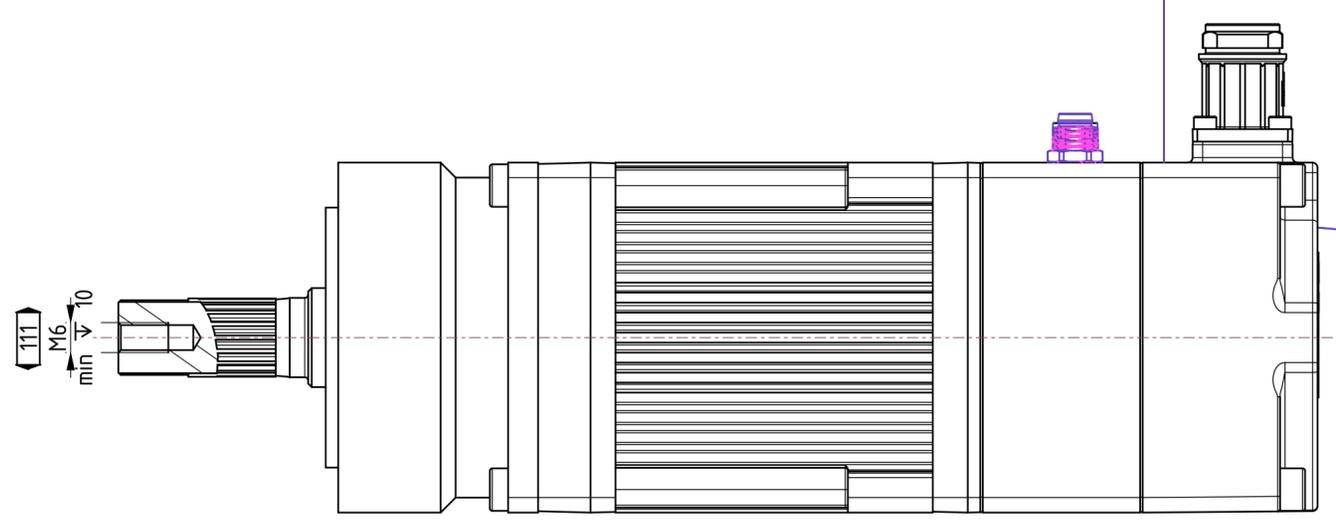
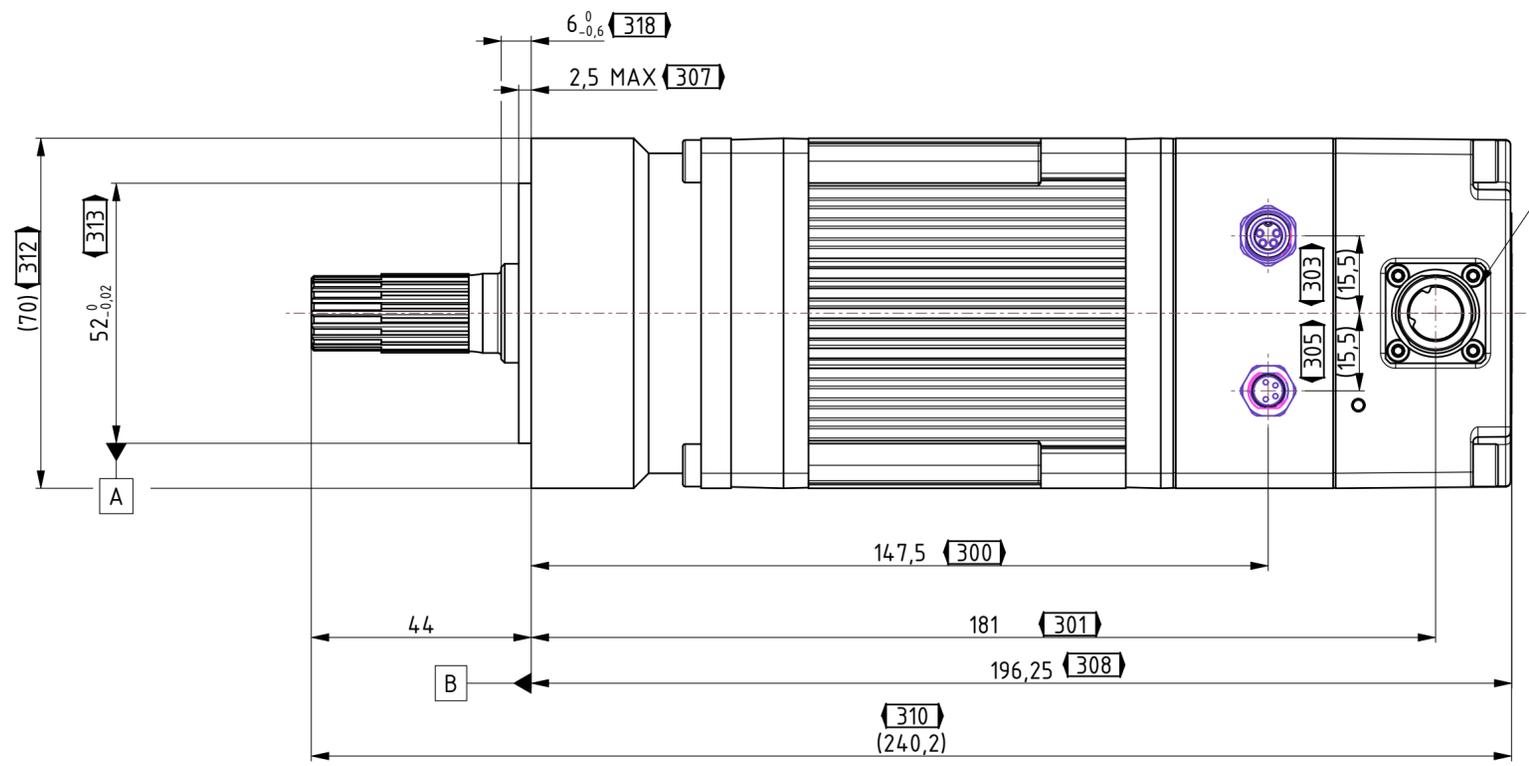
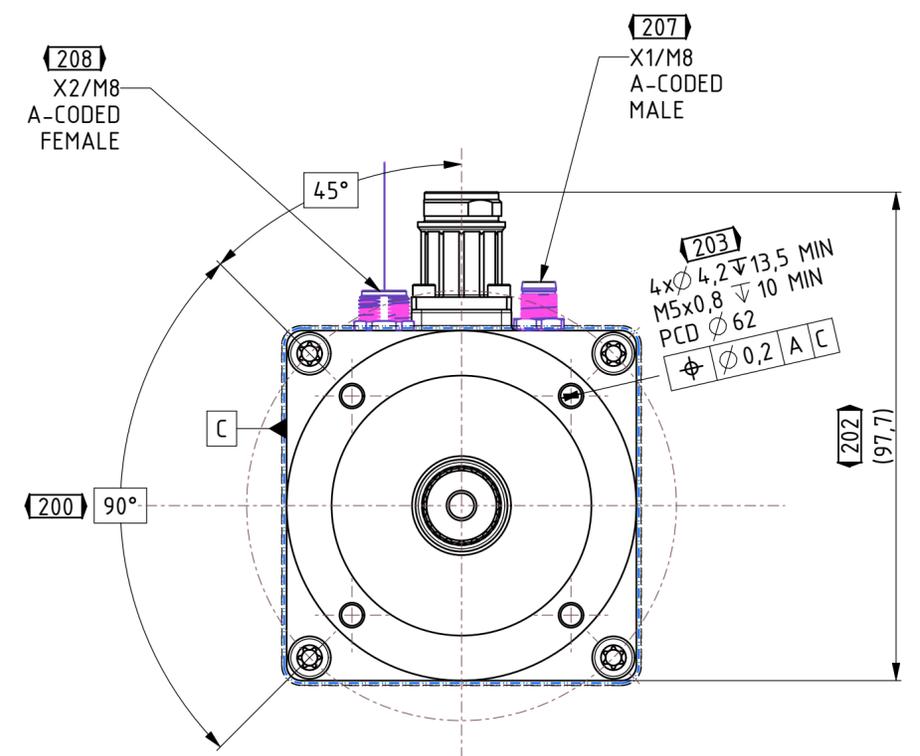


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A-A(1:1)



500
Power connector pinout:

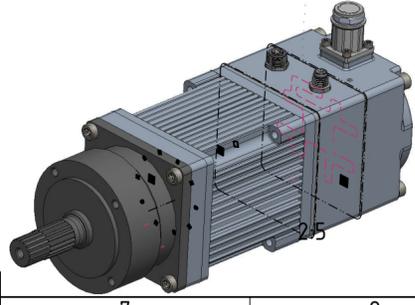
Pin number	Signal	Description
A	48V power supply	[48:60]V power supply voltage <25A
B	GND power supply	Ground for power supply <25A
C	NC	NC
PE	PE	PE
1	Logic supply	[10:26]V logic supply voltage <0.5A
2	NC	NC
+	Brake supply	[22:26]V brake supply voltage Continuous<0.5A
-	24V Brake maintain/status	[0:26]V holding brake status Continuous<0.5A

Notes : **501**

1. No axial/radial force should be applied onto output shaft until motor is fully assembled on robot

502
CAN connector pinout:

Pin Number	Signal
1	CAN-IN H
2	CAN-IN L
3	GND
4	NC



Data	Unit	Value
<i>Electrical data</i>		
Nominal power supply voltage	V DC	48
Nominal speed	RPM	4350
Nominal torque	Nm	1,25
Nominal current	A DC	14
Max. Efficiency	%	95
Nominal Power	W	570
<i>Controler data</i>		
Logic supply voltage	V DC	10-26
Protocol		CANopen CiA 301 CiA 402
<i>Other</i>		
Protection class		IP65
<i>Gearbox</i>		
Gearbox ratio		7
Allowable bending moment	Nm	125
Allowable axial force	N	1050
<i>Brake</i>		
Type		Permanent magnet
Brake Torque	Nm	2,7
Nominal Voltage	V	24
Power	W	15

Kupec/Customer Part No.	Rev	Status	Format	SAP ID	Koda/Code	Masa/Mass(kg)
	B	In Work	A2	1152395	13_2409_05	3,00
Standard	ECN	2409-26500	Merilo Scale	1:2	Naziv/Title	
	Datum Date	11.09.2025	List Sheet	1/1	BL62/45	
Izdelal Created	Martin Trček					
Hrapavost površine/Surface	KOLEKTOR					2D
						3D
						098_2409_05_ASSEMBLY_SALES/B.2
						065_2409_05_ASSEMBLY_CLIMBING/B.9