2 |
| (4) Speed at point A | r/min | 25 | 17.6 | 14.3 | 12 | 9.8 |
| (5) Frequency at point A | Hz | 107 | 119 | 120 | 121 | 132 |
| (6) Allowable range temperature | °C | 40 | | | | |
| (7) Number of phase | — | 3 | | | | |

| Item | Model | SHA58A | | | | SHA65A | | | |
|----------------------------------|-------|--------|------|------|------|--------|------|------|------|
| | | 81 | 101 | 121 | 161 | 81 | 101 | 121 | 161 |
| (1) Output at point A | W | 897 | 948 | 863 | 731 | 964 | 963 | 958 | 802 |
| (2) Voltage at point A | V | 99 | 101 | 101 | 107 | 92 | 92 | 96 | 100 |
| (3) Allowable continuous current | A | 17.7 | 17.8 | 16.4 | 13.4 | 22.0 | 21.9 | 20.1 | 16.3 |
| (4) Speed at point A | r/min | 12 | 10 | 8.5 | 7.2 | 10 | 8 | 7.4 | 6.2 |
| (5) Frequency at point A | Hz | 130 | 135 | 137 | 155 | 108 | 108 | 119 | 133 |
| (6) Allowable range temperature | °C | 40 | | | | | | | |
| (7) Number of phase | — | 3 | | | | | | | |

CG type

| Item | Model | SHA20A | | | | |
|----------------------------------|-------|--------|------|-----|-----|-----|
| | | 50 | 80 | 100 | 120 | 160 |
| (1) Output at point A | W | 97 | 108 | 108 | 106 | 85 |
| (2) Voltage at point A | V | 112 | 116 | 116 | 119 | 122 |
| (3) Allowable continuous current | A | 2.1 | 2.1 | 2.1 | 2.0 | 1.7 |
| (4) Speed at point A | r/min | 44 | 29.5 | 24 | 21 | 17 |
| (5) Frequency at point A | Hz | 183 | 197 | 200 | 210 | 227 |
| (6) Allowable range temperature | °C | 40 | | | | |
| (7) Number of phase | — | 3 | | | | |

| Item | Model | SHA25A (Motor input voltage 100 V) | | | | | SHA25A (Motor input voltage 200 V) | | | | |
|----------------------------------|-------|---------------------------------------|-----|------|------|-----|---------------------------------------|-----|-----|------|-----|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| | | (1) Output at point A | W | 167 | 191 | 192 | 174 | 127 | 177 | 201 | 204 |
| (2) Voltage at point A | V | 62 | 65 | 65 | 63 | 61 | 115 | 121 | 123 | 123 | 119 |
| (3) Allowable continuous current | A | 4.7 | 4.7 | 4.7 | 4.5 | 3.7 | 3.0 | 3.0 | 3.0 | 2.6 | 2.1 |
| (4) Speed at point A | r/min | 47 | 32 | 25.5 | 20.5 | 15 | 42 | 29 | 24 | 20.5 | 15 |
| (5) Frequency at point A | Hz | 196 | 213 | 213 | 205 | 200 | 175 | 193 | 200 | 205 | 200 |
| (6) Allowable range temperature | °C | 40 | | | | | | | | | |
| (7) Number of phase | — | 3 | | | | | | | | | |

| Item | Model | SHA32A | | | | | SHA40A | | | | |
|----------------------------------|-------|--------|------|-----|------|------|--------|------|------|------|------|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| (1) Output at point A | W | 321 | 372 | 373 | 308 | 233 | 493 | 558 | 568 | 568 | 488 |
| (2) Voltage at point A | V | 109 | 114 | 117 | 116 | 115 | 109 | 114 | 115 | 116 | 123 |
| (3) Allowable continuous current | A | 6.0 | 6.0 | 5.7 | 5.0 | 4.1 | 9.0 | 9.0 | 9.0 | 8.8 | 7.2 |
| (4) Speed at point A | r/min | 34 | 23.5 | 20 | 16.5 | 12.5 | 30 | 20.5 | 16.6 | 14.2 | 12.2 |
| (5) Frequency at point A | Hz | 142 | 157 | 167 | 165 | 167 | 125 | 137 | 138 | 142 | 163 |
| (6) Allowable range temperature | °C | 40 | | | | | | | | | |
| (7) Number of phase | — | 3 | | | | | | | | | |

Chapter 1

Outlines

This chapter explains the features, functions and specifications of the actuator.

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1-1 Outlines

SHA series AC Servo Actuators provide high torque and highly accurate rotary operation. These AC Servo Actuators are each composed of HarmonicDrive® speed reducer for precision control from model No. 20 to No. 65 and a flat AC servo motor. There are 3 types of speed reducers: SG type with SHG series incorporated, HP type with HPF series incorporated, and CG type with newly added CSG series incorporated. They are an advanced version of current FHA series AC Servo Actuators having a flat, hollow structure.

One key feature of SHA series actuators is their compact size. The outer diameter has been reduced, while the maximum torque/volume ratio is approximately double that of any conventional actuator. The hollow structure maintains the same size as conventional actuators. A through-hole is provided at the center of the actuator, through which wirings, air pipes, and even laser beams can be passed to supply power and give/receive signals to moving parts of machines and devices.

The dedicated driver series HA-800/900 is a family of servo drive units for position/speed control, developed exclusively for driving SHA series actuators. The small, multi-functional drivers control the SHA series actuators' operations with great accuracy and precision.

SHA series actuators play an important role in driving various factory automation (FA) equipment, such as robot joints, alignment mechanisms for semi-conductor and LCD devices, ATC of metal-cutting machines, printing machine roller drive, etc.

◆ Doubled torque/volume ratio

The incorporation of a high-torque HarmonicDrive® reducer for precision control SHG series or CSG series has achieved an approximately 20 % smaller external diameter when compared with our conventional products. Accordingly, the maximum torque/volume ratio has increased to approximately double the ratio of any conventional actuator. Based on the maximum torque, you can select a model of one smaller size. Also, output torque at the same volume/weight is very high compared to when a direct drive motor is used. This is another reason why the SHA series has a great advantage.

◆ Realized larger size, A wide product lineup

7 models are available for SG type including those (#58, #65) accommodating high torque up to 3400 N·m - the range not previously supported. The wide lineup also includes models supporting intermediate reduction ratios of 1/81, 1/121, and so on. CG type has 4 models available with 5 reduction ratios of 1/50 to 1/160.

◆ Modular design

The components of the SHA series, such as speed reducers, output shaft bearing, motor, brake and encoder, are arranged based on modular design. We can also custom-design a model meeting your specific requirements, so please contact your HDS sales representative.

◆ Comes standard with a 17-bit magnetic absolute encoder

The newly developed AC servo motors are equipped with HDS's original highly reliable 17-bit magnetic absolute encoder* with safety function. The serial communication saves wiring and provides not only a multi revolution counting function which is a must-have feature of actuators with speed reducers, but it also has an internal backup battery to retain absolute positions even when the encoder cable is disconnected briefly.

The encoder also constantly compares two sets of detected angles. If any abnormality is found, the encoder's built-in failsafe function outputs a signal to the host system. This certainly helps you build a safe system.

* Model No. 20 is equipped with an optical encoder.

◆ Supporting open network control when combined with a dedicated driver

By using a dedicated HA-800 series driver, you can control your actuator on a MECHATROLINK-II or CC-Link network.

◆ For high speeds

Also supports high speeds in combination with the hollow planetary speed reducer HPF series.

◆ CG type with an improved output shaft deflection accuracy is added to the product lineup

After reviewing the output rotary unit structure, the higher accuracy of the surface runout and shaft deflection has been achieved. Together with easy-to-index speed ratios that are divisible, such as 1:50 and 1:100, this is ideal for use with index tables. There is also an output shaft single revolution absolute model available as an option that can control the position even with infinite rotation in one direction.

1-2 Model

Model names for the SHA series actuators and how to read the symbols are explained below.

Examples of standard models:

| | | | | | | | | | | | | | | | | |
|-----|-----|-----|-----|-----|-----|-----|-----|-----|------|------|------|------|------|------|------|---|
| SHA | 32 | A | 101 | SG | — | B | 12 | A | 200 | — | 30 | S | 17b | A | — | C |
| (1) | (2) | (3) | (4) | (5) | (6) | (7) | (8) | (9) | (10) | (11) | (12) | (13) | (14) | (15) | (16) | |

(1) Model: AC Servo Actuator SHA series

(2) Model Nos: 25, 32: HP type
20, 25, 32, 40, 45, 58, 65: SG type
20, 25, 32, 40: CG type

(3) Version symbol

(4) Reduction ratio (indicated by R in 1/R format)
Reduction ratio 11 is for the hollow planetary speed reducer HPF series for precision control (Compatible with model Nos. 25, 32 only.)
Reduction ratios 50 and higher are for the HarmonicDrive® speed reducer for precision control combinations.

| HPF | | SHG | | CSG | |
|-----|------|-----|-------|-----|-------|
| 11 | 1/11 | 51 | 1/51 | 50 | 1/50 |
| | | 81 | 1/81 | 80 | 1/80 |
| | | 101 | 1/101 | 100 | 1/100 |
| | | 121 | 1/121 | 120 | 1/120 |
| | | 161 | 1/161 | 160 | 1/160 |

(5) Speed reducer type

| | |
|----|---|
| HP | Hollow planetary speed reducer HPF series |
| SG | HarmonicDrive® speed reducer SHG series |
| CG | HarmonicDrive® speed reducer CSG series |

(6) Motor version symbol

| | |
|---|----------------------|
| A | Model Nos 58, 65 |
| B | Model Nos 25, 32, 40 |
| C | Model No. 20 |
| D | Model No. 45 |

(7) Motor size

| | |
|----|------------------|
| 08 | Model No. 20 |
| 09 | Model No. 25 |
| 12 | Model No. 32 |
| 15 | Model No. 40 |
| 16 | Model No. 45 |
| 21 | Model Nos 58, 65 |

(8) Brake

| | |
|---|---------------|
| A | Without brake |
| B | With brake |

(9) Applicable servo driver input voltage

| | |
|-----|-------|
| 100 | 100 V |
| 200 | 200 V |

(100 V is compatible with model No.25 only.)

(10) Encoder format

| | |
|----|--|
| 10 | Conforming to A format, transmission rate: 2.5 Mbps, 1-on-1 connection, with backup capacitor |
| 30 | Conforming to A format, transmission rate: 2.5 Mbps, 1-on-1 connection, without backup capacitor |

(Encoder format "10" is compatible with SHA20 only.)

(11) Encoder type

| | |
|---|--------------------------|
| S | Multi-turn absolute type |
|---|--------------------------|

(12) Encoder resolution

| | |
|-----|-----------------------------------|
| 17b | 17 bit (131072 pulses/revolution) |
|-----|-----------------------------------|

(13) Encoder phase angle: Phase difference between induced voltage in motor phase U and absolute origin

| | |
|---|----------|
| A | 0 degree |
|---|----------|

(14) Connector specification

| | |
|---|-------------------------|
| C | With standard connector |
| N | Without connector |

(15) Option symbol

| | |
|---|--|
| L | With near origin and end limit sensors |
| Y | Cable taken out from side |
| V | With stand (CG type only) |
| S | Output shaft single revolution absolute model (CG type only) |

(Please contact us for option-compatible combinations.)

(16) Special specification

| | |
|----------------|-------------------------------|
| No description | Standard product |
| SP | Special specification product |

1-3**Combinations with drivers and extension cables**

The combinations of SHA actuators, drivers and extension cables vary depending on the communication interface. Refer to the table below.

I/O command type (HA-900A series)

| Model | Input voltage | Driver | Extension cables |
|-------|---------------|------------------------------------|---|
| SHA20 | 200V | HA-900A-3A-200 | Motor cable: EWD-MB**-A06-TN4 Encoder cable: EWD-S**-A08-MDR14 |
| SHA25 | 200V | HA-900A-3A-200 | |
| | 100V | HA-900A-6A-100 | |
| SHA32 | 200V | HA-900A-6A-200 | |
| SHA40 | 200V | HA-900A-12A-200 | Motor cable: EWD-MB**-A06-TM4 Encoder cable: EWD-S**-A08-MDR14 |
| SHA45 | 200V | HA-900A-12A-200 HA-900A-24A-200 | |
| SHA58 | 200V | HA-900A-24A-200 | Motor cable: EWD-MB**-D09-TM4 Encoder cable: EWD-S**-D10-MDR14 |
| SHA65 | 200V | HA-900A-24A-200 | |

Note 1: For SHA45, the combined driver for reduction ratios of 51/81 is HA-900A-12A-200, and the combined driver for reduction ratios of 101/121/161 is HA-900A-24A-200.

Note 2: ** in the extension cable model indicates the cable length: 03 = 3 m, 05 = 5 m, 10 = 10 m

MECHATROLINK type (HA-800B series)

| Model | Input voltage | Driver | Extension cables |
|-------|---------------|---------------------------------------|--|
| SHA20 | 200V | HA-800B-3D/E-200 | Motor cable: EWD-MB**-A06-TN3 Encoder cable: EWD-S**-A08-3M14 |
| SHA25 | 200V | HA-800B-3D/E-200 | |
| | 100V | HA-800B-6D/E-100 | |
| SHA32 | 200V | HA-800B-6D/E-200 | Motor cable: EWD-MB**-A06-TMC Encoder cable: EWD-S**-A08-3M14 |
| SHA40 | 200V | HA-800B-6D/E-200 HA-800B-24D/E-200 | |
| SHA45 | 200V | HA-800B-24D/E-200 | Motor cable: EWD-MB**-D09-TMC Encoder cable: EWD-S**-D10-3M14 |
| SHA58 | 200V | HA-800B-24D/E-200 | |
| SHA65 | 200V | HA-800B-24D/E-200 | |

Note 1: SHA40 will be derated when combined with a HA-800B-6D/E-200 driver.

Note 2: ** in the extension cable model indicates the cable length: 03 = 3 m, 05 = 5 m, 10 = 10 m

CC-Link type (HA-800C series)

| Model | Input voltage | Driver | Extension cables |
|-------|---------------|---------------------------------------|--|
| SHA20 | 200V | HA-800C-3D/E-200 | Motor cable: EWD-MB**-A06-TN3 Encoder cable: EWD-S**-A08-3M14 |
| SHA25 | 200V | HA-800C-3D/E-200 | |
| | 100V | HA-800C-6D/E-100 | |
| SHA32 | 200V | HA-800C-6D/E-200 | Motor cable: EWD-MB**-A06-TMC Encoder cable: EWD-S**-A08-3M14 |
| SHA40 | 200V | HA-800C-6D/E-200 HA-800C-24D/E-200 | |
| SHA45 | 200V | HA-800C-24D/E-200 | Motor cable: EWD-MB**-D09-TMC Encoder cable: EWD-S**-D10-3M14 |
| SHA58 | 200V | HA-800C-24D/E-200 | |
| SHA65 | 200V | HA-800C-24D/E-200 | |

Note 1: SHA40 will be derated when combined with a HA-800B-6D/E-200 driver.

Note 2: ** in the extension cable model indicates the cable length: 03 = 3 m, 05 = 5 m, 10 = 10 m

1-4 Specifications

The specifications of SHA series actuators are explained.

SG type

| Item | | Model | SHA20A | | | | |
|---|-----------------------------------|--|----------|----------|----------|----------|-----|
| | | | 51 | 81 | 101 | 121 | 161 |
| Combined driver | | HA-900A-3A -200, HA-800B/C-3D/E-200 | | | | | |
| Max. torque* ¹ | N·m | 73 | 96 | 107 | 113 | 120 | |
| | kgf·m | 7.4 | 9.8 | 10.9 | 11.5 | 12.2 | |
| Allowable continuous torque** ^{1,2} | N·m | 21 | 35 | 43 | 48 | 48 | |
| | kgf·m | 2.1 | 3.6 | 4.4 | 4.9 | 4.9 | |
| Max. rotational speed* ¹ | r/min | 117.6 | 74.1 | 59.4 | 49.6 | 37.3 | |
| Torque constant* ¹ | N·m/A | 16.5 | 27 | 33 | 40 | 53 | |
| | kgf·m/A | 1.7 | 2.7 | 3.4 | 4.1 | 5.4 | |
| Max. current* ¹ | A | 6.0 | 4.9 | 4.5 | 4.0 | 3.4 | |
| Allowable continuous current** ^{1,2} | A | 2.1 | 2.0 | 2.0 | 1.9 | 1.6 | |
| EMF constant* ³ | V/(r/min) | 1.9 | 3.0 | 3.7 | 4.5 | 5.9 | |
| Phase resistance (20 °C) | Ω | 1.4 | | | | | |
| Phase inductance | mH | 2.5 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 0.23 | 0.58 | 0.91 | 1.3 | 2.3 |
| | J | kgf·cm·s ² | 2.4 | 6.0 | 9.3 | 13 | 24 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 0.26 | 0.65 | 1.0 | 1.4 | 2.6 |
| | J | kgf·cm·s ² | 2.6 | 6.6 | 10 | 15 | 26 |
| Reduction ratio | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | |
| Permissible moment load | N·m | 187 | | | | | |
| | kgf·m | 19.1 | | | | | |
| Moment stiffness | N·m/rad | 25.2 × 10 ⁴ | | | | | |
| | kgf·m/arc-min | 7.5 | | | | | |
| Uni-directional positional accuracy | Sec. | 60 | 50 | 50 | 50 | 50 | |
| Encoder type | | Absolute encoder | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | |
| Output shaft resolution | pulse/rev | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 | |
| Mass (without brake) | kg | 2.0 | | | | | |
| Mass (with brake) | kg | 2.1 | | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | |
| Mounting direction | | Can be installed in any direction. | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 320×320×16 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

SG/HP type

| Item | Model | SHA25A (Motor input voltage 100 V) | | | | | SHA25A (Motor input voltage 200 V) | | | | | | |
|-------------------------------------|-----------------------|--|----------|----------|----------|----------|---------------------------------------|------------------------|----------|----------|----------|----------|-----|
| | | 51 | 81 | 101 | 121 | 161 | 11 | 51 | 81 | 101 | 121 | 161 | |
| Combined driver | | HA-900A-6A-100, HA-800B/C-6D/E-100 | | | | | HA-900A-3A-200, HA-800B/C-3D/E-200 | | | | | | |
| Max. torque*1 | N·m | 127 | 178 | 204 | 217 | 229 | 26 | 127 | 178 | 204 | 217 | 229 | |
| | kgf·m | 13 | 18.2 | 20.8 | 22.1 | 23.4 | 2.7 | 13 | 18.2 | 20.8 | 22.1 | 23.4 | |
| Allowable continuous torque*1*2 | N·m | 35 | 58 | 73 | 81 | 81 | 9.0 | 41 | 67 | 81 | 81 | 81 | |
| | kgf·m | 3.6 | 5.9 | 7.4 | 8.2 | 8.2 | 0.92 | 4.2 | 6.8 | 8.2 | 8.2 | 8.2 | |
| Max. rotational speed*1 | r/min | 94.1 | 59.3 | 47.5 | 39.7 | 29.8 | 509.1 | 109.8 | 69.1 | 55.4 | 46.3 | 34.8 | |
| Torque constant*1 | N·m/A | 11.1 | 17.9 | 22 | 27 | 36 | 4.2 | 19 | 31 | 39 | 46 | 62 | |
| | kgf·m/A | 1.1 | 1.8 | 2.3 | 2.7 | 3.6 | 0.43 | 2.0 | 3.2 | 4.0 | 4.7 | 6.3 | |
| Max. current*1 | A | 14.9 | 13.0 | 12.1 | 10.9 | 9.0 | 8.9 | 8.6 | 7.5 | 7.0 | 6.3 | 5.2 | |
| Allowable continuous current*1*2 | A | 4.7 | 4.7 | 4.7 | 4.5 | 3.7 | 3.0 | 3.0 | 3.0 | 2.9 | 2.6 | 2.1 | |
| EMF constant*3 | V/(r/min) | 1.3 | 2.0 | 2.5 | 3.0 | 4.0 | 0.47 | 2.2 | 3.5 | 4.3 | 5.2 | 6.9 | |
| Phase resistance (20 °C) | Ω | 0.4 | | | | | 1.2 | | | | | | |
| Phase inductance | mH | 1.0 | | | | | 3 | | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 0.56 | 1.4 | 2.2 | 3.2 | 5.6 | 0.029 | 0.56 | 1.4 | 2.2 | 3.2 | 5.6 |
| | J | kgf·cm·s ² | 5.7 | 14 | 22 | 32 | 57 | 0.30 | 5.7 | 14 | 22 | 32 | 57 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 0.66 | 1.7 | 2.6 | 3.7 | 6.6 | 0.034 | 0.66 | 1.7 | 2.6 | 3.7 | 6.6 |
| | J | kgf·cm·s ² | 6.7 | 17 | 26 | 38 | 67 | 0.35 | 6.7 | 17 | 26 | 38 | 67 |
| Reduction ratio | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | 1:11 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | |
| Permissible moment load | N·m | 258 | | | | | 410 | 258 | | | | | |
| | kgf·m | 26.3 | | | | | 41.8 | 26.3 | | | | | |
| Moment stiffness | N·m/rad | 39.2 × 10 ⁴ | | | | | 37.9 × 10 ⁴ | 39.2 × 10 ⁴ | | | | | |
| | kgf·m/arc-min | 11.6 | | | | | 11.3 | 11.6 | | | | | |
| Uni-directional positional accuracy | Sec. | 50 | 40 | 40 | 40 | 40 | 120 | 50 | 40 | 40 | 40 | 40 | |
| Encoder type | | Magnetic absolute encoder | | | | | | | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | | | | | | | |
| | Multi-turn detector*5 | 2 ¹⁶ (65536) | | | | | | | | | | | |
| Output shaft resolution | pulse/rev | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 | 1441792 | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 | |
| Mass (without brake) | kg | 2.95 | | | | | 5.0 | 2.95 | | | | | |
| Mass (with brake) | kg | 3.1 | | | | | 5.1 | 3.1 | | | | | |
| Environmental conditions*6 | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² *4 No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | | | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | | | | | | | |
| Mounting direction | | Can be installed in any direction. | | | | | | | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | | | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 350×350×18 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

SG/HP type

| Item | | Model | SHA32A | | | | | |
|--|-----------------------------------|-----------------------|--|---------------------|----------|----------|----------|----------|
| | | | 11 | 51 | 81 | 101 | 121 | 161 |
| Combined driver | | | HA-900A-6A-200, HA-800B/C-6D/E-200 | | | | | |
| Max. torque* ¹ | N·m | | 62 | 281 | 395 | 433 | 459 | 484 |
| | kgf·m | | 6.3 | 28.7 | 40.3 | 44.2 | 46.8 | 49.4 |
| Allowable continuous torque* ^{1,2} | N·m | | 20 | 92 | 153 | 178 | 178 | 178 |
| | kgf·m | | 2.1 | 9.4 | 15.6 | 18.2 | 18.2 | 18.2 |
| Max. rotational speed* ¹ | r/min | | 436.4 | 94.1 | 59.3 | 47.5 | 39.7 | 29.8 |
| Torque constant* ¹ | N·m/A | | 4.5 | 21 | 33 | 42 | 50 | 66 |
| | kgf·m/A | | 0.46 | 2.1 | 3.4 | 4.2 | 5.1 | 6.8 |
| Max. current* ¹ | A | | 19 | 17.3 | 15.2 | 13.5 | 12.2 | 9.9 |
| Allowable continuous current* ^{1,2} | A | | 6.0 | 6.0 | 6.0 | 5.7 | 5.0 | 4.1 |
| EMF constant* ³ | V/(r/min) | | 0.51 | 2.3 | 3.7 | 4.7 | 5.6 | 7.4 |
| Phase resistance (20 °C) | Ω | | 0.33 | | | | | |
| Phase inductance | mH | | 1.4 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 0.091 | 2.0 | 5.1 | 8.0 | 11 | 20 |
| | J | kgf·cm·s ² | 0.93 | 21 | 52 | 81 | 117 | 207 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 0.11 | 2.3 | 5.9 | 9.2 | 13 | 23 |
| | J | kgf·cm·s ² | 1.1 | 24 | 60 | 94 | 135 | 238 |
| Reduction ratio | | | 1:11 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Permissible moment load | N·m | | 932 | 580 | | | | |
| | kgf·m | | 95 | 59.1 | | | | |
| Moment stiffness | N·m/rad | | 86.1×10 ⁴ | 100×10 ⁴ | | | | |
| | kgf·m/arc-min | | 25.7 | 29.6 | | | | |
| Uni-directional positional accuracy | Sec. | | 120 | 50 | 40 | 40 | 40 | 40 |
| Encoder type | | | Magnetic absolute encoder | | | | | |
| Encoder resolution | Single-turn detector | | 2 ¹⁷ (131072) | | | | | |
| | Multi-turn detector* ⁵ | | 2 ¹⁶ (65536) | | | | | |
| Output shaft resolution | pulse/rev | | 1441792 | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 |
| Mass (without brake) | kg | | 9.4 | 5.9 | | | | |
| Mass (with brake) | kg | | 9.7 | 6.2 | | | | |
| Environmental conditions* ⁶ | | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | |
| Motor insulation | | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | |
| Mounting direction | | | Can be installed in any direction. | | | | | |
| Protection structure | | | Totally enclosed self-cooled type (IP54) | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 400×400×20 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).

Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

SG type

| Item | | Model | SHA40A | | | | | | | | | |
|--|-----------------------------------|-----------------------|---|----------|----------|----------|----------|--------------------------------------|----------|----------|----------|----------|
| | | | 51 | 81 | 101 | 121 | 161 | 51 | 81 | 101 | 121 | 161 |
| Combined driver | | | HA-800B/C-6D/E-200 ^{*1} | | | | | HA-900A-12A-200, HA-800B/C-24D/E-200 | | | | |
| Max. torque ^{*2} | N·m | | 340 | 560 | 686 | 802 | 841 | 523 | 675 | 738 | 802 | 841 |
| | kgf·m | | 34.7 | 57.1 | 70 | 81.8 | 85.8 | 53.4 | 68.9 | 75.3 | 81.8 | 85.8 |
| Allowable continuous torque ^{*2*3} | N·m | | 94 | 158 | 198 | 237 | 317 | 160 | 263 | 330 | 382 | 382 |
| | kgf·m | | 9.6 | 16.1 | 20.2 | 24.2 | 32.3 | 16.3 | 26.8 | 33.7 | 39 | 39 |
| Max. rotational speed ^{*2} | r/min | | 78.4 | 49.4 | 39.6 | 33.1 | 24.8 | 78.4 | 49.4 | 39.6 | 33.1 | 24.8 |
| Torque constant ^{*2} | N·m/A | | 25 | 41 | 51 | 61 | 81 | 25 | 41 | 51 | 61 | 81 |
| | kgf·m/A | | 2.6 | 4.1 | 5.2 | 6.2 | 8.2 | 2.6 | 4.1 | 5.2 | 6.2 | 8.2 |
| Max. current ^{*2} | A | | 18 | 18 | 18 | 17.9 | 14.6 | 26.7 | 21.8 | 19.4 | 17.9 | 14.6 |
| Allowable continuous current ^{*2*3} | A | | 6.0 | 6.0 | 6.0 | 6.0 | 6.0 | 9.0 | 9.0 | 9.0 | 8.8 | 7.2 |
| EMF constant ^{*4} | V/(r/min) | | 2.9 | 4.6 | 5.7 | 6.8 | 9.1 | 2.9 | 4.6 | 5.7 | 6.8 | 9.1 |
| Phase resistance (20 °C) | Ω | | 0.19 | | | | | | | | | |
| Phase inductance | mH | | 1.2 | | | | | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 5.0 | 13 | 20 | 28 | 50 | 5.0 | 13 | 20 | 28 | 50 |
| | J | kgf·cm·s ² | 51 | 130 | 202 | 290 | 513 | 51 | 130 | 202 | 290 | 513 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 6.1 | 15 | 24 | 34 | 61 | 6.1 | 15 | 24 | 34 | 61 |
| | J | kgf·cm·s ² | 62 | 157 | 244 | 350 | 619 | 62 | 157 | 244 | 350 | 619 |
| Reduction ratio | | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Permissible moment load | N·m | | 849 | | | | | | | | | |
| | kgf·m | | 86.6 | | | | | | | | | |
| Moment stiffness | N·m/rad | | 179 × 10 ⁴ | | | | | | | | | |
| | kgf·m/arc-min | | 53.2 | | | | | | | | | |
| Uni-directional positional accuracy | Sec. | | 50 | 40 | 40 | 40 | 40 | 50 | 40 | 40 | 40 | 40 |
| Encoder type | | | Magnetic absolute encoder | | | | | | | | | |
| Encoder resolution | Single-turn detector | | 2 ¹⁷ (131072) | | | | | | | | | |
| | Multi-turn detector ^{*6} | | 2 ¹⁶ (65536) | | | | | | | | | |
| Output shaft resolution | pulse/rev | | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 |
| Mass (without brake) | kg | | 9.9 | | | | | | | | | |
| Mass (with brake) | kg | | 10.7 | | | | | | | | | |
| Environmental conditions ^{*7} | | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² ^{*5} No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | | | | | |
| Motor insulation | | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | | | | | |
| Mounting direction | | | Can be installed in any direction. | | | | | | | | | |
| Protection structure | | | Totally enclosed self-cooled type (IP54) | | | | | | | | | |

The table shows typical output values of actuators.

*1: If a HA-800B/C-6D/E driver is combined with a SHA40A actuator, the maximum torque and allowable continuous torque are limited.

*2: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*3: Value after temperature rise and saturation when the 500×500×25 [mm] aluminum radiation plate is installed.

*4: Value of phase induced voltage constant multiplied by 3.

*5: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43). Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*6: The multi-turn detector range is -32768 to 32767.

*7: For details, refer to [3-3 Location and installation] (P3-6).

SG type

| Item | | Model | SHA45A | | | | |
|--|-----------------------------------|--|----------|-----------------|----------|----------|-----|
| | | | 51 | 81 | 101 | 121 | 161 |
| Combined driver | | HA-900A-24A-200 | | HA-900A-12A-200 | | | |
| | | HA-800B/C-24D/E-200 | | | | | |
| Max. torque* ¹ | N·m | 650 | 918 | 982 | 1070 | 1147 | |
| | kgf·m | 66.3 | 93.6 | 100 | 109 | 117 | |
| Allowable continuous torque* ^{1,2} | N·m | 174 | 290 | 363 | 437 | 523 | |
| | kgf·m | 17.7 | 29.6 | 37.0 | 44.6 | 53.3 | |
| Max. rotational speed* ¹ | r/min | 74.5 | 46.9 | 37.6 | 31.4 | 23.6 | |
| Torque constant* ¹ | N·m/A | 25 | 41 | 51 | 61 | 81 | |
| | kgf·m/A | 2.6 | 4.1 | 5.2 | 6.2 | 8.2 | |
| Max. current* ¹ | A | 36.5 | 29.9 | 25.9 | 24.5 | 19.3 | |
| Allowable continuous current* ^{1,2} | A | 10.0 | 10.0 | 10.0 | 10.0 | 9.2 | |
| EMF constant* ³ | V/(r/min) | 2.9 | 4.6 | 5.7 | 6.8 | 9.1 | |
| Phase resistance (20 °C) | Ω | 0.19 | | | | | |
| Phase inductance | mH | 1.2 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 6.8 | 17 | 27 | 38 | 68 |
| | J | kgf·cm·s ² | 69 | 175 | 272 | 390 | 690 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 7.9 | 20 | 31 | 45 | 79 |
| | J | kgf·cm·s ² | 81 | 204 | 316 | 454 | 804 |
| Reduction ratio | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | |
| Permissible moment load | N·m | 1127 | | | | | |
| | kgf·m | 115 | | | | | |
| Moment stiffness | N·m/rad | 257 × 10 ⁴ | | | | | |
| | kgf·m/arc-min | 76.3 | | | | | |
| Uni-directional positional accuracy | Sec. | 50 | 40 | 40 | 40 | 40 | |
| Encoder type | | Absolute encoder | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | |
| Output shaft resolution | pulse/rev | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 | |
| Mass (without brake) | kg | 12.4 | | | | | |
| Mass (with brake) | kg | 13.2 | | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | |
| Mounting direction | | Can be installed in any direction. | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 500×500×25 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

SG type

| Item | Model | SHA58A | | | | SHA65A | | | | |
|--|-----------------------------------|--|----------|----------|----------|-----------------------|----------|----------|----------|------|
| | | 81 | 101 | 121 | 161 | 81 | 101 | 121 | 161 | |
| Combined driver | | HA-900A-24A-200, HA-800B/C-24D/E-200 | | | | | | | | |
| Max. torque* ¹ | N·m | 1924 | 2067 | 2236 | 2392 | 2400 | 2990 | 3263 | 3419 | |
| | kgf·m | 196 | 211 | 228 | 244 | 245 | 305 | 333 | 349 | |
| Allowable continuous torque* ¹⁺² | N·m | 714 | 905 | 969 | 969 | 921 | 1149 | 1236 | 1236 | |
| | kgf·m | 73 | 92 | 99 | 99 | 94 | 117 | 126 | 126 | |
| Max. rotational speed* ¹ | r/min | 37.0 | 29.7 | 24.8 | 18.6 | 34.6 | 27.7 | 23.1 | 17.4 | |
| Torque constant* ¹ | N·m/A | 54 | 68 | 81 | 108 | 54 | 68 | 81 | 108 | |
| | kgf·m/A | 5.5 | 6.9 | 8.3 | 11.0 | 5.5 | 6.9 | 8.3 | 11.0 | |
| Max. current* ¹ | A | 45 | 39 | 36 | 30 | 55 | 55 | 51 | 41 | |
| Allowable continuous current* ¹⁺² | A | 17.7 | 17.8 | 16.4 | 13.4 | 22.0 | 21.9 | 20.1 | 16.3 | |
| EMF constant* ³ | V/(r/min) | 6.1 | 7.6 | 9.1 | 12.1 | 6.1 | 7.6 | 9.1 | 12.1 | |
| Phase resistance (20 °C) | Ω | 0.028 | | | | 0.028 | | | | |
| Phase inductance | mH | 0.29 | | | | 0.29 | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 96 | 149 | 214 | 379 | 110 | 171 | 245 | 433 |
| | J | kgf·cm·s ² | 980 | 1520 | 2180 | 3870 | 1120 | 1740 | 2500 | 4420 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 106 | 165 | 237 | 420 | 120 | 187 | 268 | 475 |
| | J | kgf·cm·s ² | 1090 | 1690 | 2420 | 4290 | 1230 | 1910 | 2740 | 4850 |
| Reduction ratio | | 1:81 | 1:101 | 1:121 | 1:161 | 1:81 | 1:101 | 1:121 | 1:161 | |
| Permissible moment load | N·m | 2180 | | | | 2740 | | | | |
| | kgf·m | 222 | | | | 280 | | | | |
| Moment stiffness | N·m/rad | 531 × 10 ⁴ | | | | 741 × 10 ⁴ | | | | |
| | kgf·m/arc-min | 158 | | | | 220 | | | | |
| Uni-directional positional accuracy | Sec. | 40 | 40 | 40 | 40 | 40 | 40 | 40 | 40 | |
| Encoder type | | Magnetic absolute encoder | | | | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | | | | |
| Output shaft resolution | pulse/rev | 10616832 | 13238272 | 15859712 | 21102592 | 10616832 | 13238272 | 15859712 | 21102592 | |
| Mass (without brake) | kg | 29.5 | | | | 37.5 | | | | |
| Mass (with brake) | kg | 32 | | | | 40 | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | | | | |
| Mounting direction | | Can be installed in any direction. | | | | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 650×650×30 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
 Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

CG type

| Item | | Model | SHA20A | | | | |
|--|-----------------------------------|--|----------|----------|----------|----------|-----|
| | | | 50 | 80 | 100 | 120 | 160 |
| Combined driver | | HA-900A-3A-200, HA-800B/C-3D/E-200 | | | | | |
| Max. torque* ¹ | N·m | 73 | 96 | 107 | 113 | 120 | |
| | kgf·m | 7.4 | 9.8 | 10.9 | 11.5 | 12.2 | |
| Allowable continuous torque* ^{1,2} | N·m | 21 | 35 | 43 | 48 | 48 | |
| | kgf·m | 2.1 | 3.6 | 4.4 | 4.9 | 4.9 | |
| Max. rotational speed* ¹ | r/min | 120 | 75 | 60 | 50 | 37.5 | |
| Torque constant* ¹ | N·m/A | 16 | 26 | 33 | 39 | 53 | |
| | kgf·m/A | 1.7 | 2.7 | 3.4 | 4.0 | 5.4 | |
| Max. current* ¹ | A | 6.1 | 5.0 | 4.6 | 4.1 | 3.4 | |
| Allowable continuous current* ^{1,2} | A | 2.1 | 2.1 | 2.1 | 2.0 | 1.7 | |
| EMF constant* ³ | V/(r/min) | 1.8 | 2.9 | 3.7 | 4.4 | 5.9 | |
| Phase resistance (20 °C) | Ω | 1.4 | | | | | |
| Phase inductance | mH | 2.5 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 0.21 | 0.53 | 0.82 | 1.2 | 2.1 |
| | J | kgf·cm·s ² | 2.1 | 5.4 | 8.0 | 12 | 22 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 0.23 | 0.60 | 0.94 | 1.3 | 2.4 |
| | J | kgf·cm·s ² | 2.4 | 6.1 | 9.6 | 14 | 24 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | |
| Permissible moment load | N·m | 187 | | | | | |
| | kgf·m | 19.1 | | | | | |
| Moment stiffness | N·m/rad | 25.2 × 10 ⁴ | | | | | |
| | kgf·m/arc-min | 7.5 | | | | | |
| Uni-directional positional accuracy | Sec. | 60 | 50 | 50 | 50 | 50 | |
| Repeatability | Sec. | ±5 | | | | | |
| Reverse positional accuracy | Sec. | 75 | 30 | 30 | 30 | 30 | |
| Encoder type | | Absolute encoder | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | |
| Output shaft resolution | pulse/rev | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | |
| Mass (without brake) | kg | 2.6 | | | | | |
| Mass (with brake) | kg | 2.7 | | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | |
| Mounting direction | | Can be installed in any direction | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 320×320×16 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

CG type

| Item | Model | SHA25A (Motor input voltage 100 V) | | | | | SHA25A (Motor input voltage 200 V) | | | | | |
|--|-----------------------------------|--|----------|----------|----------|----------|---------------------------------------|----------|----------|----------|----------|-----|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 | |
| | | Combined driver | | | | | | | | | | |
| | | HA-900A-6A-100, HA-800B/C-6D/E-100 | | | | | HA-900A-3A-200, HA-800B/C-3D/E-200 | | | | | |
| Max. torque* ¹ | N·m | 127 | 178 | 204 | 217 | 229 | 127 | 178 | 204 | 217 | 229 | |
| | kgf·m | 13 | 18.2 | 20.8 | 22.1 | 23.4 | 13 | 18.2 | 20.8 | 22.1 | 23.4 | |
| Allowable continuous torque** ² | N·m | 34 | 57 | 72 | 81 | 81 | 40 | 66 | 81 | 81 | 81 | |
| | kgf·m | 3.5 | 5.8 | 7.3 | 8.2 | 8.2 | 4.1 | 6.8 | 8.2 | 8.2 | 8.2 | |
| Max. rotational speed* ¹ | r/min | 96 | 60 | 48 | 40 | 30 | 112 | 70 | 56 | 46.7 | 35 | |
| Torque constant* ¹ | N·m/A | 10.9 | 17.7 | 22 | 27 | 35 | 19 | 31 | 38 | 46 | 61 | |
| | kgf·m/A | 1.1 | 1.8 | 2.3 | 2.7 | 3.6 | 1.9 | 3.1 | 3.9 | 4.7 | 6.3 | |
| Max. current* ¹ | A | 15.1 | 13.2 | 12.2 | 11.0 | 9.0 | 8.7 | 7.6 | 7.0 | 6.3 | 5.2 | |
| Allowable continuous current** ¹² | A | 4.7 | 4.7 | 4.7 | 4.5 | 3.7 | 3.0 | 3.0 | 3.0 | 2.6 | 2.1 | |
| EMF constant* ³ | V/(r/min) | 1.2 | 2.0 | 2.5 | 3.0 | 4.0 | 2.1 | 3.4 | 4.3 | 5.2 | 6.9 | |
| Phase resistance (20 °C) | Ω | 0.4 | | | | | 1.2 | | | | | |
| Phase inductance | mH | 1.0 | | | | | 3.0 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 0.50 | 1.3 | 2.0 | 2.9 | 5.1 | 0.50 | 1.3 | 2.0 | 2.9 | 5.1 |
| | J | kgf·cm·s ² | 5.1 | 13 | 20 | 29 | 52 | 5.1 | 13 | 20 | 29 | 52 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 0.60 | 1.5 | 2.4 | 3.4 | 6.1 | 0.60 | 1.5 | 2.4 | 3.4 | 6.1 |
| | J | kgf·cm·s ² | 6.1 | 16 | 24 | 35 | 62 | 6.1 | 16 | 24 | 35 | 62 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | |
| Permissible moment load | N·m | 258 | | | | | | | | | | |
| | kgf·m | 26.3 | | | | | | | | | | |
| Moment stiffness | N·m/rad | 39.2 × 10 ⁴ | | | | | | | | | | |
| | kgf·m/arc-min | 11.6 | | | | | | | | | | |
| Uni-directional positional accuracy | Sec. | 50 | 40 | 40 | 40 | 40 | 50 | 40 | 40 | 40 | 40 | |
| Repeatability | Sec. | ±5 | | | | | | | | | | |
| Reverse positional accuracy | Sec. | 60 | 25 | 25 | 25 | 25 | 60 | 25 | 25 | 25 | 25 | |
| Encoder type | | Magnetic absolute encoder | | | | | | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | | | | | | |
| Output shaft resolution | pulse/rev | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | |
| Mass (without brake) | kg | 3.95 | | | | | | | | | | |
| Mass (with brake) | kg | 4.1 | | | | | | | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | | | | | | |
| Mounting direction | | Can be installed in any direction | | | | | | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 350×350×18 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

CG type

| Item | Model | SHA32A | | | | | |
|--|-----------------------------------|--|----------|----------|----------|----------|-----|
| | | 50 | 80 | 100 | 120 | 160 | |
| Combined driver | | HA-900A-6A-200, HA-800B/C-6D/E-200 | | | | | |
| Max. torque* ¹ | N·m | 281 | 395 | 433 | 459 | 484 | |
| | kgf·m | 28.7 | 40.3 | 44.2 | 46.8 | 49.4 | |
| Allowable continuous torque* ^{1,2} | N·m | 90 | 151 | 178 | 178 | 178 | |
| | kgf·m | 9.2 | 15.4 | 18.2 | 18.2 | 18.2 | |
| Max. rotational speed* ¹ | r/min | 96 | 60 | 48 | 40 | 30 | |
| Torque constant* ¹ | N·m/A | 20 | 33 | 41 | 49 | 66 | |
| | kgf·m/A | 2.1 | 3.4 | 4.2 | 5.0 | 6.7 | |
| Max. current* ¹ | A | 17.7 | 15.4 | 13.7 | 12.2 | 10 | |
| Allowable continuous current* ^{1,2} | A | 6.0 | 6.0 | 5.7 | 5.0 | 4.1 | |
| EMF constant* ³ | V/(r/min) | 2.3 | 3.7 | 4.6 | 5.5 | 7.4 | |
| Phase resistance (20 °C) | Ω | 0.33 | | | | | |
| Phase inductance | mH | 1.4 | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 1.7 | 4.3 | 6.7 | 9.7 | 17 |
| | J | kgf·cm·s ² | 17 | 44 | 68 | 99 | 175 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 2.0 | 5.1 | 7.9 | 11 | 20 |
| | J | kgf·cm·s ² | 20 | 52 | 81 | 116 | 207 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | |
| Permissible moment load | N·m | 580 | | | | | |
| | kgf·m | 59.2 | | | | | |
| Moment stiffness | N·m/rad | 100 × 10 ⁴ | | | | | |
| | kgf·m/arc-min | 29.6 | | | | | |
| Uni-directional positional accuracy | Sec. | 40 | 30 | 30 | 30 | 30 | |
| Repeatability | Sec. | ±4 | | | | | |
| Reverse positional accuracy | Sec. | 60 | 25 | 25 | 25 | 25 | |
| Encoder type | | Magnetic absolute encoder | | | | | |
| Encoder resolution | Single-turn detector | 2 ¹⁷ (131072) | | | | | |
| | Multi-turn detector* ⁵ | 2 ¹⁶ (65536) | | | | | |
| Output shaft resolution | pulse/rev | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | |
| Mass (without brake) | kg | 7.7 | | | | | |
| Mass (with brake) | kg | 8.0 | | | | | |
| Environmental conditions* ⁶ | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² * ⁴ No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | |
| Motor insulation | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | |
| Mounting direction | | Can be installed in any direction. | | | | | |
| Protection structure | | Totally enclosed self-cooled type (IP54) | | | | | |

The table shows typical output values of actuators.

*1: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*2: Value after temperature rise and saturation when the 400×400×20 [mm] aluminum radiation plate is installed.

*3: Value of phase induced voltage constant multiplied by 3.

*4: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*5: The multi-turn detector range is -32768 to 32767.

*6: For details, refer to [3-3 Location and installation] (P3-6).

CG type

| Item | | Model | SHA40A | | | | | | | | | |
|--|-----------------------------------|-----------------------|---|----------|----------|----------|----------|--------------------------------------|----------|----------|----------|----------|
| | | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| Combined driver | | | HA-800B/C-6D/E-200 ^{*1} | | | | | HA-900A-12A-200, HA-800B/C-24D/E-200 | | | | |
| Max. torque ^{*2} | N·m | | 333 | 548 | 686 | 802 | 841 | 523 | 675 | 738 | 802 | 841 |
| | kgf·m | | 34.0 | 55.9 | 70.0 | 81.8 | 85.8 | 53.4 | 68.9 | 75.3 | 81.8 | 85.8 |
| Allowable continuous torque ^{*2,3} | N·m | | 92 | 156 | 196 | 235 | 315 | 157 | 260 | 327 | 382 | 382 |
| | kgf·m | | 9.4 | 15.9 | 20.0 | 24.0 | 32.1 | 16.0 | 26.5 | 33.3 | 39 | 39 |
| Max. rotational speed ^{*2} | r/min | | 80 | 50 | 40 | 33.3 | 25 | 80 | 50 | 40 | 33.3 | 25 |
| Torque constant ^{*2} | N·m/A | | 25 | 40 | 50 | 60 | 80 | 25 | 40 | 50 | 60 | 80 |
| | kgf·m/A | | 2.5 | 4.1 | 5.1 | 6.1 | 8.2 | 2.5 | 4.1 | 5.1 | 6.1 | 8.2 |
| Max. current ^{*2} | A | | 18 | 18 | 18 | 17.6 | 14.3 | 27.2 | 22 | 19.6 | 18 | 14.7 |
| Allowable continuous current ^{*2,3} | A | | 6.0 | 6.0 | 6.0 | 6.0 | 6.0 | 9.0 | 9.0 | 9.0 | 8.8 | 7.2 |
| EMF constant ^{*4} | V/(r/min) | | 2.8 | 4.5 | 5.6 | 6.7 | 9.0 | 2.8 | 4.5 | 5.6 | 6.7 | 9.0 |
| Phase resistance (20 °C) | Ω | | 0.19 | | | | | | | | | |
| Phase inductance | mH | | 1.2 | | | | | | | | | |
| Inertia moment (without brake) | GD ² /4 | kg·m ² | 4.8 | 12 | 19 | 27 | 49 | 4.8 | 12 | 19 | 27 | 49 |
| | J | kgf·cm·s ² | 49 | 124 | 194 | 280 | 497 | 49 | 124 | 194 | 280 | 497 |
| Inertia moment (with brake) | GD ² /4 | kg·m ² | 5.8 | 15 | 23 | 33 | 59 | 5.8 | 15 | 23 | 33 | 59 |
| | J | kgf·cm·s ² | 59 | 150 | 235 | 338 | 601 | 59 | 150 | 235 | 338 | 601 |
| Reduction ratio | | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 |
| Permissible moment load | N·m | | 849 | | | | | | | | | |
| | kgf·m | | 86.6 | | | | | | | | | |
| Moment stiffness | N·m/rad | | 179 × 10 ⁴ | | | | | | | | | |
| | kgf·m/arc-min | | 53.2 | | | | | | | | | |
| Uni-directional positional accuracy | Sec. | | 40 | 30 | 30 | 30 | 30 | 40 | 30 | 30 | 30 | 30 |
| Repeatability | Sec. | | ±4 | | | | | | | | | |
| Reverse positional accuracy | Sec. | | 50 | 20 | 20 | 20 | 20 | 50 | 20 | 20 | 20 | 20 |
| Encoder type | | | Magnetic absolute encoder | | | | | | | | | |
| Encoder resolution | Single-turn detector | | 2 ¹⁷ (131072) | | | | | | | | | |
| | Multi-turn detector ^{*6} | | 2 ¹⁶ (65536) | | | | | | | | | |
| Output shaft resolution | pulse/rev | | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 |
| Mass (without brake) | kg | | 13.0 | | | | | | | | | |
| Mass (with brake) | kg | | 13.8 | | | | | | | | | |
| Environmental conditions ^{*7} | | | Operating temperature: 0 to 40 °C/Storage temperature: -20 to 60 °C Operating humidity/storage humidity: 20 to 80 %RH (no condensation) Resistance to vibration: 25 m/s ² (frequency: 10 to 400 Hz) Shock resistance: 300 m/s ² ^{*5} No dust, no metal powder, no corrosive gas, no inflammable gas, no oil mist To be used indoors, no direct sunlight Altitude: less than 1000 m above sea level | | | | | | | | | |
| Motor insulation | | | Insulation resistance: 100 MΩ or more (by DC500 V insulation tester) Dielectric strength: AC1500 V/1 min Insulation class: A | | | | | | | | | |
| Mounting direction | | | Can be installed in any direction. | | | | | | | | | |
| Protection structure | | | Totally enclosed self-cooled type (IP54) | | | | | | | | | |

The table shows typical output values of actuators.

*1: If a HA-800B/C-6D/E driver is combined with a SHA40A actuator, the maximum torque and allowable continuous torque are limited.

*2: Typical characteristics when combined (driven by ideal sine wave) with our drivers.

*3: Value after temperature rise and saturation when the 500×500×25 [mm] aluminum radiation plate is installed.

*4: Value of phase induced voltage constant multiplied by 3.

*5: For testing conditions, refer to [1-12 Shock resistance] (P1-42) and [1-13 Resistance to vibration] (P1-43).
Motor operation is not guaranteed in applications where vibrations and impacts are continuously applied for a long period of time.

*6: The multi-turn detector range is -32768 to 32767.

*7: For details, refer to [3-3 Location and installation] (P3-6).

1-5 Motor shaft holding brake

The brakes equipped on SHA series actuators are used to hold the motor shaft in place when the power is cut off. With some model numbers (model nos. 25, 23), the actuator's built-in circuit controls the voltage supplied to the brake in order to reduce the power consumption while the brake is actuated. Be sure to use a DC power supply having proper brake excitation voltage and capable of outputting enough current consumption during suction.

Specifications

SG/HP type

| Item | Model | SHA20A | | | | |
|---|--|--|------|-----|-----|-----|
| | | 51 | 81 | 101 | 121 | 161 |
| Type | | Dry non-excitation actuation type (without power-saving control) | | | | |
| Brake excitation voltage | V | DC24 V \pm 10 % (no polarity) ¹ | | | | |
| Current consumption during suction (at 20 °C) | A | 0.37 | | | | |
| Current consumption during holding (at 20 °C) | A | Same as current consumption during suction | | | | |
| Holding torque ³ | N·m | 31 | 49 | 61 | 73 | 97 |
| | kgf·m | 3.1 | 5.0 | 6.2 | 7.4 | 9.9 |
| Inertia moment ³ (Actuator total) (with brake) | kg·m ² (GD ² /4) | 0.26 | 0.65 | 1.0 | 1.4 | 2.6 |
| | kgf·cm·s ² (J) | 2.7 | 6.6 | 10 | 15 | 26 |
| Mass (with brake) ⁴ | kg | 2.1 | | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | |

| Item | Model | SHA25A | | | | | | SHA32A | | | | | |
|---|--|---|------|-----|-----|-----|-----|------------------|-----|-----|-----|-----|-----|
| | | 11 | 51 | 81 | 101 | 121 | 161 | 11 | 51 | 81 | 101 | 121 | 161 |
| Type | | Dry non-excitation actuation type (with power-saving control) | | | | | | | | | | | |
| Brake excitation voltage | V | DC24 V \pm 10 % (no polarity) ¹ | | | | | | | | | | | |
| Current consumption during suction (at 20 °C) | A | 0.8 ² | | | | | | 0.8 ² | | | | | |
| Current consumption during holding (at 20 °C) | A | 0.3 | | | | | | 0.3 | | | | | |
| Holding torque ³ | N·m | 11 | 51 | 81 | 101 | 121 | 161 | 22 | 102 | 162 | 202 | 242 | 322 |
| | kgf·m | 1.1 | 5.2 | 8.3 | 10 | 12 | 16 | 2.2 | 10 | 17 | 21 | 25 | 33 |
| Inertia moment ³ (Actuator total) (with brake) | kg·m ² (GD ² /4) | 0.034 | 0.66 | 1.7 | 2.6 | 3.7 | 6.6 | 1.7 | 2.3 | 5.9 | 9.2 | 13 | 23 |
| | kgf·cm·s ² (J) | 0.35 | 6.7 | 17 | 26 | 38 | 67 | 17 | 24 | 60 | 94 | 135 | 238 |
| Mass (with brake) ⁴ | kg | 5.1 | 3.1 | | | | 9.7 | 6.2 | | | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | | | | | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | | | | | | | | |

| Item | Model | SHA40A | | | | | SHA45A | | | | |
|---|--|--|-----|-----|-----|-----|--------|-----|-----|-----|-----|
| | | 51 | 81 | 101 | 121 | 161 | 51 | 81 | 101 | 121 | 161 |
| Type | | Dry non-excitation actuation type (without power-saving control) | | | | | | | | | |
| Brake excitation voltage | V | DC24 V \pm 10 % (no polarity) ¹ | | | | | | | | | |
| Current consumption during suction (at 20 °C) | A | 0.7 | | | | | | | | | |
| Current consumption during holding (at 20 °C) | A | Same as current consumption during suction | | | | | | | | | |
| Holding torque ³ | N·m | 204 | 324 | 404 | 484 | 644 | 204 | 324 | 404 | 484 | 644 |
| | kgf·m | 21 | 33 | 41 | 49 | 66 | 21 | 33 | 41 | 49 | 66 |
| Inertia moment ³ (Actuator total) (With brake) | kg·m ² (GD ² /4) | 6.1 | 15 | 24 | 34 | 61 | 7.9 | 20 | 31 | 45 | 79 |
| | kgf·cm·s ² (J) | 62 | 157 | 244 | 350 | 619 | 81 | 204 | 316 | 454 | 804 |
| Mass (with brake) ⁴ | kg | 10.7 | | | | | 13.2 | | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | | | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | | | | | | |


| Item | Model | SHA58A | | | | SHA65A | | | |
|---|--|--|------|------|------|--------|------|------|------|
| | | 81 | 101 | 121 | 161 | 81 | 101 | 121 | 161 |
| Type | | Dry non-excitation actuation type (without power-saving control) | | | | | | | |
| Brake excitation voltage | V | DC24 V \pm 10 % (no polarity) ¹ | | | | | | | |
| Current consumption during suction (at 20 °C) | A | 0.9 | | | | | | | |
| Current consumption during holding (at 20 °C) | A | Same as current consumption during suction | | | | | | | |
| Holding torque ³ | N·m | 1220 | 1520 | 1820 | 2420 | 1220 | 1520 | 1820 | 2420 |
| | kgf·m | 124 | 155 | 185 | 246 | 124 | 155 | 185 | 246 |
| Inertia moment ³ (Actuator total) (With brake) | kg·m ² (GD ² /4) | 106 | 165 | 237 | 420 | 120 | 187 | 268 | 475 |
| | kgf·cm·s ² (J) | 1090 | 1690 | 2420 | 4290 | 1230 | 1910 | 2740 | 4850 |
| Mass (with brake) ⁴ | kg | 32 | | | | 40 | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | | | | |

CG type

| Item | Model | SHA20A | | | | | SHA25A | | | | |
|---|--|--|-----|------|-----|-----|---|-----|-----|-----|-----|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| Type | | Dry non-excitation actuation type (without power-saving control) | | | | | Dry non-excitation actuation type (with power-saving control) | | | | |
| Brake excitation voltage | V | DC24 V ± 10 % (no polarity) ¹ | | | | | | | | | |
| Current consumption during suction (at 20 °C) | A | 0.37 | | | | | 0.8 ² | | | | |
| Current consumption during holding (at 20 °C) | A | Same as current consumption during suction | | | | | 0.3 | | | | |
| Holding torque ³ | N·m | 30 | 48 | 60 | 72 | 96 | 50 | 80 | 100 | 120 | 160 |
| | kgf·m | 3.1 | 4.9 | 6.1 | 7.3 | 9.8 | 5.1 | 8.2 | 10 | 12 | 16 |
| Inertia moment ³ (Actuator total) (With brake) | kg·m ² (GD ² /4) | 0.23 | 0.6 | 0.94 | 1.3 | 2.4 | 0.60 | 1.5 | 2.4 | 3.4 | 6.1 |
| | kgf·cm·s ² (J) | 2.4 | 6.1 | 9.6 | 14 | 24 | 6.1 | 16 | 24 | 35 | 62 |
| Mass (with brake) ⁴ | kg | 2.7 | | | | | 4.1 | | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | | | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | | | | | | |

| Item | Model | SHA32A | | | | | SHA40A | | | | |
|---|--|---|-----|-----|-----|-----|--|-----|-----|-----|-----|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| Type | | Dry non-excitation actuation type (with power-saving control) | | | | | Dry non-excitation actuation type (without power-saving control) | | | | |
| Brake excitation voltage | V | DC24 V ± 10 % (no polarity) ¹ | | | | | | | | | |
| Current consumption during suction (at 20 °C) | A | 0.8 ² | | | | | 0.7 | | | | |
| Current consumption during holding (at 20 °C) | A | 0.3 | | | | | Same as current consumption during suction | | | | |
| Holding torque ³ | N·m | 100 | 160 | 200 | 240 | 320 | 200 | 320 | 400 | 480 | 640 |
| | kgf·m | 10 | 16 | 20 | 24 | 33 | 20 | 33 | 41 | 49 | 65 |
| Inertia moment ³ (Actuator total) (With brake) | kg·m ² (GD ² /4) | 2.0 | 5.1 | 7.9 | 11 | 20 | 5.8 | 15 | 23 | 33 | 59 |
| | kgf·cm·s ² (J) | 20 | 52 | 81 | 116 | 207 | 59 | 150 | 235 | 338 | 601 |
| Mass (with brake) ⁴ | kg | 8.0 | | | | | 13.8 | | | | |
| Allowable number of normal brakings ⁵ | | 100000 times | | | | | | | | | |
| Allowable number of emergency stops ⁶ | | 200 times | | | | | | | | | |

- *1: Power supply is user's responsibility. Use a power supply capable of outputting enough current consumption during suction for the brake.
- *2: The duration for current consumption during suction is 0.5 second or less for the power supply of DC24 V ± 10 %.
- *3: The values are converted for the output shaft of the actuator.
- *4: The values present total mass of the actuator.
- *5: The service time for normal holding is assured when the brake activates at motor shaft rotation speed of 150 r/min or less.
- *6: The service time for emergency stop is assured when the brake activates at motor speed of 3000 r/min or less provided the load inertia moment is 3 times of less than that of the actuator.



WARNING

The motor shaft holding brake cannot be used for deceleration.
 Do not use the holding brake more than the allowable number of normal brakings (100000 times at the motor shaft rotation speed of 150 r/min or less) or allowable number of emergency stops (200 times at the motor shaft rotation speed of 3000 r/min, provided the load inertia moment is 3 times or less than that of the actuator).

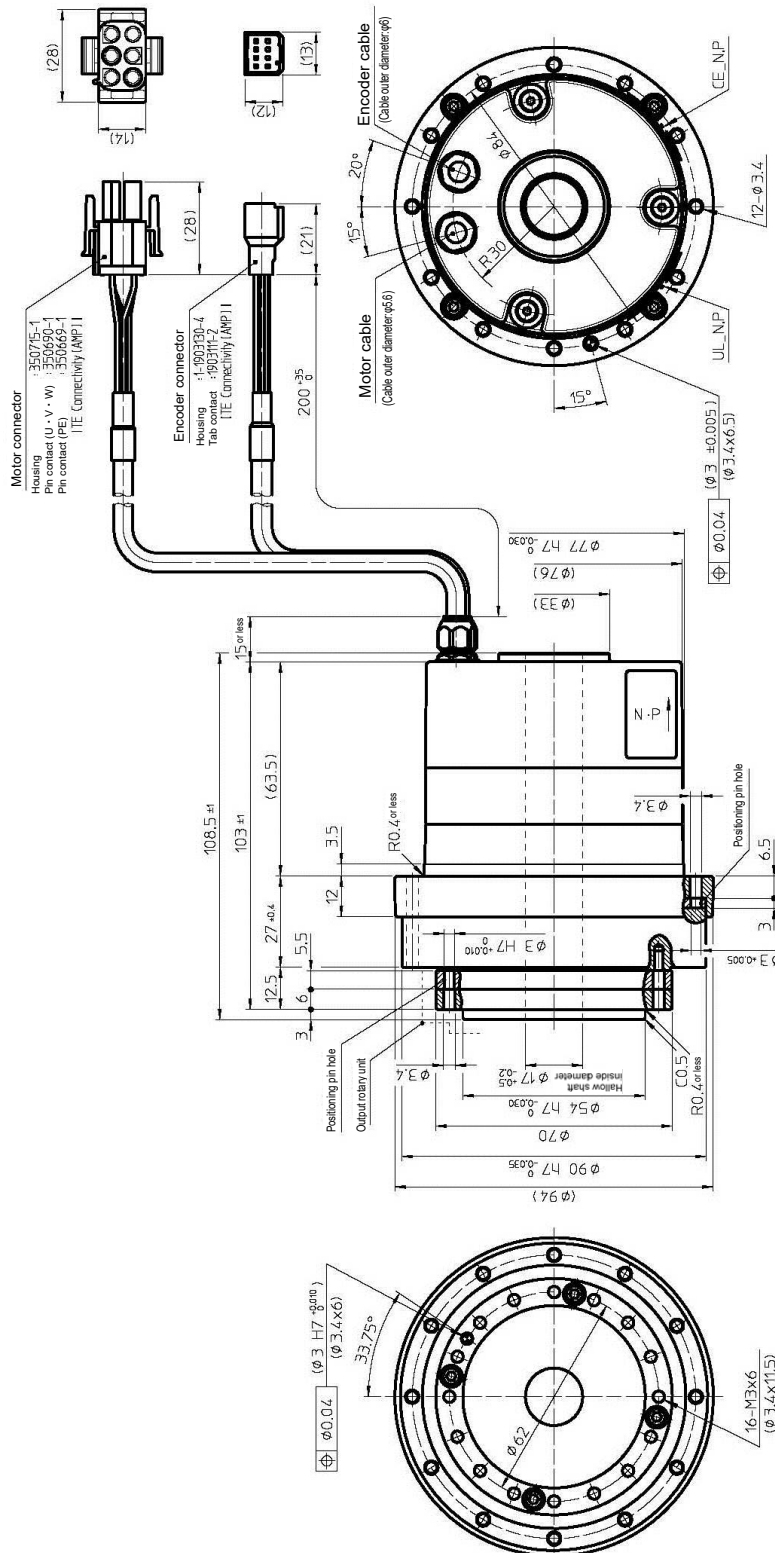
Exceeding the allowable number of normal brakings and allowable number of emergency stops may deteriorate holding torque, and may consequently become out of use as a brake.

1-6 External dimensions

The external dimensions of SHA series actuators are shown below.

- **SHA20A-SG (Speed reducer: HarmonicDrive® speed reducer SHG series for precision control)**

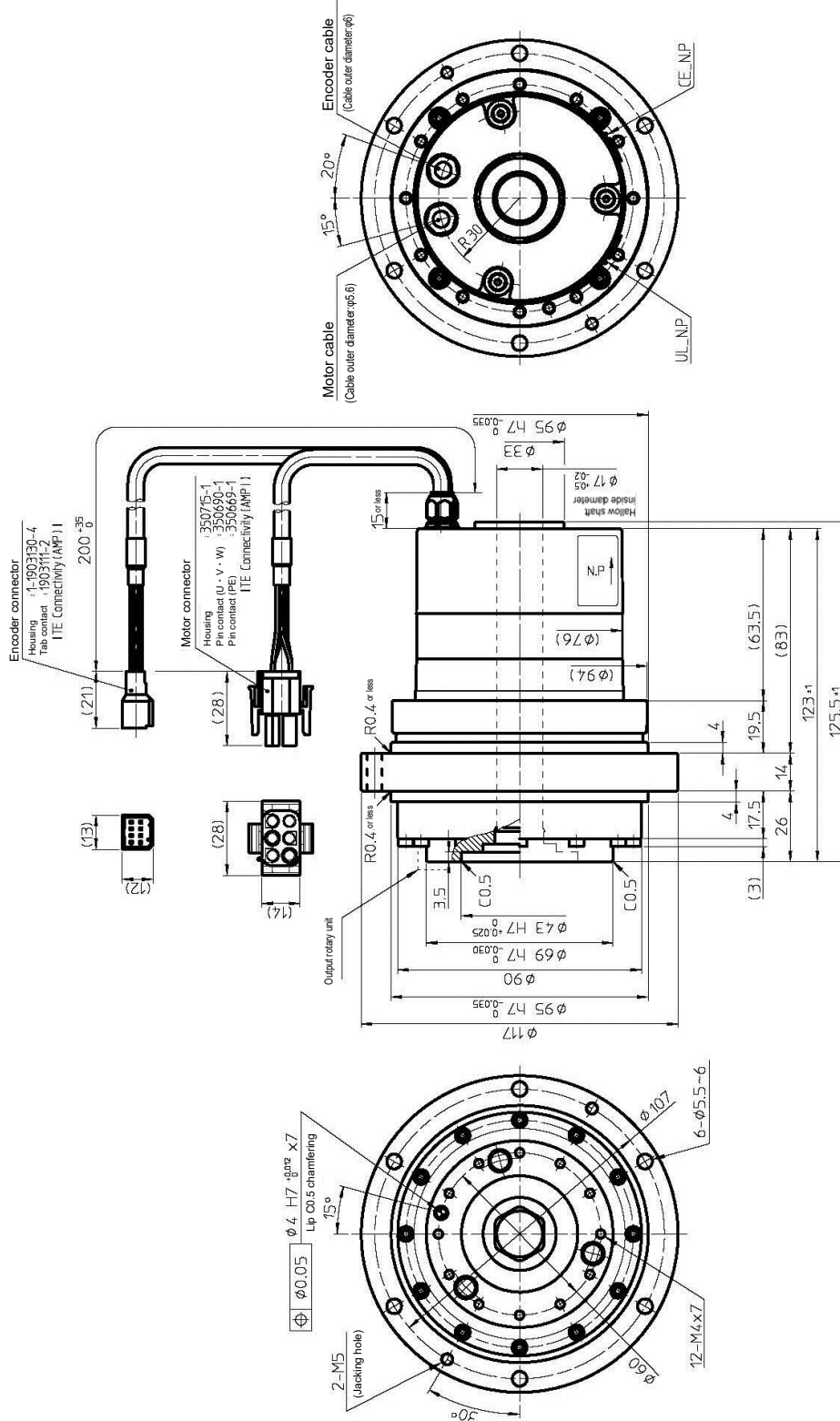
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA20A-CG (Speed reducer: HarmonicDrive® speed reducer CSG series for precision control)

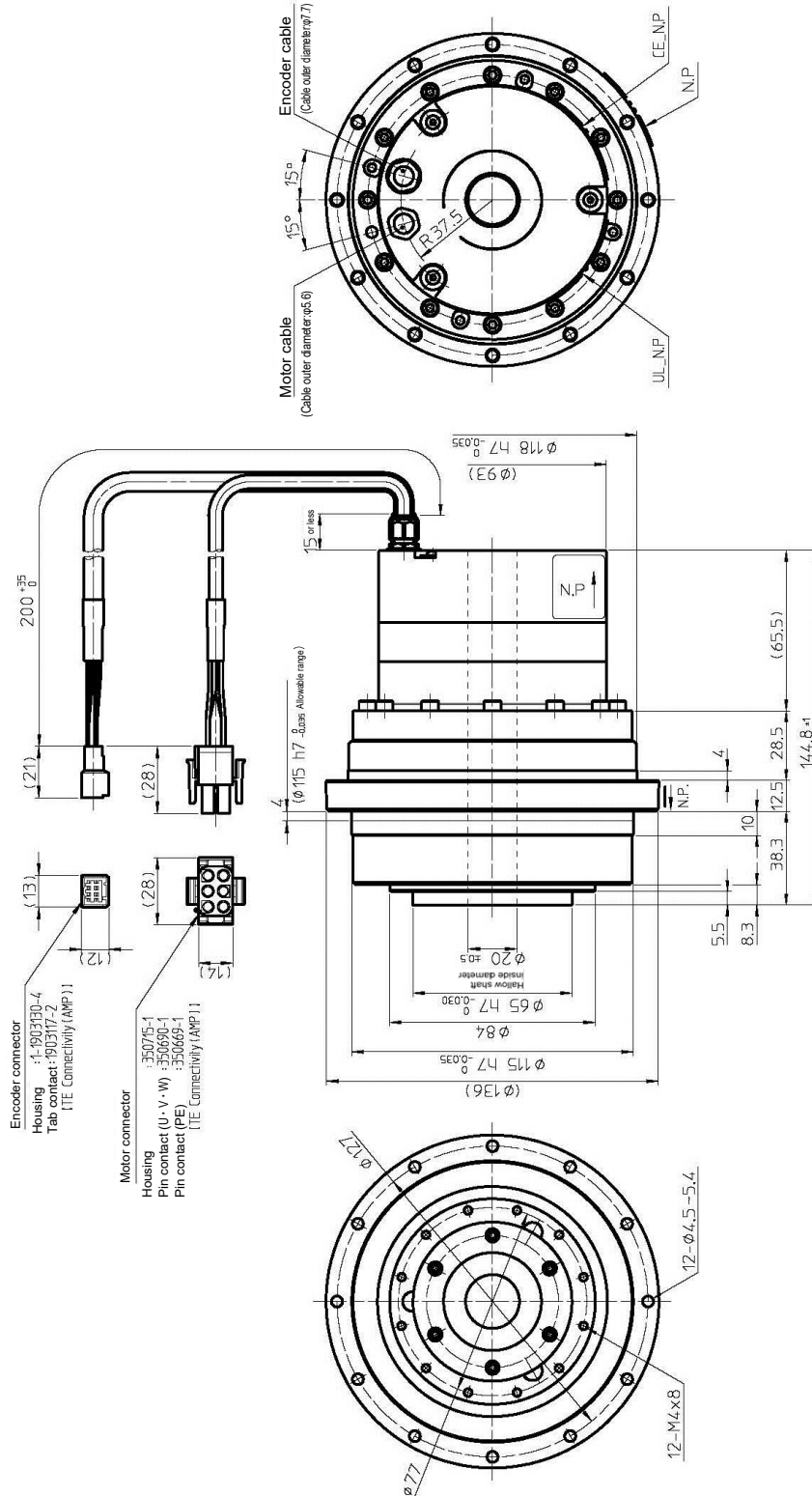
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

● SHA25A-HP (Speed reducer: hollow planetary speed reducer HPF series for precision control)

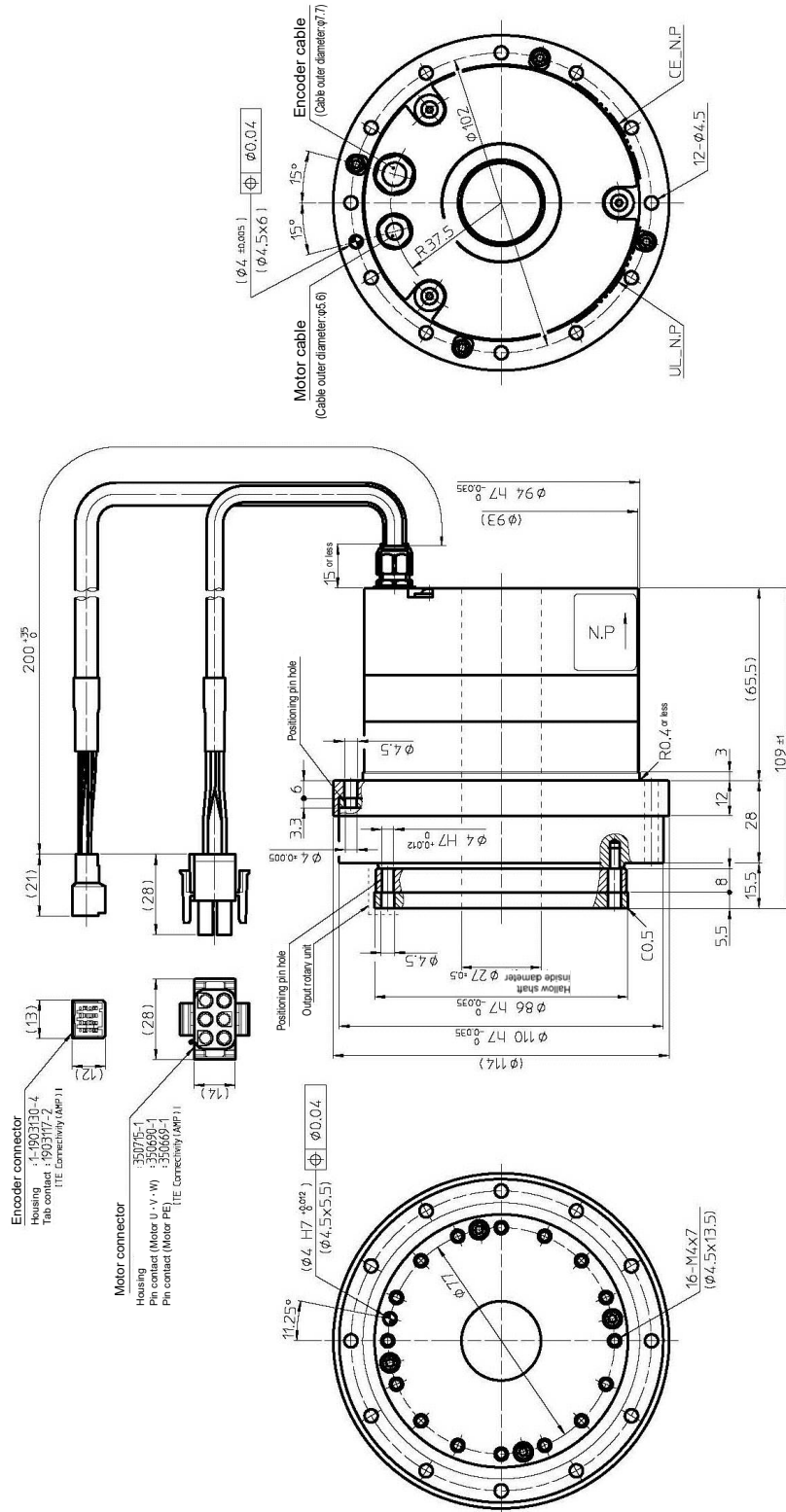
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA25A-SG (Speed reducer: HarmonicDrive® speed reducer SHG series for precision control)

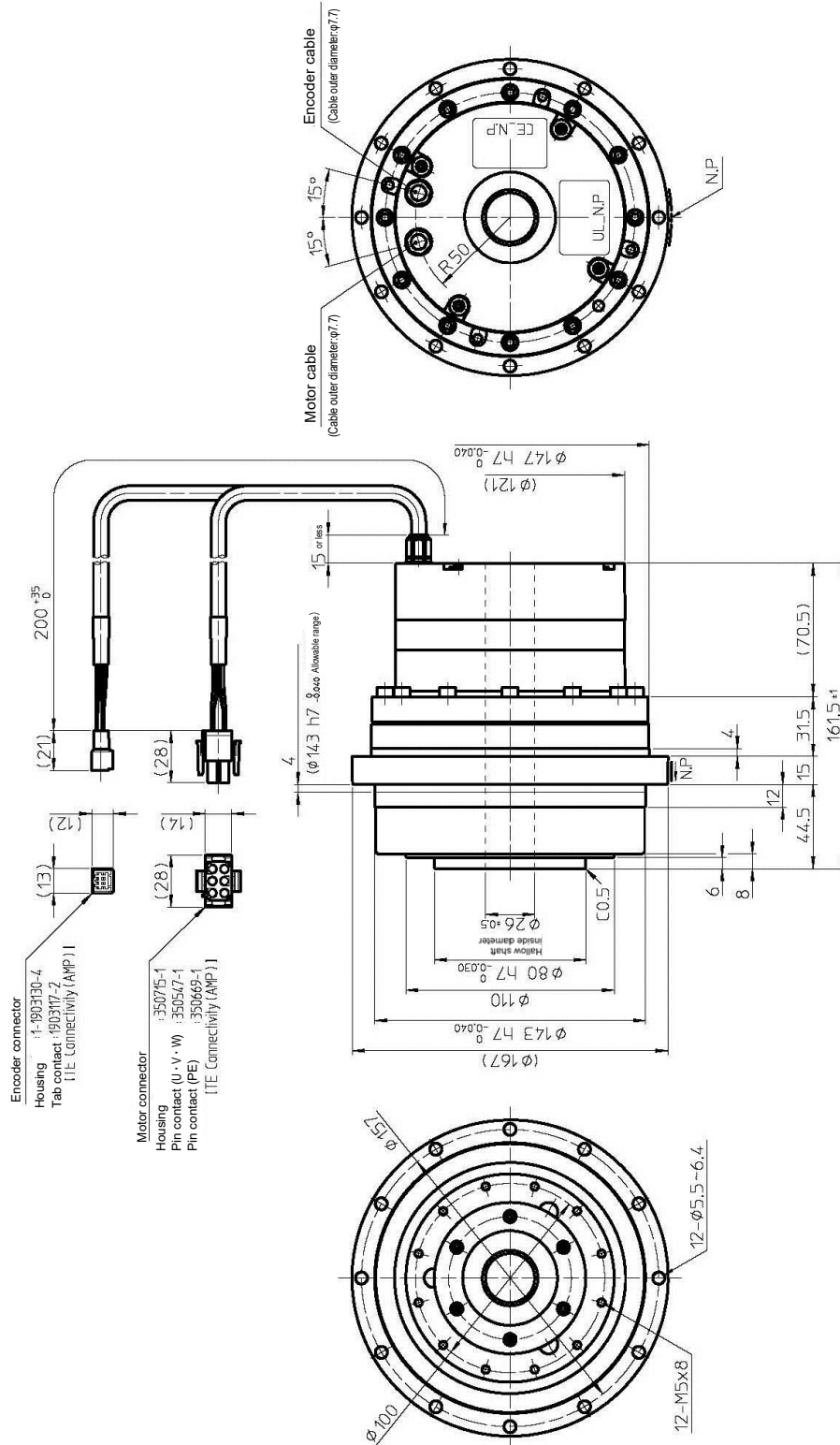
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA32A-HP (Speed reducer: hollow planetary speed reducer HPF series for precision control)

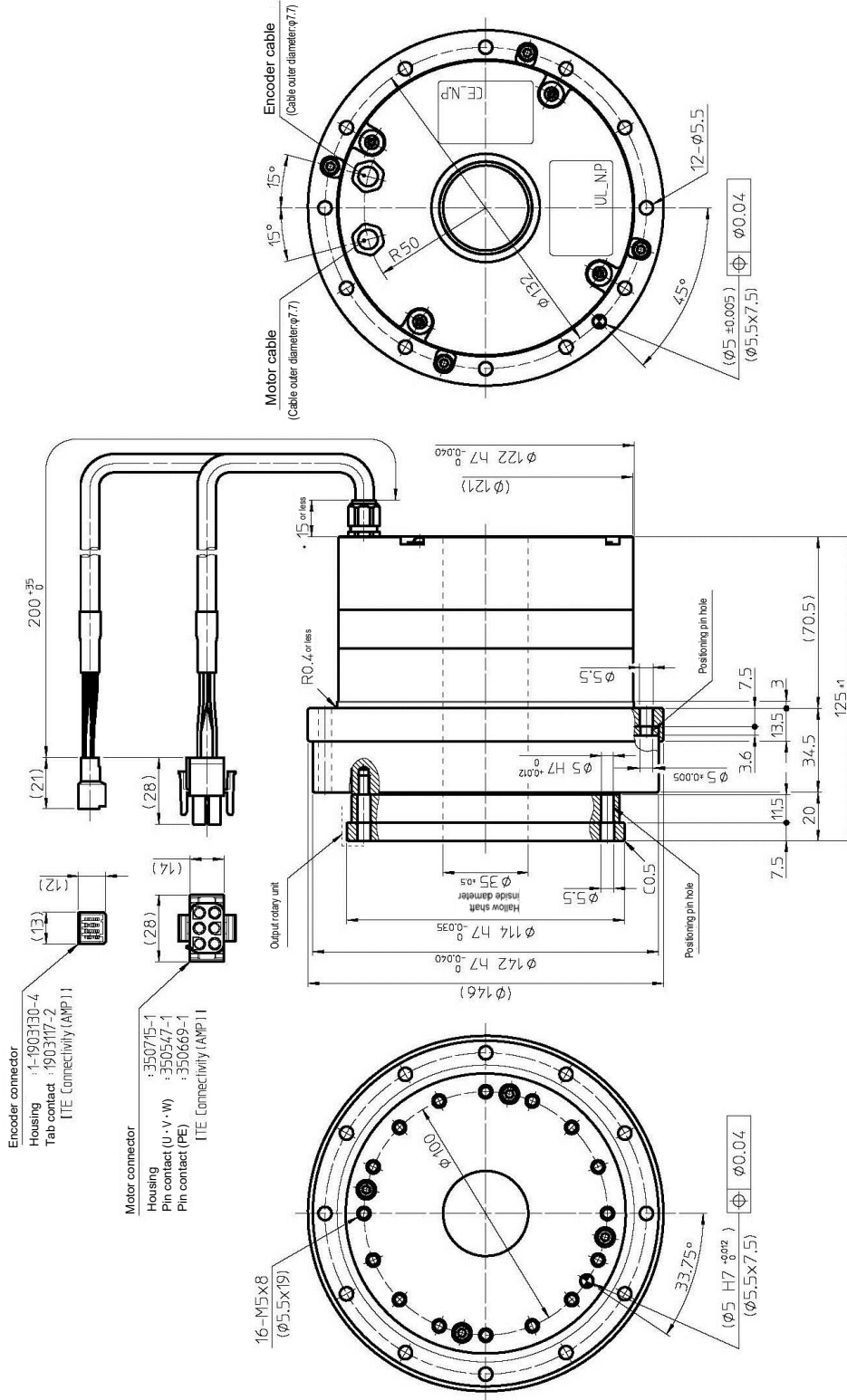
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA32A-SG (Speed reducer: HarmonicDrive® speed reducer SHG series for precision control)

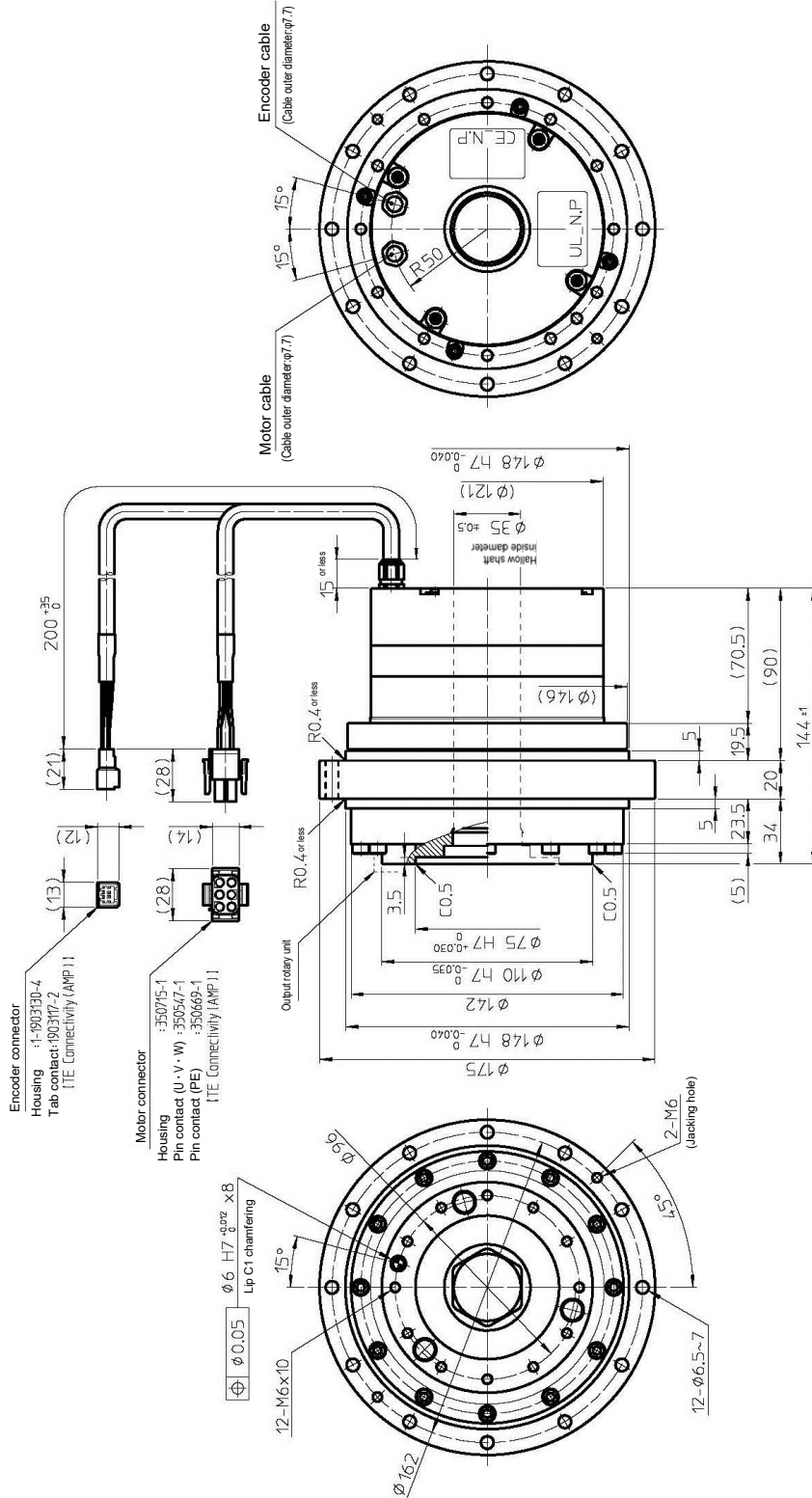
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA32A-CG (Speed reducer: HarmonicDrive® speed reducer CSG series for precision control)

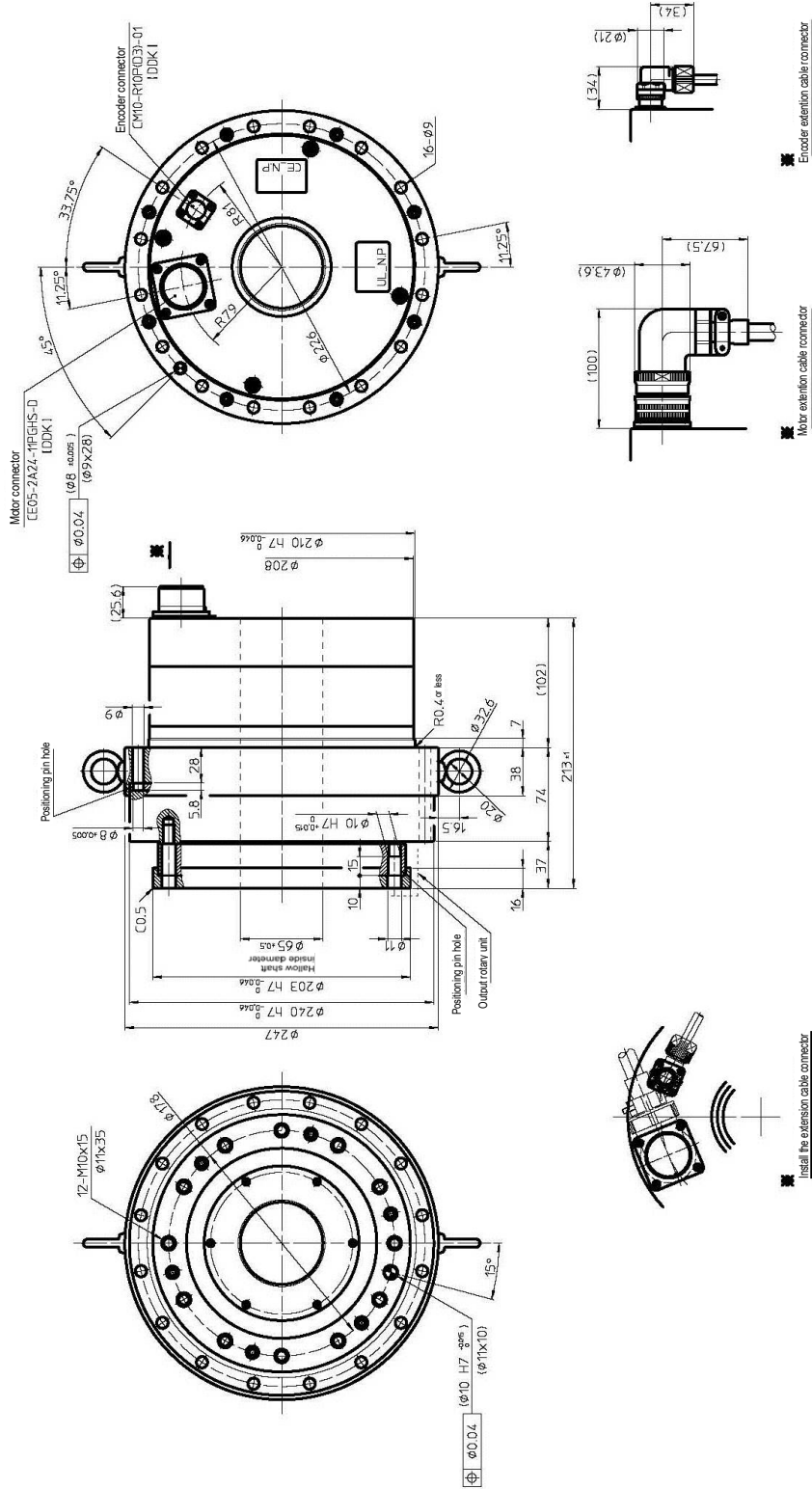
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [3-3 Location and installation] (P3-6) for the permissible cable bending radius.

- SHA58A-SG (Speed reducer: HarmonicDrive® speed reducer SHG series for precision control)

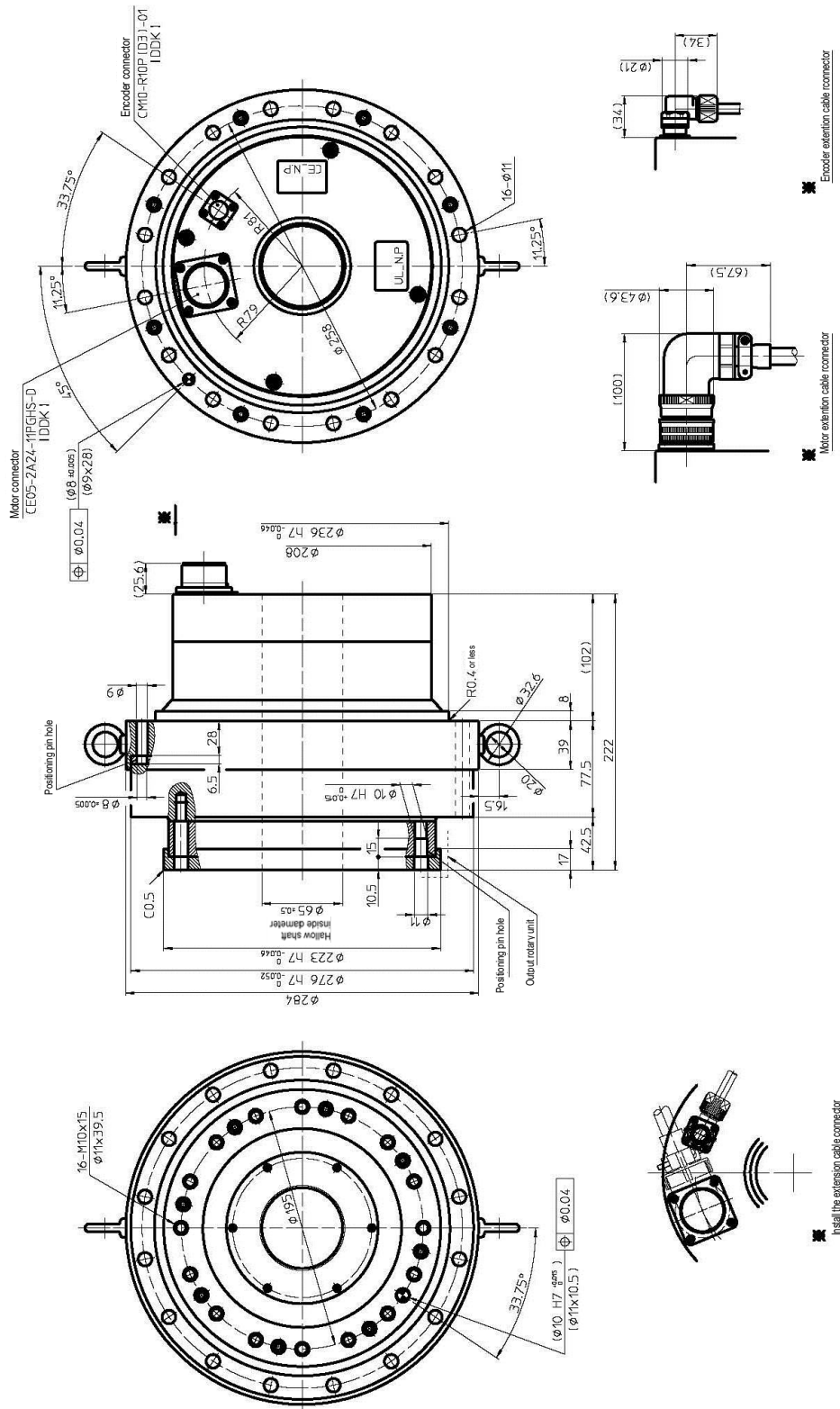
Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [4-1 Options] (P4-1) for the permissible cable bending radius.

● SHA65A-SG(Speed reducer: HarmonicDrive® speed reducer SHG series for precision control)

Unit [mm] (third angle projection)



Note: For details on external dimensions, check our illustrated specifications.
 Tolerances may vary due to product manufacturing method (foundry piece, machine-finished good).
 Please contact us for the tolerance when it is not indicated in the dimensions.
 Refer to [4-1 Options] (P4-1) for the permissible cable bending radius.

1-7 Mechanical accuracy

The mechanical accuracies of the output shaft and mounting flange are shown below for SHA series actuators:

| SG/HP type | | Unit [mm] | | | |
|---|--------|------------------|------------------|--------|--|
| Accuracy items | SHA20A | SHA25A | SHA32A | SHA40A | |
| 1. Output shaft surface runout | 0.030 | 0.035 (0.020) | 0.040 (0.020) | 0.045 | |
| 2. Deflection of output shaft | 0.030 | 0.035 | 0.040 | 0.045 | |
| 3. Parallelism between the output shaft end mounted surface | 0.030 | 0.035 | 0.040 | 0.045 | |
| 4. Parallelism between the output shaft end mounted surface | 0.055 | 0.050 | 0.055 | 0.060 | |
| 5. Concentricity between the output shaft and fitting part | 0.030 | 0.035 | 0.040 | 0.045 | |
| 6. Concentricity between the output shaft and fitting part | 0.045 | 0.060 | 0.065 | 0.070 | |

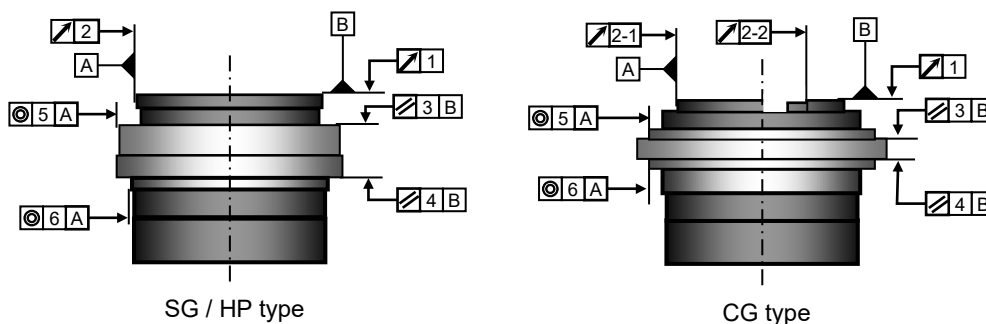
| Accuracy items | SHA45A | SHA58A | SHA65A |
|---|--------|--------|--------|
| 1. Output shaft surface runout | 0.045 | 0.050 | 0.050 |
| 2. Deflection of output shaft | 0.045 | 0.050 | 0.050 |
| 3. Parallelism between the output shaft end mounted surface | 0.045 | 0.050 | 0.050 |
| 4. Parallelism between the output shaft end mounted surface | 0.060 | 0.070 | 0.070 |
| 5. Concentricity between the output shaft and fitting part | 0.045 | 0.050 | 0.050 |
| 6. Concentricity between the output shaft and fitting part | 0.070 | 0.080 | 0.080 |

Note: All values are T.I.R. (Total Indicator Reading).

The values in parenthesis are those combined with the hollow planetary speed reducer HPF series for precision control.

| CG type | | Unit [mm] | | | |
|---|--------|-----------|--------|--------|--|
| Accuracy items | SHA20A | SHA25A | SHA32A | SHA40A | |
| 1. Output shaft surface runout | 0.010 | 0.010 | 0.010 | 0.010 | |
| 2-1. Deflection of output shaft (Outside inlay) | 0.010 | 0.010 | 0.010 | 0.010 | |
| 2-2. Deflection of output shaft (Inside inlay) | 0.015 | 0.015 | 0.015 | 0.015 | |
| 3. Parallelism between the output shaft end mounted surface | 0.030 | 0.030 | 0.035 | 0.035 | |
| 4. Parallelism between the output shaft end mounted surface | 0.040 | 0.040 | 0.045 | 0.045 | |
| 5. Concentricity between the output shaft and fitting part | 0.050 | 0.050 | 0.055 | 0.060 | |
| 6. Concentricity between the output shaft and fitting part | 0.060 | 0.060 | 0.065 | 0.070 | |

Note: All values are T.I.R. (Total Indicator Reading).



The measuring for the values are as follows:

1 Output shaft surface runout

The indicator on the fixed part measures the axial runout (maximum runout width) of the outermost circumference of output shaft of the output rotary unit per revolution.

2 Deflection of output shaft

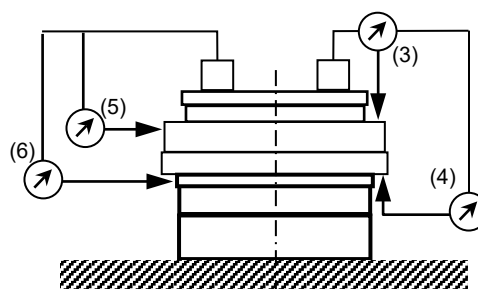
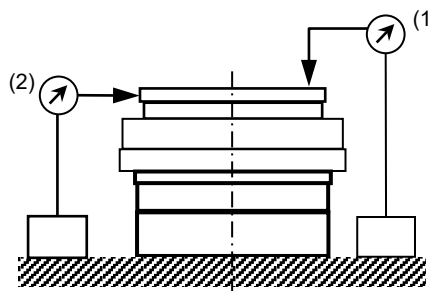
The indicator on the fixed part measures the radial runout (maximum runout width) of output shaft of the output rotary unit per revolution.

3,4 Parallelism between the output shaft and mounted surface

The indicator on the output rotary unit measures the axial runout (maximum runout width) of the outermost circumference of the mounting surface (both on the output shaft side and opposite side) of the output rotary unit per revolution.

5,6 Centricity between the output shaft and fitting part

The indicator on the output rotary unit measures the radial runout (maximum runout width) of the fitting part (both on the output shaft side and opposite side) of the output rotary unit per revolution.

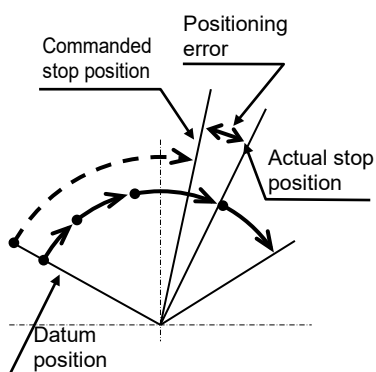


1-8 Positional accuracy

Uni-directional positional accuracy

The uni-directional positional accuracy means the maximum positional difference between the actual rotated angle from the datum position and its theoretical rotational angle in one revolution when series of positioning are performed in the same rotation direction. (Refer to JIS B-6201-1987.)

Since the SHA series incorporates a speed reducer HarmonicDrive® or HPF for precision control, the impact of motor shaft positioning error becomes 1/multiple of reduction ratio.



The uni-directional positional accuracy is shown in the table below:

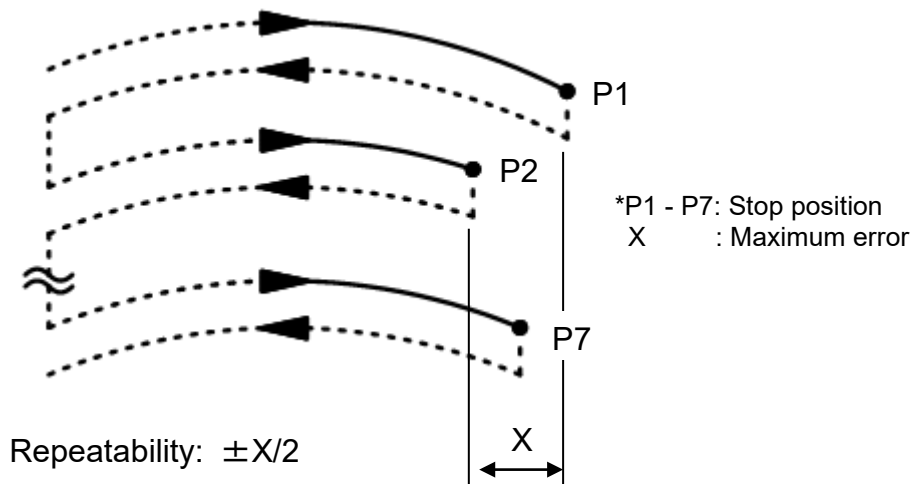
| SG/HP type | | Unit [Second] | | | | | | |
|-----------------|-------|---------------|---------|--------|--------|--------|--------|--------|
| Reduction ratio | Model | SHA20A | SHA 25A | SHA32A | SHA40A | SHA45A | SHA58A | SHA65A |
| 1:11 | | — | 120 | 120 | — | — | — | — |
| 1:51 | | 60 | 50 | 50 | 50 | 50 | — | — |
| 1:81 or more | | 50 | 40 | 40 | 40 | 40 | 40 | 40 |

| CG type | | Unit [Second] | | | |
|-----------------|-------|---------------|--------|--------|--------|
| Reduction ratio | Model | SHA20A | SHA25A | SHA32A | SHA40A |
| 1:50 | | 60 | 50 | 40 | 40 |
| 1:80 or more | | 50 | 40 | 30 | 30 |

Repeatability (CG type)

For the "repeatability", the output shaft stop position is measured by performing positioning at a position 7 times in the same direction. This measurement is performed at 4 locations on the output shaft and the maximum error is found. The measurement value is expressed as an angle which is 1/2 the maximum error with ± attached. (Refer to JIS B 6201-1987.)

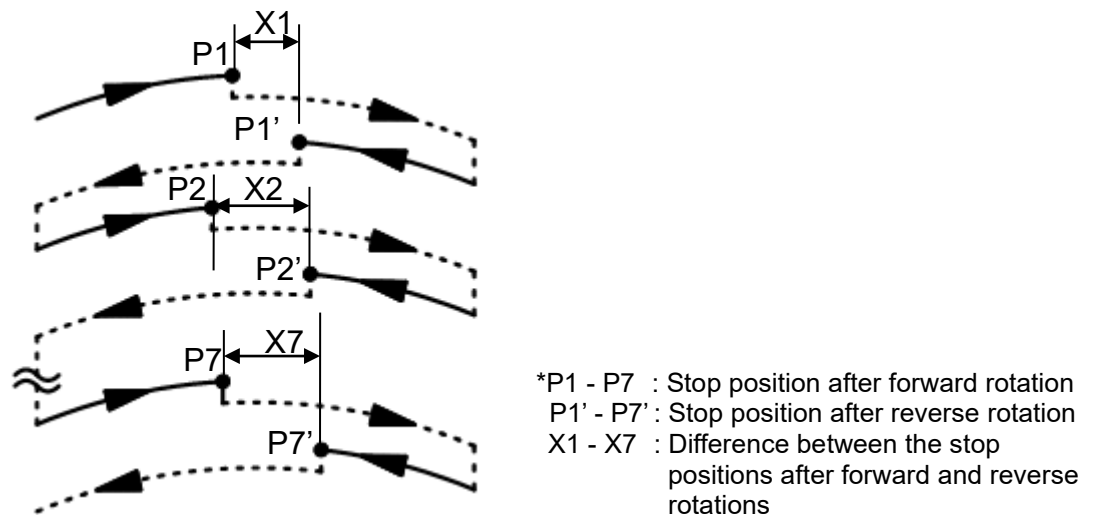
| CG type | | Unit [Second] | | | |
|---------------------|-------|---------------|--------|--------|--------|
| Reduction ratio | Model | SHA20A | SHA25A | SHA32A | SHA40A |
| Ratio to full speed | | ±5 | ±5 | ±4 | ±4 |



Reverse positional accuracy (CG type)

For the "reverse positional accuracy", the shaft is rotated beforehand in the forward (or reverse) direction and the stop position for that rotation is set as the reference position. An instruction is given to rotate the shaft in the same direction and from the stopped position, the same instruction is given in the reverse (or forward) direction and the difference between the stop position after this rotation and the reference position is measured. The average value from repeating this 7 times in each direction is shown and the maximum value measured at the 4 locations on the output shaft is shown. (Refer to JIS B 6201-1987.)

| CG type | | Unit [Second] | | | |
|-----------------|-------|---------------|--------|--------|--------|
| Reduction ratio | Model | SHA20A | SHA25A | SHA32A | SHA40A |
| 1:50 | | 75 | 60 | 60 | 50 |
| 1:80 of more | | 30 | 25 | 25 | 20 |



Reverse positional accuracy: $|X1+X2+\dots+X7|/7$

1-9 Detector specifications (Absolute encoder)

Absolute encoders installed in the SHA series are a multi revolution-type absolute encoder. This encoder consists of a detector (17 bits) for detecting the position per motor shaft revolution, and a multi-turn detector (16 bits) for detecting the number of revolutions.

This encoder constantly detects the absolute machine position and stores it by means of the backup battery, regardless of whether the driver or external controller power is turned ON/OFF. Accordingly, once the origin is detected when the machine is installed, originating is not required after subsequent power ON operations. This facilitates the recovery operation after a power failure or breakdown.

In addition, while the power is ON, the multi-turn detector portion that detects the single revolution absolute position and the number of revolutions is a dual-redundant system in which a matching check is always performed on data, and this highly reliable design allows for encoder errors to be self-detected should they occur.

It is recommended that you replace the battery while the driver is receiving power.

Specifications

| Type ^{*1} | Magnetic sensor/electronic battery backup type (Single rotation optic, multiple revolution magnetic sensor/electronic battery backup type) |
|--|---|
| Single-turn detector | 2 ¹⁷ : 131072 pulses |
| Multi-turn detector | 2 ¹⁶ : 65536 (-32768 to 32767) |
| Maximum permissible motor shaft rotational speed | 7000 r/min ^{*2} |
| Safety/redundancy | <ul style="list-style-type: none"> • Check method in which two identical single revolution detectors are compared • Check method in which two identical cumulative revolution counters are compared |
| Backup time by external battery | 1 year ^{*3} (when power is not supplied) |
| Backup time by internal battery ^{*4} | 30 minutes (after 3 hours of charge, ambient temperature of 25 °C, axis stopped) (For backup while the driver and encoder are disconnected briefly) |

*1: Model No. 20 is equipped with an optical encoder; other models are equipped with a magnetic encoder.

*2: This is the rotation speed limit of the encoder and is different from the rotation speed that the motor can drive.

*3: The value is obtained with the motor axis stopped. Frequent movement of the motor axis with no power supply would cause the external battery to drain quickly.

*4: This function is only available for SHA20. Other models do not have this function.

Resolution of output shaft

| Encoder resolution | | 17bit (2 ¹⁷ : 131072 pulses) | | | | | |
|----------------------------|-----------|---|-----------------|-----------------|------------------|------------------|------------------|
| Reduction ratio | | 1:11 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Resolution of output shaft | Pulse/rev | 1441792 | 6684672 | 10616832 | 13238272 | 15859712 | 21102592 |
| Resolvable angle per pulse | Sec. | Approx. 0.9 | Approx. 0.2 | Approx. 0.12 | Approx. 0.1 | Approx. 0.082 | Approx. 0.061 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | |
| Resolution of output shaft | pulse/rev | 6553600 | 10485760 | 13107200 | 15728640 | 20971520 | |
| Resolvable angle per pulse | Sec. | Approx. 0.2 | Approx. 0.12 | Approx. 0.1 | Approx. 0.082 | Approx. 0.062 | |

Absolute position data

[Absolute position] indicates the absolute position within one motor shaft revolution, while [multi revolution] indicates the number of motor revolutions. The position of the actuator output shaft is obtained by the following formula:

Position of actuator output shaft = (Absolute position + Multi revolution data × Encoder resolution) / Reduction ratio

Transfer of encoder data

Data is transferred via bi-directional communication in a normal condition while power is supplied. When the driver control power supply is turned OFF and the driver enters the battery backup mode, communication stops.

Output shaft single revolution absolute model (Option)

With the standard actuator, when it continues to rotate in just one direction, the absolute encoder eventually exceeds the number of revolutions that can be detected with multi-revolution detection and it becomes impossible to manage position information accurately.

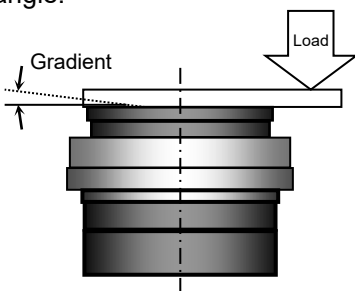
With the output shaft single revolution absolute model, each time the output shaft turns through single revolution, the cumulative multi revolution counter is cleared to 0. This is how position information is accurately managed when the shaft continuously turns in just one direction.

1-10 Rigidity

Moment stiffness


The moment stiffness refers to the torsional stiffness when a moment load is applied to the output shaft of the actuator (shown in the figure).

For example, when a load is applied to the end of an arm attached on the output shaft of the actuator, the face of the output shaft of the actuator tilts in proportion to the moment load. The moment stiffness is expressed as the load/gradient angle.



| Model | | SHA20A | SHA25A | | SHA32A | |
|------------------|---------------|--------------------|--------------------|--------------------|--------------------|-------------------|
| Reduction ratio | | 1:50 or more | 1:11 | 1: 50 or more | 1:11 | 1: 50 or more |
| Moment stiffness | N·m/rad | 25.2×10^4 | 37.9×10^4 | 39.2×10^4 | 86.1×10^4 | 100×10^4 |
| | kgf·m/rad | 25.7×10^3 | 38.7×10^3 | 40×10^3 | 87.9×10^3 | 102×10^3 |
| | kgf·m/arc-min | 7.5 | 11.3 | 11.6 | 25.7 | 29.6 |

| Model | | SHA40A | SHA45A | SHA58A | SHA65A |
|------------------|---------------|-------------------|-------------------|-------------------|-------------------|
| Reduction ratio | | 1:50 or more | 1: 51 or more | 1:81 or more | 1:81 or more |
| Moment stiffness | N·m/rad | 179×10^4 | 257×10^4 | 531×10^4 | 741×10^4 |
| | kgf·m/rad | 183×10^3 | 262×10^3 | 542×10^3 | 756×10^3 |
| | kgf·m/arc-min | 53.2 | 76.3 | 158 | 220 |

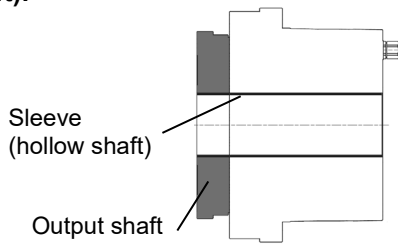


CAUTION

Do not apply torque, load or thrust to the sleeve (hollow shaft) directly.

The sleeve (hollow shaft) is adhered to the output rotary shaft. Accordingly, the adhered sleeve may be detached from the output rotary shaft if a torque or load is applied to the sleeve (hollow shaft).

Do not apply any torque, moment load or thrust load directly to the sleeve (hollow shaft).



Sleeve (hollow shaft)

Output shaft

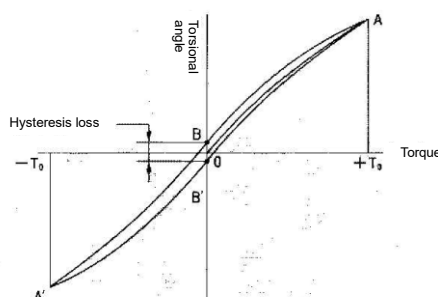
Torsional rigidity (Speed ratio 50 or more: HarmonicDrive® speed reducer for precision control)

Caution

- The speed reducer uses (1) speed ratio 50 or more for the HarmonicDrive® speed reducer for precision control and (2) speed ratio 11 for the hollow planetary speed reducer for precision control HPF series. The structures of the speed reducer are different, so their rotation direction torsional stiffness are different. Refer to individual characteristics shown on the graphs and tables.

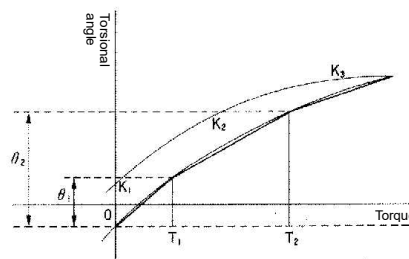
If a torque is applied to the output shaft of the actuator with the servo locked, the output shaft generates a torsional stress roughly in proportion to the torque.

The upper right figure shows the torsional angle of the output shaft when a torque starting from zero and increased to positive side [+T₀] and negative side [-T₀] is applied to the output shaft. This is called [torque vs. torsional angle] diagram, which typically follows a loop 0→A→B→A'→B'→A. The torsional rigidity of the SHA series actuator is expressed by the gradient of this [torque vs. torsional angle diagram] representing a spring constant (unit: N·m/rad).



As shown by lower right figure, this [torque vs. torsional angle] diagram is divided into three regions and the spring constants in these regions are expressed by K₁, K₂, and K₃, respectively.

- K₁: Spring constant for torque region 0 to T₁
- K₂: Spring constant for torque region T₁ to T₂
- K₃: Spring constant for torque region over T₂



The torsional angle for each region is expressed as follows: * φ: Torsional angle

- Range where torque T is T₁ or below: $\varphi = \frac{T}{K_1}$
- Range where torque T is T₁ to T₂: $\varphi = \theta_1 + \frac{T - T_1}{K_2}$
- Range where torque T is T₂ to T₃: $\varphi = \theta_2 + \frac{T - T_2}{K_3}$

The table below shows the averages of T₁ to T₃, K₁ to K₃, and θ₁ to θ₂ for each actuator.

| Model | | SHA20A | | SHA25A | | SHA32A | | SHA40A | |
|-----------------|--------------------------|--------------|-----------------|--------------|-----------------|--------------|-----------------|--------------|-----------------|
| Reduction ratio | | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more |
| T1 | N·m | 7.0 | | 14 | | 29 | | 54 | |
| | kgf·m | 0.7 | | 1.4 | | 3.0 | | 5.5 | |
| K1 | x10 ⁴ N·m/rad | 1.3 | 1.6 | 2.5 | 3.1 | 5.4 | 6.7 | 10 | 13 |
| | kgf·m/arc-min | 0.38 | 0.47 | 0.74 | 0.92 | 1.6 | 2.0 | 3.0 | 3.8 |
| θ 1 | x10 ⁻⁴ rad | 5.2 | 4.4 | 5.5 | 4.4 | 5.5 | 4.4 | 5.2 | 4.1 |
| | arc-min | 1.8 | 1.5 | 1.9 | 1.5 | 1.9 | 1.5 | 1.8 | 1.4 |
| T2 | N·m | 25 | | 48 | | 108 | | 196 | |
| | kgf·m | 2.5 | | 4.9 | | 11 | | 20 | |
| K2 | X10 ⁴ N·m/rad | 1.8 | 2.5 | 3.4 | 5.0 | 7.8 | 11 | 14 | 20 |
| | kgf·m/arc-min | 0.52 | 0.75 | 1.0 | 1.5 | 2.3 | 3.2 | 4.2 | 6.0 |
| θ 2 | x10 ⁻⁴ rad | 15.4 | 11.3 | 15.7 | 11.1 | 15.7 | 11.6 | 15.4 | 11.1 |
| | arc-min | 5.3 | 3.9 | 5.4 | 3.8 | 5.4 | 4.0 | 5.3 | 3.8 |
| K3 | x10 ⁴ N·m/rad | 2.3 | 2.9 | 4.4 | 5.7 | 9.8 | 12 | 18 | 23 |
| | kgf·m/arc-min | 0.67 | 0.85 | 1.3 | 1.7 | 2.9 | 3.7 | 5.3 | 6.8 |

| Model | | SHA45A | | SHA58A | SHA65A |
|-----------------|--------------------------|--------|-----------------|-----------------|-----------------|
| Reduction ratio | | 1:51 | 1:81 or more | 1:81 or more | 1:81 or more |
| T1 | N·m | 76 | | 168 | 235 |
| | kgf·m | 7.8 | | 17 | 24 |
| K1 | x10 ⁴ N·m/rad | 15 | 18 | 40 | 54 |
| | kgf·m/arc-min | 4.3 | 5.4 | 12 | 16 |
| θ 1 | x10 ⁻⁴ rad | 5.2 | 4.1 | 4.1 | 4.4 |
| | arc-min | 1.8 | 1.4 | 1.4 | 1.5 |
| T2 | N·m | 275 | | 598 | 843 |
| | kgf·m | 28 | | 61 | 86 |
| K2 | X10 ⁴ N·m/rad | 20 | 29 | 61 | 88 |
| | kgf·m/arc-min | 6.0 | 8.5 | 18 | 26 |
| θ 2 | x10 ⁻⁴ rad | 15.1 | 11.1 | 11.1 | 11.3 |
| | arc-min | 5.2 | 3.8 | 3.8 | 3.9 |
| K3 | x10 ⁴ N·m/rad | 26 | 33 | 71 | 98 |
| | kgf·m/arc-min | 7.6 | 9.7 | 21 | 29 |

The table below shows reference torque values calculated for different torsional angle. Unit [N·m]

| Model | SHA20A | | SHA25A | | SHA32A | | SHA40A | |
|-----------------|--------------|-----------------|--------------|-----------------|--------------|-----------------|--------------|-----------------|
| Reduction ratio | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more | 1:50 1:51 | 1:80 or more |
| 2 arc-min | 8 | 11 | 15 | 21 | 31 | 45 | 63 | 88 |
| 4 arc-min | 19 | 25 | 35 | 51 | 77 | 108 | 144 | 208 |
| 6 arc-min | 30 | 43 | 56 | 84 | 125 | 178 | 233 | 342 |

| Model | SHA45A | | SHA58A | SHA65A |
|-----------------|--------|-----------------|-----------------|-----------------|
| Reduction ratio | 1:51 | 1:81 or more | 1:81 or more | 1:81 or more |
| 2 arc-min | 88 | 124 | 273 | 360 |
| 4 arc-min | 205 | 293 | 636 | 876 |
| 6 arc-min | 336 | 483 | 1050 | 1450 |

Torsional rigidity (Speed ratio 11: hollow planetary speed reducer HPF series for precision control)

If a torque is applied to the output unit with the input and casing of the speed reducer are locked, the output unit generates a torsion in proportion to the torque. When the values for torque are gradually changed in sequence from (1) Rated output torque in the positive rotation direction→(2) zero→(3) Rated output torque in the negative rotation direction→(4) zero→(5) Rated output torque in the positive rotation direction, the values follow a loop (1)→(2)→(3)→(4)→(5) (returns to (1)) shown in Fig.1 [torque vs. torsional angle diagram].

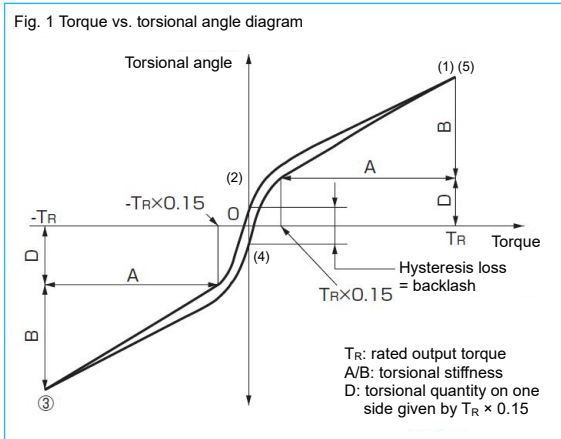
The gradient of the region [Rated output torque] from [0.15 × rated output torque] is small, and the torsional stiffness of the HPF series is the average of this gradient. The gradient of the region [0.15 × rated output torque] from [zero torque] is large. This gradient is caused by semi-partial contact in the meshing region and uneven load distribution from light loads and so forth on the planet gears.

An explanation is provided below on how to calculate the total torsional quantity on one side from a no-load state after a load has been applied by the speed reducer.

$$\theta = D + \frac{T - TL}{A/B}$$

- θ : total torsional quantity
- D: torsional quantity on one side given by rated output torque × 0.15 torque
- T: load torque
- TL: rated output torque × 0.15 torque (= $T_R \times 0.15$)
- A/B: torsional stiffness

The zero torque part widths of (2) and (4) in the figure on the right [torque vs. torsional angle diagram] is called the hysteresis loss. For the HPF series, backlash is defined as hysteresis loss [rated output torque in the negative rotation direction] from [rated output torque in the positive rotation direction]. The HPF series has a backlash of less than 3 minutes (less than 1 minute with special products) with factory settings.



| Item | Model • speed ratio | SHA25A | SHA32A |
|---|----------------------------|--------|--------|
| | | 11 | 11 |
| Backlash | 10 ⁻⁴ rad | 8.7 | 8.7 |
| | arc-min | 3 | 3 |
| Rated torque (T _R) | N·m | 21 | 44 |
| Torsional quantity on one side given by T _R × 0.15 (D) | 10 ⁻⁴ rad | 5.8 | 4.9 |
| | arc-min | 2.0 | 1.7 |
| Torsional stiffness (A/B) | × 10 ⁻⁴ N·m/rad | 5.70 | 11.7 |
| | kgf·m/arc-min | 1.7 | 3.5 |

1-11 Rotation direction

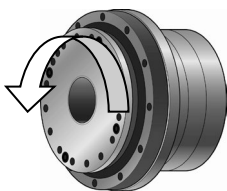
SG/HP type

As a default, the rotation direction is defined as counter-clockwise (CCW) rotation as viewed from the output shaft when a FWD command pulse is given from a driver.

This rotation direction can be changed.

HA-900 = Pr0.01: Rotation direction setting

HA-800 = SP50: Command polarity setting



Counterclockwise rotation direction

SG/HP type setting

| Set value | FWD command pulse | REV command pulse | Setting |
|-----------|----------------------------------|----------------------------------|---------|
| 0 | CCW (counterclockwise) direction | CW (clockwise) direction | Default |
| 1 | CW (clockwise) direction | CCW (counterclockwise) direction | |

CG type

As a default, the rotation direction is defined as clockwise (CW) rotation as viewed from the output shaft when a FWD command pulse is given from a driver.

This rotation direction can be changed.

HA-900 = Pr0.01: Rotation direction setting

HA-800 = SP50: Command polarity setting

CG type setting

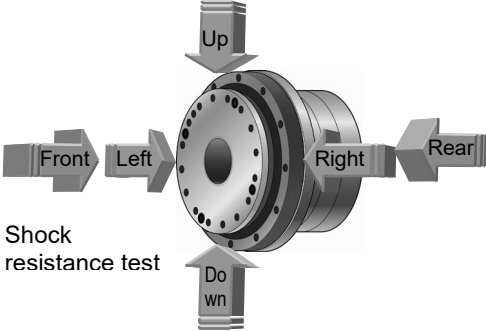
| Set value | FWD command pulse | REV command pulse | Setting |
|-----------|----------------------------------|----------------------------------|---------|
| 0 | CW (clockwise) direction | CCW (counterclockwise) direction | Default |
| 1 | CCW (counterclockwise) direction | CW (clockwise) direction | |

1-12 Shock resistance

The shock resistance of the actuator is as follows, and this value is the same in up/down, left/right and front/rear directions:

Impact acceleration: 300 m/s²

In our shock resistance test, the actuator is tested 3 times in each direction. Actuator operation is not guaranteed in applications where impact exceeding the above value is constantly applied.

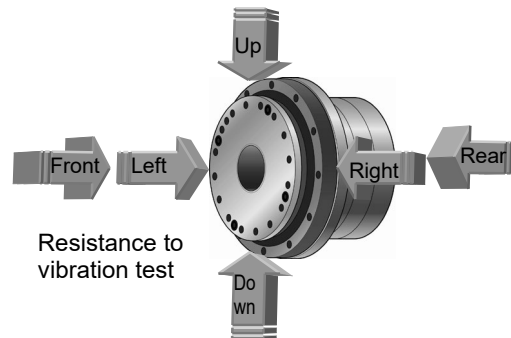


1-13 Resistance to vibration

The resistance to vibration of the actuator is as follows, and this value is the same in up/down, left/right and front/rear directions:

Vibration acceleration: 25 m/s^2 (frequency: 10 to 400 Hz)

In our test, the actuator is tested for 2 hours in each direction at a vibration frequency sweep period of 10 minutes.



1-14 Operable range

The graph on the next page indicates the operable range when a SHA series actuator is selected. For details, refer to [Chapter 2 Selection guidelines].

1. Continuous motion range

The range allows continuous operation for the actuator.

2. 50 % duty motion range

This range indicates the torque rotation speed which is operable in the 50 % duty operation (the ratio of operating time and delay time is 50:50).

Limit the operation cycle to a period of several minutes, and keep it within a range where the overload alarm of the driver does not sound.

3. Motion range during acceleration and deceleration

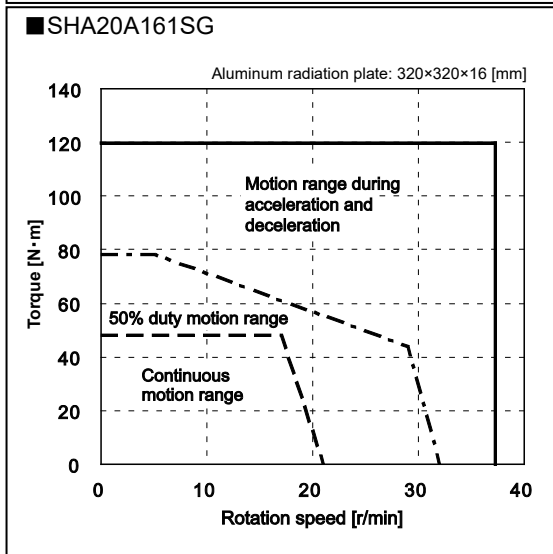
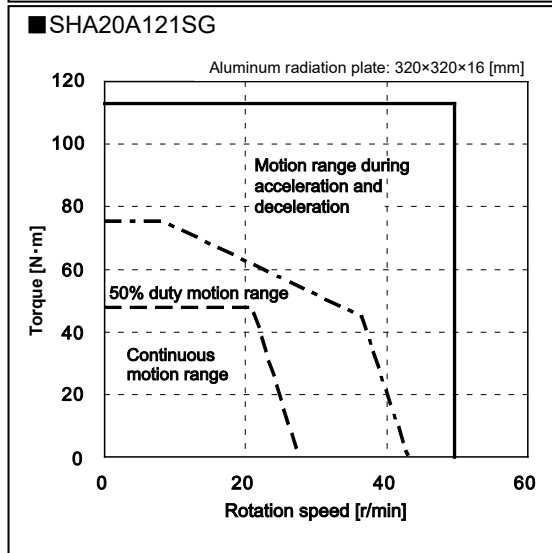
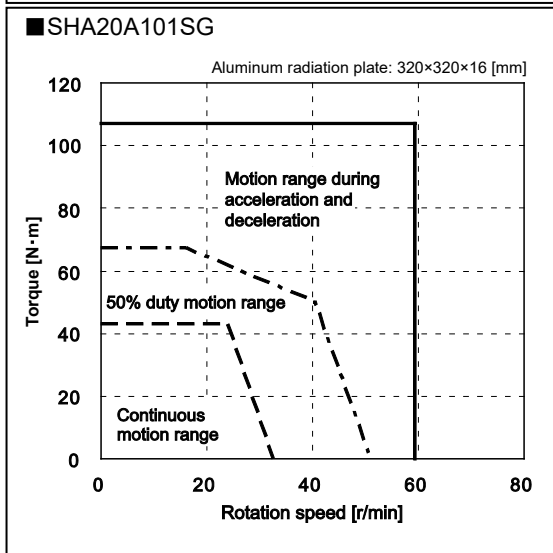
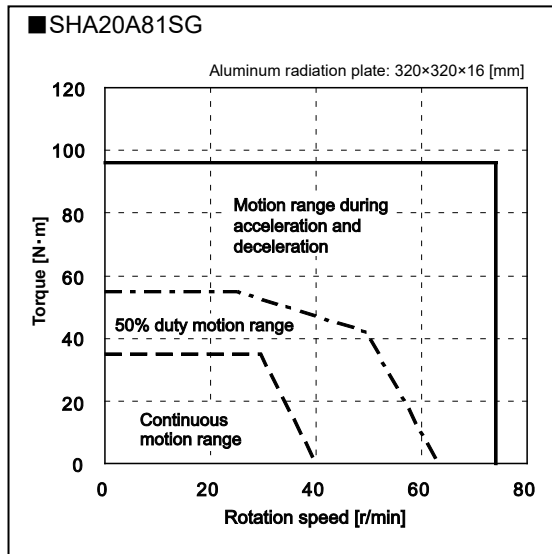
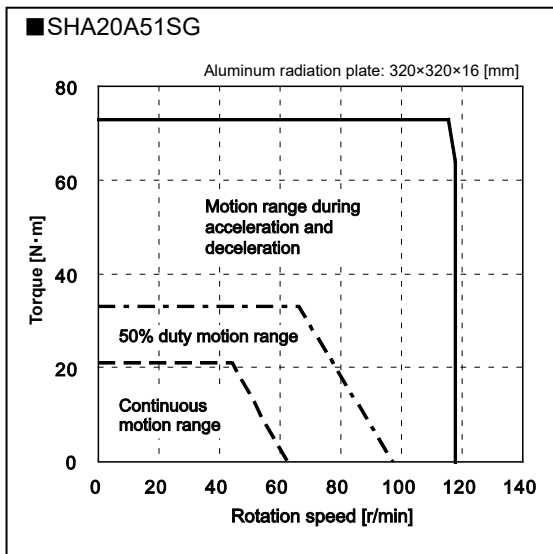
This range indicates the torque rotation speed which is operable momentarily. The range allows instantaneous operation like acceleration and deceleration, usually.

The continuous and 50 % duty motion ranges in each graph are measured on the condition where the radiation plate specified in the graph is installed.

Caution

- When using the product at constant load or in one direction continuously, it may cause lubrication problems. Contact our sales office if the product will be used in this way.
-

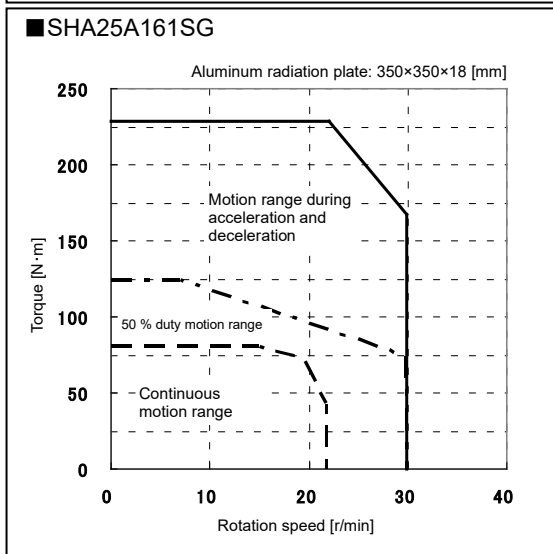
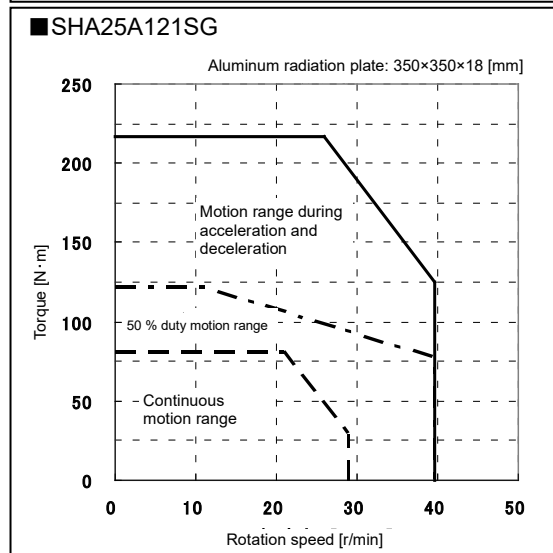
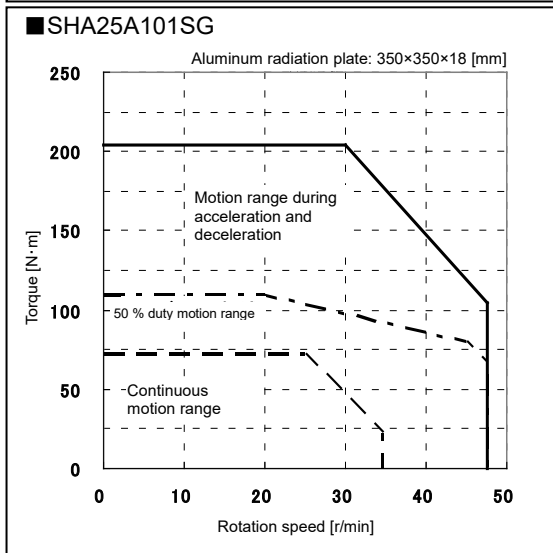
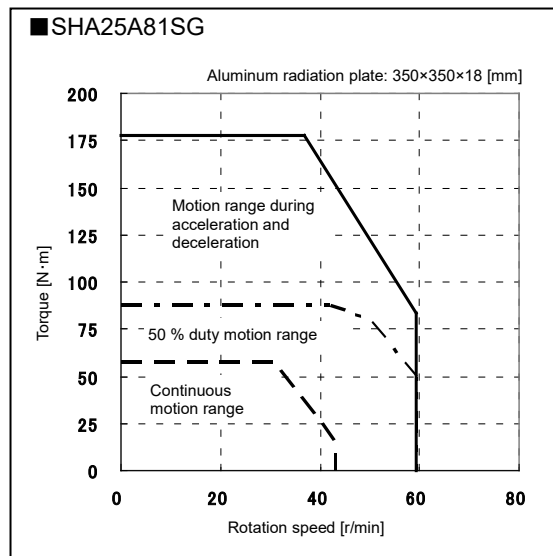
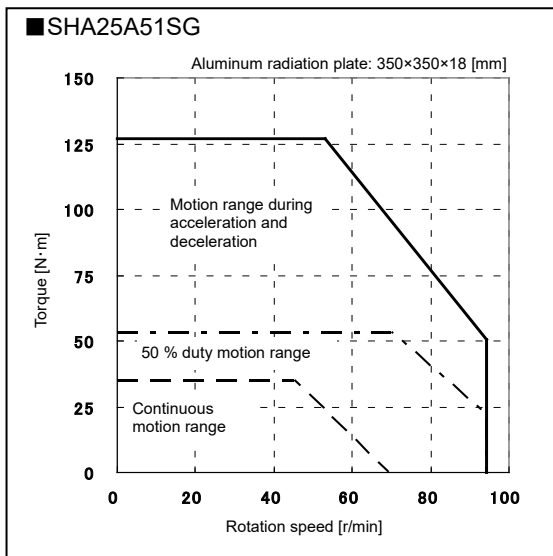
SG type
SHA20A



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

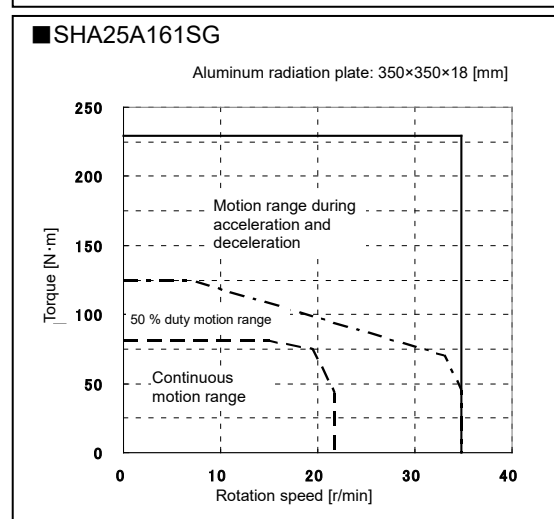
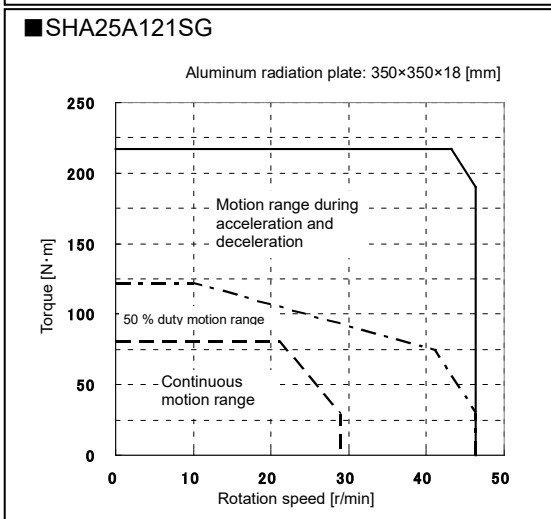
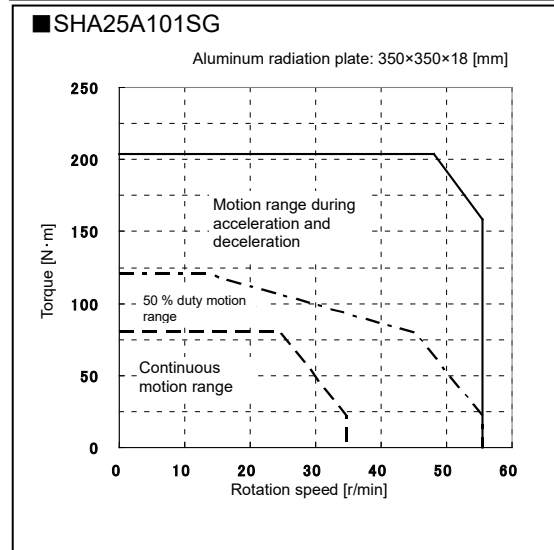
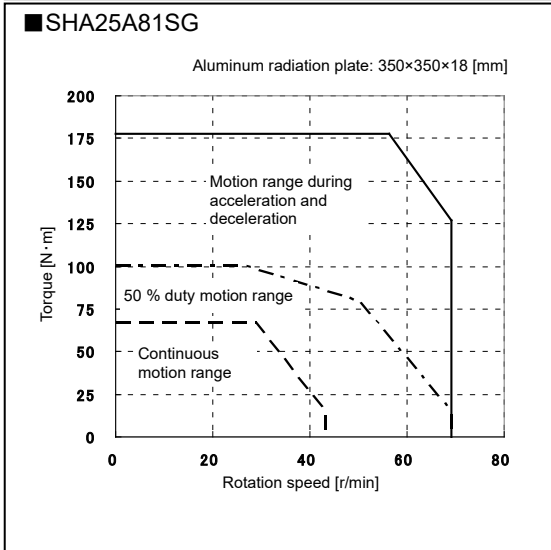
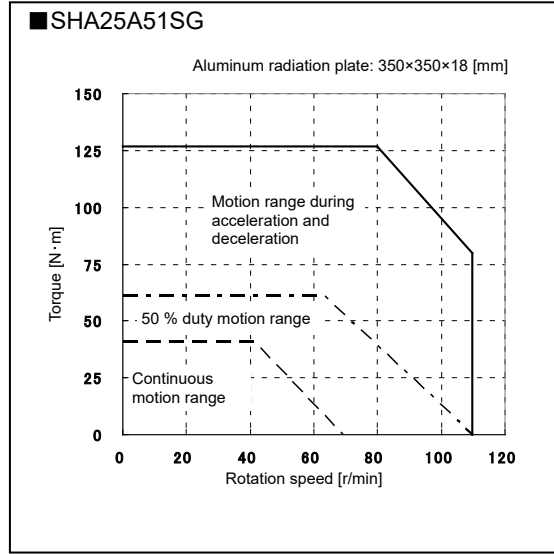
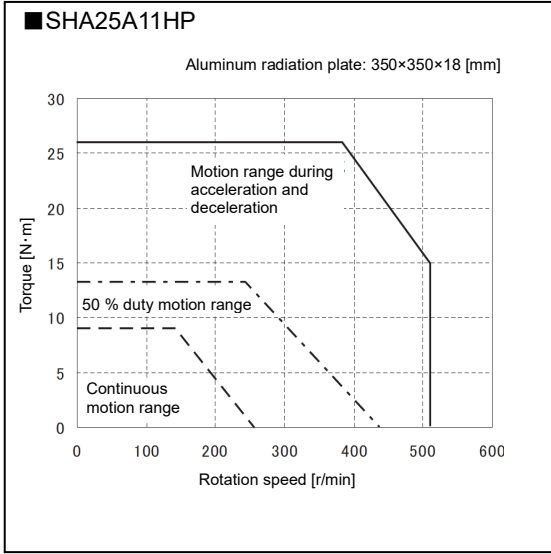
SG type
SHA25A (Specifications for motor input voltage of 100 V)



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
Note2: The graph shows typical values of single phase 100 VAC.

SG/HP type

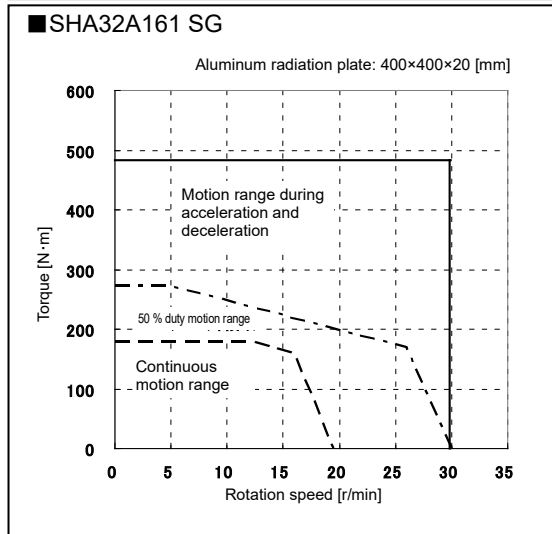
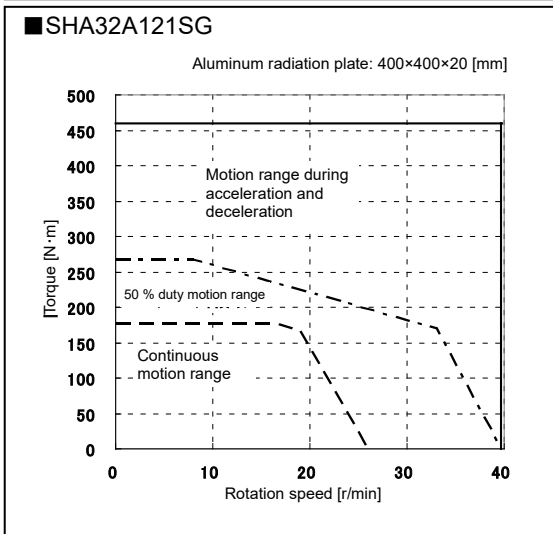
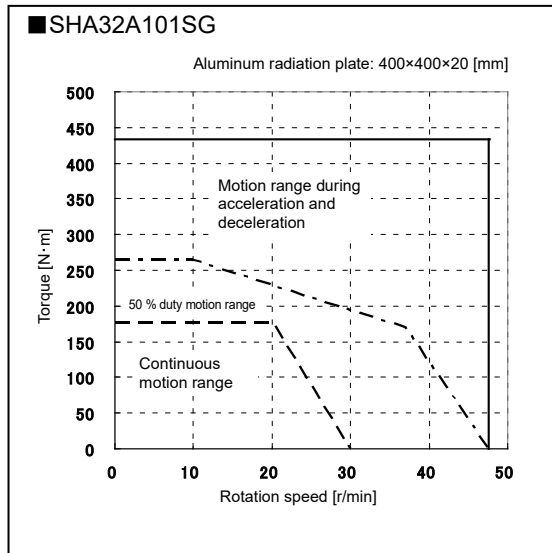
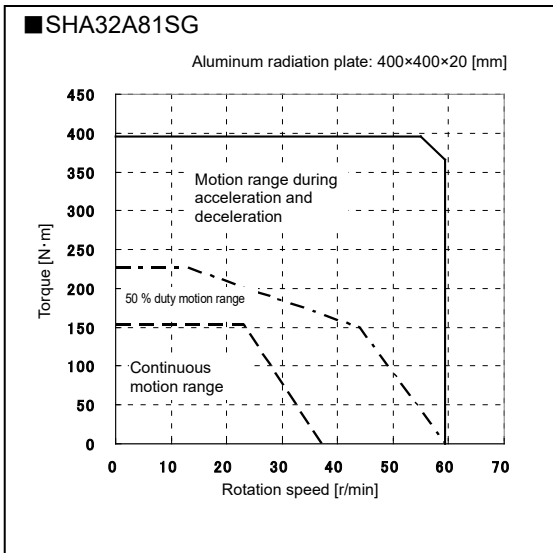
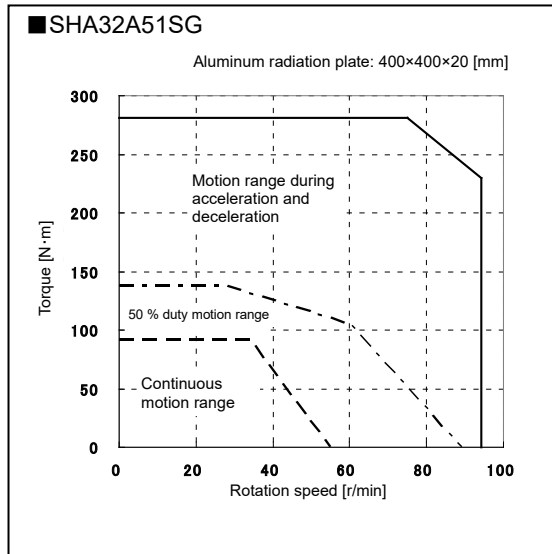
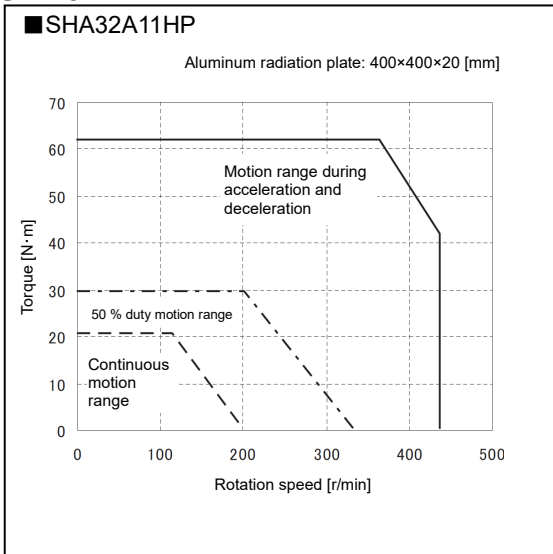
SHA25A (Specifications for motor input voltage of 200 V)



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

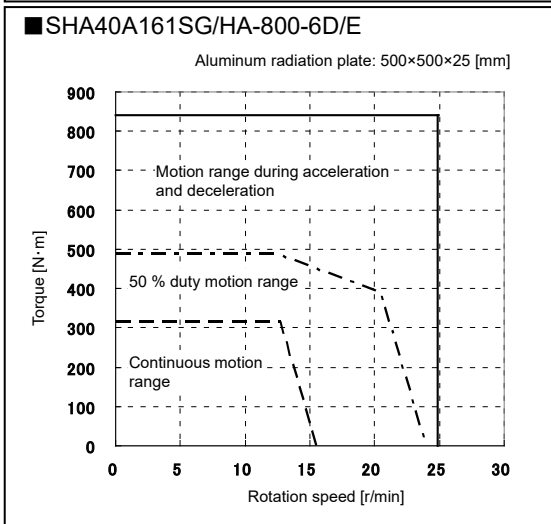
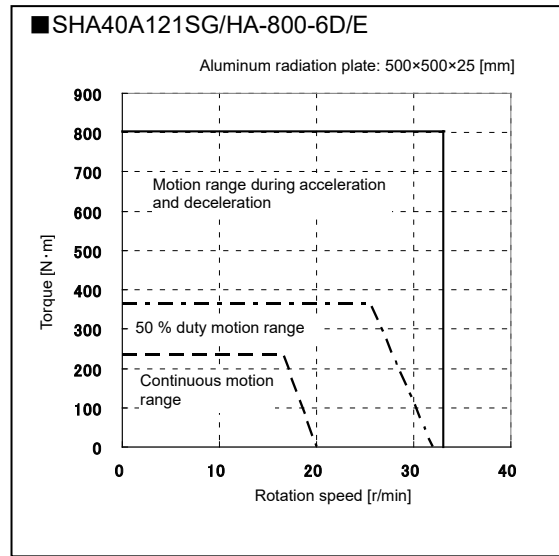
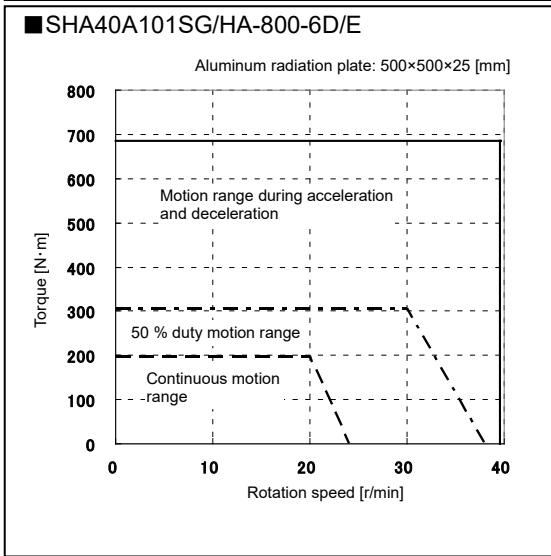
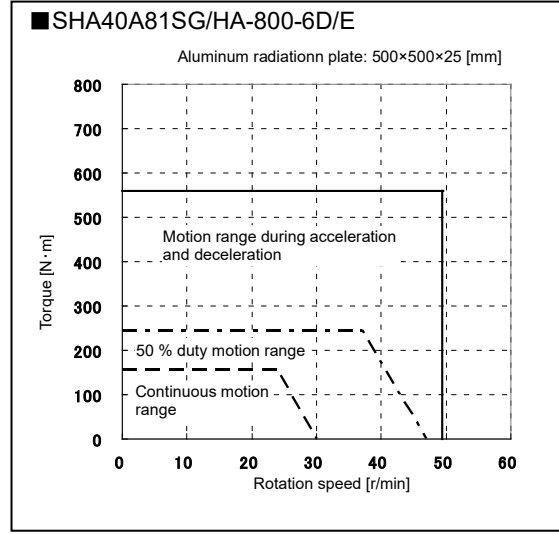
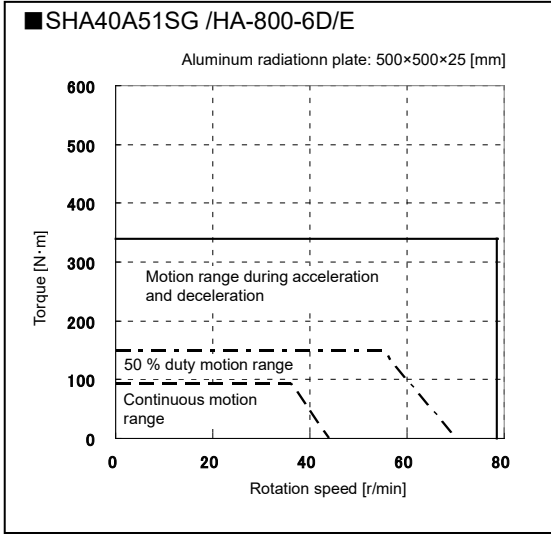
Note2: The graph shows typical values of 3-phase 200 VAC.

**SG/HP type
SHA32A**



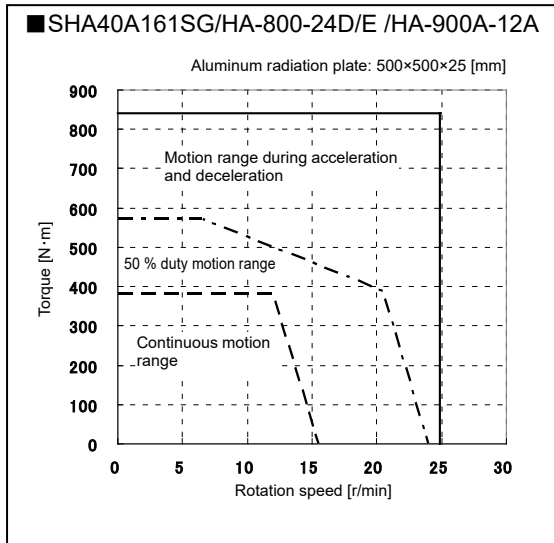
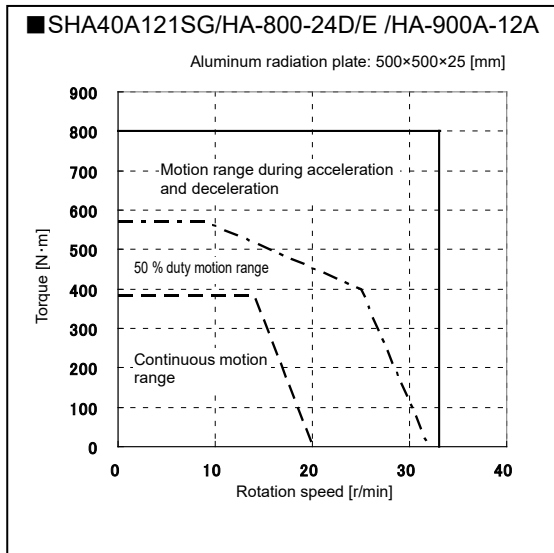
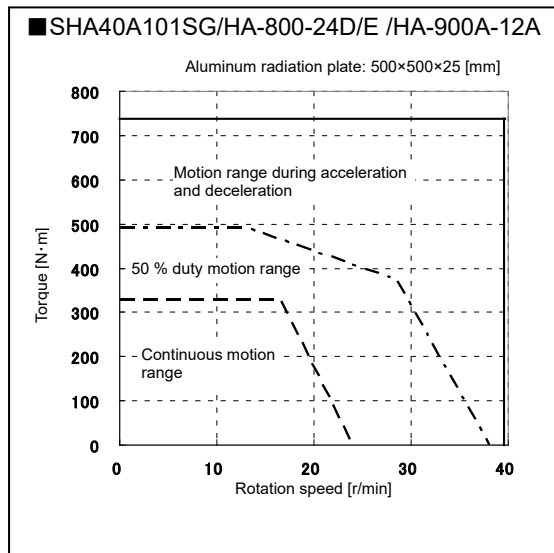
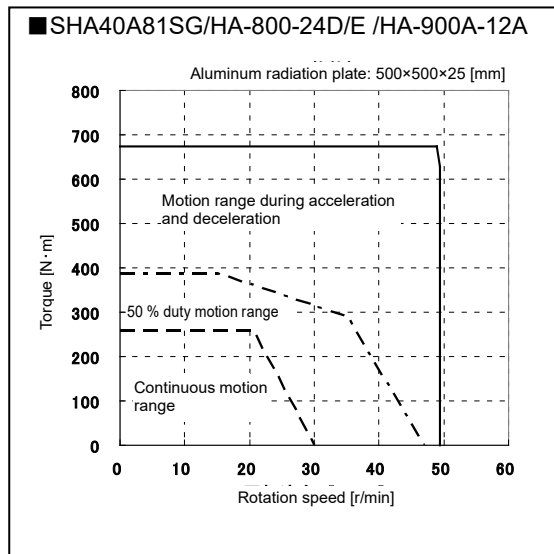
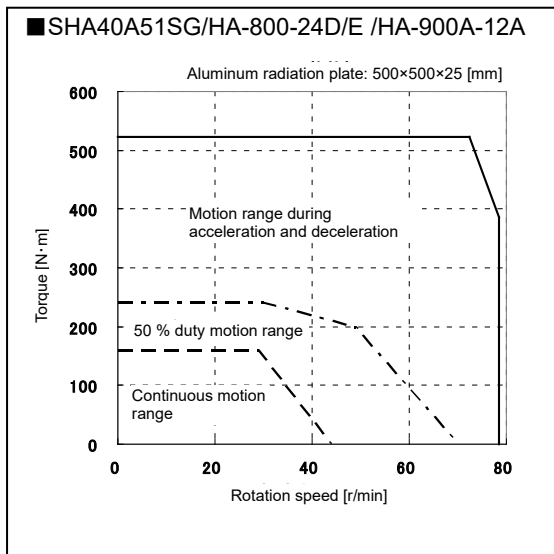
Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
 Note2: The graph shows typical values of 3-phase 200 VAC.

SG type
SHA40A



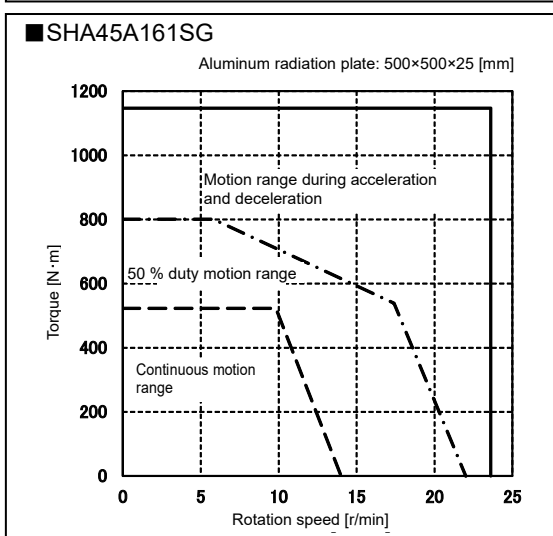
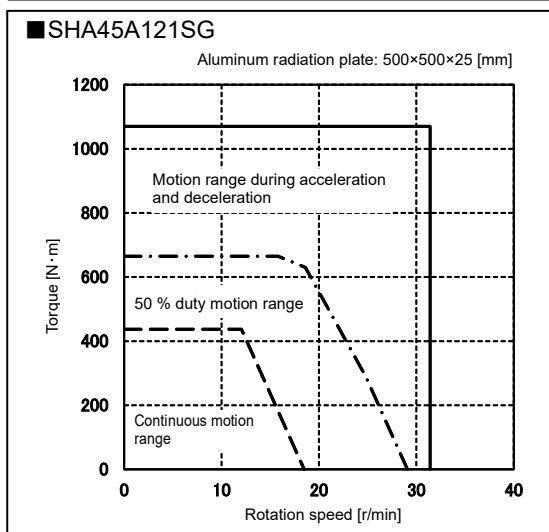
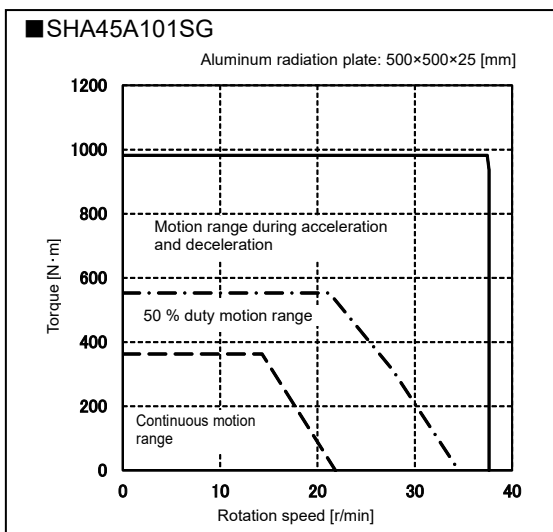
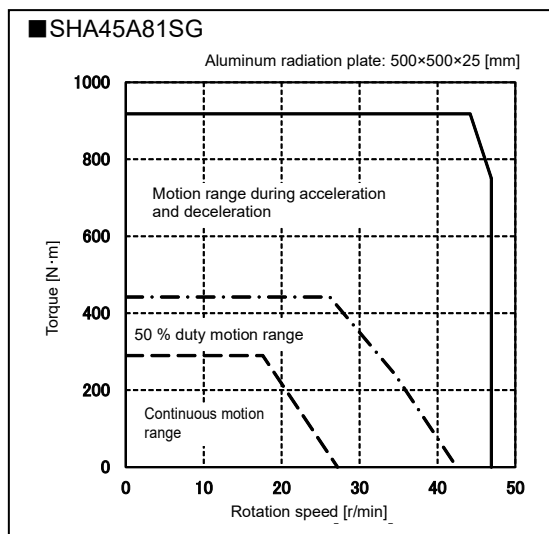
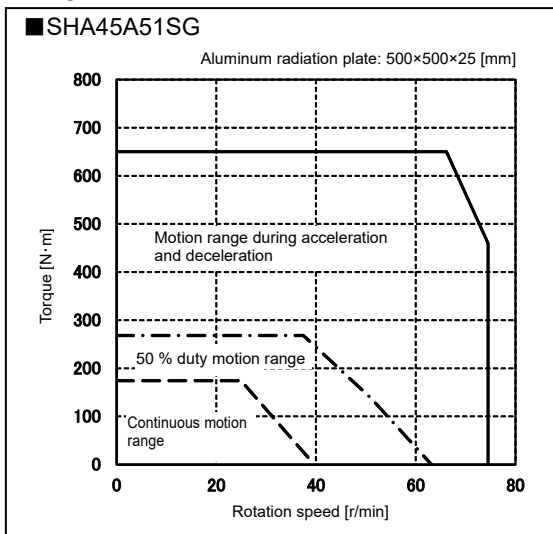
Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
 Note2: The graph shows typical values of 3-phase 200 VAC.

**SG type
SHA40**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
 Note2: The graph shows typical values of 3-phase 200 VAC.

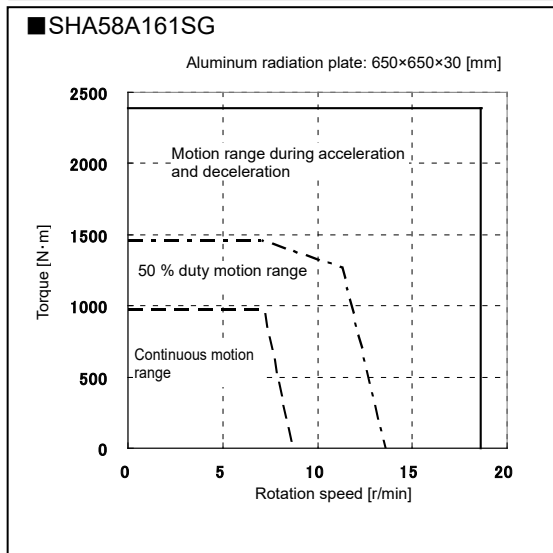
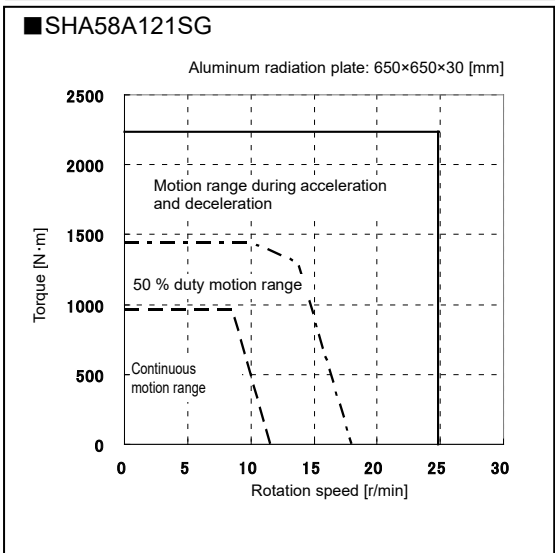
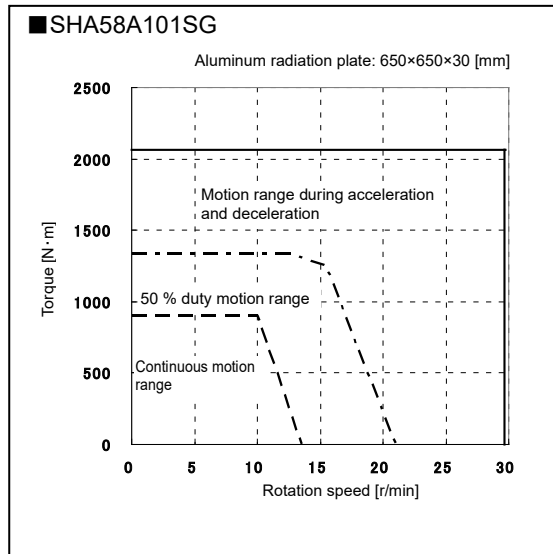
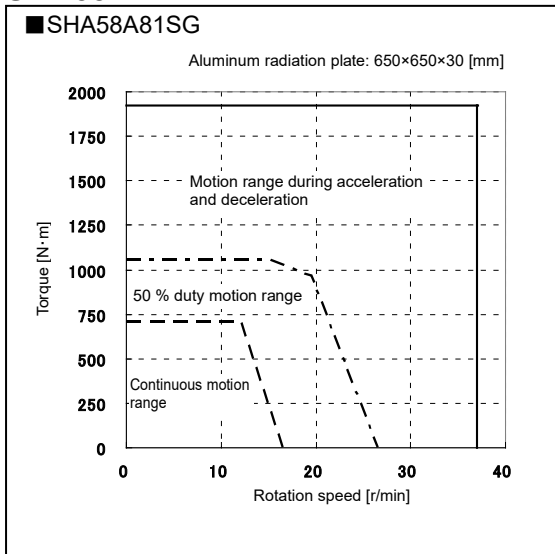
**SG type
SHA45A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

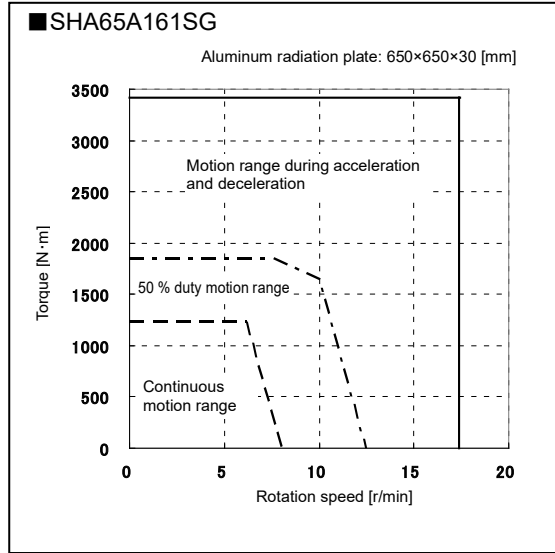
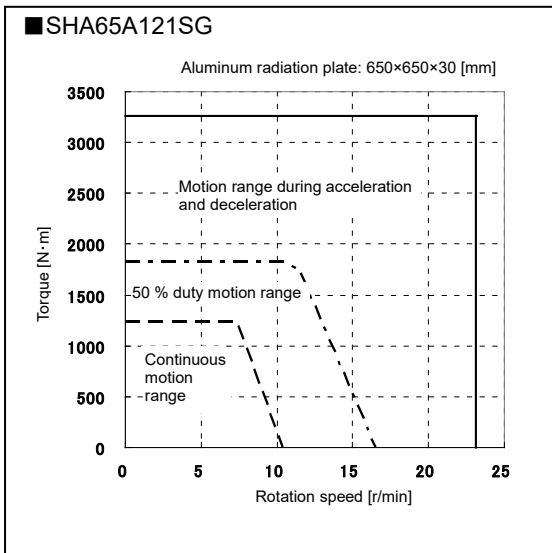
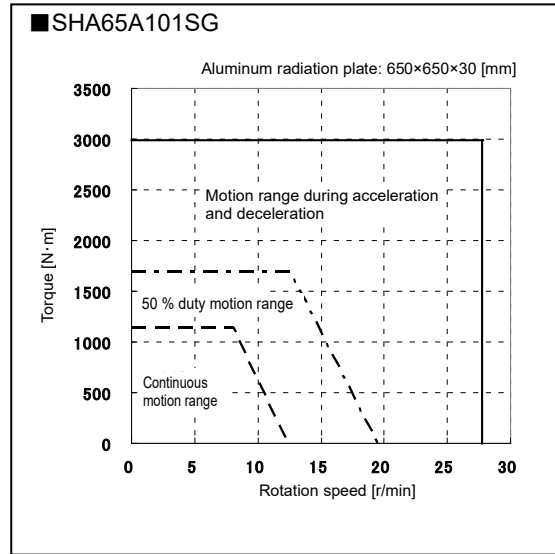
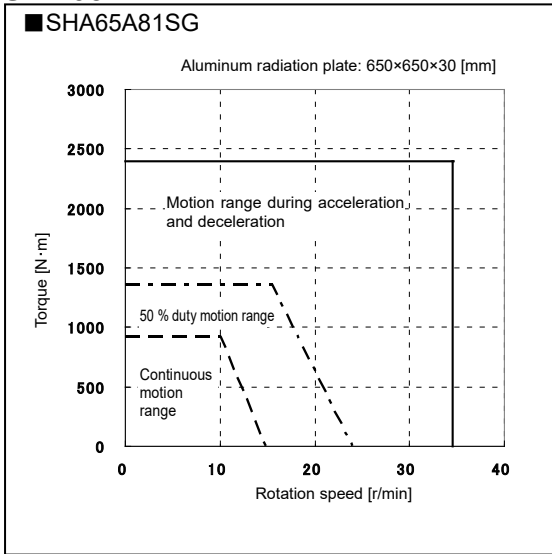
**SG type
SHA58A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

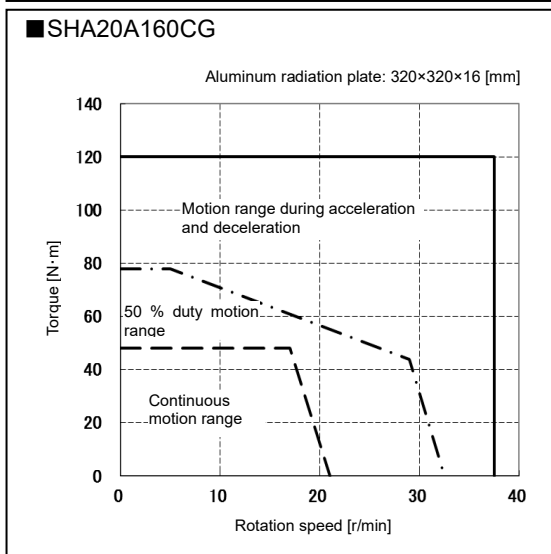
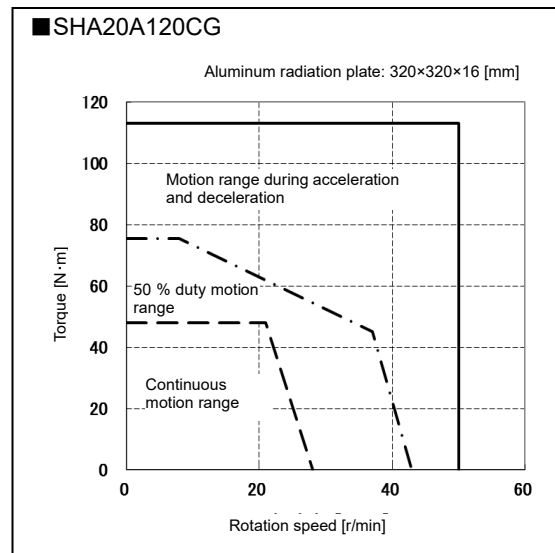
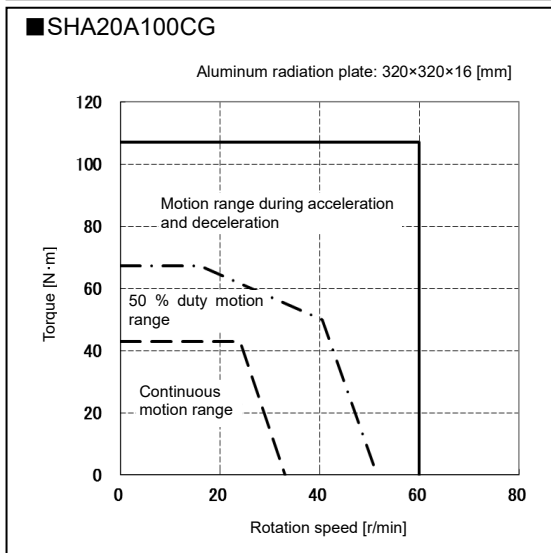
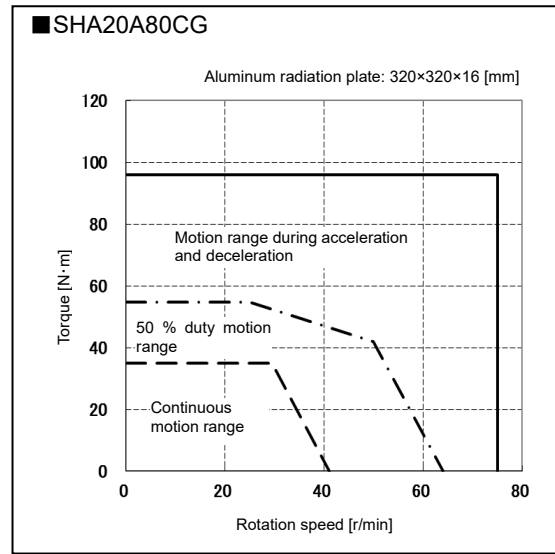
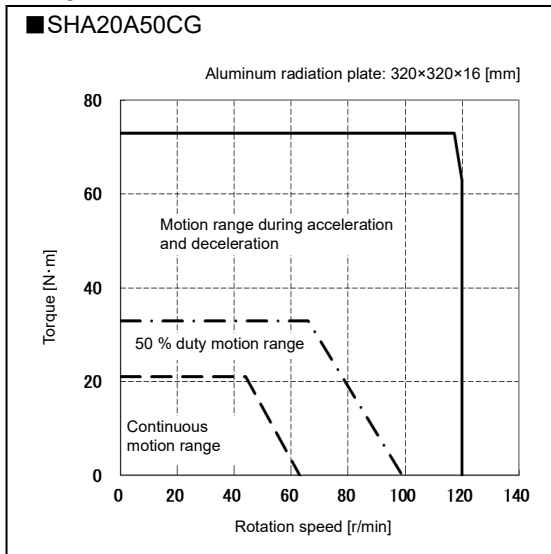
**SG type
SHA65A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

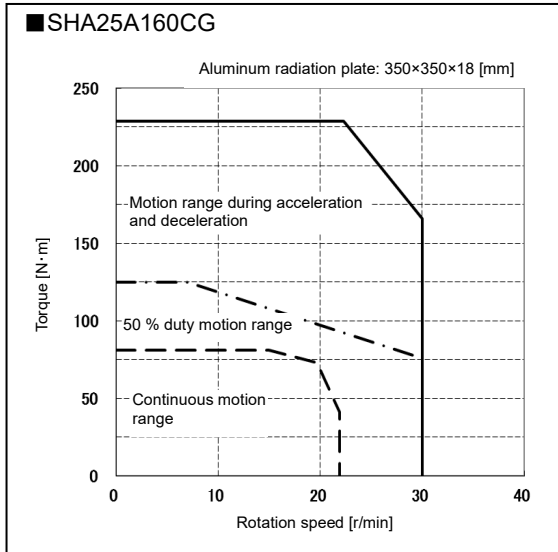
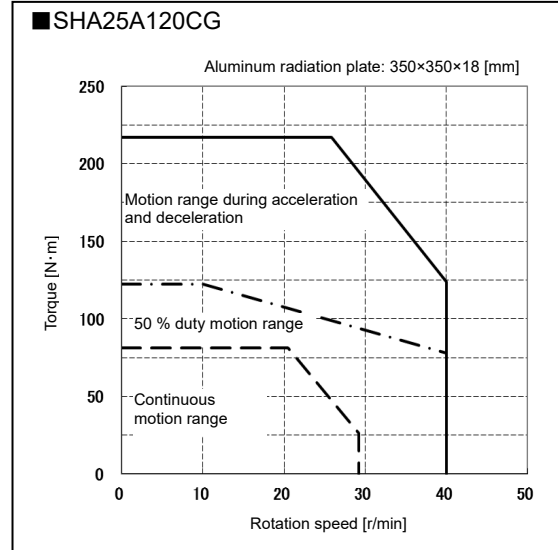
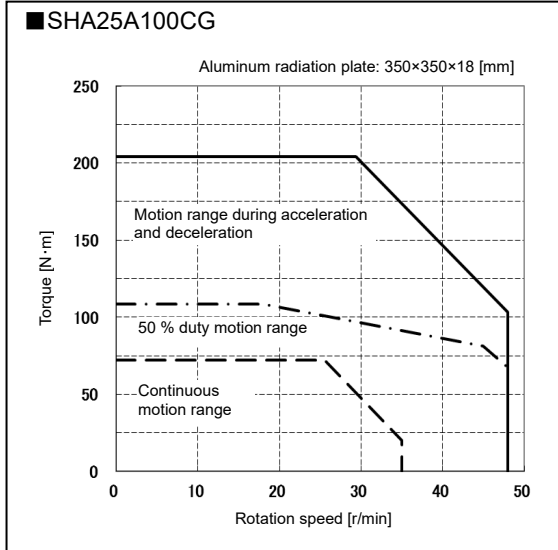
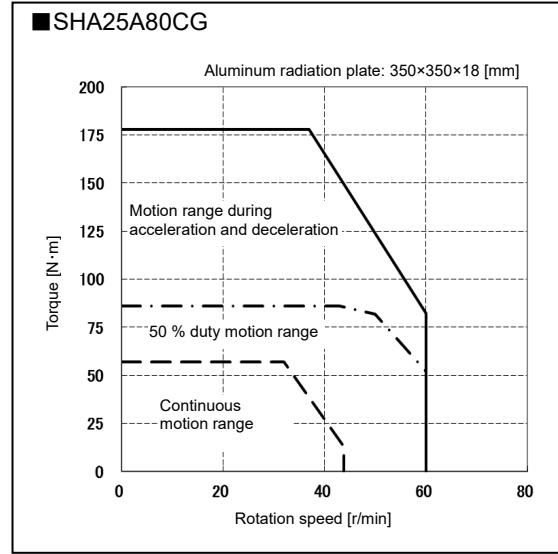
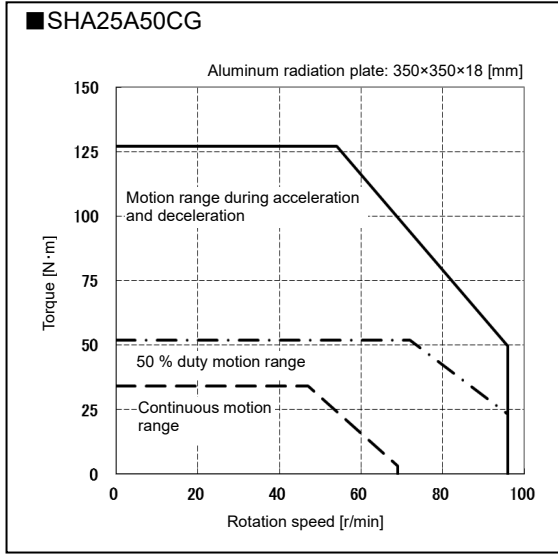
**CG type
SHA20A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

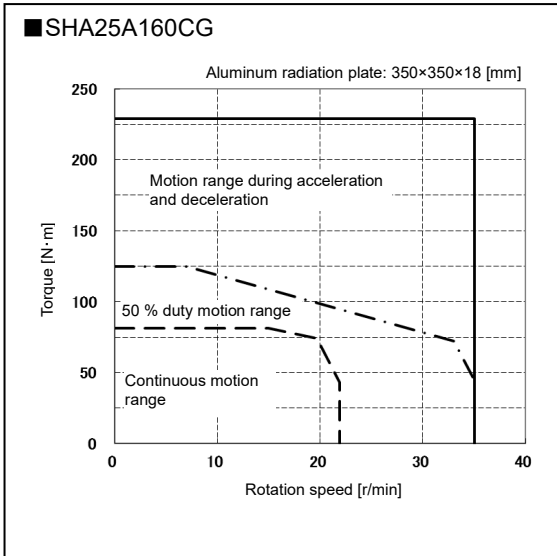
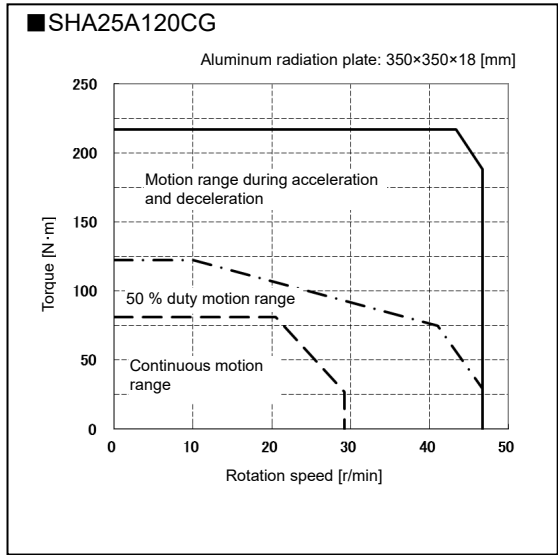
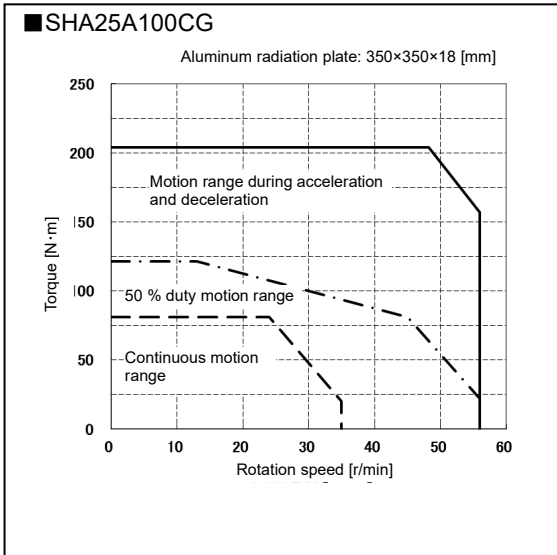
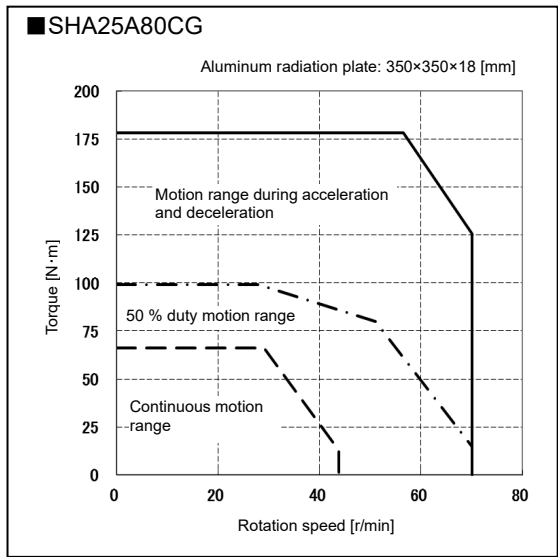
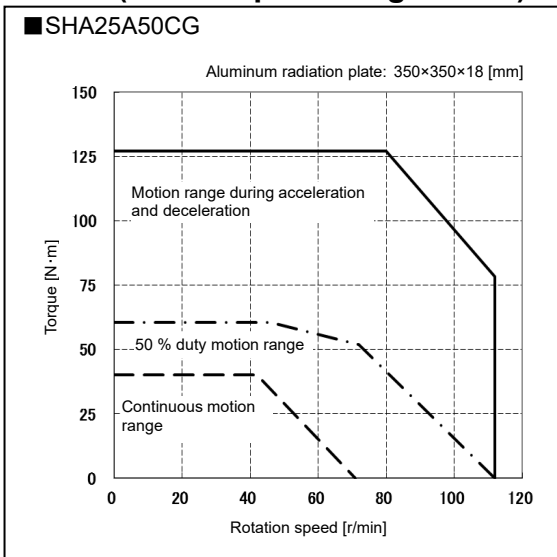
CG type
SHA25A (Motor input voltage 100 V)



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

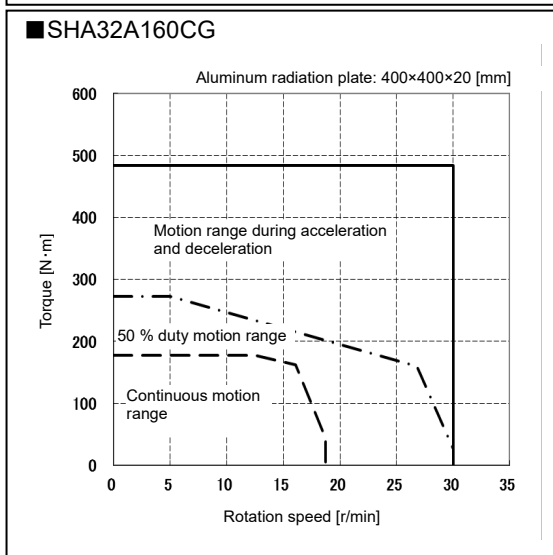
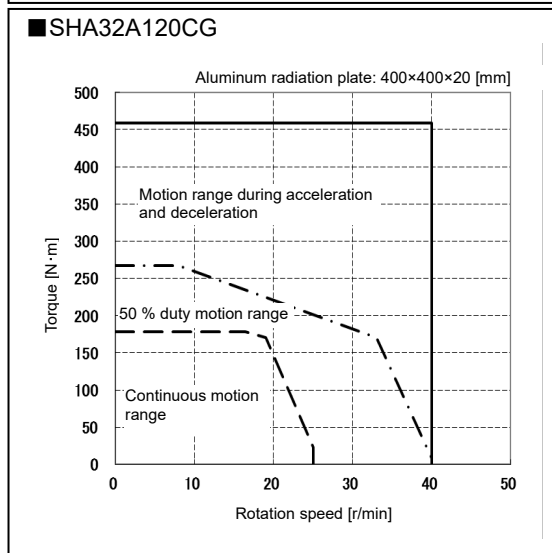
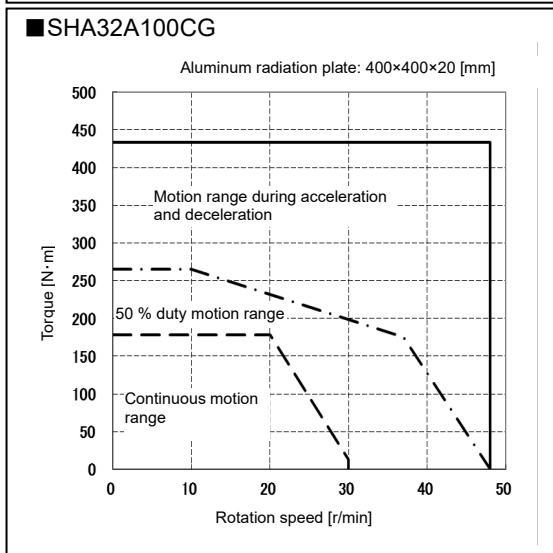
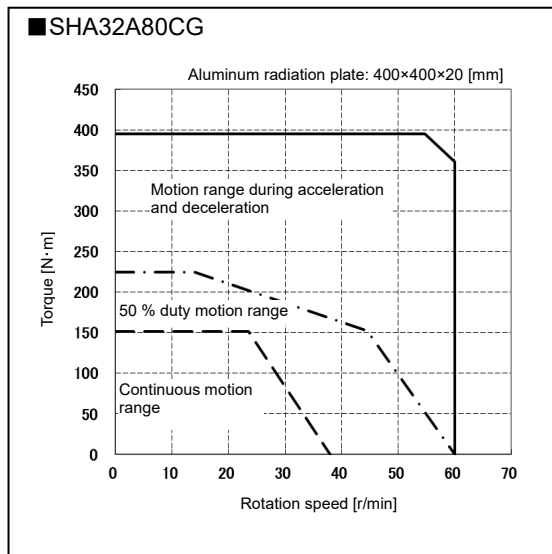
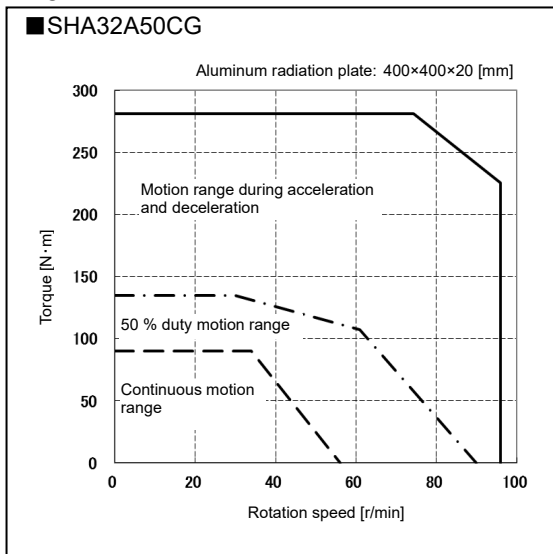
Note2: The graph shows typical values of single phase 100 VAC.

CG type
SHA25A (Motor input voltage 200 V)



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
Note2: The graph shows typical values of 3-phase 200 VAC.

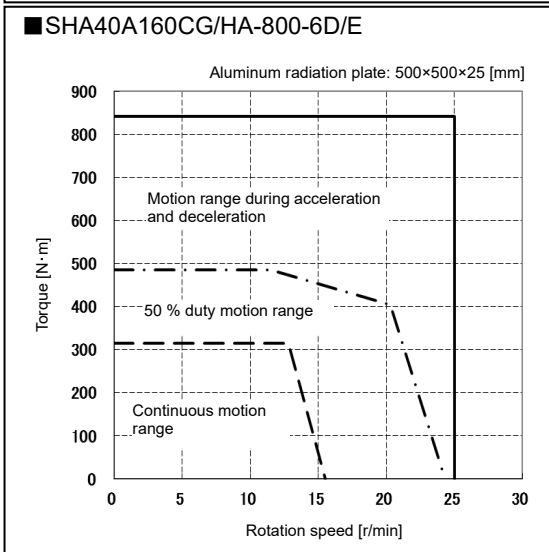
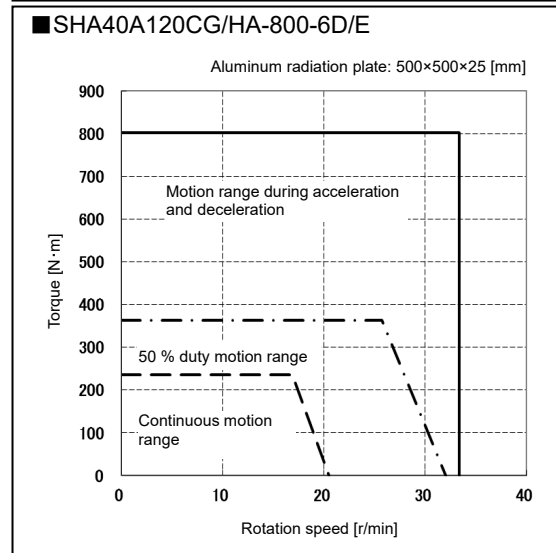
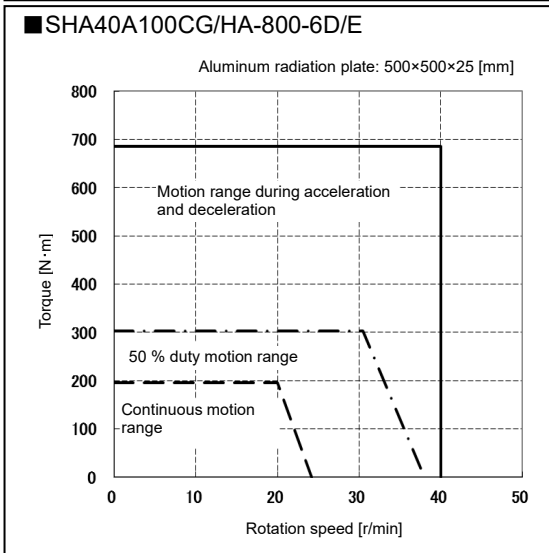
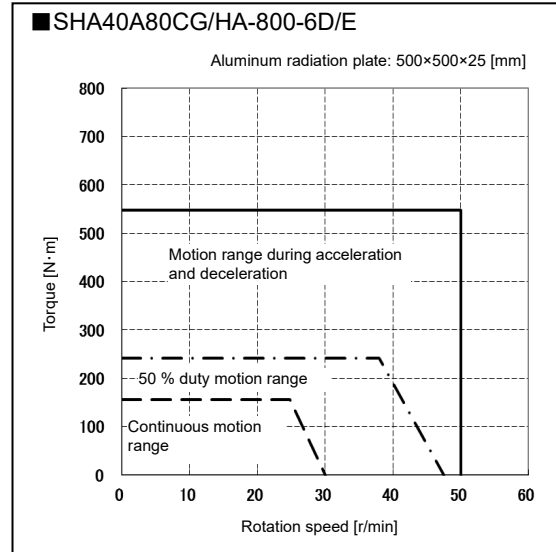
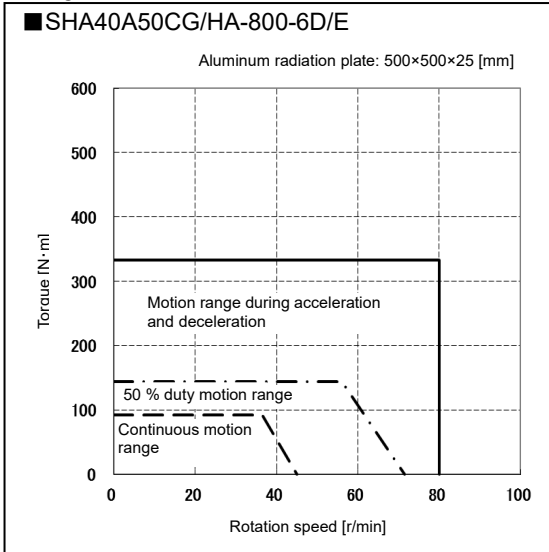
**CG type
SHA32A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

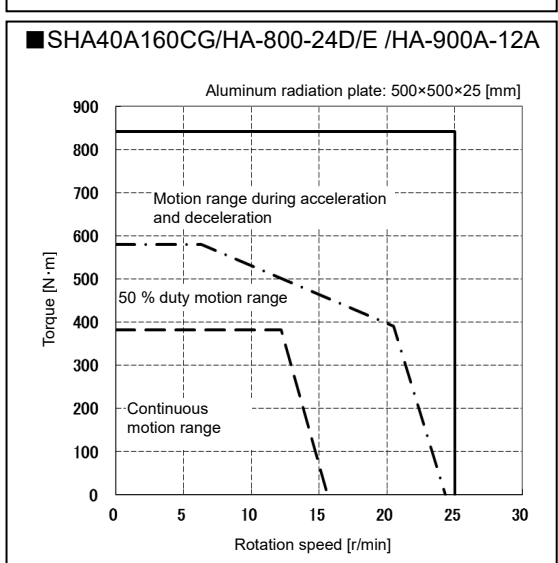
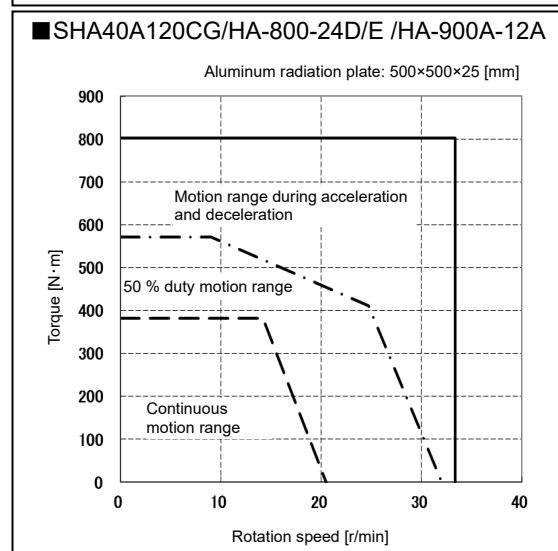
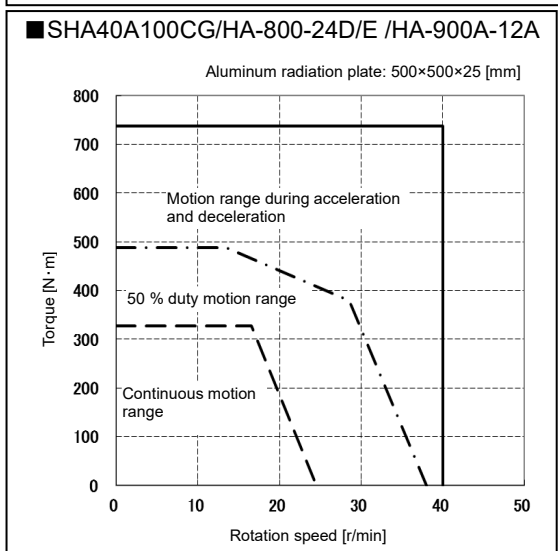
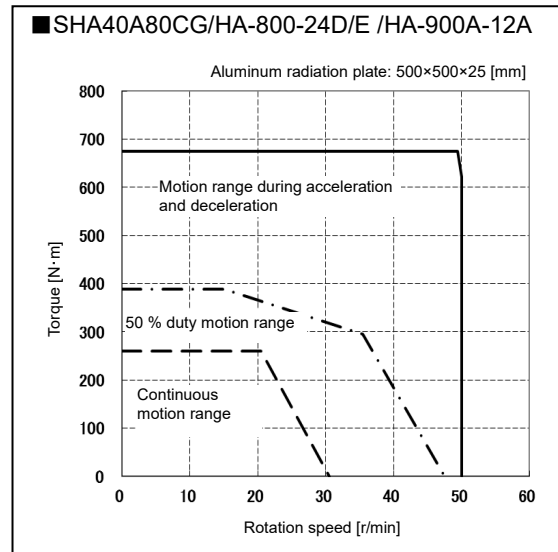
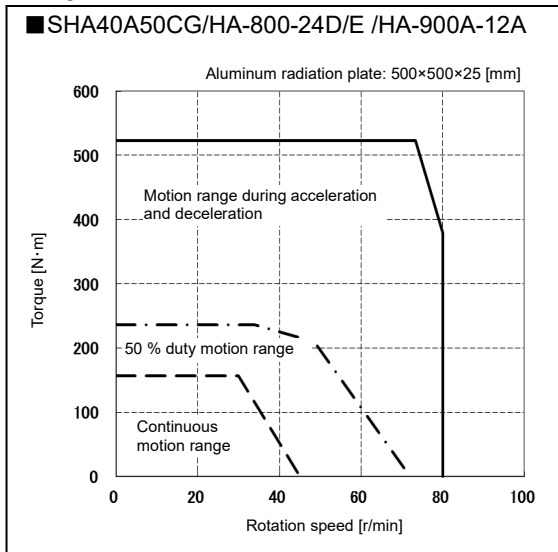
**CG type
SHA40A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.

Note2: The graph shows typical values of 3-phase 200 VAC.

**CG type
SHA40A**



Note1: Values in the continuous motion range and 50 % duty range are measured on the condition where an aluminum radiation plate of the dimensions specified in the upper right of the graph is installed.
 Note2: The graph shows typical values of 3-phase 200 VAC.

1-15 Cable specifications

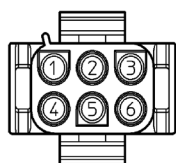
The following tables show specifications of the motor and encoder cables of the SHA series actuators.

Motor cable specifications

- Model Nos 20, 25, 32, 40, 45

| Pin number | Color | Name | |
|------------|--------------|---------------|---------------|
| | | Without brake | With brake |
| 1 | Red | Motor phase-U | Motor phase-U |
| 2 | White | Motor phase-V | Motor phase-V |
| 3 | Black | Motor phase-W | Motor phase-W |
| 4 | Green/yellow | PE | PE |
| 5 | Blue | No connection | Brake |
| 6 | Yellow | No connection | Brake |

- Connector pin layout



Connector model: 350715-1

Pin model:

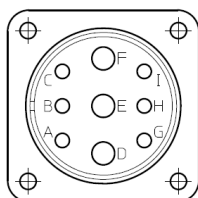
| | Model Nos 20, 25 | Model Nos 32, 40 |
|------------------|---------------------|---------------------|
| Motor UVW | 350690-1 | 350547-1 |
| Brake | 350690-1 | 350690-1 |
| Motor PE | 350669-1 | 350669-1 |

TE Connectivity (by AMP)

- Model Nos 58, 65

| Pin number | Name | | Color (Extension cables) |
|------------|---------------|---------------|-----------------------------|
| | Without brake | With brake | |
| A | No connection | Brake | Blue |
| B | No connection | Brake | Yellow |
| C | No connection | No connection | — |
| D | Motor phase-U | Motor phase-U | Red |
| E | Motor phase-V | Motor phase-V | White |
| F | Motor phase-W | Motor phase-W | Black |
| G | PE | PE | Green/yellow |
| H | PE | PE | — |
| I | No connection | No connection | — |

- Connector pin layout



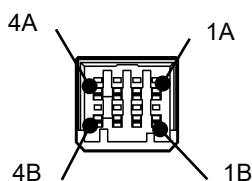
Connector model: CE05-2A24-11PGHS-D (by DDK)

Encoder cable specifications

- Model Nos 20, 25, 32, 40, 45

| Pin number | Color | Signal name | Remarks |
|------------|--------|---------------|---------------------------------------|
| 1A | Red | Vcc | Power supply input +5 V |
| 1B | Black | GND (Vcc) | Power supply input 0 V (GND) |
| 2A | Yellow | SD + | Serial signal differential output (+) |
| 2B | Blue | SD - | Serial signal differential output (-) |
| 3A | — | No connection | |
| 3B | Shield | FG | |
| 4A | Orange | Vbat | Battery + |
| 4B | Gray | GND (bat) | Battery - (GND) |

- Connector pin layout

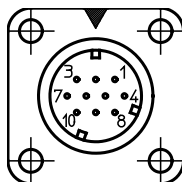


Connector model: 1-1903130-4
 Pin model: 1903111-2, 1903116-2 or 1903117-2
 TE Connectivity (by AMP)

- Model Nos 58, 65

| Pin number | Signal name | Remarks |
|------------|---------------|---------------------------------------|
| 1 | Vbat | Battery + |
| 2 | GND (bat) | Battery - (GND) |
| 3 | No connection | |
| 4 | Vcc | Power supply input +5 V |
| 5 | GND (Vcc) | Power supply input 0 V (GND) |
| 6 | No connection | |
| 7 | No connection | |
| 8 | SD + | Serial signal differential output (+) |
| 9 | SD - | Serial signal differential output (-) |
| 10 | FG | |

- Connector pin layout



Connector model: CM10-R10P(D3)-01 (by DDK)

Chapter 2

Selection guidelines

This chapter explains how to select a proper SHA series actuator.

| | | |
|-----|--------------------------------------|------|
| 2-1 | SHA series selection | 2-1 |
| 2-2 | Change in load inertia moment | 2-5 |
| 2-3 | Verifying and examining load weights | 2-6 |
| 2-4 | Examining operating status | 2-10 |

2-1 SHA series selection

2

Selection guidelines

Allowable load inertia moment

To achieve high accuracy and performance, select a SHA series actuator where the allowable load inertia moment specified for the applicable model No. is not exceeded.

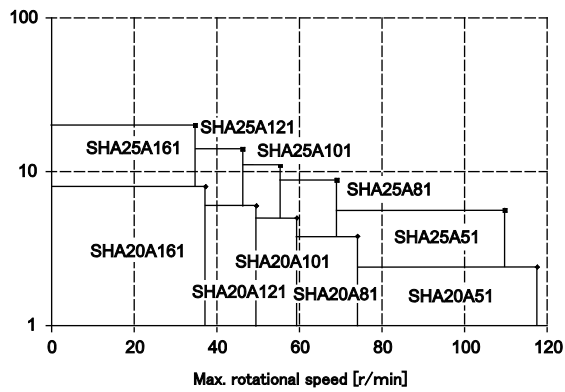
Note that the allowable values in the table below should be referenced if you wish to shorten the transient vibration period during positioning or operate the actuator at a constant speed in a stable manner.

The operation is possible with the allowable value exceeded if the actuator is accelerated/decelerated gradually, commands given from the host to the servo driver are adjusted, or the servo driver's vibration suppression function is used.

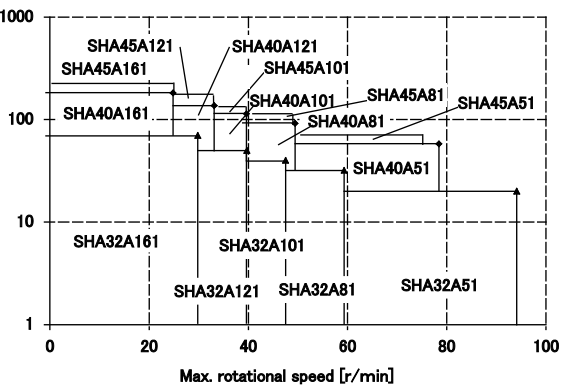
Refer to [A-2 Calculating inertia moment] (P5-3) for the calculation of inertia moment.

SG type

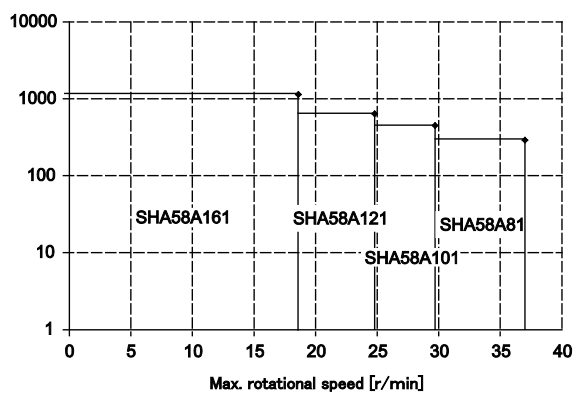
[kg·m²] Allowable load inertia moment



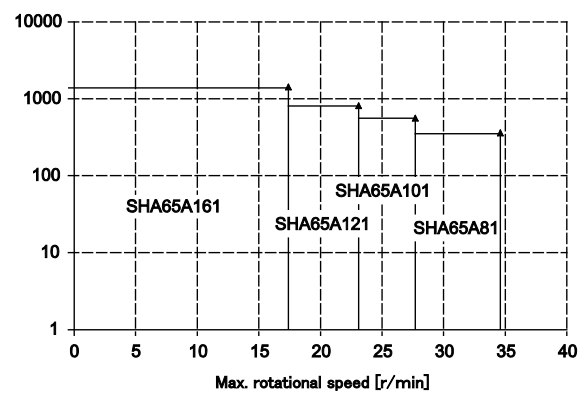
[kg·m²] Allowable load inertia moment



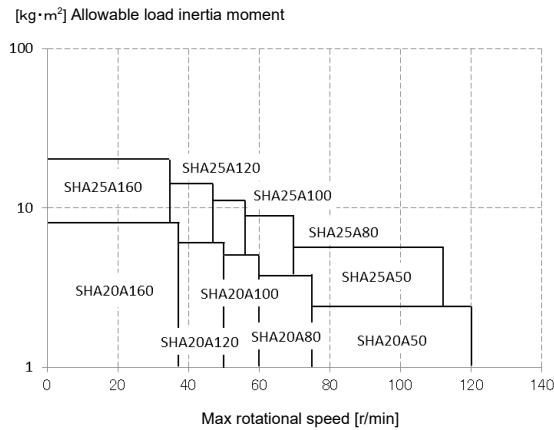
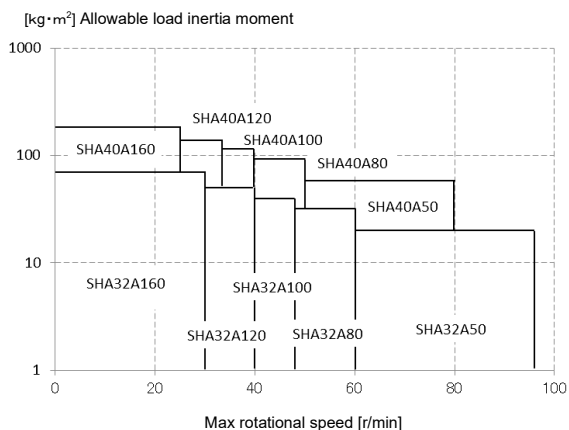
[kg·m²] Allowable load inertia moment



[kg·m²] Allowable load inertia moment



CG type



When temporarily selecting an actuator, make certain that the inertia moment and max. rotational speed do not exceed the allowable values shown in the table on the following page.

When a load generating a large inertia moment is operated frequently, a greater regenerative energy will be produced during braking. If the produced regenerative energy exceeds the absorption capacity of the built-in regenerative resistor of the servo driver, an additional regenerative resistor must be connected externally to the driver. For details, refer to the manual of your driver.

SG/HP type

| Actuator model | | SHA20A | | | | |
|---|-----------------------|--------|------|-------|-------|-------|
| | | 51 | 81 | 101 | 121 | 161 |
| Reduction ratio | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Max. rotational speed | r/min | 117.6 | 74.1 | 59.4 | 49.6 | 37.3 |
| Actuator inertia moment (without brake) | kg·m ² | 0.23 | 0.58 | 0.91 | 1.3 | 2.3 |
| | kgf·cm·s ² | 2.4 | 6.0 | 9.3 | 13 | 24 |
| Actuator inertia moment (with brake) | kg·m ² | 0.26 | 0.65 | 1.0 | 1.4 | 2.6 |
| | kgf·cm·s ² | 2.6 | 6.6 | 10 | 15 | 26 |
| Allowable load inertia moment | kg·m ² | 2.4 | 3.8 | 4.8 | 5.8 | 7.7 |
| | kgf·cm·s ² | 25 | 39 | 49 | 59 | 78 |

| Actuator model | | SHA25A | | | | | |
|---|-----------------------|--------|-------|------|-------|-------|-------|
| | | 11 | 51 | 81 | 101 | 121 | 161 |
| Reduction ratio | | 1:11 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Max. rotational speed | r/min | 509.1 | 109.8 | 69.1 | 55.4 | 46.3 | 34.8 |
| Actuator inertia moment (without brake) | kg·m ² | 0.029 | 0.56 | 1.4 | 2.2 | 3.2 | 5.6 |
| | kgf·cm·s ² | 0.30 | 5.7 | 14 | 22 | 32 | 57 |
| Actuator inertia moment (with brake) | kg·m ² | 0.034 | 0.66 | 1.7 | 2.6 | 3.7 | 6.6 |
| | kgf·cm·s ² | 0.35 | 6.7 | 17 | 26 | 38 | 67 |
| Allowable load inertia moment | kg·m ² | 0.32 | 5.6 | 8.8 | 11 | 14 | 20 |
| | kgf·cm·s ² | 3.3 | 57 | 90 | 112 | 144 | 201 |

| Actuator model | | SHA32A | | | | | |
|---|-----------------------|--------|------|------|-------|-------|-------|
| | | 11 | 51 | 81 | 101 | 121 | 161 |
| Reduction ratio | | 1:11 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Max. rotational speed | r/min | 436.4 | 94.1 | 59.3 | 47.5 | 39.7 | 29.8 |
| Actuator inertia moment (without brake) | kg·m ² | 0.091 | 2.0 | 5.1 | 8.0 | 11 | 20 |
| | kgf·cm·s ² | 0.93 | 21 | 52 | 81 | 117 | 207 |
| Actuator inertia moment (with brake) | kg·m ² | 0.11 | 2.3 | 5.9 | 9.2 | 13 | 23 |
| | kgf·cm·s ² | 1.1 | 24 | 60 | 94 | 135 | 238 |
| Allowable load inertia moment | kg·m ² | 0.99 | 20 | 32 | 40 | 50 | 70 |
| | kgf·cm·s ² | 10 | 200 | 320 | 400 | 510 | 710 |

| Actuator model | | SHA40A | | | | | SHA45A | | | | |
|---|-----------------------|--------|------|-------|-------|-------|--------|------|-------|-------|-------|
| | | 51 | 81 | 101 | 121 | 161 | 51 | 81 | 101 | 121 | 161 |
| Reduction ratio | | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 | 1:51 | 1:81 | 1:101 | 1:121 | 1:161 |
| Max. rotational speed | r/min | 78.4 | 49.4 | 39.6 | 33.1 | 24.8 | 74.5 | 46.9 | 37.6 | 31.4 | 23.6 |
| Actuator inertia moment (without brake) | kg·m ² | 5.0 | 13 | 20 | 28 | 50 | 6.8 | 17 | 27 | 38 | 68 |
| | kgf·cm·s ² | 51 | 130 | 202 | 290 | 513 | 69 | 175 | 272 | 390 | 690 |
| Actuator inertia moment (with brake) | kg·m ² | 6.1 | 15 | 24 | 34 | 61 | 7.9 | 20 | 31 | 45 | 79 |
| | kgf·cm·s ² | 62 | 157 | 244 | 350 | 619 | 81 | 204 | 316 | 454 | 804 |
| Allowable load inertia moment | kg·m ² | 58 | 92 | 114 | 137 | 182 | 75 | 119 | 148 | 178 | 236 |
| | kgf·cm·s ² | 590 | 930 | 1170 | 1400 | 1860 | 766 | 1215 | 1514 | 1814 | 2413 |

| Actuator model | | SHA58A | | | | SHA65A | | | |
|---|-----------------------|--------|-------|-------|-------|--------|-------|-------|-------|
| | | 81 | 101 | 121 | 161 | 81 | 101 | 121 | 161 |
| Reduction ratio | | 1:81 | 1:101 | 1:121 | 1:161 | 1:81 | 1:101 | 1:121 | 1:161 |
| Max. rotational speed | r/min | 37.0 | 29.7 | 24.8 | 18.6 | 34.6 | 27.7 | 23.1 | 17.4 |
| Actuator inertia moment (without brake) | kg·m ² | 96 | 149 | 214 | 379 | 110 | 171 | 245 | 433 |
| | kgf·cm·s ² | 980 | 1520 | 2180 | 3870 | 1120 | 1740 | 2500 | 4420 |
| Actuator inertia moment (with brake) | kg·m ² | 106 | 165 | 237 | 420 | 120 | 187 | 268 | 475 |
| | kgf·cm·s ² | 1090 | 1690 | 2420 | 4290 | 1230 | 1910 | 2740 | 4850 |
| Allowable load inertia moment | kg·m ² | 290 | 450 | 640 | 1140 | 360 | 560 | 810 | 1420 |
| | kgf·cm·s ² | 2900 | 4600 | 6500 | 11600 | 3700 | 5700 | 8200 | 14500 |

CG type

| Actuator model | | SHA20A | | | | |
|---|-----------------------|--------|------|-------|-------|-------|
| | | 50 | 80 | 100 | 120 | 160 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 |
| Max. rotational speed | r/min | 120 | 75 | 60 | 50 | 37.5 |
| Actuator inertia moment (without brake) | kg·m ² | 0.21 | 0.53 | 0.82 | 1.2 | 2.1 |
| | kgf·cm·s ² | 2.1 | 5.4 | 8.0 | 12 | 22 |
| Actuator inertia moment (with brake) | kg·m ² | 0.23 | 0.60 | 0.94 | 1.3 | 2.4 |
| | kgf·cm·s ² | 2.4 | 6.1 | 9.6 | 14 | 24 |
| Allowable load inertia moment | kg·m ² | 2.4 | 3.8 | 4.8 | 5.8 | 7.7 |
| | kgf·cm·s ² | 25 | 39 | 49 | 59 | 78 |

| Actuator model | | SHA25A | | | | | SHA32A | | | | |
|---|-----------------------|--------|------|-------|-------|-------|--------|------|-------|-------|-------|
| | | 50 | 80 | 100 | 120 | 160 | 50 | 80 | 100 | 120 | 160 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 |
| Max. rotational speed | r/min | 112 | 70 | 56 | 46.7 | 35 | 96 | 60 | 48 | 40 | 30 |
| Actuator inertia moment (without brake) | kg·m ² | 0.50 | 1.3 | 2.0 | 2.9 | 5.1 | 1.7 | 4.3 | 6.7 | 9.7 | 17 |
| | kgf·cm·s ² | 5.1 | 13 | 20 | 29 | 52 | 17 | 44 | 68 | 99 | 175 |
| Actuator inertia moment (with brake) | kg·m ² | 0.60 | 1.5 | 2.4 | 3.4 | 6.1 | 2.0 | 5.1 | 7.9 | 11 | 20 |
| | kgf·cm·s ² | 6.1 | 16 | 24 | 35 | 62 | 20 | 52 | 81 | 116 | 207 |
| Allowable load inertia moment | kg·m ² | 5.6 | 8.8 | 11 | 14 | 20 | 20 | 32 | 40 | 50 | 70 |
| | kgf·cm·s ² | 57 | 90 | 112 | 144 | 201 | 200 | 320 | 400 | 510 | 710 |

| Actuator model | | SHA40A | | | | |
|---|-----------------------|--------|------|-------|-------|-------|
| | | 50 | 80 | 100 | 120 | 160 |
| Reduction ratio | | 1:50 | 1:80 | 1:100 | 1:120 | 1:160 |
| Max. rotational speed | r/min | 80 | 50 | 40 | 33.3 | 25 |
| Actuator inertia moment (without brake) | kg·m ² | 4.8 | 12 | 19 | 27 | 49 |
| | kgf·cm·s ² | 49 | 124 | 194 | 280 | 497 |
| Actuator inertia moment (with brake) | kg·m ² | 5.8 | 15 | 23 | 33 | 59 |
| | kgf·cm·s ² | 59 | 150 | 235 | 338 | 601 |
| Allowable load inertia moment | kg·m ² | 58 | 92 | 114 | 137 | 182 |
| | kgf·cm·s ² | 590 | 930 | 1170 | 1400 | 1860 |

2-2 Change in load inertia moment

2

For the SHA series combined with the high reduction ratio of the HarmonicDrive®, the effects of change in load inertia moment on the servo performance are minimal. In comparison to direct servo drive mechanisms, therefore, this benefit allows the load to be driven with a better servo response.

For example, assume that the load inertia moment increases to N-times. The total inertia moment converted to motor shaft which has an effect on servo response is as follows:

The symbols in the formulas are:

- J_S : Total inertia moment converted to motor shaft
- J_M : Inertia moment of motor
- R : Reduction ratio of SHA series actuator
- L : Ratio of load inertia moment to inertia moment of motor
- N : Rate of change in load inertia moment

- Direct drive

$$\text{Before: } J_S = J_M(1+L) \qquad \text{After: } J_S' = J_M(1+NL) \qquad \text{Ratio: } J_S'/J_S = \frac{1+NL}{1+L}$$

- Driven by SHA series

$$\text{Before: } J_S = J_M \left(1 + \frac{L}{R^2} \right) \qquad \text{After: } J_S' = J_M \left(1 + \frac{NL}{R^2} \right) \qquad \text{Ratio: } J_S'/J_S = \frac{1+NL/R^2}{1+L/R^2}$$

With the SHA series, the value of R increases from 50 to 161, which means that the value increases substantially from $R^2 = 2500$ to $R^2 = 25921$. Then the ratio is $J_S'/J_S \approx 1$. This means that SHA drive systems are hardly affected by the load variation.

Therefore, it is not necessary to take change in load inertia moment into consideration when selecting a SHA series actuator or setting up the initial driver parameters.

2-3 Verifying and examining load weights

The SHA series actuator incorporates a precise cross roller bearing for directly supporting an external load (output flange). To demonstrate the full ability of the actuator, verify the maximum load moment load as well as the life and static safety coefficient of the cross roller bearing.

Checking procedure

1 Verifying the maximum load moment load (M_{max})

Calculating the maximum load moment load (M_{max})



Verifying the maximum load moment load (M_{max}) is less than or equal to the permissible moment load (M_c)

2 Verifying life

Calculate the average radial load (F_{rav}) and average axial load (F_{aav}).



Calculate the radial load coefficient (X) and the axial load coefficient (Y).



Calculate the life of the bearing and verify the life is allowable.

3 Verifying the static safety coefficient

Calculate the static equivalent radial load (P_o).



Verify the static safety coefficient (f_s).

Specifications of the main roller bearing

The following table shows the specifications of the main roller bearings built in SHA actuators.

Table 1: Specifications of the main roller bearings

| Model | Item | Circular pitch of the roller (dp) | Offset amount (R) | Basic dynamic rated load (C) | Basic static rated load (C ₀) | Permissible moment load (M _c) | Moment stiffness (K _m) |
|-------|-----------|-----------------------------------|-------------------|------------------------------|---|---|------------------------------------|
| | | mm | mm | kN | kN | N·m | ×10 ⁴ N·m/rad |
| | SHA20A-SG | 70 | 23.5 | 14.6 | 22 | 187 | 25.2 |
| | SHA20A-CG | 70 | 19.5 | 14.6 | 22 | 187 | 25.2 |
| | SHA25A-SG | 85 | 27.6 | 21.8 | 35.8 | 258 | 39.2 |
| | SHA25A-CG | 85 | 21.6 | 21.8 | 35.8 | 258 | 39.2 |
| | SHA25A-HP | 85 | 15.3 | 11.4 | 20.3 | 410 | 37.9 |
| | SHA32A-SG | 111 | 34.9 | 38.2 | 65.4 | 580 | 100 |
| | SHA32A-CG | 111 | 25.4 | 38.2 | 65.4 | 580 | 100 |
| | SHA32A-HP | 111.5 | 15 | 22.5 | 39.9 | 932 | 86.1 |
| | SHA40A-SG | 133 | 44 | 43.3 | 81.6 | 849 | 179 |
| | SHA40A-CG | 133 | 29.5 | 43.3 | 81.6 | 849 | 179 |
| | SHA45A-SG | 154 | 47.5 | 77.6 | 135 | 1127 | 257 |
| | SHA58A-SG | 195 | 62.2 | 87.4 | 171 | 2180 | 531 |
| | SHA65A-SG | 218 | 69 | 130 | 223 | 2740 | 741 |

Maximum load moment load

The formula below shows how to calculate the maximum load moment load (M_{max}).

Verify that the maximum load moment load (M_{max}) is less than or equal to the permissible moment load (M_c).

◆ **Formula (1): Maximum load moment load**

$$M_{max} = \frac{Fr_{max} \cdot (L_r + R) + Fa_{max} \cdot La}{1000}$$

Symbols used in the formula

| | | | |
|------------|--------------------------|-------|-----------------------------|
| M_{max} | Maximum load moment load | N · m | |
| Fr_{max} | Max. radial load | N | Refer to Fig.1. |
| Fa_{max} | Max. axial load | N | Refer to Fig.1. |
| L_r, La | | mm | Refer to Fig.1. |
| R | Offset amount | mm | Refer to Fig.1 and Table 1. |

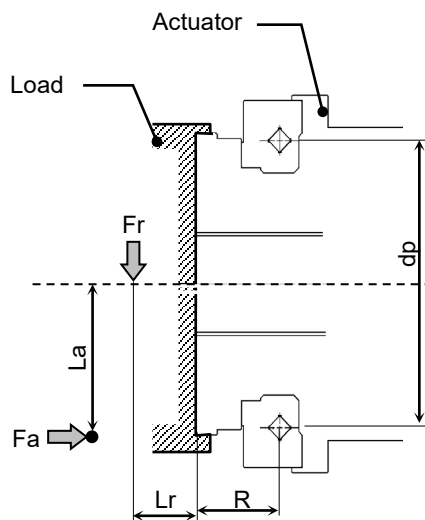


Fig. 1: External load action

Verifying life

Calculating average loads (average radial and axial loads, average output rotational speed)

When the radial and/or axial loads vary during motion, calculate and verify the life of the cross roller bearing converting the loads to their average values.

◆ **Formula (2): Average radial load (F_{rav})**

$$F_{rav} = \sqrt[10/3]{\frac{n_1 t_1 |Fr_1|^{10/3} + n_2 t_2 |Fr_2|^{10/3} + \dots + n_n t_n |Fr_n|^{10/3}}{n_1 t_1 + n_2 t_2 + \dots + n_n t_n}}$$

The maximum radial load in section t_1 is given by Fr_1 , while the maximum radial load in section t_3 is given by Fr_3 .

◆ **Formula (3): Average axial load (F_{aav})**

$$F_{aav} = \sqrt[10/3]{\frac{n_1 t_1 |Fa_1|^{10/3} + n_2 t_2 |Fa_2|^{10/3} + \dots + n_n t_n |Fa_n|^{10/3}}{n_1 t_1 + n_2 t_2 + \dots + n_n t_n}}$$

The maximum axial load in section t_1 is given by Fa_1 , while the maximum axial load in section t_3 is given by Fa_3 .

◆ **Formula (4): Average output rotational speed (N_{av})**

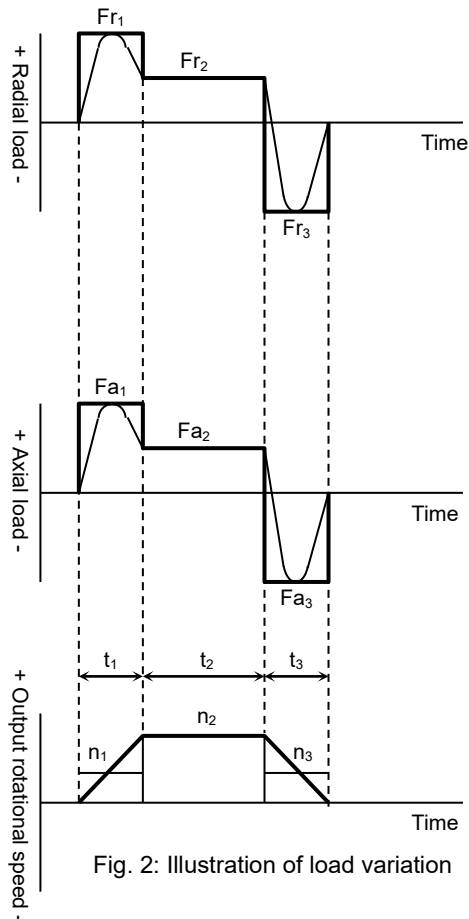
$$N_{av} = \frac{n_1 t_1 + n_2 t_2 + \dots + n_n t_n}{t_1 + t_2 + \dots + t_n}$$


Fig. 2: Illustration of load variation

Radial load coefficient and axial load coefficient

Determine the values of radial load coefficient (X) and axial load coefficient (Y) based on conditional judgment according to formula (5).

Table 2: Radial load coefficient (X), axial load coefficient (Y)

| ◆ Formula (5) | X | Y |
|--|------|------|
| $\frac{F_{aav}}{F_{rav} + 2(F_{rav}(L_r + R) + F_{aav} \cdot L_a)/d_p} \leq 1.5$ | 1 | 0.45 |
| $\frac{F_{aav}}{F_{rav} + 2(F_{rav}(L_r + R) + F_{aav} \cdot L_a)/d_p} > 1.5$ | 0.67 | 0.67 |

Symbols used in the formulas

| | | | |
|------------|-----------------------------------|----|-----------------------------|
| F_{rav} | Average radial load | N | Refer to the average load. |
| F_{aav} | Average axial load | N | Refer to the average load. |
| L_r, L_a | — | mm | Refer to Fig.1. |
| R | Offset amount | mm | Refer to Fig.1 and Table 1. |
| d_p | Pitch circle diameter of a roller | mm | Refer to Fig.1 and Table 1. |

Dynamic equivalent radial load

◆ Formula (6): Dynamic equivalent radial load

$$P_c = X \cdot \left(F_{rav} + \frac{2(F_{rav}(L_r + R) + F_{aav} \cdot L_a)}{d_p} \right) + Y \cdot F_{aav}$$

Symbols used in the formulas

| | | | |
|------------|-----------------------------------|----|-----------------------------|
| P_c | Dynamic equivalent radial load | N | |
| F_{rav} | Average radial load | N | Obtained by formula (2). |
| F_{aav} | Average axial load | N | Obtained by formula (3). |
| d_p | Pitch circle diameter of a roller | mm | Refer to Table 1. |
| X | Radial load coefficient | — | Refer to Table 2. |
| Y | Axial load coefficient | — | Refer to Table 2. |
| L_r, L_a | — | mm | Refer to Fig.1. |
| R | Offset amount | mm | Refer to Fig.1 and Table 1. |

Life of cross roller bearing

Calculate the life of cross roller bearing with the formula (7):

◆ Formula (7): Cross roller bearing life

$$L_{B-10} = \frac{10^6}{60 \times N_{av}} \times \left(\frac{C}{f_w \cdot P_c} \right)^{10/3}$$

Symbols used in the formulas

| | | | |
|------------|---------------------------------|-------|--------------------------|
| L_{B-10} | Life | hour | — |
| N_{av} | Average output rotational speed | r/min | Obtained by formula (4). |
| C | Basic dynamic rated load | N | Refer to Table 1. |
| P_c | Dynamic equivalent radial load | N | Obtained by formula (6). |
| f_w | Load coefficient | — | Refer to Table 3. |

Table 3: Load coefficient

| Loaded state | f_w |
|---|------------|
| Smooth operation free from impact/vibration | 1 to 1.2 |
| Normal operation | 1.2 to 1.5 |
| Operation subject to impact/vibration | 1.5 to 3 |

Cross roller bearing life based on oscillating movement

Use formula (8) to calculate the cross roller bearing life against oscillating movement.

◆ **Formula (8): Cross roller bearing life (oscillating)**

$$L_{oc} = \frac{10^6}{60 \times n_1} \times \frac{90}{\theta} \times \left(\frac{C}{f_w \cdot P_c} \right)^{10/3}$$

Symbols used in the formulas

| | | | |
|----------|--|------|--------------------------|
| L_{oc} | Life | hour | — |
| n_1 | Number of reciprocating oscillation per min. | cpm | — |
| C | Basic dynamic rated load | N | Refer to Table 1. |
| P_c | Dynamic equivalent radial load | N | Obtained by formula (6). |
| f_w | Load coefficient | — | Refer to Table 3. |
| θ | Oscillating angle/2 | — | Refer to Fig.3. |

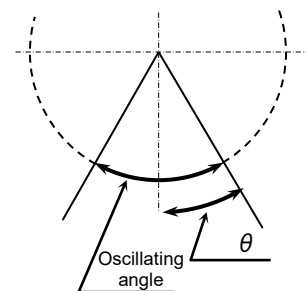


Fig. 3: Oscillating movement

If the oscillating angle is 5° or less, fretting wear may occur because oil film does not form effectively on the contact surface between the race and rolling element of the cross roller bearing. In such cases, consult HDS.

Verifying static safety coefficients

Static equivalent radial load

◆ **Formula (9): Static equivalent radial load**

$$P_o = F_{rmax} + \frac{2M_{max}}{d_p} + 0.44F_{amax}$$

Symbols used in the formulas

| | | | |
|------------|-----------------------------------|-----|---|
| F_{rmax} | Max. radial load | N | Refer to Fig.1. |
| F_{amax} | Max. axial load | N | Refer to Fig.1. |
| M_{max} | Max. moment load | N·m | Refer to the maximum load weight calculation methods. |
| d_p | Pitch circle diameter of a roller | mm | Refer to Table 1. |

Static safety coefficient

Generally, the static equivalent load is limited by the basic static rated load(C_o). However, the specific limit should be calculated according to the using conditions and required conditions. In this case, calculate the static safety coefficient (f_s) by formula (10).

Table 4 shows general values representing using conditions. Calculate the static equivalent radial load (P_o) by formula (9).

◆ **Formula (10): Static safety coefficient**

$$f_s = \frac{C_o}{P_o}$$

Symbols used in the formulas

| | | | |
|-------|-------------------------------|---|--------------------------|
| f_s | Static safety coefficient | — | Refer to Table 4. |
| C_o | Basic static rated load | N | Refer to Table 1. |
| P_o | Static equivalent radial load | N | Obtained by formula (9). |

Table 4: Static safety coefficients

| Using conditions | f_s |
|--|------------|
| High rotational accuracy is required, etc. | ≥ 3 |
| Operation subject to impact/vibration | ≥ 2 |
| Normal operation | ≥ 1.5 |

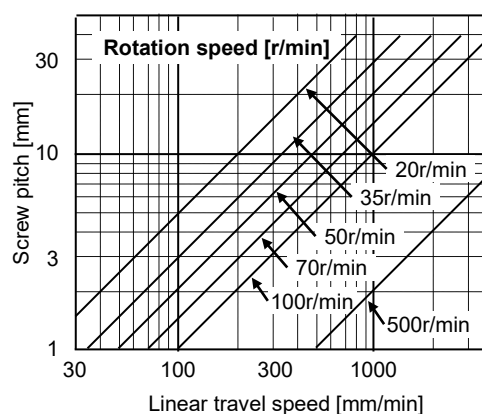
2-4 Examining operating status

The actuator generates heat if started/stopped repeatedly or operated continuously at high speed. Accordingly, examine whether or not the generated heat can be accommodated. The study is as follows:

Examining actuator rotation speed

Calculate the actuator rotation speed [r/min] of the load driven by the SHA series. For linear operation, use the rotation speed conversion formula below:

$$\text{Actuator rotation speed [r/min]} = \frac{\text{Linear travel speed [mm/min]}}{\text{Screw feed pitch [mm]}}$$



Select an appropriate reduction ratio from 11, 50, 51, 80, 81, 100, 101, 120, 121, 160 and 161 so that the calculated actuator rotation speed does not exceed the maximum rotational speed of the SHA series actuator.

Calculating and examining load inertia moment

Calculate the load inertia moment of the load driven by the SHA series actuator.

Refer to [A-2 Calculating inertia moment] (P5-3) for the calculation.

Based on the calculated result, tentatively select a SHA series actuator by referring to [Allowable load inertia moment] (P2-1).

Load torque calculation

Calculate the load torque as follows:

- Rotary motion

The rotary torque for the rotating mass W on the ring of radius r from the center of rotation is shown in the figure to the right.

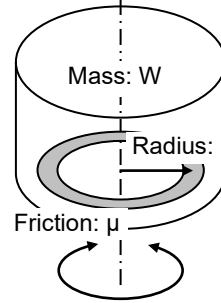
$$T = 9.8 \times \mu \times W \times r$$

T : Rotary torque [N·m]

μ : Friction coefficient

W : Mass [kg]

r : Average radius of friction side [m]



Example of rotary torque calculation (friction coefficient = 0.1)
SHA: 20 % torque of maximum torque is shown.

- Linear operation (horizontal operation)

The rotary torque when the mass W moves horizontally due to the screw of pitch P is shown below.

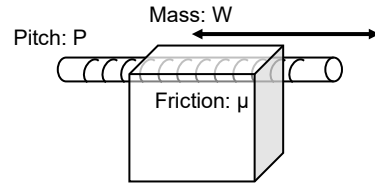
$$T = 9.8 \times \mu \times W \times \frac{P}{2 \times \pi}$$

T : Rotary torque [N·m]

μ : friction coefficient

W : mass [kg]

P : Screw feed pitch [m]



- Linear operation (vertical operation)

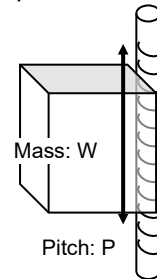
The rotary torque when the mass W moves vertically due to the screw of pitch P is shown below.

$$T = 9.8 \times W \times \frac{P}{2 \times \pi}$$

T : Rotary torque [N·m]

W : mass [kg]

P : Screw feed pitch [m]



Acceleration time and deceleration time

Calculate acceleration and deceleration times for the selected actuator.

$$\text{Acceleration time: } t_a = k \times (J_A + J_L) \times \frac{2 \times \pi}{60} \times \frac{N}{T_M - T_L}$$

$$\text{Deceleration time: } t_d = k \times (J_A + J_L) \times \frac{2 \times \pi}{60} \times \frac{N}{T_M + 2 \times T_F + T_L}$$

t_a : Acceleration time [s]
 t_d : Deceleration time [s]

k : Acceleration reduction coefficient 1 to 1.5
 The total positioning time may become shorter if the acceleration is lowered for the purpose of reducing the settling time after positioning.

J_A : Actuator inertia moment [kg·m²]

J_L : Load inertia moment [kg·m²]

N : Actuator rotation speed [r/min]

T_M : Maximum actuator torque [N·m]

T_F : Actuator friction torque [N·m]

$$T_F = K_T \times I_R - T_R$$

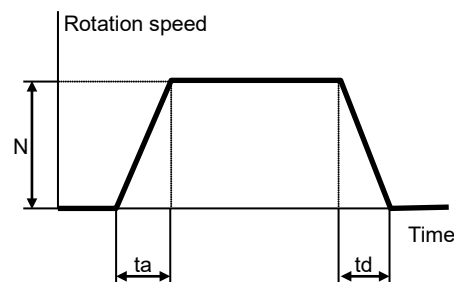
K_T : Torque constant [N·m/A]

T_R : Allowable continuous torque [N·m]

I_R : Allowable continuous current [A]

T_L : Load torque [N·m]

The polarity is positive (+) when the torque is applied in the rotation direction, or negative (-) when it is applied in the opposite direction.



● Calculation example 1

Select an actuator that best suits the following operating conditions:

- Rotation speed: 80 [r/min]
- Load inertia moment: 1.5 [kg·m²]
- Since the load mechanism is mainly inertia, the load torque is negligibly small.

(1) After applying these conditions to the graph in [2-1], SHA25A51SG-B09A200 is tentatively selected.

(2) From the rated table, the following values are obtained:

$$J_A = 0.56 \text{ [kg·m}^2\text{]}$$

$$T_M = 127 \text{ [N·m]}$$

$$T_R = 41 \text{ [N·m]}$$

$$K_T = 19 \text{ [N·m/A]}$$

$$I_R = 3 \text{ [A]}$$

(3) Based on the above formula, the actuator's friction torque T_F is calculated as $19 \times 3 - 41 = 16 \text{ [N·m]}$.

(4) If $k = 1.3$, the acceleration time and deceleration time can be obtained as follows from the above formulas:

$$t_a = 1.3 \times (0.56 + 1.5) \times 2 \times \pi / 60 \times 80 / 127 = 0.177 \text{ [s]}$$

$$t_d = 1.3 \times (0.56 + 1.5) \times 2 \times \pi / 60 \times 80 / (127 + 2 \times 16) = 0.141 \text{ [s]}$$

(5) If the calculated acceleration/deceleration times are too long, correct the situation by:

- Reducing load inertia moment
- Selecting an actuator with a larger frame size

Examining effective torque and average rotation speed

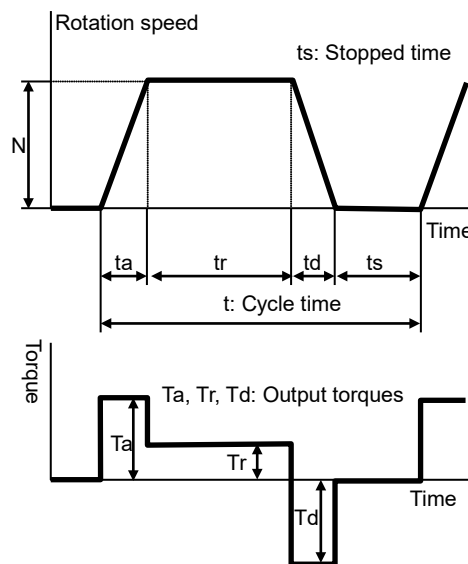
One way to check if the heat generated from the actuator during operation would present a problem is to determine if the point of operation, determined by the effective torque and average rotation speed, is inside the continuous motion range explained in [1-14 Operable range].

Using the following formula, calculate the effective torque T_m and average rotation speed N_{av} when the actuator is operated repeatedly in the drive pattern shown to the right.

$$T_m = \sqrt{\frac{T_a^2 \times t_a + T_r^2 \times t_r + T_d^2 \times t_d}{t}}$$

$$N_{av} = \frac{N/2 \times t_a + N \times t_r + N/2 \times t_d}{t}$$

- | | | |
|----------|---------------------------------------|---------|
| t_a | : Acceleration time from speed 0 to N | [s] |
| t_d | : Deceleration time from speed N to 0 | [s] |
| t_r | : Operation time at constant speed N | [s] |
| t | : Cycle time | [s] |
| T_m | : Effective torque | [N·m] |
| T_a | : Torque during acceleration | [N·m] |
| T_r | : Torque at constant speed | [N·m] |
| T_d | : Torque during deceleration | [N·m] |
| N_{av} | : Average rotation speed | [r/min] |
| N | : Rotation speed at constant speed | [r/min] |



● Calculation example 2

An example of SHA25A51SG-B09A200 is explained.

Operating conditions: Accelerate an inertia load and then let it move at a constant speed, followed by deceleration, based on conditions similar to those used in calculation example 1. The travel angle per cycle is 120° and the cycle time is 1 second.

(1) The travel angle is calculated from the area of the rotation speed vs. time diagram shown above. In other words, the travel angle θ is calculated as follows:

$$\theta = (N / 60) \times \{t_r + (t_a + t_d) / 2\} \times 360$$

Accordingly, $t_r = \theta / (6 \times N) - (t_a + t_d) / 2$

When $\theta = 120^\circ$, and

$$t_a = 0.177 \text{ [s]}$$

$$t_d = 0.141 \text{ [s]}$$

$$N = 80 \text{ [r/min]}$$

in calculation example 1, are applied to this formula, t_r is calculated as 0.091 [s].

(2) Next, calculate the torque during acceleration and torque during deceleration. Based on the acceleration/deceleration time formulas in the preceding section, the relational expressions for torque during acceleration and torque during deceleration if $k = 1$ are as follows:

$$T_a = (J_a + J_L) \times 2 \times \pi / 60 \times N / t_a + T_L$$

$$T_d = (J_a + J_L) \times 2 \times \pi / 60 \times N / t_d - 2 \times T_F - T_L$$

When the values in calculation example 1 are applied to this formula,

$$T_a = 98 \text{ [N·m]} \text{ and}$$

$$T_d = 90 \text{ [N·m]}$$

are obtained.

(3) Calculate the effective torque. Apply the values in (1) and (2), and $T_r = 0 \text{ N·m}$ and $t = 1$ second, to the above formulas.

$$T_m = \sqrt{\frac{98^2 \times 0.177 + 0^2 \times 0.091 + 90^2 \times 0.141}{1}} = 53 \text{ [N·m]}$$

- (4) Calculate the average rotation speed. Apply the values in (1), and $N = 80$ r/min and $t = 1$ second, to the above formulas.

$$N_{av} = \frac{80/2 \times 0.177 + 80 \times 0.091 + 80/2 \times 0.141}{1} = 20 \text{ [r/min]}$$

- (5) The figure on the right shows the points of operation determined by the effective torque and average rotation speed calculated above, plotted on the graph of operable range of SHA25A51, exceeding the continuous motion range. The conclusion is that this actuator cannot be operated continuously under these conditions. Accordingly,

- ◆ the operation pattern
- ◆ load (possible reduction)
- ◆ actuator model No.

etc., must be reexamined.

The following formula is a modified version of the formula for effective torque. By applying the value of allowable continuous torque to T_m in this formula, the allowable cycle time can be calculated.

$$t = \frac{T_a^2 \times t_a + T_r^2 \times t_r + T_d^2 \times t_d}{T_m^2}$$

Apply the following:

$$T_a = 98 \text{ [N}\cdot\text{m]}$$

$$T_r = 0 \text{ [N}\cdot\text{m]}$$

$$T_d = 90 \text{ [N}\cdot\text{m]}$$

$$T_m = 41 \text{ [N}\cdot\text{m]}$$

$$t_a = 0.177 \text{ [s]}$$

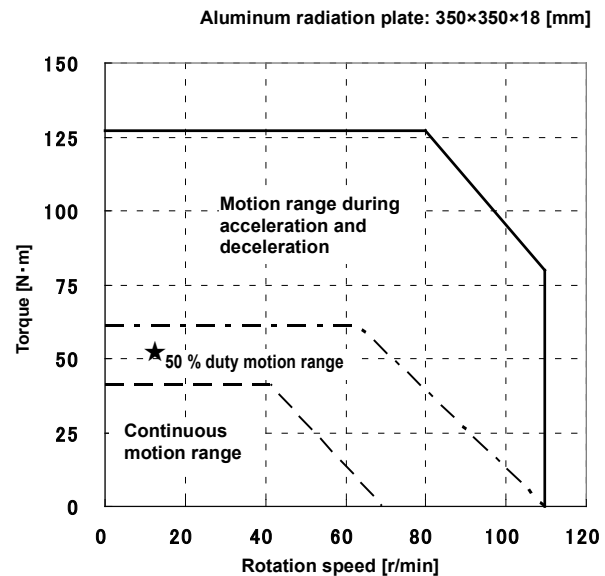
$$t_r = 0.091 \text{ [s]}$$

$$t_d = 0.141 \text{ [s]}$$

Then, the following equation is obtained:

$$t = (98^2 \times 0.177 + 90^2 \times 0.141) / 41^2 = 1.69 \text{ [s]}$$

Based on the result, setting the cycle time to 1.7 seconds or more to provide a longer stopped time gives $T_m = 41$ [N·m] or less, thereby permitting continuous operation within the allowable continuous torque.



Caution

- The aforementioned continuous motion range represents an allowable range where the actuator installed on a specified aluminum radiation plate is operated under natural air cooling. If the radiation area of the mounting member is small or heat conduction of the material is poor, adjust the operating conditions to keep the rise in the actuator's ambient temperature to 40 K or less as a guide.

2

Selection guidelines

Chapter 3

Installing the actuator

The following explains the installation procedures of the actuators.

| | |
|------------------------------------|-----|
| 3-1 Receiving Inspection..... | 3-1 |
| 3-2 Notices on handling..... | 3-2 |
| 3-3 Location and installation..... | 3-6 |

3-1 Receiving Inspection

Check the following items after unpacking the package.

3

Installing the actuator

Inspection procedure

1 Check the items thoroughly for damage sustained during transportation.

If any item is damaged, immediately contact the dealer.

2 Check if the actuator is what you ordered.

The nameplate is found on the rear end face of the SHA series actuator. Check the TYPE field on the nameplate to confirm that it is indeed the model you have ordered. If any item is wrong, immediately contact the dealer.

Refer to the section [1-2 Model] (P1-3) in this manual for the detail of the model codes.

3 Check if the driver combinations are correct.

The applicable SHA series actuator models are shown in the ADJUSTED FOR USE WITH field of the nameplate on the combined driver.

4 Check if the driver input voltages being input are correct.

The driver's model code is shown in the TYPE field of the driver's nameplate. The last three digits of this model code indicate the input voltage to be input.

100: indicates a single phase 100 VAC power supply.

200: indicates a 3-phase/single-phase 200 VAC power supply.

If the voltage to be supplied is different from the label voltage, immediately contact the dealer it was purchased from.



WARNING

Do not combine the actuator other than the one specified on the nameplate.

The characteristics of this driver have been adjusted according to the actuator. Wrong combinations of drivers and actuators may cause low torque problems or overcurrent that may cause burned damage to the actuator, injury or fire.

Do not connect a supply voltage other than the voltage specified on the driver label.

Connecting a power supply not matching the input voltage specified on the nameplate may result in damage to the driver, injury or fire.

3-2 Notices on handling

Handle the SHA series actuator carefully by observing the notices specified below.

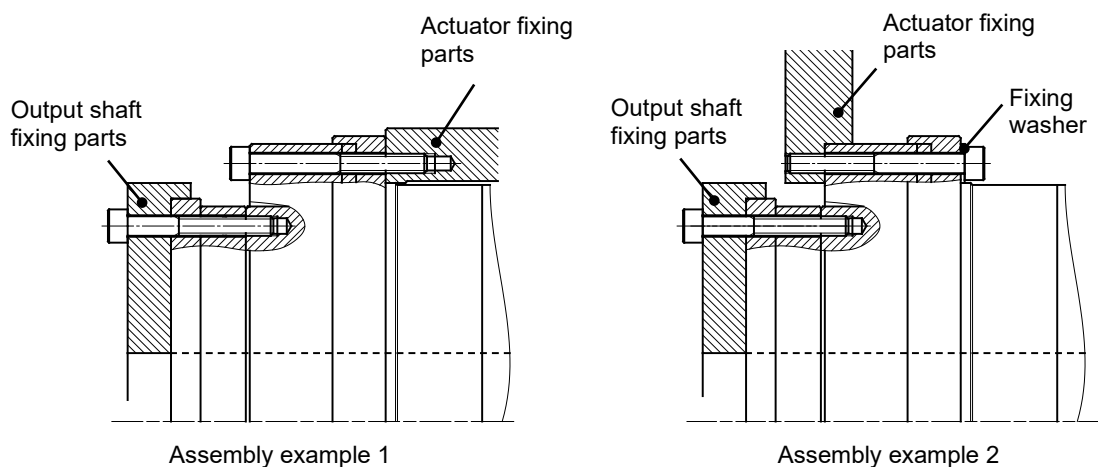


- (1) Do not apply any excessive force or impact, especially to the actuator's output shaft.
- (2) Do not put the SHA series actuator on a table, shelf, etc., where the actuator could easily fall.
- (3) Do not connect the actuator terminals directly to the power supply. The actuator may burn and cause fire or electric shock.
- (4) The allowable storage temperature is -20 to $+60$ °C. Do not expose the actuator to direct sunlight for long periods of time or store it in areas in low or high temperature.
- (5) The allowable relative storage humidity is 80 % or less. Do not store the actuator in a very humid place or in areas where temperatures are likely to fluctuate greatly during day and night.
- (6) Do not use or store the actuator in locations subject to flammable or corrosive gases or dust particles.
- (7) The large models (SHA58A, SHA65A) are heavy. Handling these models may cause lower back pain, or injury if the actuator drops or topples and you are pinned underneath. Handle your actuator with due care by wearing safety shoes or take other proper precaution and also by using supporting jigs.

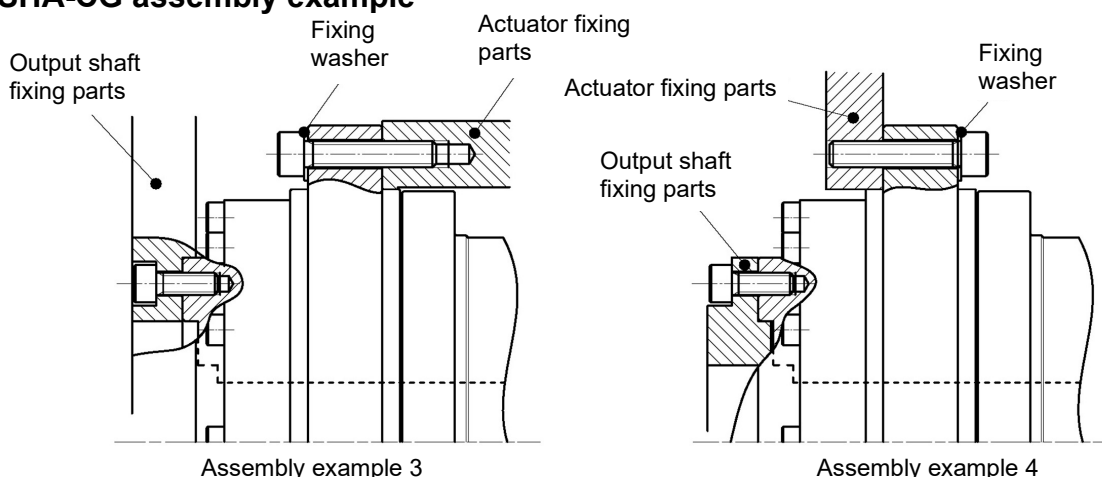
Installation and transmission torque

Examples of actuator assembly are shown below. Assembly examples 1 and 2 are for SHA-SG. Assembly examples 3 and 4 are for SHA-CG. Use high-tension bolts and tighten them with a torque wrench to control the tightening torque. In assembly example 2 to 4, use flat washers because the tightening torque is high and the actuator flange is made of aluminum.

SHA-SG assembly example



SHA-CG assembly example



- Recommended tightening torque and transmission torque

SG/HP type

| Item | | Model | SHA20A | | SHA25A | | SHA32A | |
|--------------------------|-------|-------|--------------|----------|------------------|----------------|------------------|----------------|
| | | | Output shaft | Actuator | Output shaft | Actuator | Output shaft | Actuator |
| Number of bolts, size | | | 16-M3 | 12-M3 | 16-M4 (12-M4) | 12-M4 | 16-M5 (12-M5) | 12-M5 |
| Bolt installation P.C.D. | mm | | 62 | 84 | 77 | 102 (127) | 100 | 132 (157) |
| | N·m | | 2.0 | 2.0 | 4.5 | 4.5 (3.2) | 9 | 9 (6.4) |
| Tightening torque | kgf·m | | 0.20 | 0.20 | 0.46 | 0.46 (0.33) | 0.92 | 0.92 (0.65) |
| | N·m | | 203 | 206 | 433 (325) | 430 (381) | 900 (675) | 891 (754) |
| Transmission torque | kgf·m | | 21 | 21 | 44 (33.2) | 44 (38.9) | 92 (68.9) | 91 (76.9) |

The values in parenthesis are those combined with the hollow planetary speed reducer HPF series for precision control.

| Item | | Model | SHA40A | | SHA45A | |
|--------------------------|-------|-------|--------------|----------|--------------|----------|
| | | | Output shaft | Actuator | Output shaft | Actuator |
| Number of bolts, size | | | 16-M6 | 12-M6 | 12-M8 | 18-M6 |
| Bolt installation P.C.D. | mm | | 122 | 158 | 140 | 180 |
| | N·m | | 15.3 | 15.3 | 37 | 15.3 |
| Tightening torque | kgf·m | | 1.56 | 1.56 | 3.8 | 1.56 |
| | N·m | | 1560 | 1510 | 2428 | 2582 |
| Transmission torque | kgf·m | | 159 | 154 | 248 | 263 |

| Item | | Model | SHA58A | | SHA65A | |
|--------------------------|-------|-------|--------------|----------|--------------|----------|
| | | | Output shaft | Actuator | Output shaft | Actuator |
| Number of bolts, size | | | 12-M10 | 16-M8 | 16-M10 | 16-M10 |
| Bolt installation P.C.D. | mm | | 178 | 226 | 195 | 258 |
| | N·m | | 74 | 37 | 74 | 74 |
| Tightening torque | kgf·m | | 7.5 | 3.8 | 7.5 | 7.5 |
| | N·m | | 4940 | 5230 | 7210 | 9550 |
| Transmission torque | kgf·m | | 504 | 533 | 735 | 974 |

CG type

| Item \ Model | | SHA20A | | SHA25A | |
|--------------------------|-------|--------------|----------|--------------|----------|
| | | Output shaft | Actuator | Output shaft | Actuator |
| Number of bolts, size | | 12-M4 | 6-M5 | 12-M5 | 8-M6 |
| Bolt installation P.C.D. | mm | 60 | 107 | 72 | 131 |
| | N·m | 4.5 | 6.4 | 9 | 11 |
| Tightening torque | kgf·m | 0.46 | 0.65 | 0.92 | 1.1 |
| | N·m | 253 | 257 | 486 | 600 |
| Transmission torque | kgf·m | 26 | 26 | 50 | 61 |

| Item \ Model | | SHA32A | | SHA40A | |
|--------------------------|-------|--------------|----------|--------------|----------|
| | | Output shaft | Actuator | Output shaft | Actuator |
| Number of bolts, size | | 12-M6 | 12-M6 | 12-M8 | 8-M10 |
| Bolt installation P.C.D. | mm | 96 | 162 | 116 | 203 |
| | N·m | 15.3 | 11 | 37 | 52 |
| Tightening torque | kgf·m | 1.6 | 1.1 | 3.8 | 5.3 |
| | N·m | 918 | 1114 | 2012 | 2639 |
| Transmission torque | kgf·m | 94 | 114 | 205 | 269 |

Note 1: The female thread material is premised to withstand the bolt tightening torque

2: Recommended bolt: Hexagonal bolt per JIS B 1176 Intensity category: JIS B 1051 12.9 or higher

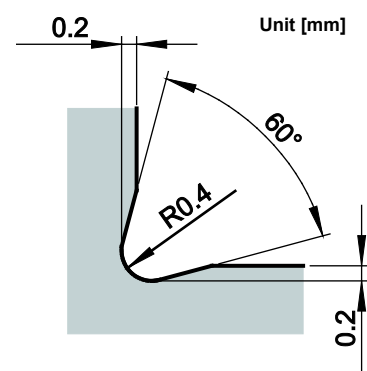
3: Calculation conditions Torque efficiency: 0.2 Tightening efficiency: 1.4 Tightening friction coefficient: 0.15

Precautions on installation

When designing the assembly, take note that application of any abnormal or excessive force that causes deformation of the installation surface may result in performance drop. To demonstrate the excellent performance of the SHA series actuator fully, take note of the following points:

- Warp and deformation on the mounting surface
- Blocking of foreign matter
- Burrs, rising and abnormal position accuracy around tapped mounting holes
- Insufficient chamfering of mounting faucet joint
- Abnormal circularity of mounting faucet joint

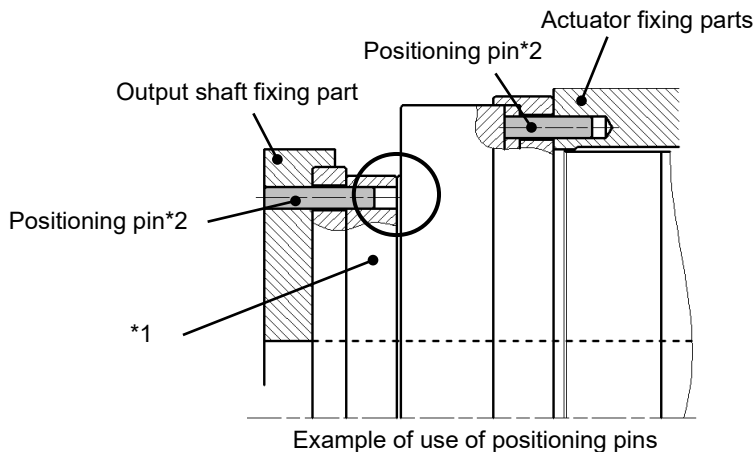
When the installation method is as shown in assembly example 2 mentioned above, the recessing shown to the right is recommended for the spigot corner section on the actuator fixing member.



Use of positioning pins

The SHA series SG type actuator has positioning pin holes in the output rotary unit and flange fixed to the actuator. The SHA series CG type has positioning pin holes only in the output rotary unit.

Use these pins as necessary. For details, refer to [1-6 External dimensions] (P1-18) or the illustrated specifications.



*1. Do not drive positioning pins into the output rotary unit, but keep proper fitting clearances to the actuator parts. Failure to do so may result in lower positional accuracy.

*2. The hollow planetary speed reducer model is not equipped with a positioning pin.

Surface treatments

Standard SHA series actuators are given the following surface treatments:

SG/HP type

| Location | Surface treatments |
|-----------------------------|---|
| Housing | No treatment (aluminum material is exposed) |
| Output shaft bearing | Raydent treatment |
| Speed reducer rotating part | Chrome plating |
| Output flange | Nickel plating or Raydent treatment |
| Hollow shaft (sleeve) | Nickel plating |
| Bolt (output shaft side) | Black oxide coating treatment |

CG type

| Location | Surface treatments |
|-----------------------------|---|
| Housing | No treatment (aluminum material is exposed) |
| Output flange | Raydent treatment |
| Speed reducer rotating part | Raydent treatment, enamel resin is applied to some surfaces |
| Hollow shaft (sleeve) | Nickel plating |
| Bolt (output shaft side) | Chrome plating or Nickel plating |

The surface treatments given to SHA series actuators do not fully prevent rust.

3-3 Location and installation

Environment of location

The environmental conditions of the installation location for SHA series actuators must be as follows. Determine an appropriate installation location by observing these conditions without fail.

- ◆ Operating temperature: 0 to 40 °C
The temperature in the cabinet may be higher than the atmosphere depending on the power loss of housed devices and size of the cabinet. Plan the cabinet size, cooling system, and device locations so the ambient temperature of the actuator is kept 40 °C or below.
- ◆ Operating humidity: Relative humidity of 20 to 80 %.
Make sure no condensation occurs. Take note that condensation is likely to occur in a place where there is a large temperature change between day and night or when the actuator is started/stopped frequently.
- ◆ Vibration: 25 m/s² (10 to 400 Hz) or less (Refer to [1-13 Resistance to vibration] (P1-43))
- ◆ Impact: 300 m/s² or less (Refer to [1-12 Shock resistance] (P1-42))
- ◆ Use environment: Free from condensation, metal powder, corrosive gases, water, oil mist, flammable gases, etc.
- ◆ Protection class: Standard products are structurally designed to meet the IP-54 requirements.

The protection class against water entry is as follows:
4: Protected against water splashed from all directions.

The protection class against contact and entry of foreign matter is as follows:
5: Protected against entry of dust/dirt. Entry of foreign matter caused by incomplete protection must not affect the operation of the system.

However, rotating and sliding areas (oil seal areas) and connectors of SHA20, 25, 32, 40, and 45 are not IP-54-compliant. Connectors of SHA58 and 65 are protected in fitted conditions.

- ◆ Locate the driver indoors or within an enclosure. Do not expose it to the sunlight.
- ◆ Altitude: lower than 1000 m above sea level
- ◆ The oil seals in rotating and sliding areas do not fully prevent leakage of lubricant. If the actuator is used in a clean room, etc., provide additional oil leakage prevention measures.

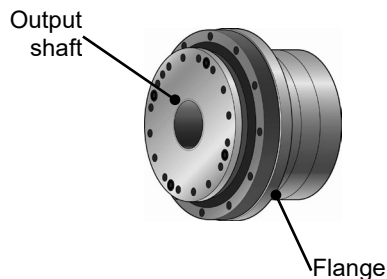
Installation

The SHA series actuator drives mechanical load system at high accuracy. When installing the actuator, pay attention to precision and do not tap the actuator output part with a hammer, etc. The actuator houses an encoder. Excessive impact may damage the encoder.

Installation procedure

1 Align the axis of rotation of the actuator and the load mechanism precisely.

Note 1: Perform this alignment carefully, especially when a rigid coupling is used. Even slight misalignment may cause the permissible load of the actuator to be exceeded, resulting in damage to the output shaft.



2 Connect the driver and wiring.

An extension cable is provided. Use it when wiring the driver. For details on wiring, refer to [1-15 Cable specifications] (P1-60) and the manual for the combined driver.

3 Wire the motor cable and encoder cable.

Do not pull the cables with a strong force. The connection points may be damaged. Install the cable with slack not to apply tension to the actuator. Provide a sufficient bending radius (at least 6 times the cable diameter), especially when the cable flexes.

Caution

- Do not bring strong magnetic bodies (magnet chucks, permanent magnets, etc.) near the rear cover of the actuator. Encoder abnormality may result.
- This encoder requires an external battery to retain absolute positions.



Do not disassemble/reassemble the actuator.

The actuator uses many precision parts. If the actuator is disassembled or reassembled by the customer, it may cause burned damage or uncontrollable operation of the actuator, resulting in fire or injury.

Chapter 4

Options

This chapter explains the options available for the SHA series actuator.

| | |
|-------------------|-----|
| 4-1 Options | 4-1 |
|-------------------|-----|

4-1 Options

With near origin and end limit sensors (option code: L)

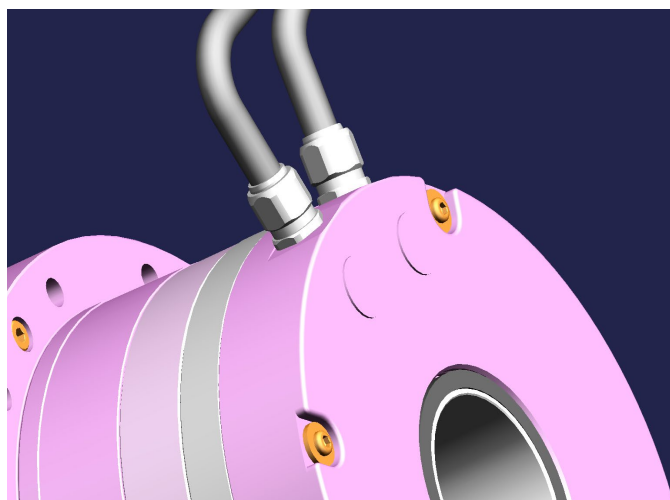
Revolution sensors are directly connected to the output shaft on the counter-output side of the actuator. Use this option if the mechanical origin is needed (when the virtual origin of the absolute encoder does not do the job) or you want to define an operation range as a safety measure. SHA20 is not compatible.

Cable taken out from side face (option code: Y)

The cables (motor and encoder wires) are taken out from the side face of the actuator. Use this option if the actuator is housed in a system and there is not enough space at the rear of the housing.

This option is not available with the SHA20 (SG type), SHA58 and SHA65.

For details on cable taken out from side face, contact our sales office.



Output shaft single revolution absolute model (option code: S)

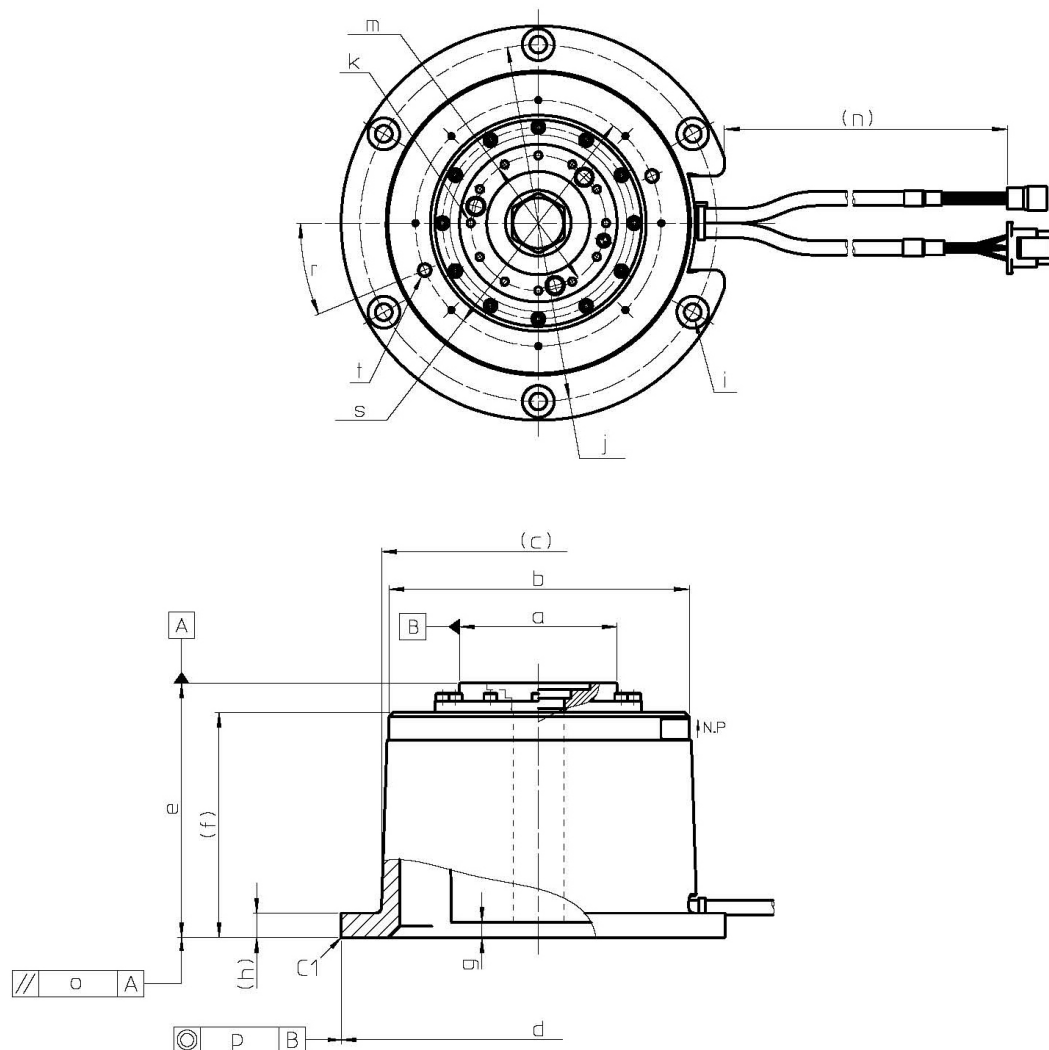
With the standard encoder, when it continues to rotate in just one direction, the absolute encoder eventually exceeds the number of revolutions that can be detected with multi-revolution detection and it becomes impossible to manage position information accurately.

With the output shaft single revolution absolute model, each time the output shaft turns through single revolution, the cumulative multi revolution counter is cleared to 0. This is how position information is accurately managed when the shaft continuously turns in just one direction. To use this function, it is necessary to setup a driver. Refer to "HA-800 Series AC Servo Driver Manual" or "HA-900 Series AC Servo Driver Manual". This model is compatible with CG type except for the model No. 20.

With stand (CG type, option code: V)

The model with an optional stand is available for purchase to use the CG type for table drive.

- Outline drawing of the actuator with an optional stand



For models with a stand, the cable is taken out from the side of the actuator (option code: Y).
Models with near home & end limit sensors (option code: L) are not supported.

● Dimensions and installation specifications of the actuator with an optional stand

| Item | Unit | SHA20 | SHA25 | SHA32 | SHA40 |
|--|------|---|---|--|--|
| a | mm | $\phi 69$ h7 0/-0.030 | $\phi 84$ h7 0/-0.035 | $\phi 110$ h7 0/-0.035 | $\phi 132$ h7 0/-0.040 |
| b | mm | $\phi 135$ | $\phi 160$ | $\phi 198$ | $\phi 248$ |
| c | mm | $\phi 143$ | $\phi 168$ | $\phi 208$ | $\phi 258$ |
| d | mm | $\phi 177$ h7 0/-0.040 | $\phi 210$ h7 0/-0.046 | $\phi 260$ h7 0/-0.052 | $\phi 316$ h7 0/-0.057 |
| e | mm | 133 ± 0.3 | 135.5 ± 0.3 | 152 ± 0.3 | 180 ± 0.3 |
| f | mm | 118 | 120 | 133 | 163 |
| g | mm | 7.5 | 8 | 8 | 10 |
| h | mm | 11 | 13 | 13 | 20 |
| i | mm | 6- $\phi 6.6$ counterbore $\phi 13$ depth 1 | 6- $\phi 9$ counterbore $\phi 17$ depth 1 | 6- $\phi 11$ counterbore $\phi 21$ depth 1 | 6- $\phi 13$ counterbore $\phi 25$ depth 1 |
| j | mm | $\phi 161$ | $\phi 190$ | $\phi 234$ | $\phi 288$ |
| k | - | 12-M4 \times 7 | 12-M5 \times 8 | 12-M6 \times 10 | 12-M8 \times 12 |
| m | mm | $\phi 60$ | $\phi 72$ | $\phi 96$ | $\phi 116$ |
| n | mm | 170 | 160 | 150 | 130 |
| o ^{Note1)} | mm | 0.050 | 0.055 | 0.060 | 0.070 |
| p ^{Note1)} | mm | $\phi 0.080$ | $\phi 0.080$ | $\phi 0.090$ | $\phi 0.100$ |
| r | ° | 60 | 22.5 | 45 | 90 |
| s | mm | $\phi 107$ | $\phi 131$ | $\phi 162$ | $\phi 203$ |
| t | mm | 2-M6 depth 11 | 2-M8 depth 13 | 2-M8 depth 15 | 2-M12 depth 23 |
| Mass ^{Note2)} | kg | 4.4 (4.5) | 6.1 (6.2) | 11.6 (11.9) | 20 (21) |
| Section i ^{Note 5)} Bolts used | - | 6-M6 | 6-M8 | 6-M10 | 6-M12 |
| Section i Recommended tightening torque | N·m | 11 | 26 | 52 | 90 |

Note 1) All values are T.I.R. (Total Indicator Reading).

2) The values in parentheses are for models with a brake.

3) For detailed dimensions and specifications of the actuator, refer to the illustrated specifications.

4) Cast aluminum is used for the material of the stand. No surface treatment has been applied.

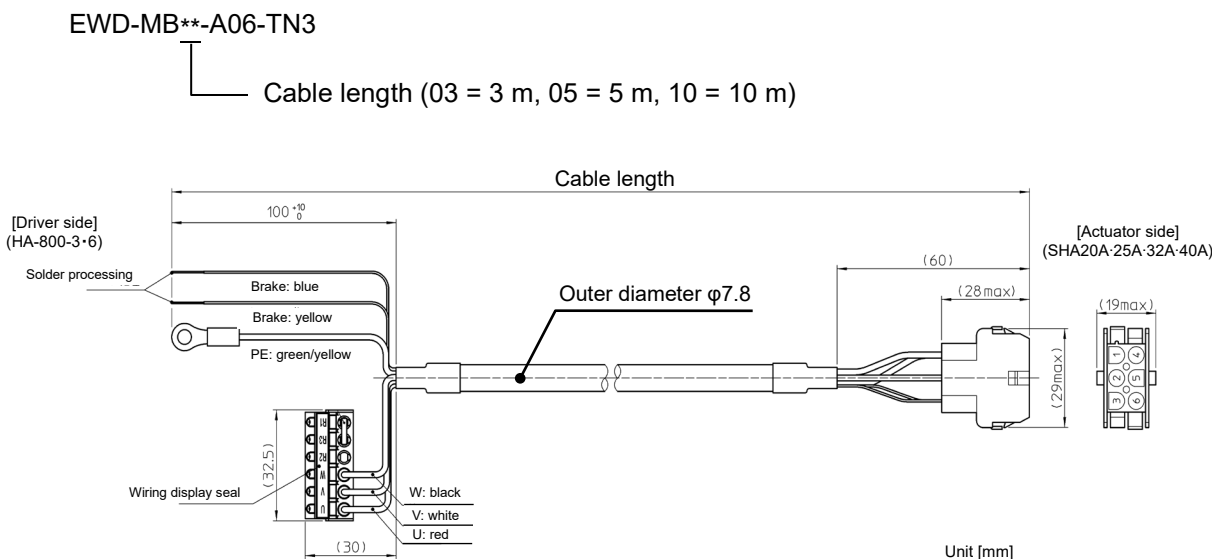
5) Use flat washers when installing the product.

Extension cables

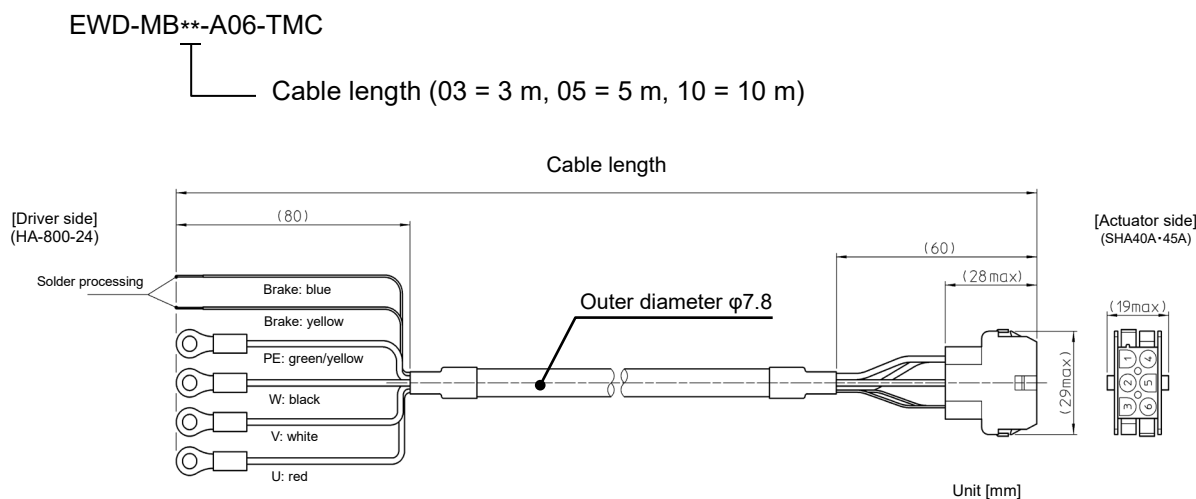
You must use an extension cable to connect your SHA series actuator and a driver.
Two types of extension cables are available for motor (including brake wire) and encoder.

Motor extension cable (HA-800):

- Actuator model Nos 20, 25, 32, 40 (Model No. 40 requires an extension cable when combined with the HA-800-6D/E.)



- Actuator model Nos 40, 45 (Model No. 40 requires an extension cable when combined with the HA-800-24D/E.)

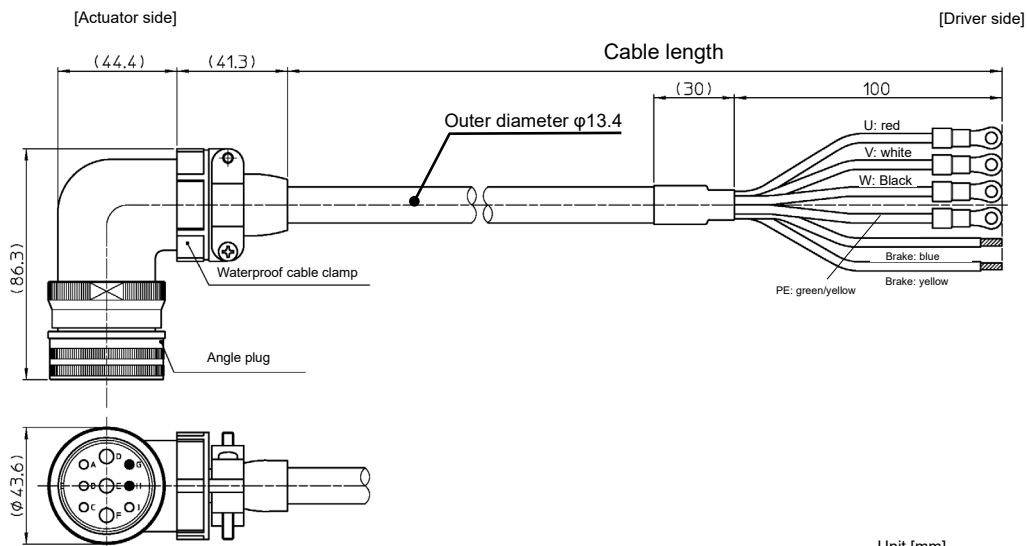


Motor extension cable (HA-800):

- **Actuator model Nos 58, 65**

EWD-MB**-D09-TMC

Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)



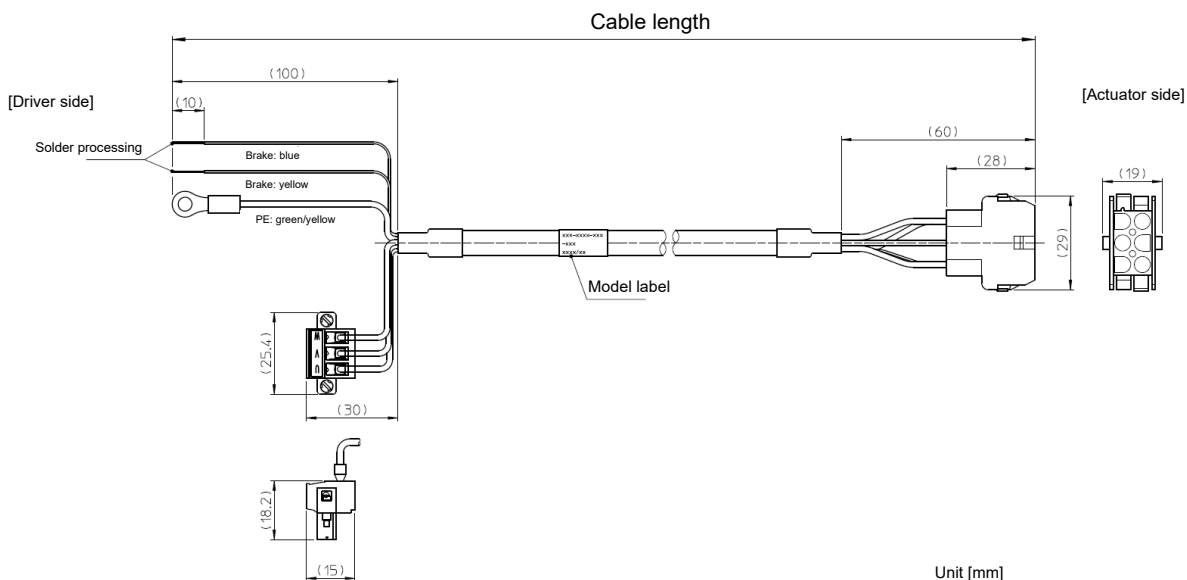
Unit [mm]

Motor extension cable (HA-900):

- **Actuator model Nos 20, 25, 32, 40 (HA-900)**

EWD-MB**-A09-TN4

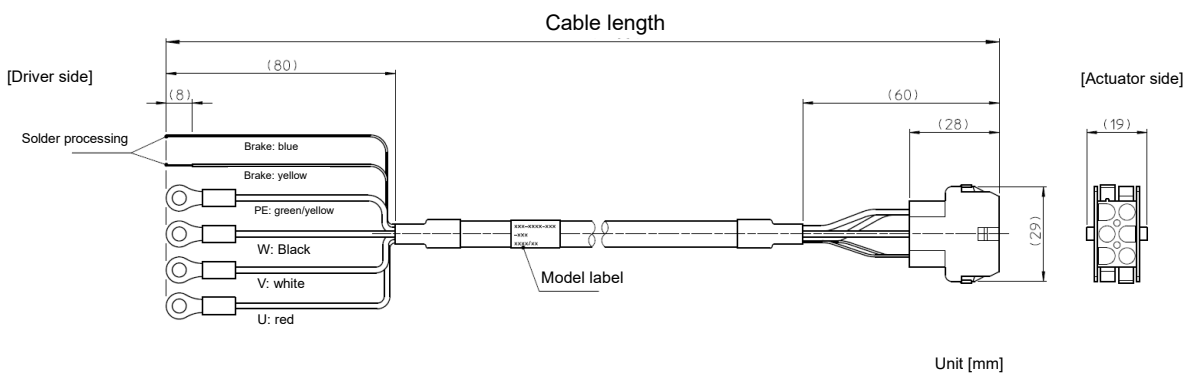
Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)



- **Actuator model No 45 (HA-900)**

EWD-MB**-A06-TM4

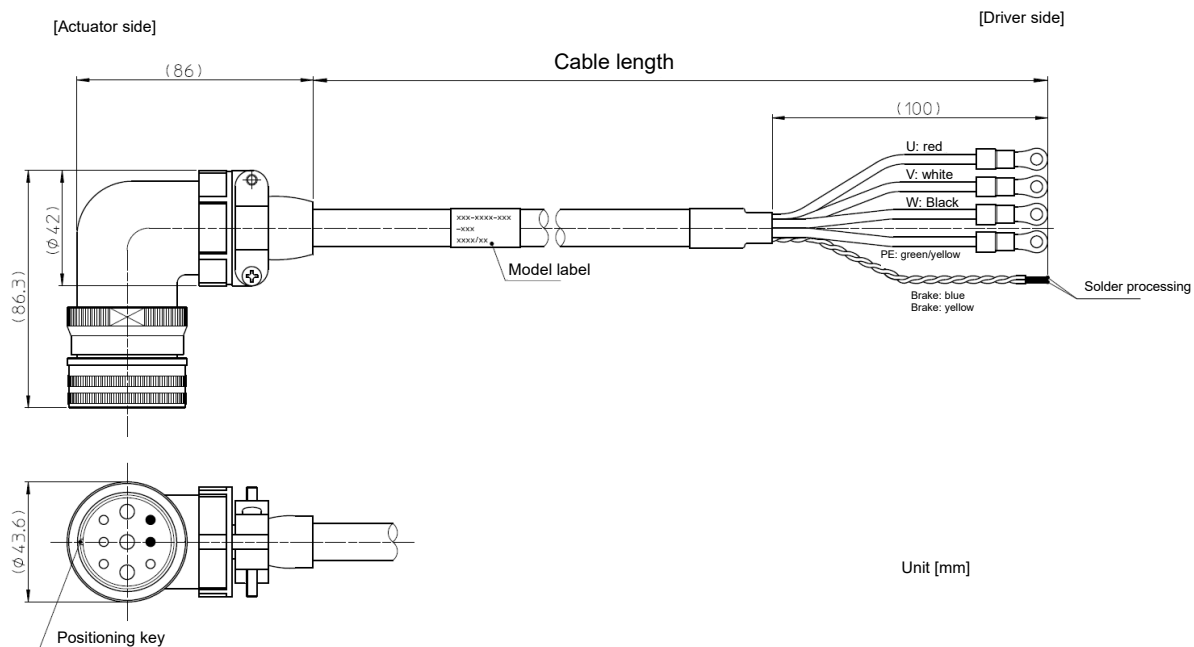
Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)



● Actuator model Nos 58, 65 (HA-900)

EWD-MB**-D09-TM4

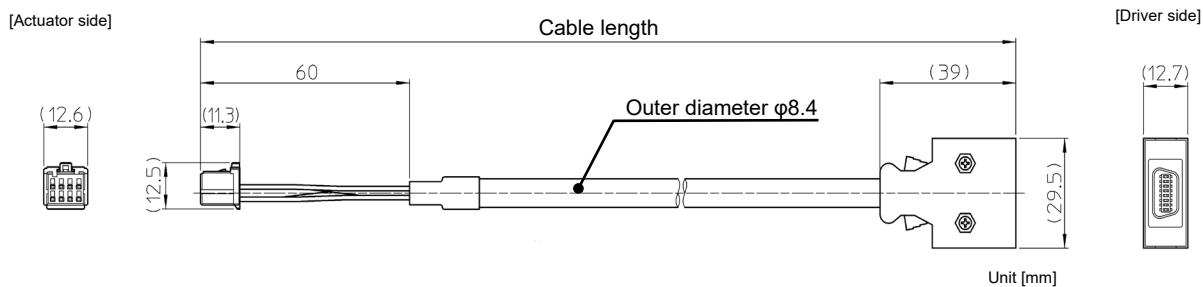
└ Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)



Encoder extension cable (HA-800):

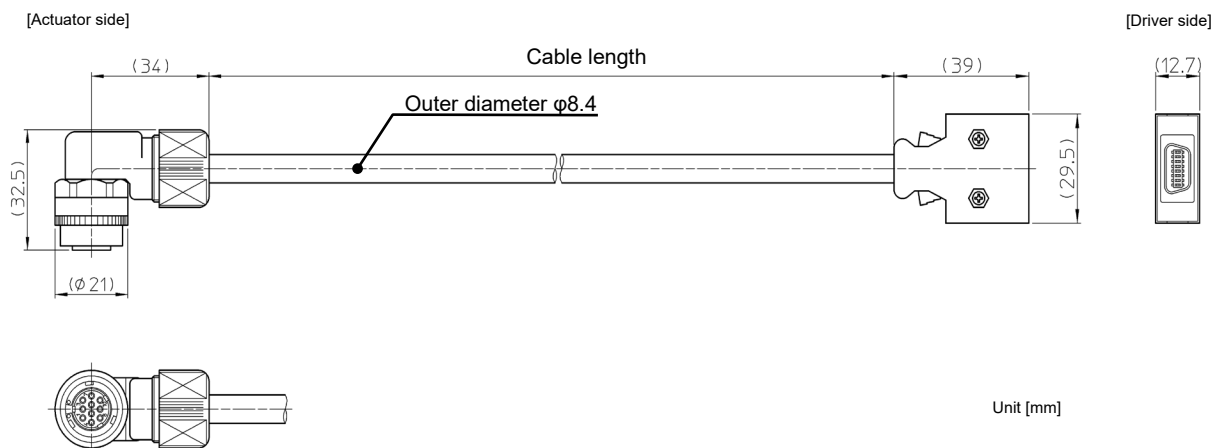
- **Actuator model Nos 20, 25, 32, 40, 45 (HA-800)**
EWD-S**-A08-3M14

Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)



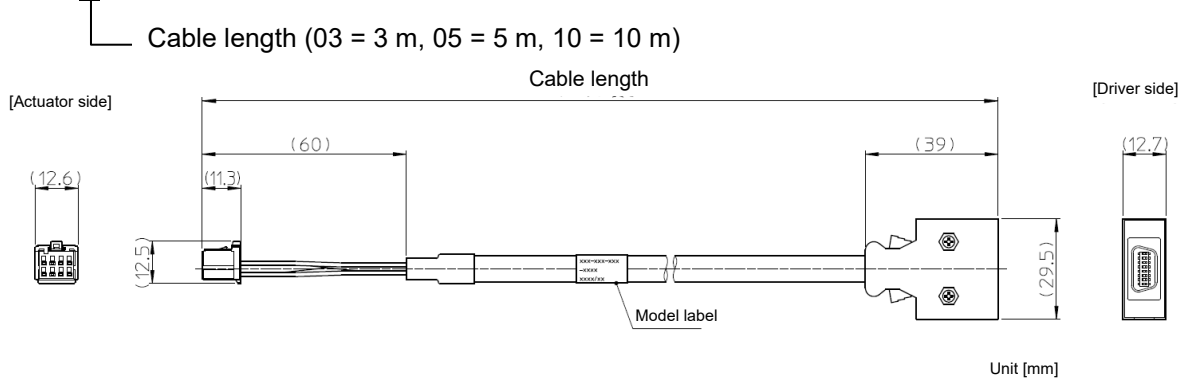
- **Actuator model Nos 58, 65 (HA-800)**
EWD-S**-D10-3M14

Cable length (03 = 3 m, 05 = 5 m, 10 = 10 m)

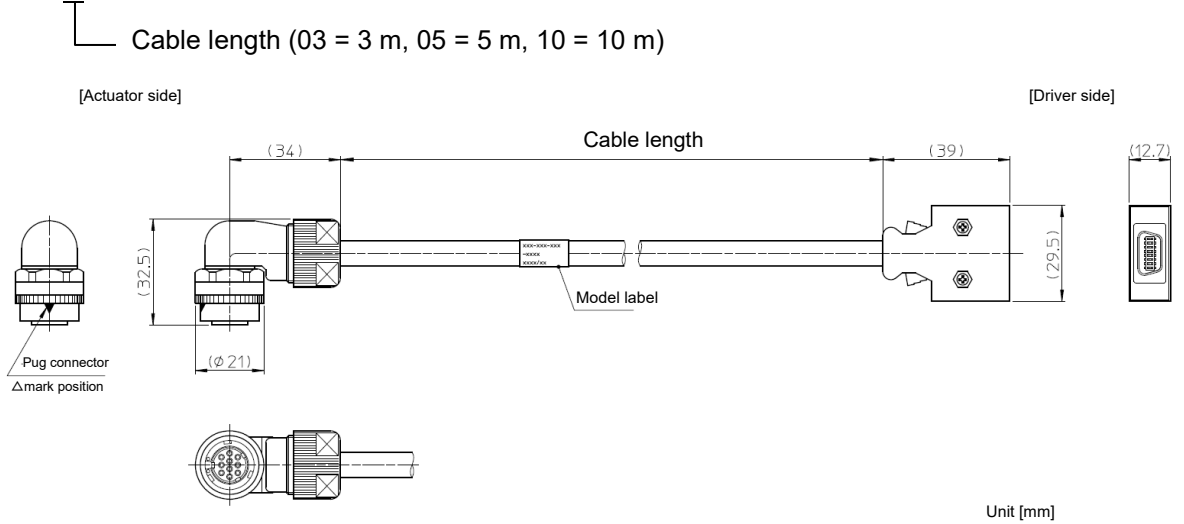


Encoder extension cable (HA-900):

- **Actuator model Nos 20, 25, 32, 40, 45 (HA-900)**
EWD-S**-A08-MDR14



- **Actuator model Nos 58, 65 (HA-900)**
EWD-S**-D10-MDR14



Caution

- Provide a sufficient bending radius (at least 6 times the cable diameter), when the cable flexes.

Appendix

| | |
|-------------------------------------|-----|
| A-1 Unit conversion..... | 5-1 |
| A-2 Calculating inertia moment..... | 5-3 |

A-1 Unit conversion

This manual employs SI system for units. Conversion factors between the SI system and other systems are as follows:

(1) Length

| | | |
|-----------|-------|-------|
| SI system | m | |
| | ↓ | |
| Unit | ft. | in. |
| Factor | 3.281 | 39.37 |

(2) Linear speed

| | | | | |
|-----------|-------|---------|-------|-------|
| SI system | m/s | | | |
| | ↓ | | | |
| Unit | m/min | ft./min | ft./s | in/s |
| Factor | 60 | 196.9 | 3.281 | 39.37 |

(3) Linear acceleration

| | | | | |
|-----------|--------------------|----------------------|--------------------|-------------------|
| SI system | m/s ² | | | |
| | ↓ | | | |
| Unit | m/min ² | ft./min ² | ft./s ² | in/s ² |
| Factor | 3600 | 1.18x10 ⁴ | 3.281 | 39.37 |

(4) Force

| | | | |
|-----------|-------|------------|------------|
| SI system | N | | |
| | ↓ | | |
| Unit | kgf | lb (force) | oz (force) |
| Factor | 0.102 | 0.225 | 4.386 |

(5) Mass

| | | |
|-----------|-------|-------|
| SI system | kg | |
| | ↓ | |
| Unit | lb. | oz. |
| Factor | 2.205 | 35.27 |

(6) Angle

| | | | |
|-----------|------|----------------------|----------------------|
| SI system | rad | | |
| | ↓ | | |
| Unit | deg. | min. | sec. |
| Factor | 57.3 | 3.44x10 ³ | 2.06x10 ⁵ |

(7) Angular speed

| | | | | |
|-----------|-------|----------------------|--------|-------|
| SI system | rad/s | | | |
| | ↓ | | | |
| Unit | deg/s | deg/min | r/s | r/min |
| Factor | 57.3 | 3.44x10 ³ | 0.1592 | 9.55 |

| | | |
|-----------|--------|--------|
| Unit | ft. | in. |
| Factor | 0.3048 | 0.0254 |
| | ↓ | |
| SI system | m | |

| | | | | |
|-----------|--------|-----------------------|--------|--------|
| Unit | m/min | ft./min | ft./s | in/s |
| Factor | 0.0167 | 5.08x10 ⁻³ | 0.3048 | 0.0254 |
| | ↓ | | | |
| SI system | m/s | | | |

| | | | | |
|-----------|------------------------|-----------------------|--------------------|-------------------|
| Unit | m/min ² | ft./min ² | ft./s ² | in/s ² |
| Factor | 2.78 x10 ⁻⁴ | 8.47x10 ⁻⁵ | 0.3048 | 0.0254 |
| | ↓ | | | |
| SI system | m/s ² | | | |

| | | | |
|-----------|------|------------|------------|
| Unit | kgf | lb (force) | oz (force) |
| Factor | 9.81 | 4.45 | 0.278 |
| | ↓ | | |
| SI system | N | | |

| | | |
|-----------|--------|---------|
| Unit | lb. | oz. |
| Factor | 0.4535 | 0.02835 |
| | ↓ | |
| SI system | kg | |

| | | | |
|-----------|---------|-----------------------|-----------------------|
| Unit | deg. | min. | sec. |
| Factor | 0.01755 | 2.93x10 ⁻⁴ | 4.88x10 ⁻⁶ |
| | ↓ | | |
| SI system | rad | | |

| | | | | |
|-----------|---------|-----------------------|------|--------|
| Unit | deg/s | deg/min | r/s | r/min |
| Factor | 0.01755 | 2.93x10 ⁻⁴ | 6.28 | 0.1047 |
| | ↓ | | | |
| SI system | rad/s | | | |

(8) Angular acceleration

| | | |
|-----------|--------------------|----------------------|
| SI system | rad/s ² | |
| ↓ | | |
| Unit | deg/s ² | deg/min ² |
| Factor | 57.3 | 3.44x10 ³ |

| | | |
|--------|--------------------|-----------------------|
| Unit | deg/s ² | deg/min ² |
| Factor | 0.01755 | 2.93x10 ⁻⁴ |

| | | |
|-----------|--------------------|--|
| SI system | rad/s ² | |
|-----------|--------------------|--|

(9) Torque

| | | | | |
|-----------|-------|-------|-------|-------|
| SI system | N·m | | | |
| ↓ | | | | |
| Unit | kgf·m | lb·ft | lb·in | oz·in |
| Factor | 0.102 | 0.738 | 8.85 | 141.6 |

| | | | | |
|--------|-------|-------|--------|-----------------------|
| Unit | kgf·m | lb·ft | lb·in | oz·in |
| Factor | 9.81 | 1.356 | 0.1130 | 7.06x10 ⁻³ |

| | | | | |
|-----------|-----|--|--|--|
| SI system | N·m | | | |
|-----------|-----|--|--|--|

(10) Inertia moment

| | | | | | | | | |
|-----------|----------------------|-----------------------|--------------------|----------------------|----------------------|----------------------|----------------------|----------------------|
| SI system | kg·m ² | | | | | | | |
| ↓ | | | | | | | | |
| Unit | kgf·m·s ² | kgf·cm·s ² | lb·ft ² | lb·ft·s ² | lb·in ² | lb·in·s ² | oz·in ² | oz·in·s ² |
| Factor | 0.102 | 10.2 | 23.73 | 0.7376 | 3.42x10 ³ | 8.85 | 5.47x10 ⁴ | 141.6 |

| | | | | | | | | |
|--------|----------------------|-----------------------|--------------------|----------------------|-----------------------|----------------------|------------------------|-----------------------|
| Unit | kgf·m·s ² | kgf·cm·s ² | lb·ft ² | lb·ft·s ² | lb·in ² | lb·in·s ² | oz·in ² | oz·in·s ² |
| Factor | 9.81 | 0.0981 | 0.0421 | 1.356 | 2.93x10 ⁻⁴ | 0.113 | 1.829x10 ⁻⁵ | 7.06x10 ⁻³ |

| | | | | | | | | |
|-----------|-------------------|--|--|--|--|--|--|--|
| SI system | kg·m ² | | | | | | | |
|-----------|-------------------|--|--|--|--|--|--|--|

(11) Torsional spring constant, moment stiffness

| | | | | | |
|-----------|-----------|------------------------|-----------------------|-----------|-----------|
| SI system | N·m/rad | | | | |
| ↓ | | | | | |
| Unit | kgf·m/rad | kgf·m/arc-min | kgf·m/deg | lb·ft/deg | lb·in/deg |
| Factor | 0.102 | 2.97 x10 ⁻⁵ | 1.78x10 ⁻³ | 0.0129 | 0.1546 |

| | | | | | |
|--------|-----------|-----------------------|-----------|-----------|-----------|
| Unit | kgf·m/rad | kgf·m/arc-min | kgf·m/deg | lb·ft/deg | lb·in/deg |
| Factor | 9.81 | 3.37 x10 ⁴ | 562 | 77.6 | 6.47 |

| | | | | | |
|-----------|---------|--|--|--|--|
| SI system | N·m/rad | | | | |
|-----------|---------|--|--|--|--|

A-2 Calculating inertia moment

Formula of mass and inertia moment

(1) The center of rotation matches the centroidal line

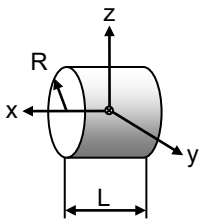
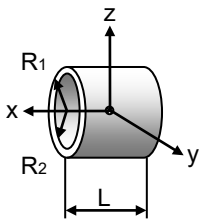
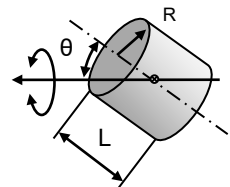
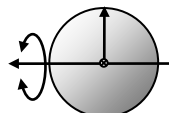
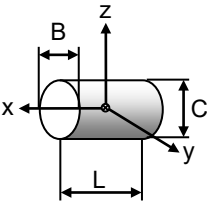
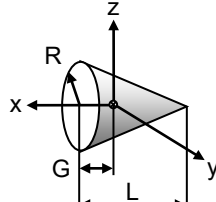
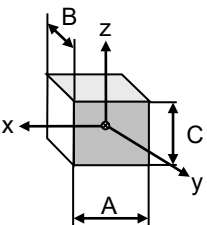
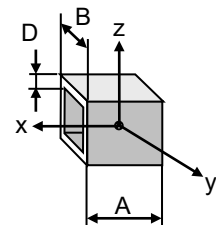
The following table includes formulas to calculate mass and inertia moment.

m: Mass [kg], I_x, I_y, I_z : inertia moments which rotate around x-, y-, z-axes respectively [kg·m²]

G: Distance from the end face to the center of gravity [m]

ρ : Specific gravity [$\times 10^3$ kg / m³]

Unit Inertia moment [kg·m²]

| Object form | Mass, inertia, gravity center | Object form | Mass, inertia, gravity center |
|---|---|---|---|
| cylinder  | $m = \pi R^2 L \rho \times 10^3$ $I_x = \frac{1}{2} m R^2$ $I_y = \frac{1}{4} m \left(R^2 + \frac{L^2}{3} \right)$ $I_z = \frac{1}{4} m \left(R^2 + \frac{L^2}{3} \right)$ | Circular pipe  | $m = \pi (R_1^2 - R_2^2) L \rho \times 10^3$ $I_x = \frac{1}{2} m (R_1^2 + R_2^2)$ $I_y = \frac{1}{4} m \left\{ (R_1^2 + R_2^2) + \frac{L^2}{3} \right\}$ $I_z = \frac{1}{4} m \left\{ (R_1^2 + R_2^2) + \frac{L^2}{3} \right\}$ <p>R₁: Outer diameter R₂: Inner diameter</p> |
| Slanted cylinder  | $m = \pi R^2 L \rho \times 10^3$ $I_\theta = \frac{1}{12} m \times \left\{ 3R^2(1 + \cos^2\theta) + L^2 \sin^2\theta \right\}$ | Ball  | $m = \frac{4}{3} \pi R^3 \rho \times 10^3$ $I = \frac{2}{5} m R^2$ |
| Ellipsoidal cylinder  | $m = \frac{1}{4} B C L \rho \times 10^3$ $I_x = \frac{1}{16} m (B^2 + C^2)$ $I_y = \frac{1}{4} m \left(\frac{C^2}{4} + \frac{L^2}{3} \right)$ $I_z = \frac{1}{4} m \left(\frac{B^2}{4} + \frac{L^2}{3} \right)$ | Cone  | $m = \frac{1}{3} \pi R^2 L \rho \times 10^3$ $I_x = \frac{3}{10} m R^2$ $I_y = \frac{3}{80} m (4R^2 + L^2)$ $I_z = \frac{3}{80} m (4R^2 + L^2)$ $G = \frac{L}{4}$ |
| Rectangular pillar  | $m = A B C \rho \times 10^3$ $I_x = \frac{1}{12} m (B^2 + C^2)$ $I_y = \frac{1}{12} m (C^2 + A^2)$ $I_z = \frac{1}{12} m (A^2 + B^2)$ | Square pipe  | $m = 4AD(B - D) \rho \times 10^3$ $I_x = \frac{1}{3} m \left\{ (B - D)^2 + D^2 \right\}$ $I_y = \frac{1}{6} m \left\{ \frac{A^2}{2} + (B - D)^2 + D^2 \right\}$ $I_z = \frac{1}{6} m \left\{ \frac{A^2}{2} + (B - D)^2 + D^2 \right\}$ |

Appe

Appendix

| Object form | Mass, inertia, gravity center | Object form | Mass, inertia, gravity center |
|----------------------------------|--|------------------------------|---|
| <p>Rhombus pillar</p> | $m = \frac{1}{2} ABC\rho \times 10^3$ $I_x = \frac{1}{24} m(B^2 + C^2)$ $I_y = \frac{1}{24} m(C^2 + 2A^2)$ $I_z = \frac{1}{24} m(B^2 + 2A^2)$ | <p>Hexagonal pillar</p> | $m = \frac{3\sqrt{3}}{2} AB^2 \rho \times 10^3$ $I_x = \frac{5}{12} mB^2$ $I_y = \frac{1}{12} m\left(A^2 + \frac{5}{2}B^2\right)$ $I_z = \frac{1}{12} m\left(A^2 + \frac{5}{2}B^2\right)$ |
| <p>Isosceles triangle pillar</p> | $m = \frac{1}{2} ABC\rho \times 10^3$ $I_x = \frac{1}{12} m\left(\frac{B^2}{2} + \frac{2}{3}C^2\right)$ $I_y = \frac{1}{12} m\left(A^2 + \frac{2}{3}C^2\right)$ $I_z = \frac{1}{12} m\left(A^2 + \frac{B^2}{2}\right)$ $G = \frac{C}{3}$ | <p>Right triangle pillar</p> | $m = \frac{1}{2} ABC\rho \times 10^3$ $I_x = \frac{1}{36} m(B^2 + C^2)$ $I_y = \frac{1}{12} m\left(A^2 + \frac{2}{3}C^2\right)$ $I_z = \frac{1}{12} m\left(A^2 + \frac{2}{3}B^2\right)$ $G_1 = \frac{C}{3} \quad G_2 = \frac{B}{3}$ |

● Example of specific gravity

The following tables show reference values for specific gravity. Check the specific gravity for each material.

| Material | Specific gravity [$\times 10^3 \text{kg} / \text{m}^3$] | Material | Specific gravity [$\times 10^3 \text{kg} / \text{m}^3$] | Material | Specific gravity [$\times 10^3 \text{kg} / \text{m}^3$] |
|-----------|--|--------------------|--|---------------------|--|
| SUS304 | 7.93 | Aluminum | 2.70 | Epoxy resin | 1.90 |
| S45C | 7.86 | Duralumin | 2.80 | ABS | 1.10 |
| SS400 | 7.85 | Silicon | 2.30 | Silicon resin | 1.80 |
| Cast iron | 7.19 | Quartz glass | 2.20 | Polyurethane rubber | 1.25 |
| Copper | 8.92 | Teflon | 2.20 | | |
| Brass | 8.50 | Fluorocarbon resin | 2.20 | | |

(2) Both centerlines of rotation and gravity are not the same:

The following formula calculates the inertia moment when the rotary center is different from the gravity center.

$$I = I_g + mF^2$$

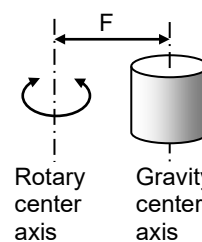
I : Inertia moment when the gravity center axis does not match the rotational axis [$\text{kg} \cdot \text{m}^2$]

I_g : Inertia moment when the gravity center axis matches the rotational axis [$\text{kg} \cdot \text{m}^2$]

Calculate according to the shape by using formula (1).

m : Mass [kg]

F : Distance between rotary center and gravity center [m]



(3) Inertia moment of linear operation objects

The inertia moment, converted to output shaft, of a linear motion object driven by a screw, etc., is calculated using the formula below.

$$I = m\left(\frac{P}{2\pi}\right)^2$$

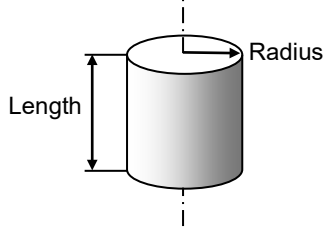
I : Inertia moment of a linear operation object converted to motor axis [$\text{kg} \cdot \text{m}^2$]

m : Mass [kg]

P : Linear travel per motor one revolution [m/rev]

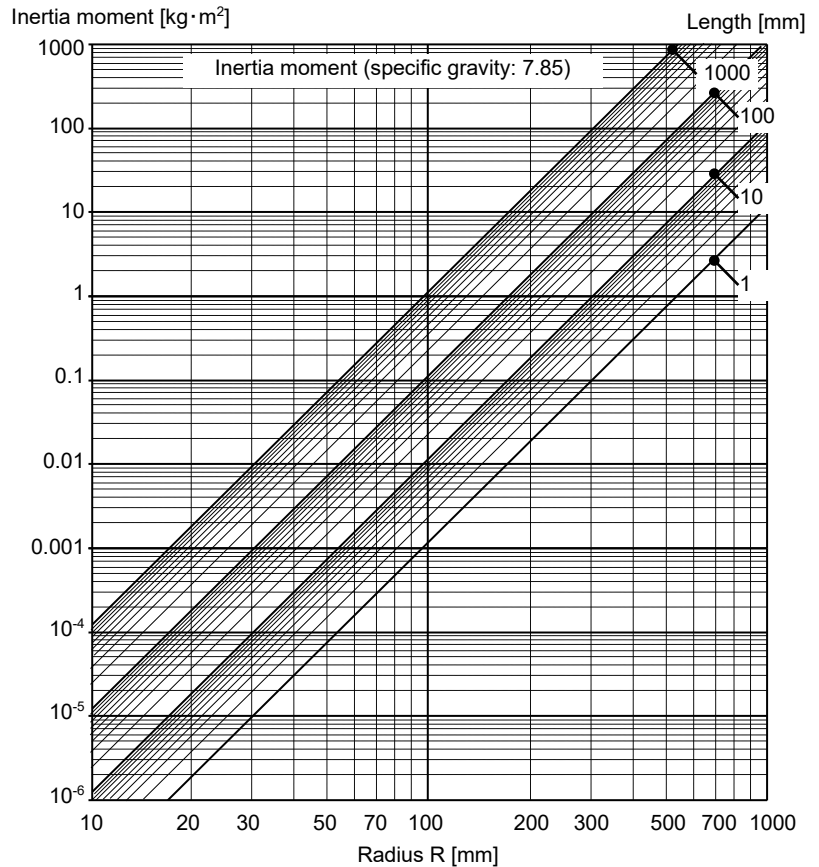
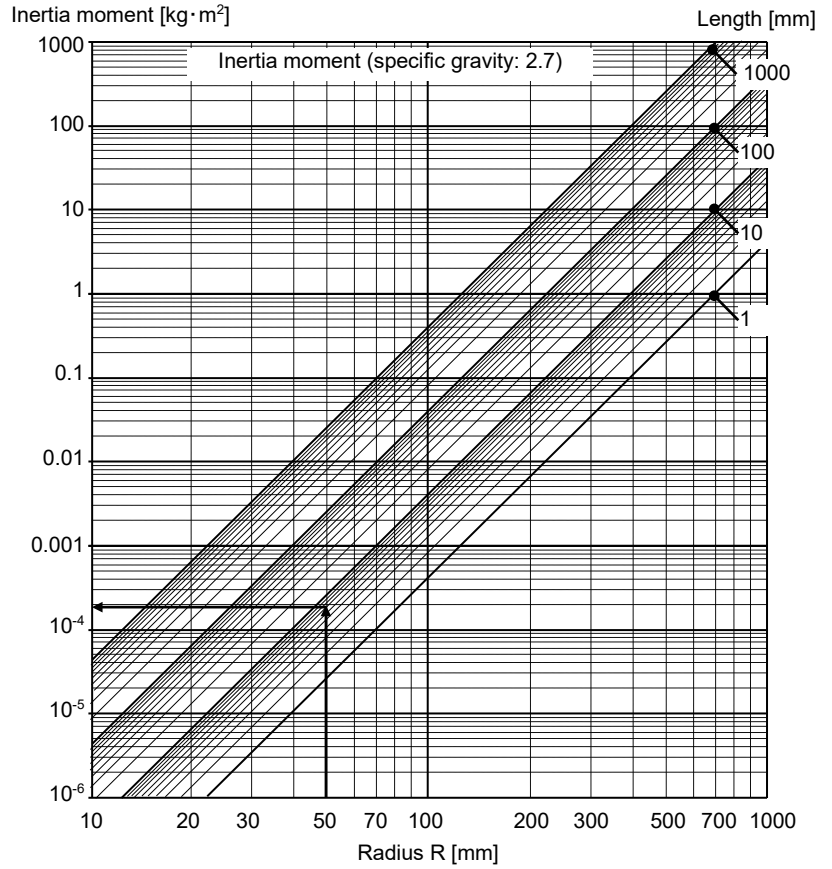
Inertia moment of cylinder

The inertia moment of a cylinder can be obtained from the graphs to the right.



Apply the top graph to aluminum materials (specific gravity: 2.7) and bottom graph to steel materials (specific gravity: 7.85):

(Example)
 Material: Aluminum
 Outer diameter: 100 [mm]
 Length: 7 [mm]
 Shape: Column
 Outer diameter: 100 [mm]
 Inner diameter: 50 [mm]
 Inertia moment:
 Approx. 1.9×10^{-4} [kg · m²] (by the graph on the right)



Appendix

Warranty Period and Terms

The equipment listed in this document is warranted as follows:

■ Warranty period

Under the condition that the actuator are handled, used and maintained properly followed each item of the documents and the manuals, all the applicable products are warranted against defects in workmanship and materials for the shorter period of either one year after delivery or 2,000 hours of operation time.

■ Warranty terms

All the applicable products are warranted against defects in workmanship and materials for the warranted period. This limited warranty does not apply to any product that has been subject to:

- (1) user's misapplication, improper installation, inadequate maintenance, or misuse.
- (2) disassembling, modification or repair by others than Harmonic Drive Systems, Inc.
- (3) imperfection caused by a non-applicable product.
- (4) disaster or others that does not belong to the responsibility of Harmonic Drive Systems, Inc.

Our liability shall be limited exclusively to repairing or replacing the product only found by Harmonic Drive Systems, Inc. to be defective. Harmonic Drive Systems, Inc. shall not be liable for consequential damages of other equipment caused by the defective products, and shall not be liable for the incidental and consequential expenses and the labor costs for detaching and installing to the driven equipment.

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