

Synchronous servo geared motors



STÖBER

Synchronous servo geared motors

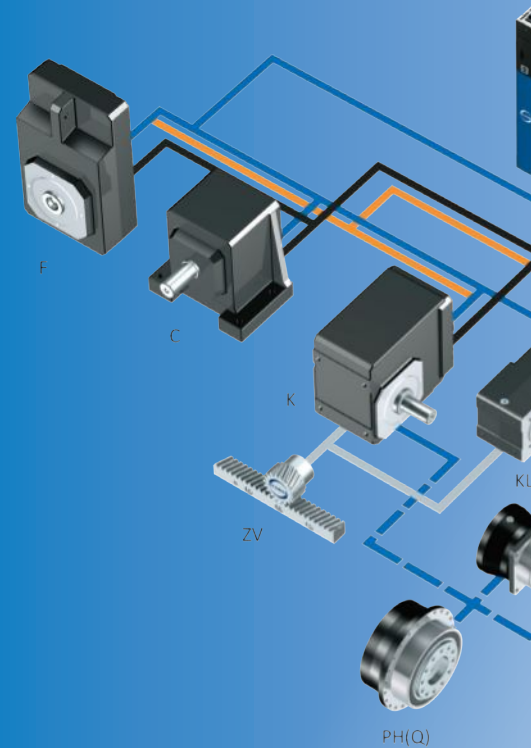
One partner. All the possibilities.

STOBER has developed and produced excellent drive technology since 1934 and is active internationally with around 1000 employees at 14 locations. STOBER impresses machine manufacturers in wide-ranging industries and markets around the world with tailor-made, highly efficient drive systems for demanding movements.



"Together with our customers, we achieve perfect motion in a wide variety of applications with our precisely coordinated system. Whenever precision, dynamics and quality are required, we are at your side as a reliable partner."

Rainer Wegener, Chief Executive Officer, STÖBER Antriebstechnik



Synchronous servo geared motors – what you can expect!

Power density redefined! Learn more about our powerhouses: STOBER synchronous servo motors of the EZ series. You will be convinced of the latest servo technology for screw drives. They are extra dynamic and efficient in direct attachment with precise, high-performing STOBER servo gearboxes. It's impossible to be more compact.

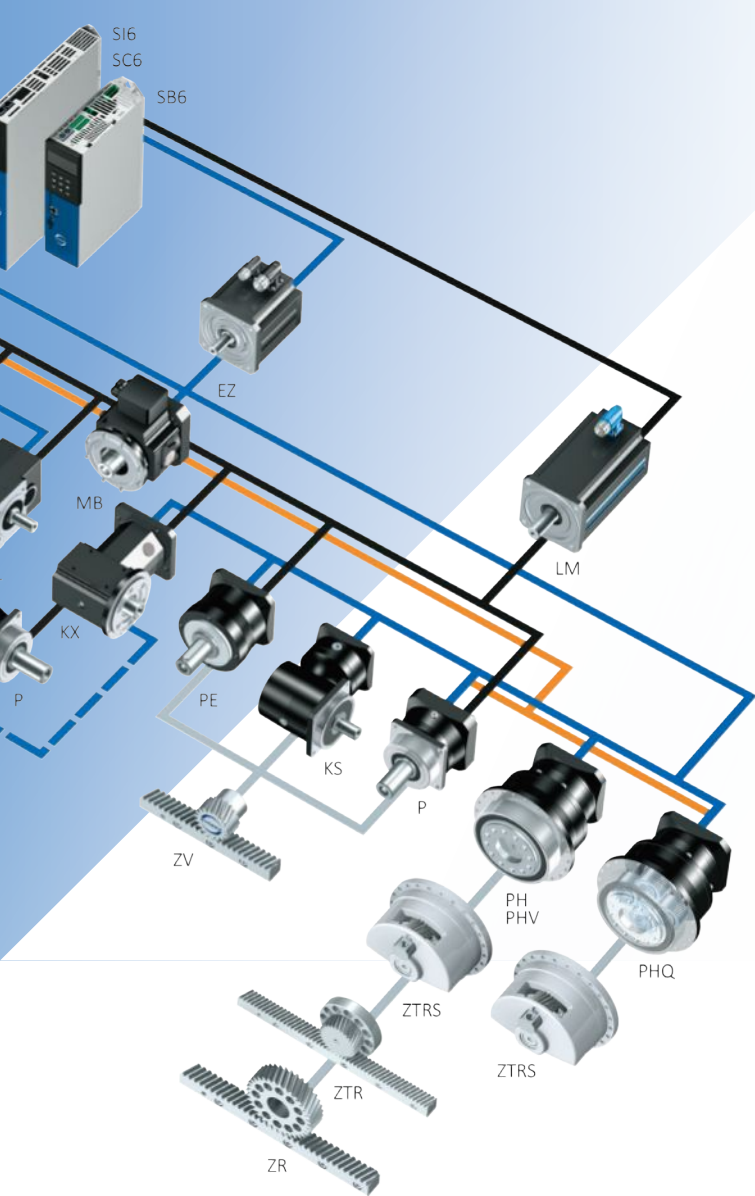
At home in the world of demanding motion

Gearboxes

Geared motors

Motors

Cables and drive controllers



Everything from a single source.

The STÖBER drive system consisting of gearboxes, motors, cables and drive controllers has a modular design and is freely scalable—for tailor-made, compact and powerful machine concepts. It can be adapted to your individual requirements and combined as needed in nearly all industries and applications areas.

We check every single component and how it works together with others, taking on the responsibility for the complete drive train. For you, this means that one contact partner, certified operating safety and maximum availability are guaranteed.

Need special solutions?

Numerous one-of-a-kind product highlights and project-related adjustments make it possible. With a holistic approach to your specific task, we work together on individualized solutions that are optimally coordinated to your requirements. Dedicated and solution-oriented in the support of your visions and projects.

STÖBER moves integrally and precisely.



"Versatile products, countless possibilities. Your perfect motion is what drives us!"

Markus Graf, Chief Sales Officer, STÖBER Antriebstechnik



STOBER moves as a team and with personality.

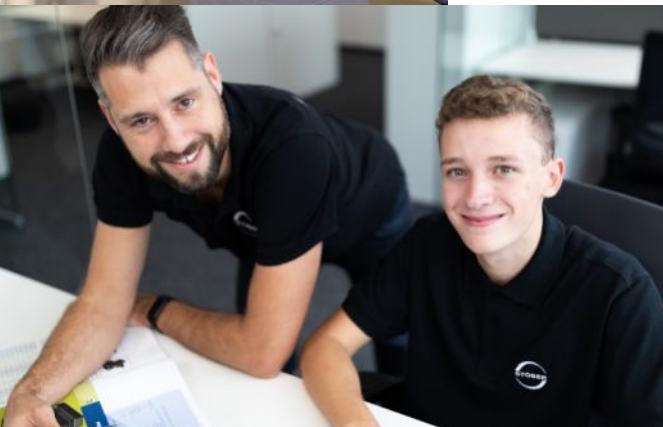
As a family-owned company, it is very important to us to maintain close relationships and treat each other with trust. We put people first.

We are committed to the well-being of our employees, identify with the expectations of our customers, and show personal commitment to mutual success.



"We have installed gearboxes, motors and drive controllers from STOBER in nearly all our systems. STOBER supports us in new projects from the first stroke of a pencil in the design phase until commissioning. Our years of cooperation are shaped by openness and honesty and emanate a rather special spirit. The technical consulting, the support—that is real, experienced partnership"

Jürgen Leicht, Managing Partner of Leicht Stanzautomation



Working together. Worldwide. Successfully.

With an eye to the future, STOBER is facing the challenges of digitalization and investing in integrated solutions and a strong global presence in production, sales and service. STOBER China was founded at the end of 2019. As a result, we are present in more than 40 countries around in the world at 12 locations and with 80 service partners.



**STOBER drives
Systems technology
Taicang, China.**



Table of contents

■	1	Selection tool.....	9
■	2	P planetary geared motors	15
■	3	PH planetary geared motors	47
■	4	PHQ planetary geared motors	71
■	5	PHV planetary geared motors.....	95
■	6	PE planetary geared motors.....	109
■	7	C helical geared motors	127
■	8	F offset helical geared motors.....	185
■	9	KS right-angle servo geared motors	233
■	10	PKX right-angle planetary geared motors	265
■	11	PK right-angle planetary geared motors	301
■	12	PHKX right-angle planetary geared motors.....	335
■	13	PHK right-angle planetary geared motors	365
■	14	PHQK right-angle planetary geared motors	397
■	15	KL helical bevel geared motors	427
■	16	K helical bevel geared motors	465
■	17	EZ synchronous servo motors	559
■	18	Connecting to drive controllers of third-party manufacturers.....	603
■	19	Close to customers around the world.....	634
■	20	Appendix	635

1 Selection tool

1.1 Inline and Offset Geared Motors



Product chapter

P

PE

C

F

Chapter number

[2]

[6]

[7]

[8]

Technical data

i	3 – 100	3 – 50	2 – 270	4.3 – 440
M_{2acc}	10 – 3450 Nm	5.7 – 250 Nm	9.7 – 6500 Nm	21 – 1100 Nm
$\Delta\phi_2$	1 – 8 arcmin	8 – 13 arcmin	10 – 20 arcmin	5 – 11 arcmin
η_{get}	95 – 97 %	95 – 97 %	96 – 97 %	96 – 97 %

An explanation of the formula symbols can be found in Chapter [\[20.1 \]](#).

Features

Power density	★★★★☆	★★★☆☆	★★☆☆☆	★☆☆☆☆
Backlash	★★★★★	★★★☆☆	★★☆☆☆	★★★☆☆
Price category	€€	€	€	€
Shaft load	★★★★☆	★★☆☆☆	★★☆☆☆	★★★☆☆
Smooth operation	★★★★☆	★★★☆☆	★★★☆☆	★★★☆☆
Torsional stiffness	★★★☆☆	★★★☆☆	★★☆☆☆	★★☆☆☆
Mass moment of inertia	★★★★★	★★★★★	★★★★★	★★★★★
Key	★★☆☆☆ good ★★★★★ excellent € Economy €€€€€ Premium			

Shaft design				
Solid shaft with feather key	✓	✓	✓	✓
Solid shaft without feather key	✓		C0 – C5: ✓ Starting at C6: Request	✓
Hollow shaft with keyway				✓
Hollow shaft with shrink ring				✓
Bearing design				
Standard	✓	✓	✓	✓
Axially reinforced	✓			
Radially reinforced	✓			
Maintenance-free				
	✓	✓	C0 – C5: ✓	✓

1 Selection tool

1.1 Inline and Offset Geared Motors



Product chapter

PH

PHQ

PHV

Chapter number

[▶ 3](#)

[\[4](#)

[▶ 5\]](#)

Technical data

i	4 – 100	5.5 – 600	61 – 121
M_{2acc}	24 – 7500 Nm	72 – 22000 Nm	1638 – 7500 Nm
$\Delta\phi_2$	1 – 4 arcmin	1 – 3 arcmin	1 – 3 arcmin
η_{get}	93 – 96 %	90 – 96 %	90 %

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

Features

Power density	★★★★☆	★★★★★	★★★★☆
Backlash	★★★★★	★★★★★	★★★★☆
Price category	€€€	€€€€	€€€
Shaft load	★★★★★	★★★★★	★★★★★
Smooth operation	★★★★☆	★★★★☆	★★★★☆
Torsional stiffness	★★★★☆	★★★★★	★★★★☆
Mass moment of inertia	★★★★★	★★★★★	★★★★★

Key
 ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Shaft design			
Flange shaft	✓	✓	✓
Bearing design			
Standard	✓	✓	✓
Reinforced	✓ (PH3 – PH5)	✓ (PHQ4 – PHQ5)	
Maintenance-free	✓	✓	✓

1 Selection tool

1.2 Right-angle geared motors



Product chapter

KS

PKX

PK

Chapter number

[▶ 9](#)

[\[10\]](#)

[▶ 11](#)

Technical data

	KS	PKX	PK
i	2 – 100	3 – 300	12 – 555
M_{2acc}	9.7 – 400 Nm	11 – 3300 Nm	68 – 3105 Nm
$\Delta\phi_2$	3 – 7 arcmin	2 – 8.5 arcmin	1.5 – 5 arcmin
η_{get}	93 – 97 %	94 – 96 %	94 %

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

Features

Power density	★★★☆☆	★★★★☆	★★★☆☆
Backlash	★★★☆☆	★★★★★	★★★★★
Price category	€€€	€€€	€€€
Shaft load	★★★★★	★★★★☆	★★★★☆
Smooth operation	★★★★☆	★★★☆☆	★★★☆☆
Torsional stiffness	★★★☆☆	★★★☆☆	★★★☆☆
Mass moment of inertia	★★★★★	★★★☆☆	★★★★★
Key	★★★☆☆ good ★★★★★ excellent € Economy €€€€€ Premium		

Shaft design	KS	PKX	PK
Solid shaft with feather key	✓	✓	✓
Solid shaft without feather key	✓	✓	✓
Hollow shaft with shrink ring	✓		
Flange hollow shaft	✓		
Bearing design	KS	PKX	PK
Standard	✓	✓	✓
Axially reinforced		✓	✓
Radially reinforced		✓	✓
Maintenance-free	KS	PKX	PK
	✓	✓	✓

1 Selection tool

1.2 Right-angle geared motors



Product chapter

KS

PHKX

PHK

PHQK

Chapter number

[9]

[12]

[13]

[14]

Technical data

i	2 – 100	4 – 210	16 – 555	22 – 2242
M_{2acc}	9.7 – 400 Nm	26 – 6975 Nm	89 – 7500 Nm	123 – 43000 Nm
$\Delta\phi_2$	3 – 7 arcmin	1 – 6 arcmin	1.5 – 4.5 arcmin	1.5 – 4 arcmin
η_{get}	93 – 97 %	92 – 95 %	92 – 93 %	90 – 93 %

An explanation of the formula symbols can be found in Chapter [20.1].

Features

Power density	★★★☆☆	★★★★★	★★★★☆	★★★★★
Backlash	★★★☆☆	★★★★★	★★★★★	★★★★★
Price category	€€€	€€€€	€€€€	€€€€€
Shaft load	★★★★★	★★★★★	★★★★★	★★★★★
Smooth operation	★★★★☆	★★☆☆☆	★★★★☆	★★★☆☆
Torsional stiffness	★★★☆☆	★★★★☆	★★★★☆	★★★★★
Mass moment of inertia	★★★★★	★★★☆☆	★★★★★	★★★★★
Key	★★☆☆☆ good ★★★★★ excellent € Economy €€€€€ Premium			

Shaft design				
Solid shaft with feather key	✓			
Solid shaft without feather key	✓			
Hollow shaft with shrink ring	✓			
Flange hollow shaft	✓			
Flange shaft		✓	✓	✓
Bearing design				
Standard	✓	✓	✓	✓
Reinforced		✓ (PH3 – PH5)	✓ (PH5)	✓ (PHQ5)
Maintenance-free	✓	✓	✓	✓

1 Selection tool

1.2 Right-angle geared motors



Product chapter

KL

K

Chapter number

[▶ 15](#)

[\[16\]](#)

Technical data

i	4 – 32	4 – 381
M_{2acc}	10 – 65 Nm	23 – 12750 Nm
$\Delta\phi_2$	16 – 25 arcmin	1.5 – 12 arcmin
η_{get}	97 %	94 – 97 %

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

Features

Power density	★★☆☆☆	★★☆☆☆
Backlash	★★☆☆☆	★★★★☆
Price category	€	€€
Shaft load	★★☆☆☆	★★☆☆☆
Smooth operation	★★☆☆☆	★★☆☆☆
Torsional stiffness	★★☆☆☆	★★☆☆☆
Mass moment of inertia	★★★★★	★★★★★
Key	★★☆☆☆ good ★★★★★ excellent € Economy €€€€€ Premium	

Shaft design		
Solid shaft with feather key	✓	✓
Solid shaft without feather key	✓	K1 – K4: ✓ Starting at K5: Request
Solid shaft on both sides	✓	✓
Hollow shaft with keyway	✓	✓
Hollow shaft with shrink ring	✓	✓

Accessories		
Flange	✓	✓
Foot plates	✓	✓
Torque arm bracket	KL2: ✓	✓

Bearing design		
Standard	✓	✓

Maintenance-free	✓	K1 – K4: ✓
-------------------------	---	------------

1 Selection tool

1.3 Synchronous servo motors



Product chapter

EZ

Chapter number

[▶ 17](#)

Technical data

M_N	0.4 – 91 Nm
M_0	0.44 – 100 Nm

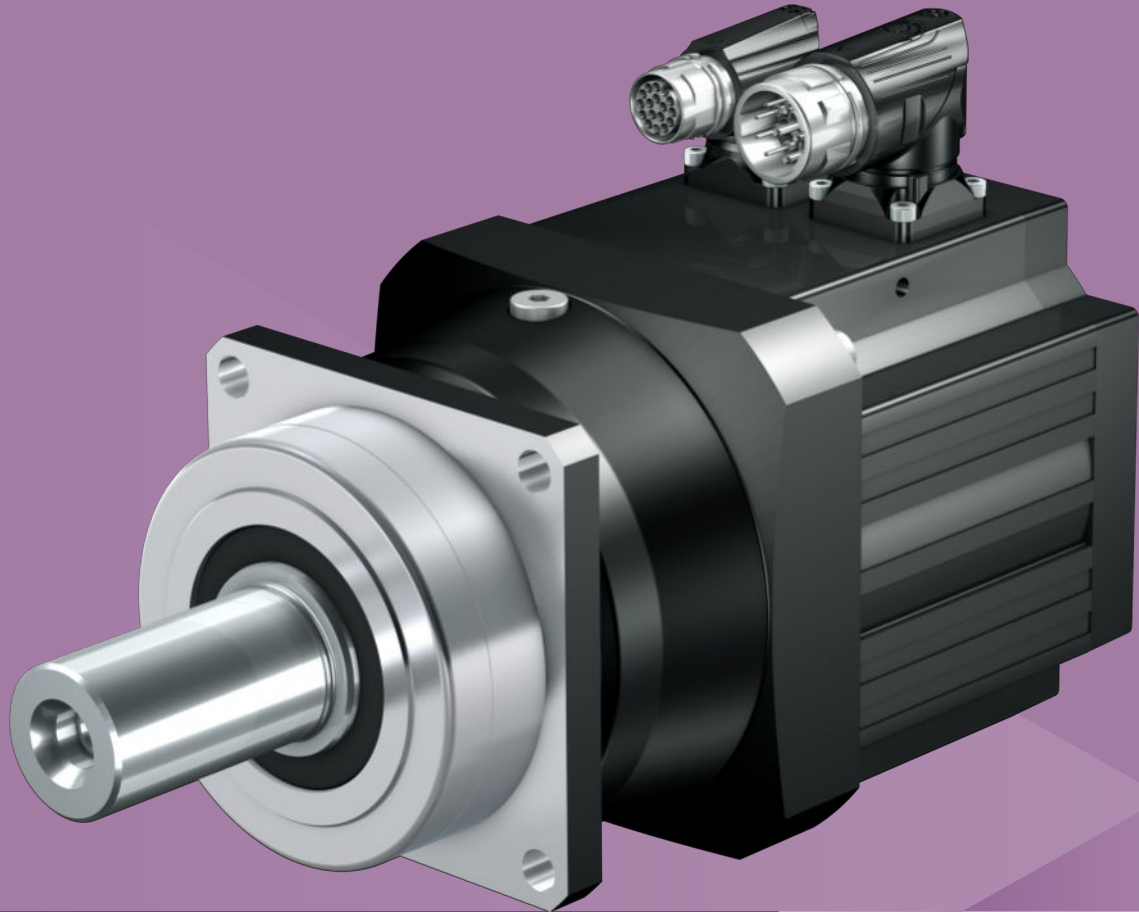
An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

Shaft design	
Solid shaft without feather key	✓
Encoder	
EnDat 3 One Cable Solution (OCS)	✓
EnDat 2.2	✓
EnDat 2.1	✓
Resolvers	✓
Cooling	
Convection cooling	✓
Forced ventilation	✓
Brake	
Permanent magnet holding brake	✓
Marks and test symbols	
CE	✓
cURus	✓
UKCA	✓

2 P planetary geared motors

Table of contents

2.1	Overview	16
2.2	Selection tables	17
2.3	Dimensional drawings	31
2.3.1	G shaft design (solid shaft without feather key)	32
2.3.2	P shaft design (solid shaft with feather key)	34
2.4	Type designation	36
2.5	Product description	36
2.5.1	Input options	36
2.5.2	Installation conditions	37
2.5.3	Lubricants	37
2.5.4	Position of the plug connectors	37
2.5.5	Other product features	38
2.5.6	Direction of rotation.....	38
2.6	Project configuration.....	38
2.6.1	Drive selection.....	39
2.6.2	Permitted shaft loads for the output shaft	43
2.6.3	Recommendation for radial shaft seal rings	45
2.6.4	Reverse operation	46
2.7	Additional documentation	46



2

Planetary geared motors

P

2.1 Overview

Helical-gear precision planetary geared motors

Features

Power density	★★★★☆
Backlash	★★★★★
Price category	€€
Shaft load	★★★★☆
Smooth operation	★★★★☆
Torsional stiffness	★★★☆☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
Any mounting position	✓
Continuous operation without cooling	✓
Reinforced output bearing	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	3 – 100
M_{2acc}	10 – 3450 Nm
$\Delta\phi_2$	1 – 8 arcmin
η_{get}	95 – 97 %

2.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)
- M_{2acc} , M_{2accHT} : Solid shaft design without feather key (we generally recommend this shaft design for cyclic operation)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_2$ [arcmin]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
P2 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 25 \text{ Nm}$)																	
188	14	14	5.8	1.1	P232_0160 EZ301U	24	–	48	16.00	16/1	6000	8000	0.23	8.0	–	1.8	2.9
300	9.0	9.2	1.1	1.1	P231_0100 EZ301U	21	–	41	10.00	10/1	6000	8000	0.20	6.0	–	1.6	2.3
375	7.2	7.4	1.2	1.7	P231_0080 EZ301U	21	–	41	8.000	8/1	6000	8000	0.20	6.0	–	1.7	2.3
429	6.3	6.5	1.3	2.1	P231_0070 EZ301U	19	–	46	7.000	7/1	6000	8000	0.20	6.0	–	1.8	2.3
429	11	11	2.2	1.3	P231_0070 EZ302U	23	–	46	7.000	7/1	6000	8000	0.30	6.0	–	1.8	2.9
600	4.5	4.6	1.9	3.0	P231_0050 EZ301U	14	–	51	5.000	5/1	6000	8000	0.22	6.0	–	1.9	2.3
600	7.7	8.1	3.3	1.8	P231_0050 EZ302U	24	–	51	5.000	5/1	6000	8000	0.32	6.0	–	1.9	2.9
600	10	11	4.3	1.3	P231_0050 EZ303U	25	–	51	5.000	5/1	6000	8000	0.43	6.0	–	1.9	3.4
750	3.6	3.7	2.5	3.7	P231_0040 EZ301U	11	–	51	4.000	4/1	6000	8000	0.24	6.0	–	1.9	2.3
750	6.2	6.5	4.3	2.2	P231_0040 EZ302U	19	–	51	4.000	4/1	6000	8000	0.34	6.0	–	1.9	2.9
750	8.0	8.5	5.6	1.7	P231_0040 EZ303U	25	–	51	4.000	4/1	6000	8000	0.45	6.0	–	1.9	3.4
P2 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 25 \text{ Nm}$)																	
171	13	15	1.9	1.0	P232_0350 EZ202U	25	–	51	35.00	35/1	6000	8000	0.14	8.0	–	1.8	2.8
188	12	13	2.1	1.1	P232_0320 EZ202U	21	–	41	32.00	32/1	6000	8000	0.17	8.0	–	1.7	2.8
214	11	12	2.3	1.2	P232_0280 EZ202U	24	–	48	28.00	28/1	6000	8000	0.14	8.0	–	1.8	2.8
240	9.5	10	2.4	1.4	P232_0250 EZ202U	25	–	51	25.00	25/1	6000	8000	0.15	8.0	–	1.8	2.8
300	7.6	8.4	2.7	1.7	P232_0200 EZ202U	25	–	51	20.00	20/1	6000	8000	0.17	8.0	–	1.8	2.8
300	12	13	4.1	1.1	P232_0200 EZ203U	25	–	51	20.00	20/1	6000	8000	0.21	8.0	–	1.8	3.0
375	6.1	6.7	3.0	2.2	P232_0160 EZ202U	22	–	48	16.00	16/1	6000	8000	0.17	8.0	–	1.8	2.8
375	9.3	10	4.6	1.4	P232_0160 EZ203U	24	–	48	16.00	16/1	6000	8000	0.21	8.0	–	1.8	3.0
600	3.9	4.3	0.6	2.1	P231_0100 EZ202U	14	–	41	10.00	10/1	6000	8000	0.13	6.0	–	1.6	2.2
600	5.9	6.7	0.9	1.4	P231_0100 EZ203U	21	–	41	10.00	10/1	6000	8000	0.17	6.0	–	1.6	2.5
750	3.1	3.4	0.7	3.0	P231_0080 EZ202U	11	–	41	8.000	8/1	6000	8000	0.14	6.0	–	1.7	2.2
750	4.7	5.4	1.0	2.0	P231_0080 EZ203U	21	–	41	8.000	8/1	6000	8000	0.18	6.0	–	1.7	2.5
750	6.9	7.4	1.5	1.4	P231_0080 EZ301U	21	–	41	8.000	8/1	6000	8000	0.20	6.0	–	1.7	2.3
857	2.7	3.0	0.7	3.9	P231_0070 EZ202U	10	–	46	7.000	7/1	6000	8000	0.14	6.0	–	1.8	2.2
857	4.1	4.7	1.1	2.6	P231_0070 EZ203U	18	–	46	7.000	7/1	6000	8000	0.18	6.0	–	1.8	2.5
857	6.0	6.5	1.6	1.8	P231_0070 EZ301U	19	–	46	7.000	7/1	6000	8000	0.20	6.0	–	1.8	2.3
857	10	11	2.6	1.1	P231_0070 EZ302U	23	–	46	7.000	7/1	6000	8000	0.30	6.0	–	1.8	2.9
1200	3.0	3.3	1.6	3.6	P231_0050 EZ203U	13	–	51	5.000	5/1	6000	8000	0.20	6.0	–	1.9	2.5
1200	4.3	4.6	2.3	2.5	P231_0050 EZ301U	14	–	51	5.000	5/1	6000	8000	0.22	6.0	–	1.9	2.3
1200	7.3	8.1	3.9	1.5	P231_0050 EZ302U	24	–	51	5.000	5/1	6000	8000	0.32	6.0	–	1.9	2.9
1200	9.5	11	5.1	1.1	P231_0050 EZ303U	25	–	51	5.000	5/1	6000	8000	0.43	6.0	–	1.9	3.4
1500	2.4	2.7	2.1	4.5	P231_0040 EZ203U	10	–	51	4.000	4/1	6000	8000	0.21	6.0	–	1.9	2.5
1500	3.5	3.7	3.0	3.1	P231_0040 EZ301U	11	–	51	4.000	4/1	6000	8000	0.24	6.0	–	1.9	2.3
1500	5.8	6.5	5.1	1.8	P231_0040 EZ302U	19	–	51	4.000	4/1	6000	8000	0.34	6.0	–	1.9	2.9
1500	7.6	8.7	6.7	1.4	P231_0040 EZ303U	25	–	51	4.000	4/1	6000	8000	0.45	6.0	–	1.9	3.4
P3 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 75 \text{ Nm}$)																	
60	44	45	1.2	1.1	P332_0500 EZ301U	75	75	150	50.00	50/1	6000	8000	0.20	5.0	3.0	5.0	3.4
75	35	36	1.6	1.2	P332_0400 EZ301U	65	65	130	40.00	40/1	6000	8000	0.20	5.0	3.0	4.8	3.4
86	31	32	1.4	1.6	P332_0350 EZ301U	75	75	150	35.00	35/1	6000	8000	0.20	5.0	3.0	5.2	3.4
94	28	29	1.5	1.7	P332_0320 EZ301U	63	65	126	32.00	32/1	5500	8000	0.23	5.0	3.0	4.6	3.4
94	48	51	2.6	1.0	P332_0320 EZ302U	63	65	126	32.00	32/1	5500	8000	0.33	5.0	3.0	4.6	4.0
107	25	25	1.8	1.8	P332_0280 EZ301U	65	70	130	28.00	28/1	6000	8000	0.22	5.0	3.0	5.1	3.4
107	42	45	3.0	1.1	P332_0280 EZ302U	65	70	130	28.00	28/1	6000	8000	0.32	5.0	3.0	5.1	4.0
120	22	23	1.7	2.3	P332_0250 EZ301U	67	67	150	25.00	25/1	6000	8000	0.21	5.0	3.0	5.2	3.4
120	38	40	2.9	1.3	P332_0250 EZ302U	75	75	150	25.00	25/1	6000	8000	0.31	5.0	3.0	5.2	4.0
120	49	52	3.8	1.0	P332_0250 EZ303U	75	75	150	25.00	25/1	6000	8000	0.42	5.0	3.0	5.2	4.5
150	18	18	1.9	2.8	P332_0200 EZ301U	53	53	150	20.00	20/1	5500	8000	0.23	5.0	3.0	5.3	3.4
150	30	32	3.2	1.7	P332_0200 EZ302U	75	75	150	20.00	20/1	5500	8000	0.33	5.0	3.0	5.3	4.0
150	39	42	4.2	1.3	P332_0200 EZ303U	75	75	150	20.00	20/1	5500	8000	0.44	5.0	3.0	5.3	4.5

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_2$ [arcmin]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
P9 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 3300 \text{ Nm}$)																	
57	1676	2906	1.1	1.4	P932_0700 EZ813U	3156	–	6312	70.00	70/1	2800	4500	107	4.0	–	372	93
57	1736	4465	1.1	1.3	P932_0700 EZ815U	3156	–	6312	70.00	70/1	2800	4500	170	4.0	–	372	106
80	1197	2076	1.2	1.9	P932_0500 EZ813U	3200	–	6400	50.00	50/1	2800	4500	107	4.0	–	399	93
80	1240	3189	1.3	1.8	P932_0500 EZ815U	3200	–	6400	50.00	50/1	2800	4500	170	4.0	–	399	106
100	958	1661	1.6	2.1	P932_0400 EZ813U	3000	–	6000	40.00	40/1	2800	4500	107	4.0	–	394	93
100	992	2551	1.6	2.0	P932_0400 EZ815U	3000	–	6000	40.00	40/1	2800	4500	170	4.0	–	394	106
114	838	1453	1.5	2.7	P932_0350 EZ813U	3300	–	6600	35.00	35/1	2800	4500	110	4.0	–	404	93
114	868	2232	1.5	2.6	P932_0350 EZ815U	3300	–	6600	35.00	35/1	2800	4500	173	4.0	–	404	106
143	670	1162	1.7	3.4	P932_0280 EZ813U	3000	–	6000	28.00	28/1	2800	4500	110	4.0	–	402	93
143	695	1786	1.7	3.3	P932_0280 EZ815U	3000	–	6000	28.00	28/1	2800	4500	173	4.0	–	402	106
160	599	1038	1.8	3.8	P932_0250 EZ813U	3300	–	6600	25.00	25/1	2500	4000	115	4.0	–	407	93
160	620	1595	1.8	3.7	P932_0250 EZ815U	3300	–	6600	25.00	25/1	2500	4000	178	4.0	–	407	106

2.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

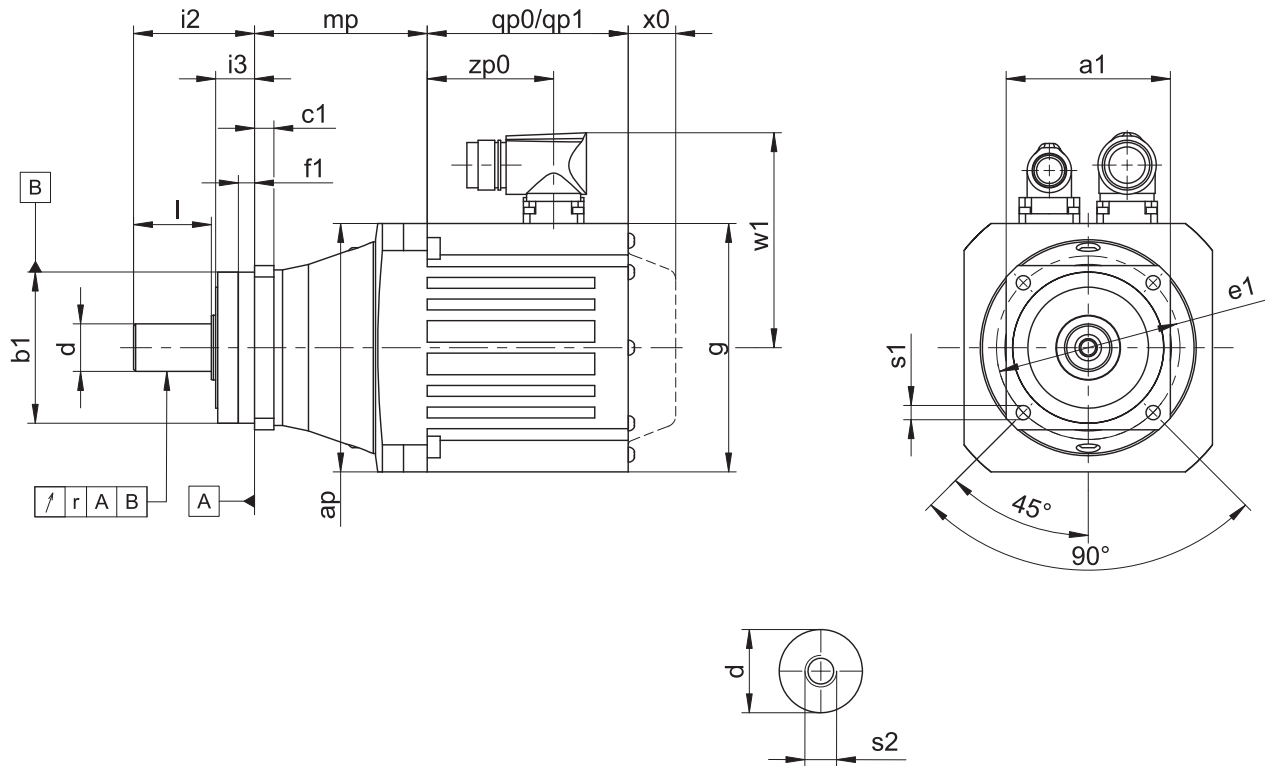
Tolerances

Solid shaft	Tolerance
Fit	ISO k6
Feather keys	DIN 6885-1, high form A
Balancing	With half feather key

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

2.3.1 G shaft design (solid shaft without feather key)



- qp0 Applies to motors without brake.
- qp1 Applies to motors with brake.
- x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method
- w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)
- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	Øb1	c1	Ød	Øe1	f1	i2	i3	l	r	Øs1	s2
P231	55	50 _{h6}	6	12 _{k6}	63	7.0	36	12	22	-	5.5	M4
P232	55	50 _{h6}	6	12 _{k6}	63	7.0	36	12	22	-	5.5	M4
P331	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	28	0.025	5.5	M5
P332	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	28	0.025	5.5	M5
P431	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	36	0.025	6.6	M8
P432	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	36	0.025	6.6	M8
P531	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	58	0.030	9.0	M12
P532	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	58	0.030	9.0	M12
P731	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	82	0.035	11.0	M16
P732	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	82	0.035	11.0	M16
P831	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	82	0.035	13.5	M20
P832	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	82	0.035	13.5	M20
P932	212	180 _{h6}	17	75 _{k6}	250	10.0	143	34	105	0.040	17.5	M20

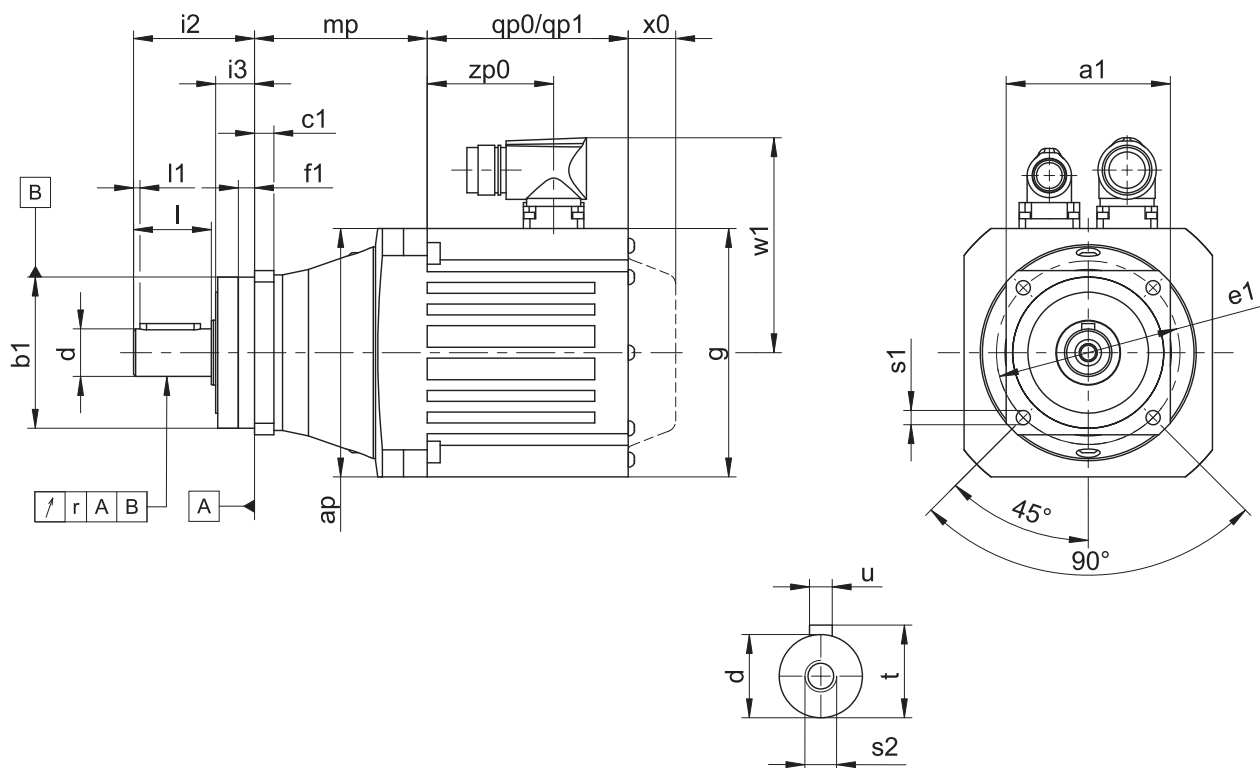
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	ap	mp	ap	mp	ap	mp	ap	mp	ap	mp	ap	mp
P231	□55	48.0	□72	61.5	-	-	-	-	-	-	-	-
P232	□55	80.0	□72	93.5	-	-	-	-	-	-	-	-
P331	-	-	□72	68.5	□98	65.0	-	-	-	-	-	-
P332	∅75	89.5	∅75	103.0	-	-	-	-	-	-	-	-
P431	-	-	-	-	□98	80.5	□115	80.0	-	-	-	-
P432	-	-	∅100	117.5	∅100	114.0	-	-	-	-	-	-
P531	-	-	-	-	-	-	□115	80.5	□145	83.5	-	-
P532	-	-	-	-	∅120	122.5	∅120	122.0	-	-	-	-
P731	-	-	-	-	-	-	-	-	□158	100.5	□190	110.5
P732	-	-	-	-	-	-	∅150	148.5	∅150	151.5	-	-
P831	-	-	-	-	-	-	-	-	-	-	□214	141.5
P832	-	-	-	-	-	-	-	-	∅204	192.5	∅204	202.5
P932	-	-	-	-	-	-	-	-	-	-	∅230	262.5

2.3.2 P shaft design (solid shaft with feather key)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	f1	i2	i3	l	l1	r	∅s1	s2	t	u
P231	55	50 _{h6}	6	12 _{k6}	63	7.0	36	12	22	2	-	5.5	M4	13.5	A4×4×18
P232	55	50 _{h6}	6	12 _{k6}	63	7.0	36	12	22	2	-	5.5	M4	13.5	A4×4×18
P331	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	28	2	0.025	5.5	M5	18.0	A5×5×22
P332	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	28	2	0.025	5.5	M5	18.0	A5×5×22
P431	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	36	3	0.025	6.6	M8	24.5	A6×6×28
P432	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	36	3	0.025	6.6	M8	24.5	A6×6×28
P531	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	58	3	0.030	9.0	M12	35.0	A10×8×50
P532	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	58	3	0.030	9.0	M12	35.0	A10×8×50
P731	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	82	4	0.035	11.0	M16	43.0	A12×8×70
P732	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	82	4	0.035	11.0	M16	43.0	A12×8×70
P831	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	82	6	0.035	13.5	M20	59.0	A16×10×70
P832	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	82	6	0.035	13.5	M20	59.0	A16×10×70
P932	212	180 _{h6}	17	75 _{k6}	250	10.0	143	34	105	7	0.040	17.5	M20	79.5	A20×12×90

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	ap	mp	ap	mp	ap	mp	ap	mp	ap	mp	ap	mp
P231	□55	48.0	□72	61.5	-	-	-	-	-	-	-	-
P232	□55	80.0	□72	93.5	-	-	-	-	-	-	-	-
P331	-	-	□72	68.5	□98	65.0	-	-	-	-	-	-
P332	∅75	89.5	∅75	103.0	-	-	-	-	-	-	-	-
P431	-	-	-	-	□98	80.5	□115	80.0	-	-	-	-
P432	-	-	∅100	117.5	∅100	114.0	-	-	-	-	-	-
P531	-	-	-	-	-	-	□115	80.5	□145	83.5	-	-
P532	-	-	-	-	∅120	122.5	∅120	122.0	-	-	-	-
P731	-	-	-	-	-	-	-	-	□158	100.5	□190	110.5
P732	-	-	-	-	-	-	∅150	148.5	∅150	151.5	-	-
P831	-	-	-	-	-	-	-	-	-	-	□214	141.5
P832	-	-	-	-	-	-	-	-	∅204	192.5	∅204	202.5
P932	-	-	-	-	-	-	-	-	-	-	∅230	262.5

2.4 Type designation

In this chapter, you can find an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

P	4	3	1	S	G	S	S	0100	EZ401U
---	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
P	Type	Planetary gearbox
4	Size	4 (example)
3	Generation	Generation 3
1	Stages	Single-stage
2		Two-stage
S	Housing	Standard
G	Shaft	Solid shaft without feather key
P		Solid shaft with feather key
S	Bearing	Standard bearing
D		Axially reinforced bearing (P3 – P9)
Z		Radially reinforced bearing (P3 – P9) ¹
S	Backlash	Standard
R		Reduced
0100	Transmission ratio (i x 10)	i = 10 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 2.6.3](#)
- Position of the plug connectors, see the chapter [▶ 2.5.4](#)
- For reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, note the chapter [▶ 2.6.4](#)

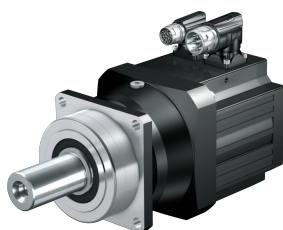
To make selecting your geared motor easy, use our STOEER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

2.5 Product description

2.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

LM Lean motor



Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

2.5.2 Installation conditions

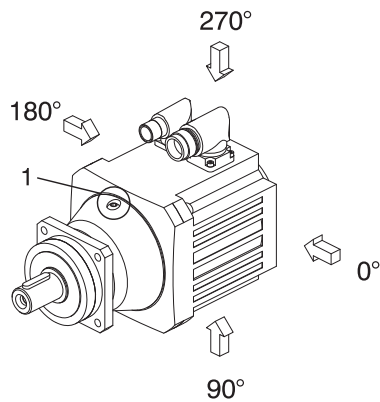
The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 12.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

2.5.3 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate.

You will receive lubricants for use in the food industry upon request.

2.5.4 Position of the plug connectors



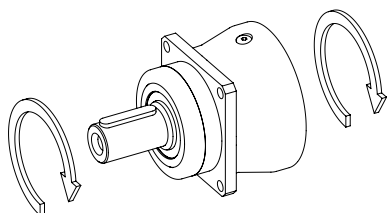
In the standard version, the plug connectors are attached in the 270° position (relative to the oil drain plug (1) of the planetary gearbox). Indicate variations for your geared motor in the order.

2.5.5 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} single-stage	97%
η_{get} two-stage	95%
Protection class:²	
Gearbox	IP65
Motor	IP56, optionally IP66

2.5.6 Direction of rotation

The input and output rotate in the same direction.



2.6 Project configuration

Project your drives using our SERVOSOFT designing software. Download SERVOSOFT free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

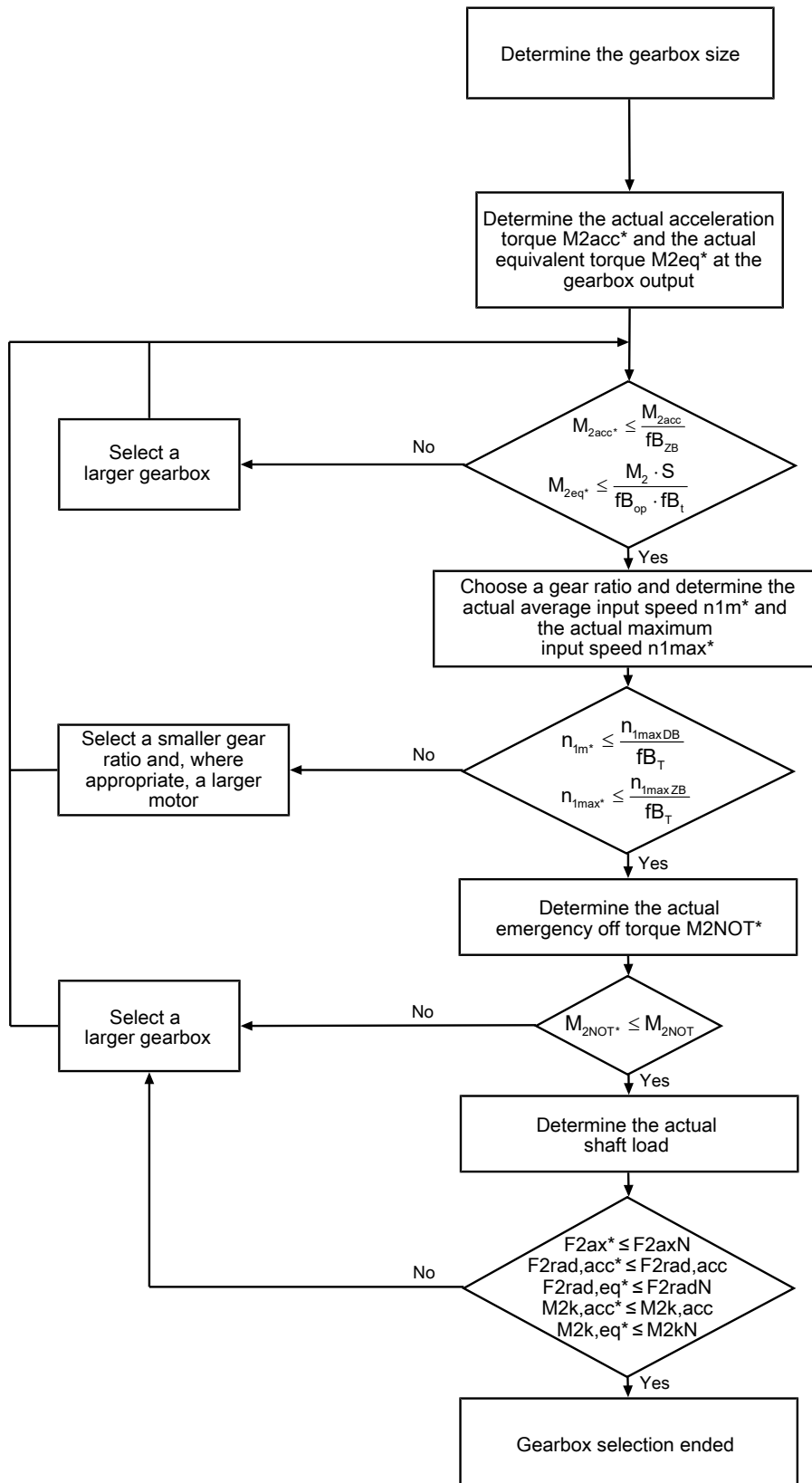
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

2.6.1 Drive selection

Drive selection for gearboxes

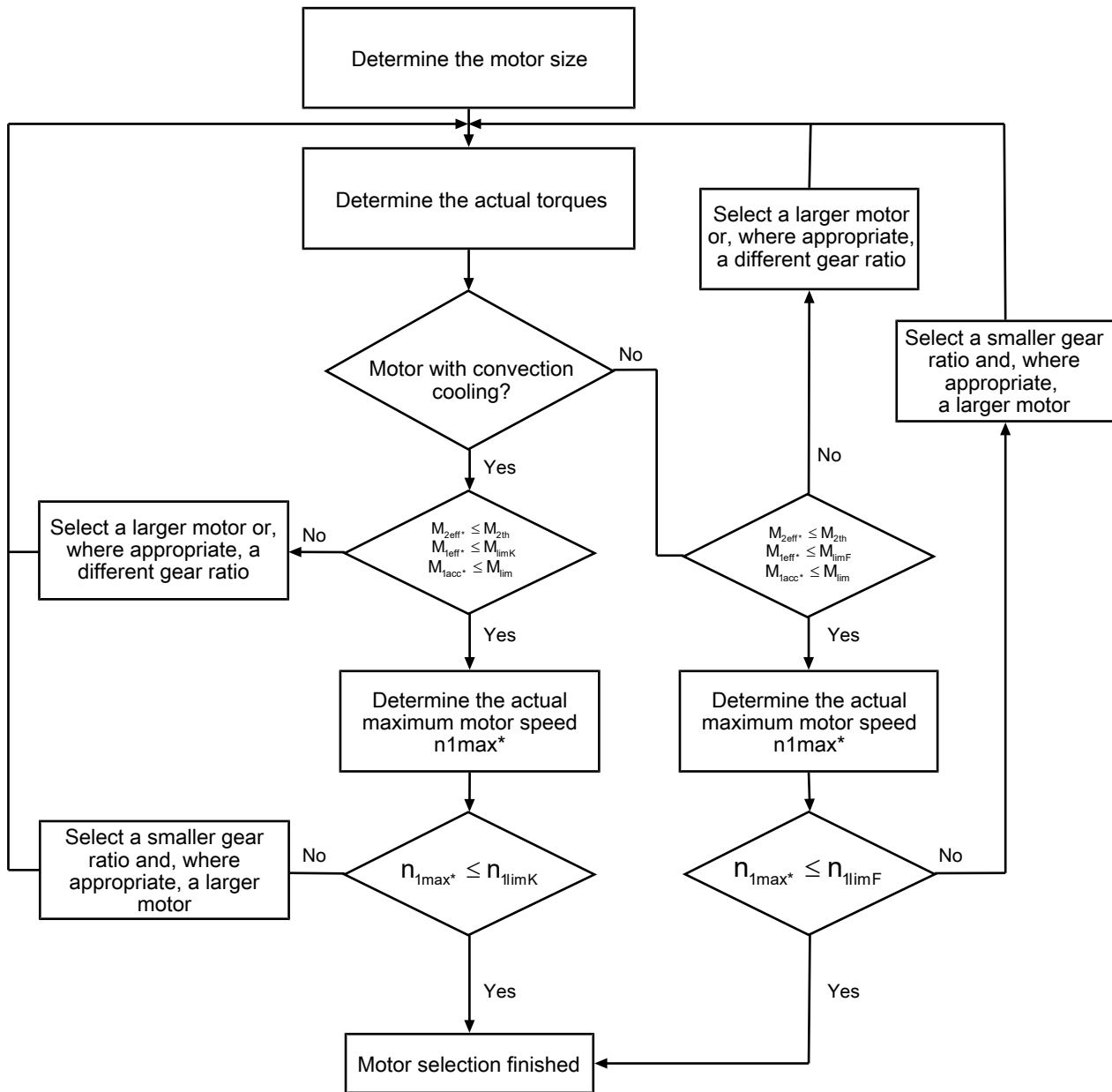


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

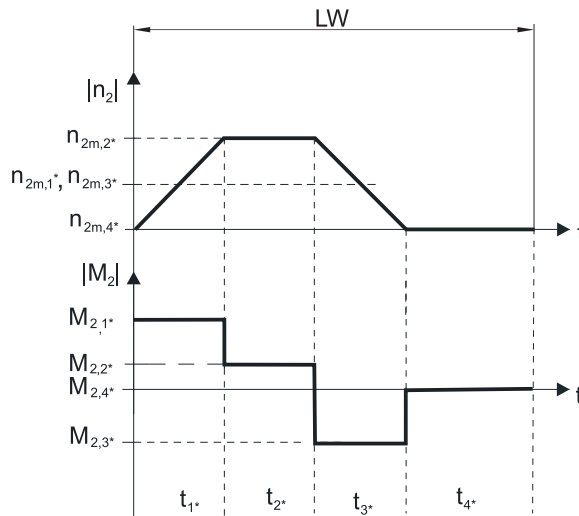
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:

**Calculation of the actual maximum acceleration torques**

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |M_{2,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |M_{2,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m^*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m^*} accordingly or select another geared motor size.)

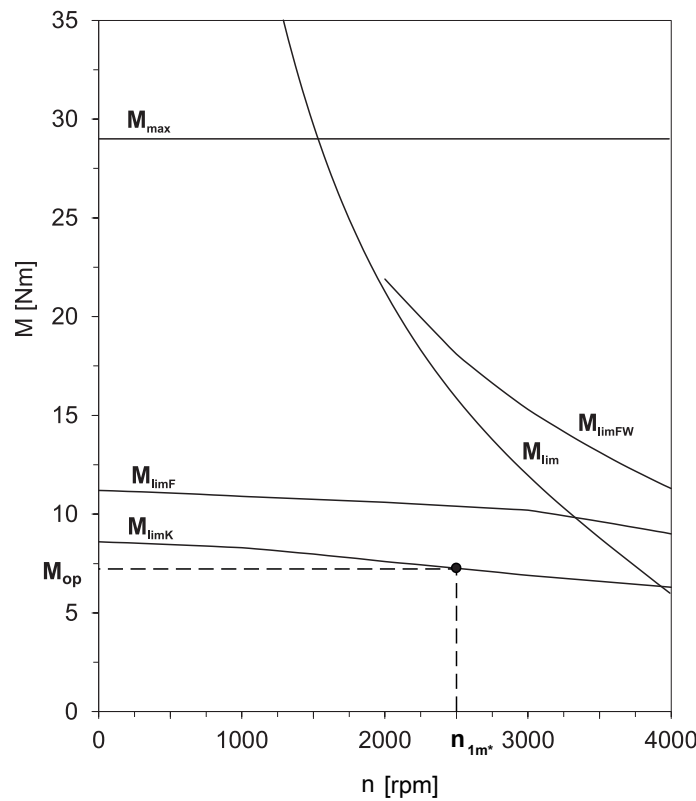
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m^*}}{1000} \right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.00
Reversing load cyclic operation	1.00
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

2.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P2	17.0	500	1200	1300	34	36
P3	17.5	1000	2500	2500	79	79
P4	18.5	1500	4000	4500	146	164
P5	19.5	2300	6500	7000	315	340
P7	23.0	2900	8500	9000	544	576
P8	24.5	4700	13000	18000	852	1179
P9	33.0	6000	18000	27000	1539	2309

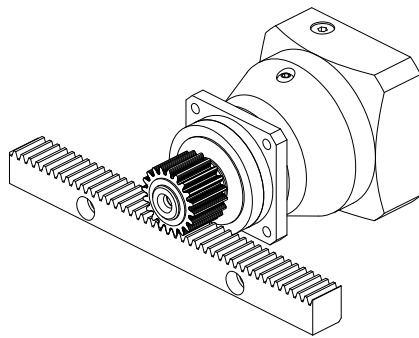


Fig. 1: Recommendation for bearing assignment S (e.g. for straight-cut gearing)

Permitted shaft loads for axially reinforced bearing D

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	20.0	2500	2750	2750	94	94
P4	22.5	4000	4500	5000	182	203
P5	25.5	6000	7000	8000	382	436
P7	29.0	10000	9500	10000	665	700
P8	32.0	15500	15000	18000	1095	1314
P9	44.0	25000	20000	30000	1930	2895

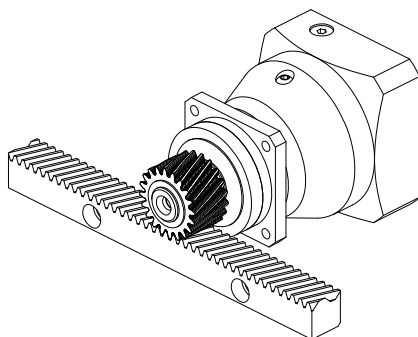


Fig. 2: Recommendation for bearing assignment D (e.g. for helical gearing)

Permitted shaft loads for radially reinforced bearing Z

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	17.5	600	3000	3000	95	95
P4	18.5	1000	5000	5000	183	183
P5	19.5	1600	8000	8000	388	388
P7	23.0	2000	10000	10000	640	640
P8	24.5	3600	18000	18000	1179	1179
P9	33.0	5000	27000	35000	2309	2993

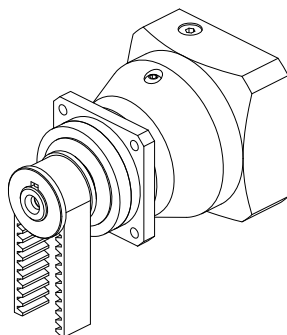


Fig. 3: Recommendation for bearing assignment Z (e.g. for belt drives)

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

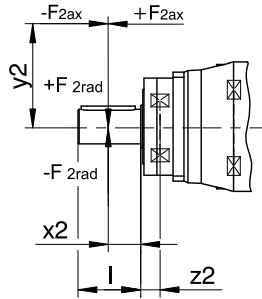


Fig. 4: Force application points

The specified values for $F_{2rad100}$ and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1*} \cdot |M_{2k,acc,1*}|^3 + \dots + |n_{2m,n}| \cdot t_{n*} \cdot |M_{2k,acc,n*}|^3}{|n_{2m,1}| \cdot t_{1*} + \dots + |n_{2m,n}| \cdot t_{n*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1*} \cdot |F_{2rad,acc,1*}|^3 + \dots + |n_{2m,n}| \cdot t_{n*} \cdot |F_{2rad,acc,n*}|^3}{|n_{2m,1}| \cdot t_{1*} + \dots + |n_{2m,n}| \cdot t_{n*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$L_{10h} > 10000$ h with $1 < M_{2kN}/M_{2k*} < 1.25$

$L_{10h} > 20000$ h with $1.25 < M_{2kN}/M_{2k*} < 1.5$

$L_{10h} > 30000$ h with $1.5 < M_{2kN}/M_{2k*}$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

2.6.3 Recommendation for radial shaft seal rings

For a duty cycle $> 60\%$ and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

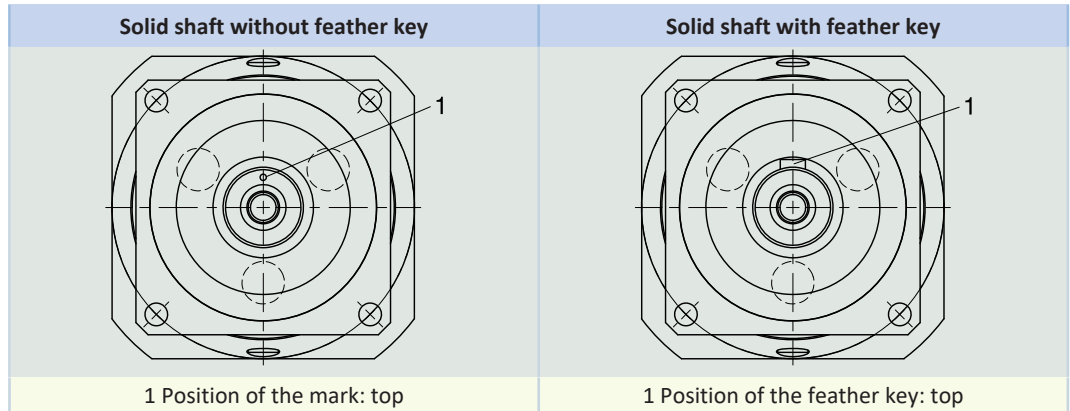
- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

2.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below. The images show the center position of reverse operation. Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Notes

- If you use the solid shaft without a feather key (G), you must note the position of the mark during assembly.
- As an alternative, you can use the solid shaft with a feather key (P). In that case, the feather key functions for position orientation. For a backlash-free connection, also use a clamp.

2.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

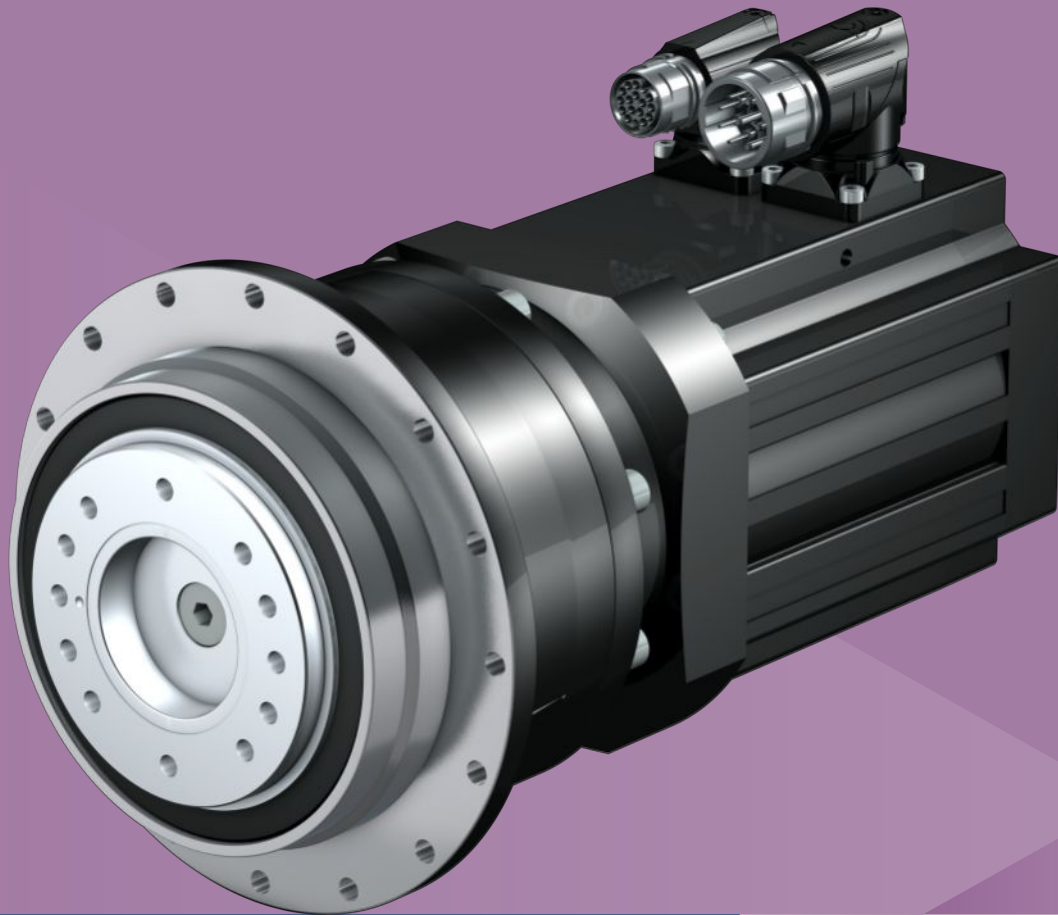
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors P23 – P93	443356_en
Operating manual for EZ synchronous servo motors	443032_en

3 PH planetary geared motors

Table of contents

3.1	Overview	48
3.2	Selection tables	49
3.3	Dimensional drawings	59
3.3.1	F shaft design (flange shaft)	60
3.4	Type designation	62
3.5	Product description	62
3.5.1	Input options	62
3.5.2	Installation conditions	63
3.5.3	Lubricants	63
3.5.4	Other product features	63
3.5.5	Direction of rotation	63
3.6	Project configuration	63
3.6.1	Drive selection	64
3.6.2	Permitted shaft loads for the output shaft	68
3.6.3	Recommendation for radial shaft seal rings	69
3.6.4	Reverse operation	70
3.7	Additional documentation	70



3

Planetary geared motors

PH

3.1 Overview

High-performance precision planetary geared motors

Features

Power density	★★★★☆
Backlash	★★★★★
Price category	€€€
Shaft load	★★★★★
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
Any mounting position	✓
Continuous operation without cooling	✓
Stiff output bearings due to pretension	✓
Reinforced output bearing (PH3 – PH5)	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	4 – 100
M_{2acc}	24 – 7500 Nm
$\Delta\phi_2$	1 – 4 arcmin
η_{get}	93 – 96 %

3.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to <https://configurator.stoeber.de/en-US/>.

In the case of the version with a reinforced bearing and gear ratios ≤ 5 , the maximum permitted input speed n_{1maxZB} is reduced. You can find values at <https://configurator.stoeber.de/en-US/>

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_2$ [arcmin]	$\Delta\phi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PH3 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 80 \text{ Nm}$)																	
60	43	44	1.4	1.2	PH332_0500 EZ301U	75	75	150	50.00	50/1	6000	8000	0.21	4.0	2.0	12	3.2
75	35	35	1.5	1.4	PH332_0400 EZ301U	67	67	134	40.00	40/1	6000	8000	0.22	4.0	2.0	9.0	3.2
86	30	31	1.6	1.7	PH332_0350 EZ301U	80	85	160	35.00	35/1	6000	8000	0.21	4.0	2.0	14	3.2
107	24	25	1.8	2.1	PH332_0280 EZ301U	73	73	150	28.00	28/1	6000	8000	0.22	4.0	2.0	12	3.2
107	41	44	3.1	1.2	PH332_0280 EZ302U	75	75	150	28.00	28/1	6000	8000	0.32	4.0	2.0	12	3.8
120	22	22	1.9	2.3	PH332_0250 EZ301U	65	65	160	25.00	25/1	6000	8000	0.21	4.0	2.0	14	3.2
120	37	39	3.3	1.4	PH332_0250 EZ302U	80	85	160	25.00	25/1	6000	8000	0.31	4.0	2.0	14	3.8
120	48	51	4.3	1.0	PH332_0250 EZ303U	80	85	160	25.00	25/1	6000	8000	0.42	4.0	2.0	14	4.3
150	17	18	2.4	2.6	PH332_0200 EZ301U	52	52	160	20.00	20/1	5500	8000	0.23	4.0	2.0	14	3.2
150	30	31	4.1	1.5	PH332_0200 EZ302U	80	85	160	20.00	20/1	5500	8000	0.33	4.0	2.0	14	3.8
150	39	41	5.4	1.2	PH332_0200 EZ303U	80	85	160	20.00	20/1	5500	8000	0.44	4.0	2.0	14	4.3
300	8.9	9.1	1.5	3.2	PH331_0100 EZ301U	27	27	120	10.00	10/1	5500	8000	0.21	4.0	2.0	9.2	2.7
300	15	16	2.6	1.9	PH331_0100 EZ302U	48	48	120	10.00	10/1	5500	8000	0.31	4.0	2.0	9.2	3.3
300	20	21	3.3	1.4	PH331_0100 EZ303U	60	60	120	10.00	10/1	5500	8000	0.42	4.0	2.0	9.2	3.8
300	27	29	4.5	1.1	PH331_0100 EZ401U	60	60	120	10.00	10/1	5500	8000	0.95	4.0	2.0	9.2	5.2
429	11	11	2.9	3.7	PH331_0070 EZ302U	34	34	150	7.000	7/1	5000	8000	0.33	4.0	2.0	13	3.3
429	14	15	3.7	2.8	PH331_0070 EZ303U	47	47	150	7.000	7/1	5000	8000	0.44	4.0	2.0	13	3.8
429	19	20	5.0	2.1	PH331_0070 EZ401U	57	57	150	7.000	7/1	5000	8000	0.97	4.0	2.0	13	5.2
429	32	35	8.4	1.2	PH331_0070 EZ402U	75	77	150	7.000	7/1	5000	8000	1.7	4.0	2.0	13	6.3
600	9.9	11	5.6	4.0	PH331_0050 EZ303U	34	34	160	5.000	5/1	4000	8000	0.48	4.0	2.0	15	3.8
600	13	14	7.5	2.9	PH331_0050 EZ401U	41	41	160	5.000	5/1	4000	8000	1.0	4.0	2.0	15	5.2
600	23	25	13	1.7	PH331_0050 EZ402U	77	77	160	5.000	5/1	4000	8000	1.7	4.0	2.0	15	6.3
PH3 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 80 \text{ Nm}$)																	
86	26	29	0.6	1.7	PH332_0700 EZ202U	69	69	138	70.00	70/1	6000	8000	0.14	4.0	2.0	12	3.1
86	40	45	0.8	1.1	PH332_0700 EZ203U	69	69	138	70.00	70/1	6000	8000	0.18	4.0	2.0	12	3.4
120	19	20	0.7	2.2	PH332_0500 EZ202U	69	69	150	50.00	50/1	6000	8000	0.15	4.0	2.0	12	3.1
120	28	32	1.1	1.4	PH332_0500 EZ203U	75	75	150	50.00	50/1	6000	8000	0.19	4.0	2.0	12	3.4
150	15	16	0.8	2.8	PH332_0400 EZ202U	55	55	134	40.00	40/1	6000	8000	0.16	4.0	2.0	9.0	3.1
150	23	26	1.2	1.8	PH332_0400 EZ203U	67	67	134	40.00	40/1	6000	8000	0.20	4.0	2.0	9.0	3.4
150	33	35	1.8	1.2	PH332_0400 EZ301U	67	67	134	40.00	40/1	6000	8000	0.22	4.0	2.0	9.0	3.2
171	13	14	0.8	3.5	PH332_0350 EZ202U	48	48	160	35.00	35/1	6000	8000	0.15	4.0	2.0	14	3.1
171	20	22	1.2	2.3	PH332_0350 EZ203U	80	85	160	35.00	35/1	6000	8000	0.19	4.0	2.0	14	3.4
171	29	31	1.7	1.6	PH332_0350 EZ301U	80	85	160	35.00	35/1	6000	8000	0.21	4.0	2.0	14	3.2
214	10	11	0.9	4.0	PH332_0280 EZ202U	39	39	150	28.00	28/1	6000	8000	0.16	4.0	2.0	12	3.1
214	16	18	1.4	2.6	PH332_0280 EZ203U	70	70	150	28.00	28/1	6000	8000	0.20	4.0	2.0	12	3.4
214	23	25	2.1	1.8	PH332_0280 EZ301U	73	73	150	28.00	28/1	6000	8000	0.22	4.0	2.0	12	3.2
214	39	44	3.6	1.1	PH332_0280 EZ302U	75	75	150	28.00	28/1	6000	8000	0.32	4.0	2.0	12	3.8
240	9.3	10	0.9	4.8	PH332_0250 EZ202U	34	34	160	25.00	25/1	6000	8000	0.15	4.0	2.0	14	3.1
240	14	16	1.4	3.2	PH332_0250 EZ203U	63	63	160	25.00	25/1	6000	8000	0.19	4.0	2.0	14	3.4
240	21	22	2.1	2.2	PH332_0250 EZ301U	65	65	160	25.00	25/1	6000	8000	0.21	4.0	2.0	14	3.2
240	35	39	3.5	1.3	PH332_0250 EZ302U	80	85	160	25.00	25/1	6000	8000	0.31	4.0	2.0	14	3.8
300	11	13	1.9	3.3	PH332_0200 EZ203U	50	50	160	20.00	20/1	5500	8000	0.20	4.0	2.0	14	3.4
300	17	18	2.7	2.3	PH332_0200 EZ301U	52	52	160	20.00	20/1	5500	8000	0.23	4.0	2.0	14	3.2
300	28	31	4.6	1.4	PH332_0200 EZ302U	80	85	160	20.00	20/1	5500	8000	0.33	4.0	2.0	14	3.8
300	36	42	6.0	1.0	PH332_0200 EZ303U	80	85	160	20.00	20/1	5500	8000	0.44	4.0	2.0	14	4.3
600	8.5	9.1	1.8	2.7	PH331_0100 EZ301U	27	27	120	10.00	10/1	5500	8000	0.21	4.0	2.0	9.2	2.7
600	14	16	3.0	1.6	PH331_0100 EZ302U	48	48	120	10.00	10/1	5500	8000	0.31	4.0	2.0	9.2	3.3
600	19	22	4.0	1.2	PH331_0100 EZ303U	60	60	120	10.00	10/1	5500	8000	0.42	4.0	2.0	9.2	3.8
600	22	27	4.7	1.0	PH331_0100 EZ401U	60	60	120	10.00	10/1	5500	8000	0.95	4.0	2.0	9.2	5.2
857	10	11	3.4	3.1	PH331_0070 EZ302U	34	34	150	7.000	7/1	5000	8000	0.33	4.0	2.0	13	3.3
857	13	15	4.4	2.4	PH331_0070 EZ303U	47	47	150	7.000	7/1	5000	8000	0.44	4.0	2.0	13	3.8

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_2$ [arcmin]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PH9 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 5000 \text{ Nm}$)																	
100	1074	1279	3.9	2.8	PH942_0200 EZ815U	3720	3720	9548	20.00	20/1	2500	4000	182	3.0	1.0	1193	111
111	653	732	2.8	4.6	PH942_0180 EZ813U	2344	2344	8655	18.00	18/1	1800	3000	149	3.0	1.0	1141	99
111	967	1151	4.1	3.1	PH942_0180 EZ815U	3348	3348	8655	18.00	18/1	1800	3000	213	3.0	1.0	1141	111
125	859	1023	4.4	3.5	PH942_0160 EZ815U	2976	2976	7670	16.00	16/1	2000	3500	190	3.0	1.0	1211	111
167	644	767	5.1	4.7	PH942_0120 EZ815U	2232	2232	5770	12.00	12/1	1800	3000	218	3.0	1.0	1256	111
PH9 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 5000 \text{ Nm}$)																	
67	1406	2438	0.9	2.3	PH942_0600 EZ813U	5000	5000	10000	60.00	60/1	2800	4500	108	3.0	1.0	1065	99
67	1457	3746	1.0	2.2	PH942_0600 EZ815U	5000	5000	10000	60.00	60/1	2800	4500	171	3.0	1.0	1065	111
83	1125	1951	0.9	3.1	PH942_0480 EZ813U	5000	5000	10000	48.00	48/1	2800	4500	110	3.0	1.0	1084	99
83	1166	2997	1.0	3.0	PH942_0480 EZ815U	5000	5000	10000	48.00	48/1	2800	4500	173	3.0	1.0	1084	111
95	984	1707	1.0	3.6	PH942_0420 EZ813U	5000	5000	10000	42.00	42/1	2800	4500	111	3.0	1.0	1103	99
95	1020	2622	1.0	3.4	PH942_0420 EZ815U	5000	5000	10000	42.00	42/1	2800	4500	174	3.0	1.0	1103	111
100	937	1626	1.6	2.5	PH942_0400 EZ813U	4600	4600	9200	40.00	40/1	2800	4500	108	3.0	1.0	1068	99
100	971	2498	1.6	2.4	PH942_0400 EZ815U	4600	4600	9200	40.00	40/1	2800	4500	171	3.0	1.0	1068	111
125	750	1301	1.7	3.3	PH942_0320 EZ813U	4166	4166	9200	32.00	32/1	2800	4500	110	3.0	1.0	1112	99
125	777	1998	1.7	3.1	PH942_0320 EZ815U	4600	4600	9200	32.00	32/1	2800	4500	173	3.0	1.0	1112	111
133	703	1219	1.3	4.7	PH942_0300 EZ813U	3906	3906	10000	30.00	30/1	2500	4000	116	3.0	1.0	1117	99
133	728	1873	1.3	4.5	PH942_0300 EZ815U	5000	5000	10000	30.00	30/1	2500	4000	179	3.0	1.0	1117	111
143	656	1138	1.4	4.6	PH942_0280 EZ813U	3646	3646	10000	28.00	28/1	2800	4500	112	3.0	1.0	1156	99
143	680	1748	1.5	4.5	PH942_0280 EZ815U	5000	5000	10000	28.00	28/1	2800	4500	175	3.0	1.0	1156	111
PH10 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 7500 \text{ Nm}$)																	
33	2176	2440	1.1	2.0	PH1042_0600 EZ813U	7000	–	14000	60.00	60/1	2800	4500	108	3.0	–	1615	114
33	3222	3837	1.6	1.4	PH1042_0600 EZ815U	7000	–	14000	60.00	60/1	2800	4500	171	3.0	–	1615	127
48	1523	1708	1.2	3.3	PH1042_0420 EZ813U	5468	–	15000	42.00	42/1	2800	4500	111	3.0	–	1702	114
48	2256	2686	1.7	2.2	PH1042_0420 EZ815U	7500	–	15000	42.00	42/1	2800	4500	174	3.0	–	1702	127
67	1088	1220	1.4	4.6	PH1042_0300 EZ813U	3906	–	14323	30.00	30/1	2500	4000	117	3.0	–	1737	114
67	1611	1918	2.1	3.1	PH1042_0300 EZ815U	5580	–	14323	30.00	30/1	2500	4000	180	3.0	–	1737	127
83	1289	1535	2.5	3.6	PH1042_0240 EZ815U	4464	–	11506	24.00	24/1	2000	3500	188	3.0	–	1754	127
111	967	1151	2.9	4.8	PH1042_0180 EZ815U	3348	–	8655	18.00	18/1	1800	3000	214	3.0	–	1778	127
PH10 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 7500 \text{ Nm}$)																	
67	1406	2438	0.9	2.5	PH1042_0600 EZ813U	7000	–	14000	60.00	60/1	2800	4500	108	3.0	–	1615	114
67	1457	3746	0.9	2.4	PH1042_0600 EZ815U	7000	–	14000	60.00	60/1	2800	4500	171	3.0	–	1615	127
95	984	1707	0.8	4.6	PH1042_0420 EZ813U	5468	–	15000	42.00	42/1	2800	4500	111	3.0	–	1702	114
95	1020	2622	0.9	4.5	PH1042_0420 EZ815U	7500	–	15000	42.00	42/1	2800	4500	174	3.0	–	1702	127

3.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

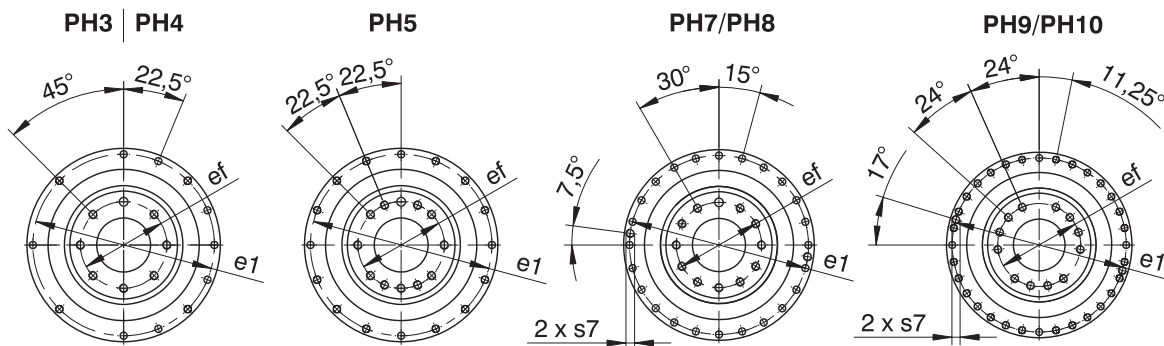
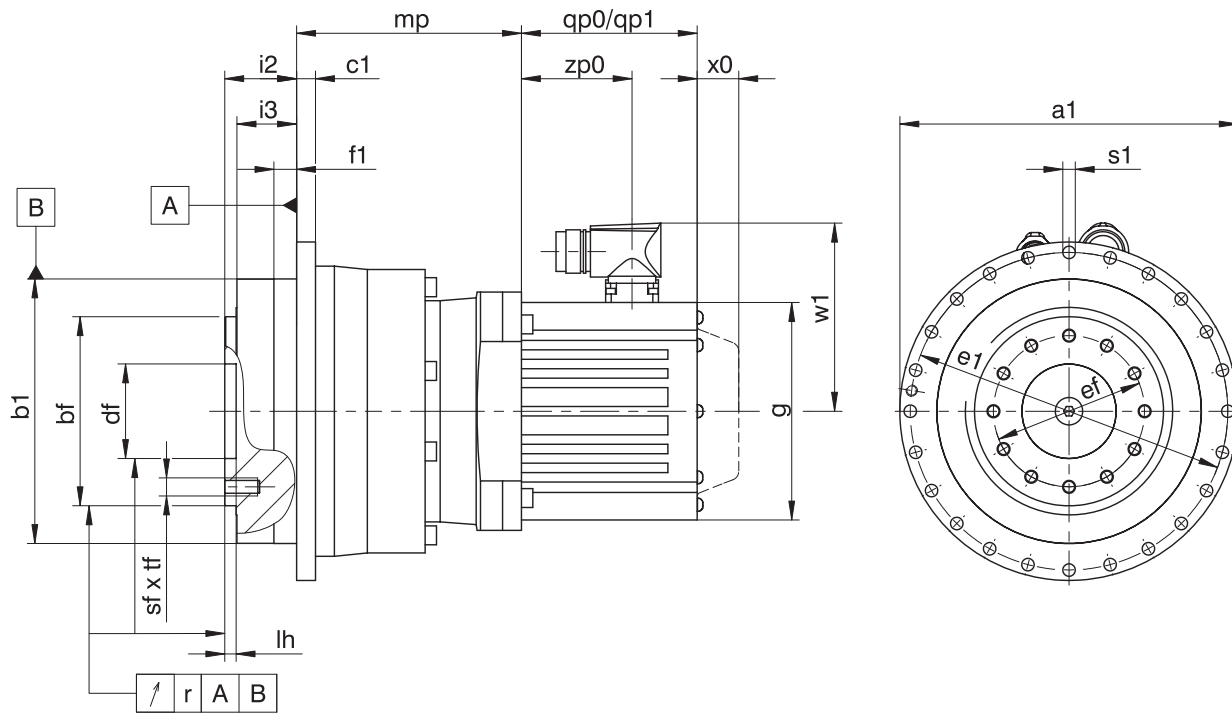
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

3.3.1 F shaft design (flange shaft)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	i2	i3	lh	r	Øs1	s7	sf	tf
PH331	86	64 _{h7}	40 _{h7}	4	20.0 ^{H6}	79	31.5	7	19.5	16.5	4	0.020	4.5	–	M5	7
PH332	86	64 _{h7}	40 _{h7}	4	20.0 ^{H6}	79	31.5	7	19.5	16.5	4	0.020	4.5	–	M5	7
PH431	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50.0	10	30.0	24.0	6	0.020	5.5	–	M6	11
PH432	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50.0	10	30.0	24.0	6	0.020	5.5	–	M6	11
PH531	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63.0	12	29.0	23.0	6	0.020	5.5	–	M6	11
PH532	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63.0	12	29.0	23.0	6	0.020	5.5	–	M6	11
PH731	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80.0	12	38.0	32.0	6	0.025	6.6	–	M8	14
PH732	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80.0	12	38.0	32.0	6	0.025	6.6	–	M8	14
PH831	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125.0	15	50.0	42.0	8	0.030	9.0	M10	M10	18
PH832	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125.0	15	50.0	42.0	8	0.030	9.0	M10	M10	18
PH942	300	255 _{h7}	180 _{h7}	18	90.0 ^{H6}	280	140.0	20	66.0	55.0	12	0.030	13.5	M8	M16	24
PH1042	330	285 _{h7}	200 _{h7}	20	95.0 ^{H6}	310	160.0	20	75.0	60.0	10	0.040	13.5	M10	M20	28

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
PH331	-	51.0	47.5	-	-	-
PH332	71.0	84.5	-	-	-	-
PH431	-	-	54.5	54.0	-	-
PH432	-	99.0	95.5	-	-	-
PH531	-	-	-	61.0	64.0	-
PH532	-	-	103.0	102.5	-	-
PH731	-	-	-	-	71.0	81.0
PH732	-	-	-	119.0	122.0	-
PH831	-	-	-	-	-	110.0
PH832	-	-	-	-	161.0	171.0
PH942	-	-	-	-	-	210.5
PH1042	-	-	-	-	-	217.5

3.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PH	5	3	2	S	F	S	S	0250	EZ401U
----	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
PH	Type	Planetary gearbox
5	Size	5 (example)
3	Generation	Generation 3
4		Generation 4
1	Stages	Single-stage
2		Two-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
V		Reinforced bearing (PH3 – PH5)
S	Backlash	Standard
R		Reduced (PH3 – PH9)
0250	Transmission ratio (i x 10)	i = 25 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 3.6.3](#)
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 3.6.4](#)

To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

3.5 Product description

3.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter + EZ synchronous servo motor



Catalog ID 443311_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

3.5.2 Installation conditions

The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b1$. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

3.5.3 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate.

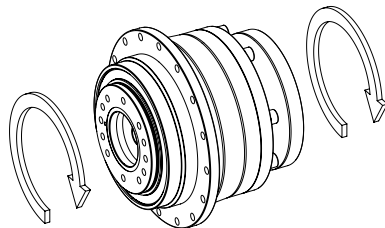
You will receive lubricants for use in the food industry upon request.

3.5.4 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} single-stage	96%
η_{get} two-stage	93%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

3.5.5 Direction of rotation

The input and output rotate in the same direction.



3.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

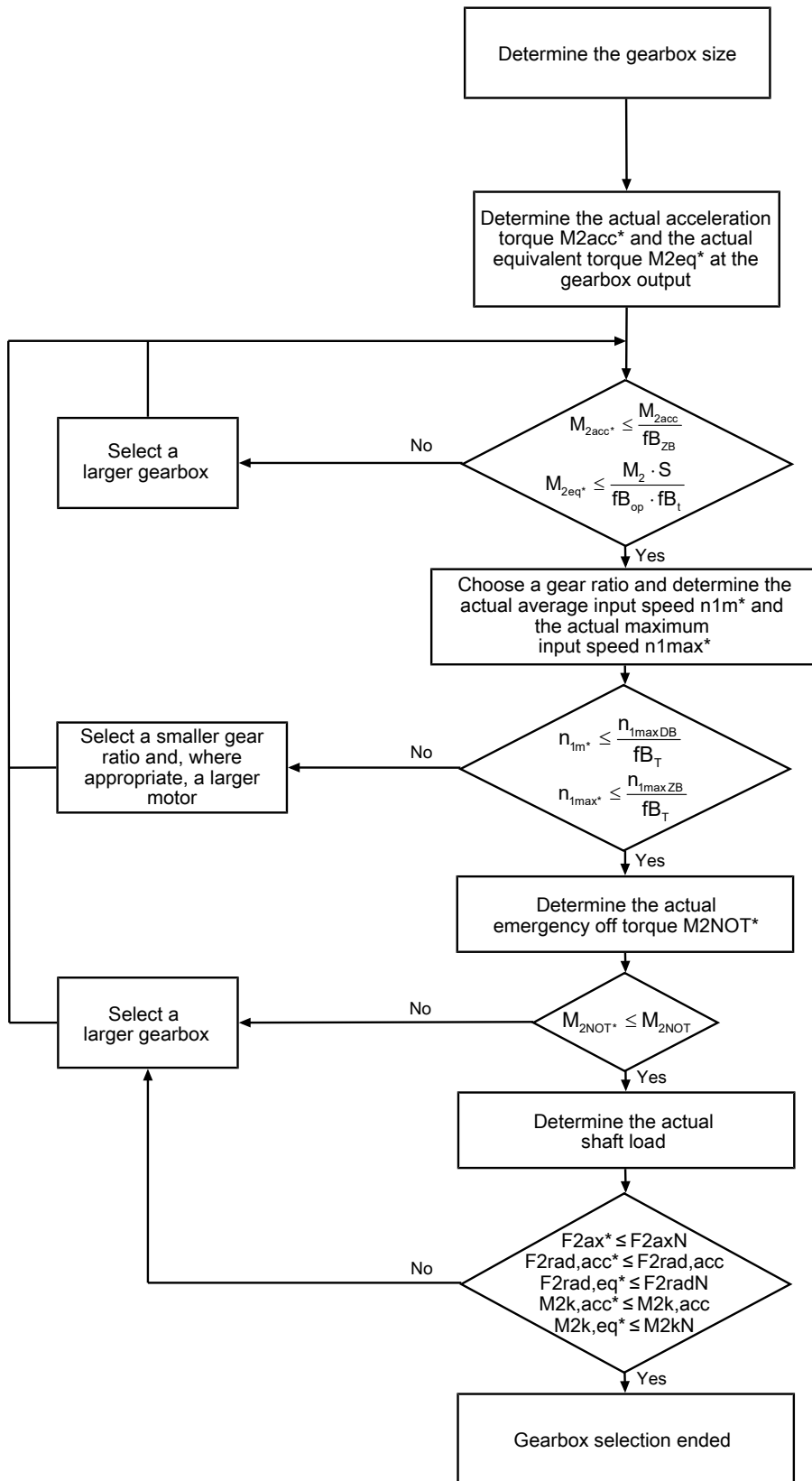
An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

¹Observe the protection class of all the components.

3.6.1 Drive selection

Drive selection for gearboxes

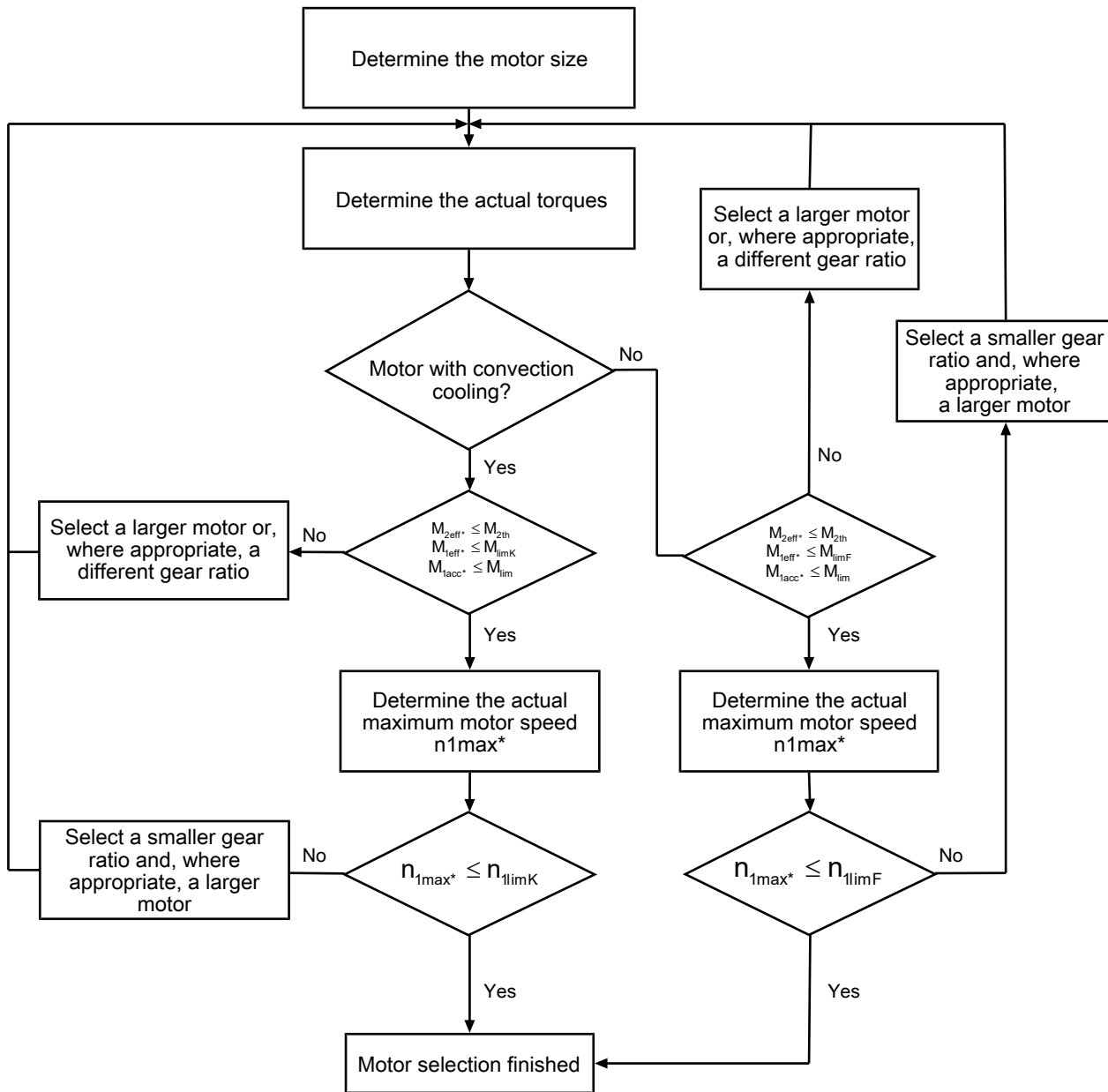


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for fB_T , fB_{op} , fB_t and fB_{ZB} can be found in the corresponding tables in this chapter.

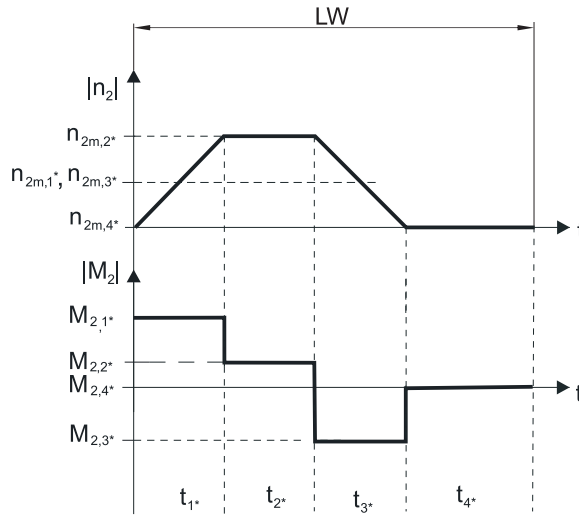
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

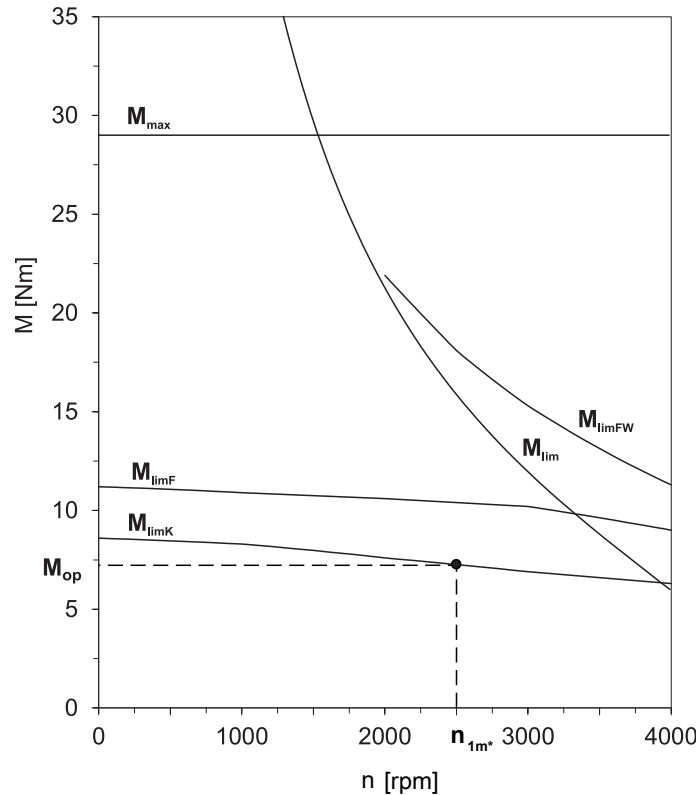
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.00
Reversing load cyclic operation		1.00
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

3.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	62.5	1650	1613	1613	101	101	75
PH4	83.0	2150	3095	3571	257	296	192
PH5	97.0	4150	4536	4897	440	475	429
PH7	86.0	6150	17045	17045	1466	1466	500
PH8	125.5	10050	27778	27778	3486	3486	1550
PH9	155.0	33000	48387	70968	7500	11000	7500
PH10	171.0	50000	51462	73099	8800	12500	9500

Permitted shaft loads for reinforced bearing V

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	66.5	2200	2250	2250	150	150	80
PH4	88.5	2900	4000	4000	354	354	217
PH5	104.0	5000	5500	5500	572	572	478

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

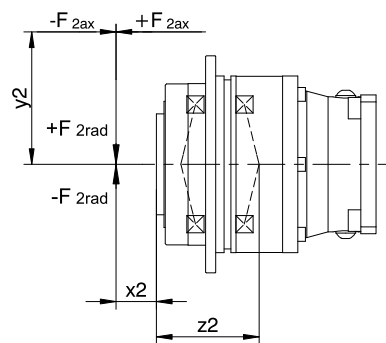


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

3.6.3 Recommendation for radial shaft seal rings

For a duty cycle $> 60\%$ and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

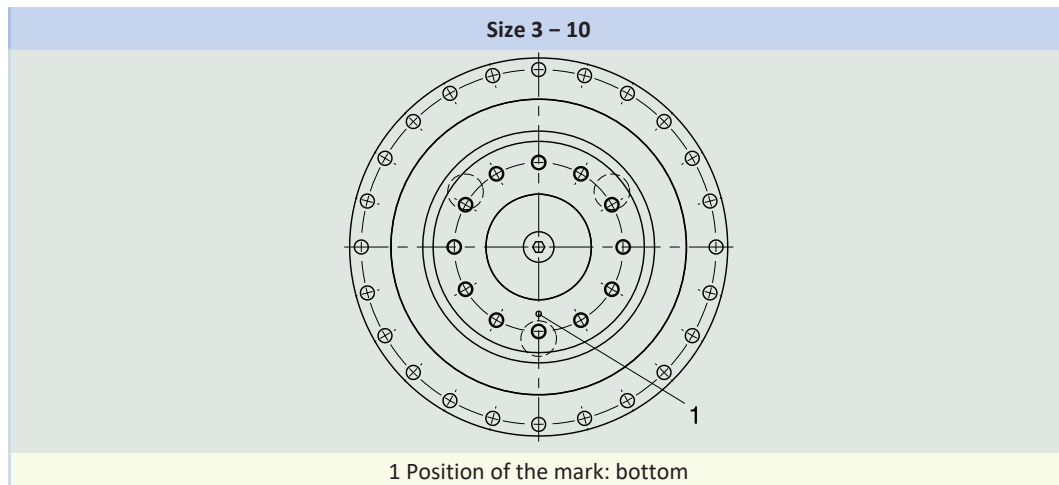
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

3.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

3.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PH33 – PH83, PH94 – PH104	443354_en
Operating manual for EZ synchronous servo motors	443032_en

4 PHQ planetary geared motors

Table of contents

4.1	Overview	72
4.2	Selection tables	73
4.3	Dimensional drawings	81
4.3.1	PHQ4 – PHQ10 F shaft design (flange shaft)	82
4.3.2	PHQ11 F shaft design (flange shaft)	84
4.4	Type designation	85
4.5	Product description	85
4.5.1	Input options	85
4.5.2	Installation conditions	86
4.5.3	Mounting positions	86
4.5.4	Lubricants	86
4.5.5	Other product features	86
4.5.6	Direction of rotation	87
4.6	Project configuration	87
4.6.1	Drive selection	88
4.6.2	Permitted shaft loads for the output shaft	92
4.6.3	Recommendation for radial shaft seal rings	93
4.6.4	Reverse operation	94
4.7	Additional documentation	94



4

Planetary geared motors

PHQ

4.1 Overview

Quattro-Power for maximum power density

Features

- Power density ★★★★★
- Backlash ★★★★★
- Price category €€€€
- Shaft load ★★★★★
- Smooth operation ★★★★★☆
- Torsional stiffness ★★★★★
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free ✓
- Any mounting position (single/two stage) ✓
- High power density ✓
- Continuous operation without cooling ✓
- Stiff output bearings due to pretension ✓
- Reinforced output bearing (PHQ4 – PHQ5) ✓ (optional)
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	5.5 – 600
M_{2acc}	72 – 22000 Nm
$\Delta\phi_2$	1 – 3 arcmin
η_{get}	90 – 96 %

4.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to <https://configurator.stoeber.de/en-US/>.

In the case of the version with a reinforced bearing and gear ratios ≤ 5, the maximum permitted input speed n_{1maxZB} is reduced. You can find values at <https://configurator.stoeber.de/en-US/>

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_2$ [arcmin]	$\Delta\phi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PHQ4 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 200 \text{ Nm}$)																	
55	48	49	0.6	2.7	PHQ432_0550 EZ301U	143	143	400	55.00	55/1	4500	8000	0.21	3.0	1.0	38	5.8
55	81	86	1.0	1.6	PHQ432_0550 EZ302U	200	247	400	55.00	55/1	4500	8000	0.31	3.0	1.0	38	6.4
55	106	112	1.3	1.2	PHQ432_0550 EZ303U	200	247	400	55.00	55/1	4500	8000	0.42	3.0	1.0	38	6.9
78	33	34	0.7	3.9	PHQ432_0390 EZ301U	100	100	400	38.50	77/2	4500	8000	0.22	3.0	1.0	40	5.8
78	57	60	1.2	2.3	PHQ432_0390 EZ302U	179	179	400	38.50	77/2	4500	8000	0.32	3.0	1.0	40	6.4
78	74	78	1.5	1.8	PHQ432_0390 EZ303U	200	246	400	38.50	77/2	4500	8000	0.43	3.0	1.0	40	6.9
78	100	107	2.0	1.3	PHQ432_0390 EZ401U	200	246	400	38.50	77/2	4500	8000	0.96	3.0	1.0	40	8.3
109	41	43	1.5	3.0	PHQ432_0280 EZ302U	128	128	400	27.50	55/2	4500	8000	0.35	3.0	1.0	40	6.4
109	53	56	1.9	2.3	PHQ432_0280 EZ303U	179	179	400	27.50	55/2	4500	8000	0.46	3.0	1.0	40	6.9
109	72	77	2.6	1.7	PHQ432_0280 EZ401U	200	217	400	27.50	55/2	4500	8000	0.99	3.0	1.0	40	8.3
136	33	34	1.7	3.7	PHQ432_0220 EZ302U	102	102	400	22.00	22/1	4000	8000	0.39	3.0	1.0	41	6.4
136	42	45	2.2	2.8	PHQ432_0220 EZ303U	143	143	400	22.00	22/1	4000	8000	0.50	3.0	1.0	41	6.9
136	57	61	2.9	2.1	PHQ432_0220 EZ401U	174	174	400	22.00	22/1	4000	8000	1.0	3.0	1.0	41	8.3
136	96	106	4.9	1.2	PHQ432_0220 EZ402U	200	238	400	22.00	22/1	4000	8000	1.7	3.0	1.0	41	9.4
545	23	25	4.8	4.2	PHQ431_0055 EZ501U	84	84	400	5.500	11/2	3000	6000	3.2	3.0	1.0	44	8.0
545	25	27	5.2	3.8	PHQ431_0055 EZ402U	84	84	400	5.500	11/2	3000	6000	1.9	3.0	1.0	44	8.1
545	36	45	7.7	2.6	PHQ431_0055 EZ404U	153	153	400	5.500	11/2	3000	6000	3.2	3.0	1.0	44	10
545	39	42	8.2	2.4	PHQ431_0055 EZ502U	164	164	400	5.500	11/2	3000	6000	5.5	3.0	1.0	44	9.5
545	51	59	11	1.9	PHQ431_0055 EZ503U	200	220	400	5.500	11/2	3000	6000	7.8	3.0	1.0	44	11
545	71	84	15	1.3	PHQ431_0055 EZ505U	200	220	400	5.500	11/2	3000	6000	12	3.0	1.0	44	14
PHQ4 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 200 \text{ Nm}$)																	
109	46	49	0.7	2.3	PHQ432_0550 EZ301U	143	143	400	55.00	55/1	4500	8000	0.21	3.0	1.0	38	5.8
109	77	86	1.1	1.3	PHQ432_0550 EZ302U	200	247	400	55.00	55/1	4500	8000	0.31	3.0	1.0	38	6.4
109	100	115	1.5	1.0	PHQ432_0550 EZ303U	200	247	400	55.00	55/1	4500	8000	0.42	3.0	1.0	38	6.9
156	32	34	0.8	3.2	PHQ432_0390 EZ301U	100	100	400	38.50	77/2	4500	8000	0.22	3.0	1.0	40	5.8
156	54	60	1.4	1.9	PHQ432_0390 EZ302U	179	179	400	38.50	77/2	4500	8000	0.32	3.0	1.0	40	6.4
156	70	81	1.8	1.5	PHQ432_0390 EZ303U	200	246	400	38.50	77/2	4500	8000	0.43	3.0	1.0	40	6.9
156	82	100	2.1	1.3	PHQ432_0390 EZ401U	200	246	400	38.50	77/2	4500	8000	0.96	3.0	1.0	40	8.3
218	23	24	1.0	4.2	PHQ432_0280 EZ301U	72	72	400	27.50	55/2	4500	8000	0.25	3.0	1.0	40	5.8
218	38	43	1.8	2.5	PHQ432_0280 EZ302U	128	128	400	27.50	55/2	4500	8000	0.35	3.0	1.0	40	6.4
218	50	58	2.3	1.9	PHQ432_0280 EZ303U	179	179	400	27.50	55/2	4500	8000	0.46	3.0	1.0	40	6.9
218	59	72	2.7	1.6	PHQ432_0280 EZ401U	200	217	400	27.50	55/2	4500	8000	0.99	3.0	1.0	40	8.3
218	90	125	4.1	1.1	PHQ432_0280 EZ402U	200	246	400	27.50	55/2	4500	8000	1.7	3.0	1.0	40	9.4
273	31	34	2.0	3.1	PHQ432_0220 EZ302U	102	102	400	22.00	22/1	4000	8000	0.39	3.0	1.0	41	6.4
273	40	46	2.6	2.4	PHQ432_0220 EZ303U	143	143	400	22.00	22/1	4000	8000	0.50	3.0	1.0	41	6.9
273	47	57	3.0	2.0	PHQ432_0220 EZ401U	174	174	400	22.00	22/1	4000	8000	1.0	3.0	1.0	41	8.3
273	72	100	4.6	1.3	PHQ432_0220 EZ402U	200	238	400	22.00	22/1	4000	8000	1.7	3.0	1.0	41	9.4
1091	18	23	4.8	4.2	PHQ431_0055 EZ501U	84	84	400	5.500	11/2	3000	6000	3.2	3.0	1.0	44	8.0
1091	18	26	4.9	4.1	PHQ431_0055 EZ402U	84	84	400	5.500	11/2	3000	6000	1.9	3.0	1.0	44	8.1
1091	27	41	7.3	2.8	PHQ431_0055 EZ502U	164	164	400	5.500	11/2	3000	6000	5.5	3.0	1.0	44	9.5
1091	31	44	8.1	2.5	PHQ431_0055 EZ404U	153	153	400	5.500	11/2	3000	6000	3.2	3.0	1.0	44	10
1091	33	56	8.7	2.3	PHQ431_0055 EZ503U	200	220	400	5.500	11/2	3000	6000	7.8	3.0	1.0	44	11
PHQ5 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 550 \text{ Nm}$)																	
55	143	153	0.8	2.2	PHQ532_0550 EZ401U	435	435	948	55.00	55/1	4000	8000	0.97	3.0	1.0	95	11
55	220	240	1.2	1.5	PHQ532_0550 EZ501U	500	500	948	55.00	55/1	4000	8000	2.9	3.0	1.0	95	12
55	240	266	1.3	1.3	PHQ532_0550 EZ402U	500	500	948	55.00	55/1	4000	8000	1.7	3.0	1.0	95	12
78	100	107	0.9	3.2	PHQ532_0390 EZ401U	304	304	948	38.50	77/2	4000	8000	1.0	3.0	1.0	100	11
78	154	168	1.4	2.1	PHQ532_0390 EZ501U	530	552	948	38.50	77/2	4000	8000	3.0	3.0	1.0	100	12
78	168	186	1.5	1.9	PHQ532_0390 EZ402U	530	552	948	38.50	77/2	4000	8000	1.7	3.0	1.0	100	12
78	247	308	2.3	1.3	PHQ532_0390 EZ404U	530	552	948	38.50	77/2	4000	8000	3.1	3.0	1.0	100	14

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_2$ [arcmin]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PHQ9 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 6600 \text{ Nm}$)																	
29	1361	2703	0.1	3.1	PHQ943_2100 EZ702U	6600	6600	13200	210.0	210/1	3000	6000	15	3.0	1.0	1200	92
36	786	1194	0.1	4.8	PHQ943_1680 EZ701U	3024	3024	13200	168.0	168/1	3000	6000	9.9	3.0	1.0	1204	90
36	1089	2162	0.1	3.5	PHQ943_1680 EZ702U	6199	6199	13200	168.0	168/1	3000	6000	15	3.0	1.0	1204	92
PHQ10 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 10000 \text{ Nm}$)																	
12	5895	6612	0.4	1.1	PHQ1043_1680 EZ813U	10000	–	20000	168.0	168/1	2800	4500	110	3.0	–	2064	156
13	5264	5904	0.5	1.2	PHQ1043_1500 EZ813U	10000	–	20000	150.0	150/1	2500	4000	115	3.0	–	2061	156
17	4211	4723	0.5	1.5	PHQ1043_1200 EZ813U	10000	–	20000	120.0	120/1	2000	3500	123	3.0	–	2062	156
17	6237	7426	0.8	1.0	PHQ1043_1200 EZ815U	10000	–	20000	120.0	120/1	2000	3500	186	3.0	–	2062	169
21	3369	3778	0.6	1.9	PHQ1043_0960 EZ813U	10000	–	20000	96.00	96/1	2000	3500	124	3.0	–	2068	156
21	4990	5941	0.9	1.3	PHQ1043_0960 EZ815U	10000	–	20000	96.00	96/1	2000	3500	187	3.0	–	2068	169
PHQ10 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 10000 \text{ Nm}$)																	
17	5443	9439	0.2	1.2	PHQ1043_2400 EZ813U	10000	–	20000	240.0	240/1	2800	4500	107	3.0	–	2055	156
17	5640	14502	0.2	1.2	PHQ1043_2400 EZ815U	10000	–	20000	240.0	240/1	2800	4500	170	3.0	–	2055	169
19	4763	8259	0.3	1.4	PHQ1043_2100 EZ813U	10000	–	20000	210.0	210/1	2800	4500	110	3.0	–	2059	156
19	4935	12689	0.3	1.3	PHQ1043_2100 EZ815U	10000	–	20000	210.0	210/1	2800	4500	173	3.0	–	2059	169
24	3810	6607	0.3	1.7	PHQ1043_1680 EZ813U	10000	–	20000	168.0	168/1	2800	4500	110	3.0	–	2064	156
24	3948	10152	0.3	1.6	PHQ1043_1680 EZ815U	10000	–	20000	168.0	168/1	2800	4500	173	3.0	–	2064	169
27	3402	5900	0.3	1.9	PHQ1043_1500 EZ813U	10000	–	20000	150.0	150/1	2500	4000	115	3.0	–	2061	156
27	3525	9064	0.3	1.8	PHQ1043_1500 EZ815U	10000	–	20000	150.0	150/1	2500	4000	178	3.0	–	2061	169
PHQ11 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 22000 \text{ Nm}$)																	
6.7	10527	11807	0.2	1.2	PHQ1143_3000 EZ813U	22000	–	40000	300.0	300/1	2800	4500	108	3.0	–	3490	266
8.3	8422	9446	0.2	1.5	PHQ1143_2400 EZ813U	22000	–	40000	240.0	240/1	2800	4500	108	3.0	–	3495	266
8.3	12474	14852	0.3	1.0	PHQ1143_2400 EZ815U	22000	–	40000	240.0	240/1	2800	4500	171	3.0	–	3495	278
9.5	7369	8265	0.2	1.8	PHQ1143_2100 EZ813U	22000	–	40000	210.0	210/1	2800	4500	111	3.0	–	3506	266
9.5	10915	12996	0.3	1.2	PHQ1143_2100 EZ815U	22000	–	40000	210.0	210/1	2800	4500	174	3.0	–	3506	278
12	5895	6612	0.2	2.2	PHQ1143_1680 EZ813U	21168	–	40000	168.0	168/1	2800	4500	112	3.0	–	3520	266
12	8732	10397	0.3	1.5	PHQ1143_1680 EZ815U	22000	–	40000	168.0	168/1	2800	4500	175	3.0	–	3520	278
13	5264	5904	0.2	2.5	PHQ1143_1500 EZ813U	18900	–	40000	150.0	150/1	2500	4000	118	3.0	–	3511	266
13	7796	9283	0.4	1.7	PHQ1143_1500 EZ815U	22000	–	40000	150.0	150/1	2500	4000	181	3.0	–	3511	278
17	4211	4723	0.3	3.1	PHQ1143_1200 EZ813U	15120	–	40000	120.0	120/1	2000	3500	127	3.0	–	3514	266
17	6237	7426	0.4	2.1	PHQ1143_1200 EZ815U	21600	–	40000	120.0	120/1	2000	3500	190	3.0	–	3514	278
21	3369	3778	0.3	3.9	PHQ1143_0960 EZ813U	12096	–	40000	96.00	96/1	2000	3500	130	3.0	–	3533	266
21	4990	5941	0.5	2.6	PHQ1143_0960 EZ815U	17280	–	40000	96.00	96/1	2000	3500	193	3.0	–	3533	278
PHQ11 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 22000 \text{ Nm}$)																	
13	6804	11799	0.1	1.9	PHQ1143_3000 EZ813U	22000	–	40000	300.0	300/1	2800	4500	108	3.0	–	3490	266
13	7050	18128	0.1	1.8	PHQ1143_3000 EZ815U	22000	–	40000	300.0	300/1	2800	4500	171	3.0	–	3490	278
17	5443	9439	0.1	2.3	PHQ1143_2400 EZ813U	22000	–	40000	240.0	240/1	2800	4500	108	3.0	–	3495	266
17	5640	14502	0.1	2.2	PHQ1143_2400 EZ815U	22000	–	40000	240.0	240/1	2800	4500	171	3.0	–	3495	278
19	4763	8259	0.1	2.7	PHQ1143_2100 EZ813U	22000	–	40000	210.0	210/1	2800	4500	111	3.0	–	3506	266
19	4935	12689	0.1	2.6	PHQ1143_2100 EZ815U	22000	–	40000	210.0	210/1	2800	4500	174	3.0	–	3506	278
24	3810	6607	0.2	3.4	PHQ1143_1680 EZ813U	21168	–	40000	168.0	168/1	2800	4500	112	3.0	–	3520	266
24	3948	10152	0.2	3.3	PHQ1143_1680 EZ815U	22000	–	40000	168.0	168/1	2800	4500	175	3.0	–	3520	278
27	3402	5900	0.2	3.8	PHQ1143_1500 EZ813U	18900	–	40000	150.0	150/1	2500	4000	118	3.0	–	3511	266
27	3525	9064	0.2	3.7	PHQ1143_1500 EZ815U	22000	–	40000	150.0	150/1	2500	4000	181	3.0	–	3511	278

4.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

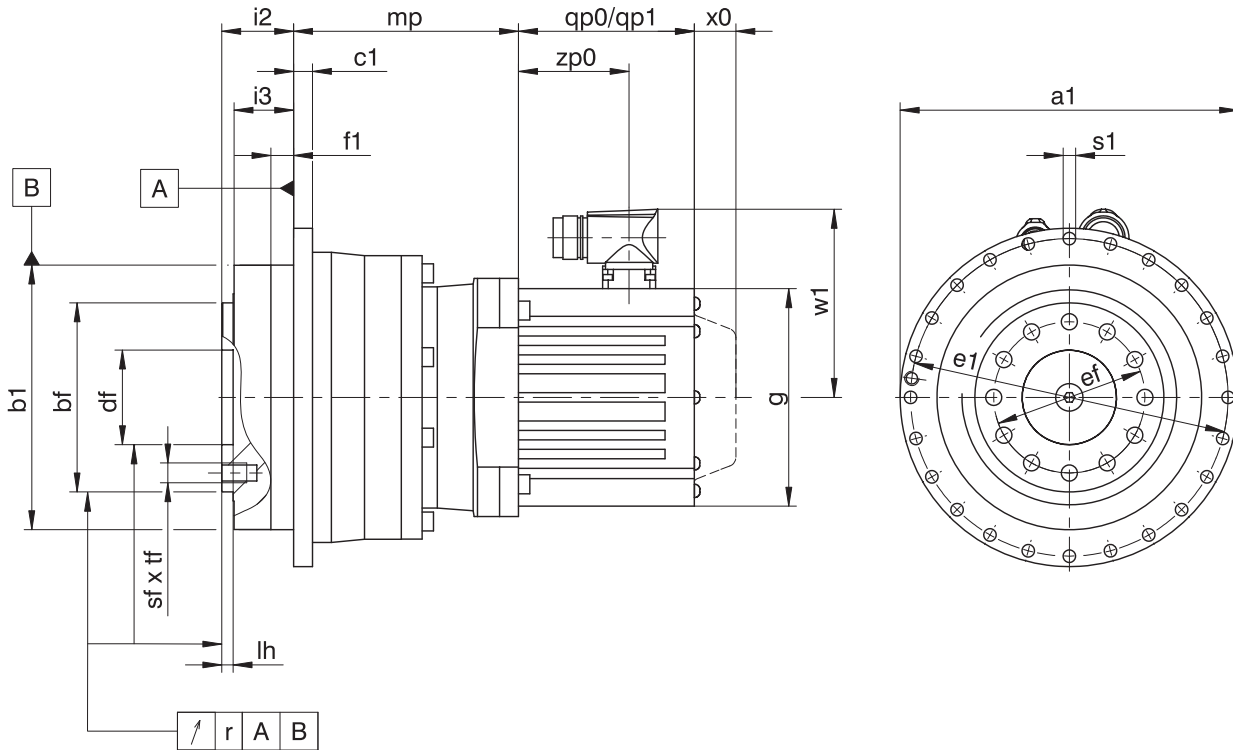
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

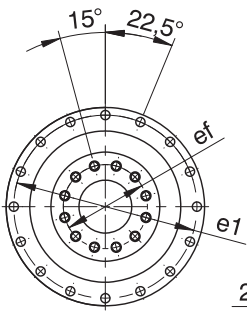
You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

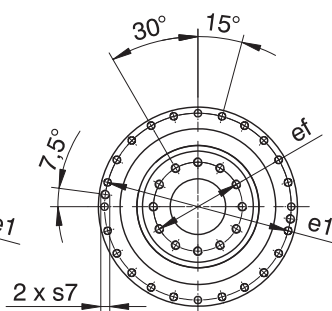
4.3.1 PHQ4 – PHQ10 F shaft design (flange shaft)



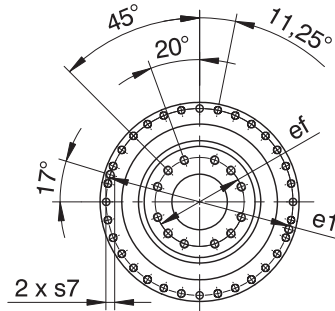
PHQ4/PHQ5



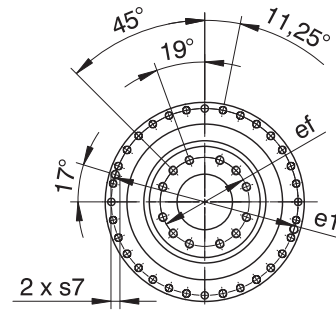
PHQ7/PHQ8



PHQ9



PHQ10



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	i2	i3	lh	r	Øs1	s7	sf	tf
PHQ431	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50	10	30	24	6	0.020	5.5	–	M6	11.0
PHQ432	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50	10	30	24	6	0.020	5.5	–	M6	11.0
PHQ531	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63	12	29	23	6	0.020	5.5	–	M8	12.0
PHQ532	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63	12	29	23	6	0.020	5.5	–	M8	12.0
PHQ731	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80	12	38	32	6	0.025	6.6	–	M10	16.0
PHQ732	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80	12	38	32	6	0.025	6.6	–	M10	16.0
PHQ733	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80	12	38	32	6	0.025	6.6	–	M10	16.0
PHQ832	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125	15	50	42	8	0.030	9.0	M10	M12	17.0
PHQ833	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125	15	50	42	8	0.030	9.0	M10	M12	17.0
PHQ942	300	255 _{h7}	180 _{h7}	18	90.0 ^{H6}	280	145	20	66	55	12	0.030	13.5	M8	M20	28.0
PHQ943	300	255 _{h7}	180 _{h7}	18	90.0 ^{H6}	280	145	20	66	55	12	0.030	13.5	M8	M20	28.0
PHQ1043	330	285 _{h7}	200 _{h7}	20	95.0 ^{H6}	310	166	20	75	60	10	0.040	13.5	M10	M24	35.0

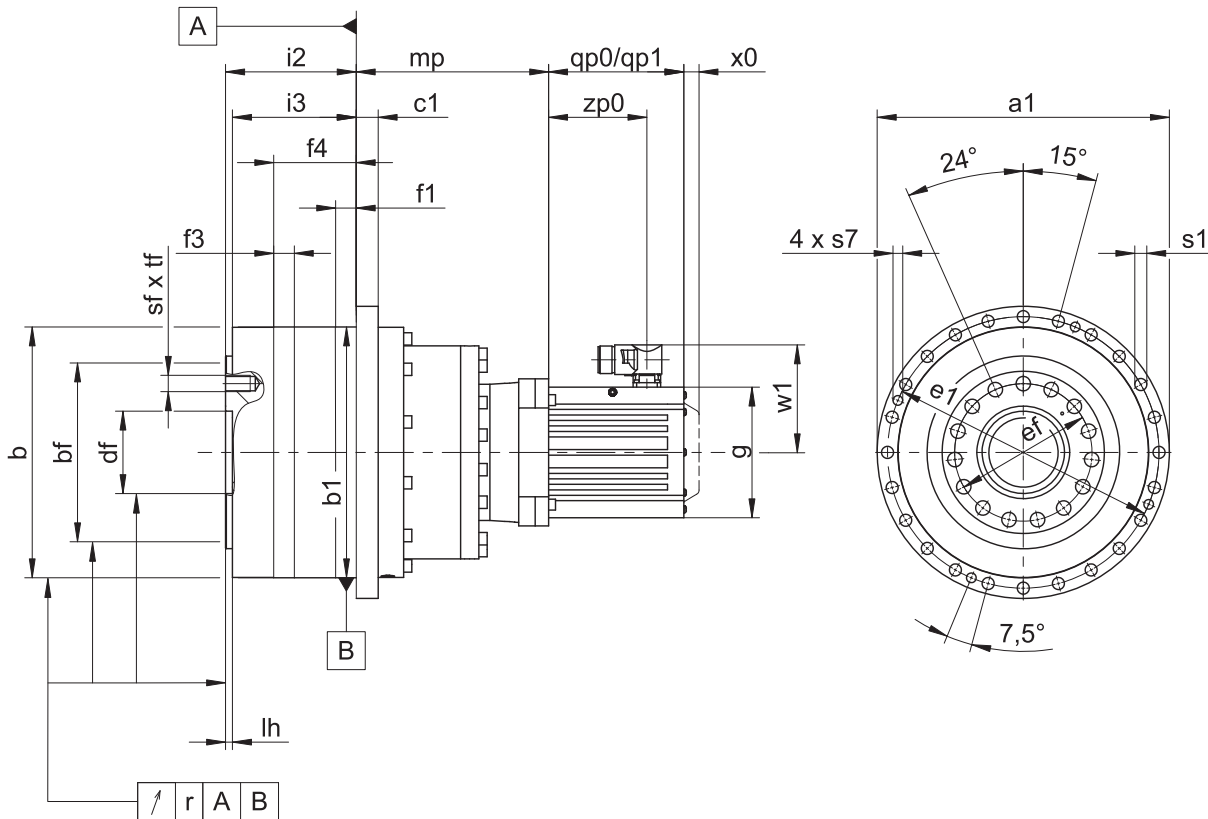
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
PHQ431	–	54.5	54.0	–	–
PHQ432	91.5	88.0	–	–	–
PHQ531	–	–	–	64.0	–
PHQ532	–	103.0	102.5	–	–
PHQ731	–	–	–	–	81.0
PHQ732	–	–	119.0	122.0	–
PHQ733	–	161.0	160.5	–	–
PHQ832	–	–	–	161.0	171.0
PHQ833	–	–	209.0	212.0	–
PHQ942	–	–	–	–	210.5
PHQ943	–	–	–	261.5	271.5
PHQ1043	–	–	–	–	324.5

4.3.2 PHQ11 F shaft design (flange shaft)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	$\varnothing a1$	$\varnothing b$	$\varnothing b1$	$\varnothing bf$	c1	$\varnothing df$	$\varnothing e1$	$\varnothing ef$	f1	f3	f4	i2	i3	lh	r	$\varnothing s1$	s7	sf	tf
PHQ1143	425	365_{g6}	365_{h6}	260_{h7}	32	120.0^{H6}	395	200	30	30	120	190	180	10	0.040	17.5	M16	M24	35.5

Dimensions of motors

Type	$\square g$	qp0	qp1	w1	x0	zp0
EZ813U	190	238	315	156.5	22	184
EZ815U	190	320	397	156.5	22	266

Dimensions of geared motors

Type	EZ8
PHQ1143	mp 280

4.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PHQ	7	3	3	S	F	S	S	0880	EZ401U
-----	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
PHQ	Type	Planetary gearbox
7	Size	7 (example)
3	Generation	Generation 3
4		Generation 4
1	Stages	Single-stage
2		Two-stage
3		Three-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
V		Reinforced bearing (PHQ4 – PHQ5)
S	Backlash	Standard
R		Reduced (PHQ4 – PHQ9)
0880	Transmission ratio (i x 10)	i = 88 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- For a detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Mounting position (for three-stage gearboxes), see the chapter [▶ 4.5.3](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 4.6.3](#)
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 4.6.4](#)

To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

4.5 Product description

4.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

4.5.2 Installation conditions

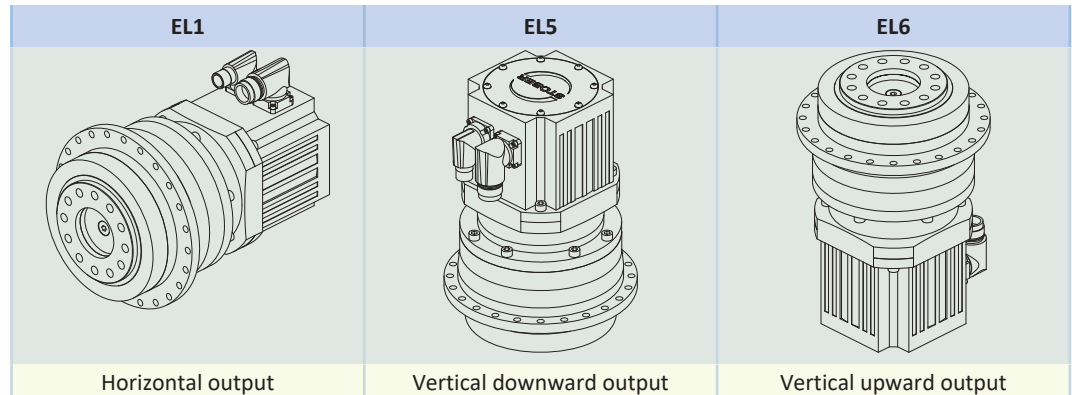
The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b_1$, and also at pilot $\varnothing b$ for size PHQ11. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

4.5.3 Mounting positions

The following table shows the standard mounting positions.

Please indicate the mounting position when ordering three-stage geared motors.



4.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

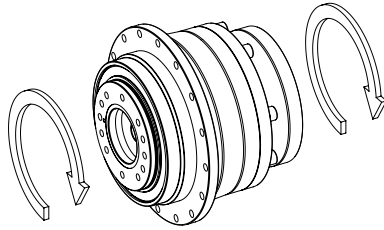
You will receive lubricants for use in the food industry upon request.

4.5.5 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	$\leq 90\text{ }^{\circ}\text{C}$
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} single-stage	96%
η_{get} two-stage	93%
η_{get} three-stage	90%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

4.5.6 Direction of rotation

The input and output rotate in the same direction.



4.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

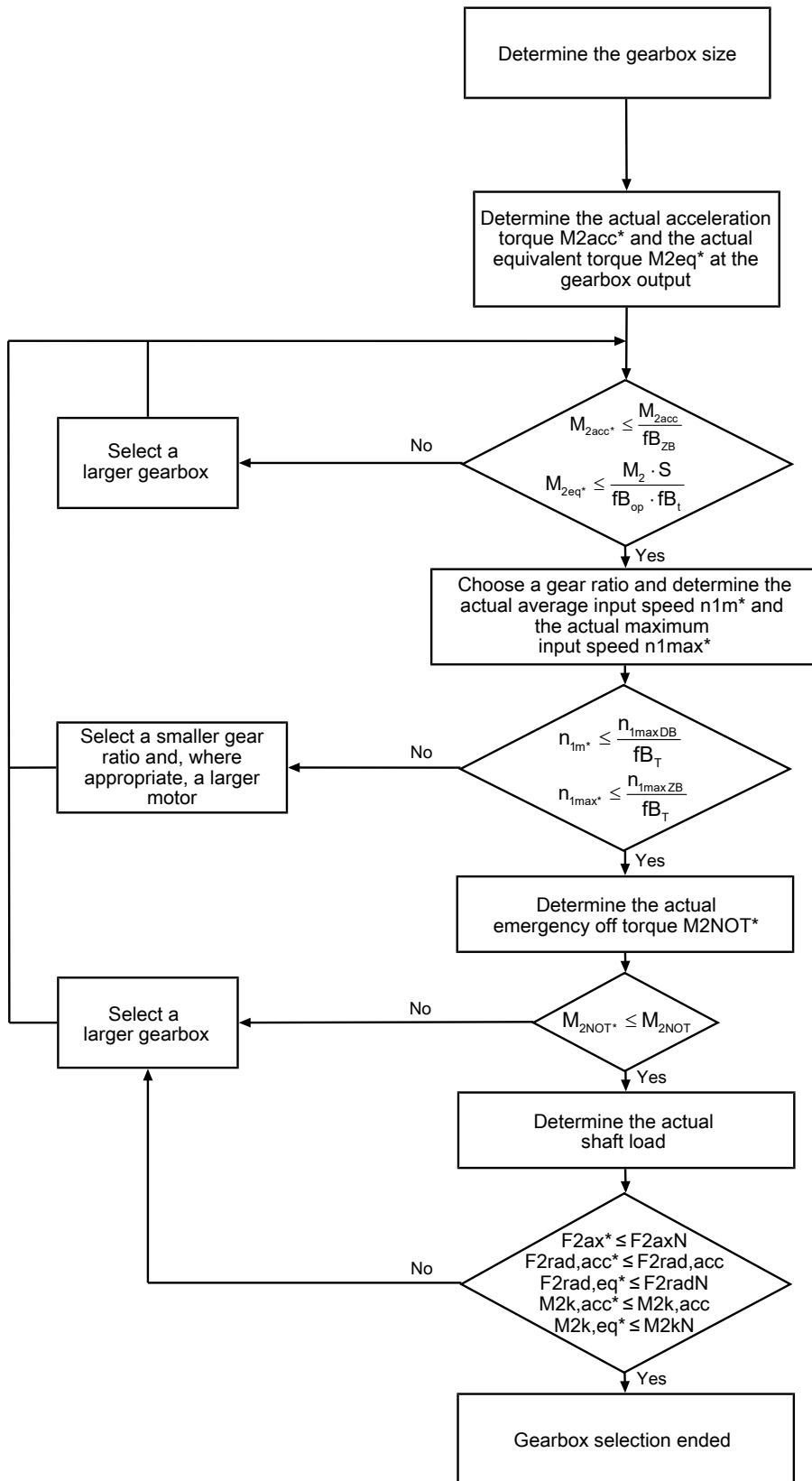
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

4.6.1 Drive selection

Drive selection for gearboxes

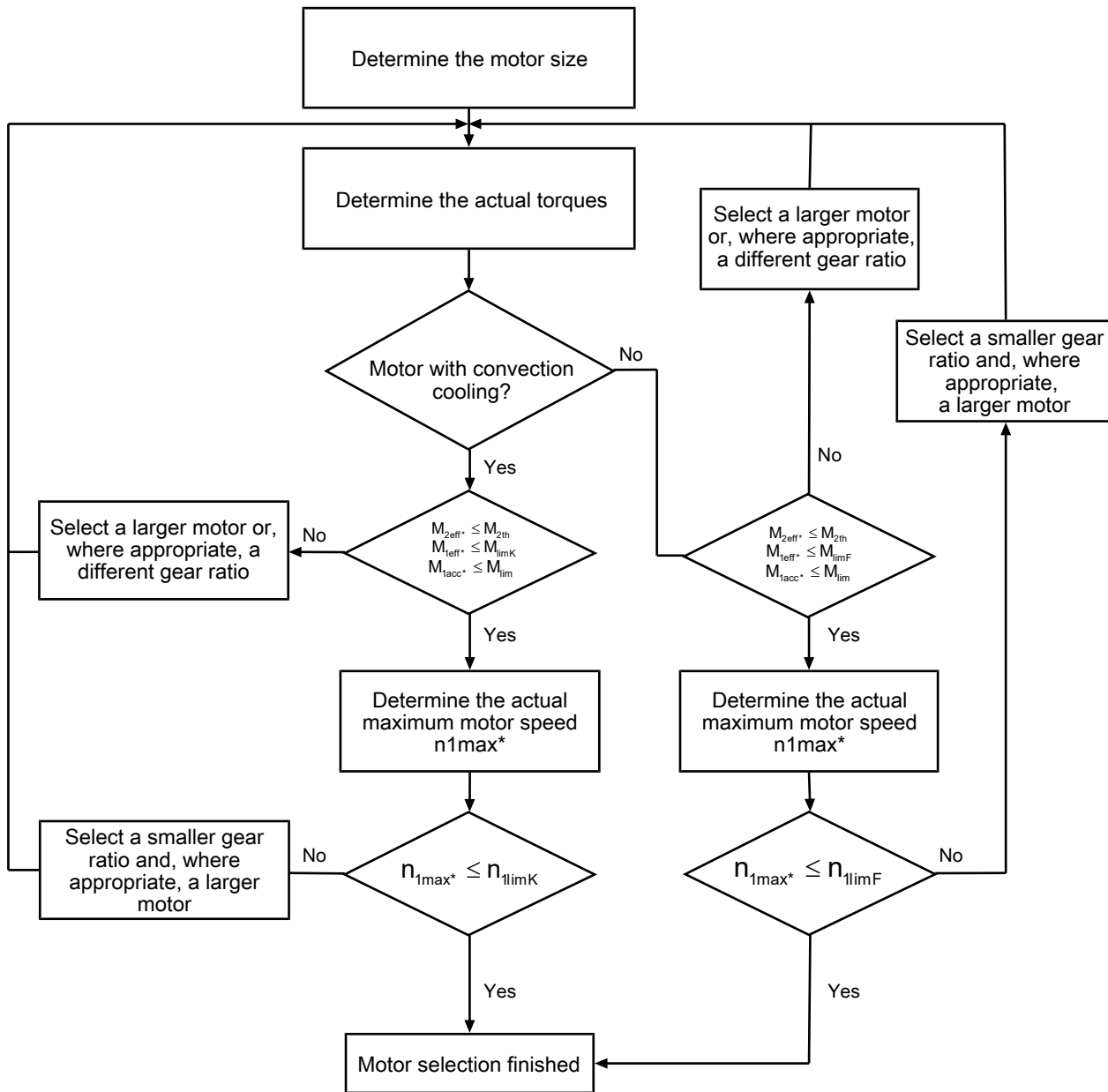


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

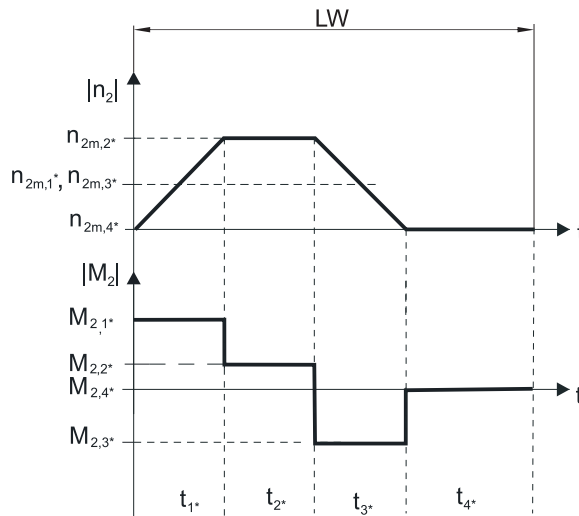
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

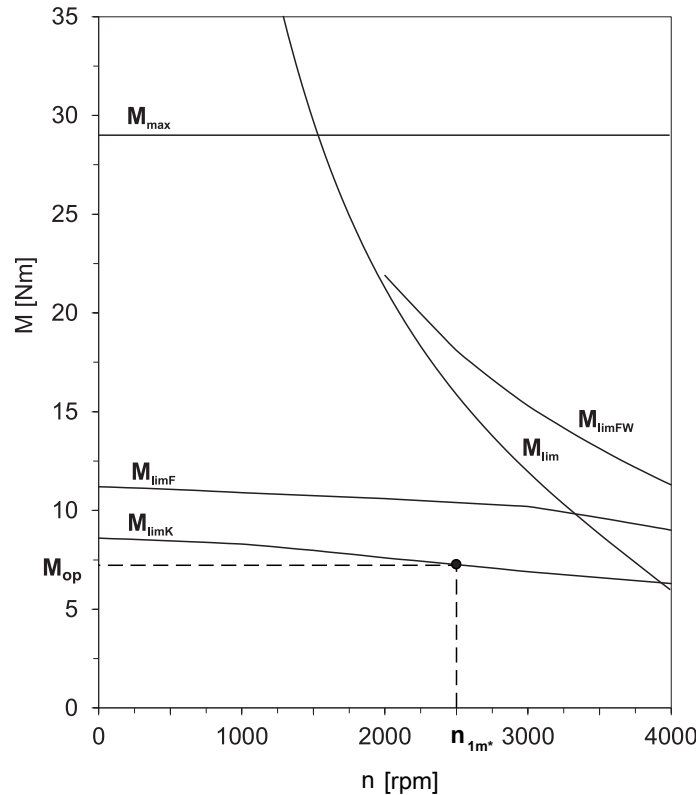
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.00
Reversing load cyclic operation		1.00
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

4.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PHQ4	83.0	2150	3095	3929	257	326	192
PHQ5	97.0	4150	4536	4897	440	475	429
PHQ7	86.0	6150	17045	17045	1466	1466	500
PHQ8	125.5	10050	27778	33333	3486	4183	1550
PHQ9	155.0	33000	48387	70968	7500	11000	7500
PHQ10	171.0	50000	51462	73099	8800	12500	9500
PHQ11	231.0	60000	47619	69264	11000	16000	11500
PHQ12	281.0	70000	64057	106761	18000	30000	14000

Permitted shaft loads for reinforced bearing V

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PHQ4	88.5	2900	4000	4000	354	354	217
PHQ5	104.0	5000	5500	5500	572	572	478

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

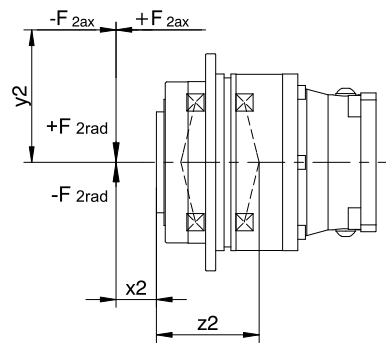


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

4.6.3 Recommendation for radial shaft seal rings

For a duty cycle $> 60\%$ and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

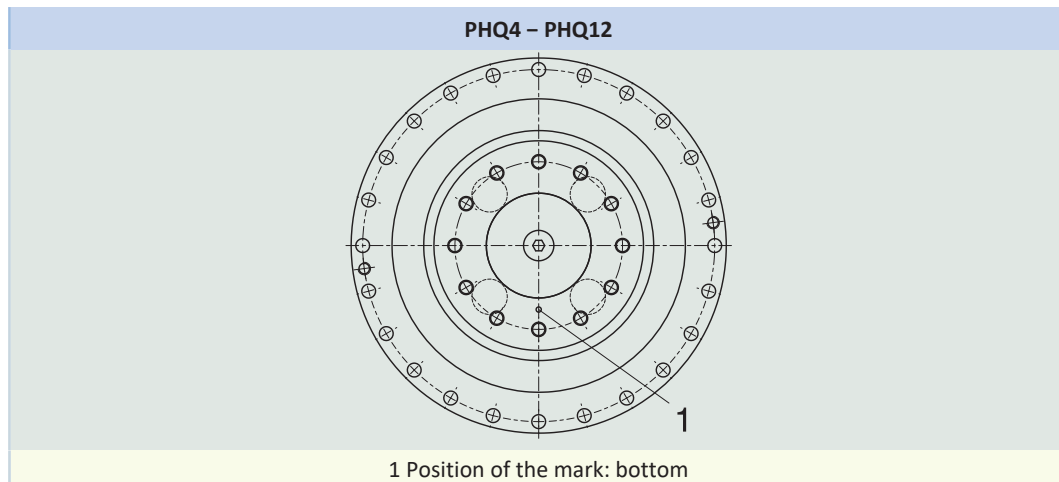
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

4.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

4.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PHQ43 – PHQ83, PHQ94 – PHQ124	443353_en
Operating manual for EZ synchronous servo motors	443032_en

5 PHV planetary geared motors

Table of contents

5.1	Overview	96
5.2	Selection tables	97
5.3	Dimensional drawings	98
5.3.1	F shaft design (flange shaft)	98
5.4	Type designation	100
5.5	Product description	100
5.5.1	Input options	100
5.5.2	Installation conditions	100
5.5.3	Lubricants	101
5.5.4	Other product features	101
5.5.5	Direction of rotation	101
5.6	Project configuration	101
5.6.1	Drive selection	102
5.6.2	Permitted shaft loads for the output shaft	106
5.6.3	Recommendation for radial shaft seal rings	107
5.6.4	Reverse operation	107
5.7	Additional documentation	107



5 Planetary geared motors

PHV

5.1 Overview

High-performance precision planetary geared motors for large gear ratios

Features

Power density	★★★★☆
Backlash	★★★★☆
Price category	€€€
Shaft load	★★★★★
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
Any mounting position	✓
Continuous operation without cooling	✓
Stiff output bearings due to pretension	✓
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	61 – 121
M_{2acc}	1638 – 7500 Nm
$\Delta\phi_2$	1 – 3 arcmin
η_{get}	90 %

5.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2accHT} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_2$ [arcmin]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PHV9 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 4250 \text{ Nm}$)																	
25	806	904	0.2	3.1	PHV943_1210 EZ701U	2178	2178	9000	121.0	121/1	2500	4500	9.8	3.0	1.0	805	67
25	1307	1568	0.4	1.9	PHV943_1210 EZ702U	4250	4250	9000	121.0	121/1	2500	4500	15	3.0	1.0	805	70
25	1797	2265	0.5	1.4	PHV943_1210 EZ703U	4250	4250	9000	121.0	121/1	2500	4500	23	3.0	1.0	805	72
25	2320	3289	0.7	1.1	PHV943_1210 EZ705U	4250	4250	9000	121.0	121/1	2500	4500	35	3.0	1.0	805	77
33	606	680	0.3	4.1	PHV943_0910 EZ701U	1638	1638	9000	91.00	91/1	2500	4500	11	3.0	1.0	838	67
33	983	1179	0.4	2.5	PHV943_0910 EZ702U	3358	3358	9000	91.00	91/1	2500	4500	16	3.0	1.0	838	70
33	1351	1704	0.6	1.9	PHV943_0910 EZ703U	4250	4250	9000	91.00	91/1	2500	4500	24	3.0	1.0	838	72
33	1744	2473	0.8	1.4	PHV943_0910 EZ705U	4250	4250	9000	91.00	91/1	2500	4500	36	3.0	1.0	838	77
49	659	791	0.5	3.8	PHV943_0610 EZ702U	2251	2251	9000	61.00	61/1	2500	4500	19	3.0	1.0	850	70
49	906	1142	0.7	2.8	PHV943_0610 EZ703U	3569	3569	9000	61.00	61/1	2500	4500	27	3.0	1.0	850	72
49	1169	1658	1.0	2.1	PHV943_0610 EZ705U	4250	4250	9000	61.00	61/1	2500	4500	40	3.0	1.0	850	77
PHV9 ($n_{1N} = 4500 \text{ min}^{-1}$, $M_{2acc,max} = 4250 \text{ Nm}$)																	
37	1318	2178	0.4	1.7	PHV943_1210 EZ703U	4250	4250	9000	121.0	121/1	2500	4500	23	3.0	1.0	805	72
37	1786	3267	0.6	1.3	PHV943_1210 EZ705U	4250	4250	9000	121.0	121/1	2500	4500	35	3.0	1.0	805	77
49	991	1638	0.5	2.3	PHV943_0910 EZ703U	4250	4250	9000	91.00	91/1	2500	4500	24	3.0	1.0	838	72
49	1343	2457	0.7	1.7	PHV943_0910 EZ705U	4250	4250	9000	91.00	91/1	2500	4500	36	3.0	1.0	838	77
74	664	1098	0.6	3.4	PHV943_0610 EZ703U	3569	3569	9000	61.00	61/1	2500	4500	27	3.0	1.0	850	72
74	900	1647	0.8	2.5	PHV943_0610 EZ705U	4250	4250	9000	61.00	61/1	2500	4500	40	3.0	1.0	850	77
PHV10 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 7500 \text{ Nm}$)																	
22	3193	3581	1.0	1.3	PHV1043_0910 EZ813U	7500	–	15000	91.00	91/1	2500	4500	108	3.0	–	1342	118
33	2141	2401	1.2	1.9	PHV1043_0610 EZ813U	7500	–	15000	61.00	61/1	2500	4500	111	3.0	–	1370	118
33	3170	3775	1.7	1.3	PHV1043_0610 EZ815U	7500	–	15000	61.00	61/1	2500	4500	174	3.0	–	1370	131
PHV10 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 7500 \text{ Nm}$)																	
44	2064	3579	0.6	1.9	PHV1043_0910 EZ813U	7500	–	15000	91.00	91/1	2500	4500	108	3.0	–	1342	118
44	2138	5499	0.7	1.9	PHV1043_0910 EZ815U	7500	–	15000	91.00	91/1	2500	4500	171	3.0	–	1342	131
66	1383	2399	0.8	2.9	PHV1043_0610 EZ813U	7500	–	15000	61.00	61/1	2500	4500	111	3.0	–	1370	118
66	1433	3686	0.8	2.8	PHV1043_0610 EZ815U	7500	–	15000	61.00	61/1	2500	4500	174	3.0	–	1370	131

5.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

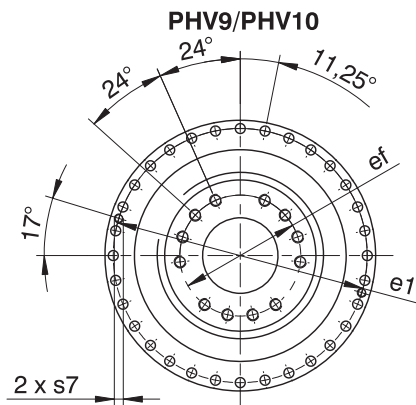
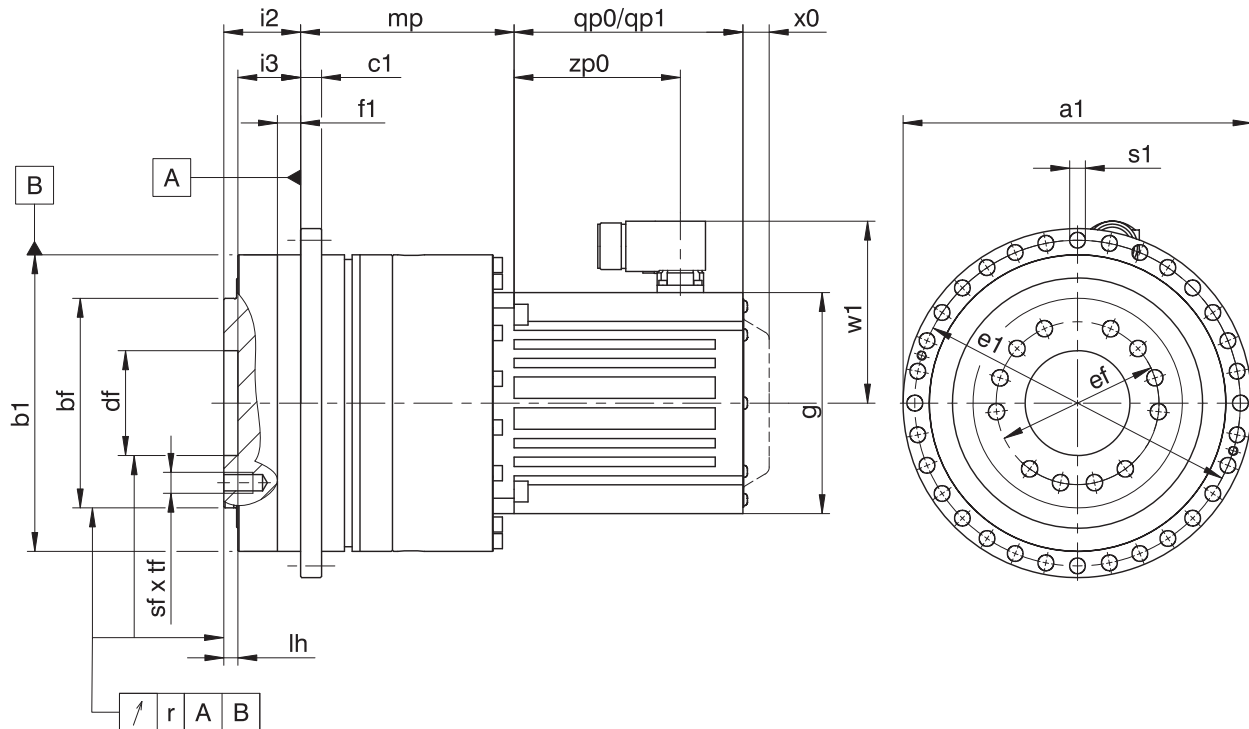
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

5.3.1 F shaft design (flange shaft)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method.

w1 Different for the One Cable Solution (OCS), see the chapter [▶ 17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	i2	i3	lh	r	Øs1	s7	sf	tf
PHV943	300	255 _{h7}	180 _{h7}	18	90 ^{H6}	280	140	20	66	55	12	0.030	13.5	M8	M16	24
PHV1043	330	285 _{h7}	200 _{h7}	20	95 ^{H6}	310	160	20	75	60	10	0.040	13.5	M10	M20	28

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ701U	145	102	161	115.0	22	64
EZ702U	145	127	186	115.0	22	89
EZ703U	145	152	211	115.0	22	114
EZ705U	145	207	266	134.0	22	165
EZ813U	190	238	315	156.5	22	184
EZ815U	190	320	397	156.5	22	266

Dimensions of geared motors

Type	EZ7 mp	EZ8 mp
PHV943	174	–
PHV1043	–	208

5.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PHV	9	4	3	S	F	S	S	0910	EZ703U
-----	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
PHV	Type	Planetary gearbox
9	Size	9 (example)
4	Generation	Generation 4
3	Stages	Three-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
S	Backlash	Standard
R		Reduced (PHV9)
0910	Transmission ratio (i x 10)	i = 91 (example)
EZ703U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 5.6.3](#)
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 5.6.4](#)

To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

5.5 Product description

5.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

5.5.2 Installation conditions

The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b1$. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

5.5.3 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate.

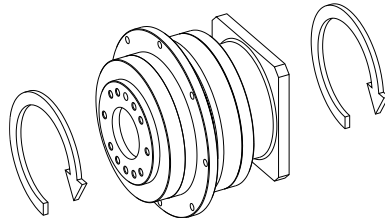
You will receive lubricants for use in the food industry upon request.

5.5.4 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} three-stage	90%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

5.5.5 Direction of rotation

The input and output rotate in the same direction.



5.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

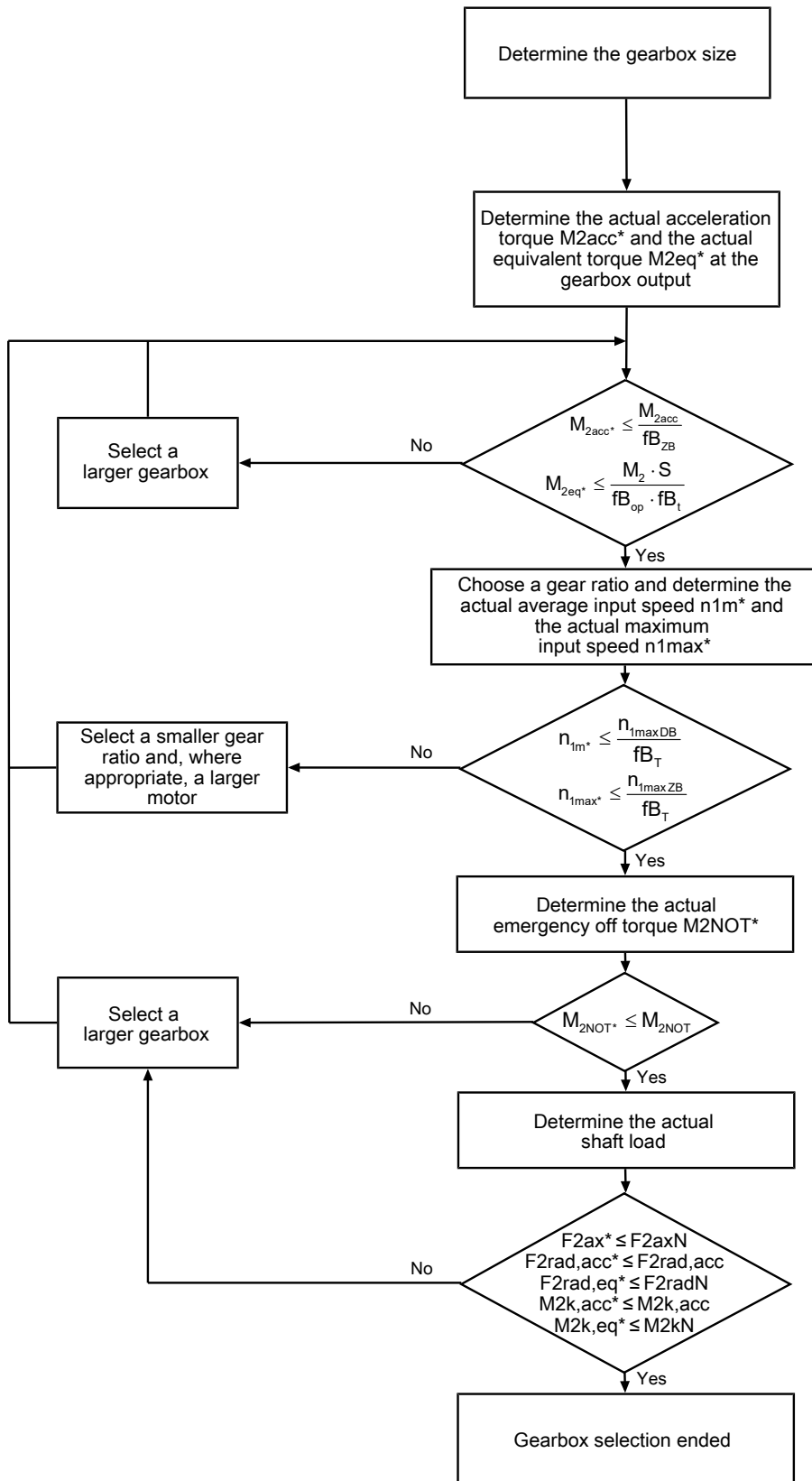
An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

¹Observe the protection class of all the components.

5.6.1 Drive selection

Drive selection for gearboxes

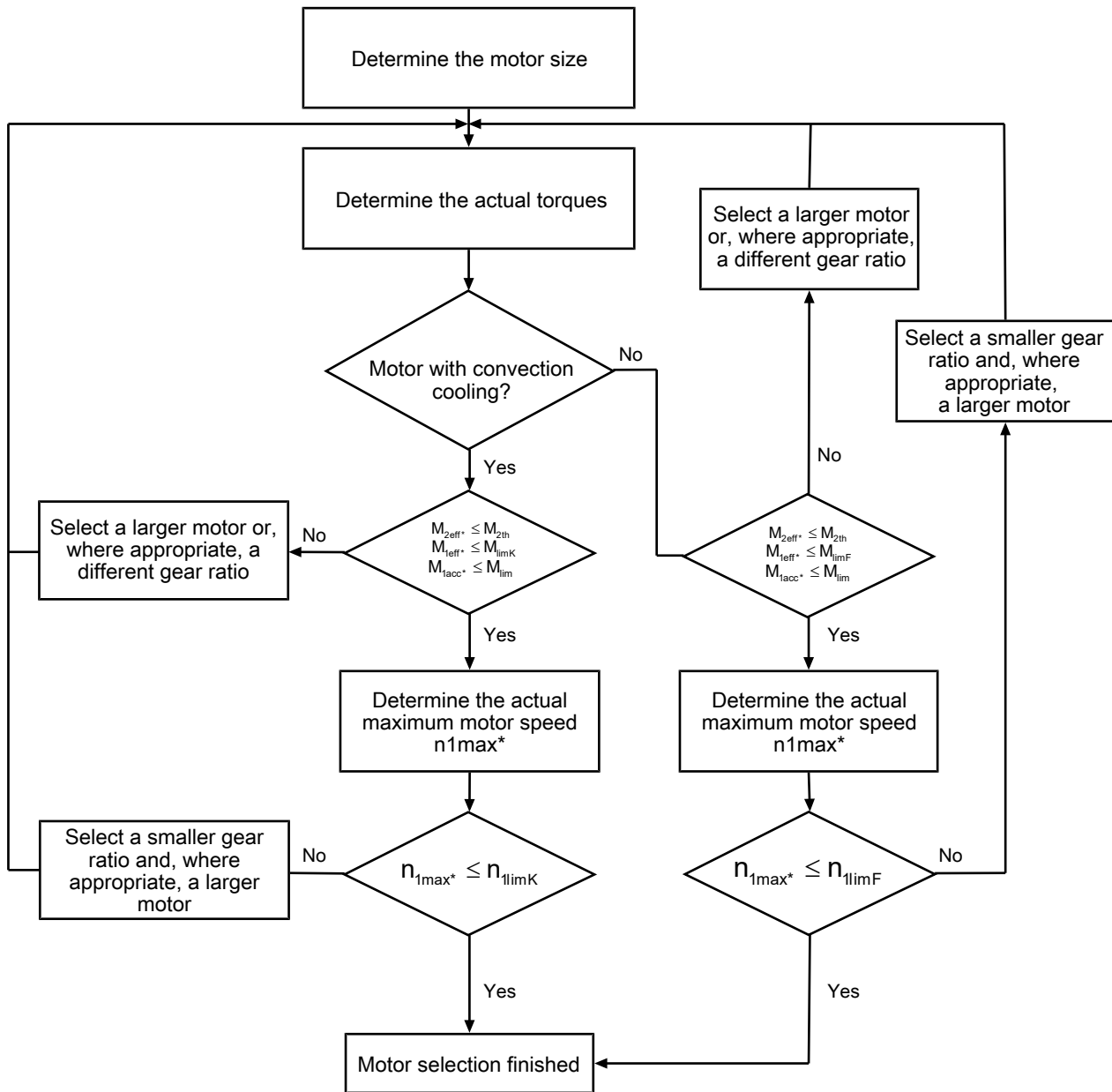


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{zB}}$ can be found in the corresponding tables in this chapter.

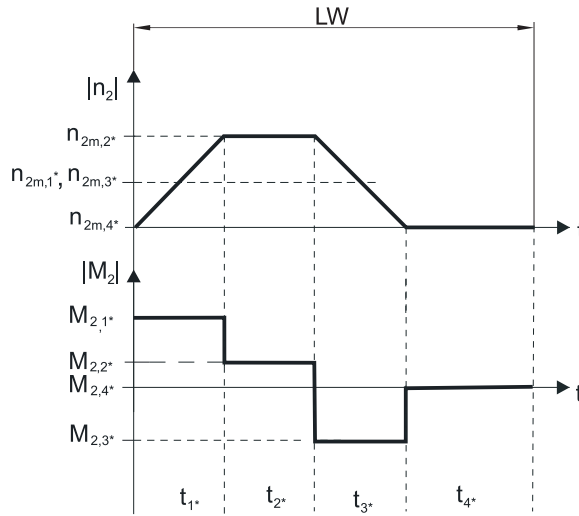
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

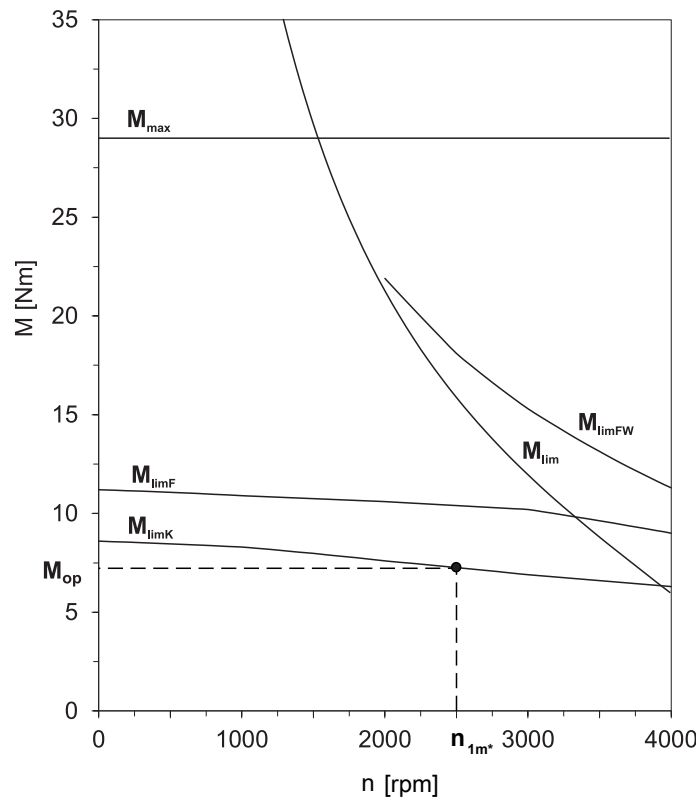
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.00
Reversing load cyclic operation		1.00
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

5.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PHV9	155.0	33000	48387	70968	7500	11000	7500
PHV10	171.0	50000	51462	73099	8800	12500	9500

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

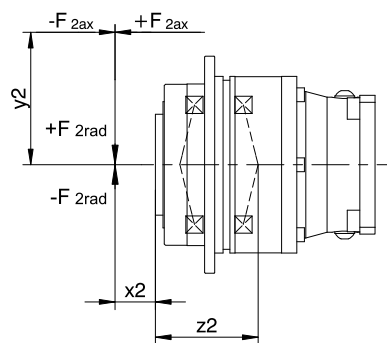


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

5.6.3 Recommendation for radial shaft seal rings

For a duty cycle > 60% and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

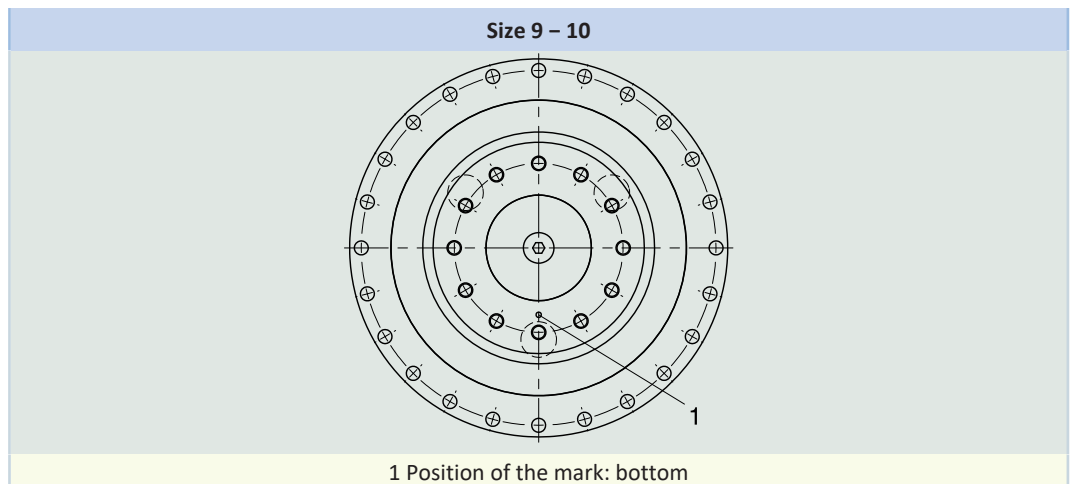
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

5.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

5.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

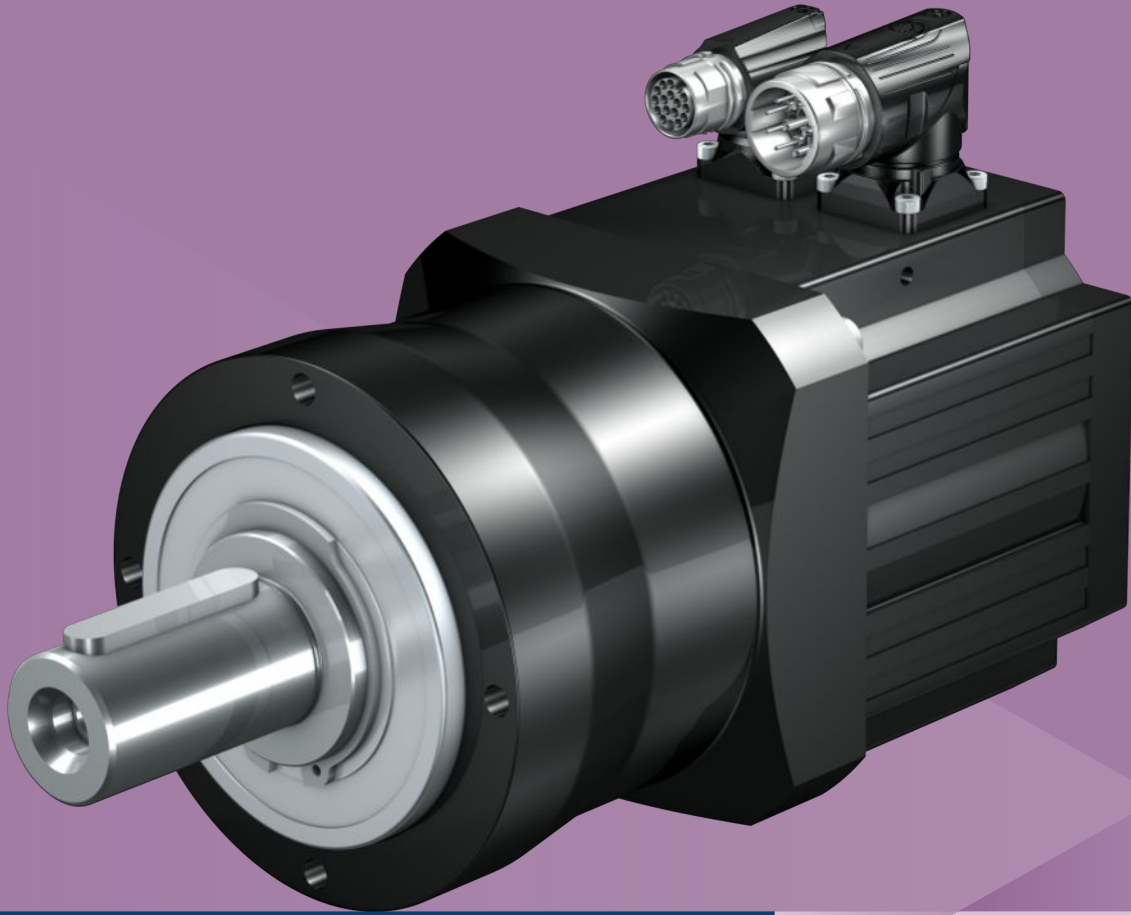
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PHV94 – PHV104	443355_en
Operating manual for EZ synchronous servo motors	443032_en

6 PE planetary geared motors

Table of contents

6.1	Overview	110
6.2	Selection tables	111
6.3	Dimensional drawings	115
6.3.1	P shaft design (solid shaft with feather key)	116
6.4	Type designation	118
6.5	Product description	118
6.5.1	Input options	118
6.5.2	Installation conditions	118
6.5.3	Lubricants	118
6.5.4	Other product features	119
6.5.5	Direction of rotation	119
6.6	Project configuration	119
6.6.1	Drive selection	120
6.6.2	Permitted shaft loads for the output shaft	124
6.6.3	Radial shaft seal rings	125
6.7	Additional documentation	125



6

Planetary geared motors

PE

6.1 Overview

Cost-efficient helical-gear planetary geared motors

Features

- Power density ★★★★★
- Backlash ★★★★★
- Price category €
- Shaft load ★★★★★
- Smooth operation ★★★★★
- Torsional stiffness ★★★★★
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free ✓
- Any mounting position ✓
- Non-contact sealing at the input ✓
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	3 – 50
M_{2acc}	5.7 – 250 Nm
$\Delta\phi_2$	8 – 13 arcmin
η_{get}	95 – 97 %

6.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n ₂ [rpm]	M ₂ [Nm]	M _{2,0} [Nm]	a _{th}	S	Type	M _{2acc} [Nm]	M _{2NOT} [Nm]	i	i _{exakt}	n _{1maxDB} [rpm]	n _{1maxZB} [rpm]	J ₁ [kgcm ²]	Δφ ₂ [arcmin]	C ₂ [Nm/ arcmin]	m [kg]
PE2 (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 19 Nm)															
429	6.3	6.5	2.7	1.0	PE221_0070 EZ301U	18	32	7.000	7/1	4500	8000	0.20	10.0	1.3	2.1
600	4.5	4.6	4.1	1.4	PE221_0050 EZ301U	14	32	5.000	5/1	4000	8000	0.21	10.0	1.4	2.1
750	3.6	3.7	5.4	1.8	PE221_0040 EZ301U	11	32	4.000	4/1	4000	8000	0.22	10.0	1.5	2.1
750	6.2	6.5	9.2	1.0	PE221_0040 EZ302U	19	32	4.000	4/1	4000	8000	0.32	10.0	1.5	2.7
PE2 (n_{1N} = 6000 min⁻¹, M_{2acc,max} = 19 Nm)															
375	6.1	6.7	6.3	1.0	PE222_0160 EZ202U	19	32	16.00	16/1	4000	8000	0.17	13.0	1.4	2.6
600	3.9	4.3	1.0	1.3	PE221_0100 EZ202U	14	32	10.00	10/1	4500	8000	0.13	10.0	1.2	2.1
857	2.7	3.0	1.5	1.9	PE221_0070 EZ202U	10	32	7.000	7/1	4500	8000	0.14	10.0	1.3	2.1
857	4.1	4.7	2.3	1.2	PE221_0070 EZ203U	18	32	7.000	7/1	4500	8000	0.18	10.0	1.3	2.3
1200	1.9	2.1	2.2	2.6	PE221_0050 EZ202U	7.2	32	5.000	5/1	4000	8000	0.14	10.0	1.4	2.1
1200	3.0	3.3	3.4	1.7	PE221_0050 EZ203U	13	32	5.000	5/1	4000	8000	0.18	10.0	1.4	2.3
1200	4.3	4.6	5.0	1.2	PE221_0050 EZ301U	14	32	5.000	5/1	4000	8000	0.21	10.0	1.4	2.1
1500	1.6	1.7	2.9	3.2	PE221_0040 EZ202U	5.7	32	4.000	4/1	4000	8000	0.16	10.0	1.5	2.1
1500	2.4	2.7	4.4	2.1	PE221_0040 EZ203U	10	32	4.000	4/1	4000	8000	0.20	10.0	1.5	2.3
1500	3.5	3.7	6.5	1.5	PE221_0040 EZ301U	11	32	4.000	4/1	4000	8000	0.22	10.0	1.5	2.1
PE3 (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 50 Nm)															
120	22	23	3.6	1.1	PE322_0250 EZ301U	50	90	25.00	25/1	4000	8000	0.23	10.0	4.2	3.6
150	18	18	4.0	1.3	PE322_0200 EZ301U	50	90	20.00	20/1	4000	8000	0.25	10.0	4.0	3.6
188	14	14	4.5	1.7	PE322_0160 EZ301U	43	90	16.00	16/1	4000	8000	0.25	10.0	4.1	3.6
300	9.0	9.2	0.7	2.3	PE321_0100 EZ301U	27	90	10.00	10/1	4000	7000	0.20	8.0	3.7	3.0
300	15	16	1.2	1.3	PE321_0100 EZ302U	48	90	10.00	10/1	4000	7000	0.30	8.0	3.7	3.6
300	20	21	1.6	1.0	PE321_0100 EZ303U	48	90	10.00	10/1	4000	7000	0.41	8.0	3.7	4.1
429	6.3	6.5	1.1	3.3	PE321_0070 EZ301U	19	90	7.000	7/1	4000	7000	0.22	8.0	4.1	3.0
429	11	11	1.8	1.9	PE321_0070 EZ302U	34	90	7.000	7/1	4000	7000	0.32	8.0	4.1	3.6
429	14	15	2.4	1.5	PE321_0070 EZ303U	48	90	7.000	7/1	4000	7000	0.43	8.0	4.1	4.1
429	19	20	3.3	1.1	PE321_0070 EZ401U	50	90	7.000	7/1	4000	7000	0.96	8.0	4.1	5.5
600	4.5	4.6	1.7	4.4	PE321_0050 EZ301U	14	90	5.000	5/1	3700	7000	0.24	8.0	4.5	3.0
600	7.7	8.1	2.9	2.6	PE321_0050 EZ302U	24	90	5.000	5/1	3700	7000	0.34	8.0	4.5	3.6
600	10	11	3.7	2.0	PE321_0050 EZ303U	34	90	5.000	5/1	3700	7000	0.45	8.0	4.5	4.1
600	14	15	5.1	1.5	PE321_0050 EZ401U	41	90	5.000	5/1	3700	7000	0.98	8.0	4.5	5.5
750	6.2	6.5	3.9	3.1	PE321_0040 EZ302U	19	85	4.000	4/1	3700	7000	0.38	8.0	4.4	3.6
750	8.0	8.5	5.1	2.4	PE321_0040 EZ303U	27	85	4.000	4/1	3700	7000	0.49	8.0	4.4	4.1
750	11	12	6.9	1.8	PE321_0040 EZ401U	33	85	4.000	4/1	3700	7000	1.0	8.0	4.4	5.5
750	18	20	12	1.0	PE321_0040 EZ402U	46	85	4.000	4/1	3700	7000	1.7	8.0	4.4	6.6
1000	4.6	4.9	6.3	3.6	PE321_0030 EZ302U	15	64	3.000	3/1	3500	6000	0.47	8.0	3.5	3.6
1000	6.0	6.4	8.2	2.8	PE321_0030 EZ303U	20	64	3.000	3/1	3500	6000	0.58	8.0	3.5	4.1
1000	8.1	8.7	11	2.0	PE321_0030 EZ401U	25	64	3.000	3/1	3500	6000	1.1	8.0	3.5	5.5
1000	14	15	19	1.2	PE321_0030 EZ402U	40	64	3.000	3/1	3500	6000	1.8	8.0	3.5	6.6
PE3 (n_{1N} = 6000 min⁻¹, M_{2acc,max} = 50 Nm)															
150	15	17	1.5	1.2	PE322_0400 EZ202U	44	88	40.00	40/1	4500	8000	0.14	10.0	3.9	3.5
171	13	15	1.6	1.4	PE322_0350 EZ202U	49	90	35.00	35/1	4000	8000	0.15	10.0	4.2	3.5
214	11	12	1.8	1.8	PE322_0280 EZ202U	39	88	28.00	28/1	4000	8000	0.15	10.0	4.0	3.5
214	16	18	2.8	1.2	PE322_0280 EZ203U	44	88	28.00	28/1	4000	8000	0.19	10.0	4.0	3.8
240	9.5	10	1.9	2.0	PE322_0250 EZ202U	35	90	25.00	25/1	4000	8000	0.17	10.0	4.2	3.5
240	14	16	2.9	1.3	PE322_0250 EZ203U	50	90	25.00	25/1	4000	8000	0.21	10.0	4.2	3.8
300	7.6	8.4	2.2	2.5	PE322_0200 EZ202U	28	90	20.00	20/1	4000	8000	0.19	10.0	4.0	3.5
300	12	13	3.3	1.6	PE322_0200 EZ203U	50	90	20.00	20/1	4000	8000	0.23	10.0	4.0	3.8
300	17	18	4.8	1.1	PE322_0200 EZ301U	50	90	20.00	20/1	4000	8000	0.25	10.0	4.0	3.6
375	6.1	6.7	2.4	3.1	PE322_0160 EZ202U	22	90	16.00	16/1	4000	8000	0.19	10.0	4.1	3.5
375	9.3	10	3.7	2.0	PE322_0160 EZ203U	41	90	16.00	16/1	4000	8000	0.23	10.0	4.1	3.8
375	14	14	5.4	1.4	PE322_0160 EZ301U	43	90	16.00	16/1	4000	8000	0.25	10.0	4.1	3.6
600	8.6	9.2	0.9	1.9	PE321_0100 EZ301U	27	90	10.00	10/1	4000	7000	0.20	8.0	3.7	3.0
600	15	16	1.4	1.1	PE321_0100 EZ302U	48	90	10.00	10/1	4000	7000	0.30	8.0	3.7	3.6

6.2 Selection tables 6 PE planetary geared motors

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_2$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
PE5 ($n_{IN} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 250 \text{ Nm}$)															
750	47	56	18	2.2	PE521_0040 EZ702U	159	500	4.000	4/1	2600	5000	15	8.0	37	17
750	52	62	20	2.0	PE521_0040 EZ505U	250	345	4.000	4/1	2600	5000	13	8.0	37	17
750	64	81	25	1.6	PE521_0040 EZ703U	250	500	4.000	4/1	2600	5000	23	8.0	37	19
750	83	117	32	1.2	PE521_0040 EZ705U	250	500	4.000	4/1	2600	5000	35	8.0	37	24
1000	22	23	23	3.3	PE521_0030 EZ502U	90	259	3.000	3/1	2500	4500	7.1	8.0	33	12
1000	22	24	23	3.3	PE521_0030 EZ701U	58	360	3.000	3/1	2500	4500	10	8.0	33	14
1000	28	32	30	2.5	PE521_0030 EZ503U	125	259	3.000	3/1	2500	4500	9.5	8.0	33	14
1000	35	42	37	2.0	PE521_0030 EZ702U	119	360	3.000	3/1	2500	4500	16	8.0	33	17
1000	39	47	42	1.8	PE521_0030 EZ505U	180	259	3.000	3/1	2500	4500	14	8.0	33	17
1000	48	61	51	1.5	PE521_0030 EZ703U	180	360	3.000	3/1	2500	4500	24	8.0	33	19
1000	62	88	66	1.2	PE521_0030 EZ705U	180	360	3.000	3/1	2500	4500	36	8.0	33	24
PE5 ($n_{IN} = 4500 \text{ min}^{-1}$, $M_{2acc,max} = 250 \text{ Nm}$)															
643	65	104	8.4	1.4	PE521_0070 EZ505U	250	500	7.000	7/1	2800	5000	12	8.0	32	17
643	82	136	11	1.1	PE521_0070 EZ703U	250	500	7.000	7/1	2800	5000	22	8.0	32	19
900	46	74	13	2.0	PE521_0050 EZ505U	250	432	5.000	5/1	2600	5000	13	8.0	36	17
900	59	97	16	1.5	PE521_0050 EZ703U	250	500	5.000	5/1	2600	5000	22	8.0	36	19
900	80	146	22	1.1	PE521_0050 EZ705U	250	500	5.000	5/1	2600	5000	35	8.0	36	24
1125	37	59	16	2.4	PE521_0040 EZ505U	250	345	4.000	4/1	2600	5000	13	8.0	37	17
1125	47	78	21	1.9	PE521_0040 EZ703U	250	500	4.000	4/1	2600	5000	23	8.0	37	19
1125	64	116	28	1.4	PE521_0040 EZ705U	250	500	4.000	4/1	2600	5000	35	8.0	37	24
1500	28	45	34	2.3	PE521_0030 EZ505U	180	259	3.000	3/1	2500	4500	14	8.0	33	17
1500	35	58	43	1.8	PE521_0030 EZ703U	180	360	3.000	3/1	2500	4500	24	8.0	33	19
1500	48	87	58	1.3	PE521_0030 EZ705U	180	360	3.000	3/1	2500	4500	36	8.0	33	24
PE5 ($n_{IN} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 250 \text{ Nm}$)															
150	87	106	2.1	1.2	PE522_0400 EZ401U	240	480	40.00	40/1	3600	6000	0.99	10.0	33	12
171	76	93	2.2	1.3	PE522_0350 EZ401U	250	500	35.00	35/1	3600	6000	1.0	10.0	33	12
214	61	74	2.5	1.6	PE522_0280 EZ401U	226	480	28.00	28/1	3600	6000	1.0	10.0	33	12
214	90	117	3.6	1.1	PE522_0280 EZ501U	240	480	28.00	28/1	3600	6000	3.0	10.0	33	13
214	93	130	3.7	1.1	PE522_0280 EZ402U	240	480	28.00	28/1	3600	6000	1.7	10.0	33	13
240	55	67	2.6	1.8	PE522_0250 EZ401U	202	500	25.00	25/1	3400	6000	1.1	10.0	33	12
240	81	105	3.8	1.2	PE522_0250 EZ501U	250	500	25.00	25/1	3400	6000	3.1	10.0	33	13
240	83	116	4.0	1.2	PE522_0250 EZ402U	250	500	25.00	25/1	3400	6000	1.8	10.0	33	13
300	44	53	2.9	2.3	PE522_0200 EZ401U	162	500	20.00	20/1	3400	6000	1.3	10.0	33	12
300	65	84	4.3	1.6	PE522_0200 EZ501U	250	500	20.00	20/1	3400	6000	3.2	10.0	33	13
300	67	93	4.4	1.5	PE522_0200 EZ402U	250	500	20.00	20/1	3400	6000	2.0	10.0	33	13
300	99	148	6.6	1.0	PE522_0200 EZ502U	250	500	20.00	20/1	3400	6000	5.5	10.0	33	15
375	35	43	3.3	2.9	PE522_0160 EZ401U	129	480	16.00	16/1	3400	6000	1.3	10.0	33	12
375	52	67	4.8	2.0	PE522_0160 EZ501U	240	480	16.00	16/1	3400	6000	3.3	10.0	33	13
375	53	74	4.9	1.9	PE522_0160 EZ402U	240	480	16.00	16/1	3400	6000	2.0	10.0	33	13
375	79	119	7.4	1.3	PE522_0160 EZ502U	240	480	16.00	16/1	3400	6000	5.6	10.0	33	15
375	88	128	8.2	1.1	PE522_0160 EZ404U	240	480	16.00	16/1	3400	6000	3.3	10.0	33	15
375	94	161	8.8	1.1	PE522_0160 EZ503U	240	480	16.00	16/1	3400	6000	7.9	10.0	33	16

6.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

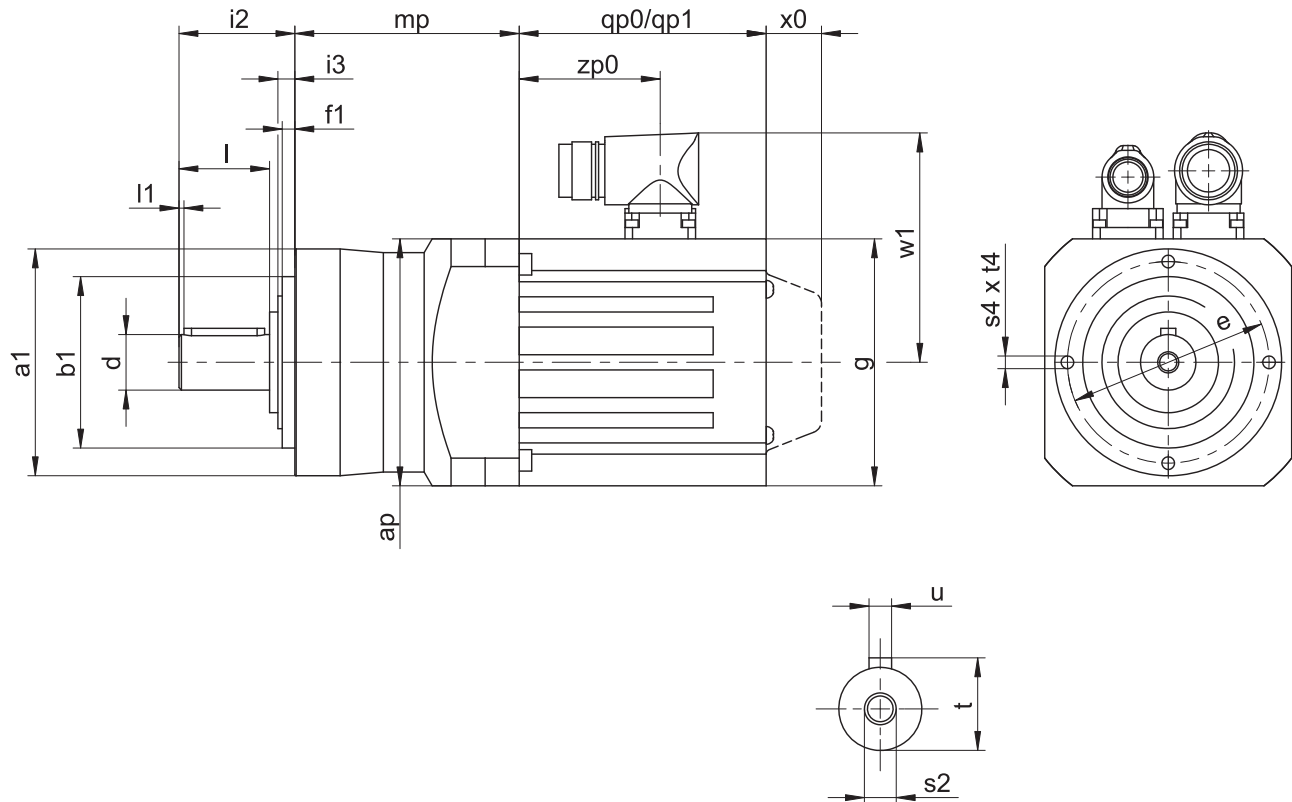
Tolerances

Solid shaft	Tolerance
Fit	ISO k6
Feather keys	DIN 6885-1, high form A
Balancing	With half feather key

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

6.3.1 P shaft design (solid shaft with feather key)



- qp0 Applies to motors without brake.
- qp1 Applies to motors with brake.
- x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method
- w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Ød	Øe	f1	i2	i3	l	l1	s2	s4	t	t4	u
PE221	50	35 _{h6}	12 _{k6}	44	4	24.5	5.0	18	2	M4	M4	13.5	8	A4×4×14
PE222	50	35 _{h6}	12 _{k6}	44	4	24.5	5.0	18	2	M4	M4	13.5	8	A4×4×14
PE321	70	52 _{h6}	16 _{k6}	62	5	36.0	6.0	28	2	M5	M5	18.0	10	A5×5×22
PE322	70	52 _{h6}	16 _{k6}	62	5	36.0	6.0	28	2	M5	M5	18.0	10	A5×5×22
PE421	90	68 _{h6}	22 _{k6}	80	5	46.0	6.5	36	2	M8	M6	24.5	12	A6×6×32
PE422	90	68 _{h6}	22 _{k6}	80	5	46.0	6.5	36	2	M8	M6	24.5	12	A6×6×32
PE521	120	90 _{h6}	32 _{k6}	108	6	70.0	8.0	58	4	M12	M8	35.0	16	A10×8×50
PE522	120	90 _{h6}	32 _{k6}	108	6	70.0	8.0	58	4	M12	M8	35.0	16	A10×8×50

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7	
	ap	mp	ap	mp	ap	mp	ap	mp	ap	mp
PE221	□55	59.5	□72	73.0	-	-	-	-	-	-
PE222	□55	91.5	-	-	-	-	-	-	-	-
PE321	-	-	□72	86.5	□98	83.0	-	-	-	-
PE322	∅75	106.5	∅75	120.0	-	-	-	-	-	-
PE421	-	-	-	-	□98	89.0	□115	91.5	-	-
PE422	-	-	∅100	129.0	∅100	125.5	-	-	-	-
PE521	-	-	-	-	-	-	∅120	110.0	□145	113.0
PE522	-	-	-	-	∅120	152.0	∅120	151.5	-	-

6.4 Type designation

In this chapter, you can find an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PE	4	2	2	S	P	S	S	0200	EZ401U
----	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
PE	Type	Planetary gearbox
4	Size	4 (example)
2	Generation	Generation 2
1	Stages	Single-stage
2		Two-stage
S	Housing	Standard
P	Shaft	Solid shaft with feather key
S	Bearing	Standard bearing
S	Backlash	Standard
0200	Transmission ratio (i x 10)	i = 20 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)

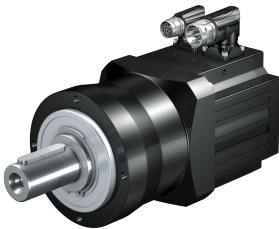
To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

6.5 Product description

6.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

LM Lean motor



Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

6.5.2 Installation conditions

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 10.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

6.5.3 Lubricants

STOBBER fills the gearboxes with the amount and type of lubricant specified on the nameplate.

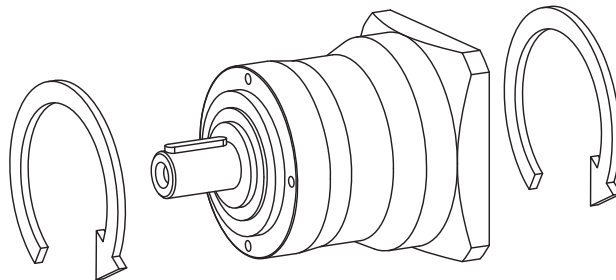
You will receive lubricants for use in the food industry upon request.

6.5.4 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 80 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} single-stage	97%
η_{get} two-stage	95%
Protection class:¹	
Gearbox	IP64
Motor	IP56, optionally IP66

6.5.5 Direction of rotation

The input and output rotate in the same direction.



6.6 Project configuration

Project your drives using our SERVOSOFT designing software. Download SERVOSOFT free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

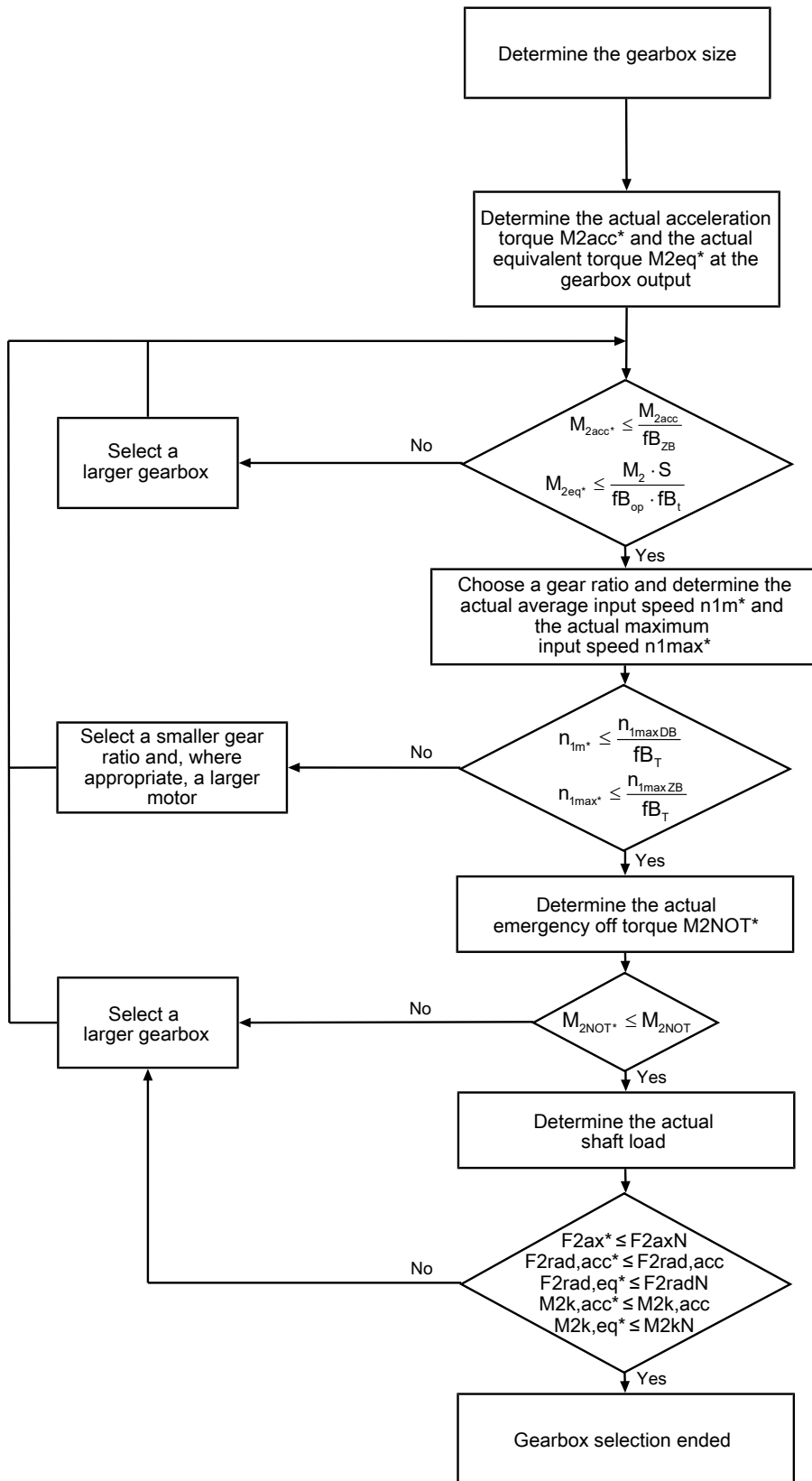
An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

¹Observe the protection class of all the components.

6.6.1 Drive selection

Drive selection for gearboxes

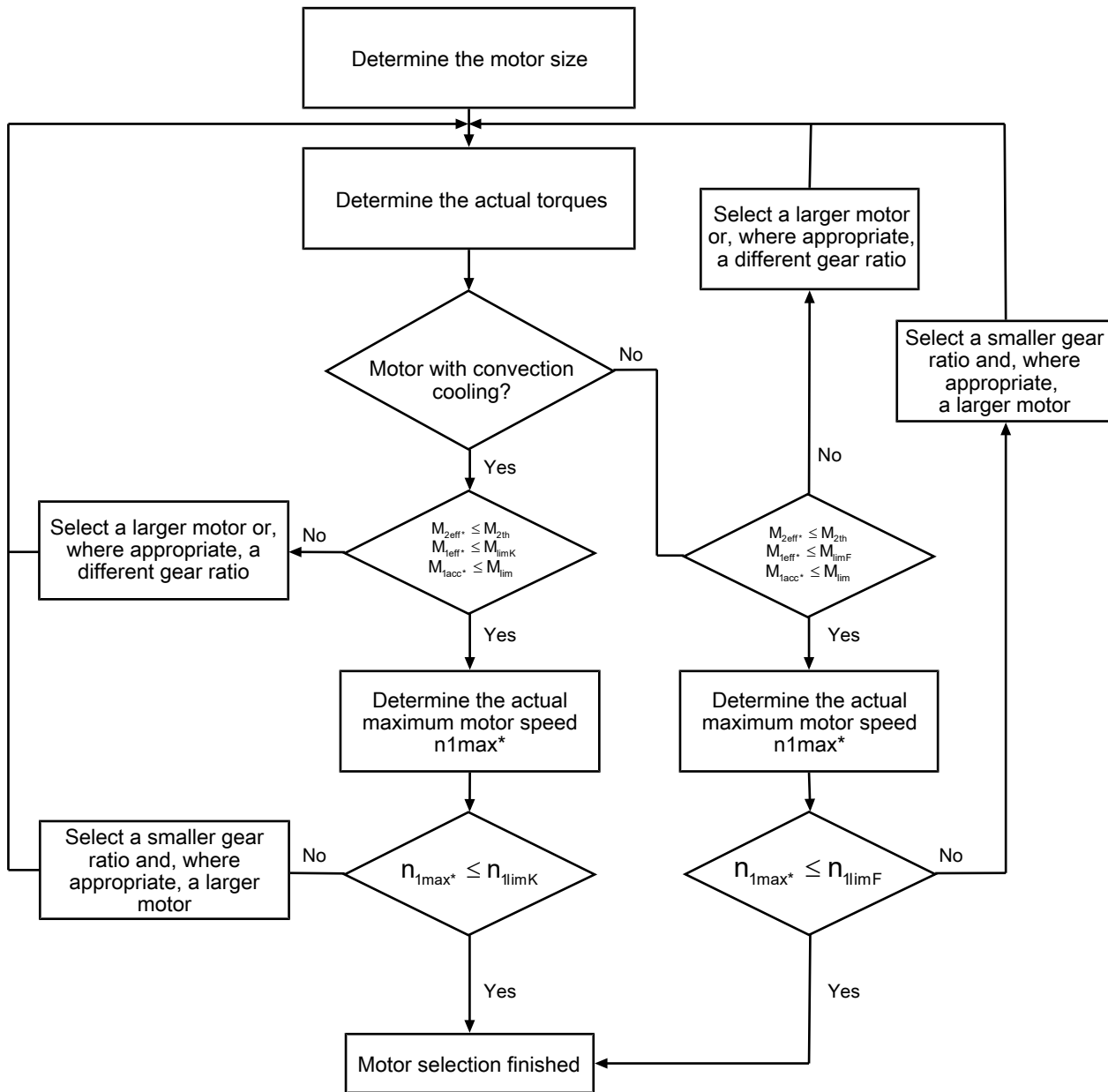


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{zB}}$ can be found in the corresponding tables in this chapter.

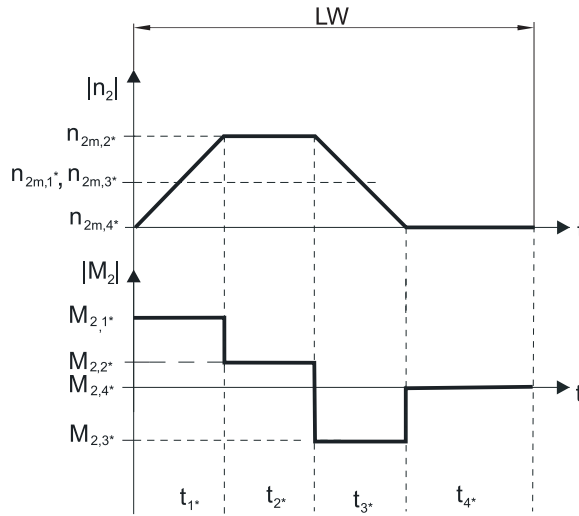
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

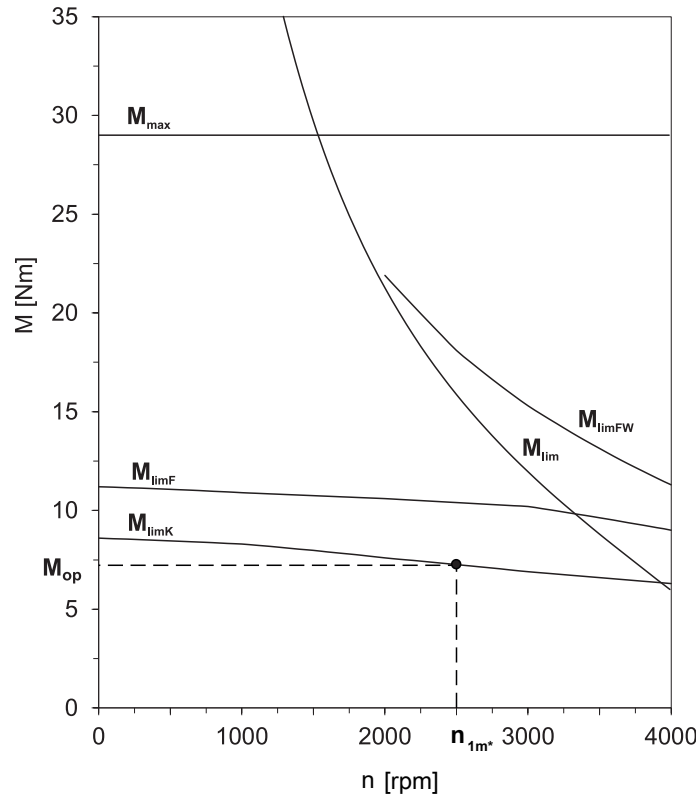
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000} \right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.00
Reversing load cyclic operation		1.00
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

6.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
PE2	8.0	400	800	800	13	13
PE3	11.0	800	1600	1600	40	40
PE4	13.0	1900	2400	2400	73	73
PE5	16.0	4000	4600	4600	206	206

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

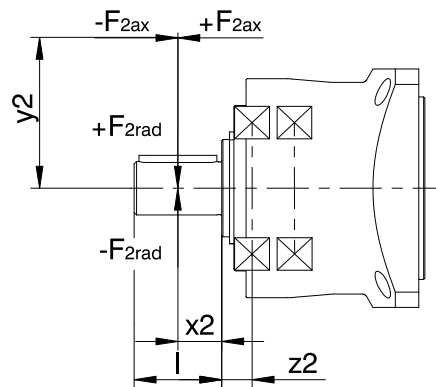


Fig. 1: Force application points

The specified values for $F_{2rad100}$ and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

6.6.3 Radial shaft seal rings

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

6.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

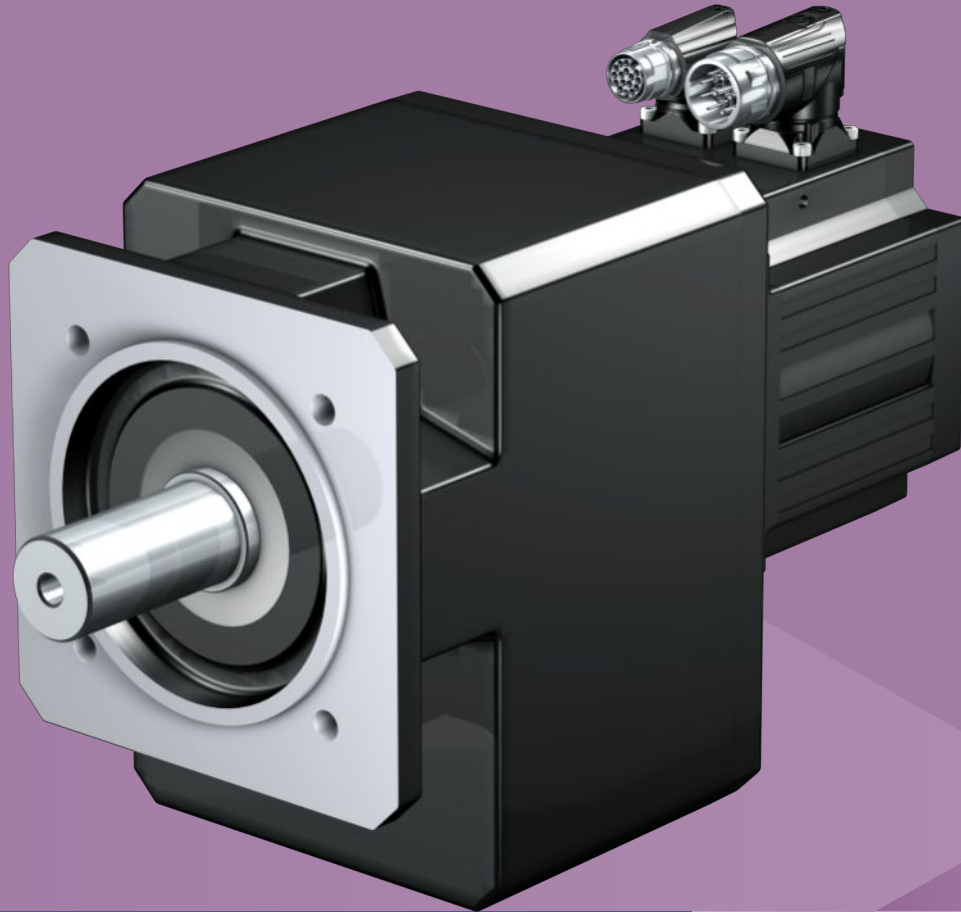
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual for PE22 – PE52 planetary gearboxes and planetary geared motors	443252_en
Operating manual for EZ synchronous servo motors	443032_en

7 C helical geared motors

Table of contents

7.1	Overview	128
7.2	Selection tables	129
7.3	Dimensional drawings	163
7.3.1	Solid shaft design with feather key, N housing design (foot)	164
7.3.2	Solid shaft design with feather key, G housing design (pitch circle diameter)	166
7.3.3	Solid shaft design with feather key, F housing design (round flange)	168
7.3.4	Solid shaft design with feather key, Q housing design (square flange)	170
7.3.5	Oil expansion tank	172
7.4	Type designation	173
7.5	Product description	173
7.5.1	Input options	173
7.5.2	Housing design	174
7.5.3	Shaft design	174
7.5.4	Installation conditions	174
7.5.5	Mounting positions	175
7.5.6	Lubricants	175
7.5.7	Position of the plug connectors	176
7.5.8	Other product features	176
7.5.9	Maintenance	176
7.5.10	Direction of rotation	177
7.6	Project configuration	177
7.6.1	Drive selection	178
7.6.2	Permitted shaft loads for the output shaft	182
7.6.3	Radial shaft seal rings	183
7.6.4	Oil expansion tank	183
7.7	Additional documentation	183



7 Helical geared motors

C

7.1 Overview

Compact helical geared motors

Features

- Power density ★☆☆☆☆
- Backlash ★★☆☆☆
- Price category €
- Shaft load ★★☆☆☆
- Smooth operation ★★☆☆☆
- Torsional stiffness ★★☆☆☆
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free (C0 – C5) ✓
- FKM seal ring at the input ✓
- Reinforced output bearing ✓ (on request)
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	2 – 270
M_{2acc}	9.7 – 6500 Nm
$\Delta\phi_2$	10 – 20 arcmin
η_{get}	96 – 97 %

7.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)
- Weight specification for mounting position EL1, housing design N

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n ₂	M ₂	M _{2,0}	a _{th}	S	Type	M _{2acc}	M _{2NOT}	i	i _{exakt}	n _{1maxDB}		n _{1maxZB}	J ₁	Δφ ₂	C ₂	m
										EL1,2,3,4	EL5,6					
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]			[rpm]	[rpm]	[rpm]	[kgcm ²]	[arcmin]	[Nm/arcmin]	[kg]
C0 (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 72 Nm)																
48	56	57	2.1	1.1	C002_0620 EZ301U	72	120	62.35	1247/20	4000	4000	7000	0.20	16.0	1.6	7.5
54	50	52	2.0	1.2	C002_0560 EZ301U	65	120	55.97	2015/36	4000	4000	7000	0.21	16.0	1.6	7.5
60	45	46	1.9	1.3	C002_0500 EZ301U	72	120	49.94	899/18	4000	4000	7000	0.21	16.0	1.6	7.5
64	42	43	1.9	1.4	C002_0470 EZ301U	65	120	46.82	7865/168	4000	4000	7000	0.21	16.0	1.6	7.5
72	38	38	1.7	1.6	C002_0420 EZ301U	72	120	41.77	3509/84	4000	4000	7000	0.21	16.0	1.6	7.5
86	32	32	1.6	1.9	C002_0350 EZ301U	65	120	35.03	1261/36	4000	4000	7000	0.23	16.0	1.6	7.5
86	54	57	2.7	1.1	C002_0350 EZ302U	65	120	35.03	1261/36	4000	4000	7000	0.33	16.0	1.6	8.1
96	28	29	1.5	2.1	C002_0310 EZ301U	72	120	31.26	2813/90	4000	4000	7000	0.23	16.0	1.6	7.5
96	48	51	2.6	1.2	C002_0310 EZ302U	72	120	31.26	2813/90	4000	4000	7000	0.33	16.0	1.6	8.1
107	25	26	1.4	2.4	C002_0280 EZ301U	65	120	27.99	2015/72	4000	4000	7000	0.25	16.0	1.6	7.5
107	43	46	2.4	1.4	C002_0280 EZ302U	65	120	27.99	2015/72	4000	4000	7000	0.35	16.0	1.6	8.1
107	56	59	3.2	1.1	C002_0280 EZ303U	65	120	27.99	2015/72	4000	4000	7000	0.46	16.0	1.6	8.6
120	23	23	1.4	2.7	C002_0250 EZ301U	68	120	24.97	899/36	4000	4000	7000	0.25	16.0	1.6	7.5
120	39	41	2.3	1.6	C002_0250 EZ302U	72	120	24.97	899/36	4000	4000	7000	0.35	16.0	1.6	8.1
120	50	53	3.0	1.2	C002_0250 EZ303U	72	120	24.97	899/36	4000	4000	7000	0.46	16.0	1.6	8.6
129	21	21	1.3	2.9	C002_0230 EZ301U	63	120	23.21	325/14	4000	4000	7000	0.27	16.0	1.6	7.5
129	36	38	2.2	1.7	C002_0230 EZ302U	65	120	23.21	325/14	4000	4000	7000	0.37	16.0	1.6	8.1
129	47	49	2.9	1.3	C002_0230 EZ303U	65	120	23.21	325/14	4000	4000	7000	0.48	16.0	1.6	8.6
145	19	19	1.2	3.2	C002_0210 EZ301U	56	120	20.71	145/7	4000	4000	7000	0.27	16.0	1.6	7.5
145	32	34	2.1	1.9	C002_0210 EZ302U	72	120	20.71	145/7	4000	4000	7000	0.37	16.0	1.6	8.1
145	42	44	2.7	1.4	C002_0210 EZ303U	72	120	20.71	145/7	4000	4000	7000	0.48	16.0	1.6	8.6
145	56	60	3.7	1.1	C002_0210 EZ401U	72	120	20.71	145/7	4000	4000	7000	1.0	16.0	1.6	10
171	16	16	1.1	3.8	C002_0175 EZ301U	48	120	17.53	3575/204	4000	4000	6500	0.31	16.0	1.6	7.5
171	27	29	1.9	2.2	C002_0175 EZ302U	65	120	17.53	3575/204	4000	4000	6500	0.41	16.0	1.6	8.1
171	35	37	2.5	1.7	C002_0175 EZ303U	65	120	17.53	3575/204	4000	4000	6500	0.52	16.0	1.6	8.6
171	48	51	3.4	1.3	C002_0175 EZ401U	65	120	17.53	3575/204	4000	4000	6500	1.0	16.0	1.6	10
192	14	14	1.1	4.3	C002_0155 EZ301U	42	114	15.64	1595/102	4000	4000	6500	0.31	16.0	1.6	7.5
192	24	25	1.8	2.5	C002_0155 EZ302U	72	114	15.64	1595/102	4000	4000	6500	0.41	16.0	1.6	8.1
192	31	33	2.4	1.9	C002_0155 EZ303U	72	114	15.64	1595/102	4000	4000	6500	0.52	16.0	1.6	8.6
192	42	46	3.2	1.4	C002_0155 EZ401U	72	120	15.64	1595/102	4000	4000	6500	1.0	16.0	1.6	10
213	13	13	1.0	4.7	C002_0140 EZ301U	38	102	14.08	169/12	4000	4000	6500	0.35	16.0	1.6	7.5
213	22	23	1.7	2.8	C002_0140 EZ302U	65	102	14.08	169/12	4000	4000	6500	0.45	16.0	1.6	8.1
213	28	30	2.3	2.1	C002_0140 EZ303U	65	102	14.08	169/12	4000	4000	6500	0.56	16.0	1.6	8.6
213	38	41	3.1	1.6	C002_0140 EZ401U	65	120	14.08	169/12	4000	4000	6500	1.1	16.0	1.6	10
213	59	64	4.7	1.0	C002_0140 EZ501U	65	120	14.08	169/12	4000	4000	6500	3.1	16.0	1.6	11
239	19	20	1.6	3.1	C002_0125 EZ302U	61	91	12.57	377/30	4000	4000	6500	0.45	16.0	1.6	8.1
239	25	27	2.1	2.4	C002_0125 EZ303U	72	91	12.57	377/30	4000	4000	6500	0.56	16.0	1.6	8.6
239	34	37	2.9	1.8	C002_0125 EZ401U	72	120	12.57	377/30	4000	4000	6500	1.1	16.0	1.6	10
239	52	57	4.4	1.1	C002_0125 EZ501U	72	120	12.57	377/30	4000	4000	6500	3.1	16.0	1.6	11
239	57	63	4.9	1.0	C002_0125 EZ402U	72	120	12.57	377/30	4000	4000	6500	1.8	16.0	1.6	11
260	18	19	1.6	3.3	C002_0115 EZ302U	56	84	11.54	3185/276	3700	3600	6000	0.49	16.0	1.6	8.1
260	23	25	2.1	2.5	C002_0115 EZ303U	65	84	11.54	3185/276	3700	3600	6000	0.60	16.0	1.6	8.6
260	31	34	2.9	1.9	C002_0115 EZ401U	65	120	11.54	3185/276	3700	3600	6000	1.1	16.0	1.6	10
260	48	53	4.4	1.2	C002_0115 EZ501U	65	120	11.54	3185/276	3700	3600	6000	3.1	16.0	1.6	11
260	53	58	4.8	1.1	C002_0115 EZ402U	65	120	11.54	3185/276	3700	3600	6000	1.8	16.0	1.6	11
291	16	17	1.6	3.5	C002_0105 EZ302U	50	75	10.30	1421/138	3700	3600	6000	0.49	16.0	1.6	8.1
291	21	22	2.1	2.7	C002_0105 EZ303U	60	75	10.30	1421/138	3700	3600	6000	0.60	16.0	1.6	8.6
291	28	30	2.8	2.0	C002_0105 EZ401U	72	120	10.30	1421/138	3700	3600	6000	1.1	16.0	1.6	10
291	43	47	4.3	1.3	C002_0105 EZ501U	72	120	10.30	1421/138	3700	3600	6000	3.1	16.0	1.6	11
291	47	52	4.7	1.2	C002_0105 EZ402U	72	120	10.30	1421/138	3700	3600	6000	1.8	16.0	1.6	11
325	14	15	1.6	3.8	C002_0092 EZ302U	45	67	9.228	1495/162	3700	3600	6000	0.56	16.0	1.6	8.1

7.2 Selection tables 7 C helical geared motors

n ₂	M ₂	M _{2,0}	a _{th}	S	Type	M _{2acc}	M _{2NOT}	i	i _{exakt}	n _{1maxDB}		n _{1maxZB}	J ₁	Δφ ₂	C ₂	m
										EL1,2,3,4	EL5,6					
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]			[rpm]	[rpm]	[rpm]	[kgcm ²]	[arcmin]	[Nm/arcmin]	[kg]
C8 (n_{1N} = 4000 min⁻¹, M_{2acc,max} = 4800 Nm)																
40	2421	4199	2.5	1.4	C813_1010 EZ813U	4800	7453	100.5	28143/280	2900	2700	4300	107	10.0	204	200
40	2509	6451	2.6	1.3	C813_1010 EZ815U	4800	7453	100.5	28143/280	2900	2700	4300	170	10.0	204	213
45	2155	3737	2.2	1.7	C813_0890 EZ813U	4140	7200	89.44	14400/161	2900	2700	4300	108	10.0	204	200
45	2233	5741	2.2	1.6	C813_0890 EZ815U	4140	7200	89.44	14400/161	2900	2700	4300	171	10.0	204	213
51	1882	3264	2.3	1.7	C813_0780 EZ813U	4800	6759	78.13	54693/700	2900	2700	4300	108	10.0	204	200
51	1950	5015	2.4	1.6	C813_0780 EZ815U	4800	6759	78.13	54693/700	2900	2700	4300	171	10.0	204	213
58	1684	2920	1.9	2.1	C812_0690 EZ813U	4140	6652	68.89	620/9	2900	2700	4300	110	10.0	204	188
58	1745	4486	2.0	2.1	C812_0690 EZ815U	4140	6652	68.89	620/9	2900	2700	4300	173	10.0	204	200
61	1589	2756	2.2	1.9	C813_0660 EZ813U	4800	6222	65.96	10620/161	2900	2700	4300	108	10.0	204	200
61	1647	4234	2.3	1.8	C813_0660 EZ815U	4800	6222	65.96	10620/161	2900	2700	4300	171	10.0	204	213
74	1324	2296	1.7	2.7	C812_0540 EZ813U	4140	6248	54.15	704/13	2900	2700	4300	113	10.0	204	188
74	1372	3527	1.8	2.6	C812_0540 EZ815U	4140	6248	54.15	704/13	2900	2700	4300	176	10.0	204	200
81	1185	2054	2.1	2.3	C813_0490 EZ813U	3710	4638	49.18	49914/1015	2900	2700	4300	110	10.0	204	200
81	1227	3156	2.1	2.3	C813_0490 EZ815U	3710	4638	49.18	49914/1015	2900	2700	4300	173	10.0	204	213
88	1113	1930	1.6	3.2	C812_0460 EZ813U	4140	7200	45.54	592/13	2900	2700	4300	116	10.0	204	188
88	1153	2966	1.6	3.1	C812_0460 EZ815U	4140	7200	45.54	592/13	2900	2700	4300	179	10.0	204	200
100	976	1693	1.4	3.8	C812_0400 EZ813U	3686	4608	39.94	2596/65	2900	2700	4300	113	10.0	145	188
100	1011	2601	1.5	3.6	C812_0400 EZ815U	3686	4608	39.94	2596/65	2900	2700	4300	176	10.0	145	200
113	864	1498	1.4	4.2	C812_0350 EZ813U	4140	7200	35.33	106/3	2900	2700	4300	122	10.0	204	188
113	895	2301	1.4	4.0	C812_0350 EZ815U	4140	7200	35.33	106/3	2900	2700	4300	185	10.0	204	200
119	821	1424	1.3	4.4	C812_0340 EZ813U	4561	8400	33.59	2183/65	2900	2700	4300	117	10.0	145	188
119	851	2187	1.4	4.2	C812_0340 EZ815U	4800	8400	33.59	2183/65	2900	2700	4300	180	10.0	145	200
146	696	1789	1.3	4.8	C812_0270 EZ815U	4140	7200	27.47	412/15	2900	2700	4300	193	10.0	204	200
C9 (n_{1N} = 2000 min⁻¹, M_{2acc,max} = 6500 Nm)																
18	4116	4617	2.4	1.5	C913_1100 EZ813U	6500	9997	110.4	21645/196	2800	2600	4000	110	10.0	393	307
26	2897	3249	2.6	1.6	C913_0780 EZ813U	5630	7037	77.73	60939/784	2800	2600	4000	110	10.0	393	307
26	4291	5109	3.9	1.1	C913_0780 EZ815U	5630	7037	77.73	60939/784	2800	2600	4000	173	10.0	393	320
C9 (n_{1N} = 4000 min⁻¹, M_{2acc,max} = 6500 Nm)																
19	5188	8997	2.2	1.1	C913_2150 EZ813U	6500	12000	215.4	3015/14	2800	2600	4000	108	10.0	393	307
19	5376	13823	2.3	1.1	C913_2150 EZ815U	6500	12000	215.4	3015/14	2800	2600	4000	171	10.0	393	320
23	4242	7357	2.0	1.3	C913_1760 EZ813U	6500	12000	176.1	34515/196	2800	2600	4000	108	10.0	393	307
23	4396	11303	2.1	1.3	C913_1760 EZ815U	6500	12000	176.1	34515/196	2800	2600	4000	171	10.0	393	320
36	2660	4614	1.8	1.9	C913_1100 EZ813U	6500	9997	110.4	21645/196	2800	2600	4000	110	10.0	393	307
36	2757	7088	1.8	1.9	C913_1100 EZ815U	6500	9997	110.4	21645/196	2800	2600	4000	173	10.0	393	320
51	1873	3247	2.1	1.9	C913_0780 EZ813U	5630	7037	77.73	60939/784	2800	2600	4000	110	10.0	393	307
51	1940	4989	2.2	1.9	C913_0780 EZ815U	5630	7037	77.73	60939/784	2800	2600	4000	173	10.0	393	320

7.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

Tolerances

Axis height in accordance with DIN 747	Tolerance
Up to 50 mm	-0.4 mm
Up to 250 mm	-0.5 mm
Up to 630 mm	-0.6 mm

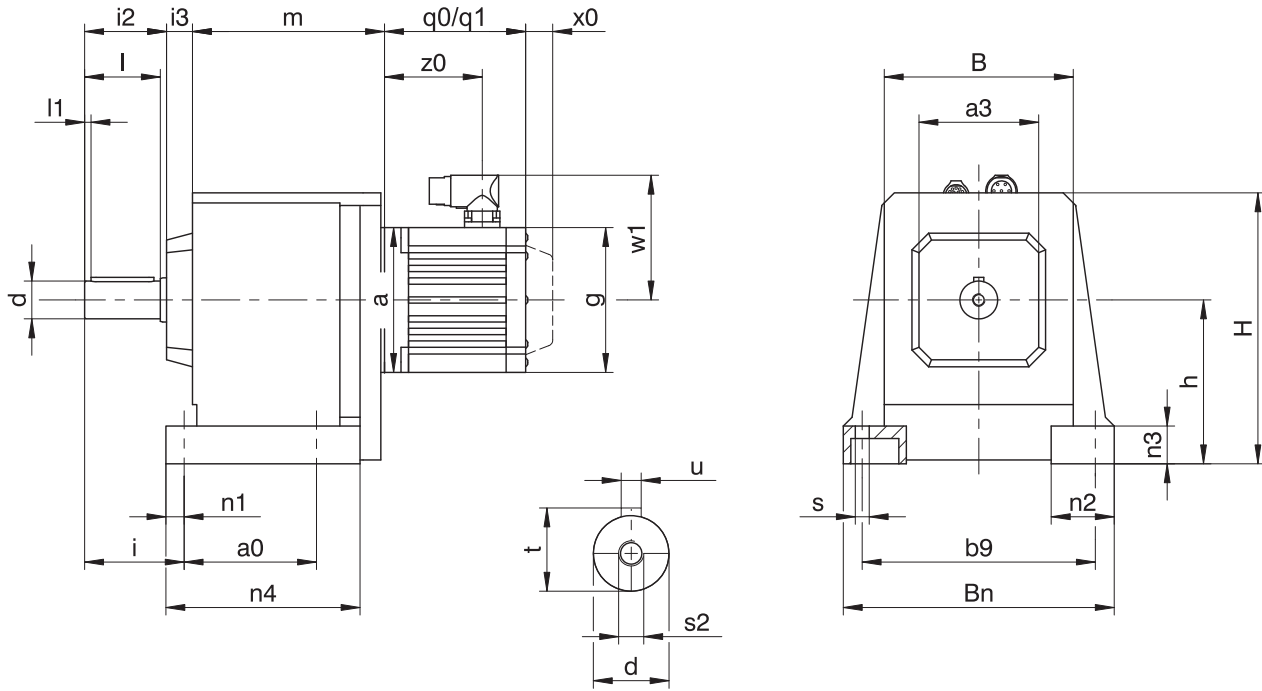
Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6
Feather keys	DIN 6885-1, high form A

Flange	Pilot tolerance
Up to 300 mm	ISO j6
Starting at 350 mm	ISO h6

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

7.3.1 Solid shaft design with feather key, N housing design (foot)



q_0 Applies to motors without brake.

q_1 Applies to motors with brake.

x_0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
 EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

C203, C303, C612, C613: Motor and gearbox are sometimes non-coaxial.

Options: C0 – C5 also available with solid shaft without feather key; on request starting at C6.

Dimensions of gearboxes

Type	a0	a3	b9	B	Bn	Ød	h	H	i	i2	i3	l	l1	n1	n2	n3	n4	Øs	s2	t	u
C0	62	60	110	92	132	20 _{k6}	82	144	55	44	13	40	3	11	35	20	95.0	7	M6	22.5	A6×6×32
C1	70	80	150	124	176	25 _{k6}	102	177	67	54	15	50	5	13	42	25	117.5	9	M10	28.0	A8×7×40
C2	85	95	170	138	200	30 _{k6}	115	195	79	65	21	60	5	14	50	30	134.5	11	M10	33.0	A8×7×50
C3	105	95	185	150	215	30 _{k6}	130	215	79	65	20	60	5	14	50	30	153.5	11	M10	33.0	A8×7×50
C4	110	110	220	175	255	40 _{k6}	145	245	105	86	20	80	5	19	60	35	180.0	14	M16	43.0	A12×8×70
C5	130	130	245	192	290	40 _{k6}	170	290	108	86	21	80	5	22	70	40	197.0	18	M16	43.0	A12×8×70
C6	215	177	245	225	300	50 _{k6}	200	315	130	106	47	100	5	25	75	40	265.0	18	M16	53.5	A14×9×90
C7	235	192	300	265	365	60 _{m6}	235	375	163	127	58	120	5	25	90	50	285.0	18	M20	64.0	A18×11×100
C8	300	223	340	310	435	70 _{m6}	290	450	190	148	70	140	5	29	95	55	360.0	22	M20	74.5	A20×12×125
C9	340	277	400	365	510	90 _{m6}	340	530	222	178	78	170	5	34	110	60	410.0	26	M24	95.0	A25×14×140

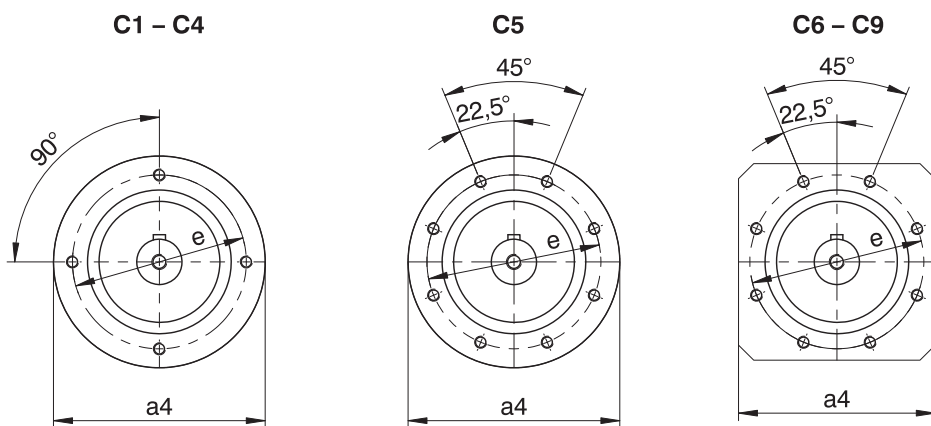
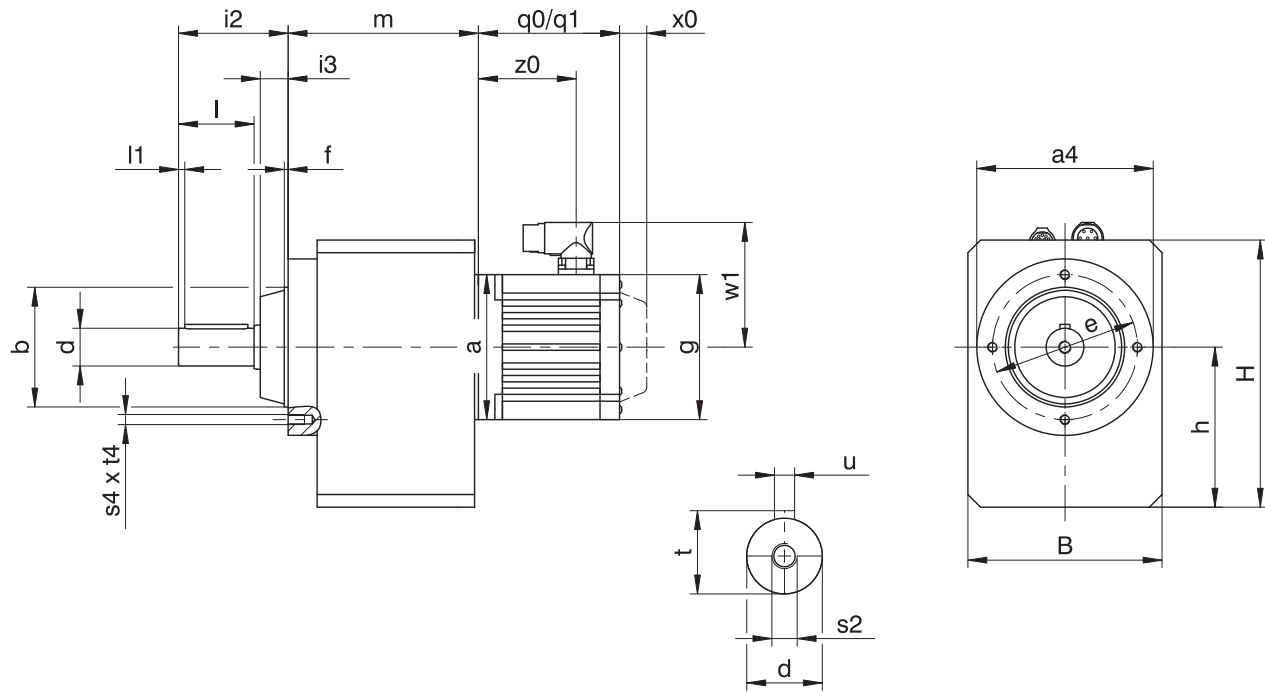
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	a	m	a	m	a	m	a	m	a	m	a	m
C002	□55	97.5	□72	97.5	□98	97.5	□115	101.5	□145	103.5	-	-
C102	-	-	□72	118.0	□98	118.0	□115	122.0	□145	124.0	-	-
C103	-	-	∅140	155.0	-	-	-	-	-	-	-	-
C202	-	-	∅140	129.0	∅140	129.0	□115	133.0	□145	135.0	-	-
C203	-	-	∅140	166.0	∅140	166.0	-	-	-	-	-	-
C302	-	-	-	-	-	-	∅160	152.5	□145	154.5	□190	157.5
C303	-	-	∅140	185.5	∅140	185.5	∅160	195.5	-	-	-	-
C402	-	-	-	-	-	-	∅160	180.0	□145	182.0	□190	185.0
C403	-	-	-	-	-	-	∅160	223.0	-	-	-	-
C502	-	-	-	-	-	-	∅160	200.0	∅200	202.0	□190	205.0
C503	-	-	-	-	-	-	∅160	243.0	-	-	-	-
C612	-	-	-	-	-	-	-	-	∅200	180.0	□190	183.0
C613	-	-	-	-	-	-	∅160	222.0	∅200	242.0	-	-
C712	-	-	-	-	-	-	-	-	∅200	201.0	∅250	203.0
C713	-	-	-	-	-	-	-	-	∅200	262.0	∅250	274.0
C812	-	-	-	-	-	-	-	-	-	-	∅250	237.0
C813	-	-	-	-	-	-	-	-	∅200	296.0	∅250	308.0
C913	-	-	-	-	-	-	-	-	-	-	∅250	337.0

7.3.2 Solid shaft design with feather key, G housing design (pitch circle diameter)



- q_0 Applies to motors without brake.
- q_1 Applies to motors with brake.
- x_0 EZ2: Applies only to motors with brake and encoders using w_1 an optical or inductive measuring method
- EZ3 - EZ8: Applies to encoders using an optical measuring method

C203, C303, C612, C613: Motor and gearbox are sometimes non-coaxial.

Options: C0 - C5 also available with solid shaft without feather key; on request starting at C6.

Dimensions of gearboxes

Type	a_4	$\varnothing b$	B	$\varnothing d$	$\varnothing e$	f	h	H	i_2	i_3	l	l_1	s_2	s_4	t	t_4	u
C0	$\varnothing 87$	55_{j_6}	97	20_{k_6}	75	3.0	79.0	141.0	58	14	40	3	M6	M6	22.5	10	A6×6×32
C1	$\varnothing 120$	80_{j_6}	130	25_{k_6}	100	3.0	100.0	175.0	71	17	50	5	M10	M6	28.0	13	A8×7×40
C2	$\varnothing 140$	95_{j_6}	142	30_{k_6}	115	3.0	112.0	192.0	87	22	60	5	M10	M8	33.0	13	A8×7×50
C3	$\varnothing 140$	95_{j_6}	154	30_{k_6}	115	3.0	127.0	212.0	87	22	60	5	M10	M8	33.0	13	A8×7×50
C4	$\varnothing 160$	110_{j_6}	178	40_{k_6}	130	3.5	142.5	242.5	108	22	80	5	M16	M10	43.0	16	A12×8×70
C5	$\varnothing 192$	130_{j_6}	195	40_{k_6}	165	3.5	166.0	286.0	109	23	80	5	M16	M10	43.0	16	A12×8×70
C6	$\square 180$	140_{j_6}	225	50_{k_6}	165	5.0	195.0	310.0	136	30	100	5	M16	M10	53.5	16	A14×9×90
C7	$\square 195$	155_{j_6}	265	60_{m_6}	185	8.0	231.0	371.0	164	37	120	5	M20	M12	64.0	19	A18×11×100
C8	$\square 226$	185_{j_6}	310	70_{m_6}	215	5.0	285.0	445.0	185	37	140	5	M20	M12	74.5	19	A20×12×125
C9	$\square 280$	230_{j_6}	365	90_{m_6}	265	5.0	334.0	524.0	220	42	170	5	M24	M16	95.0	26	A25×14×140

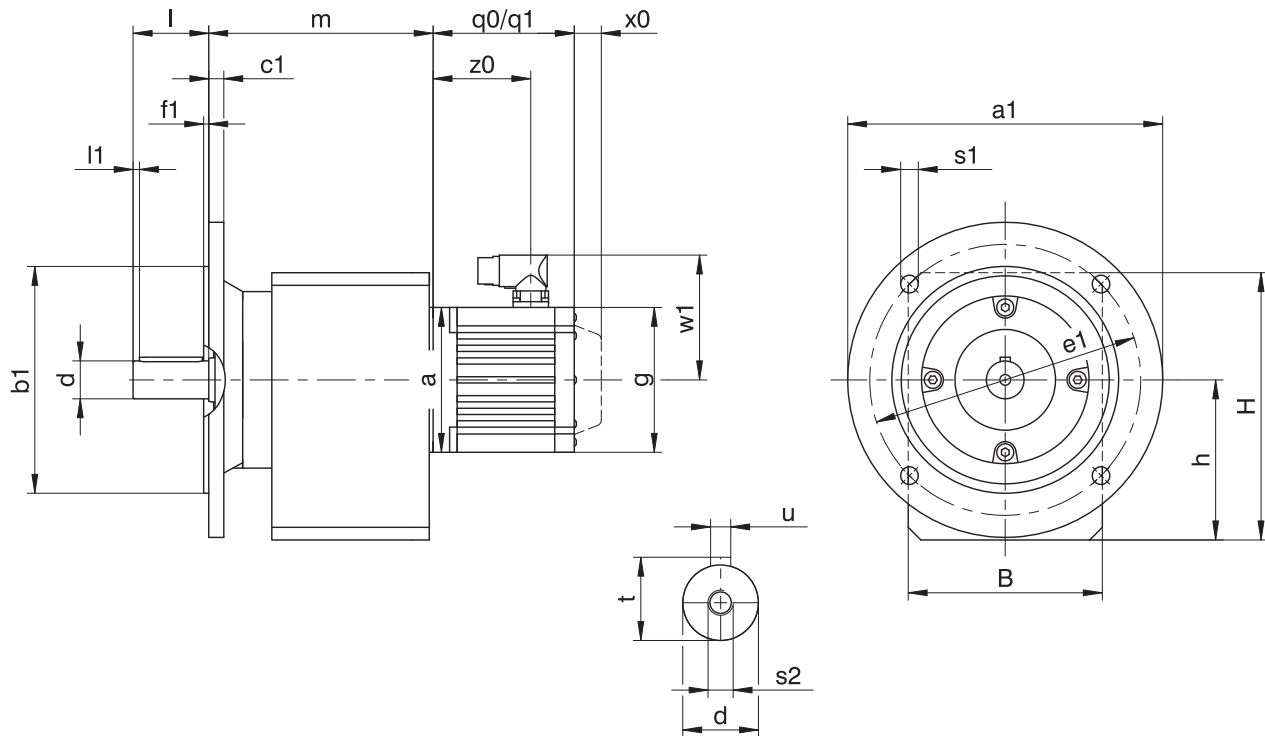
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	a	m	a	m	a	m	a	m	a	m	a	m
C002	□55	96	□72	96	□98	96	□115	100	□145	102	-	-
C102	-	-	□72	116	□98	116	□115	120	□145	122	-	-
C103	-	-	∅140	153	-	-	-	-	-	-	-	-
C202	-	-	∅140	128	∅140	128	□115	132	□145	134	-	-
C203	-	-	∅140	165	∅140	165	-	-	-	-	-	-
C302	-	-	-	-	-	-	∅160	151	□145	153	□190	156
C303	-	-	∅140	184	∅140	184	∅160	194	-	-	-	-
C402	-	-	-	-	-	-	∅160	178	□145	180	□190	183
C403	-	-	-	-	-	-	∅160	221	-	-	-	-
C502	-	-	-	-	-	-	∅160	198	∅200	200	□190	203
C503	-	-	-	-	-	-	∅160	241	-	-	-	-
C612	-	-	-	-	-	-	-	-	∅200	197	□190	200
C613	-	-	-	-	-	-	∅160	239	∅200	259	-	-
C712	-	-	-	-	-	-	-	-	∅200	222	∅250	224
C713	-	-	-	-	-	-	-	-	∅200	283	∅250	295
C812	-	-	-	-	-	-	-	-	-	-	∅250	270
C813	-	-	-	-	-	-	-	-	∅200	329	∅250	341
C913	-	-	-	-	-	-	-	-	-	-	∅250	373

7.3.3 Solid shaft design with feather key, F housing design (round flange)



- q_0 Applies to motors without brake.
- q_1 Applies to motors with brake.
- x_0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
- EZ3 – EZ8: Applies to encoders using an optical measuring method

C203, C303, C612, C613: Motor and gearbox are sometimes non-coaxial.

Options: C0 – C5 also available with solid shaft without feather key; on request starting at C6.

Dimensions of gearboxes

Type	$\varnothing a_1$	$\varnothing b_1$	B	c_1	$\varnothing d$	$\varnothing e_1$	f_1	h	H	l	l1	$\varnothing s_1$	s2	t	u
C0	160	110 _{f6}	97	10	20 _{k6}	130	3.0	79.0	141.0	40	3	9	M6	22.5	A6×6×32
C1	200	130 _{f6}	130	12	25 _{k6}	165	3.5	100.0	175.0	50	5	11	M10	28.0	A8×7×40
C2	200	130 _{f6}	142	12	30 _{k6}	165	3.5	112.0	192.0	60	5	11	M10	33.0	A8×7×50
C3	250	180 _{f6}	154	12	30 _{k6}	215	4.0	127.0	212.0	60	5	14	M10	33.0	A8×7×50
C4	250	180 _{f6}	178	14	40 _{k6}	215	4.0	142.5	242.5	80	5	14	M16	43.0	A12×8×70
C5	300	230 _{f6}	195	16	40 _{k6}	265	4.0	166.0	286.0	80	5	14	M16	43.0	A12×8×70
C6	300	230 _{f6}	225	17	50 _{k6}	265	4.0	195.0	310.0	100	5	14	M16	53.5	A14×9×90
C7	350	250 _{h6}	265	18	60 _{m6}	300	5.0	231.0	371.0	120	5	18	M20	64.0	A18×11×100
C8	400	300 _{h6}	310	20	70 _{m6}	350	5.0	285.0	445.0	140	5	18	M20	74.5	A20×12×125
C9	450	350 _{h6}	365	23	90 _{m6}	400	5.0	334.0	524.0	170	5	18	M24	95.0	A25×14×140

Dimensions of additional round flanges

Type	$\varnothing a_1$	$\varnothing b_1$	c_1	$\varnothing e_1$	f_1	$\varnothing s_1$
C0	120	80 _{f6}	10	100	3.0	7
C0	140	95 _{f6}	10	115	3.0	9
C1	140	95 _{f6}	8	115	3.5	9
C1	160	110 _{f6}	10	130	3.5	9
C2	160	110 _{f6}	10	130	3.5	9
C2	250	180 _{f6}	12	215	4.0	14
C3	160	110 _{f6}	10	130	3.5	9
C3	200	130 _{f6}	12	165	3.5	11
C4	200	130 _{f6}	14	165	3.5	11
C4	300	230 _{f6}	14	265	4.0	14
C5	250	180 _{f6}	14	215	4.0	14
C8	350	250 _{h6}	18	300	5.0	18
C8	450	350 _{h6}	20	400	5.0	18

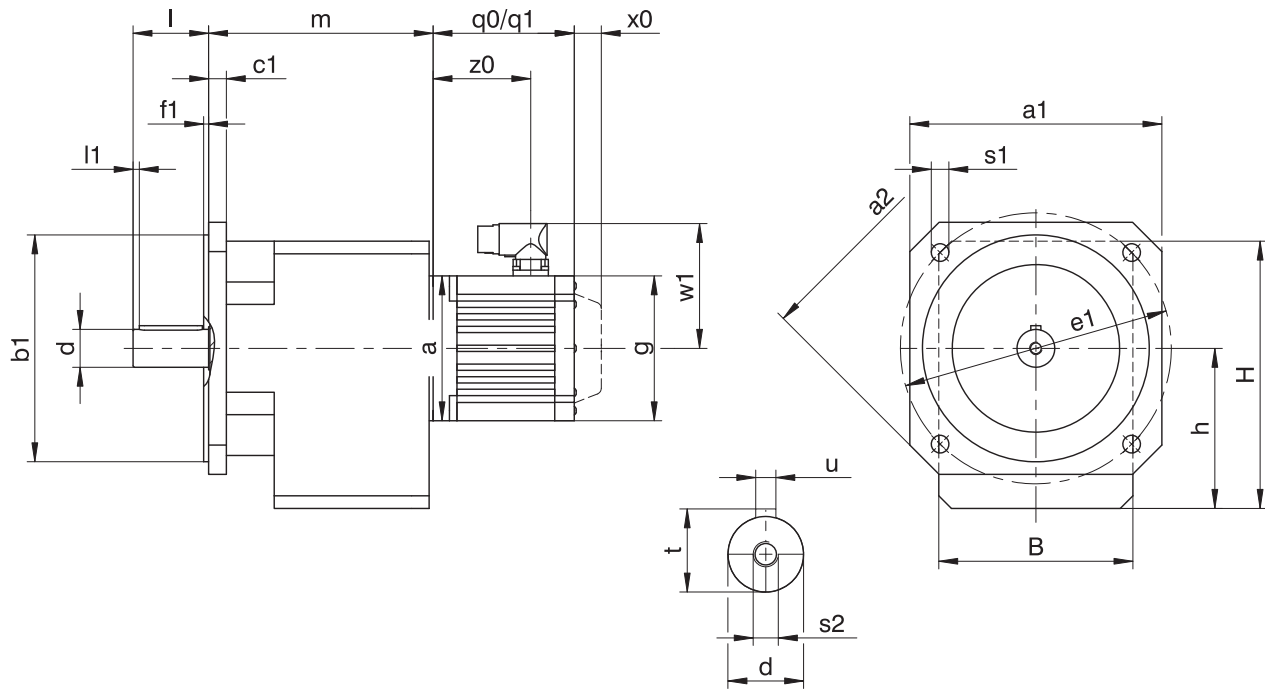
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	a	m	a	m	a	m	a	m	a	m	a	m
C002	□55	114	□72	114	□98	114	□115	118	□145	120	-	-
C102	-	-	□72	137	□98	137	□115	141	□145	143	-	-
C103	-	-	∅140	174	-	-	-	-	-	-	-	-
C202	-	-	∅140	155	∅140	155	□115	159	□145	161	-	-
C203	-	-	∅140	192	∅140	192	-	-	-	-	-	-
C302	-	-	-	-	-	-	∅160	178	□145	180	□190	183
C303	-	-	∅140	211	∅140	211	∅160	221	-	-	-	-
C402	-	-	-	-	-	-	∅160	206	□145	208	□190	211
C403	-	-	-	-	-	-	∅160	249	-	-	-	-
C502	-	-	-	-	-	-	∅160	227	∅200	229	□190	232
C503	-	-	-	-	-	-	∅160	270	-	-	-	-
C612	-	-	-	-	-	-	-	-	∅200	233	□190	236
C613	-	-	-	-	-	-	∅160	275	∅200	295	-	-
C712	-	-	-	-	-	-	-	-	∅200	266	∅250	268
C713	-	-	-	-	-	-	-	-	∅200	327	∅250	339
C812	-	-	-	-	-	-	-	-	-	-	∅250	315
C813	-	-	-	-	-	-	-	-	∅200	374	∅250	386
C913	-	-	-	-	-	-	-	-	-	-	∅250	423

7.3.4 Solid shaft design with feather key, Q housing design (square flange)



q_0 Applies to motors without brake.

q_1 Applies to motors with brake.

x_0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

w_1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

C203, C303: Motor and gearbox are sometimes non-coaxial.

Options: C0 – C4 also available with solid shaft without feather key.

Dimensions of gearboxes

Type	$\square a_1$	$\square a_2$	$\varnothing b_1$	B	c_1	$\varnothing d$	$\varnothing e_1$	f_1	h	H	l	l_1	$\varnothing s_1$	s2	t	u
C0	124	160	110 _{β}	97	9	20 _{k_6}	130	3.0	79.0	141.0	40	3	9	M6	22.5	A6×6×32
C1	145	192	130 _{β}	130	11	25 _{k_6}	165	3.5	100.0	175.0	50	5	11	M10	28.0	A8×7×40
C2	145	192	130 _{β}	142	11	30 _{k_6}	165	3.5	112.0	192.0	60	5	11	M10	33.0	A8×7×50
C3	200	250	180 _{β}	154	14	30 _{k_6}	215	4.0	127.0	212.0	60	5	14	M10	33.0	A8×7×50
C4	200	250	180 _{β}	178	14	40 _{k_6}	215	4.0	142.5	242.5	80	5	14	M16	43.0	A12×8×70

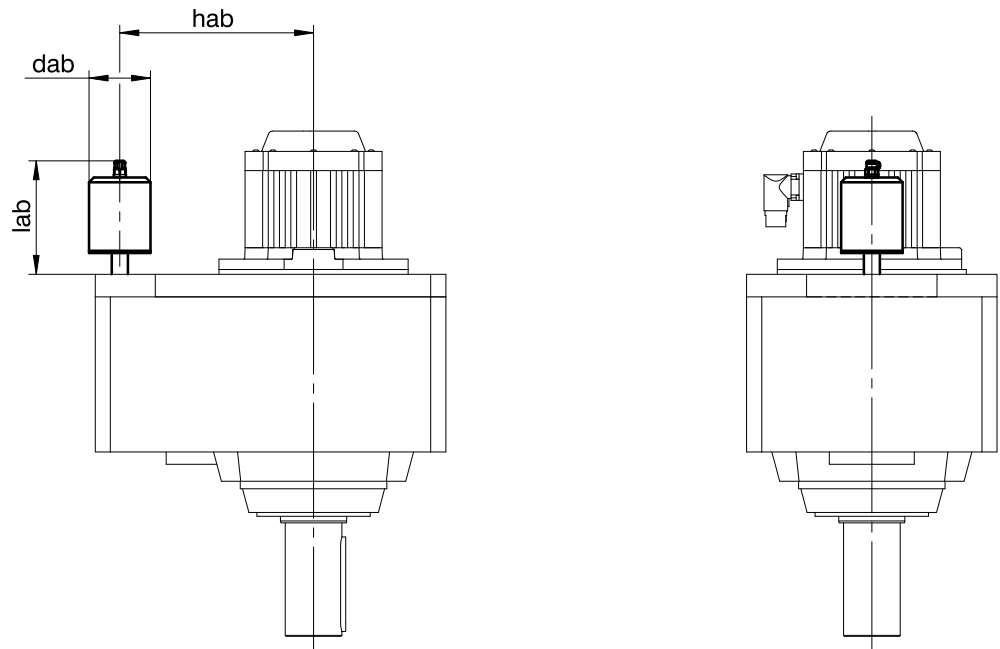
Dimensions of motors

Type	$\square g$	q_0	q_1	w_1	x_0	z_0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2		EZ3		EZ4		EZ5		EZ7		EZ8	
	a	m	a	m	a	m	a	m	a	m	a	m
C002	□55	114	□72	114	□98	114	□115	118	□145	120	-	-
C102	-	-	□72	137	□98	137	□115	141	□145	143	-	-
C103	-	-	∅140	174	-	-	-	-	-	-	-	-
C202	-	-	∅140	155	∅140	155	□115	159	□145	161	-	-
C203	-	-	∅140	192	∅140	192	-	-	-	-	-	-
C302	-	-	-	-	-	-	∅160	178	□145	180	□190	183
C303	-	-	∅140	211	∅140	211	∅160	221	-	-	-	-
C402	-	-	-	-	-	-	∅160	206	□145	208	□190	211
C403	-	-	-	-	-	-	∅160	249	-	-	-	-

7.3.5 Oil expansion tank



Dimensions

Type	EZ7			EZ8		
	dab	hab	lab	dab	hab	lab
C612	65	170	114.5	65	170	112
C712	73	205	129.5	73	205	129.5

More information can be found in Chapter [▶ 7.6.4](#)

7.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

C	2	0	2	N	0280	EZ401U
---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
C	Type	Helical gearbox
2	Size	2 (example)
0	Generation	Generation 0
1		Generation 1
2	Stages	Two-stage
3		Three-stage
G	Housing	Pitch circle diameter
F		Round flange
Q		Square flange
N		Foot
0280	Transmission ratio (i x 10 rounded)	i = 28.24 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Mounting position, see the chapter [▶ 7.5.5](#)
- Position of the plug connectors, see the chapter [▶ 7.5.7](#)
- Oil expansion tank (option, recommended for gearboxes in mounting position EL5), see the chapter [▶ 7.6.4](#)

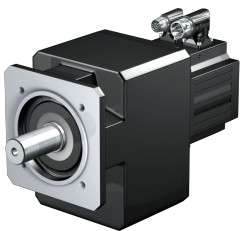
To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

7.5 Product description

7.5.1 Input options

EZ synchronous servo motor



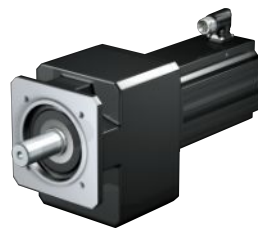
Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

LM Lean motor

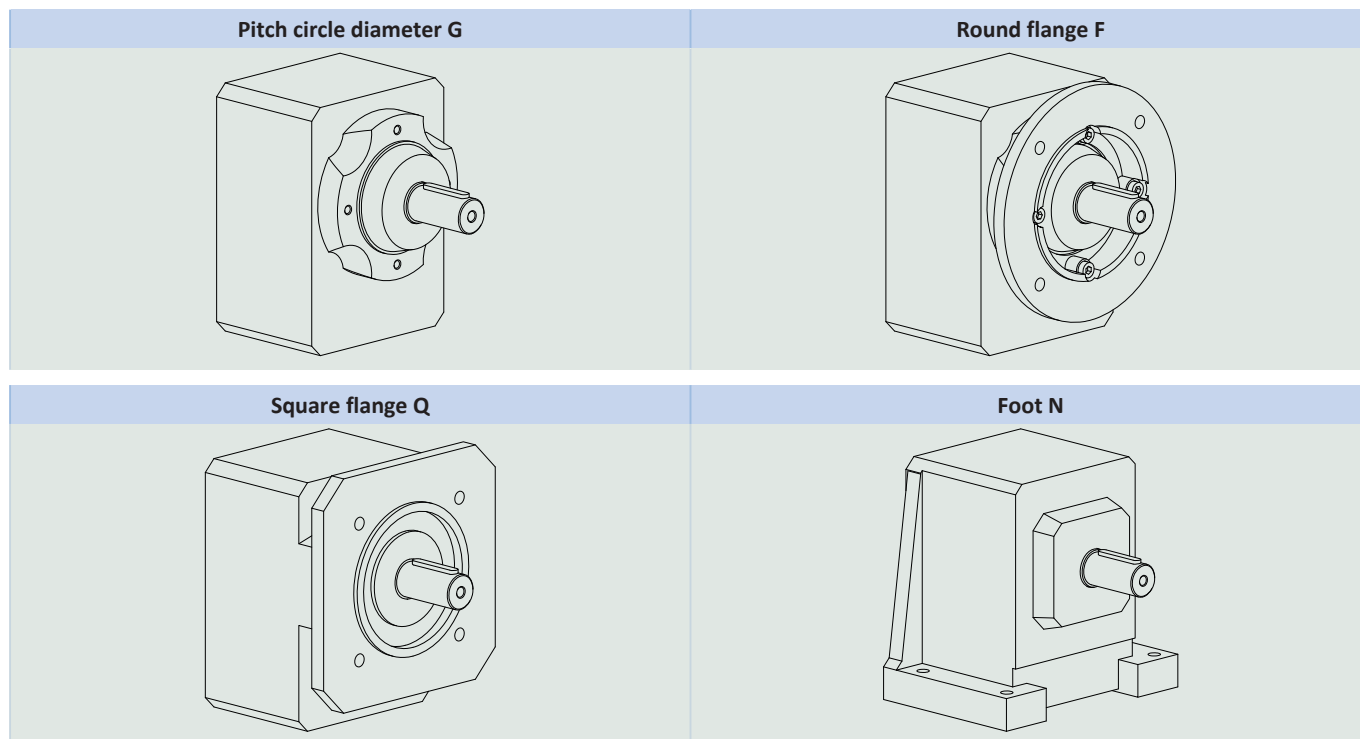


Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

7.5.2 Housing design



	G	F	Q	N
C0	✓	✓	✓	✓
C1	✓	✓	✓	✓
C2	✓	✓	✓	✓
C3	✓	✓	✓	✓
C4	✓	✓	✓	✓
C5	✓	✓	-	✓
C6	✓	✓	-	✓
C7	✓	✓	-	✓
C8	✓	✓	-	✓
C9	✓	✓	-	✓

7.5.3 Shaft design

Gearboxes in sizes C0 – C9 come standard with a solid shaft with feather key.

Gearboxes in sizes C0 – C5 can be ordered with the option of a solid shaft without feather key. Only upon request starting at size C6.

7.5.4 Installation conditions

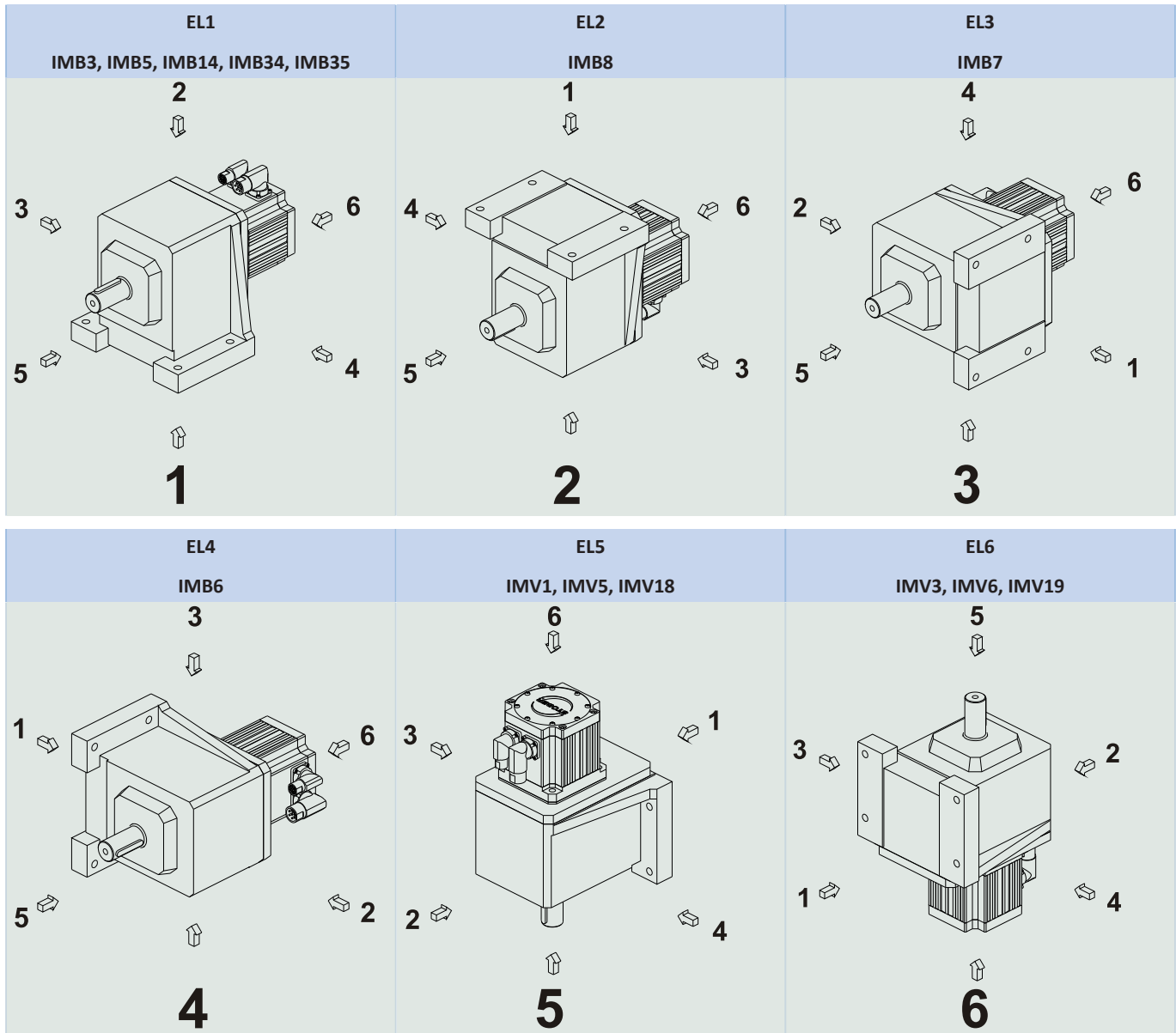
Fastening the gearboxes on the machine side using the pitch circle diameter

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 10.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

7.5.5 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

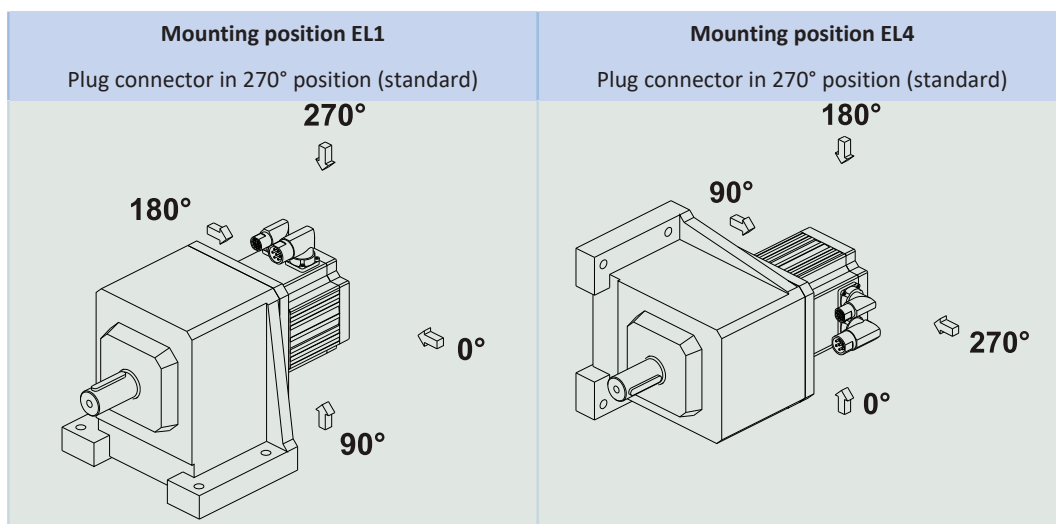
7.5.6 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

7.5.7 Position of the plug connectors



Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

7.5.8 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 80 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	97%
η_{get} three-stage	96%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

7.5.9 Maintenance

The instructions for maintenance can be found in the operating manual, ID 443365_en, at <http://www.stoeber.de/en/downloads/>. Enter the ID of the documentation in the Search... field.

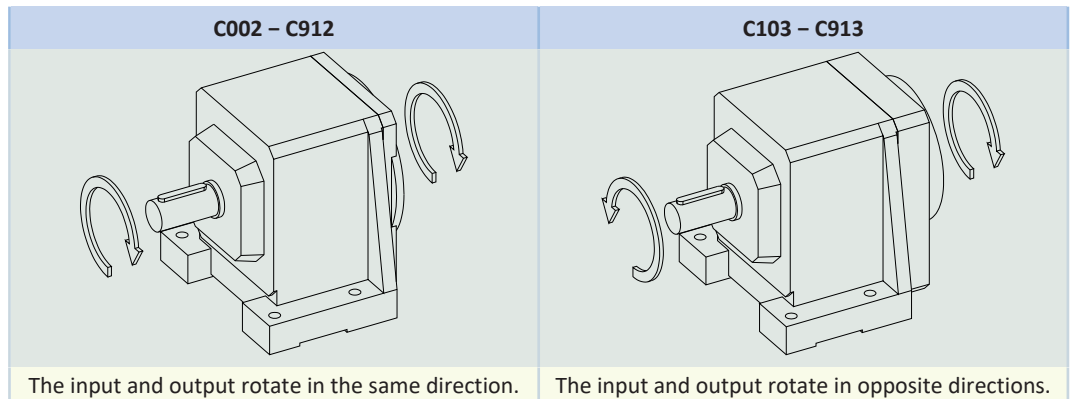
Ventilation

Air release valves are fitted as a standard feature and independently of installation position for gearbox sizes C6 to C9.

For the position and dimensions of the air release valve, refer to the 3D model.

Download the 3D model at <https://configurator.stoeber.de/en-US/>.

7.5.10 Direction of rotation



The pictures show mounting position EL1.

7.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

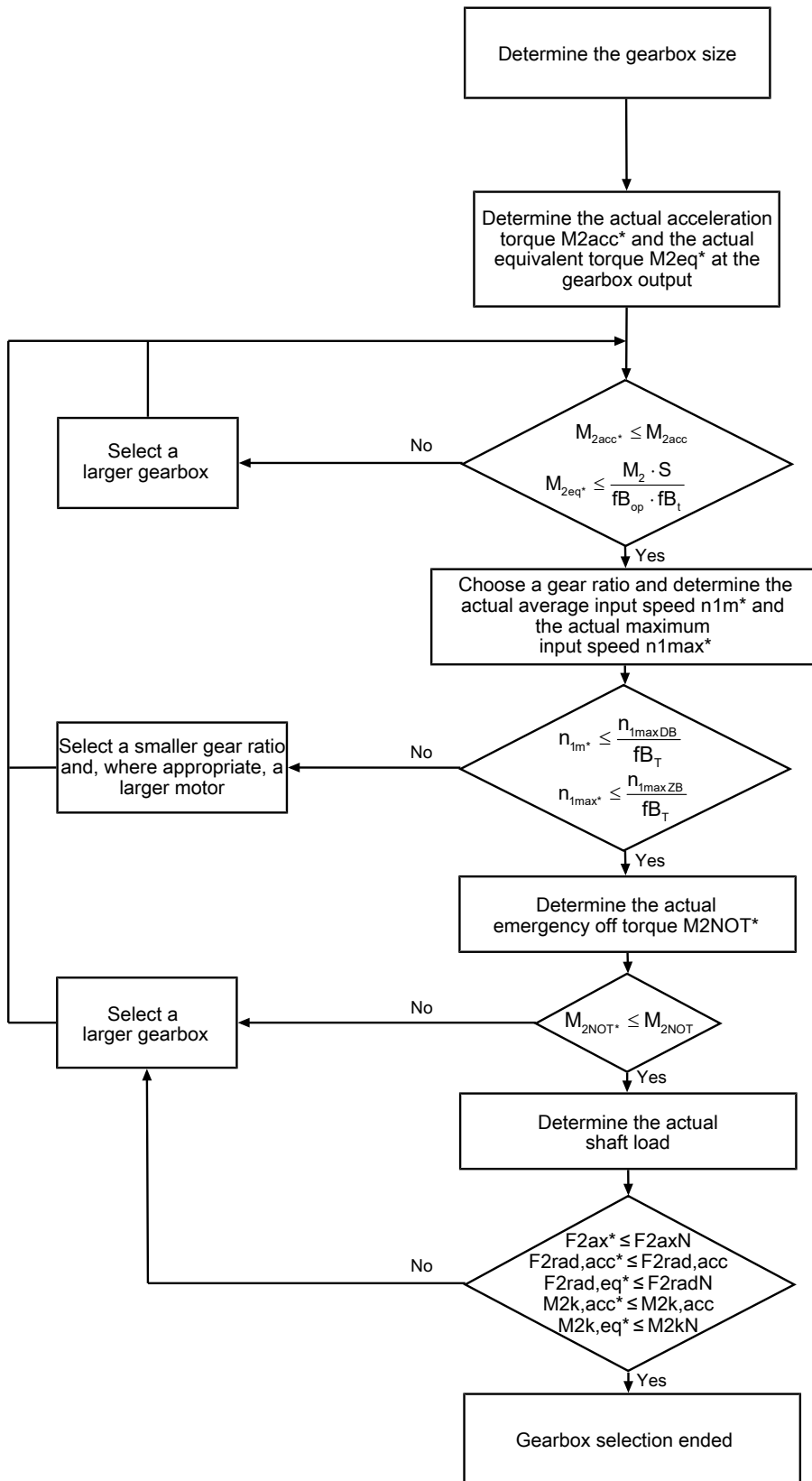
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

7.6.1 Drive selection

Drive selection for gearboxes

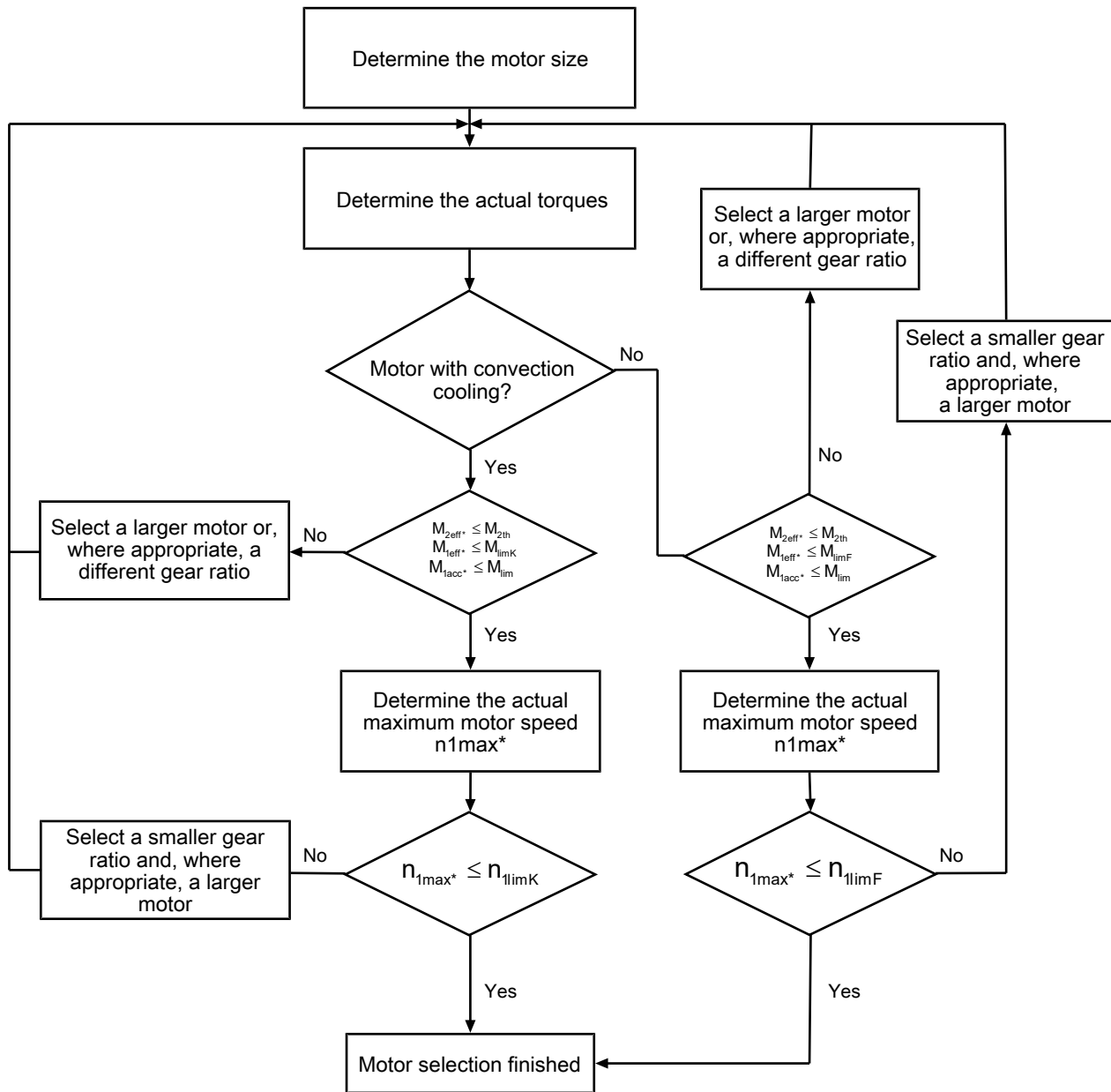


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for fb_T , fb_{op} and fb_t can be found in the corresponding tables in this chapter.

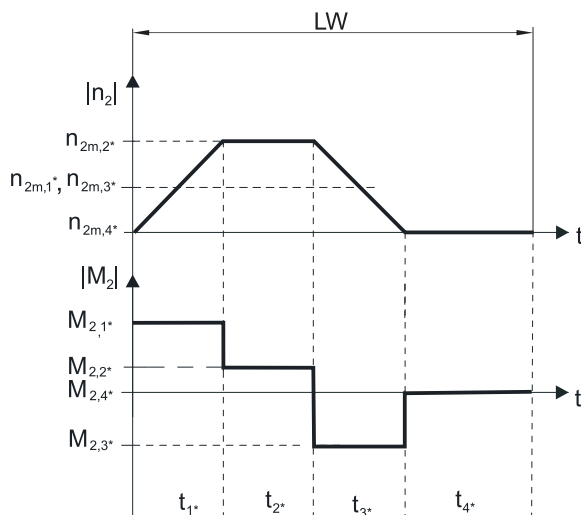
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{limK} and n_{limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} accordingly or select another geared motor size.)

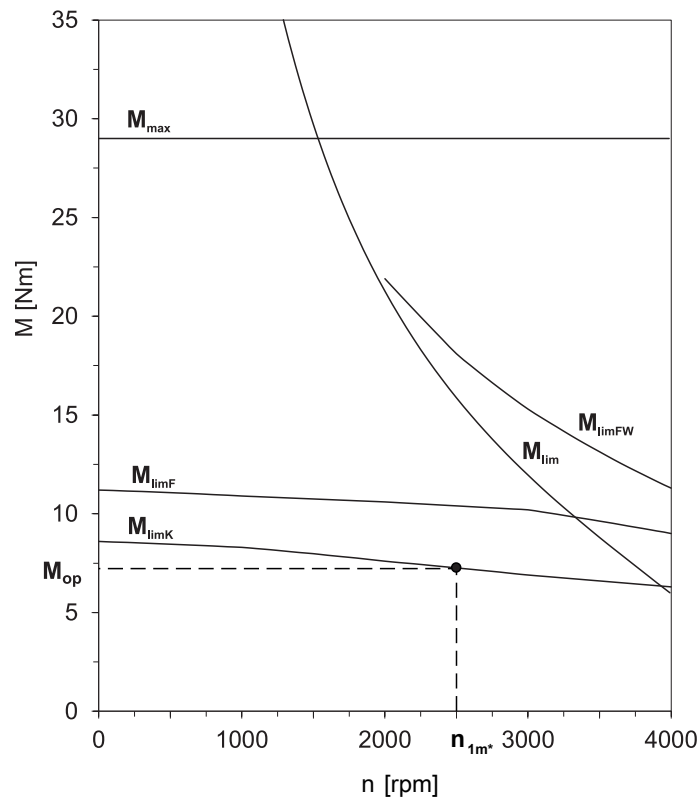
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot a_{thEL} \cdot f_{B_T} \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2, 5, 6	1.0
EL3, 4	1.1

Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40

Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20

Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

7.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 20$ rpm ($F_{2axN} = F_{2ax20}$; $F_{2radN} = F_{2rad20}$; $M_{2kN} = M_{2k20}$)
- Only if radial forces on the gearbox are stabilized by its pilots for the pitch circle diameter and flange housing design

Permitted shaft loads

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
C0	20.0	500	1900	1900	80	80
C1	30.0	850	3400	3400	190	190
C2	30.0	1050	4200	4200	260	260
C3	30.0	1400	5650	5650	350	350
C4	35.0	2400	9700	9700	750	750
C5	42.0	3000	11000	11000	900	900
C6	40.0	4000	16000	16000	1500	1500
C7	45.0	5500	22000	22000	2400	2400
C8	50.0	7500	30000	30000	3700	3700
C9	55.0	9500	37000	37000	5200	5200

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 20$ rpm:

$$F_{2axN} = \frac{F_{2ax20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

The values for F_{2ax20} , F_{2rad20} and M_{2k20} can be found in the table "Permitted shaft loads" in this chapter.

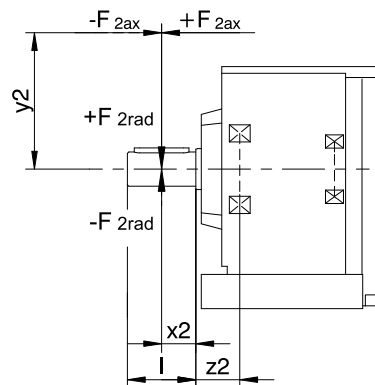


Fig. 1: Force application points

The specified values for F_{2rad20} and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

7.6.3 Radial shaft seal rings

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

7.6.4 Oil expansion tank

The gearboxes have a higher fill level in mounting position EL5. The oil expansion tank prevents oil from escaping out of the gearbox.

Notes

- We recommend using an oil expansion tank in mounting position EL5 (additional cost) for fast running gearboxes with an input speed $n_1 > 1750$ rpm and gear ratios $i < 20$.
- It is not possible to use an oil expansion tank if the plug connector is at 90°!
- The oil expansion tank can only be used with certain sizes; see the chapter [\[▶ 7.3.5\]](#)

7.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

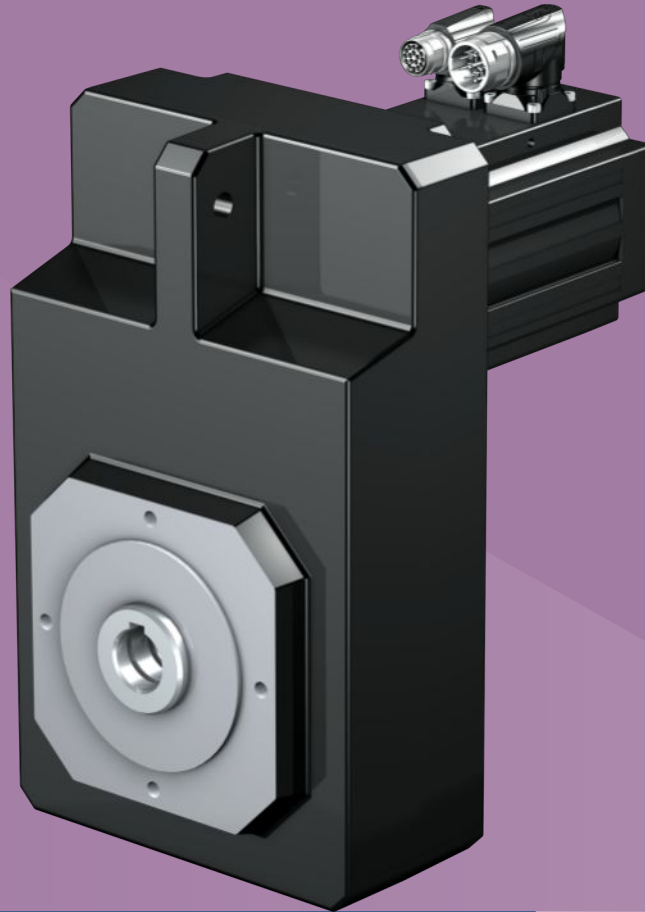
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors C	443365_en

8 F offset helical geared motors

Table of contents

8.1	Overview	186
8.2	Selection tables	187
8.3	Dimensional drawings	199
8.3.1	A shaft design (hollow shaft), G housing design (pitch circle diameter)	200
8.3.2	A shaft design (hollow shaft), GN housing design (pitch circle diameter + side fastening)	202
8.3.3	A shaft design (hollow shaft), F housing design (round flange)	204
8.3.4	A shaft design (hollow shaft), Q housing design (square flange)	206
8.3.5	V shaft design (solid shaft), F housing design (round flange)	208
8.3.6	V shaft design (solid shaft), Q housing design (square flange)	210
8.3.7	S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter)	212
8.3.8	S shaft design (hollow shaft with shrink disk), GN housing design (pitch circle diameter + side fastening)	214
8.3.9	S shaft design (hollow shaft with shrink disk), F housing design (round flange)	216
8.3.10	S shaft design (hollow shaft with shrink disk), Q housing design (square flange)	218
8.4	Type designation	220
8.5	Product description	220
8.5.1	Input options	220
8.5.2	Housing design	221
8.5.3	Combinatorial shaft/housing design	222
8.5.4	Installation conditions	222
8.5.5	Mounting positions	223
8.5.6	Lubricants	223
8.5.7	Position of the plug connectors	224
8.5.8	Other product features	224
8.5.9	Direction of rotation	224
8.6	Project configuration	225
8.6.1	Drive selection	226
8.6.2	Permitted shaft loads for the output shaft	230
8.6.3	Radial shaft seal rings	232
8.7	Additional documentation	232



8

Offset helical geared motors

F

8.1 Overview

Offset helical geared motors with large axial distances

Features

- Power density ★☆☆☆☆
- Backlash ★★☆☆☆
- Price category €
- Shaft load ★★☆☆☆
- Smooth operation ★★☆☆☆
- Torsional stiffness ★★☆☆☆
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free ✓
- FKM seal ring at the input ✓
- Large axial distances, suitable for confined situations ✓
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	4.3 – 440
M_{2acc}	21 – 1100 Nm
$\Delta\phi_2$	5 – 11 arcmin
η_{get}	96 – 97 %

8.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)
- Weight specification for mounting position EL1, housing design G

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n ₂	M ₂	M _{2,0}	a _{in}	S	Type	M _{2acc}	M _{2NOT}	i	i _{exakt}	n _{1max}		J ₁	Δφ ₂	Δφ _{2redll}	C ₂	m	
										EL1,2,3,4 [rpm]	EL5,6 [rpm]						n _{1max} ZB [rpm]
F1 (n _{1in} = 3000 min ⁻¹ , M _{2acc,max} = 120 Nm)																	
27	101	103	1.6	1.2	F102_1120 EZ301U	120	240	111.9	2015/18	4000	4000	7000	0.21	11.0	6.0	7.7	13
32	84	86	1.5	1.4	F102_0940 EZ301U	120	240	93.63	7865/84	4000	4000	7000	0.22	11.0	6.0	7.7	13
43	63	65	1.3	1.9	F102_0700 EZ301U	120	240	70.06	1261/18	4000	4000	7000	0.23	11.0	6.0	7.7	13
43	108	114	2.2	1.1	F102_0700 EZ302U	120	240	70.06	1261/18	4000	4000	7000	0.33	11.0	6.0	7.7	13
54	50	52	1.1	2.4	F102_0560 EZ301U	120	240	55.97	2015/36	4000	4000	7000	0.25	11.0	6.0	7.7	13
54	86	91	1.9	1.4	F102_0560 EZ302U	120	240	55.97	2015/36	4000	4000	7000	0.35	11.0	6.0	7.7	13
54	112	119	2.5	1.1	F102_0560 EZ303U	120	240	55.97	2015/36	4000	4000	7000	0.46	11.0	6.0	7.7	14
65	42	43	1.0	2.9	F102_0460 EZ301U	120	240	46.43	325/7	4000	4000	7000	0.28	11.0	6.0	7.7	13
65	72	76	1.8	1.7	F102_0460 EZ302U	120	240	46.43	325/7	4000	4000	7000	0.38	11.0	6.0	7.7	13
65	93	99	2.3	1.3	F102_0460 EZ303U	120	240	46.43	325/7	4000	4000	7000	0.49	11.0	6.0	7.7	14
86	32	32	1.0	3.5	F102_0350 EZ301U	95	240	35.05	3575/102	4000	4000	6500	0.32	11.0	6.0	7.7	13
86	54	57	1.7	2.0	F102_0350 EZ302U	120	240	35.05	3575/102	4000	4000	6500	0.42	11.0	6.0	7.7	13
86	70	74	2.2	1.6	F102_0350 EZ303U	120	240	35.05	3575/102	4000	4000	6500	0.53	11.0	6.0	7.7	14
86	95	102	2.9	1.2	F102_0350 EZ401U	120	240	35.05	3575/102	4000	4000	6500	1.1	11.0	6.0	7.7	15
107	25	26	0.9	4.0	F102_0280 EZ301U	77	205	28.17	169/6	4000	4000	6500	0.37	11.0	6.0	7.7	13
107	43	46	1.6	2.3	F102_0280 EZ302U	120	205	28.17	169/6	4000	4000	6500	0.47	11.0	6.0	7.7	13
107	57	60	2.1	1.8	F102_0280 EZ303U	120	205	28.17	169/6	4000	4000	6500	0.58	11.0	6.0	7.7	14
107	77	82	2.8	1.3	F102_0280 EZ401U	120	240	28.17	169/6	4000	4000	6500	1.1	11.0	6.0	7.7	15
130	21	21	0.9	4.6	F102_0230 EZ301U	63	168	23.08	3185/138	3700	3600	6000	0.43	11.0	6.0	7.7	13
130	36	38	1.6	2.7	F102_0230 EZ302U	112	168	23.08	3185/138	3700	3600	6000	0.53	11.0	6.0	7.7	13
130	46	49	2.0	2.1	F102_0230 EZ303U	120	168	23.08	3185/138	3700	3600	6000	0.64	11.0	6.0	7.7	14
130	63	67	2.7	1.5	F102_0230 EZ401U	120	240	23.08	3185/138	3700	3600	6000	1.2	11.0	6.0	7.7	15
163	28	30	1.5	3.1	F102_0185 EZ302U	90	134	18.46	1495/81	3700	3600	6000	0.62	11.0	6.0	7.7	13
163	37	39	2.0	2.4	F102_0185 EZ303U	107	134	18.46	1495/81	3700	3600	6000	0.73	11.0	6.0	7.7	14
163	50	54	2.6	1.8	F102_0185 EZ401U	120	240	18.46	1495/81	3700	3600	6000	1.3	11.0	6.0	7.7	15
163	77	84	4.1	1.1	F102_0185 EZ501U	120	240	18.46	1495/81	3700	3600	6000	3.2	11.0	6.0	7.7	16
163	84	93	4.4	1.1	F102_0185 EZ402U	120	240	18.46	1495/81	3700	3600	6000	2.0	11.0	6.0	7.7	16
221	21	22	1.4	3.8	F102_0135 EZ302U	66	99	13.59	231/17	4000	4000	6500	0.51	11.0	8.0	6.5	13
221	27	29	1.9	2.9	F102_0135 EZ303U	79	99	13.59	231/17	4000	4000	6500	0.62	11.0	8.0	6.5	14
221	37	40	2.5	2.2	F102_0135 EZ401U	105	200	13.59	231/17	4000	4000	6500	1.1	11.0	8.0	6.5	15
221	57	62	3.9	1.4	F102_0135 EZ501U	105	200	13.59	231/17	4000	4000	6500	3.1	11.0	8.0	6.5	16
221	62	69	4.2	1.3	F102_0135 EZ402U	105	200	13.59	231/17	4000	4000	6500	1.8	11.0	8.0	6.5	16
275	17	18	1.6	3.8	F102_0110 EZ302U	53	79	10.92	273/25	4000	4000	6500	0.60	11.0	8.0	6.5	13
275	22	23	2.1	2.9	F102_0110 EZ303U	64	79	10.92	273/25	4000	4000	6500	0.71	11.0	8.0	6.5	14
275	30	32	2.4	2.5	F102_0110 EZ401U	90	200	10.92	273/25	4000	4000	6500	1.2	11.0	8.0	6.5	15
275	46	50	3.7	1.6	F102_0110 EZ501U	105	200	10.92	273/25	4000	4000	6500	3.2	11.0	8.0	6.5	16
275	50	55	4.1	1.5	F102_0110 EZ402U	105	200	10.92	273/25	4000	4000	6500	1.9	11.0	8.0	6.5	16
275	73	91	6.0	1.0	F102_0110 EZ404U	105	200	10.92	273/25	4000	4000	6500	3.3	11.0	8.0	6.5	18
335	14	15	1.8	3.8	F102_0089 EZ302U	43	65	8.948	1029/115	3700	3600	6000	0.73	11.0	8.0	6.5	13
335	18	19	2.3	2.9	F102_0089 EZ303U	52	65	8.948	1029/115	3700	3600	6000	0.84	11.0	8.0	6.5	14
335	24	26	2.3	2.9	F102_0089 EZ401U	74	200	8.948	1029/115	3700	3600	6000	1.4	11.0	8.0	6.5	15
335	37	41	3.6	1.9	F102_0089 EZ501U	105	200	8.948	1029/115	3700	3600	6000	3.3	11.0	8.0	6.5	16
335	41	45	3.9	1.7	F102_0089 EZ402U	105	200	8.948	1029/115	3700	3600	6000	2.1	11.0	8.0	6.5	16
335	60	75	5.8	1.2	F102_0089 EZ404U	105	200	8.948	1029/115	3700	3600	6000	3.4	11.0	8.0	6.5	18
335	64	69	6.2	1.1	F102_0089 EZ502U	105	200	8.948	1029/115	3700	3600	6000	5.6	11.0	8.0	6.5	18
335	64	72	6.2	1.1	F102_0089 EZ701U	105	200	8.948	1029/115	3700	3600	6000	8.9	11.0	8.0	6.5	20
419	11	12	2.0	3.8	F102_0072 EZ302U	35	52	7.156	322/45	3700	3600	6000	0.92	11.0	8.0	6.5	13
419	14	15	2.6	2.9	F102_0072 EZ303U	42	52	7.156	322/45	3700	3600	6000	1.0	11.0	8.0	6.5	14
419	19	21	2.3	3.3	F102_0072 EZ401U	59	200	7.156	322/45	3700	3600	6000	1.6	11.0	8.0	6.5	15
419	30	33	3.5	2.2	F102_0072 EZ501U	105	200	7.156	322/45	3700	3600	6000	3.5	11.0	8.0	6.5	16
419	33	36	3.8	2.0	F102_0072 EZ402U	105	200	7.156	322/45	3700	3600	6000	2.3	11.0	8.0	6.5	16

8.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

Tolerances

Axis height in accordance with DIN 747	Tolerance
Up to 50 mm	-0.4 mm
Up to 250 mm	-0.5 mm
Up to 630 mm	-0.6 mm

Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6
Feather keys	DIN 6885-1, high form A

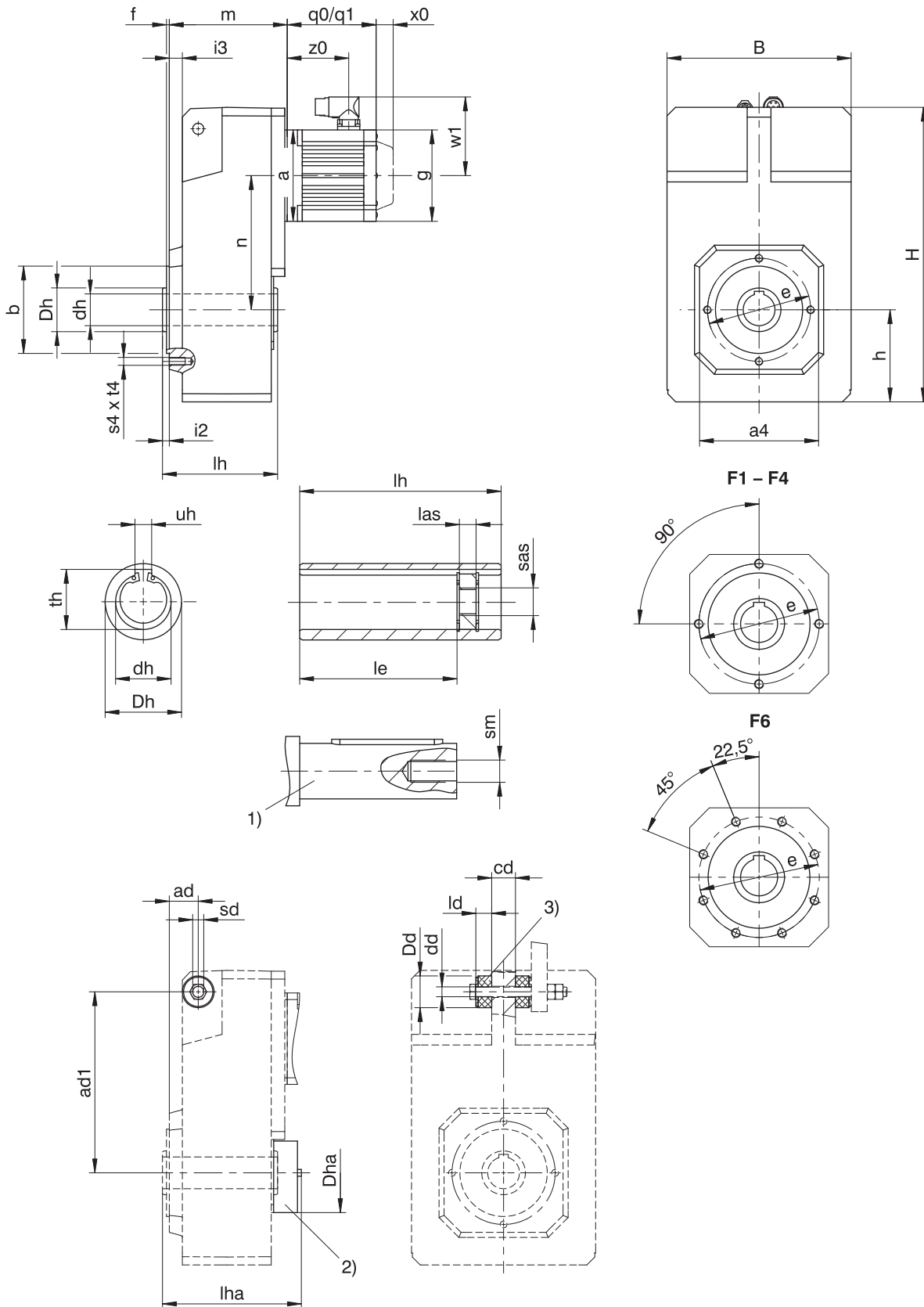
Hollow shaft	Tolerance
Hollow shaft hole fit	ISO H7
Feather keys	DIN 6885-1, high form

Flange	Pilot tolerance
Up to 300 mm	ISO j6
Starting at 350 mm	ISO h6

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

8.3.1 A shaft design (hollow shaft), G housing design (pitch circle diameter)



- q0 Applies to motors without brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method
- 1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

- q1 Applies to motors with brake.
- 2) Cover (optional)
- Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- 3) Rubber buffer for torque arm bracket (optional). Dimension $\varnothing Dd$ = outer diameter of the rubber buffer when not tensioned.

Dimensions of gearboxes

Type	$\square a4$	ad	ad1	$\varnothing b$	B	cd	$\varnothing dd$	$\varnothing dh$	$\varnothing Dd$	$\varnothing Dh$	$\varnothing Dha$	$\varnothing e$	f	h	H	i2	i3	ld	le	lh	las	lha	s4	sd	sm	sas	t4	th	uh
F1	100	28.5	150	70_{j6}	145	20	$11.0^{+0.5}$	20^{H7}	30	35	70	85	2.5	74	238.0	6.5	12.5	15	73	95	12	112	M8	M10	M6	M8	13	22.8	6^{JS9}
F2	130	32.0	181	95_{j6}	180	22	$11.0^{+0.5}$	25^{H7}	30	45	82	115	3.0	93	299.0	8.0	15.0	15	92	115	12	132	M8	M10	M10	M12	13	28.3	8^{JS9}
F3	150	36.5	205	110_{j6}	206	30	$14.0^{+0.5}$	30^{H7}	37	50	88	130	3.5	106	335.5	8.5	16.5	20	103	130	12	157	M10	M12	M10	M12	16	33.3	8^{JS9}
F4	150	36.5	228	110_{j6}	230	30	$14.0^{+0.5}$	40^{H7}	37	55	100	130	3.5	116	370.0	8.5	16.5	20	114	145	12	175	M10	M12	M16	M20	16	43.3	12^{JS9}
F6	180	44.5	270	130_{j6}	265	35	$22.0^{+0.5}$	50^{H7}	60	70	115	165	3.5	137	433.0	10.5	20.5	30	143	180	12	194	M10	M20	M16	M20	16	53.8	14^{JS9}

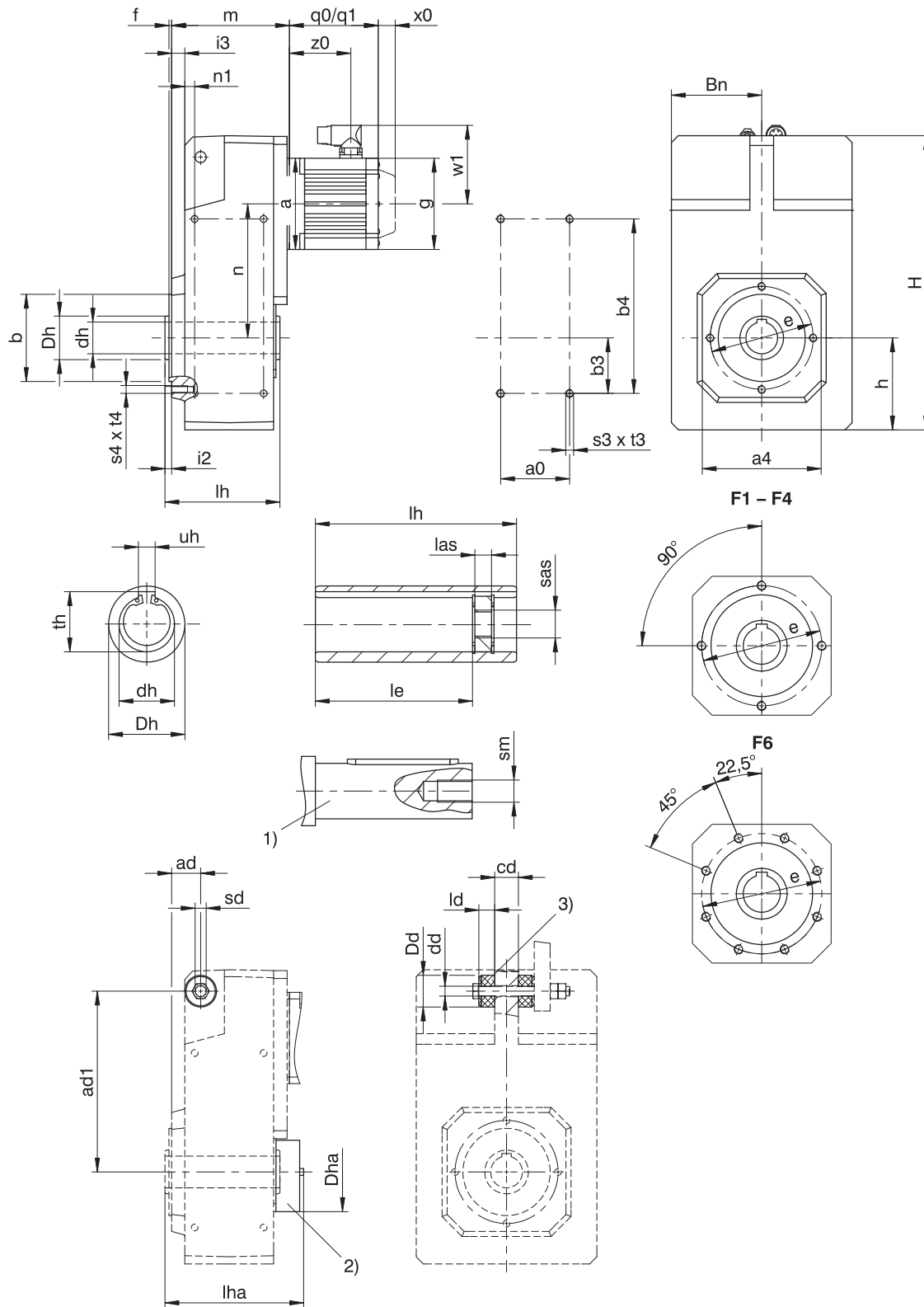
Dimensions of motors

Type	$\square g$	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	$\square 55$	97.5	102.0	$\square 72$	97.5	102.0	$\square 98$	97.5	102.0	$\square 115$	101.5	102.0	$\square 145$	103.5	102.0	-	-	-
F202	-	-	-	$\square 72$	115.0	131.0	$\square 98$	115.0	131.0	$\square 115$	119.0	131.0	$\square 145$	121.0	131.0	-	-	-
F203	-	-	-	$\varnothing 140$	152.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	$\varnothing 140$	129.5	149.5	$\varnothing 140$	129.5	149.5	$\square 115$	133.5	149.5	$\square 145$	135.5	149.5	-	-	-
F303	-	-	-	$\varnothing 140$	166.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	$\varnothing 160$	148.5	169.0	$\square 145$	150.5	169.0	$\square 190$	153.5	169.0
F403	-	-	-	$\varnothing 140$	181.5	169.0	$\varnothing 140$	181.5	169.0	$\varnothing 160$	191.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	$\varnothing 160$	179.5	196.0	$\square 145$	181.5	196.0	$\square 190$	184.5	196.0
F603	-	-	-	-	-	-	-	-	-	$\varnothing 160$	222.5	196.0	-	-	-	-	-	-

8.3.2 A shaft design (hollow shaft), GN housing design (pitch circle diameter + side fastening)



- | | | | |
|----|---|----|--|
| q0 | Applies to motors without brake. | q1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$. | 2) | Cover (optional) |

- 3) Rubber buffer for torque arm bracket (optional). Dimension $\varnothing Dd$ = outer diameter of the rubber buffer when not tensioned.

Dimensions of gearboxes

Type	a0	□a4	ad	ad1	Øb	b3	b4	Bn	cd	Ødd	Ødh	ØDd	ØDh	ØDha	Øe	f	h	H
F1	50	100	28.5	150	70 _β	40	140	71	20	11.0 ^{+0.5}	20 ^{H7}	30	35	70	85	2.5	74	238.0
F2	64	130	32.0	181	95 _β	55	175	88	22	11.0 ^{+0.5}	25 ^{H7}	30	45	82	115	3.0	93	299.0
F3	72	150	36.5	205	110 _β	60	200	102	30	14.0 ^{+0.5}	30 ^{H7}	37	50	88	130	3.5	106	335.5
F4	87	150	36.5	228	110 _β	70	220	114	30	14.0 ^{+0.5}	40 ^{H7}	37	55	100	130	3.5	116	370.0
F6	108	180	44.5	270	130 _β	85	270	131	35	22.0 ^{+0.5}	50 ^{H7}	60	70	115	165	3.5	137	433.0

Type	i2	i3	ld	le	lh	las	lha	n1	s3	s4	sd	sm	sas	t3	t4	th	uh
F1	6.5	12.5	15	73	95	12	112	10.0	M6	M8	M10	M6	M8	11	13	22.8	6 ^{JS9}
F2	8.0	15.0	15	92	115	12	132	10.5	M8	M8	M10	M10	M12	13	13	28.3	8 ^{JS9}
F3	8.5	16.5	20	103	130	12	157	12.5	M10	M10	M12	M10	M12	16	16	33.3	8 ^{JS9}
F4	8.5	16.5	20	114	145	12	175	12.5	M10	M10	M12	M16	M20	16	16	43.3	12 ^{JS9}
F6	10.5	20.5	30	143	180	12	194	15.5	M12	M10	M20	M16	M20	19	16	53.8	14 ^{JS9}

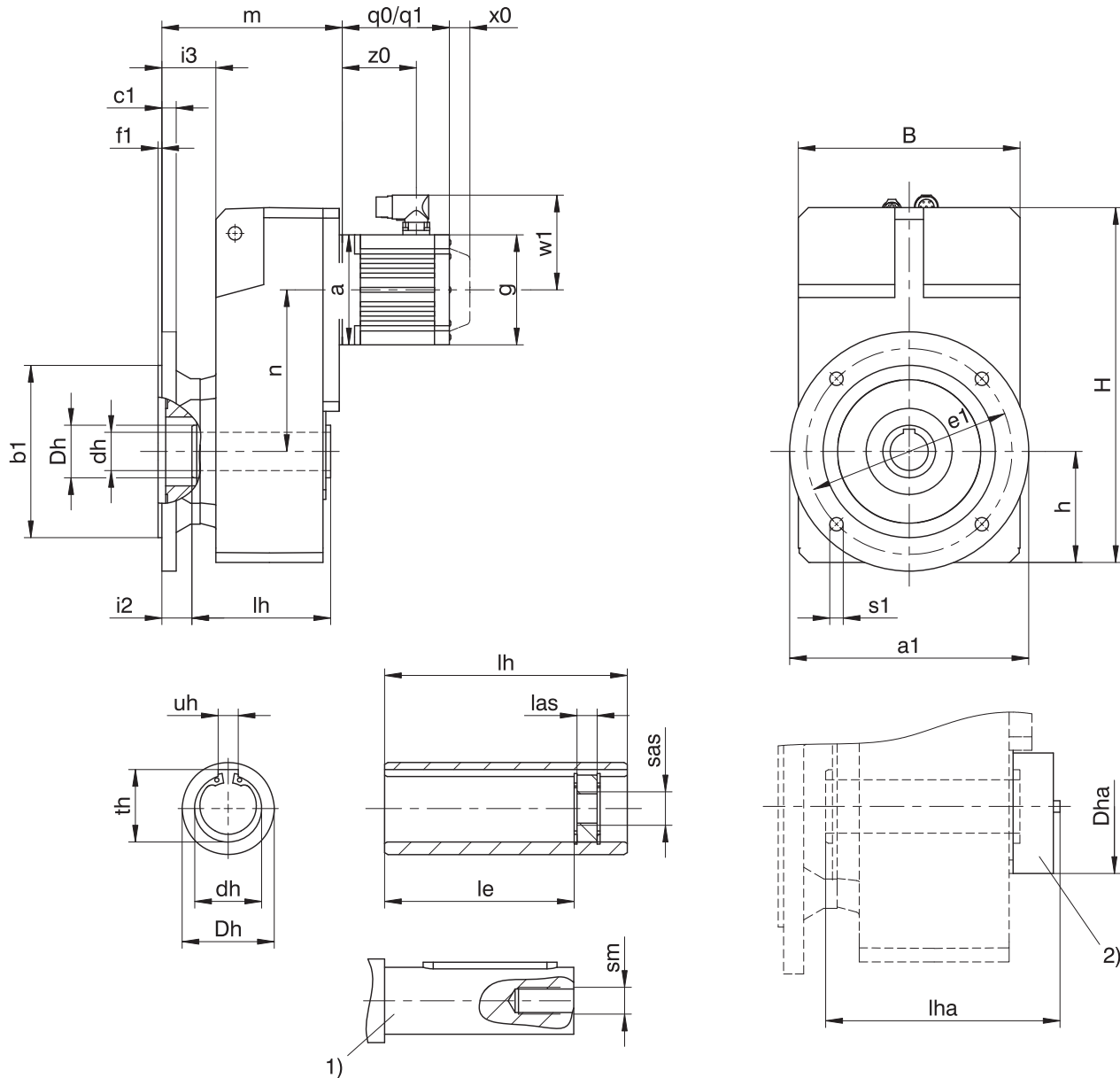
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	97.5	102.0	□72	97.5	102.0	□98	97.5	102.0	□115	101.5	102.0	□145	103.5	102.0	-	-	-
F202	-	-	-	□72	115.0	131.0	□98	115.0	131.0	□115	119.0	131.0	□145	121.0	131.0	-	-	-
F203	-	-	-	Ø140	152.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	Ø140	129.5	149.5	Ø140	129.5	149.5	□115	133.5	149.5	□145	135.5	149.5	-	-	-
F303	-	-	-	Ø140	166.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	Ø160	148.5	169.0	□145	150.5	169.0	□190	153.5	169.0
F403	-	-	-	Ø140	181.5	169.0	Ø140	181.5	169.0	Ø160	191.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	Ø160	179.5	196.0	□145	181.5	196.0	□190	184.5	196.0
F603	-	-	-	-	-	-	-	-	-	Ø160	222.5	196.0	-	-	-	-	-	-

8.3.3 A shaft design (hollow shaft), F housing design (round flange)



q0 Applies to motors without brake.

q1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

2) Cover (optional)

Dimensions of gearboxes

Type	$\varnothing a1$	$\varnothing b1$	B	c1	$\varnothing dh$	$\varnothing Dh$	$\varnothing Dha$	$\varnothing e1$	f1	h	H	i2	i3	le	lh	las	lha	$\varnothing s1$	sm	sas	th	uh
F1	160	110 _f	145	10	20 ^{H7}	35	70	130	3.5	74	238.0	25.5	44.5	73	95	12	112	9	M6	M8	22.8	6 ^{JS9}
F2	200	130 _f	180	14	25 ^{H7}	45	82	165	3.5	93	299.0	30.0	53.0	92	115	12	132	11	M10	M12	28.3	8 ^{JS9}
F3	250	180 _f	206	15	30 ^{H7}	50	88	215	4.0	106	335.5	31.5	56.5	103	130	12	157	14	M10	M12	33.3	8 ^{JS9}
F4	250	180 _f	230	15	40 ^{H7}	55	100	215	4.0	116	370.0	31.5	56.5	114	145	12	175	14	M16	M20	43.3	12 ^{JS9}
F6	300	230 _f	265	17	50 ^{H7}	70	115	265	4.0	137	433.0	29.5	60.5	143	180	12	194	14	M16	M20	53.8	14 ^{JS9}

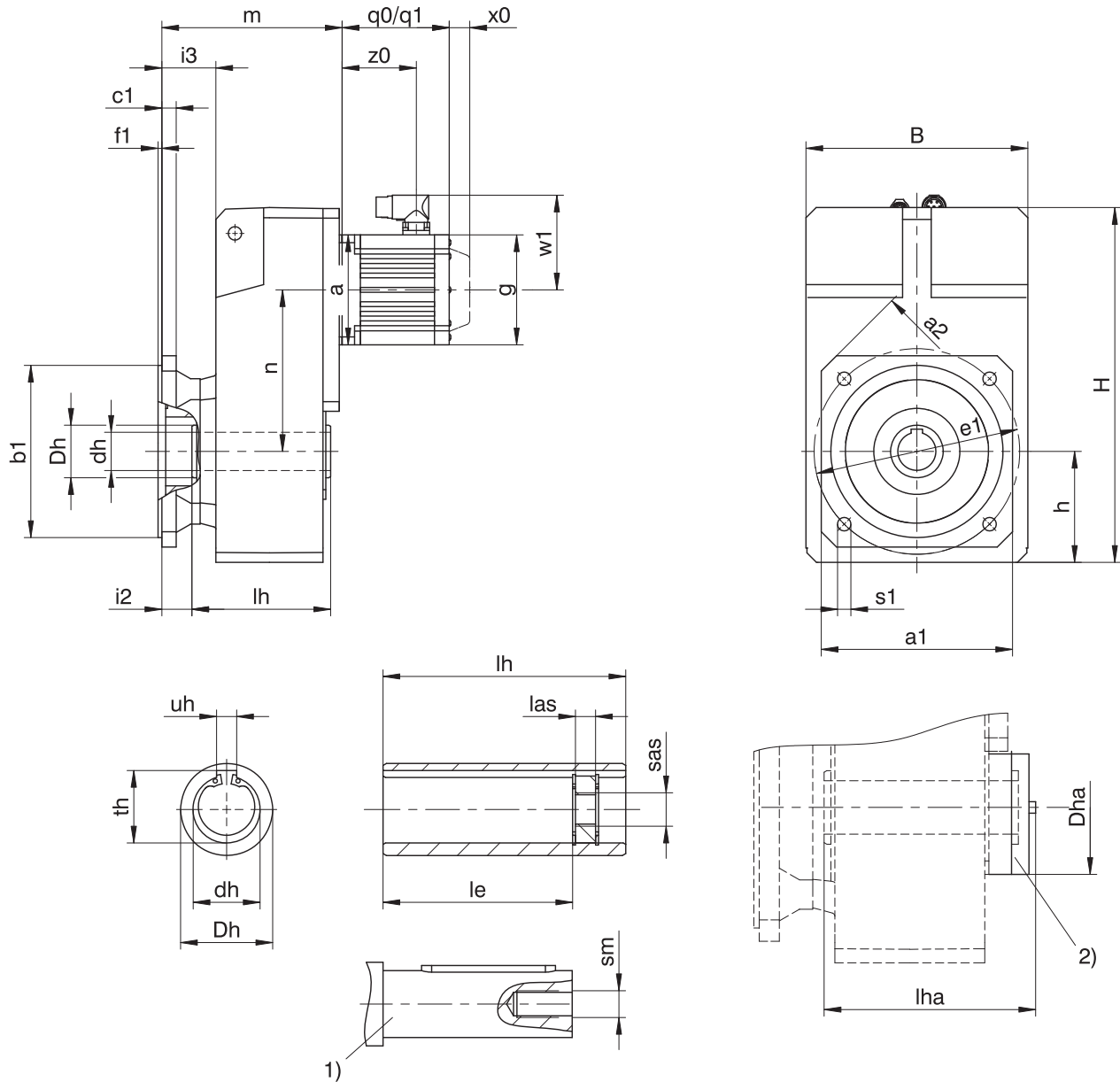
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	∅140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	∅140	169.5	149.5	∅140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	∅140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	∅160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	∅140	221.5	169.0	∅140	221.5	169.0	∅160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	∅160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	∅160	262.5	196.0	-	-	-	-	-	-

8.3.4 A shaft design (hollow shaft), Q housing design (square flange)



- q0 Applies to motors without brake. q1 Applies to motors with brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method Different for the One Cable Solution (OCS), see the chapter [17.4](#)
- EZ3 – EZ8: Applies to encoders using an optical measuring method
- 1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$. 2) Cover (optional)

Dimensions of gearboxes

Type	□a1	□a2	∅b1	B	c1	∅dh	∅Dh	∅Dha	∅e1	f1	h	H	i2	i3	le	lh	las	lha	∅s1	sm	sas	th	uh
F1	125	160	110 _β	145	10	20 ^{H7}	35	70	130	3.5	74	238.0	25.5	44.5	73	95	12	112	9	M6	M8	22.8	6 ^{JS9}
F2	150	195	130 _β	180	14	25 ^{H7}	45	82	165	3.5	93	299.0	30.0	53.0	92	115	12	132	11	M10	M12	28.3	8 ^{JS9}
F3	200	260	180 _β	206	15	30 ^{H7}	50	88	215	4.0	106	335.5	31.5	56.5	103	130	12	157	14	M10	M12	33.3	8 ^{JS9}
F4	200	260	180 _β	230	15	40 ^{H7}	55	100	215	4.0	116	370.0	31.5	56.5	114	145	12	175	14	M16	M20	43.3	12 ^{JS9}
F6	250	325	230 _β	265	17	50 ^{H7}	70	115	265	4.0	137	433.0	29.5	60.5	143	180	12	194	14	M16	M20	53.8	14 ^{JS9}

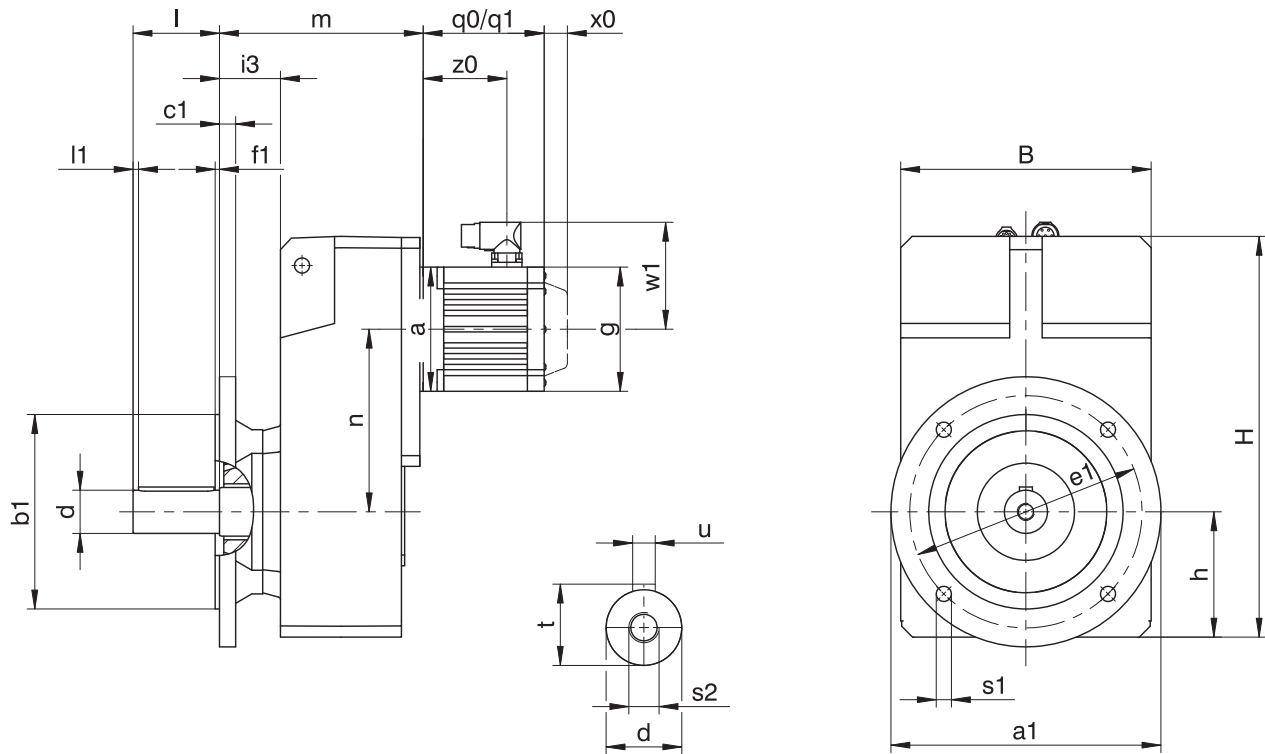
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	∅140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	∅140	169.5	149.5	∅140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	∅140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	∅160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	∅140	221.5	169.0	∅140	221.5	169.0	∅160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	∅160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	∅160	262.5	196.0	-	-	-	-	-	-

8.3.5 V shaft design (solid shaft), F housing design (round flange)



$q0$ Applies to motors without brake.

$q1$

Applies to motors with brake.

$x0$ EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

EZ3 – EZ8: Applies to encoders using an optical measuring method

Dimensions of gearboxes

Type	$\varnothing a1$	$\varnothing b1$	B	c1	$\varnothing d$	$\varnothing e1$	f1	h	H	i3	l	l1	$\varnothing s1$	s2	t	u
F1	160	110 _{f6}	145	10	25 _{k6}	130	3.5	74	238.0	44.5	50	5	9	M10	28.0	A8×7×40
F2	200	130 _{f6}	180	14	30 _{k6}	165	3.5	93	299.0	53.0	60	5	11	M10	33.0	A8×7×50
F3	250	180 _{f6}	206	15	35 _{k6}	215	4.0	106	335.5	56.5	70	5	14	M12	38.0	A10×8×60
F4	250	180 _{f6}	230	15	40 _{k6}	215	4.0	116	370.0	56.5	80	5	14	M16	43.0	A12×8×70
F6	300	230 _{f6}	265	17	50 _{k6}	265	4.0	137	433.0	60.5	100	5	14	M16	53.5	A14×9×90

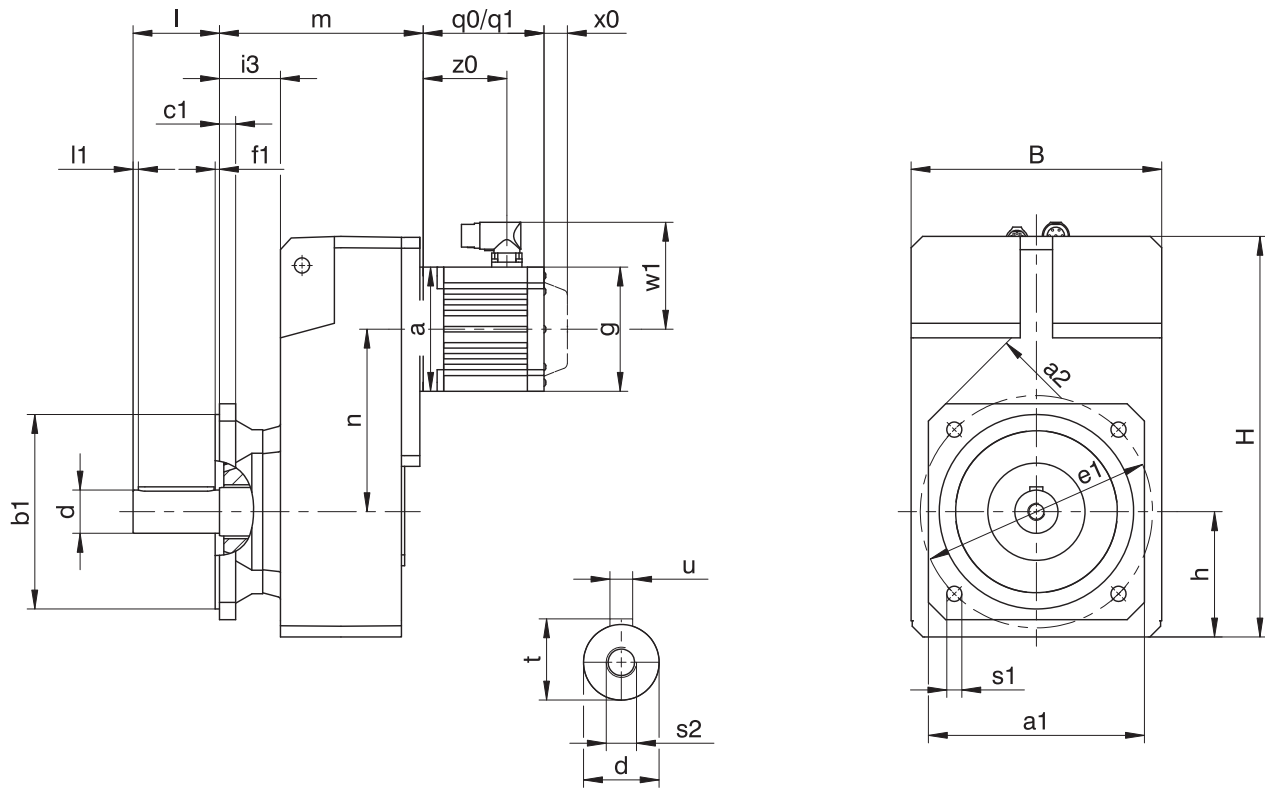
Dimensions of motors

Type	$\square g$	$q0$	$q1$	$w1$	$x0$	$z0$
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	∅140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	∅140	169.5	149.5	∅140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	∅140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	∅160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	∅140	221.5	169.0	∅140	221.5	169.0	∅160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	∅160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	∅160	262.5	196.0	-	-	-	-	-	-

8.3.6 V shaft design (solid shaft), Q housing design (square flange)



q0 Applies to motors without brake.

q1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	□a1	□a2	∅b1	c1	B	∅d	∅e1	f1	h	H	i3	l	l1	∅s1	s2	t	u
F1	125	160	110 _{f6}	10	145	25 _{f6}	130	3.5	74	238.0	44.5	50	5	9	M10	28.0	A8×7×40
F2	150	195	130 _{f6}	14	180	30 _{f6}	165	3.5	93	299.0	53.0	60	5	11	M10	33.0	A8×7×50
F3	200	260	180 _{f6}	15	206	35 _{f6}	215	4.0	106	335.5	56.5	70	5	14	M12	38.0	A10×8×60
F4	200	260	180 _{f6}	15	230	40 _{f6}	215	4.0	116	370.0	56.5	80	5	14	M16	43.0	A12×8×70
F6	250	325	230 _{f6}	17	265	50 _{f6}	265	4.0	137	433.0	60.5	100	5	14	M16	53.5	A14×9×90

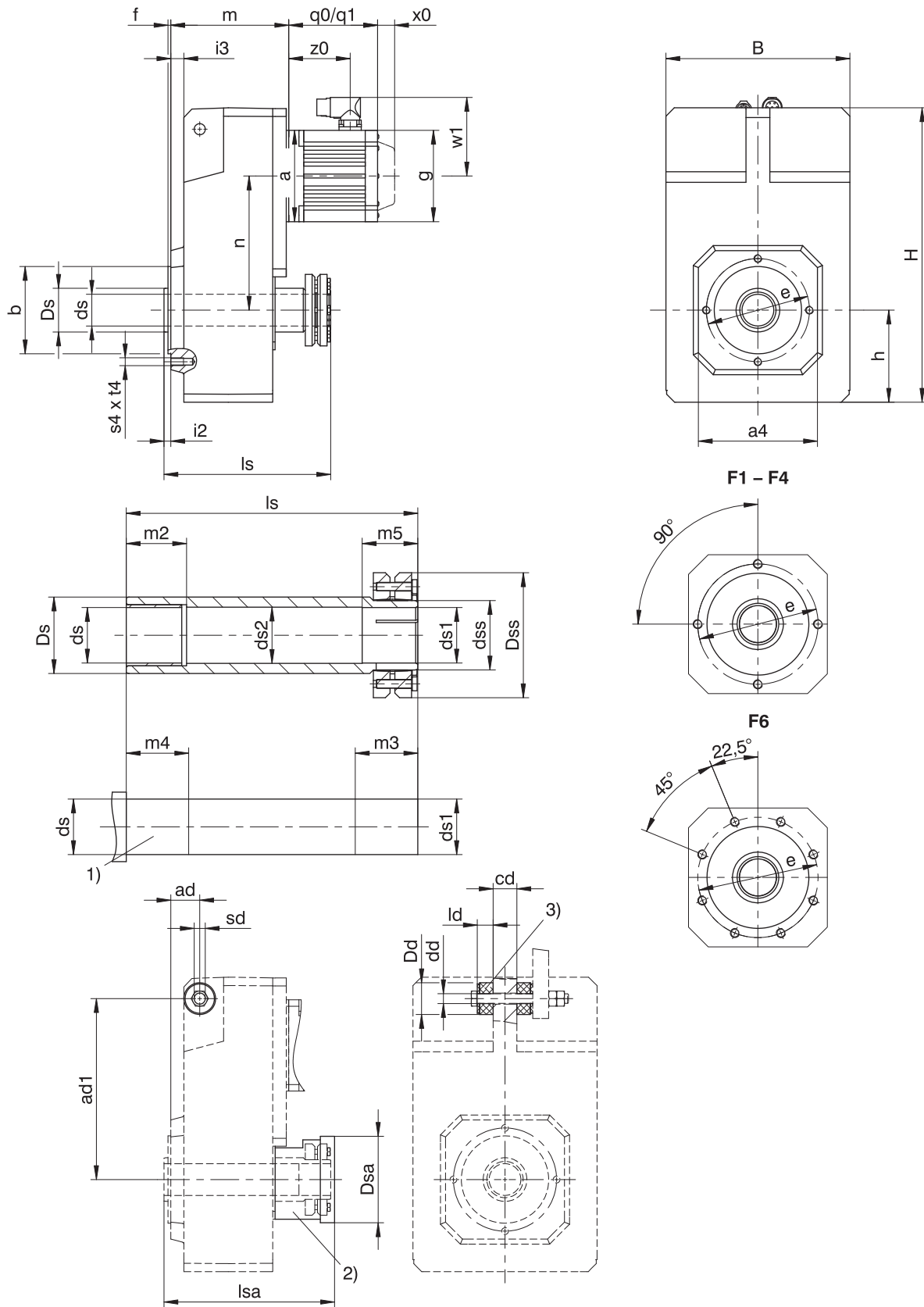
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	∅140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	∅140	169.5	149.5	∅140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	∅140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	∅160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	∅140	221.5	169.0	∅140	221.5	169.0	∅160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	∅160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	∅160	262.5	196.0	-	-	-	-	-	-

8.3.7 S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter)



- q0 Applies to motors without brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method
- 1) Machine shaft: The dimension ls must meet or exceed the specified value.

- q1 Applies to motors with brake.
- Different for the One Cable Solution (OCS), see the chapter [▶ 17.4](#)
- 2) Cover (optional)

- 3) Rubber buffer for torque arm bracket (optional). Dimension $\varnothing Dd$ = outer diameter of the rubber buffer when not tensioned.

Dimensions of gearboxes

Type	a4	ad	ad1	$\varnothing b$	B	cd	$\varnothing dd$	$\varnothing ds$	$\varnothing ds1$	$\varnothing ds2$	$\varnothing ds3$	$\varnothing Dd$	$\varnothing Ds$	$\varnothing Dsa$	$\varnothing Dss$	$\varnothing e$	f	h	H	i2	i3	ld	ls	lsa	m2	m3	m4	m5	s4	sd	t4
F1	100	28.5	150	70_{j6}	145	20	$11.0^{+0.5}$	20_{h9}	20_{h9}^{H7}	20.5	24	30	35	63	50	85	2.5	74	238.0	6.5	12.5	15	146	150	20	31	25	26	M8	M10	13
F2	130	32.0	181	95_{j6}	180	22	$11.0^{+0.5}$	25_{h9}	25_{h9}^{H7}	25.5	30	30	45	73	60	115	3.0	93	299.0	8.0	15.0	15	175	180	20	37	25	32	M8	M10	13
F3	150	36.5	205	110_{j6}	206	30	$14.0^{+0.5}$	30_{h9}	30_{h9}^{H7}	30.5	36	37	50	83	72	130	3.5	106	335.5	8.5	16.5	20	192	196	25	37	30	32	M10	M12	16
F4	150	36.5	228	110_{j6}	230	30	$14.0^{+0.5}$	40_{h9}	40_{h9}^{H7}	40.5	50	37	55	108	90	130	3.5	116	370.0	8.5	16.5	20	210	215	40	45	45	40	M10	M12	16
F6	180	44.5	270	130_{j6}	265	35	$22.0^{+0.5}$	50_{h9}	50_{h9}^{H7}	50.5	62	60	70	128	106	165	3.5	137	433.0	10.5	20.5	30	248	251	40	47	45	42	M10	M20	16

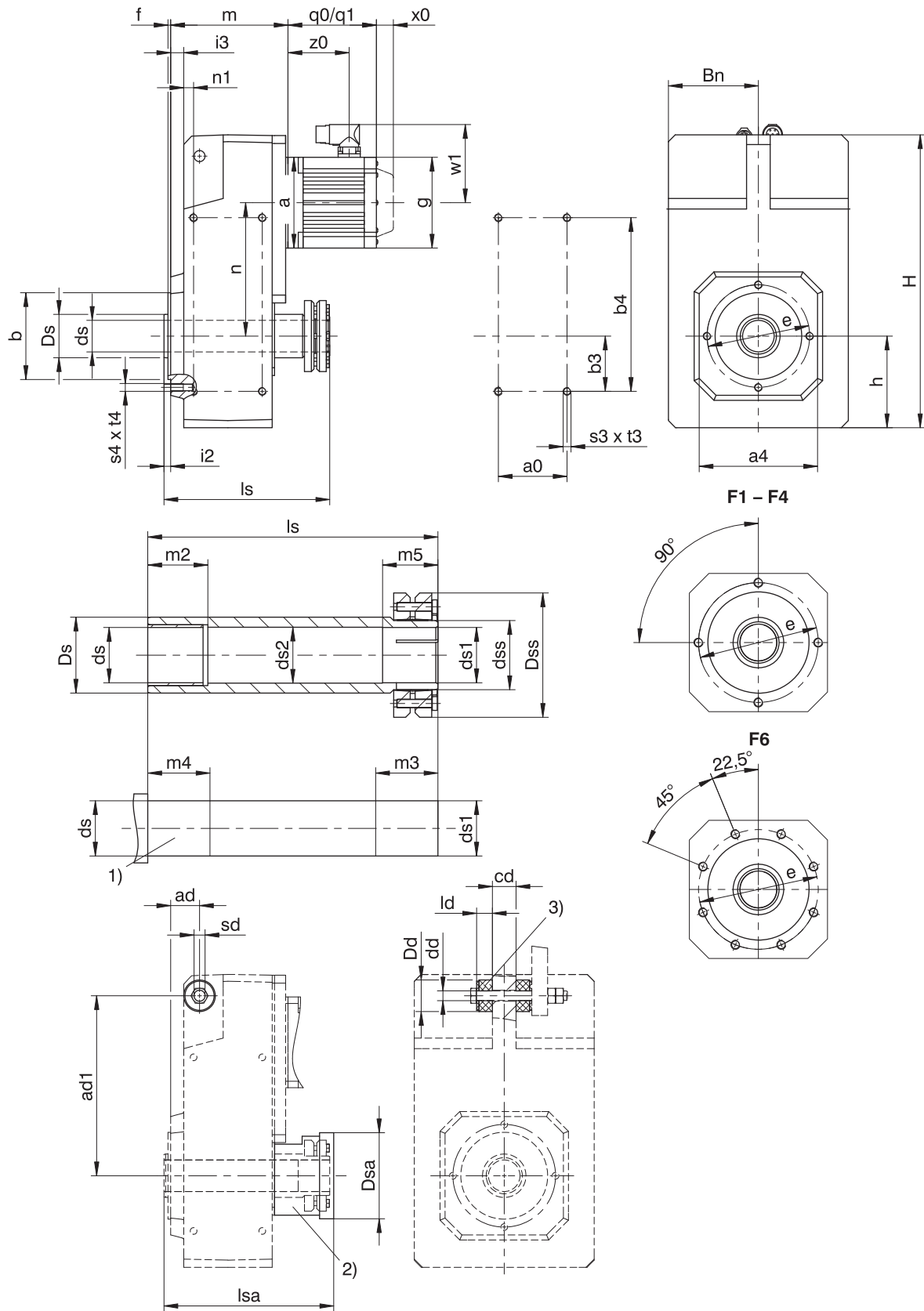
Dimensions of motors

Type	g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	$\square 55$	97.5	102.0	$\square 72$	97.5	102.0	$\square 98$	97.5	102.0	$\square 115$	101.5	102.0	$\square 145$	103.5	102.0	-	-	-
F202	-	-	-	$\square 72$	115.0	131.0	$\square 98$	115.0	131.0	$\square 115$	119.0	131.0	$\square 145$	121.0	131.0	-	-	-
F203	-	-	-	$\varnothing 140$	152.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	$\varnothing 140$	129.5	149.5	$\varnothing 140$	129.5	149.5	$\square 115$	133.5	149.5	$\square 145$	135.5	149.5	-	-	-
F303	-	-	-	$\varnothing 140$	166.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	$\varnothing 160$	148.5	169.0	$\square 145$	150.5	169.0	$\square 190$	153.5	169.0
F403	-	-	-	$\varnothing 140$	181.5	169.0	$\varnothing 140$	181.5	169.0	$\varnothing 160$	191.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	$\varnothing 160$	179.5	196.0	$\square 145$	181.5	196.0	$\square 190$	184.5	196.0
F603	-	-	-	-	-	-	-	-	-	$\varnothing 160$	222.5	196.0	-	-	-	-	-	-

8.3.8 S shaft design (hollow shaft with shrink disk), GN housing design (pitch circle diameter + side fastening)



F1 - F4

F6

- q0 Applies to motors without brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method
- 1) Machine shaft: The dimension ls must meet or exceed the specified value.

- q1 Applies to motors with brake.
- Different for the One Cable Solution (OCS), see the chapter [17.4](#)
- 2) Cover (optional)

- 3) Rubber buffer for torque arm bracket (optional). Dimension $\varnothing Dd$ = outer diameter of the rubber buffer when not tensioned.

Dimensions of gearboxes

Type	a0	□a4	ad	ad1	Øb	b3	b4	Bn	cd	Ødd	Øds	Øds1	Øds2	Ødss	ØDd	ØDs	ØDsa	ØDss
F1	50	100	29.5	150	70 _{f6}	40	140	71	20	11.0 ^{+0.5}	20 _{h9}	20 _{h9} ^{H7}	20.5	24	30	63	63	50
F2	64	130	33.0	181	95 _{f6}	55	175	88	22	11.0 ^{+0.5}	25 _{h9}	25 _{h9} ^{H7}	25.5	30	30	73	73	60
F3	72	150	38.5	205	110 _{f6}	60	200	102	30	14.0 ^{+0.5}	30 _{h9}	30 _{h9} ^{H7}	30.5	36	37	83	83	72
F4	87	150	38.5	228	110 _{f6}	70	220	114	30	14.0 ^{+0.5}	40 _{h9}	40 _{h9} ^{H7}	40.5	50	37	108	108	90
F6	108	180	44.5	270	130 _{f6}	85	270	131	35	22.0 ^{+0.5}	50 _{h9}	50 _{h9} ^{H7}	50.5	62	60	128	128	106

Type	Øe	f	h	H	i2	i3	ld	ls	lsa	n1	m2	m3	m4	m5	s3	s4	sd	t3	t4
F1	85	2.5	74	238.0	6.5	12.5	15	146	150	10	20	31	25	26	M6	M8	M10	11	13
F2	115	3.0	93	299.0	8.0	15.0	15	175	180	10.5	20	37	25	32	M8	M8	M10	13	13
F3	130	3.5	106	335.5	8.5	16.5	20	192	196	12.5	25	37	30	32	M10	M10	M12	16	16
F4	130	3.5	116	370.0	8.5	16.5	20	210	215	12.5	40	45	45	40	M10	M10	M12	16	16
F6	165	3.5	137	433.0	10.5	20.5	30	248	251	15.5	40	47	45	42	M12	M10	M20	19	16

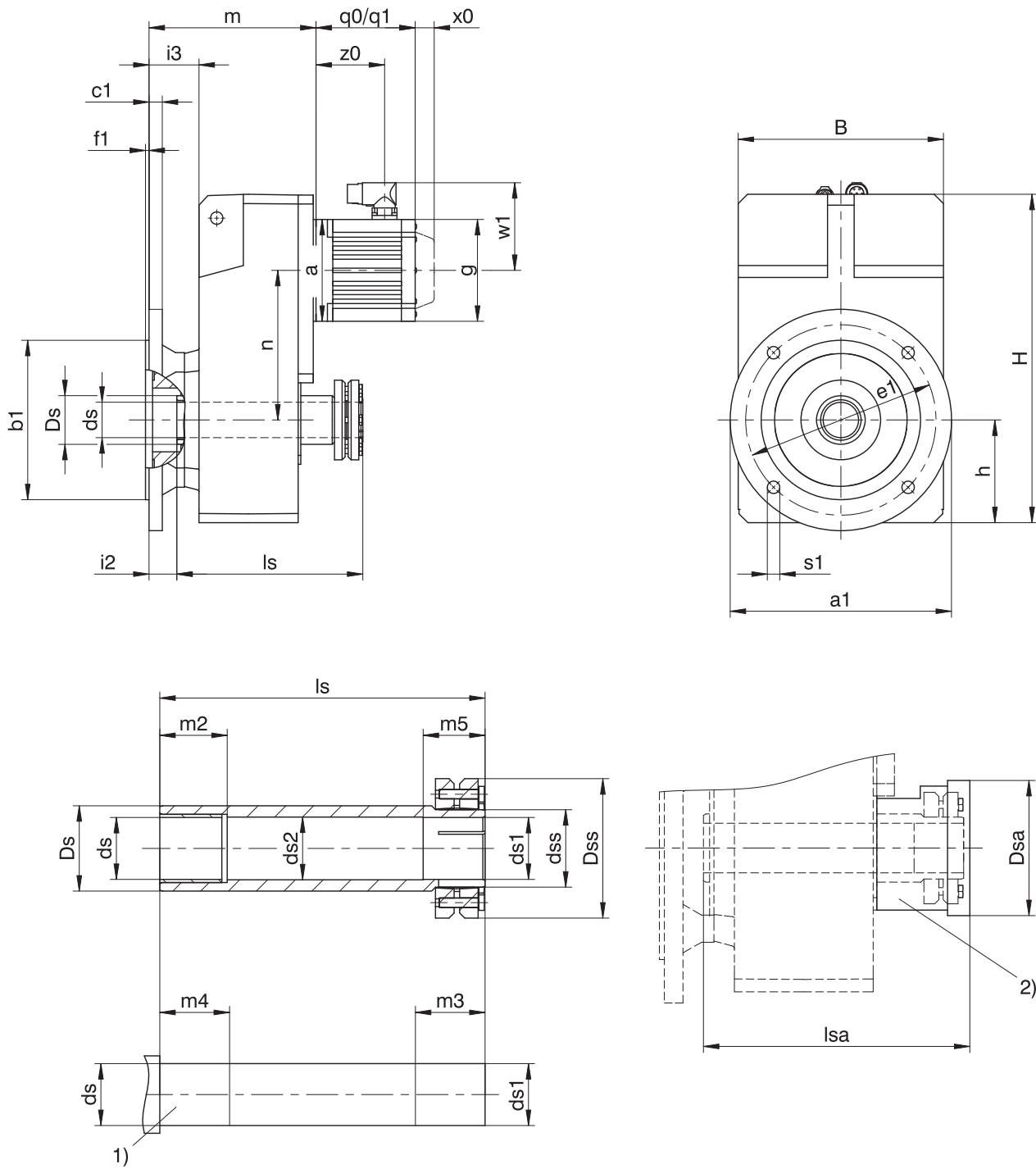
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	97.5	102.0	□72	97.5	102.0	□98	97.5	102.0	□115	101.5	102.0	□145	103.5	102.0	-	-	-
F202	-	-	-	□72	115.0	131.0	□98	115.0	131.0	□115	119.0	131.0	□145	121.0	131.0	-	-	-
F203	-	-	-	Ø140	152.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	Ø140	129.5	149.5	Ø140	129.5	149.5	□115	133.5	149.5	□145	135.5	149.5	-	-	-
F303	-	-	-	Ø140	166.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	Ø160	148.5	169.0	□145	150.5	169.0	□190	153.5	169.0
F403	-	-	-	Ø140	181.5	169.0	Ø140	181.5	169.0	Ø160	191.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	Ø160	179.5	196.0	□145	181.5	196.0	□190	184.5	196.0
F603	-	-	-	-	-	-	-	-	-	Ø160	222.5	196.0	-	-	-	-	-	-

8.3.9 S shaft design (hollow shaft with shrink disk), F housing design (round flange)



- | | | | |
|----|--|----|--|
| q0 | Applies to motors without brake. | q1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension l_s must meet or exceed the specified value. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	Øa1	Øb1	B	c1	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe1	f1	h	H	i2	i3	ls	lsa	m2	m3	m4	m5	Øs1
F1	160	110 _{f6}	145	10	20 _{h9}	20 _{h9} ^{H7}	20.5	24	35	63	50	130	3.5	74	238.0	25.5	44.5	146	150	20	31	25	26	9
F2	200	130 _{f6}	180	14	25 _{h9}	25 _{h9} ^{H7}	25.5	30	45	73	60	165	3.5	93	299.0	30.0	53.0	175	180	20	37	25	32	11
F3	250	180 _{f6}	206	15	30 _{h9}	30 _{h9} ^{H7}	30.5	36	50	83	72	215	4.0	106	335.5	31.5	56.5	192	196	25	37	30	32	14
F4	250	180 _{f6}	230	15	40 _{h9}	40 _{h9} ^{H7}	40.5	50	55	108	90	215	4.0	116	370.0	31.5	56.5	210	215	40	45	45	40	14
F6	300	230 _{f6}	265	17	50 _{h9}	50 _{h9} ^{H7}	50.5	62	70	128	106	265	4.0	137	433.0	29.5	60.5	248	251	40	47	45	42	14

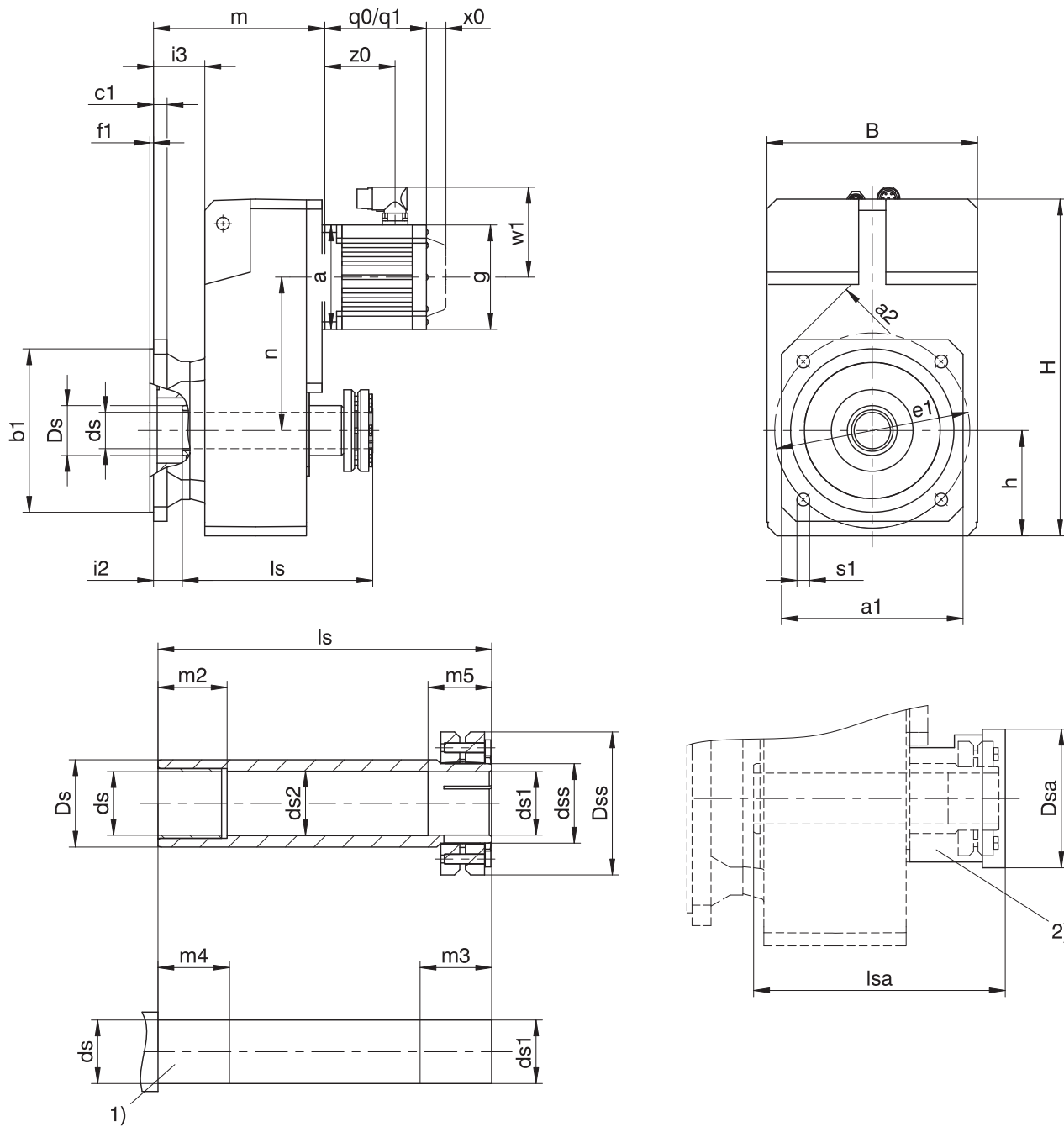
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	Ø140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	Ø140	169.5	149.5	Ø140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	Ø140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	Ø160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	Ø140	221.5	169.0	Ø140	221.5	169.0	Ø160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	Ø160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	Ø160	262.5	196.0	-	-	-	-	-	-

8.3.10 S shaft design (hollow shaft with shrink disk), Q housing design (square flange)



- q0 Applies to motors without brake.
- q1 Applies to motors with brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method
- 2) Different for the One Cable Solution (OCS), see the chapter [17.4](#)
- 1) Machine shaft: The dimension ls must meet or exceed the specified value.
- 2) Cover (optional)

Dimensions of gearboxes

Type	□a1	□a2	Øb1	B	c1	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe1	f1	h	H	i2	i3	ls	lsa	m2	m3	m4	m5	Øs1
F1	125	160	110 _{f6}	145	10	20 _{h9}	20 _{h9} ^{H7}	20.5	24	35	63	50	130	3.5	74	238.0	25.5	44.5	146	150	20	31	25	26	9
F2	150	195	130 _{f6}	180	14	25 _{h9}	25 _{h9} ^{H7}	25.5	30	45	73	60	165	3.5	93	299.0	30.0	53.0	175	180	20	37	25	32	11
F3	200	260	180 _{f6}	206	15	30 _{h9}	30 _{h9} ^{H7}	30.5	36	50	83	72	215	4.0	106	335.5	31.5	56.5	192	196	25	37	30	32	14
F4	200	260	180 _{f6}	230	15	40 _{h9}	40 _{h9} ^{H7}	40.5	50	55	108	90	215	4.0	116	370.0	31.5	56.5	210	215	40	45	45	40	14
F6	250	325	230 _{f6}	265	17	50 _{h9}	50 _{h9} ^{H7}	50.5	62	70	128	106	265	4.0	137	433.0	29.5	60.5	248	251	40	47	45	42	14

Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ203U	55	166.0	175.0	47.0	25	111.0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ2			EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
F102	□55	129.5	102.0	□72	129.5	102.0	□98	129.5	102.0	□115	133.5	102.0	□145	135.5	102.0	-	-	-
F202	-	-	-	□72	153.0	131.0	□98	153.0	131.0	□115	157.0	131.0	□145	159.0	131.0	-	-	-
F203	-	-	-	∅140	190.0	131.0	-	-	-	-	-	-	-	-	-	-	-	-
F302	-	-	-	∅140	169.5	149.5	∅140	169.5	149.5	□115	173.5	149.5	□145	175.5	149.5	-	-	-
F303	-	-	-	∅140	206.5	149.5	-	-	-	-	-	-	-	-	-	-	-	-
F402	-	-	-	-	-	-	-	-	-	∅160	188.5	169.0	□145	190.5	169.0	□190	193.5	169.0
F403	-	-	-	∅140	221.5	169.0	∅140	221.5	169.0	∅160	231.5	132.0	-	-	-	-	-	-
F602	-	-	-	-	-	-	-	-	-	∅160	219.5	196.0	□145	221.5	196.0	□190	224.5	196.0
F603	-	-	-	-	-	-	-	-	-	∅160	262.5	196.0	-	-	-	-	-	-

8.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

F	2	0	2	A	G	0700	EZ401U
---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
F	Type	Offset helical gearbox
2	Size	2 (example)
0	Generation	Generation 0
2	Stages	Two-stage
3		Three-stage
A	Shaft	Hollow shaft with keyway
S		Hollow shaft with shrink ring
V		Solid shaft
G	Housing	Pitch circle diameter
F		Round flange
Q		Square flange
GN		Pitch circle diameter + side fastening
/0700	Transmission ratio (i x 10 rounded)	i = 70.13 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Mounting position, see the chapter [▶ 8.5.5](#)
- Position of the plug connectors, see the chapter [▶ 8.5.7](#)

To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

8.5 Product description

8.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter + EZ synchronous servo motor



Catalog ID 443311_en

LM Lean motor

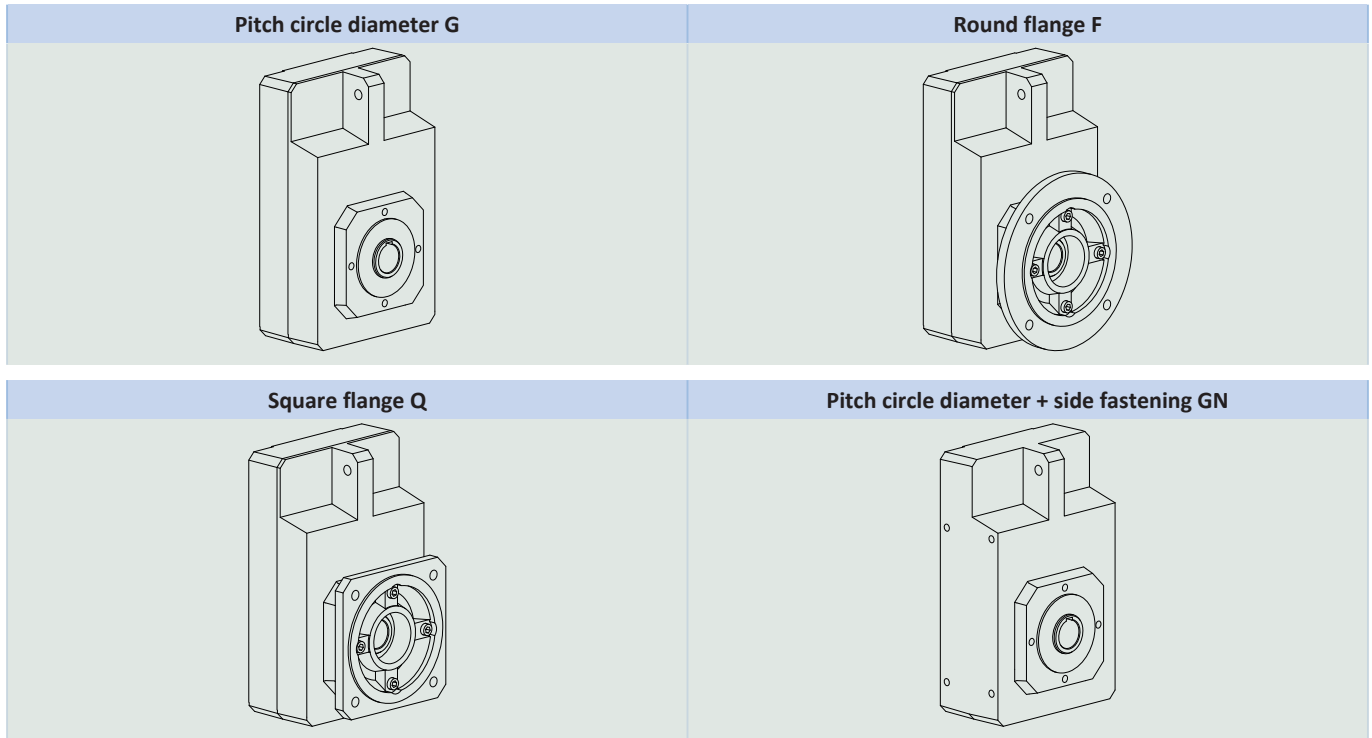


Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

8.5.2 Housing design



	G	F	Q	GN
F1	✓	✓	✓	✓
F2	✓	✓	✓	✓
F3	✓	✓	✓	✓
F4	✓	✓	✓	✓
F6	✓	✓	✓	✓

8.5.3 Combinatorial shaft/housing design

Shaft design	Housing design				
	Code	G	F	Q	GN
Hollow shaft with keyway	A	AG	AF	AQ	AGN
Hollow shaft with shrink ring	S	SG	SF	SQ	SGN
Solid shaft	V	–	VF	VQ	–

8.5.4 Installation conditions

Hollow shaft

The hollow shaft hole tolerance is ISO H7. The tolerance of the machine shaft must be ISO k6.

Take care to align the machine shaft with the gearbox hollow shaft when attaching the gearbox.

Maximum deviation ≤ 0.03 mm.

For simpler assembly and disassembly of the machine shaft, the hollow shafts are equipped with a spiral groove (as a grease deposit).

A hardened, threaded keeper plate is included in the scope of delivery. You also have the option to order the hollow shaft without a keeper plate.

Hollow shaft with shrink ring

The tolerance of the hollow shaft hole is ISO H7.

The machine shaft must be ISO h9.

Select a material for the machine shaft with a permitted surface pressure of $p \geq 325$ N/mm².

Possible materials:

- C45E +QT
- 42CrMo4

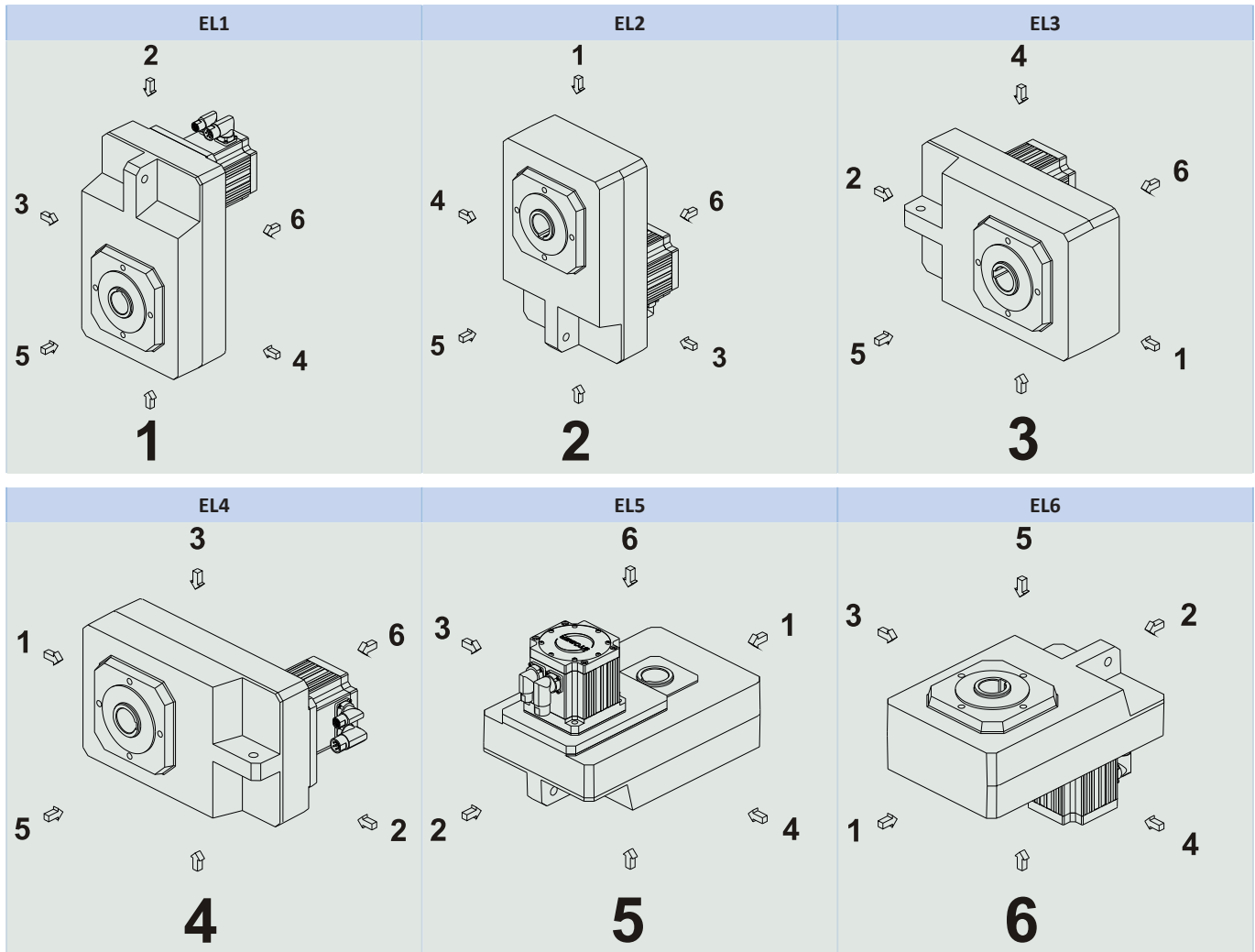
Fastening the gearboxes on the machine side using the pitch circle diameter

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 10.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

8.5.5 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

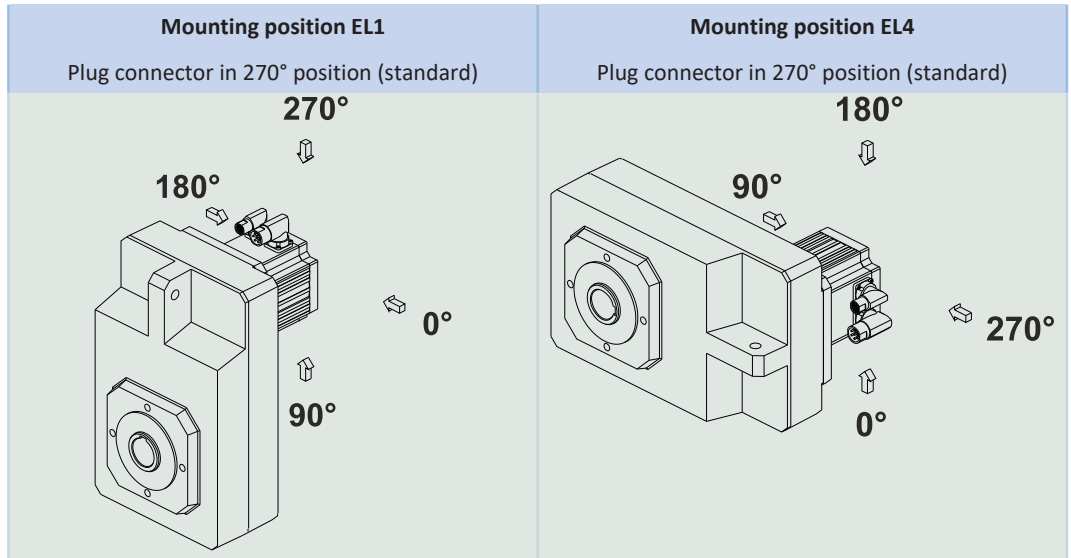
8.5.6 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

8.5.7 Position of the plug connectors



Indicate variations for your geared motor in the order.

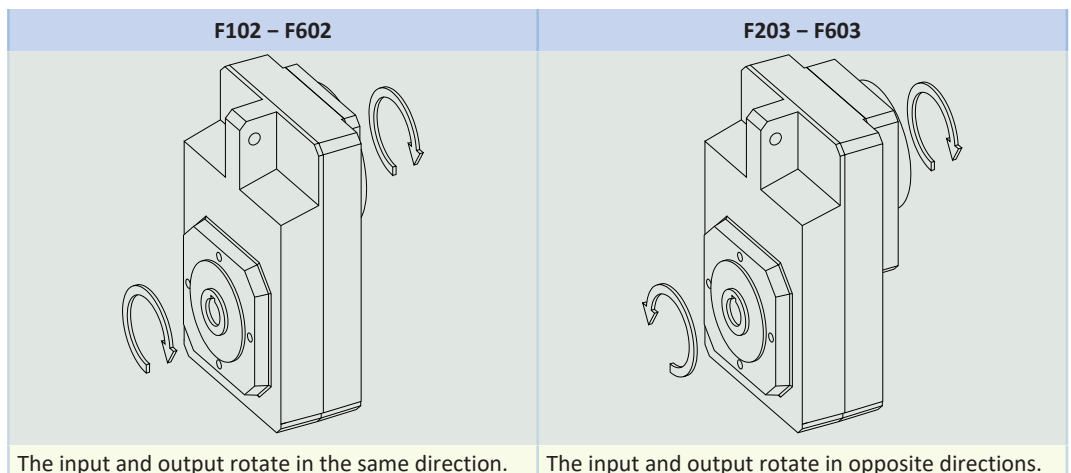
Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

8.5.8 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 80 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	97%
η_{get} three-stage	96%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

8.5.9 Direction of rotation

Solid shaft (V), hollow shaft with keyway (A), hollow shaft with shrink ring (S)



The pictures show mounting position EL1.

¹Observe the protection class of all the components.

8.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

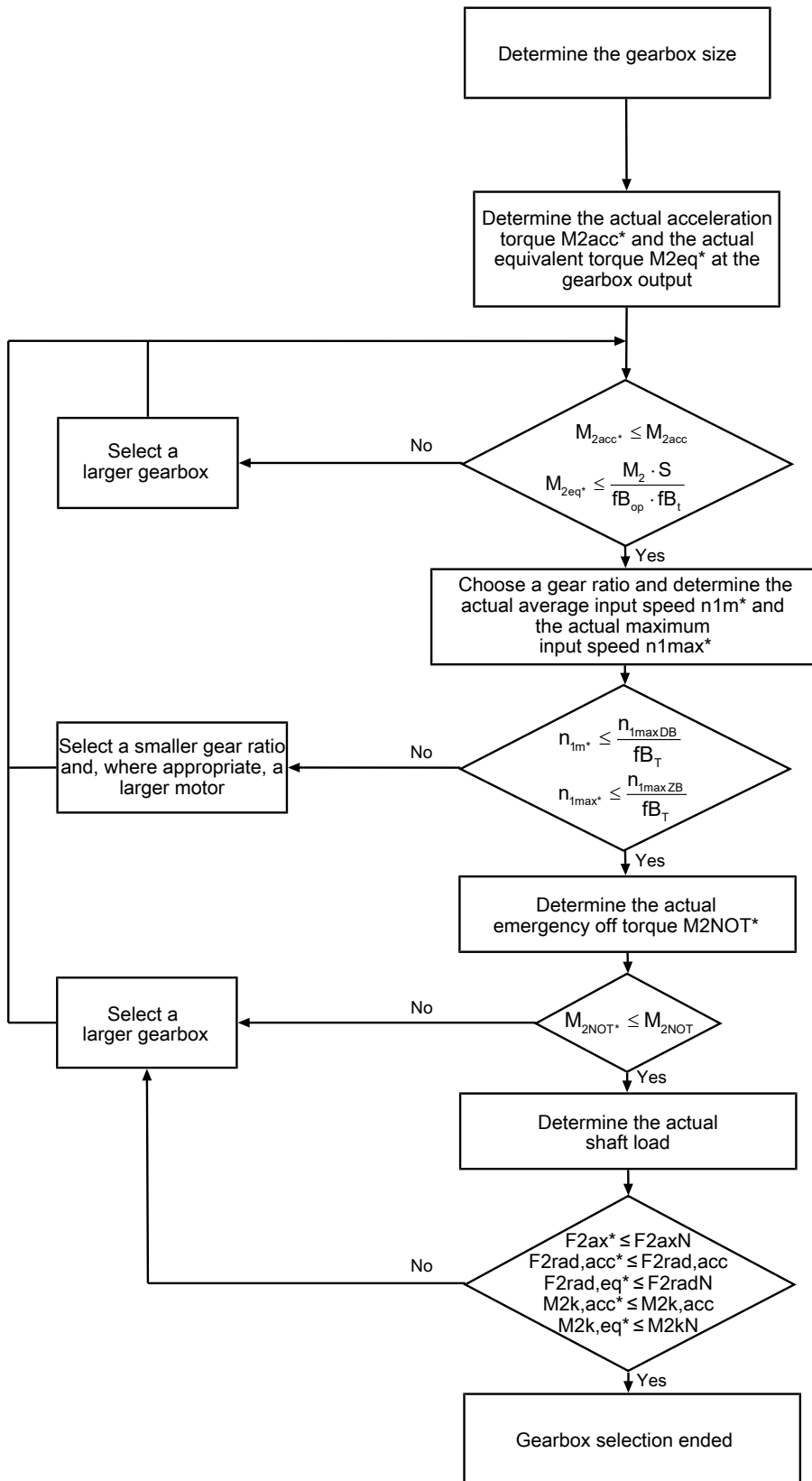
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

8.6.1 Drive selection

Drive selection for gearboxes

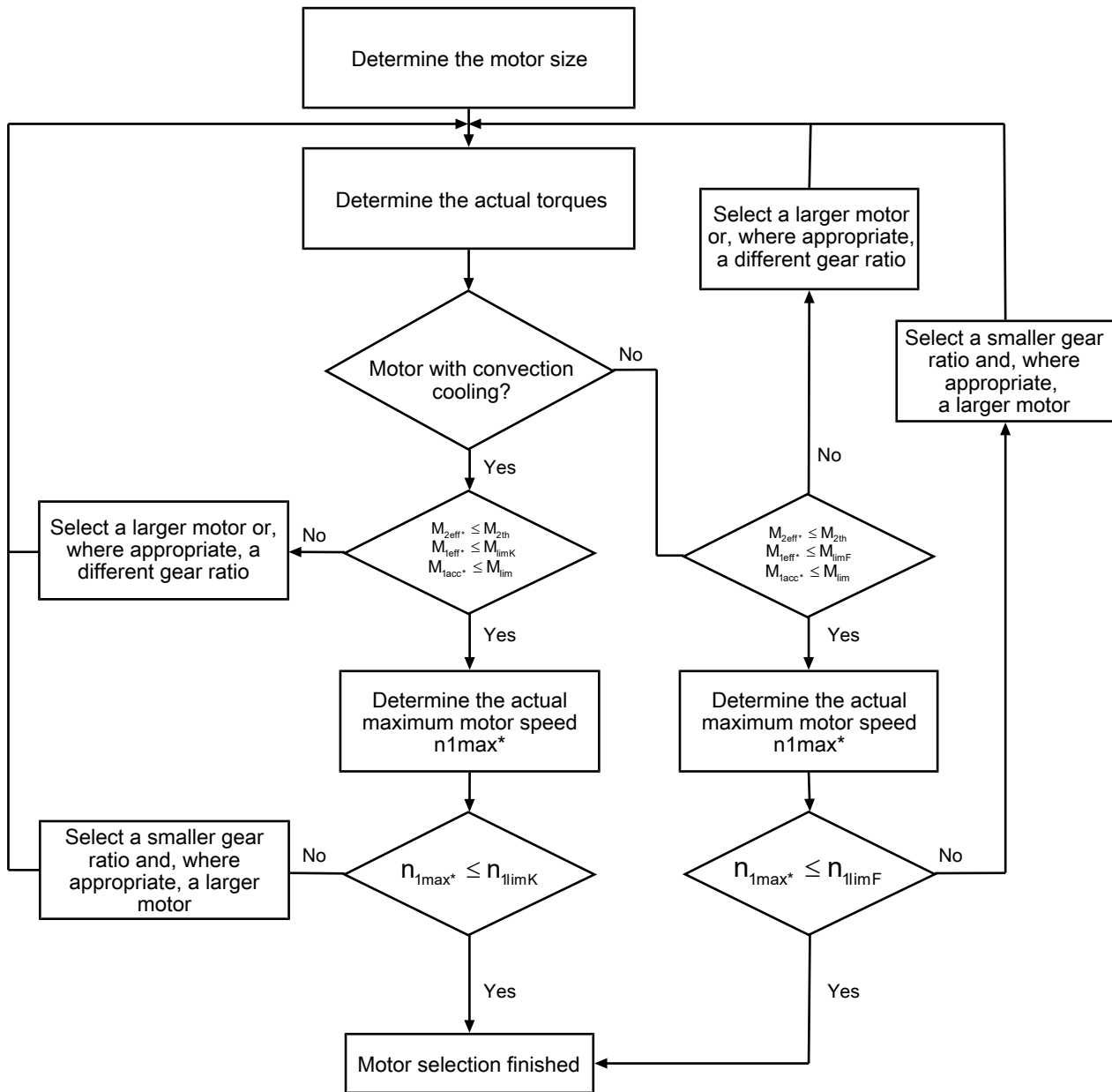


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for fb_T , fb_{op} and fb_t can be found in the corresponding tables in this chapter.

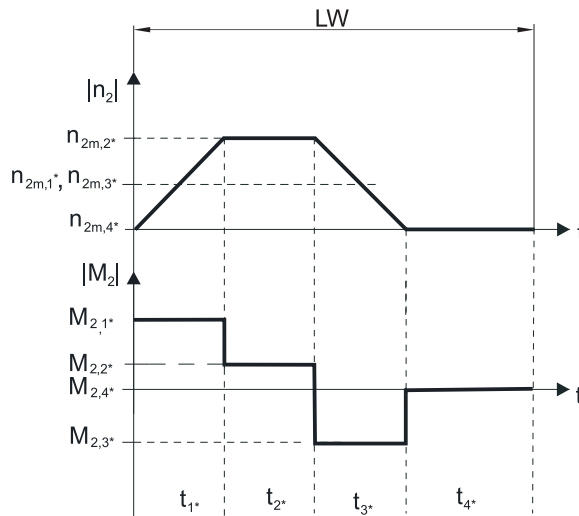
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

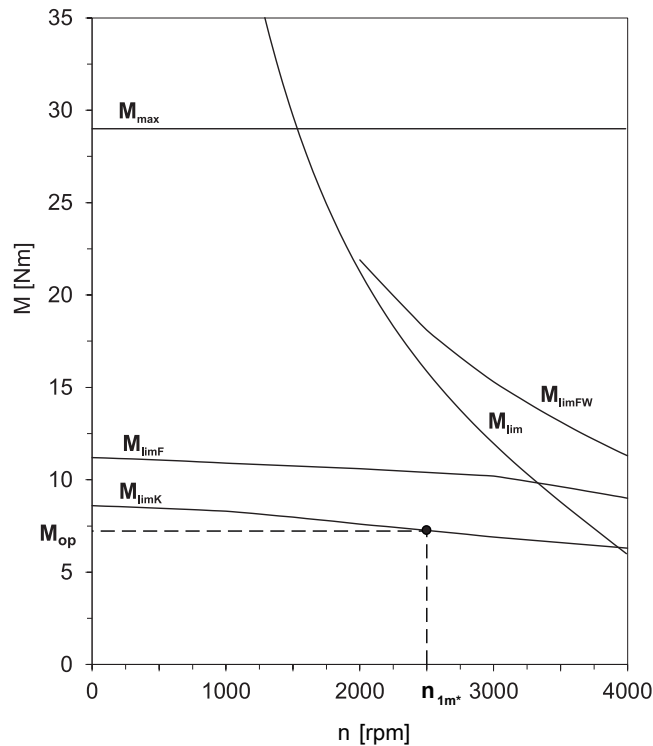
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot athEL \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2, 5, 6	1.0
EL3, 4	1.1

Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40

Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20

Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

8.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 20$ rpm ($F_{2axN} = F_{2ax20}$; $F_{2radN} = F_{2rad20}$; $M_{2kN} = M_{2k20}$)
- Only if radial forces on the gearbox are stabilized by its pilots for the pitch circle diameter and flange housing design

8.6.2.1 V shaft design

Permitted shaft loads for V shaft design (solid shaft)

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
F1	35.0	1100	4200	4200	260	260
F2	41.0	1400	5400	5400	400	400
F3	43.0	1900	7500	7500	600	600
F4	44.0	2350	9250	9250	800	800
F6	44.0	3100	12500	12500	1200	1200

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 20$ rpm:

$$F_{2axN} = \frac{F_{2ax20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

The values for F_{2ax20} , F_{2rad20} and M_{2k20} can be found in the table "Permitted shaft loads" in this chapter.

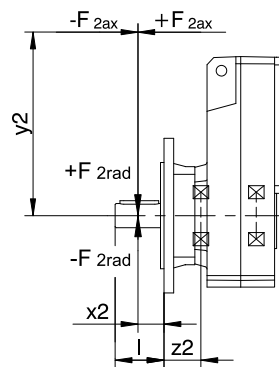


Fig. 1: Force application points for solid shaft

The specified values for F_{2rad20} and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1^*} \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*} \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*} \cdot t_{1^*} + \dots + |n_{2m,n^*} \cdot t_{n^*}|}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1^*} \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*} \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*} \cdot t_{1^*} + \dots + |n_{2m,n^*} \cdot t_{n^*}|}}$$

8.6.2.2 A and S shaft design

Permitted shaft loads for A shaft design (hollow shaft with keyway)

Type	z ₂ [mm]	F _{2ax20} [N]	F _{2rad20} [N]	F _{2rad,acc} [N]	M _{2k20} [Nm]	M _{2k,acc} [Nm]
F1	30.0	900	4200	4200	175	175
F2	33.0	1200	5400	5400	250	250
F3	33.0	1350	7500	7500	375	375
F4	39.0	1900	9250	9250	550	550
F6	45.0	2200	12500	12500	800	800

Permitted shaft loads for S shaft design (hollow shaft with shrink ring)

Type	z ₂ [mm]	F _{2ax20} [N]	F _{2rad20} [N]	F _{2rad,acc} [N]	M _{2k20} [Nm]	M _{2k,acc} [Nm]
F1	30.0	900	4200	4200	175	175
F2	33.0	1200	5400	5400	250	250
F3	33.0	1350	7500	7500	375	375
F4	39.0	1900	9250	9250	550	550
F6	45.0	2200	12500	12500	800	800

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds n_{2m*} > 20 rpm:

$$F_{2axN} = \frac{F_{2ax20}}{\sqrt[3]{\frac{n_{2m*}}{20 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad20}}{\sqrt[3]{\frac{n_{2m*}}{20 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k20}}{\sqrt[3]{\frac{n_{2m*}}{20 \text{ rpm}}}}$$

The values for F_{2ax20}, F_{2rad20} and M_{2k20} can be found in the table "Permitted shaft loads" in this chapter.

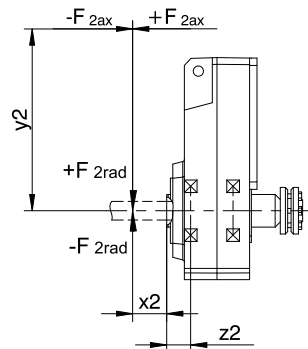


Fig. 2: Force application points for hollow shaft

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and M_{2k,acc}. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end (x₂ = 0).

$$M_{2k,acc*} = \frac{2 \cdot F_{2ax*} \cdot y_2 + F_{2rad,acc*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20}, F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |M_{2k,acc,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |M_{2k,acc,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

$$F_{2rad,eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |F_{2rad,acc,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |F_{2rad,acc,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

8.6.3 Radial shaft seal rings

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

8.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

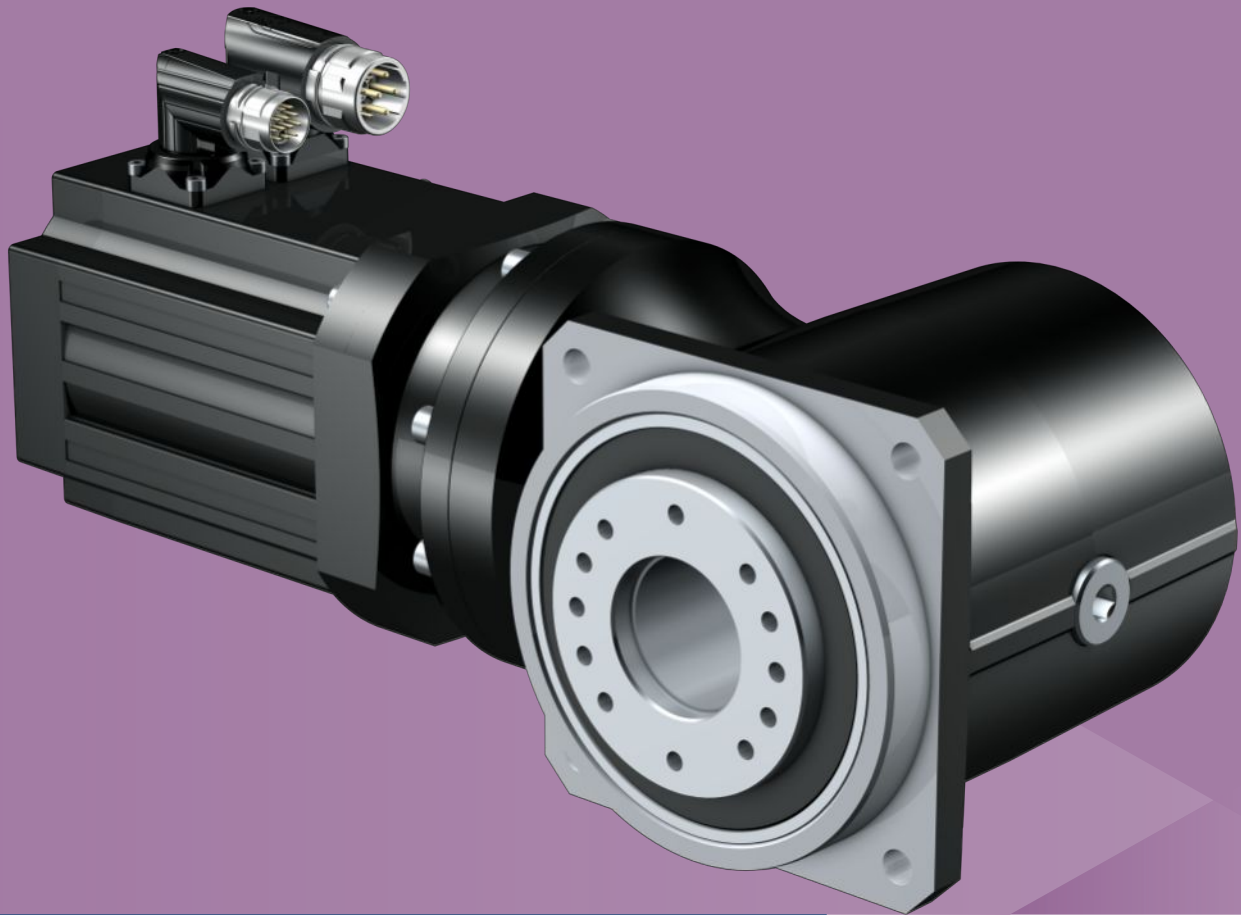
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors F	443366_en

9 KS right-angle servo geared motors

Table of contents

9.1	Overview	234
9.2	Selection tables	235
9.3	Dimensional drawings	243
9.3.1	F shaft design (flange hollow shaft)	244
9.3.2	S shaft design (hollow shaft with shrink disk)	246
9.3.3	G shaft design (solid shaft without feather key)	249
9.3.4	P shaft design (solid shaft with feather key)	251
9.4	Type designation	253
9.5	Product description	253
9.5.1	Input options	253
9.5.2	Installation conditions	254
9.5.3	Mounting positions	254
9.5.4	Lubricants	255
9.5.5	Position of the plug connectors	255
9.5.6	Other product features	255
9.5.7	Direction of rotation	255
9.6	Project configuration	256
9.6.1	Drive selection	257
9.6.2	Permitted shaft loads for the output shaft	261
9.6.3	Recommendation for radial shaft seal rings	264
9.7	Additional documentation	264



9

Right-angle servo geared motors

KS

9.1 Overview

Precision right-angle servo geared motors

Features

Power density	★★★★☆
Backlash	★★★★☆
Price category	€€€
Shaft load	★★★★★
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
FKM seal ring at the input	✓
Stiff output bearings due to pretension	✓
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	2 – 100
M_{2acc}	9.7 – 400 Nm
$\Delta\phi_2$	3 – 7 arcmin
η_{get}	93 – 97 %

9.2 Selection tables

The technical data specified in the selection tables applies to:

- Hollow shaft design with shrink ring (S)
- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B) as well as all other technical data, refer to

<https://configurator.stoeber.de/en-US/>

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
KS3 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 45 \text{ Nm}$)															
1500	4.0	4.2	56	4.5	KS311_0020 MF EZ303U	14	40	2.000	2/1	3200	6000	1.5	6.0	2.3	6.5
1500	5.4	5.8	76	3.4	KS311_0020 MF EZ401U	16	40	2.000	2/1	3200	6000	2.0	6.0	2.3	7.9
1500	9.1	10	128	2.0	KS311_0020 MF EZ402U	31	40	2.000	2/1	3200	6000	2.7	6.0	2.3	9.0
1500	13	17	187	1.4	KS311_0020 MF EZ404U	32	40	2.000	2/1	3200	6000	4.1	6.0	2.3	11
750	6.2	6.5	86	3.0	KS311_0040 MF EZ302U	19	64	4.000	4/1	4000	6000	0.96	6.0	3.0	6.0
750	8.0	8.5	112	2.3	KS311_0040 MF EZ303U	27	64	4.000	4/1	4000	6000	1.1	6.0	3.0	6.5
750	11	12	152	1.7	KS311_0040 MF EZ401U	32	64	4.000	4/1	4000	6000	1.6	6.0	3.0	7.9
750	18	20	255	1.0	KS311_0040 MF EZ402U	32	64	4.000	4/1	4000	6000	2.3	6.0	3.0	9.0
3000	2.9	3.3	51	5.0	KS311_0020 MF EZ302U	9.7	40	2.000	2/1	3200	6000	1.4	6.0	2.3	6.0
3000	3.8	4.4	67	3.8	KS311_0020 MF EZ303U	14	40	2.000	2/1	3200	6000	1.5	6.0	2.3	6.5
3000	4.5	5.4	79	3.2	KS311_0020 MF EZ401U	16	40	2.000	2/1	3200	6000	2.0	6.0	2.3	7.9
3000	6.8	9.5	120	2.1	KS311_0020 MF EZ402U	31	40	2.000	2/1	3200	6000	2.7	6.0	2.3	9.0
3000	11	16	198	1.3	KS311_0020 MF EZ404U	32	40	2.000	2/1	3200	6000	4.1	6.0	2.3	11
1500	3.5	3.7	61	4.2	KS311_0040 MF EZ301U	11	64	4.000	4/1	4000	6000	0.86	6.0	3.0	5.4
1500	5.8	6.5	103	2.5	KS311_0040 MF EZ302U	19	64	4.000	4/1	4000	6000	0.96	6.0	3.0	6.0
1500	7.6	8.7	134	1.9	KS311_0040 MF EZ303U	27	64	4.000	4/1	4000	6000	1.1	6.0	3.0	6.5
1500	8.9	11	157	1.6	KS311_0040 MF EZ401U	32	64	4.000	4/1	4000	6000	1.6	6.0	3.0	7.9
1500	14	19	239	1.1	KS311_0040 MF EZ402U	32	64	4.000	4/1	4000	6000	2.3	6.0	3.0	9.0
KS3 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 45 \text{ Nm}$)															
1500	9.1	10	72	4.4	KS411_0020 MF EZ402U	31	100	2.000	2/1	2500	5000	5.4	5.0	5.2	13
1500	13	17	105	3.0	KS411_0020 MF EZ404U	56	100	2.000	2/1	2500	5000	6.7	5.0	5.2	15
1500	8.3	9.1	65	4.8	KS411_0020 MF EZ501U	31	100	2.000	2/1	2500	5000	6.6	5.0	5.2	13
1500	14	16	113	2.8	KS411_0020 MF EZ502U	60	100	2.000	2/1	2500	5000	8.9	5.0	5.2	14
1500	19	22	148	2.1	KS411_0020 MF EZ503U	80	100	2.000	2/1	2500	5000	11	5.0	5.2	16
1500	26	31	206	1.5	KS411_0020 MF EZ505U	80	100	2.000	2/1	2500	5000	16	5.0	5.2	19
750	11	12	85	3.7	KS411_0040 MF EZ401U	33	130	4.000	4/1	3500	6000	2.9	5.0	7.2	12
750	18	20	143	2.2	KS411_0040 MF EZ402U	62	130	4.000	4/1	3500	6000	3.6	5.0	7.2	13
750	27	33	210	1.5	KS411_0040 MF EZ404U	65	130	4.000	4/1	3500	6000	5.0	5.0	7.2	15
750	17	18	131	2.4	KS411_0040 MF EZ501U	62	130	4.000	4/1	3500	6000	4.9	5.0	7.2	13
750	29	31	225	1.4	KS411_0040 MF EZ502U	65	130	4.000	4/1	3500	6000	7.2	5.0	7.2	14
750	38	43	296	1.1	KS411_0040 MF EZ503U	65	130	4.000	4/1	3500	6000	9.6	5.0	7.2	16
1500	8.9	11	88	3.5	KS411_0040 MF EZ401U	33	130	4.000	4/1	3500	6000	2.9	5.0	7.2	12
1500	14	19	134	2.3	KS411_0040 MF EZ402U	62	130	4.000	4/1	3500	6000	3.6	5.0	7.2	13
1500	23	33	223	1.4	KS411_0040 MF EZ404U	65	130	4.000	4/1	3500	6000	5.0	5.0	7.2	15
1500	13	17	130	2.4	KS411_0040 MF EZ501U	62	130	4.000	4/1	3500	6000	4.9	5.0	7.2	13
1500	20	30	200	1.6	KS411_0040 MF EZ502U	65	130	4.000	4/1	3500	6000	7.2	5.0	7.2	14
1500	24	41	238	1.3	KS411_0040 MF EZ503U	65	130	4.000	4/1	3500	6000	9.6	5.0	7.2	16
1500	19	22	87	4.2	KS511_0020 MF EZ503U	83	225	2.000	2/1	2000	4600	19	4.0	21	22
1500	26	31	121	3.0	KS511_0020 MF EZ505U	130	225	2.000	2/1	2000	4600	24	4.0	21	25
1500	23	28	108	3.4	KS511_0020 MF EZ702U	80	225	2.000	2/1	2000	4600	25	4.0	21	25
1500	32	40	148	2.5	KS511_0020 MF EZ703U	126	225	2.000	2/1	2000	4600	33	4.0	21	27
1500	41	59	191	1.9	KS511_0020 MF EZ705U	180	225	2.000	2/1	2000	4600	45	4.0	21	32
750	17	18	77	4.8	KS511_0040 MF EZ501U	62	280	4.000	4/1	2500	6000	9.5	4.0	19	19
750	29	31	133	2.8	KS511_0040 MF EZ502U	120	280	4.000	4/1	2500	6000	12	4.0	19	20
750	38	43	174	2.1	KS511_0040 MF EZ503U	140	280	4.000	4/1	2500	6000	14	4.0	19	22
750	52	62	243	1.5	KS511_0040 MF EZ505U	140	280	4.000	4/1	2500	6000	19	4.0	19	25
750	29	32	133	2.8	KS511_0040 MF EZ701U	78	280	4.000	4/1	2500	6000	15	4.0	19	22
750	47	56	216	1.7	KS511_0040 MF EZ702U	140	280	4.000	4/1	2500	6000	20	4.0	19	25
750	64	81	296	1.2	KS511_0040 MF EZ703U	140	280	4.000	4/1	2500	6000	28	4.0	19	27
2250	18	30	98	3.8	KS511_0020 MF EZ505U	130	225	2.000	2/1	2000	4600	24	4.0	21	25

n_2 [rpm]	M_2 [Nm]	$M_{2.0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]	
KS4 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 90 \text{ Nm}$)																
300	45	49	7.8	1.2	KS412_0100 EZ402U	90	140	10.00	10/1	4500	6000	1.8	6.0	7.3	13	
250	11	11	5.7	4.9	KS412_0120 EZ301U	32	140	12.00	12/1	4000	6000	0.51	6.0	10	9.1	
250	18	19	9.8	2.8	KS412_0120 EZ302U	57	140	12.00	12/1	4000	6000	0.61	6.0	10	9.7	
250	24	25	13	2.2	KS412_0120 EZ303U	65	140	12.00	12/1	4000	6000	0.72	6.0	10	10	
250	32	34	17	1.6	KS412_0120 EZ401U	65	140	12.00	12/1	4000	6000	1.2	6.0	10	12	
214	12	13	1.0	4.2	KS412_0140 EZ301U	37	140	14.00	14/1	4500	6000	0.28	6.0	7.1	9.1	
214	21	22	1.8	2.4	KS412_0140 EZ302U	67	140	14.00	14/1	4500	6000	0.38	6.0	7.1	9.7	
214	28	29	2.3	1.9	KS412_0140 EZ303U	90	140	14.00	14/1	4500	6000	0.49	6.0	7.1	10	
214	37	40	3.1	1.4	KS412_0140 EZ401U	90	140	14.00	14/1	4500	6000	1.0	6.0	7.1	12	
188	14	14	4.0	3.7	KS412_0160 EZ301U	43	140	16.00	16/1	4000	6000	0.35	6.0	10	9.1	
188	24	26	6.9	2.1	KS412_0160 EZ302U	65	140	16.00	16/1	4000	6000	0.45	6.0	10	9.7	
188	31	33	9.0	1.6	KS412_0160 EZ303U	65	140	16.00	16/1	4000	6000	0.56	6.0	10	10	
188	43	46	12	1.2	KS412_0160 EZ401U	65	140	16.00	16/1	4000	6000	1.1	6.0	10	12	
150	18	18	0.7	2.9	KS412_0200 EZ301U	53	140	20.00	20/1	5000	6000	0.23	6.0	7.0	9.1	
150	30	32	1.2	1.7	KS412_0200 EZ302U	90	140	20.00	20/1	5000	6000	0.33	6.0	7.0	9.7	
150	39	42	1.5	1.3	KS412_0200 EZ303U	90	140	20.00	20/1	5000	6000	0.44	6.0	7.0	10	
107	25	25	2.1	2.1	KS412_0280 EZ301U	65	140	28.00	28/1	4500	6000	0.24	6.0	9.6	9.1	
107	42	45	3.5	1.2	KS412_0280 EZ302U	65	140	28.00	28/1	4500	6000	0.34	6.0	9.6	9.7	
75	35	36	1.3	1.5	KS412_0400 EZ301U	65	140	40.00	40/1	5000	6000	0.22	6.0	9.5	9.1	
94	28	28	0.3	2.2	KS413_0320 EZ301U	83	140	32.00	32/1	4000	6000	0.24	6.0	7.4	9.6	
94	47	50	0.6	1.3	KS413_0320 EZ302U	90	140	32.00	32/1	4000	6000	0.34	6.0	7.4	10	
60	43	44	0.2	1.4	KS413_0500 EZ301U	90	140	50.00	50/1	4500	6000	0.22	6.0	7.3	9.6	
1000	8.6	9.6	6.3	4.4	KS412_0060 EZ302U	29	140	6.000	6/1	3500	6000	0.80	6.0	7.5	9.7	
1000	11	13	8.2	3.4	KS412_0060 EZ303U	40	140	6.000	6/1	3500	6000	0.91	6.0	7.5	10	
1000	13	16	9.6	2.9	KS412_0060 EZ401U	48	140	6.000	6/1	3500	6000	1.4	6.0	7.5	12	
1000	20	28	15	1.9	KS412_0060 EZ402U	90	140	6.000	6/1	3500	6000	2.1	6.0	7.5	13	
750	11	13	4.1	3.6	KS412_0080 EZ302U	38	140	8.000	8/1	4000	6000	0.56	6.0	7.4	9.7	
750	15	17	5.4	2.7	KS412_0080 EZ303U	53	140	8.000	8/1	4000	6000	0.67	6.0	7.4	10	
750	17	21	6.3	2.3	KS412_0080 EZ401U	65	140	8.000	8/1	4000	6000	1.2	6.0	7.4	12	
750	27	37	9.6	1.5	KS412_0080 EZ402U	90	140	8.000	8/1	4000	6000	1.9	6.0	7.4	13	
600	8.5	9.0	1.9	4.8	KS412_0100 EZ301U	27	140	10.00	10/1	4500	6000	0.36	6.0	7.3	9.1	
600	14	16	3.1	2.9	KS412_0100 EZ302U	48	140	10.00	10/1	4500	6000	0.46	6.0	7.3	9.7	
600	19	21	4.1	2.2	KS412_0100 EZ303U	67	140	10.00	10/1	4500	6000	0.57	6.0	7.3	10	
600	22	27	4.8	1.9	KS412_0100 EZ401U	81	140	10.00	10/1	4500	6000	1.1	6.0	7.3	12	
600	33	47	7.3	1.2	KS412_0100 EZ402U	90	140	10.00	10/1	4500	6000	1.8	6.0	7.3	13	
KS5 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 200 \text{ Nm}$)																
500	10	11	6.9	4.0	KS412_0120 EZ301U	32	140	12.00	12/1	4000	6000	0.51	6.0	10	9.1	
500	17	19	12	2.4	KS412_0120 EZ302U	57	140	12.00	12/1	4000	6000	0.61	6.0	10	9.7	
500	22	26	15	1.8	KS412_0120 EZ303U	65	140	12.00	12/1	4000	6000	0.72	6.0	10	10	
500	26	32	18	1.6	KS412_0120 EZ401U	65	140	12.00	12/1	4000	6000	1.2	6.0	10	12	
500	40	56	27	1.0	KS412_0120 EZ402U	65	140	12.00	12/1	4000	6000	1.9	6.0	10	13	
429	12	13	1.2	3.5	KS412_0140 EZ301U	37	140	14.00	14/1	4500	6000	0.28	6.0	7.1	9.1	
429	20	22	2.1	2.1	KS412_0140 EZ302U	67	140	14.00	14/1	4500	6000	0.38	6.0	7.1	9.7	
429	26	30	2.7	1.6	KS412_0140 EZ303U	90	140	14.00	14/1	4500	6000	0.49	6.0	7.1	10	
429	31	37	3.2	1.3	KS412_0140 EZ401U	90	140	14.00	14/1	4500	6000	1.0	6.0	7.1	12	
375	14	14	4.9	3.0	KS412_0160 EZ301U	43	140	16.00	16/1	4000	6000	0.35	6.0	10	9.1	
375	23	26	8.2	1.8	KS412_0160 EZ302U	65	140	16.00	16/1	4000	6000	0.45	6.0	10	9.7	
375	30	34	11	1.4	KS412_0160 EZ303U	65	140	16.00	16/1	4000	6000	0.56	6.0	10	10	
375	35	43	13	1.2	KS412_0160 EZ401U	65	140	16.00	16/1	4000	6000	1.1	6.0	10	12	
300	17	18	0.8	2.4	KS412_0200 EZ301U	53	140	20.00	20/1	5000	6000	0.23	6.0	7.0	9.1	
300	29	32	1.4	1.4	KS412_0200 EZ302U	90	140	20.00	20/1	5000	6000	0.33	6.0	7.0	9.7	
300	37	43	1.8	1.1	KS412_0200 EZ303U	90	140	20.00	20/1	5000	6000	0.44	6.0	7.0	10	
214	24	25	2.5	1.7	KS412_0280 EZ301U	65	140	28.00	28/1	4500	6000	0.24	6.0	9.6	9.1	
214	40	45	4.2	1.0	KS412_0280 EZ302U	65	140	28.00	28/1	4500	6000	0.34	6.0	9.6	9.7	
150	34	36	1.6	1.2	KS412_0400 EZ301U	65	140	40.00	40/1	5000	6000	0.22	6.0	9.5	9.1	
188	12	13	0.2	4.0	KS413_0320 EZ202U	44	140	32.00	32/1	4000	6000	0.18	6.0	7.4	9.6	
188	18	21	0.3	2.6	KS413_0320 EZ203U	80	140	32.00	32/1	4000	6000	0.22	6.0	7.4	9.8	
188	26	28	0.4	1.8	KS413_0320 EZ301U	83	140	32.00	32/1	4000	6000	0.24	6.0	7.4	9.6	
188	45	50	0.7	1.1	KS413_0320 EZ302U	90	140	32.00	32/1	4000	6000	0.34	6.0	7.4	10	
120	19	20	0.1	2.5	KS413_0500 EZ202U	69	140	50.00	50/1	4500	6000	0.15	6.0	7.3	9.6	
120	28	32	0.2	1.7	KS413_0500 EZ203U	90	140	50.00	50/1	4500	6000	0.19	6.0	7.3	9.8	
120	41	44	0.2	1.1	KS413_0500 EZ301U	90	140	50.00	50/1	4500	6000	0.22	6.0	7.3	9.6	
94	24	26	0.4	1.7	KS413_0640 EZ202U	65	140	64.00	64/1	4000	6000	0.17	6.0	10	9.6	
94	36	41	0.6	1.1	KS413_0640 EZ203U	65	140	64.00	64/1	4000	6000	0.21	6.0	10	9.8	
86	26	29	0.1	1.8	KS413_0700 EZ202U	90	140	70.00	70/1	4500	6000	0.14	6.0	7.3	9.6	

9.2 Selection tables 9 KS right-angle servo geared motors

n ₂ [rpm]	M ₂ [Nm]	M _{2,0} [Nm]	a _{th}	S	Type	M _{2acc} [Nm]	M _{2NOT} [Nm]	i	i _{exakt}	n _{1maxDB} [rpm]	n _{1maxZB} [rpm]	J ₁ [kgcm ²]	Δφ _{2red} [arcmin]	C ₂ [Nm/ arcmin]	m [kg]
KS5 (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 200 Nm)															
86	40	45	0.1	1.2	KS413_0700 EZ203U	90	140	70.00	70/1	4500	6000	0.18	6.0	7.3	9.8
75	30	33	0.1	1.6	KS413_0800 EZ202U	90	140	80.00	80/1	5000	6000	0.13	6.0	9.9	9.6
75	45	51	0.1	1.0	KS413_0800 EZ203U	90	140	80.00	80/1	5000	6000	0.17	6.0	9.9	9.8
60	37	41	-	1.3	KS413_1000 EZ202U	90	140	100.0	100/1	5000	6000	0.13	6.0	7.3	9.6
500	16	17	6.6	5.0	KS512_0060 EZ401U	48	300	6.000	6/1	2500	5500	2.5	5.0	19	18
500	27	30	11	3.0	KS512_0060 EZ402U	91	300	6.000	6/1	2500	5500	3.2	5.0	19	19
500	39	49	16	2.0	KS512_0060 EZ404U	165	300	6.000	6/1	2500	5500	4.5	5.0	19	21
500	25	27	10	3.2	KS512_0060 EZ501U	91	300	6.000	6/1	2500	5500	4.4	5.0	19	19
500	42	46	17	1.9	KS512_0060 EZ502U	177	300	6.000	6/1	2500	5500	6.7	5.0	19	20
500	55	63	23	1.4	KS512_0060 EZ503U	200	300	6.000	6/1	2500	5500	9.1	5.0	19	22
500	77	91	32	1.0	KS512_0060 EZ505U	200	300	6.000	6/1	2500	5500	14	5.0	19	25
375	21	23	3.7	4.7	KS512_0080 EZ401U	65	300	8.000	8/1	3300	6000	1.7	5.0	18	18
375	36	40	6.3	2.8	KS512_0080 EZ402U	122	300	8.000	8/1	3300	6000	2.4	5.0	18	19
375	52	65	9.2	1.9	KS512_0080 EZ404U	200	300	8.000	8/1	3300	6000	3.8	5.0	18	21
375	33	36	5.7	3.0	KS512_0080 EZ501U	122	300	8.000	8/1	3300	6000	3.7	5.0	18	19
375	56	61	9.9	1.8	KS512_0080 EZ502U	200	300	8.000	8/1	3300	6000	6.0	5.0	18	20
375	74	84	13	1.3	KS512_0080 EZ503U	200	300	8.000	8/1	3300	6000	8.4	5.0	18	22
300	27	29	2.9	3.7	KS512_0100 EZ401U	81	300	10.00	10/1	3500	6000	1.4	5.0	17	18
300	45	49	4.8	2.2	KS512_0100 EZ402U	152	300	10.00	10/1	3500	6000	2.1	5.0	17	19
300	66	82	7.0	1.5	KS512_0100 EZ404U	200	300	10.00	10/1	3500	6000	3.5	5.0	17	21
300	41	45	4.4	2.4	KS512_0100 EZ501U	152	300	10.00	10/1	3500	6000	3.4	5.0	17	19
300	70	76	7.6	1.4	KS512_0100 EZ502U	200	300	10.00	10/1	3500	6000	5.7	5.0	17	20
300	92	105	9.9	1.1	KS512_0100 EZ503U	200	300	10.00	10/1	3500	6000	8.1	5.0	17	22
250	32	34	11	3.1	KS512_0120 EZ401U	97	280	12.00	12/1	2500	5500	1.9	5.0	17	18
250	54	59	18	1.9	KS512_0120 EZ402U	140	280	12.00	12/1	2500	5500	2.6	5.0	17	19
250	79	98	26	1.3	KS512_0120 EZ404U	140	280	12.00	12/1	2500	5500	4.0	5.0	17	21
250	49	54	16	2.0	KS512_0120 EZ501U	140	280	12.00	12/1	2500	5500	3.9	5.0	17	19
250	84	91	28	1.2	KS512_0120 EZ502U	140	280	12.00	12/1	2500	5500	6.2	5.0	17	20
214	37	40	1.9	2.7	KS512_0140 EZ401U	113	300	14.00	14/1	3700	6000	1.2	5.0	17	18
214	63	69	3.2	1.6	KS512_0140 EZ402U	200	300	14.00	14/1	3700	6000	1.9	5.0	17	19
214	92	114	4.7	1.1	KS512_0140 EZ404U	200	300	14.00	14/1	3700	6000	3.2	5.0	17	21
214	57	63	2.9	1.7	KS512_0140 EZ501U	200	300	14.00	14/1	3700	6000	3.2	5.0	17	19
214	98	106	5.0	1.0	KS512_0140 EZ502U	200	300	14.00	14/1	3700	6000	5.5	5.0	17	20
KS5 (n_{1N} = 4500 min⁻¹, M_{2acc,max} = 200 Nm)															
188	43	46	7.5	2.3	KS512_0160 EZ401U	129	280	16.00	16/1	3300	6000	1.4	5.0	17	18
188	71	79	13	1.4	KS512_0160 EZ402U	140	280	16.00	16/1	3300	6000	2.1	5.0	17	19
188	65	71	11	1.5	KS512_0160 EZ501U	140	280	16.00	16/1	3300	6000	3.4	5.0	17	19
150	53	57	1.2	1.9	KS512_0200 EZ401U	162	300	20.00	20/1	3700	6000	1.1	5.0	16	18
150	89	99	2.1	1.1	KS512_0200 EZ402U	200	300	20.00	20/1	3700	6000	1.8	5.0	16	19
150	82	89	1.9	1.2	KS512_0200 EZ501U	200	300	20.00	20/1	3700	6000	3.0	5.0	16	19
107	74	80	3.8	1.3	KS512_0280 EZ401U	140	280	28.00	28/1	3700	6000	1.1	5.0	15	18
94	28	28	0.2	4.3	KS513_0320 EZ301U	83	300	32.00	32/1	3500	6000	0.34	5.0	18	16
KS5 (n_{1N} = 6000 min⁻¹, M_{2acc,max} = 200 Nm)															
94	47	50	0.3	2.5	KS513_0320 EZ302U	149	300	32.00	32/1	3500	6000	0.44	5.0	18	17
94	62	65	0.4	1.9	KS513_0320 EZ303U	200	300	32.00	32/1	3500	6000	0.55	5.0	18	17
94	83	89	0.6	1.4	KS513_0320 EZ401U	200	300	32.00	32/1	3500	6000	1.1	5.0	18	19
60	43	44	0.1	2.8	KS513_0500 EZ301U	130	300	50.00	50/1	3500	6000	0.27	5.0	17	16
60	74	78	0.2	1.6	KS513_0500 EZ302U	200	300	50.00	50/1	3500	6000	0.37	5.0	17	17
60	96	102	0.3	1.2	KS513_0500 EZ303U	200	300	50.00	50/1	3500	6000	0.48	5.0	17	17
47	55	57	0.5	1.8	KS513_0640 EZ301U	140	280	64.00	64/1	3300	6000	0.32	5.0	17	16
47	95	100	0.8	1.0	KS513_0640 EZ302U	140	280	64.00	64/1	3300	6000	0.42	5.0	17	17
43	61	62	0.1	2.0	KS513_0700 EZ301U	182	300	70.00	70/1	4200	6000	0.23	5.0	17	16
43	104	109	0.1	1.2	KS513_0700 EZ302U	200	300	70.00	70/1	4200	6000	0.33	5.0	17	17
38	69	71	0.1	1.7	KS513_0800 EZ301U	200	300	80.00	80/1	4200	6000	0.21	5.0	18	16
38	118	125	0.1	1.0	KS513_0800 EZ302U	200	300	80.00	80/1	4200	6000	0.31	5.0	18	17
30	86	88	-	1.4	KS513_1000 EZ301U	200	300	100.0	100/1	4200	6000	0.21	5.0	17	16
750	54	87	26	1.3	KS512_0060 EZ505U	200	300	6.000	6/1	2500	5500	14	5.0	19	25
563	72	116	15	1.2	KS512_0080 EZ505U	200	300	8.000	8/1	3300	6000	13	5.0	18	25
750	17	21	3.9	4.5	KS512_0080 EZ401U	65	300	8.000	8/1	3300	6000	1.7	5.0	18	18
750	27	37	5.9	3.0	KS512_0080 EZ402U	122	300	8.000	8/1	3300	6000	2.4	5.0	18	19
750	44	64	9.7	1.8	KS512_0080 EZ404U	200	300	8.000	8/1	3300	6000	3.8	5.0	18	21
750	26	33	5.7	3.0	KS512_0080 EZ501U	122	300	8.000	8/1	3300	6000	3.7	5.0	18	19
750	40	59	8.7	2.0	KS512_0080 EZ502U	200	300	8.000	8/1	3300	6000	6.0	5.0	18	20
750	47	81	10	1.7	KS512_0080 EZ503U	200	300	8.000	8/1	3300	6000	8.4	5.0	18	22
600	22	27	3.0	3.6	KS512_0100 EZ401U	81	300	10.00	10/1	3500	6000	1.4	5.0	17	18

n_2 [rpm]	M_2 [Nm]	$M_{2.0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\varphi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
KS5 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 200 \text{ Nm}$)															
600	33	47	4.5	2.4	KS512_0100 EZ402U	152	300	10.00	10/1	3500	6000	2.1	5.0	17	19
600	55	80	7.5	1.4	KS512_0100 EZ404U	200	300	10.00	10/1	3500	6000	3.5	5.0	17	21
600	32	42	4.4	2.4	KS512_0100 EZ501U	152	300	10.00	10/1	3500	6000	3.4	5.0	17	19
600	49	74	6.7	1.6	KS512_0100 EZ502U	200	300	10.00	10/1	3500	6000	5.7	5.0	17	20
600	59	101	8.0	1.3	KS512_0100 EZ503U	200	300	10.00	10/1	3500	6000	8.1	5.0	17	22
429	31	37	2.0	2.6	KS512_0140 EZ401U	113	300	14.00	14/1	3700	6000	1.2	5.0	17	18
429	47	65	3.0	1.7	KS512_0140 EZ402U	200	300	14.00	14/1	3700	6000	1.9	5.0	17	19
429	77	112	5.0	1.0	KS512_0140 EZ404U	200	300	14.00	14/1	3700	6000	3.2	5.0	17	21
429	45	59	2.9	1.7	KS512_0140 EZ501U	200	300	14.00	14/1	3700	6000	3.2	5.0	17	19
429	69	104	4.5	1.1	KS512_0140 EZ502U	200	300	14.00	14/1	3700	6000	5.5	5.0	17	20
375	35	43	7.7	2.3	KS512_0160 EZ401U	129	280	16.00	16/1	3300	6000	1.4	5.0	17	18
375	53	74	12	1.5	KS512_0160 EZ402U	140	280	16.00	16/1	3300	6000	2.1	5.0	17	19
375	52	67	11	1.5	KS512_0160 EZ501U	140	280	16.00	16/1	3300	6000	3.4	5.0	17	19
300	44	53	1.3	1.8	KS512_0200 EZ401U	162	300	20.00	20/1	3700	6000	1.1	5.0	16	18
300	67	93	2.0	1.2	KS512_0200 EZ402U	200	300	20.00	20/1	3700	6000	1.8	5.0	16	19
300	65	84	1.9	1.2	KS512_0200 EZ501U	200	300	20.00	20/1	3700	6000	3.0	5.0	16	19
214	61	74	3.9	1.3	KS512_0280 EZ401U	140	280	28.00	28/1	3700	6000	1.1	5.0	15	18
188	26	28	0.2	3.6	KS513_0320 EZ301U	83	300	32.00	32/1	3500	6000	0.34	5.0	18	16
KS7 ($n_{1N} = 2000 \text{ min}^{-1}$, $M_{2acc,max} = 320 \text{ Nm}$)															
188	45	50	0.4	2.1	KS513_0320 EZ302U	149	300	32.00	32/1	3500	6000	0.44	5.0	18	17
188	58	67	0.5	1.6	KS513_0320 EZ303U	200	300	32.00	32/1	3500	6000	0.55	5.0	18	17
188	68	83	0.6	1.4	KS513_0320 EZ401U	200	300	32.00	32/1	3500	6000	1.1	5.0	18	19
KS7 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 400 \text{ Nm}$)															
120	41	44	0.1	2.3	KS513_0500 EZ301U	130	300	50.00	50/1	3500	6000	0.27	5.0	17	16
120	70	78	0.2	1.4	KS513_0500 EZ302U	200	300	50.00	50/1	3500	6000	0.37	5.0	17	17
120	91	105	0.3	1.0	KS513_0500 EZ303U	200	300	50.00	50/1	3500	6000	0.48	5.0	17	17
94	53	57	0.6	1.5	KS513_0640 EZ301U	140	280	64.00	64/1	3300	6000	0.32	5.0	17	16
86	58	62	0.1	1.6	KS513_0700 EZ301U	182	300	70.00	70/1	4200	6000	0.23	5.0	17	16
75	66	71	0.1	1.4	KS513_0800 EZ301U	200	300	80.00	80/1	4200	6000	0.21	5.0	18	16
60	83	88	0.1	1.1	KS513_1000 EZ301U	200	300	100.0	100/1	4200	6000	0.21	5.0	17	16
500	42	46	24	3.8	KS712_0060 EZ502U	177	600	6.000	6/1	2200	5000	10	4.0	38	33
500	55	63	32	2.9	KS712_0060 EZ503U	245	600	6.000	6/1	2200	5000	13	4.0	38	34
500	77	91	44	2.1	KS712_0060 EZ505U	382	600	6.000	6/1	2200	5000	17	4.0	38	37
500	42	47	24	3.8	KS712_0060 EZ701U	114	600	6.000	6/1	2200	5000	13	4.0	38	34
500	68	82	39	2.3	KS712_0060 EZ702U	234	600	6.000	6/1	2200	5000	19	4.0	38	37
500	94	119	54	1.7	KS712_0060 EZ703U	371	600	6.000	6/1	2200	5000	27	4.0	38	39
500	121	172	70	1.3	KS712_0060 EZ705U	400	600	6.000	6/1	2200	5000	39	4.0	38	44
375	56	61	14	3.5	KS712_0080 EZ502U	236	600	8.000	8/1	3000	6000	7.8	4.0	38	33
375	74	84	18	2.7	KS712_0080 EZ503U	327	600	8.000	8/1	3000	6000	10	4.0	38	34
375	103	122	25	1.9	KS712_0080 EZ505U	400	600	8.000	8/1	3000	6000	15	4.0	38	37
375	56	63	14	3.5	KS712_0080 EZ701U	152	600	8.000	8/1	3000	6000	11	4.0	38	34
375	91	109	22	2.2	KS712_0080 EZ702U	312	600	8.000	8/1	3000	6000	16	4.0	38	37
375	125	158	31	1.6	KS712_0080 EZ703U	400	600	8.000	8/1	3000	6000	24	4.0	38	39
375	162	230	39	1.2	KS712_0080 EZ705U	400	600	8.000	8/1	3000	6000	37	4.0	38	44
300	41	45	6.1	4.9	KS712_0100 EZ501U	152	600	10.00	10/1	3000	6000	4.6	4.0	38	31
300	70	76	10	2.8	KS712_0100 EZ502U	295	600	10.00	10/1	3000	6000	6.9	4.0	38	33
300	92	105	14	2.2	KS712_0100 EZ503U	400	600	10.00	10/1	3000	6000	9.2	4.0	38	34
300	128	152	19	1.5	KS712_0100 EZ505U	400	600	10.00	10/1	3000	6000	14	4.0	38	37
300	70	79	10	2.8	KS712_0100 EZ701U	190	600	10.00	10/1	3000	6000	10	4.0	38	34
300	114	137	17	1.7	KS712_0100 EZ702U	390	600	10.00	10/1	3000	6000	15	4.0	38	37
300	157	198	23	1.3	KS712_0100 EZ703U	400	600	10.00	10/1	3000	6000	23	4.0	38	39
250	49	54	22	4.0	KS712_0120 EZ501U	182	570	12.00	12/1	2200	5000	5.9	4.0	40	31
250	84	91	39	2.4	KS712_0120 EZ502U	285	570	12.00	12/1	2200	5000	8.2	4.0	40	33
250	111	127	51	1.8	KS712_0120 EZ503U	285	570	12.00	12/1	2200	5000	11	4.0	40	34
250	154	182	71	1.3	KS712_0120 EZ505U	285	570	12.00	12/1	2200	5000	15	4.0	40	37
250	84	95	39	2.4	KS712_0120 EZ701U	228	570	12.00	12/1	2200	5000	11	4.0	40	34
250	137	164	63	1.5	KS712_0120 EZ702U	285	570	12.00	12/1	2200	5000	17	4.0	40	37
250	188	237	86	1.1	KS712_0120 EZ703U	285	570	12.00	12/1	2200	5000	25	4.0	40	39
214	57	63	4.1	3.5	KS712_0140 EZ501U	213	600	14.00	14/1	3200	6000	3.8	4.0	38	31
214	98	106	7.0	2.0	KS712_0140 EZ502U	400	600	14.00	14/1	3200	6000	6.1	4.0	38	33
214	129	148	9.2	1.5	KS712_0140 EZ503U	400	600	14.00	14/1	3200	6000	8.4	4.0	38	34
214	180	213	13	1.1	KS712_0140 EZ505U	400	600	14.00	14/1	3200	6000	13	4.0	38	37
214	98	110	7.0	2.0	KS712_0140 EZ701U	266	600	14.00	14/1	3200	6000	9.4	4.0	38	34
214	160	192	11	1.2	KS712_0140 EZ702U	400	600	14.00	14/1	3200	6000	15	4.0	38	37
188	65	71	16	3.0	KS712_0160 EZ501U	243	570	16.00	16/1	3000	6000	4.4	4.0	40	31

9.2 Selection tables 9 KS right-angle servo geared motors

n_2 [rpm]	M_2 [Nm]	$M_{2.0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
KS7 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 400 \text{ Nm}$)															
188	112	122	27	1.8	KS712_0160 EZ502U	285	570	16.00	16/1	3000	6000	6.7	4.0	40	33
188	147	169	36	1.3	KS712_0160 EZ503U	285	570	16.00	16/1	3000	6000	9.1	4.0	40	34
188	112	126	27	1.8	KS712_0160 EZ701U	285	570	16.00	16/1	3000	6000	10	4.0	40	34
188	182	219	44	1.1	KS712_0160 EZ702U	285	570	16.00	16/1	3000	6000	15	4.0	40	37
150	82	89	2.7	2.4	KS712_0200 EZ501U	304	600	20.00	20/1	3300	6000	3.3	4.0	38	31
150	141	152	4.6	1.4	KS712_0200 EZ502U	400	600	20.00	20/1	3300	6000	5.6	4.0	38	33
150	184	211	6.0	1.1	KS712_0200 EZ503U	400	600	20.00	20/1	3300	6000	8.0	4.0	38	34
150	141	158	4.6	1.4	KS712_0200 EZ701U	380	600	20.00	20/1	3300	6000	8.9	4.0	38	34
107	114	125	8.1	1.7	KS712_0280 EZ501U	285	570	28.00	28/1	3300	6000	3.4	4.0	40	31
107	197	213	14	1.0	KS712_0280 EZ502U	285	570	28.00	28/1	3300	6000	5.7	4.0	40	33
107	197	221	14	1.0	KS712_0280 EZ701U	285	570	28.00	28/1	3300	6000	9.0	4.0	40	34
75	163	179	5.3	1.2	KS712_0400 EZ501U	285	570	40.00	40/1	3300	6000	3.2	4.0	40	31
94	83	89	0.4	2.9	KS713_0320 EZ401U	253	600	32.00	32/1	3000	6000	1.4	4.0	38	32
94	140	155	0.6	1.7	KS713_0320 EZ402U	400	600	32.00	32/1	3000	6000	2.1	4.0	38	33
94	205	256	0.9	1.2	KS713_0320 EZ404U	400	600	32.00	32/1	3000	6000	3.4	4.0	38	35
94	128	140	0.6	1.9	KS713_0320 EZ501U	400	600	32.00	32/1	3000	6000	3.3	4.0	38	33
94	220	238	1.0	1.1	KS713_0320 EZ502U	400	600	32.00	32/1	3000	6000	5.6	4.0	38	35
60	130	140	0.2	1.8	KS713_0500 EZ401U	395	600	50.00	50/1	3500	6000	1.2	4.0	38	32
60	219	242	0.4	1.1	KS713_0500 EZ402U	400	600	50.00	50/1	3500	6000	1.9	4.0	38	33
60	200	219	0.3	1.2	KS713_0500 EZ501U	400	600	50.00	50/1	3500	6000	3.1	4.0	38	33
47	167	179	0.9	1.2	KS713_0640 EZ401U	285	570	64.00	64/1	3000	6000	1.3	4.0	40	32
KS7 ($n_{1N} = 4000 \text{ min}^{-1}$, $M_{2acc,max} = 290 \text{ Nm}$)															
43	182	195	0.1	1.3	KS713_0700 EZ401U	400	600	70.00	70/1	3500	6000	1.1	4.0	38	32
38	208	223	0.1	1.1	KS713_0800 EZ401U	400	600	80.00	80/1	4000	6000	1.0	4.0	38	32
KS7 ($n_{1N} = 4500 \text{ min}^{-1}$, $M_{2acc,max} = 400 \text{ Nm}$)															
750	54	87	36	2.6	KS712_0060 EZ505U	382	600	6.000	6/1	2200	5000	17	4.0	38	37
750	69	114	45	2.0	KS712_0060 EZ703U	371	600	6.000	6/1	2200	5000	27	4.0	38	39
750	93	171	61	1.5	KS712_0060 EZ705U	400	600	6.000	6/1	2200	5000	39	4.0	38	44
563	72	116	20	2.4	KS712_0080 EZ505U	400	600	8.000	8/1	3000	6000	15	4.0	38	37
563	92	152	26	1.9	KS712_0080 EZ703U	400	600	8.000	8/1	3000	6000	24	4.0	38	39
563	125	228	35	1.4	KS712_0080 EZ705U	400	600	8.000	8/1	3000	6000	37	4.0	38	44
450	90	145	15	1.9	KS712_0100 EZ505U	400	600	10.00	10/1	3000	6000	14	4.0	38	37
450	115	190	20	1.5	KS712_0100 EZ703U	400	600	10.00	10/1	3000	6000	23	4.0	38	39
450	156	285	27	1.1	KS712_0100 EZ705U	400	600	10.00	10/1	3000	6000	36	4.0	38	44
375	108	174	57	1.6	KS712_0120 EZ505U	285	570	12.00	12/1	2200	5000	15	4.0	40	37
375	138	228	72	1.3	KS712_0120 EZ703U	285	570	12.00	12/1	2200	5000	25	4.0	40	39
321	126	203	10	1.4	KS712_0140 EZ505U	400	600	14.00	14/1	3200	6000	13	4.0	38	37
321	161	266	13	1.1	KS712_0140 EZ703U	400	600	14.00	14/1	3200	6000	22	4.0	38	39
281	144	233	40	1.2	KS712_0160 EZ505U	285	570	16.00	16/1	3000	6000	14	4.0	40	37
KS7 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 400 \text{ Nm}$)															
750	40	59	12	4.0	KS712_0080 EZ502U	236	600	8.000	8/1	3000	6000	7.8	4.0	38	33
750	47	81	14	3.3	KS712_0080 EZ503U	327	600	8.000	8/1	3000	6000	10	4.0	38	34
750	40	60	12	4.0	KS712_0080 EZ701U	152	600	8.000	8/1	3000	6000	11	4.0	38	34
750	55	109	17	2.9	KS712_0080 EZ702U	312	600	8.000	8/1	3000	6000	16	4.0	38	37
600	32	42	6.1	4.9	KS712_0100 EZ501U	152	600	10.00	10/1	3000	6000	4.6	4.0	38	31
600	49	74	9.3	3.2	KS712_0100 EZ502U	295	600	10.00	10/1	3000	6000	6.9	4.0	38	33
600	59	101	11	2.7	KS712_0100 EZ503U	400	600	10.00	10/1	3000	6000	9.2	4.0	38	34
600	49	75	9.3	3.2	KS712_0100 EZ701U	190	600	10.00	10/1	3000	6000	10	4.0	38	34
600	68	136	13	2.3	KS712_0100 EZ702U	390	600	10.00	10/1	3000	6000	15	4.0	38	37
429	45	59	4.1	3.5	KS712_0140 EZ501U	213	600	14.00	14/1	3200	6000	3.8	4.0	38	31
429	69	104	6.2	2.3	KS712_0140 EZ502U	400	600	14.00	14/1	3200	6000	6.1	4.0	38	33
429	82	141	7.4	1.9	KS712_0140 EZ503U	400	600	14.00	14/1	3200	6000	8.4	4.0	38	34
429	69	105	6.2	2.3	KS712_0140 EZ701U	266	600	14.00	14/1	3200	6000	9.4	4.0	38	34
429	96	190	8.6	1.6	KS712_0140 EZ702U	400	600	14.00	14/1	3200	6000	15	4.0	38	37
375	52	67	16	3.0	KS712_0160 EZ501U	243	570	16.00	16/1	3000	6000	4.4	4.0	40	31
375	79	119	24	2.0	KS712_0160 EZ502U	285	570	16.00	16/1	3000	6000	6.7	4.0	40	33
375	94	161	29	1.7	KS712_0160 EZ503U	285	570	16.00	16/1	3000	6000	9.1	4.0	40	34
375	79	120	24	2.0	KS712_0160 EZ701U	285	570	16.00	16/1	3000	6000	10	4.0	40	34
375	109	217	34	1.4	KS712_0160 EZ702U	285	570	16.00	16/1	3000	6000	15	4.0	40	37
300	65	84	2.6	2.4	KS712_0200 EZ501U	304	600	20.00	20/1	3300	6000	3.3	4.0	38	31
300	99	148	4.0	1.6	KS712_0200 EZ502U	400	600	20.00	20/1	3300	6000	5.6	4.0	38	33
300	118	201	4.8	1.3	KS712_0200 EZ503U	400	600	20.00	20/1	3300	6000	8.0	4.0	38	34
300	99	150	4.0	1.6	KS712_0200 EZ701U	380	600	20.00	20/1	3300	6000	8.9	4.0	38	34
300	137	272	5.6	1.2	KS712_0200 EZ702U	400	600	20.00	20/1	3300	6000	14	4.0	38	37
214	90	117	8.1	1.7	KS712_0280 EZ501U	285	570	28.00	28/1	3300	6000	3.4	4.0	40	31

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_{2red}$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
KS7 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 400 \text{ Nm}$)															
214	138	207	12	1.1	KS712_0280 EZ502U	285	570	28.00	28/1	3300	6000	5.7	4.0	40	33
214	138	210	12	1.1	KS712_0280 EZ701U	285	570	28.00	28/1	3300	6000	9.0	4.0	40	34
150	129	167	5.3	1.2	KS712_0400 EZ501U	285	570	40.00	40/1	3300	6000	3.2	4.0	40	31
188	68	83	0.4	2.8	KS713_0320 EZ401U	253	600	32.00	32/1	3000	6000	1.4	4.0	38	32
188	104	146	0.6	1.8	KS713_0320 EZ402U	400	600	32.00	32/1	3000	6000	2.1	4.0	38	33
188	173	250	1.0	1.1	KS713_0320 EZ404U	400	600	32.00	32/1	3000	6000	3.4	4.0	38	35
188	101	131	0.6	1.9	KS713_0320 EZ501U	400	600	32.00	32/1	3000	6000	3.3	4.0	38	33
188	155	232	0.9	1.2	KS713_0320 EZ502U	400	600	32.00	32/1	3000	6000	5.6	4.0	38	35
188	185	315	1.1	1.0	KS713_0320 EZ503U	400	600	32.00	32/1	3000	6000	8.0	4.0	38	36
120	107	130	0.2	1.8	KS713_0500 EZ401U	395	600	50.00	50/1	3500	6000	1.2	4.0	38	32
120	163	228	0.3	1.2	KS713_0500 EZ402U	400	600	50.00	50/1	3500	6000	1.9	4.0	38	33
120	158	205	0.3	1.2	KS713_0500 EZ501U	400	600	50.00	50/1	3500	6000	3.1	4.0	38	33
94	137	167	0.9	1.2	KS713_0640 EZ401U	285	570	64.00	64/1	3000	6000	1.3	4.0	40	32
86	150	182	0.2	1.3	KS713_0700 EZ401U	400	600	70.00	70/1	3500	6000	1.1	4.0	38	32
75	171	208	0.1	1.1	KS713_0800 EZ401U	400	600	80.00	80/1	4000	6000	1.0	4.0	38	32

9.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

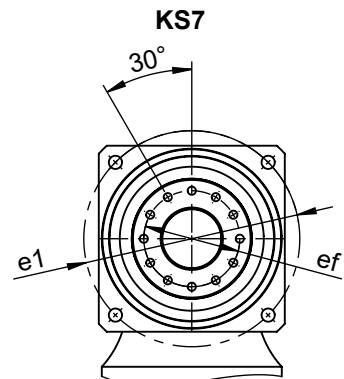
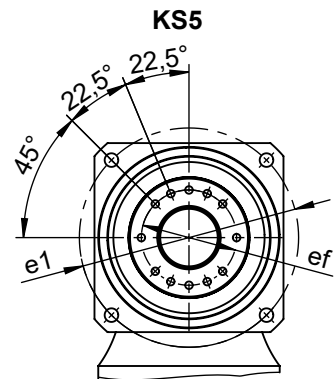
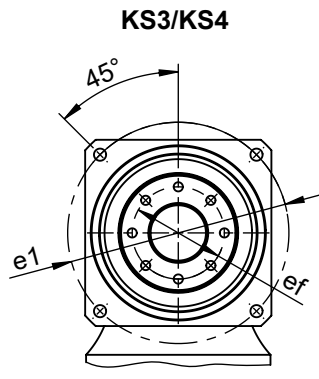
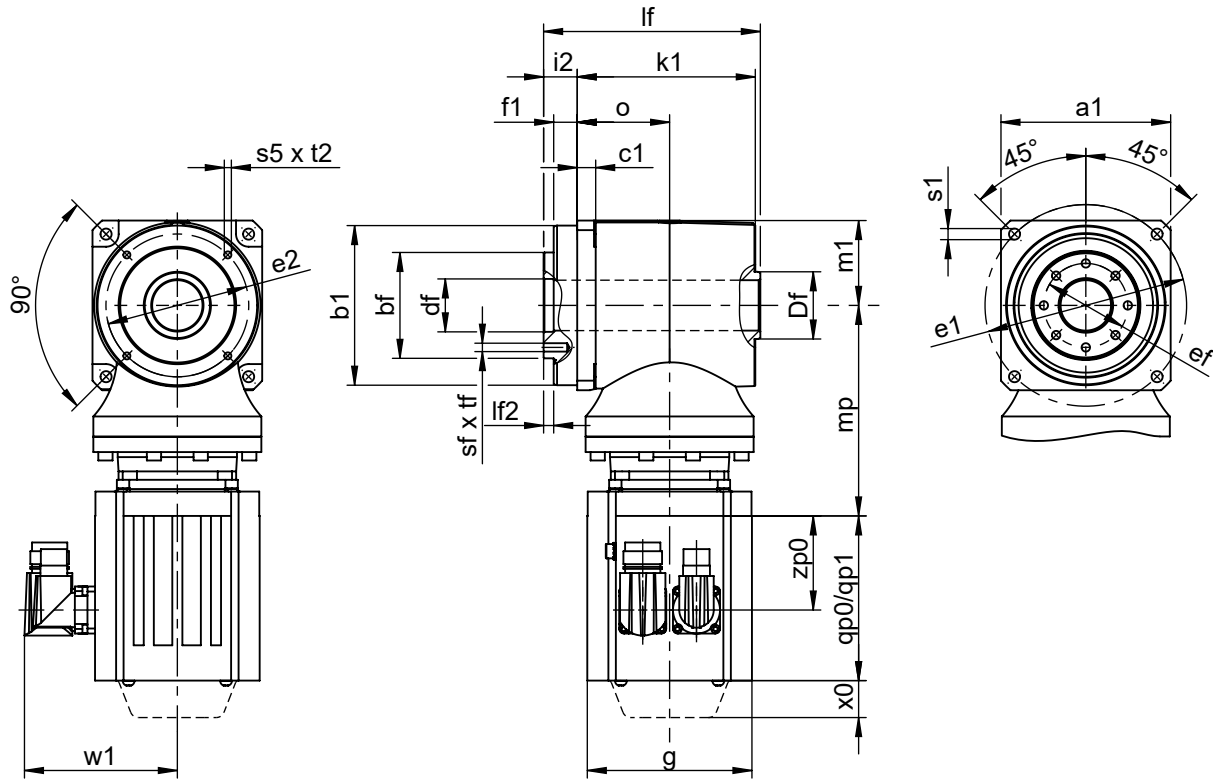
Tolerances

Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6
Feather keys	DIN 6885-1, high form A
Hollow shaft	Tolerance
Hollow shaft hole fit	ISO H7
Feather keys	DIN 6885-1, high form

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M8	M12	M16
Thread depth	19	28	36

9.3.1 F shaft design (flange hollow shaft)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

EZ3 – EZ8: Applies to encoders using an optical measuring method

Dimensions of gearboxes

Type	□a1	Øb1	bf	c1	Ødf	Ødf1	ØDf	Øe1	Øe2	ef	f1	i2	k1	lf	lf2	m1	o	Øs1	s5	sf	t2	tf
KS311	80	75 _{h6}	40 _{h7}	8	20.0 ^{H7}	19	25 _{g9}	90	68	31.5	13.0	16.5	88.5	107	3.5	40.0	43	6.6	M4	M5	8	9
KS312	80	75 _{h6}	40 _{h7}	8	20.0 ^{H7}	19	25 _{g9}	90	68	31.5	13.0	16.5	88.5	107	3.5	40.0	43	6.6	M4	M5	8	9
KS313	80	75 _{h6}	40 _{h7}	8	20.0 ^{H7}	19	25 _{g9}	90	68	31.5	13.0	16.5	88.5	107	3.5	40.0	43	6.6	M4	M5	8	9
KS411	101	95 _{h6}	63 _{h7}	10	31.5 ^{H7}	30	40 _{g9}	120	85	50.0	14.0	20.0	106.0	129	6.0	50.5	55	6.6	M5	M6	9	11
KS412	101	95 _{h6}	63 _{h7}	10	31.5 ^{H7}	30	40 _{g9}	120	85	50.0	14.0	20.0	106.0	129	6.0	50.5	55	6.6	M5	M6	9	11
KS413	101	95 _{h6}	63 _{h7}	10	31.5 ^{H7}	30	40 _{g9}	120	85	50.0	14.0	20.0	106.0	129	6.0	50.5	55	6.6	M5	M6	9	11
KS511	125	120 _{h6}	80 _{h7}	10	40.0 ^{H7}	38	50 _{g9}	145	105	63.0	15.5	22.0	125.0	150	6.5	62.5	65	9.0	M6	M6	12	12
KS512	125	120 _{h6}	80 _{h7}	10	40.0 ^{H7}	38	50 _{g9}	145	105	63.0	15.5	22.0	125.0	150	6.5	62.5	65	9.0	M6	M6	12	12
KS513	125	120 _{h6}	80 _{h7}	10	40.0 ^{H7}	38	50 _{g9}	145	105	63.0	15.5	22.0	125.0	150	6.5	62.5	65	9.0	M6	M6	12	12
KS711	155	150 _{h6}	100 _{h7}	15	50.0 ^{H7}	49	65 _{g9}	180	126	80.0	20.0	27.0	150.0	180	7.0	77.5	80	11.0	M8	M8	14	16
KS712	155	150 _{h6}	100 _{h7}	15	50.0 ^{H7}	49	65 _{g9}	180	126	80.0	20.0	27.0	150.0	180	7.0	77.5	80	11.0	M8	M8	14	16
KS713	155	150 _{h6}	100 _{h7}	15	50.0 ^{H7}	49	65 _{g9}	180	126	80.0	20.0	27.0	150.0	180	7.0	77.5	80	11.0	M8	M8	14	16

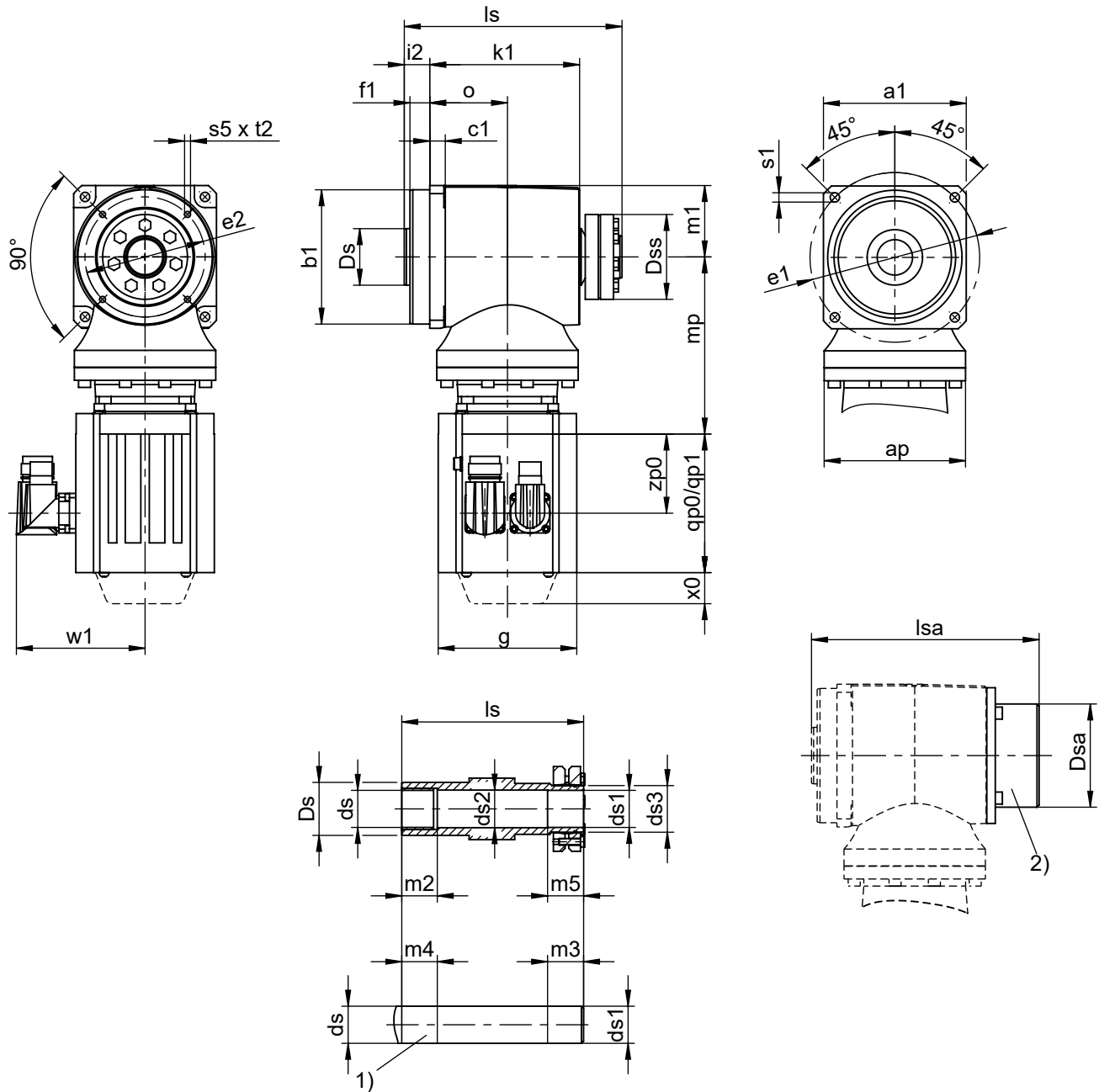
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
KS311	–	151.5	146.0	–	–	–
KS312	99.0	112.5	–	–	–	–
KS313	131.0	–	–	–	–	–
KS411	–	–	165.8	170.3	–	–
KS412	–	128.8	125.3	–	–	–
KS413	149.8	163.3	–	–	–	–
KS511	–	–	–	196.0	199.0	–
KS512	–	–	154.0	153.5	–	–
KS513	–	191.0	187.5	–	–	–
KS711	–	–	–	–	236.0	242.0
KS712	–	–	–	185.0	188.0	–
KS713	–	–	227.0	226.5	–	–

9.3.2 S shaft design (hollow shaft with shrink disk)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 E22: Applies only to motors with brake and encoders using an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

1) Machine shaft: The dimension ls must be met.

2) Cover (optional)

Dimensions of gearboxes

Type	$\square a1$	$\varnothing b1$	$c1$	$\varnothing ds$	$\varnothing ds1$	$\varnothing ds2$	$\varnothing ds3$	$\varnothing Ds$	$\varnothing Dsa$	$\varnothing Dss$	$\varnothing e1$	$\varnothing e2$	$f1$	$i2$	$k1$	ls	lsa	$m1$	$m2$	$m3$	$m4$	$m5$	o	$\varnothing s1$	$s5$	$t2$
KS311	80	75_{h6}	8	16_{h6}	16_{h6}^{H7}	17.5	20	25	59	47	90	68	13.0	15.0	88.5	127.5	133.5	40.0	16	32	20	27	43	6.6	M4	8
KS312	80	75_{h6}	8	16_{h6}	16_{h6}^{H7}	17.5	20	25	59	47	90	68	13.0	15.0	88.5	127.5	133.5	40.0	16	32	20	27	43	6.6	M4	8
KS313	80	75_{h6}	8	16_{h6}	16_{h6}^{H7}	17.5	20	25	59	47	90	68	13.0	15.0	88.5	127.5	133.5	40.0	16	32	20	27	43	6.6	M4	8
KS411	101	95_{h6}	10	25_{h6}	25_{h6}^{H7}	25.5	30	40	73	60	120	85	14.0	18.0	106.0	154.0	161.0	50.5	20	34	25	29	55	6.6	M5	9
KS412	101	95_{h6}	10	25_{h6}	25_{h6}^{H7}	25.5	30	40	73	60	120	85	14.0	18.0	106.0	154.0	161.0	50.5	20	34	25	29	55	6.6	M5	9
KS413	101	95_{h6}	10	25_{h6}	25_{h6}^{H7}	25.5	30	40	73	60	120	85	14.0	18.0	106.0	154.0	161.0	50.5	20	34	25	29	55	6.6	M5	9
KS511	125	120_{h6}	10	35_{h6}	35_{h6}^{H7}	35.5	44	50	92	80	145	105	15.5	19.5	125.0	178.5	185.5	62.5	30	39	35	34	65	9.0	M6	12
KS512	125	120_{h6}	10	35_{h6}	35_{h6}^{H7}	35.5	44	50	92	80	145	105	15.5	19.5	125.0	178.5	185.5	62.5	30	39	35	34	65	9.0	M6	12
KS513	125	120_{h6}	10	35_{h6}	35_{h6}^{H7}	35.5	44	50	92	80	145	105	15.5	19.5	125.0	178.5	185.5	62.5	30	39	35	34	65	9.0	M6	12
KS711	155	150_{h6}	15	45_{h6}	45_{h6}^{H7}	45.5	55	65	113	100	180	126	20.0	24.0	150.0	214.0	221.0	77.5	40	42	45	37	80	11.0	M8	14

Type	□a1	∅b1	c1	∅ds	∅ds1	∅ds2	∅ds3	∅Ds	∅Dsa	∅Dss	∅e1	∅e2	f1	i2	k1	ls	lsa	m1	m2	m3	m4	m5	o	∅s1	s5	t2
KS712	155	150 _{h6}	15	45 _{h6}	45 _{h6} ^{H7}	45.5	55	65	113	100	180	126	20.0	24.0	150.0	214.0	221.0	77.5	40	42	45	37	80	11.0	M8	14
KS713	155	150 _{h6}	15	45 _{h6}	45 _{h6} ^{H7}	45.5	55	65	113	100	180	126	20.0	24.0	150.0	214.0	221.0	77.5	40	42	45	37	80	11.0	M8	14

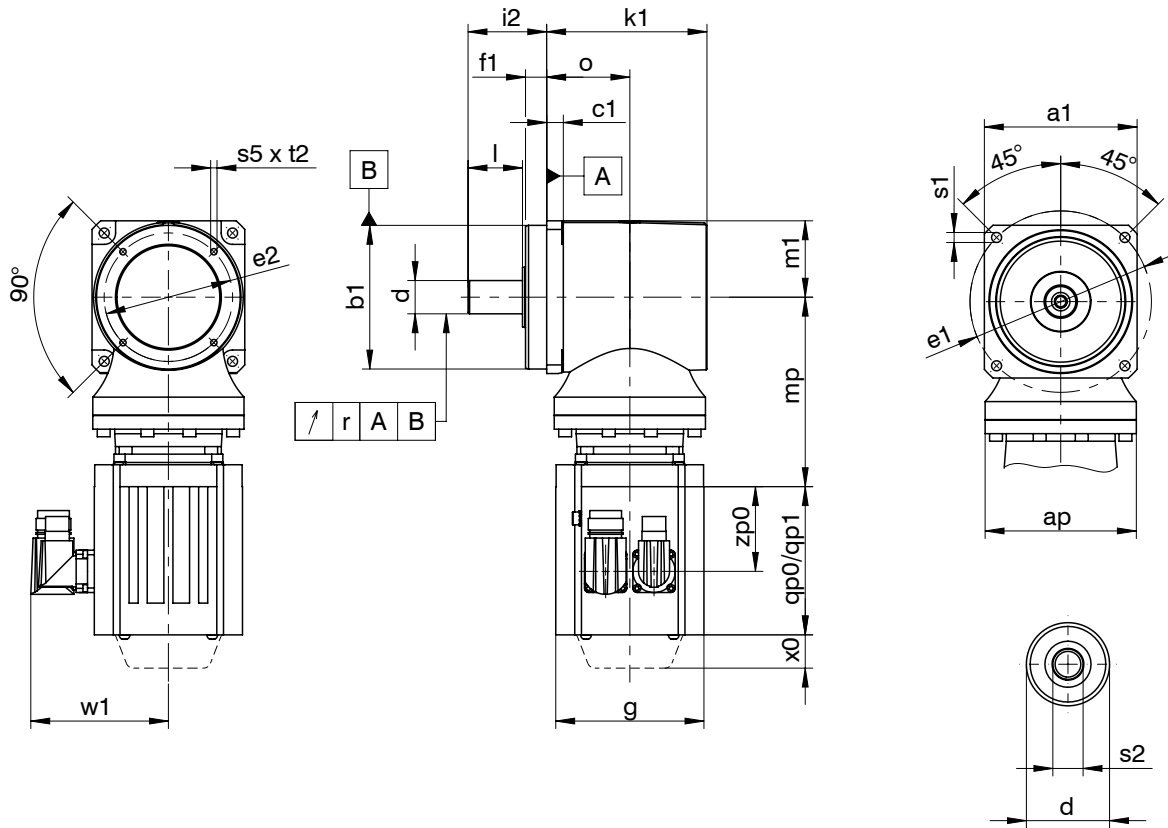
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
KS311	–	151.5	146.0	–	–	–
KS312	99.0	112.5	–	–	–	–
KS313	131.0	–	–	–	–	–
KS411	–	–	165.8	170.3	–	–
KS412	–	128.8	125.3	–	–	–
KS413	149.8	163.3	–	–	–	–
KS511	–	–	–	196.0	199.0	–
KS512	–	–	154.0	153.5	–	–
KS513	–	191.0	187.5	–	–	–
KS711	–	–	–	–	236.0	242.0
KS712	–	–	–	185.0	188.0	–
KS713	–	–	227.0	226.5	–	–

9.3.3 G shaft design (solid shaft without feather key)



- qp0 Applies to motors without brake.
- qp1 Applies to motors with brake.
- x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method

Dimensions of gearboxes

Type	a1	b1	c1	d	e1	e2	f1	i2	l	k1	m1	o	r	s1	s2	s5	t2
KS311	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	88.5	40.0	43	0.020	6.6	M5	M4	8
KS312	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	88.5	40.0	43	0.020	6.6	M5	M4	8
KS313	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	88.5	40.0	43	0.020	6.6	M5	M4	8
KS411	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	106.0	50.5	55	0.020	6.6	M8	M5	9
KS412	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	106.0	50.5	55	0.020	6.6	M8	M5	9
KS413	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	106.0	50.5	55	0.020	6.6	M8	M5	9
KS511	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	125.0	62.5	65	0.020	9.0	M12	M6	12
KS512	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	125.0	62.5	65	0.020	9.0	M12	M6	12
KS513	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	125.0	62.5	65	0.020	9.0	M12	M6	12
KS711	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	150.0	77.5	80	0.025	11.0	M16	M8	14
KS712	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	150.0	77.5	80	0.025	11.0	M16	M8	14
KS713	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	150.0	77.5	80	0.025	11.0	M16	M8	14

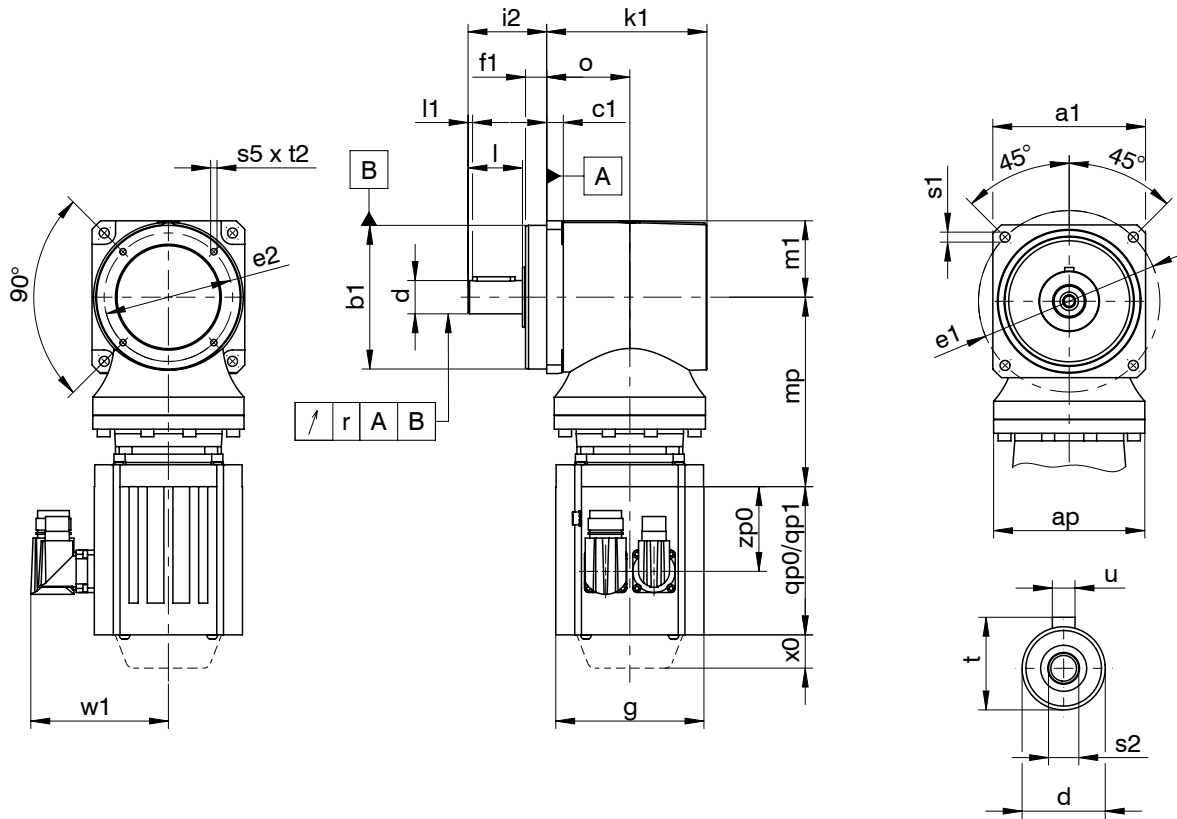
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
KS311	–	151.5	146.0	–	–	–
KS312	99.0	112.5	–	–	–	–
KS313	131.0	–	–	–	–	–
KS411	–	–	165.8	170.3	–	–
KS412	–	128.8	125.3	–	–	–
KS413	149.8	163.3	–	–	–	–
KS511	–	–	–	196.0	199.0	–
KS512	–	–	154.0	153.5	–	–
KS513	–	191.0	187.5	–	–	–
KS711	–	–	–	–	236.0	242.0
KS712	–	–	–	185.0	188.0	–
KS713	–	–	227.0	226.5	–	–

9.3.4 P shaft design (solid shaft with feather key)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 E22: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
 E23 – E28: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	∅e2	f1	i2	l	l1	k1	m1	o	r	∅s1	s2	s5	t	t2	u
KS311	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	2	88.5	40.0	43	0.020	6.6	M5	M4	18.0	8	A5×5×22
KS312	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	2	88.5	40.0	43	0.020	6.6	M5	M4	18.0	8	A5×5×22
KS313	80	75 _{h6}	8	16 _{k6}	90	68	13.0	43.0	28	2	88.5	40.0	43	0.020	6.6	M5	M4	18.0	8	A5×5×22
KS411	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	3	106.0	50.5	55	0.020	6.6	M8	M5	24.5	9	A6×6×28
KS412	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	3	106.0	50.5	55	0.020	6.6	M8	M5	24.5	9	A6×6×28
KS413	101	95 _{h6}	10	22 _{k6}	120	85	14.0	52.0	36	3	106.0	50.5	55	0.020	6.6	M8	M5	24.5	9	A6×6×28
KS511	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	3	125.0	62.5	65	0.020	9.0	M12	M6	35.0	12	A10×8×50
KS512	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	3	125.0	62.5	65	0.020	9.0	M12	M6	35.0	12	A10×8×50
KS513	125	120 _{h6}	10	32 _{k6}	145	105	15.5	75.5	58	3	125.0	62.5	65	0.020	9.0	M12	M6	35.0	12	A10×8×50
KS711	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	4	150.0	77.5	80	0.025	11.0	M16	M8	43.0	14	A12×8×70
KS712	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	4	150.0	77.5	80	0.025	11.0	M16	M8	43.0	14	A12×8×70
KS713	155	150 _{h6}	15	40 _{k6}	180	126	20.0	105.0	82	4	150.0	77.5	80	0.025	11.0	M16	M8	43.0	14	A12×8×70

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp	EZ5 mp	EZ7 mp	EZ8 mp
KS311	–	151.5	146.0	–	–	–
KS312	99.0	112.5	–	–	–	–
KS313	131.0	–	–	–	–	–
KS411	–	–	165.8	170.3	–	–
KS412	–	128.8	125.3	–	–	–
KS413	149.8	163.3	–	–	–	–
KS511	–	–	–	196.0	199.0	–
KS512	–	–	154.0	153.5	–	–
KS513	–	191.0	187.5	–	–	–
KS711	–	–	–	–	236.0	242.0
KS712	–	–	–	185.0	188.0	–
KS713	–	–	227.0	226.5	–	–

9.4 Type designation

In this chapter, you will find an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

KS	5	1	2	S	G	S	R	0200	EZ401U
----	---	---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
KS	Type	Right-angle servo gearbox
5	Size	5 (example)
1	Generation	Generation 1
1	Stages	Single-stage
2		Two-stage
3		Three-stage
S	Housing	Standard
F	Shaft	Flange hollow shaft
S		Hollow shaft with shrink ring
G		Solid shaft without feather key
P		Solid shaft with feather key
S	Bearing	Standard bearing
R	Backlash	Reduced
0200	Transmission ratio (i x 10)	i = 20 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Mounting position, see the chapter [▶ 9.5.3](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 9.6.3](#)
- Position of the plug connectors, see the chapter [▶ 9.5.5](#)

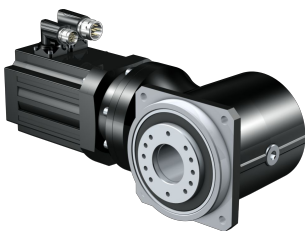
To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

9.5 Product description

9.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

9.5.2 Installation conditions

Take care to align the machine shaft with the gearbox hollow shaft when attaching the gearbox.

Maximum deviation ≤ 0.03 mm.

Hollow shaft with shrink ring

The tolerance of the hollow shaft hole is ISO H7.

The machine shaft must be ISO h6.

Select a material for the machine shaft with a permitted surface pressure of $p \geq 325$ N/mm².

Possible materials:

- C45E +QT
- 42CrMo4

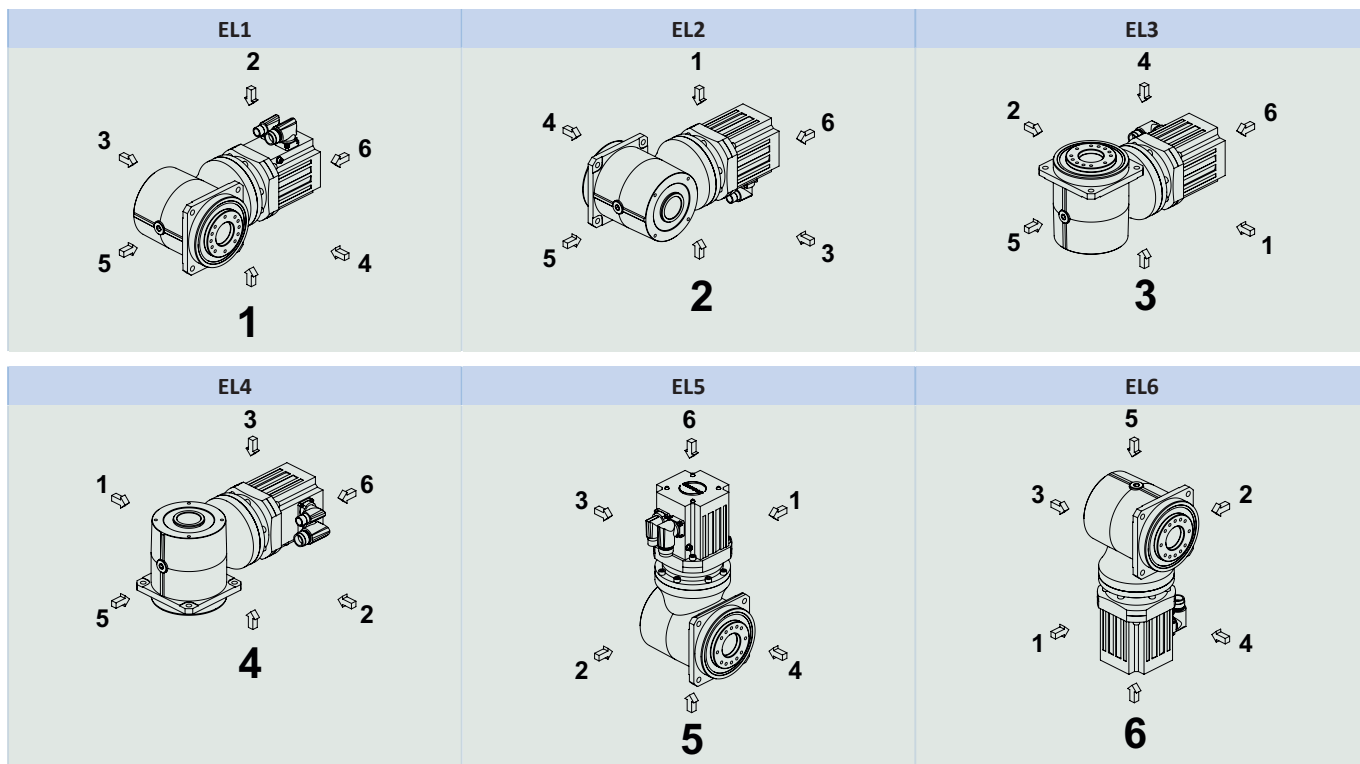
The torque and force values listed in this catalog are valid under the following conditions:

- When the gear housing is fastened on the machine side using screws of strength class 12.9
- When the gear housing is adjusted at pilot $\varnothing b1$. The machine-side fit must be H7.
- For the flange hollow shaft design: If the connecting element is fitted to pilot $\varnothing bf$ or $\varnothing df$ of the flange hollow shaft and fastened using screws of strength class 12.9.

9.5.3 Mounting positions

The following table shows the standard mounting positions for two- and three-stage gearboxes. Single-stage gearboxes can be used in any mounting position.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position for two- and three-stage gearboxes must be specified when ordering.

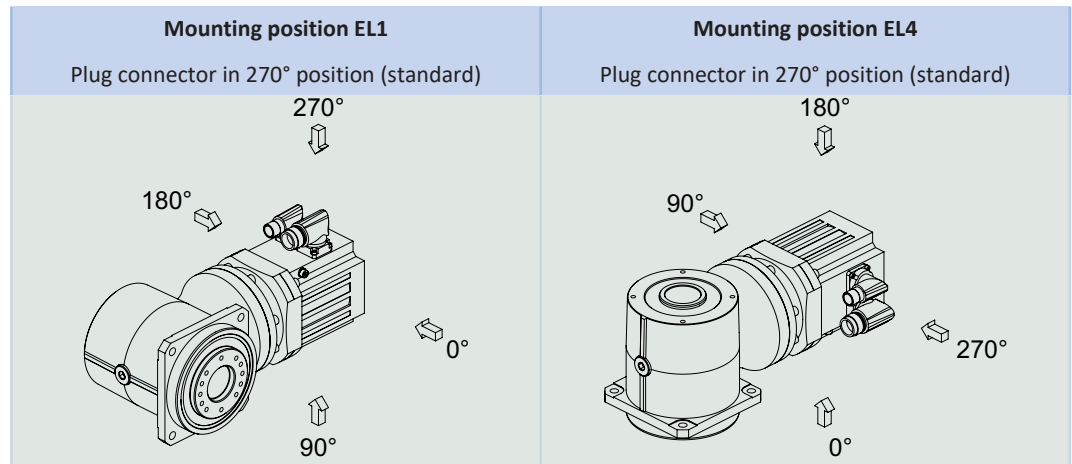
9.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

9.5.5 Position of the plug connectors



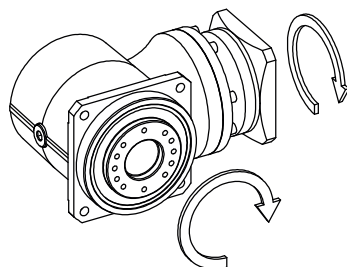
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

9.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	$\leq 90\text{ °C}$
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} single-stage	97%
η_{get} two-stage	95%
η_{get} three-stage	93%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

9.5.7 Direction of rotation



The figure shows the EL1 mounting position.

¹ Observe the protection class of all the components.

9.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

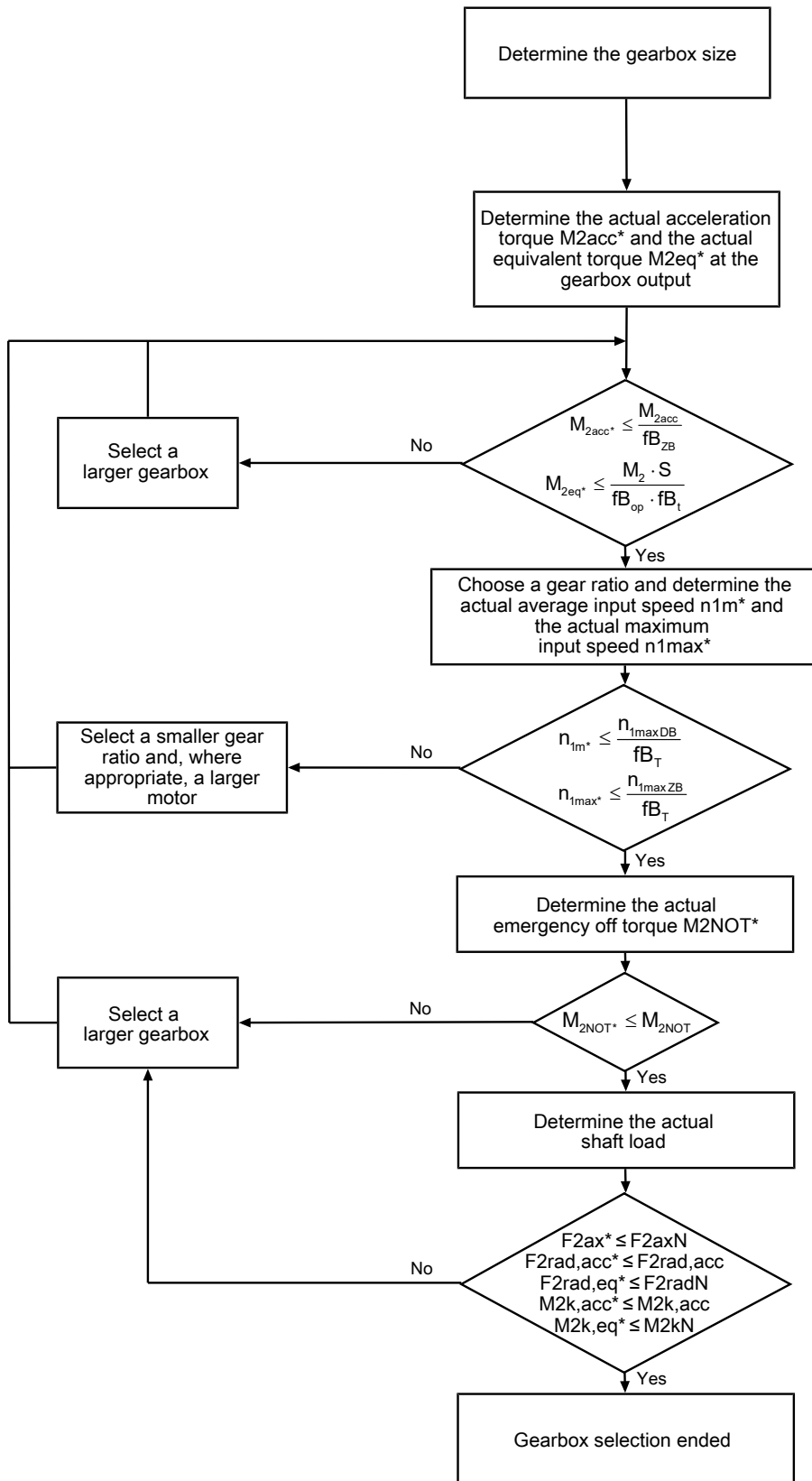
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

9.6.1 Drive selection

Drive selection for gearboxes

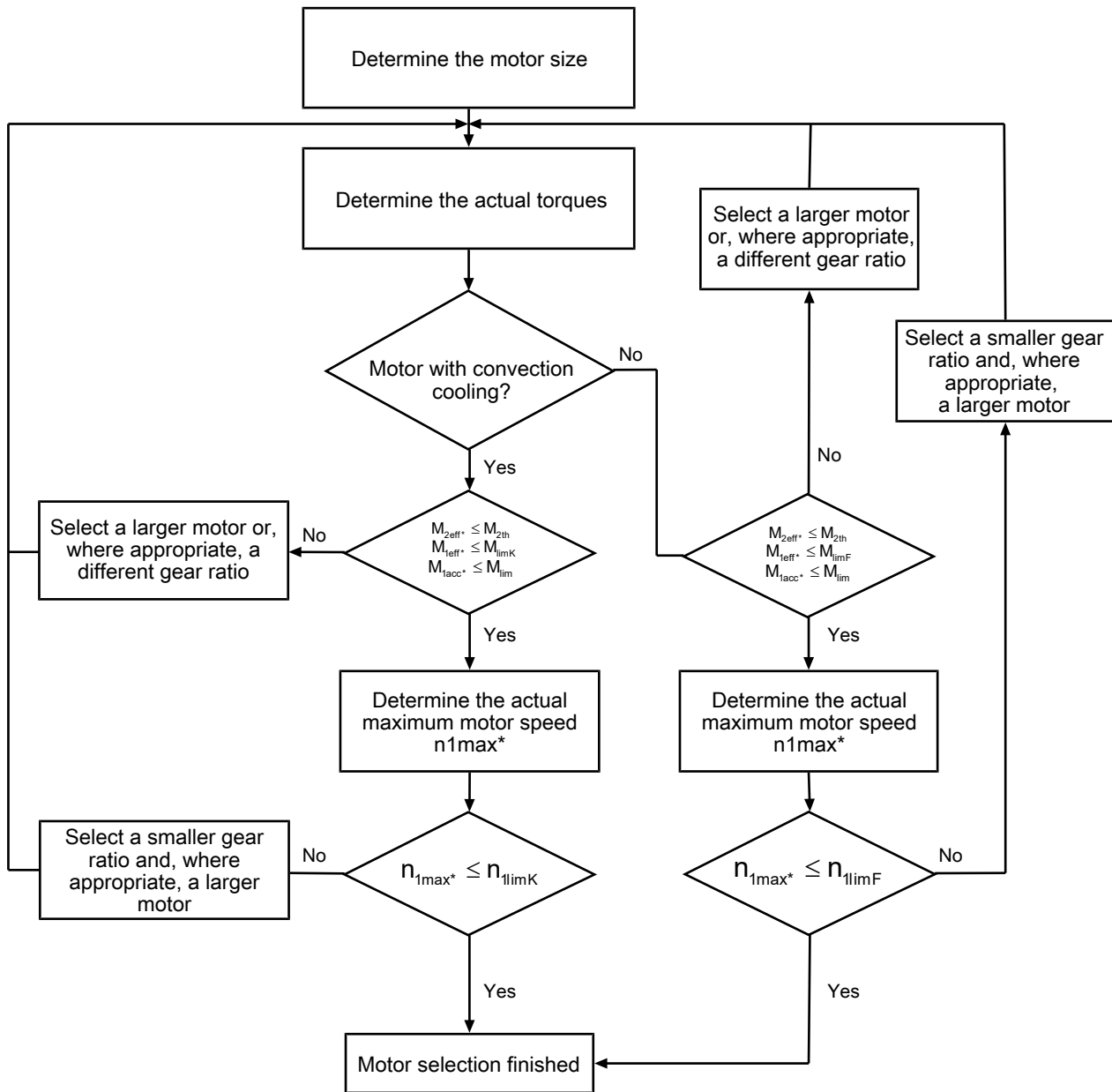


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

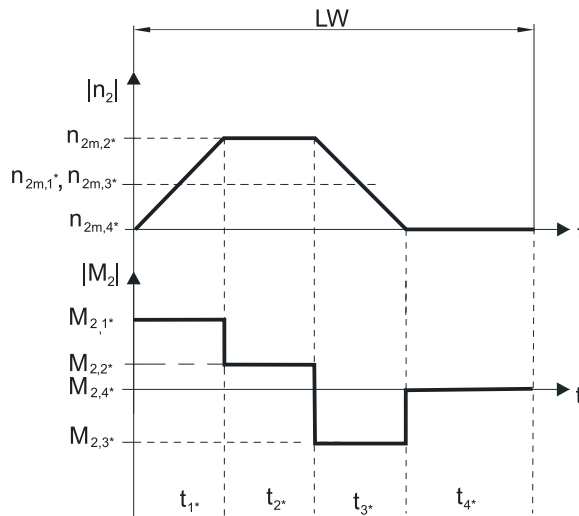
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{limK} and n_{limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:



Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

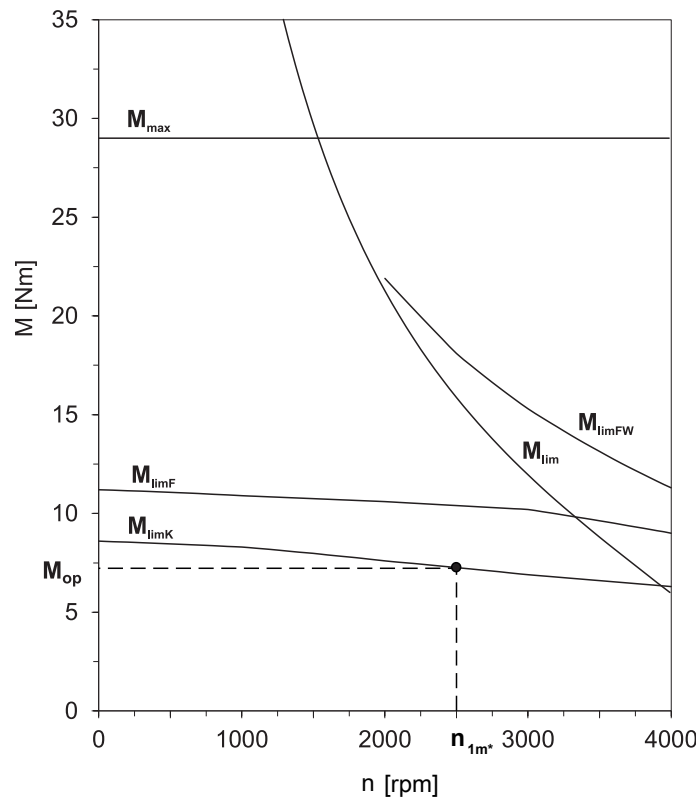
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.00
Reversing load cyclic operation		1.00
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

9.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

9.6.2.1 F shaft design

Permitted shaft loads for F shaft design (flange hollow shaft)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KS3	32.5	2500	4500	5000	146	163
KS4	40.5	4000	7500	10300	304	417
KS5	47.0	6000	13700	18500	644	870
KS7	55.5	10000	18400	25100	1020	1400

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

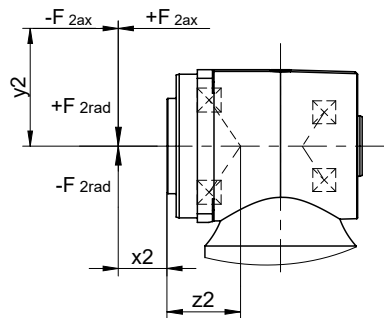


Fig. 1: Force application points for flange hollow shaft

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

9.6.2.2 S shaft design

Permitted shaft loads for S shaft design (hollow shaft with shrink ring)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KS3	31.0	2500	2750	2750	124	124
KS4	38.5	4000	5000	5000	283	283
KS5	44.5	6000	9000	9000	662	662
KS7	52.5	10000	11000	11000	1030	1030

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

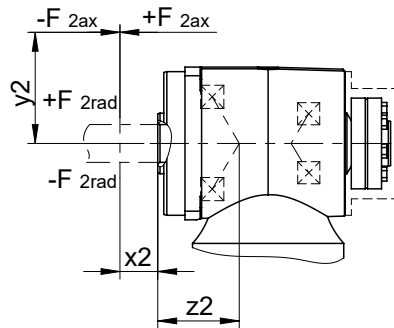


Fig. 2: Force application points for the hollow shaft with shrink ring

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

9.6.2.3 G and P shaft designs

Permitted shaft loads for G and P shaft designs (solid shaft)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KS3	31.0	2500	2750	2750	124	124
KS4	36.5	4000	5000	5000	273	273
KS5	42.5	6000	9000	9000	644	644
KS7	51.5	10000	11000	11000	1020	1020

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

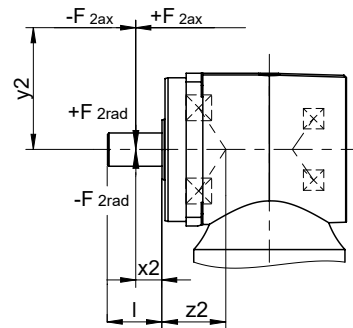


Fig. 3: Force application points for solid shaft

The specified values for $F_{2rad100}$ and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

9.6.3 Recommendation for radial shaft seal rings

For a duty cycle > 60% and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

9.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

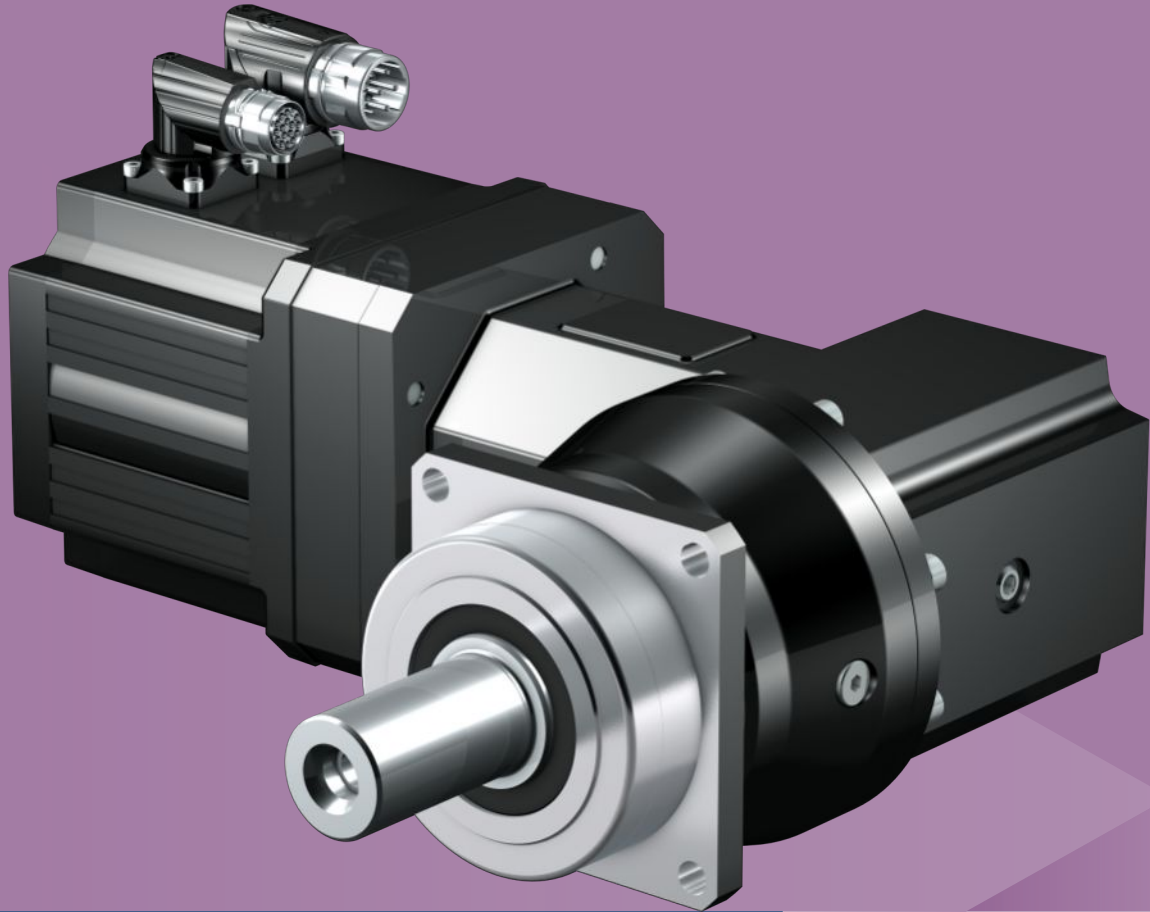
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual for gearboxes, geared motors KS31 – KS71	443506_en
Operating manual for EZ synchronous servo motors	443032_en

10 PKX right-angle planetary geared motors

Table of contents

10.1 Overview	266
10.2 Selection tables	267
10.3 Dimensional drawings	283
10.3.1 G shaft design (solid shaft without feather key)	284
10.3.2 P shaft design (solid shaft with feather key)	286
10.4 Type designation	288
10.5 Product description	289
10.5.1 Input options	289
10.5.2 Installation conditions	289
10.5.3 Mounting positions	289
10.5.4 Lubricants	290
10.5.5 Position of the plug connectors	290
10.5.6 Other product features	290
10.5.7 Direction of rotation	290
10.6 Project configuration	291
10.6.1 Drive selection	292
10.6.2 Permitted shaft loads for the output shaft	296
10.6.3 Recommendation for radial shaft seal rings	298
10.6.4 Reverse operation	299
10.7 Additional documentation	299



10

Right-angle planetary geared motors

PKX

10.1 Overview

Helical-gear precision right-angle planetary geared motors

Features

Power density	★★★★☆
Backlash	★★★★★
Price category	€€€
Shaft load	★★★★☆
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★☆
Helical gearing	✓
Maintenance-free	✓
Small installation space	✓
Continuous operation without cooling	✓
Reinforced output bearing	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	3 – 300
M_{2acc}	11 – 3300 Nm
$\Delta\phi_2$	2 – 8.5 arcmin
η_{get}	94 – 96 %

10.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)
- M_{2acc} , M_{2accHT} : Solid shaft design without feather key (we generally recommend this shaft design for cyclic operation)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to <https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2	M_2	$M_{2,0}$	a_{th}	S	Type	M_{2acc}	M_{2accHT}	M_{2NOT}	i	i_{exakt}	n_{1maxDB}	n_{1maxZB}	J_1	$\Delta\Phi_2$	$\Delta\Phi_{2red}$	C_2	m	
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]	[Nm]			EL1,2,5,6 [rpm]	EL3,4 [rpm]	[kgcm ²]	[arcmin]	[arcmin]	[Nm/ arcmin]	[kg]	
P231KX ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 25 \text{ Nm}$)																		
200	13	14	35	1.2	P231_0050KX301_0030 MF EZ301U	25	-	51	15.00	15/1	3500	3500	6000	0.94	8.0	-	1.6	4.5
250	11	11	28	1.5	P231_0040KX301_0030 MF EZ301U	25	-	51	12.00	12/1	3500	3500	6000	0.94	8.5	-	1.5	4.5
300	8.9	9.1	32	1.8	P231_0050KX301_0020 MF EZ301U	25	-	51	10.00	10/1	3500	3000	5500	1.0	8.0	-	1.6	4.5
300	15	16	54	1.1	P231_0050KX301_0020 MF EZ302U	25	-	51	10.00	10/1	3500	3000	5500	1.1	8.0	-	1.6	5.1
375	7.1	7.3	25	2.3	P231_0040KX301_0020 MF EZ301U	21	-	51	8.000	8/1	3500	3000	5500	1.0	8.5	-	1.5	4.5
375	12	13	43	1.3	P231_0040KX301_0020 MF EZ302U	25	-	51	8.000	8/1	3500	3000	5500	1.1	8.5	-	1.5	5.1
375	16	17	56	1.0	P231_0040KX301_0020 MF EZ303U	25	-	51	8.000	8/1	3500	3000	5500	1.2	8.5	-	1.5	5.6
429	6.2	6.4	44	2.2	P231_0070KX301_0010 MF EZ301U	19	-	46	7.000	7/1	3000	2500	4500	1.2	7.5	-	1.7	4.5
429	11	11	76	1.3	P231_0070KX301_0010 MF EZ302U	23	-	46	7.000	7/1	3000	2500	4500	1.3	7.5	-	1.7	5.1
600	4.4	4.5	32	3.0	P231_0050KX301_0010 MF EZ301U	13	-	51	5.000	5/1	3000	2500	4500	1.2	8.0	-	1.6	4.5
600	7.6	8.0	54	1.8	P231_0050KX301_0010 MF EZ302U	24	-	51	5.000	5/1	3000	2500	4500	1.3	8.0	-	1.6	5.1
600	9.9	10	70	1.4	P231_0050KX301_0010 MF EZ303U	25	-	51	5.000	5/1	3000	2500	4500	1.4	8.0	-	1.6	5.6
600	13	14	95	1.0	P231_0050KX301_0010 MF EZ401U	25	-	51	5.000	5/1	3000	2500	4500	2.0	8.0	-	1.6	7.0
750	3.6	3.6	25	3.8	P231_0040KX301_0010 MF EZ301U	11	-	51	4.000	4/1	3000	2500	4500	1.2	8.5	-	1.5	4.5
750	6.1	6.4	43	2.2	P231_0040KX301_0010 MF EZ302U	19	-	51	4.000	4/1	3000	2500	4500	1.3	8.5	-	1.5	5.1
750	7.9	8.4	56	1.7	P231_0040KX301_0010 MF EZ303U	25	-	51	4.000	4/1	3000	2500	4500	1.5	8.5	-	1.5	5.6
750	11	11	76	1.3	P231_0040KX301_0010 MF EZ401U	25	-	51	4.000	4/1	3000	2500	4500	2.0	8.5	-	1.5	7.0
P231KX ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 25 \text{ Nm}$)																		
400	13	14	35	1.2	P231_0050KX301_0030 MF EZ301U	25	-	51	15.00	15/1	3500	3500	6000	0.94	8.0	-	1.6	4.5
500	10	11	28	1.5	P231_0040KX301_0030 MF EZ301U	25	-	51	12.00	12/1	3500	3500	6000	0.94	8.5	-	1.5	4.5
P331KX ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 69 \text{ Nm}$)																		
100	27	27	31	1.4	P331_0100KX301_0030 MF EZ301U	60	60	120	30.00	30/1	3500	3500	6000	0.94	5.0	3.0	4.0	5.3
125	21	22	22	1.9	P331_0080KX301_0030 MF EZ301U	63	64	126	24.00	24/1	3500	3500	6000	0.94	5.5	3.5	4.1	5.3
125	36	39	38	1.1	P331_0080KX301_0030 MF EZ302U	63	65	126	24.00	24/1	3500	3500	6000	1.0	5.5	3.5	4.1	5.9
143	19	19	17	2.4	P331_0070KX301_0030 MF EZ301U	56	56	138	21.00	21/1	3500	3500	6000	0.94	5.5	3.5	4.2	5.3
143	32	34	30	1.4	P331_0070KX301_0030 MF EZ302U	69	75	138	21.00	21/1	3500	3500	6000	1.0	5.5	3.5	4.2	5.9
143	42	44	39	1.1	P331_0070KX301_0030 MF EZ303U	69	75	138	21.00	21/1	3500	3500	6000	1.1	5.5	3.5	4.2	6.4
150	18	18	28	2.0	P331_0100KX301_0020 MF EZ301U	54	54	120	20.00	20/1	3500	3000	5500	1.0	5.0	3.0	4.0	5.3
150	30	32	48	1.2	P331_0100KX301_0020 MF EZ302U	60	60	120	20.00	20/1	3500	3000	5500	1.1	5.0	3.0	4.0	5.9
188	14	15	20	2.8	P331_0080KX301_0020 MF EZ301U	43	43	126	16.00	16/1	3500	3000	5500	1.0	5.5	3.5	4.1	5.3
188	24	26	35	1.6	P331_0080KX301_0020 MF EZ302U	63	65	126	16.00	16/1	3500	3000	5500	1.1	5.5	3.5	4.1	5.9
188	32	33	45	1.3	P331_0080KX301_0020 MF EZ303U	63	65	126	16.00	16/1	3500	3000	5500	1.2	5.5	3.5	4.1	6.4
200	13	14	13	3.2	P331_0050KX301_0030 MF EZ301U	40	40	129	15.00	15/1	3500	3500	6000	0.94	6.0	4.0	3.8	5.3
200	23	24	23	1.9	P331_0050KX301_0030 MF EZ302U	63	63	129	15.00	15/1	3500	3500	6000	1.0	6.0	4.0	3.8	5.9
200	30	31	29	1.4	P331_0050KX301_0030 MF EZ303U	63	63	129	15.00	15/1	3500	3500	6000	1.2	6.0	4.0	3.8	6.4
200	40	43	40	1.1	P331_0050KX301_0030 MF EZ401U	63	63	129	15.00	15/1	3500	3500	6000	1.7	6.0	4.0	3.8	7.8
214	12	13	16	3.6	P331_0070KX301_0020 MF EZ301U	37	37	138	14.00	14/1	3500	3000	5500	1.0	5.5	3.5	4.2	5.3
214	21	22	27	2.1	P331_0070KX301_0020 MF EZ302U	67	67	138	14.00	14/1	3500	3000	5500	1.1	5.5	3.5	4.2	5.9
214	28	29	35	1.6	P331_0070KX301_0020 MF EZ303U	69	75	138	14.00	14/1	3500	3000	5500	1.2	5.5	3.5	4.2	6.4
214	37	40	48	1.2	P331_0070KX301_0020 MF EZ401U	69	75	138	14.00	14/1	3500	3000	5500	1.7	5.5	3.5	4.2	7.8
250	11	11	13	3.2	P331_0040KX301_0030 MF EZ301U	32	32	103	12.00	12/1	3500	3500	6000	0.95	6.5	4.5	3.3	5.3
250	18	19	23	1.9	P331_0040KX301_0030 MF EZ302U	50	50	103	12.00	12/1	3500	3500	6000	1.0	6.5	4.5	3.3	5.9
250	24	25	29	1.4	P331_0040KX301_0030 MF EZ303U	50	50	103	12.00	12/1	3500	3500	6000	1.2	6.5	4.5	3.3	6.4
250	32	34	40	1.1	P331_0040KX301_0030 MF EZ401U	50	50	103	12.00	12/1	3500	3500	6000	1.7	6.5	4.5	3.3	7.8
300	8.9	9.1	12	4.8	P331_0050KX301_0020 MF EZ301U	27	27	129	10.00	10/1	3500	3000	5500	1.0	6.0	4.0	3.8	5.3
300	15	16	20	2.8	P331_0050KX301_0020 MF EZ302U	48	48	129	10.00	10/1	3500	3000	5500	1.1	6.0	4.0	3.8	5.9
300	20	21	27	2.1	P331_0050KX301_0020 MF EZ303U	63	63	129	10.00	10/1	3500	3000	5500	1.2	6.0	4.0	3.8	6.4
300	27	29	36	1.6	P331_0050KX301_0020 MF EZ401U	63	63	129	10.00	10/1	3500	3000	5500	1.8	6.0	4.0	3.8	7.8
375	7.1	7.3	12	4.8	P331_0040KX301_0020 MF EZ301U	21	21	103	8.000	8/1	3500	3000	5500	1.0	6.5	4.5	3.3	5.3

n ₂	M ₂	M _{2,0}	a _{th}	S	Type	M _{2acc}	M _{2accHT}	M _{2NOT}	i	i _{exakt}	n _{1maxDB}		n _{1maxZB}	J ₁	Δφ ₂	Δφ _{2red}	C ₂	m
											EL1,2,5,6	EL3,4						
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]	[Nm]			[rpm]	[rpm]	[rpm]	[kgcm ²]	[arcmin]	[arcmin]	[Nm/arcmin]	[kg]
P932KX (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 3300 Nm)																		
54	508	582	48	4.5	P932_0280KX701_0020 MF EZ503U	2253	-	6000	56.00	56/1	1800	1800	3500	24	4.5	-	381	80
54	629	755	59	3.6	P932_0280KX701_0020 MF EZ702U	2148	-	6000	56.00	56/1	1800	1800	3500	30	4.5	-	381	83
54	707	838	66	3.2	P932_0280KX701_0020 MF EZ505U	3000	-	6000	56.00	56/1	1800	1800	3500	28	4.5	-	381	83
54	865	1090	81	2.6	P932_0280KX701_0020 MF EZ703U	3000	-	6000	56.00	56/1	1800	1800	3500	38	4.5	-	381	85
54	1116	1583	105	2.0	P932_0280KX701_0020 MF EZ705U	3000	-	6000	56.00	56/1	1800	1800	3500	50	4.5	-	381	90
60	454	519	47	4.6	P932_0250KX701_0020 MF EZ503U	2012	-	6579	50.00	50/1	1800	1800	3500	25	4.5	-	381	80
60	561	674	58	3.7	P932_0250KX701_0020 MF EZ702U	1918	-	6579	50.00	50/1	1800	1800	3500	31	4.5	-	381	83
60	632	749	65	3.3	P932_0250KX701_0020 MF EZ505U	2969	-	6579	50.00	50/1	1800	1800	3500	30	4.5	-	381	83
60	772	973	80	2.7	P932_0250KX701_0020 MF EZ703U	2969	-	6579	50.00	50/1	1800	1800	3500	39	4.5	-	381	85
60	997	1413	103	2.1	P932_0250KX701_0020 MF EZ705U	2969	-	6579	50.00	50/1	1800	1800	3500	51	4.5	-	381	90
75	363	415	47	4.6	P932_0200KX701_0020 MF EZ503U	1609	-	5263	40.00	40/1	1800	1800	3500	27	4.5	-	368	80
75	449	539	58	3.7	P932_0200KX701_0020 MF EZ702U	1535	-	5263	40.00	40/1	1800	1800	3500	33	4.5	-	368	83
75	505	599	65	3.3	P932_0200KX701_0020 MF EZ505U	2375	-	5263	40.00	40/1	1800	1800	3500	31	4.5	-	368	83
75	618	779	80	2.7	P932_0200KX701_0020 MF EZ703U	2375	-	5263	40.00	40/1	1800	1800	3500	41	4.5	-	368	85
75	797	1130	103	2.1	P932_0200KX701_0020 MF EZ705U	2375	-	5263	40.00	40/1	1800	1800	3500	53	4.5	-	368	90
86	540	681	82	4.4	P932_0350KX701_0010 MF EZ703U	2129	-	6600	35.00	35/1	1800	1600	3000	52	4.5	-	391	85
86	698	989	106	3.4	P932_0350KX701_0010 MF EZ705U	3300	-	6600	35.00	35/1	1800	1600	3000	64	4.5	-	391	90
94	290	332	47	4.6	P932_0160KX701_0020 MF EZ503U	1288	-	4211	32.00	32/1	1800	1800	3500	27	4.5	-	348	80
94	359	431	58	3.7	P932_0160KX701_0020 MF EZ702U	1228	-	4211	32.00	32/1	1800	1800	3500	33	4.5	-	348	83
94	404	479	65	3.3	P932_0160KX701_0020 MF EZ505U	1900	-	4211	32.00	32/1	1800	1800	3500	32	4.5	-	348	83
94	494	623	80	2.7	P932_0160KX701_0020 MF EZ703U	1900	-	4211	32.00	32/1	1800	1800	3500	41	4.5	-	348	85
94	638	904	103	2.1	P932_0160KX701_0020 MF EZ705U	1900	-	4211	32.00	32/1	1800	1800	3500	54	4.5	-	348	90
107	558	791	88	4.1	P932_0280KX701_0010 MF EZ705U	2725	-	6000	28.00	28/1	1800	1600	3000	65	4.5	-	381	90
120	498	706	86	4.2	P932_0250KX701_0010 MF EZ705U	2433	-	5789	25.00	25/1	1800	1600	3000	70	4.5	-	381	90
150	399	565	86	4.2	P932_0200KX701_0010 MF EZ705U	1946	-	4632	20.00	20/1	1800	1600	3000	77	4.5	-	368	90
188	319	452	86	4.2	P932_0160KX701_0010 MF EZ705U	1557	-	3705	16.00	16/1	1800	1600	3000	78	4.5	-	348	90
P932KX (n_{1N} = 4000 min⁻¹, M_{2acc,max} = 3000 Nm)																		
48	1981	3435	148	1.1	P932_0280KX701_0030 MF EZ813U	3000	-	6000	84.00	84/1	2100	2100	4000	118	4.5	-	381	108
48	2052	5277	153	1.0	P932_0280KX701_0030 MF EZ815U	3000	-	6000	84.00	84/1	2100	2100	4000	181	4.5	-	381	120
53	1769	3067	148	1.1	P932_0250KX701_0030 MF EZ813U	2969	-	6579	75.00	75/1	2100	2100	4000	118	4.5	-	381	108
53	1832	4712	153	1.0	P932_0250KX701_0030 MF EZ815U	2969	-	6579	75.00	75/1	2100	2100	4000	181	4.5	-	381	120
67	1415	2454	148	1.1	P932_0200KX701_0030 MF EZ813U	2375	-	5263	60.00	60/1	2100	2100	4000	119	4.5	-	368	108
67	1466	3770	153	1.0	P932_0200KX701_0030 MF EZ815U	2375	-	5263	60.00	60/1	2100	2100	4000	182	4.5	-	368	120

10.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

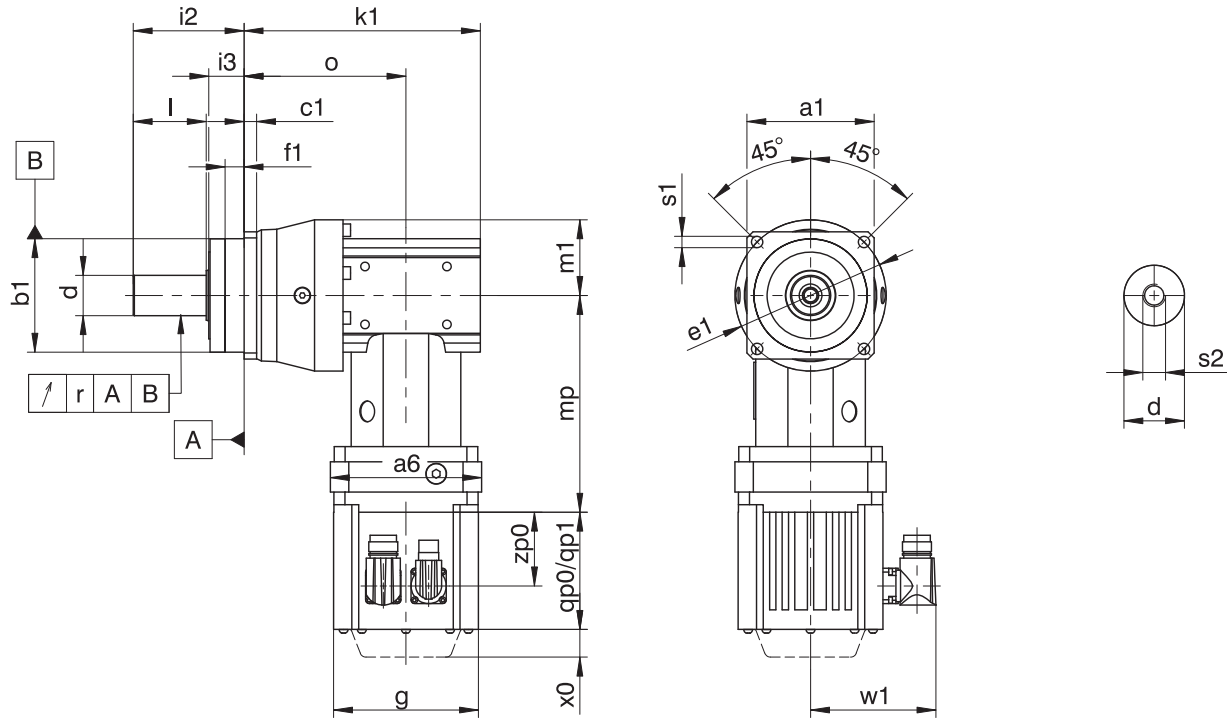
Tolerances

Solid shaft	Tolerance
Fit	ISO k6
Feather keys	DIN 6885-1, high form A
Balancing	With half feather key

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

10.3.1 G shaft design (solid shaft without feather key)



qp0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

qp1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	f1	i2	i3	k1	l	m1	o	r	∅s1	s2
P231_KX301_	55	50 _{h6}	6	12 _{k6}	63	7.0	36	12	124.0	22	31	84.0	-	5.5	M4
P331_KX301_	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	131.0	28	36	91.0	0.025	5.5	M5
P332_KX301_	72	60 _{h6}	7	16 _{k6}	75	7.5	48	18	165.5	28	38	125.5	0.025	5.5	M5
P431_KX401_	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	165.0	36	49	115.0	0.025	6.6	M8
P432_KX301_	76	70 _{h6}	9	22 _{k6}	85	7.5	56	18	180.0	36	50	140.0	0.025	6.6	M8
P531_KX501_	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	187.5	58	58	128.5	0.030	9.0	M12
P532_KX401_	101	90 _{h6}	10	32 _{k6}	120	15.0	88	28	207.0	58	60	157.0	0.030	9.0	M12
P731_KX701_	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	232.5	82	75	158.5	0.035	11.0	M16
P732_KX501_	144	130 _{h6}	15	40 _{k6}	165	3.5	112	27	255.5	82	75	196.5	0.035	11.0	M16
P831_KX701_	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	267.0	82	102	193.0	0.035	13.5	M20
P832_KX701_	190	160 _{h6}	15	55 _{k6}	215	10.0	112	27	324.5	82	102	250.5	0.035	13.5	M20
P932_KX701_	212	180 _{h6}	17	75 _{k6}	250	10.0	143	34	388.0	105	115	314.0	0.040	17.5	M20

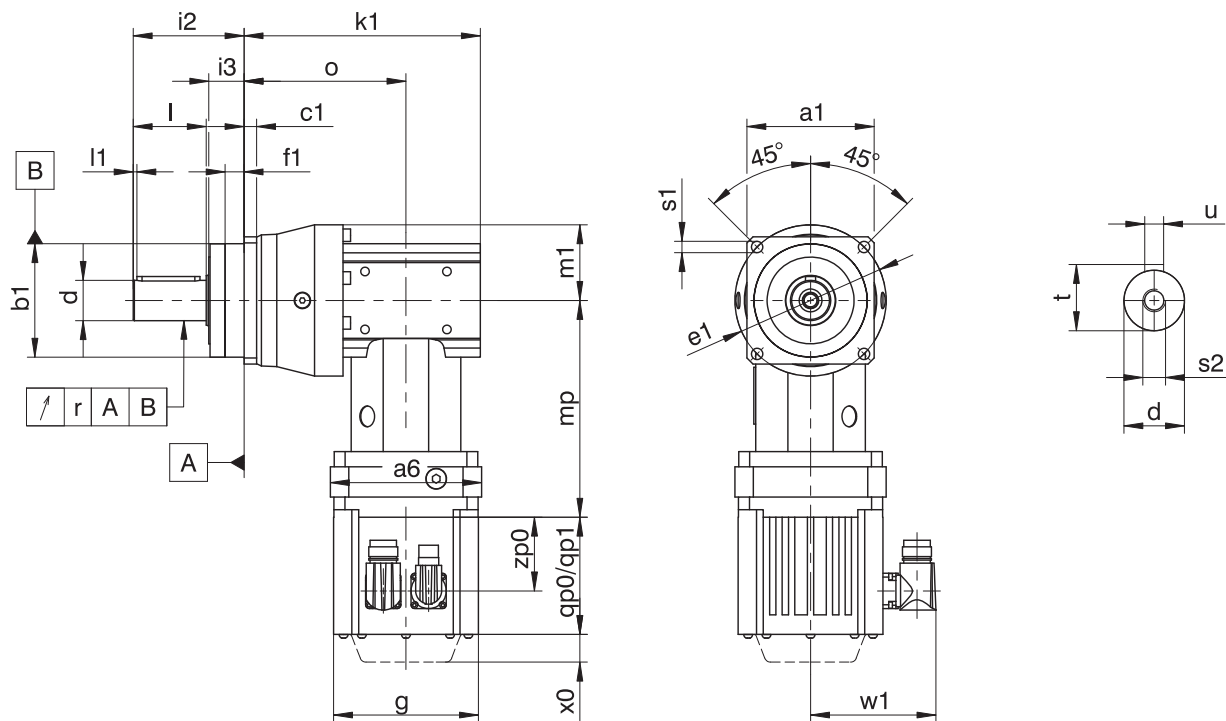
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ3		EZ4		EZ5		EZ7		EZ8	
	□a6	mp	□a6	mp	□a6	mp	□a6	mp	□a6	mp
P231_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P331_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P332_KX301_	75	139.5	–	–	–	–	–	–	–	–
P431_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	–	–
P432_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P531_KX501_	–	–	120	176.5	120	172.0	140	183.0	–	–
P532_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	–	–
P731_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P732_KX501_	–	–	120	176.5	120	172.0	140	183.0	–	–
P831_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P832_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P932_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5

10.3.2 P shaft design (solid shaft with feather key)



qp0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

qp1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	f1	i2	i3	k1	l	l1	m1	o	r	∅s1	s2	t	u
P231_KX301_	55	50 _{h6}	6	12 _{h6}	63	7.0	36	12	124.0	22	2	31	84.0	-	5.5	M4	13.5	A4×4×18
P331_KX301_	72	60 _{h6}	7	16 _{h6}	75	7.5	48	18	131.0	28	2	36	91.0	0.025	5.5	M5	18.0	A5×5×22
P332_KX301_	72	60 _{h6}	7	16 _{h6}	75	7.5	48	18	165.5	28	2	37.5	125.5	0.025	5.5	M5	18.0	A5×5×22
P431_KX401_	76	70 _{h6}	9	22 _{h6}	85	7.5	56	18	165.0	36	3	49	115.0	0.025	6.6	M8	24.5	A6×6×28
P432_KX301_	76	70 _{h6}	9	22 _{h6}	85	7.5	56	18	180.0	36	3	50	140.0	0.025	6.6	M8	24.5	A6×6×28
P531_KX501_	101	90 _{h6}	10	32 _{h6}	120	15.0	88	28	187.5	58	3	57.5	128.5	0.030	9.0	M12	35.0	A10×8×50
P532_KX401_	101	90 _{h6}	10	32 _{h6}	120	15.0	88	28	207.0	58	3	60	157.0	0.030	9.0	M12	35.0	A10×8×50
P731_KX701_	144	130 _{h6}	15	40 _{h6}	165	3.5	112	27	232.5	82	4	75	158.5	0.035	11.0	M16	43.0	A12×8×70
P732_KX501_	144	130 _{h6}	15	40 _{h6}	165	3.5	112	27	255.5	82	4	75	196.5	0.035	11.0	M16	43.0	A12×8×70
P831_KX701_	190	160 _{h6}	15	55 _{h6}	215	10.0	112	27	267.0	82	6	102	193.0	0.035	13.5	M20	59.0	A16×10×70
P832_KX701_	190	160 _{h6}	15	55 _{h6}	215	10.0	112	27	324.5	82	6	102	250.5	0.035	13.5	M20	59.0	A16×10×70
P932_KX701_	212	180 _{h6}	17	75 _{h6}	250	10.0	143	34	388.0	105	7	115	314.0	0.040	17.5	M20	79.5	A20×12×90

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ3		EZ4		EZ5		EZ7		EZ8	
	□a6	mp	□a6	mp	□a6	mp	□a6	mp	□a6	mp
P231_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P331_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P332_KX301_	75	139.5	–	–	–	–	–	–	–	–
P431_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	–	–
P432_KX301_	75	139.5	100	134.0	–	–	–	–	–	–
P531_KX501_	–	–	120	176.5	120	172.0	140	183.0	–	–
P532_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	–	–
P731_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P732_KX501_	–	–	120	176.5	120	172.0	140	183.0	–	–
P831_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P832_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5
P932_KX701_	–	–	–	–	150	214.5	150	217.5	190	242.5

10.4 Type designation

In this chapter, you can find an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

P	7	3	1	S	G	S	S	0050	KX701VF	0030	MF	EZ703U
---	---	---	---	---	---	---	---	------	---------	------	----	--------

Explanation

Code	Designation	Design
P	Type	Planetary gearbox
7	Size	7 (example)
3	Generation	Generation 3
1	Stages	Single-stage
2		Two-stage
S	Housing	Standard
G	Shaft	Solid shaft without feather key
P		Solid shaft with feather key
S	Bearing	Standard bearing
D		Axially reinforced bearing (P3 – P9)
Z		Radially reinforced bearing (P3 – P9) ¹
S	Backlash	Standard
R		Reduced
0050	Transmission ratio of output (i x 10)	i = 5 (example)
KX701 VF	Input	KX7 right-angle geared motor (example)
0030	Transmission ratio of input (i x 10)	i = 3 (example)
MF	Motor adapter	Motor adapter with FlexiAdapt coupling
EZ703U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5]
- Mounting position, see the chapter [▶ 10.5.3]
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 10.6.3]
- Position of the plug connectors, see the chapter [▶ 10.5.5]
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 10.6.4]

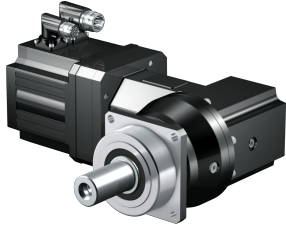
To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1].

10.5 Product description

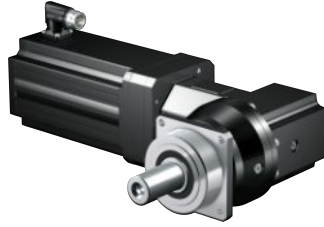
10.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

LM Lean motor



Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

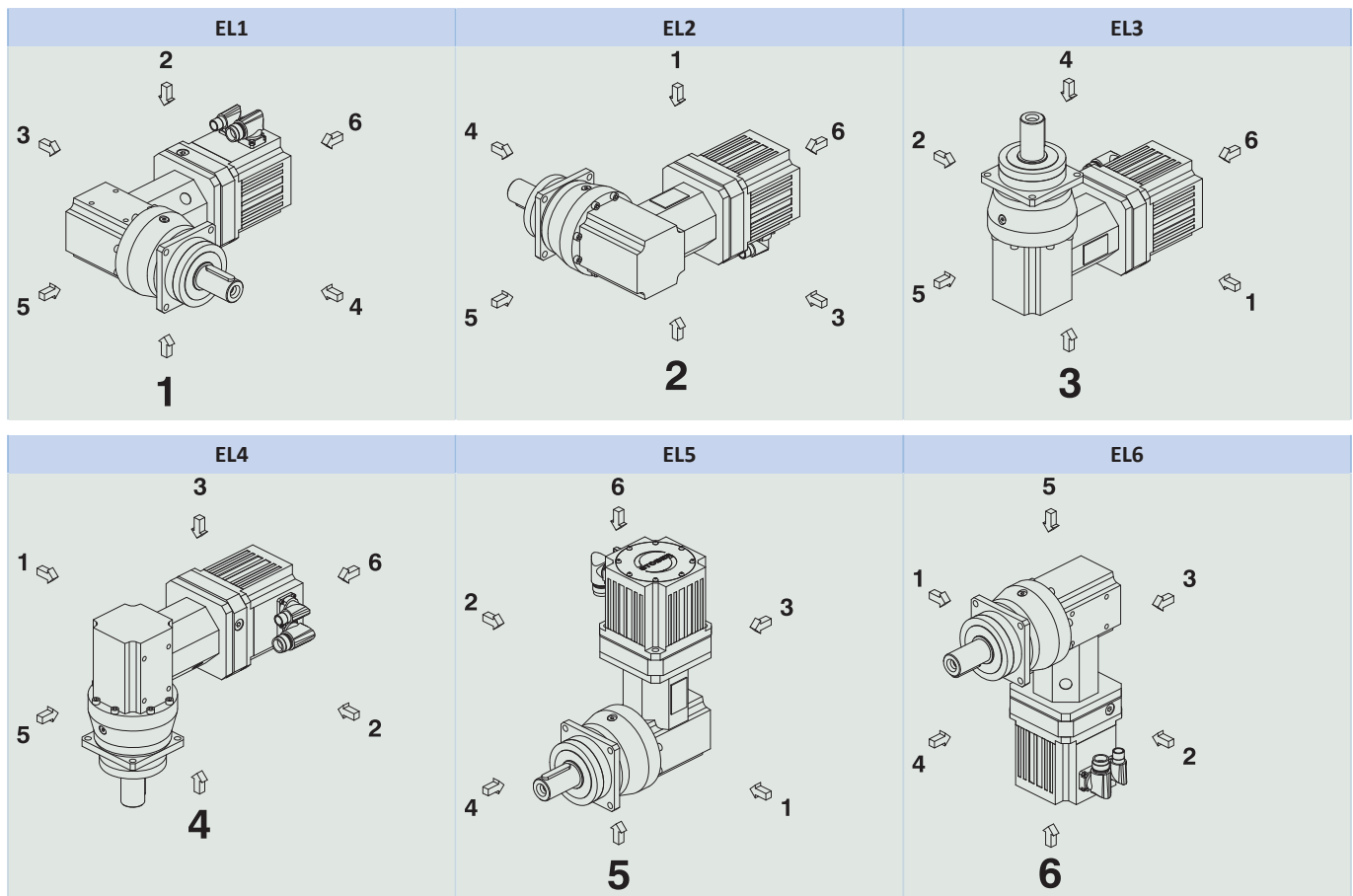
10.5.2 Installation conditions

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 12.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

10.5.3 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

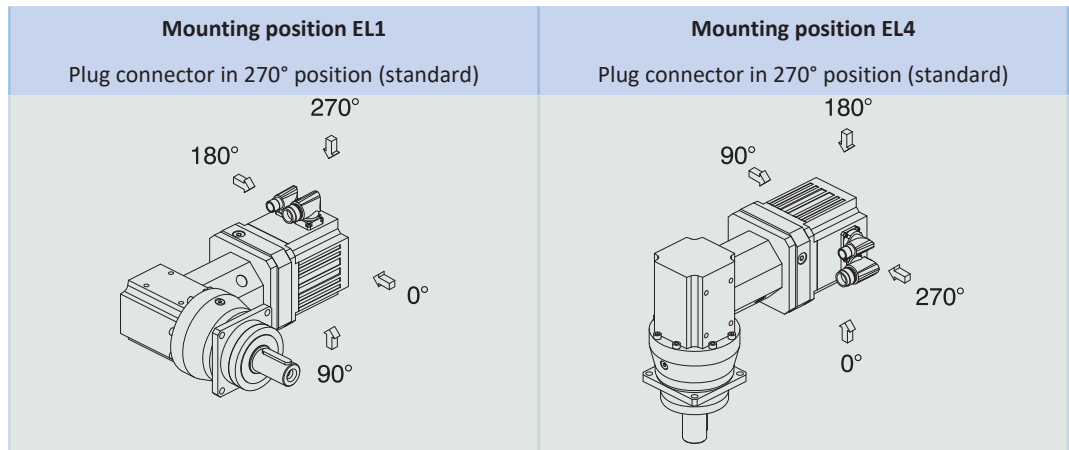
10.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

10.5.5 Position of the plug connectors



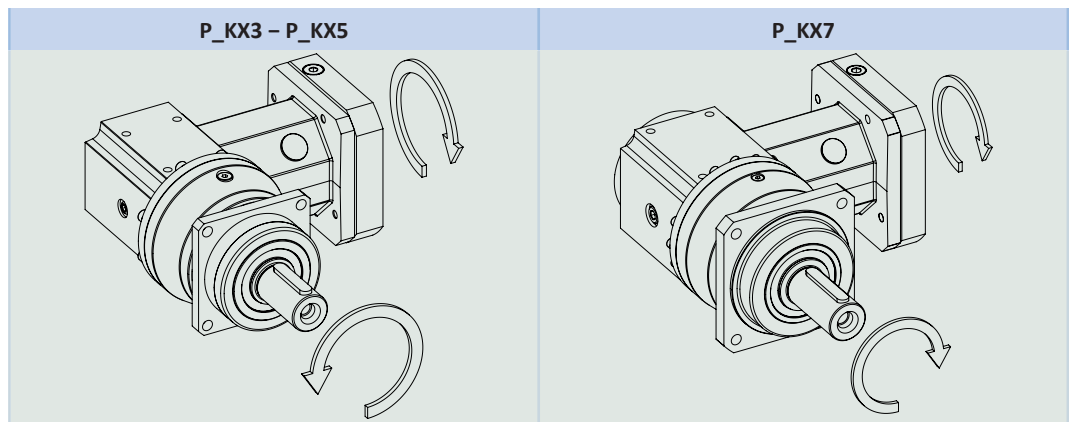
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

10.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	96%
η_{get} three-stage	94%
Protection class:²	
Gearbox	IP65
Motor	IP56, optionally IP66

10.5.7 Direction of rotation



The figures show mounting position EL1.

²Observe the protection class of all the components.

10.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

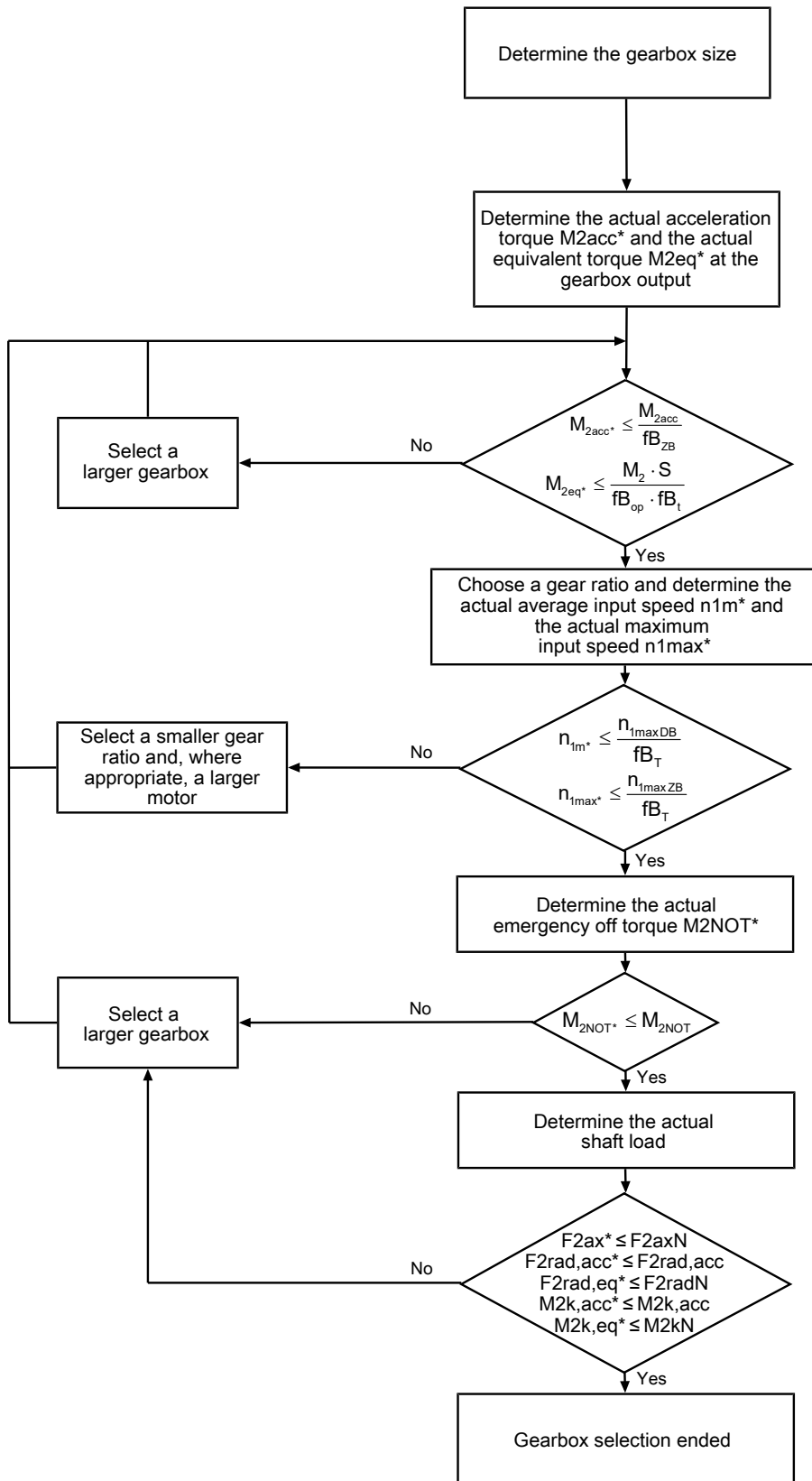
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

10.6.1 Drive selection

Drive selection for gearboxes

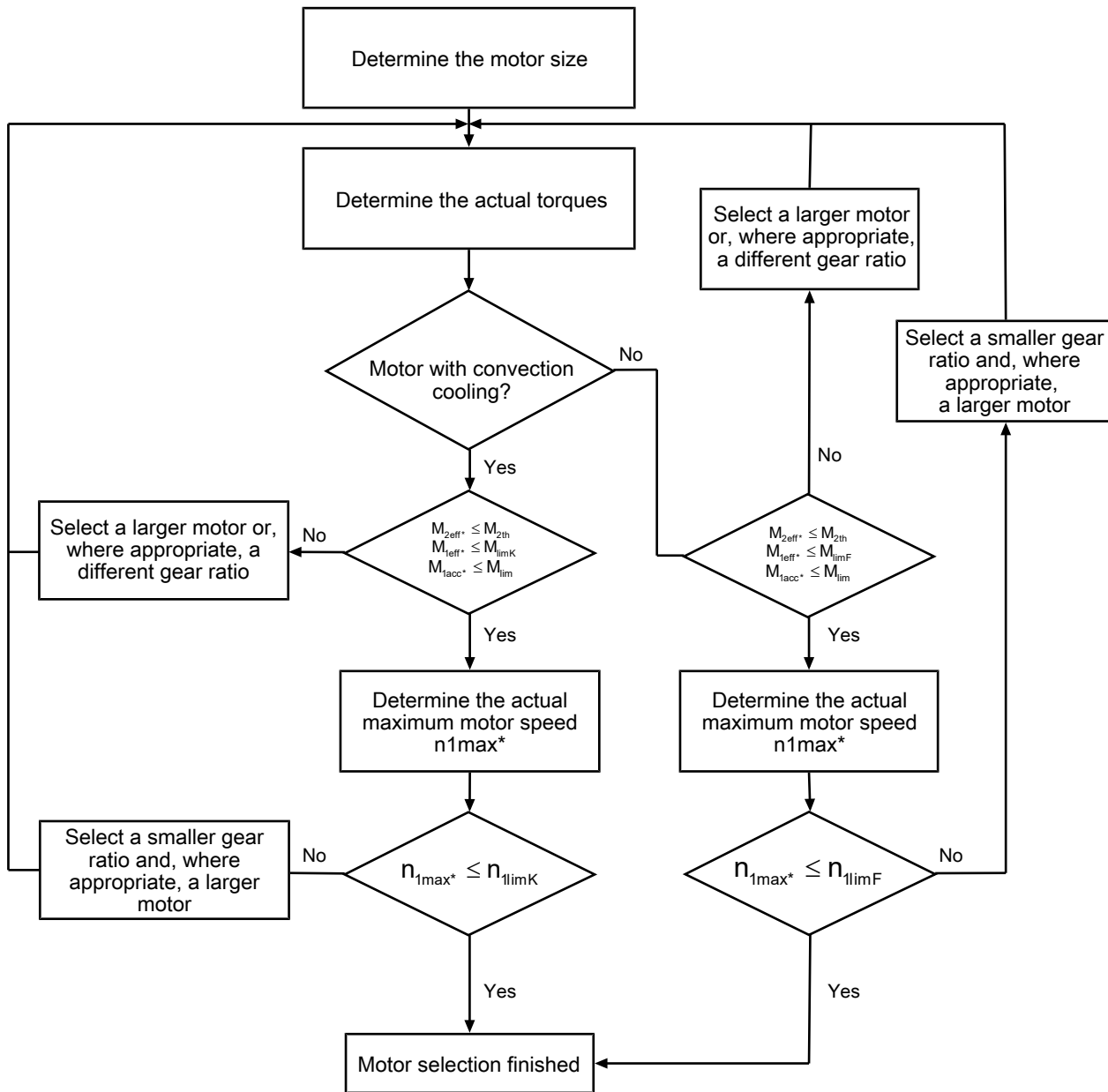


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for fB_T , fB_{op} , fB_t and fB_{ZB} can be found in the corresponding tables in this chapter.

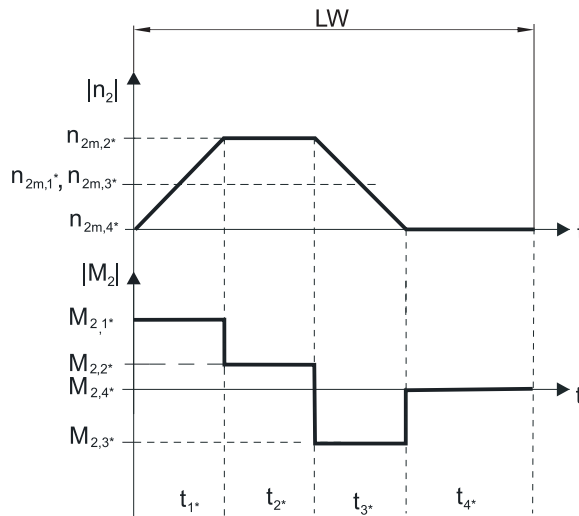
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |M_{2,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |M_{2,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

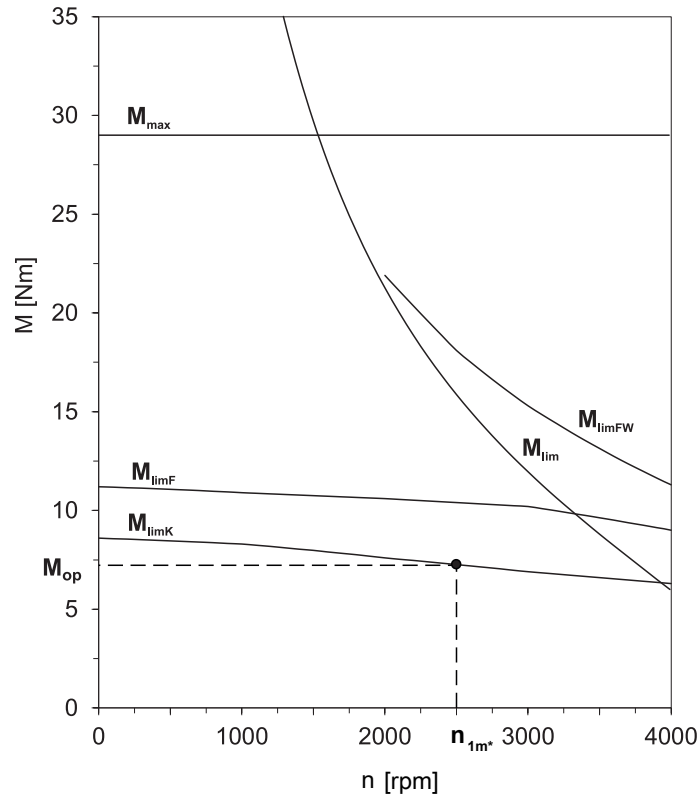
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,9 - \frac{a_{th}}{1000} \cdot a_{thEL} \cdot f_{B_T} \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2, 5, 6	1.0
EL3, 4	1.1
Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

10.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P2	17.0	500	1200	1300	34	36
P3	17.5	1000	2500	2500	79	79
P4	18.5	1500	4000	4500	146	164
P5	19.5	2300	6500	7000	315	340
P7	23.0	2900	8500	9000	544	576
P8	24.5	4700	13000	18000	852	1179
P9	33.0	6000	18000	27000	1539	2309

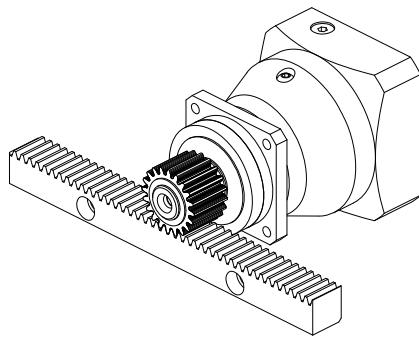


Fig. 1: Recommendation for bearing assignment S (e.g. for straight-cut gearing)

Permitted shaft loads for axially reinforced bearing D

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	20.0	2500	2750	2750	94	94
P4	22.5	4000	4500	5000	182	203
P5	25.5	6000	7000	8000	382	436
P7	29.0	10000	9500	10000	665	700
P8	32.0	15500	15000	18000	1095	1314
P9	44.0	25000	20000	30000	1930	2895

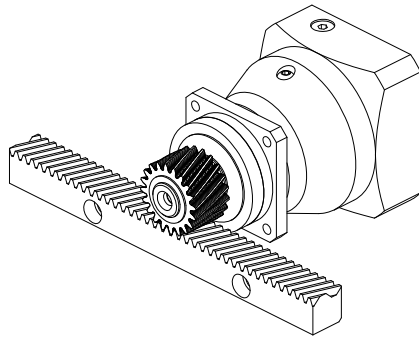


Fig. 2: Recommendation for bearing assignment D (e.g. for helical gearing)

Permitted shaft loads for radially reinforced bearing Z

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	17.5	600	3000	3000	95	95
P4	18.5	1000	5000	5000	183	183
P5	19.5	1600	8000	8000	388	388
P7	23.0	2000	10000	10000	640	640
P8	24.5	3600	18000	18000	1179	1179
P9	33.0	5000	27000	35000	2309	2993

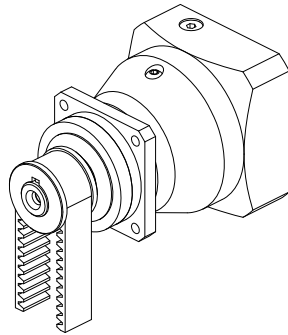


Fig. 3: Recommendation for bearing assignment Z (e.g. for belt drives)

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

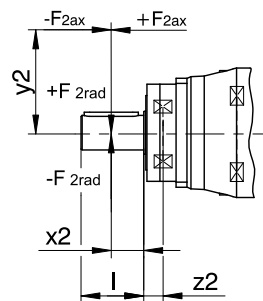


Fig. 4: Force application points

The specified values for $F_{2rad100}$ and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$L_{10h} > 10000$ h with $1 < M_{2kN}/M_{2k^*} < 1.25$

$L_{10h} > 20000$ h with $1.25 < M_{2kN}/M_{2k^*} < 1.5$

$L_{10h} > 30000$ h with $1.5 < M_{2kN}/M_{2k^*}$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

10.6.3 Recommendation for radial shaft seal rings

For a duty cycle > 60% and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

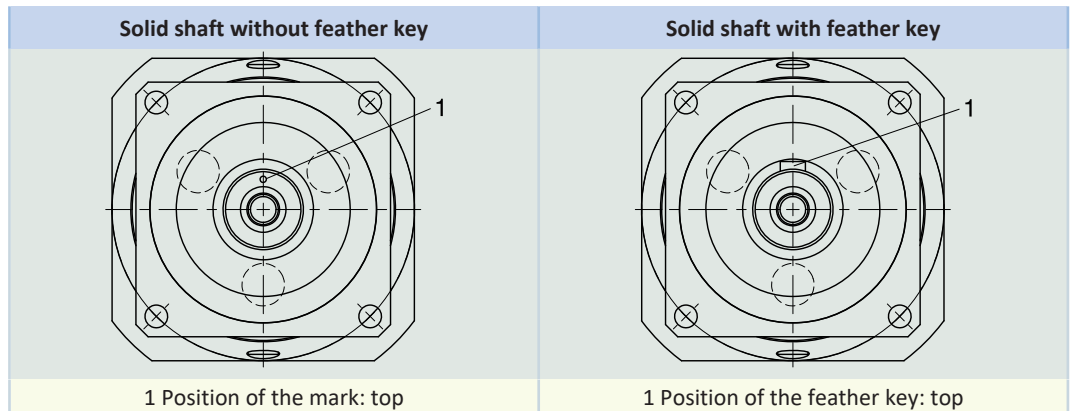
- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

10.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below. The images show the center position of reverse operation. Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Notes

- If you use the solid shaft without a feather key (G), you must note the position of the mark during assembly.
- As an alternative, you can use the solid shaft with a feather key (P). In that case, the feather key functions for position orientation. For a backlash-free connection, also use a clamp.

10.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

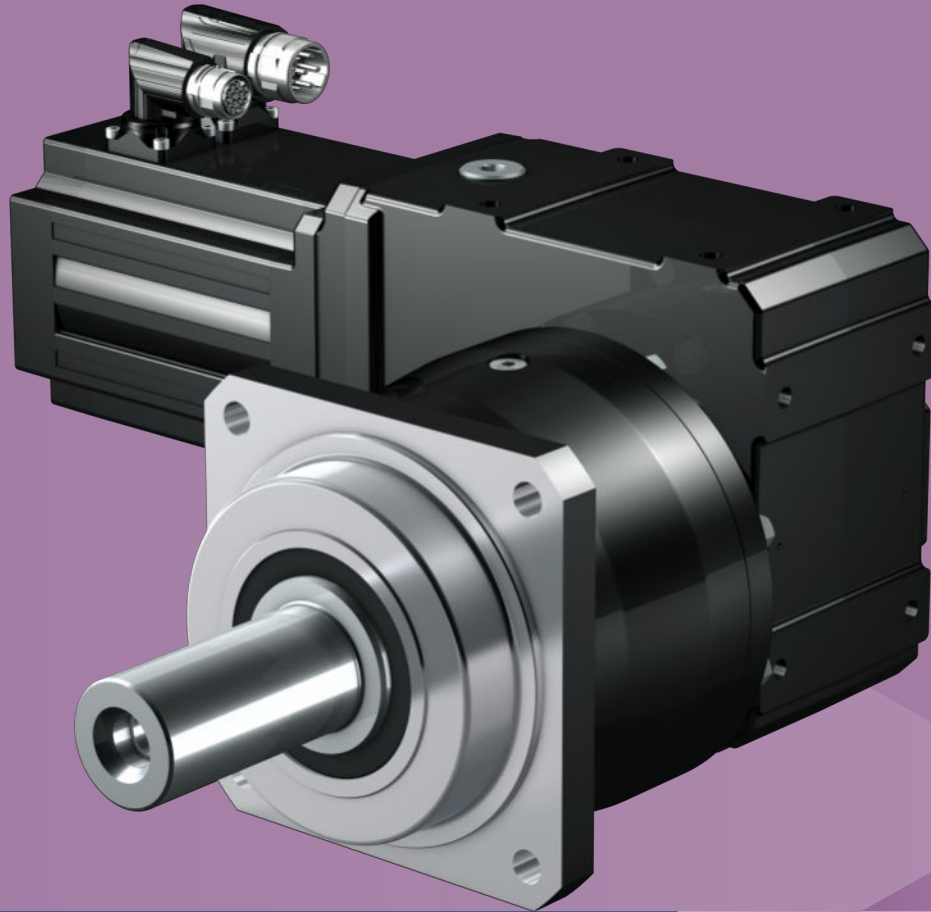
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors P23KX – P93KX	443361_en

11 PK right-angle planetary geared motors

Table of contents

11.1 Overview	302
11.2 Selection tables	303
11.3 Dimensional drawings	319
11.3.1 G shaft design (solid shaft without feather key)	320
11.3.2 P shaft design (solid shaft with feather key)	322
11.4 Type designation	323
11.5 Product description	324
11.5.1 Input options	324
11.5.2 Installation conditions	324
11.5.3 Mounting positions	324
11.5.4 Lubricants	325
11.5.5 Position of the plug connectors	325
11.5.6 Other product features	325
11.5.7 Direction of rotation	325
11.6 Project configuration	326
11.6.1 Drive selection	327
11.6.2 Permitted shaft loads for the output shaft	331
11.6.3 Recommendation for radial shaft seal rings	333
11.6.4 Reverse operation	334
11.7 Additional documentation	334



11

Right-angle planetary geared motors

PK

11.1 Overview

Helical-gear precision right-angle planetary geared motors

Features

Power density	★★★★☆
Backlash	★★★★★
Price category	€€€
Shaft load	★★★★☆
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
Continuous operation without cooling	✓
Reinforced output bearing	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	12 – 555
M_{2acc}	68 – 3105 Nm
$\Delta\phi_2$	1.5 – 5 arcmin
η_{get}	94 %

11.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

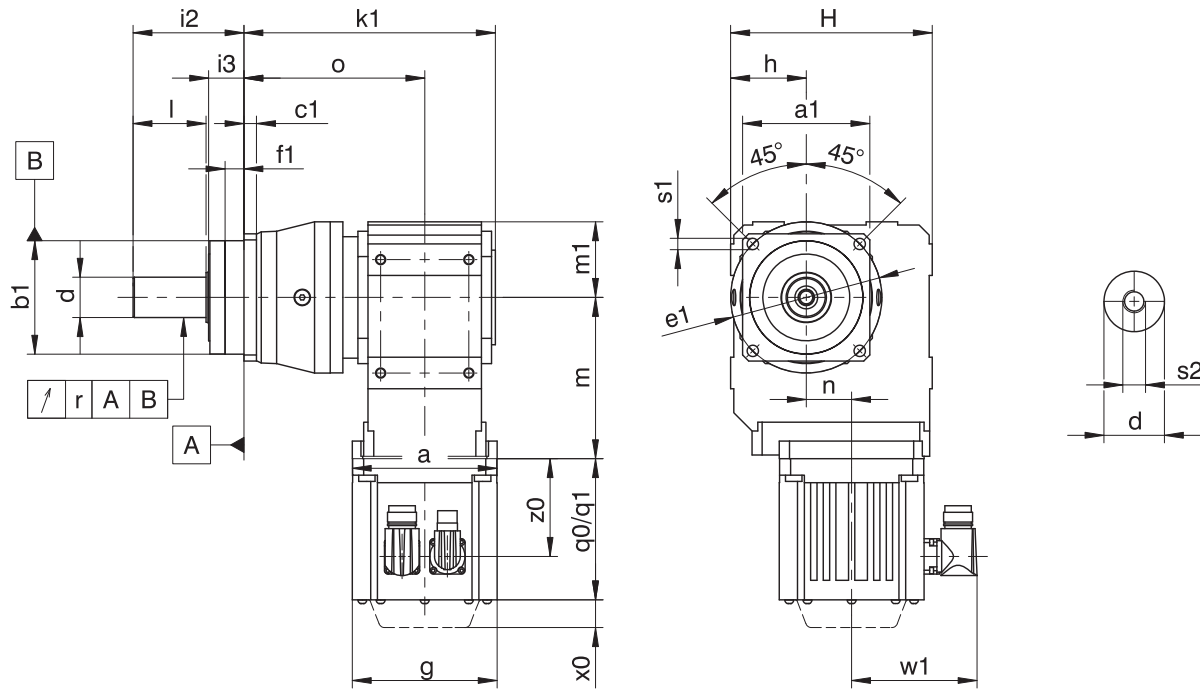
Tolerances

Solid shaft	Tolerance
Fit	ISO k6
Feather keys	DIN 6885-1, high form A
Balancing	With half feather key

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

11.3.1 G shaft design (solid shaft without feather key)



- q0 Applies to motors without brake.
 - q1 Applies to motors with brake.
 - x0 Applies to encoders using an optical measuring method.
 - w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)
- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	f1	h	H	i2	i3	k1	l	m1	o	r	∅s1	s2
P531_K102_	101	90 _{h6}	10	32 _{k6}	120	15.0	60	160	88	28	199.5	58	60.0	143.5	0.030	9.0	M12
P731_K102_	144	130 _{h6}	15	40 _{k6}	165	3.5	60	160	112	27	212.5	82	75.0	156.5	0.035	11.0	M16
P731_K202_	144	130 _{h6}	15	40 _{k6}	165	3.5	65	190	112	27	240.5	82	75.0	170.5	0.035	11.0	M16
P831_K202_	190	160 _{h6}	15	55 _{k6}	215	10.0	65	190	112	27	277.5	82	102.0	207.5	0.035	13.5	M20
P831_K302_	190	160 _{h6}	15	55 _{k6}	215	10.0	75	213	112	27	291.0	82	102.0	215.0	0.035	13.5	M20
P931_K402_	212	180 _{h6}	17	75 _{k6}	250	10.0	90	240	143	34	350.5	105	115.0	260.5	0.040	17.5	M20

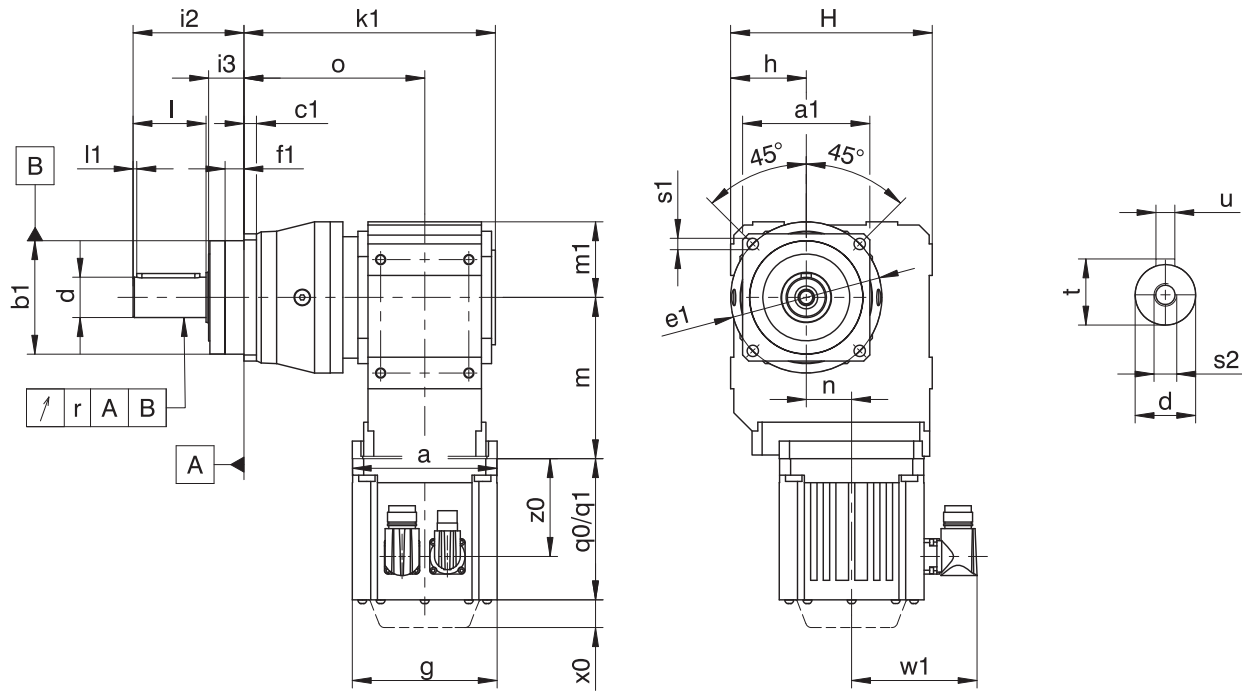
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
P531_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
P731_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
P731_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
P831_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
P831_K302_	–	–	–	∅140	163	52.5	□115	167	52.5	□145	169	52.5	–	–	–
P931_K402_	–	–	–	–	–	–	∅160	187	60.0	□145	189	60.0	□190	192	60.0

11.3.2 P shaft design (solid shaft with feather key)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- The radial runout specification applies only to the reinforced bearing D.

Dimensions of gearboxes

Type	□a1	∅b1	c1	∅d	∅e1	f1	h	H	i2	i3	k1	l	l1	m1	o	r	∅s1	s2	t	u
P531_K102_	101	90 _{h6}	10	32 _{k6}	120	15.0	60	160	88	28	199.5	58	3	60.0	143.5	0.030	9.0	M12	35.0	A10×8×50
P731_K102_	144	130 _{h6}	15	40 _{k6}	165	3.5	60	160	112	27	212.5	82	4	75.0	156.5	0.035	11.0	M16	43.0	A12×8×70
P731_K202_	144	130 _{h6}	15	40 _{k6}	165	3.5	65	190	112	27	240.5	82	4	75.0	170.5	0.035	11.0	M16	43.0	A12×8×70
P831_K202_	190	160 _{h6}	15	55 _{k6}	215	10.0	65	190	112	27	277.5	82	6	102.0	207.5	0.035	13.5	M20	59.0	A16×10×70
P831_K302_	190	160 _{h6}	15	55 _{k6}	215	10.0	75	213	112	27	291.0	82	6	102.0	215.0	0.035	13.5	M20	59.0	A16×10×70
P931_K402_	212	180 _{h6}	17	75 _{k6}	250	10.0	90	240	143	34	350.5	105	7	115.0	260.5	0.040	17.5	M20	79.5	A20×12×90

Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
P531_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
P731_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
P731_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
P831_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
P831_K302_	–	–	–	∅140	163	52.5	□115	167	52.5	□145	169	52.5	–	–	–
P931_K402_	–	–	–	–	–	–	∅160	187	60.0	□145	189	60.0	□190	192	60.0

11.4 Type designation

In this chapter, you can find an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

P	5	3	1	S	G	S	S	0050	K102VF	0060	EZ401U
---	---	---	---	---	---	---	---	------	--------	------	--------

Explanation

Code	Designation	Design
P	Type	Planetary gearbox
5	Size	5 (example)
3	Generation	Generation 3
1	Stages	Single-stage
S	Housing	Standard
G	Shaft	Solid shaft without feather key
P		Solid shaft with feather key
S	Bearing	Standard bearing
D		Axially reinforced bearing (P3 – P9)
Z		Radially reinforced bearing (P3 – P9) ¹
S	Backlash	Standard
R		Reduced
0050	Transmission ratio of output (i x 10)	i = 5 (example)
K102VF	Input	K1 right-angle geared motor (example)
0060	Transmission ratio of input (i x 10)	i = 6 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- For a detailed type designation of the motor, see the chapter [▶ 17.5]
- For the mounting position, see the chapter [▶ 11.5.3]
- Output gearbox side 3 or 4, see the chapter [▶ 11.5.3]
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 11.6.3]
- Position of the plug connectors, see the chapter [▶ 11.5.5]
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 11.6.4]

To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

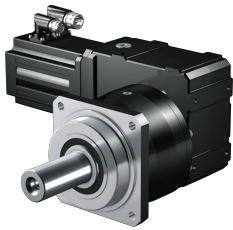
You can find a detailed description of the nameplate in the chapter [▶ 17.5.1].

¹ Not for reduced-backlash option.

11.5 Product description

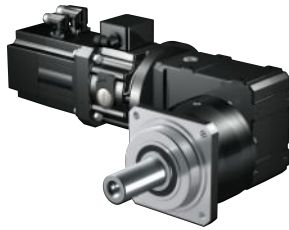
11.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

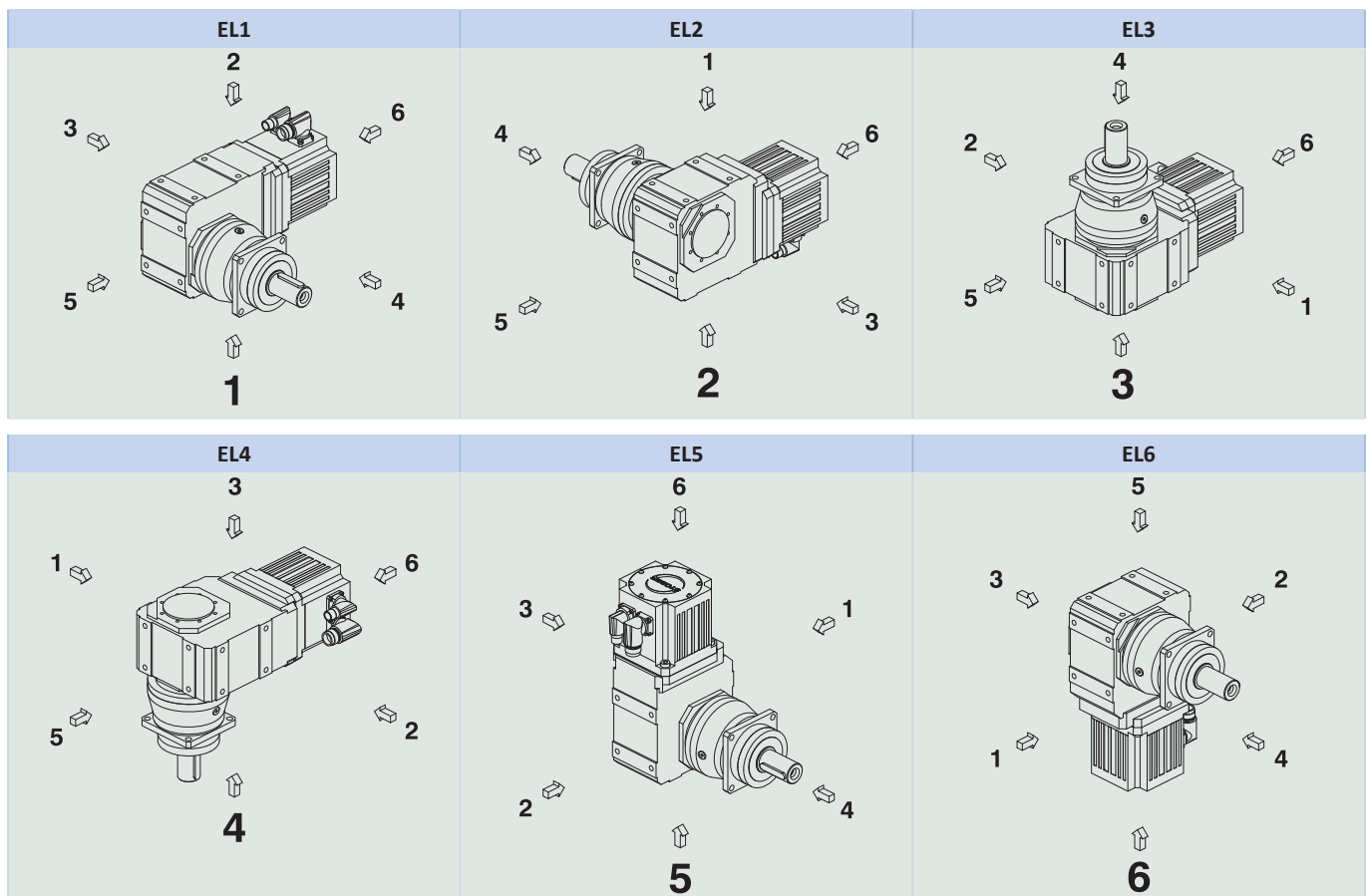
11.5.2 Installation conditions

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 12.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

11.5.3 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

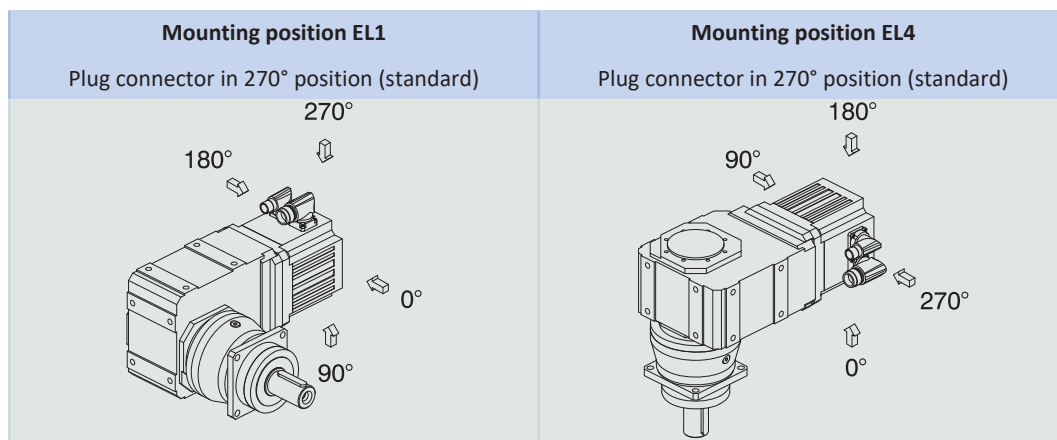
11.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

11.5.5 Position of the plug connectors



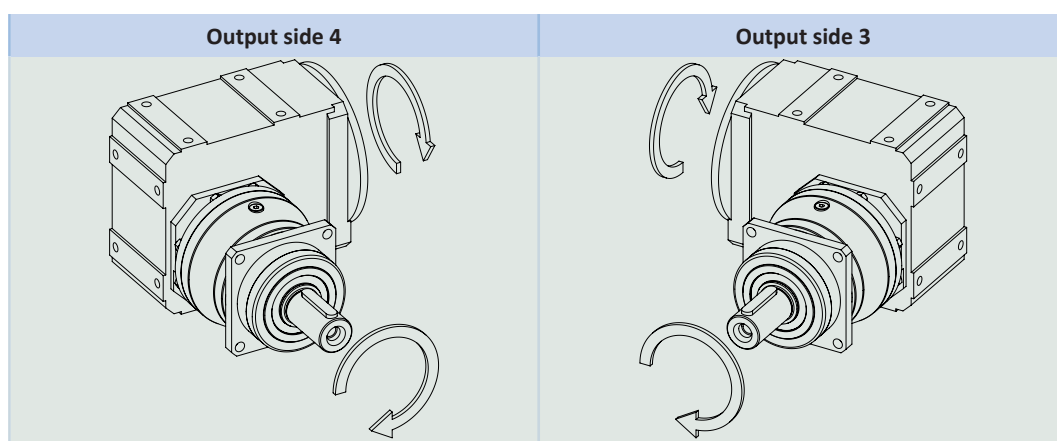
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

11.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} three-stage	94%
Protection class:²	
Gearbox	IP65
Motor	IP56, optionally IP66

11.5.7 Direction of rotation



The pictures show mounting position EL1.

²Observe the protection class of all the components.

11.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

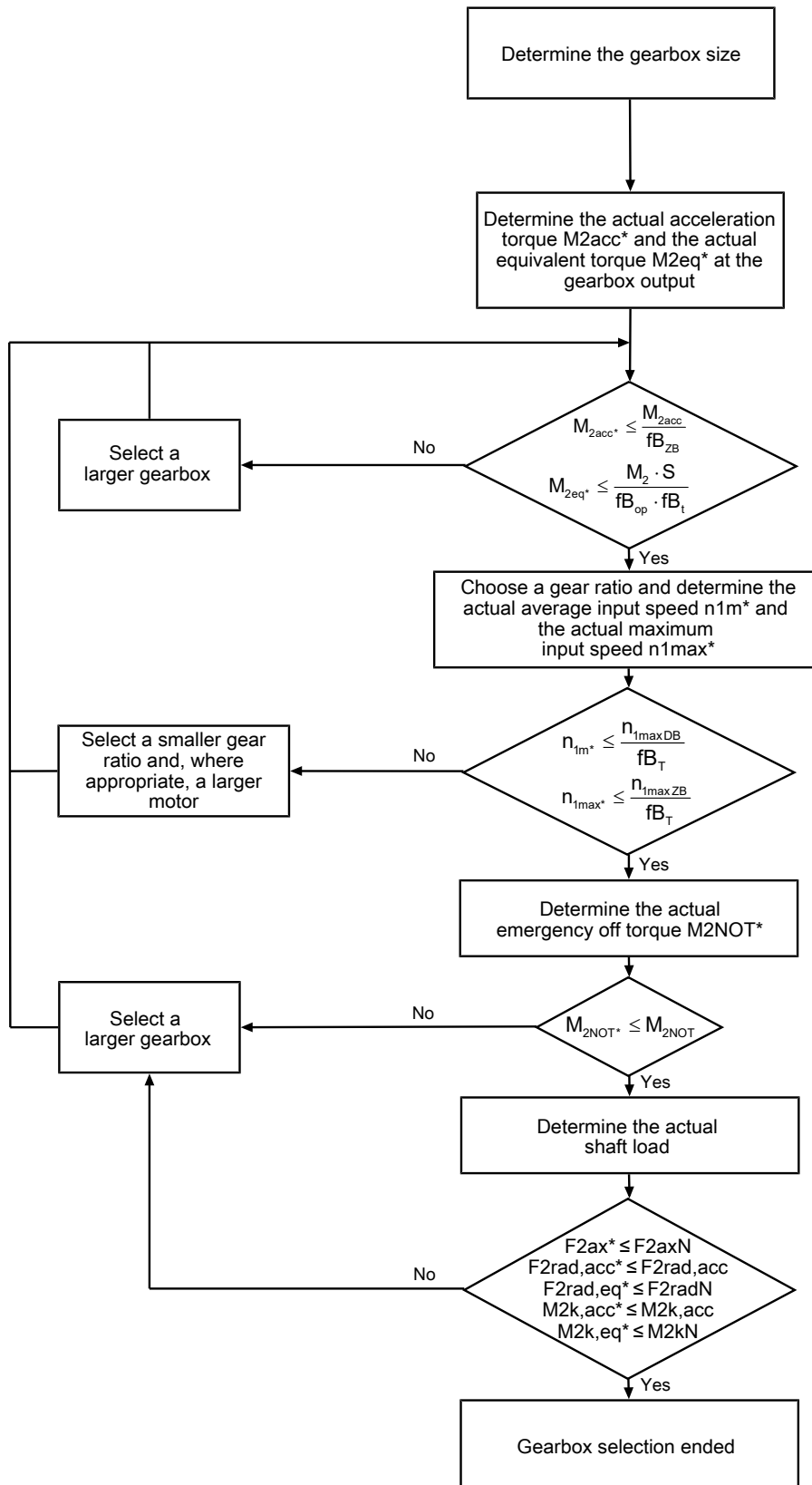
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

11.6.1 Drive selection

Drive selection for gearboxes

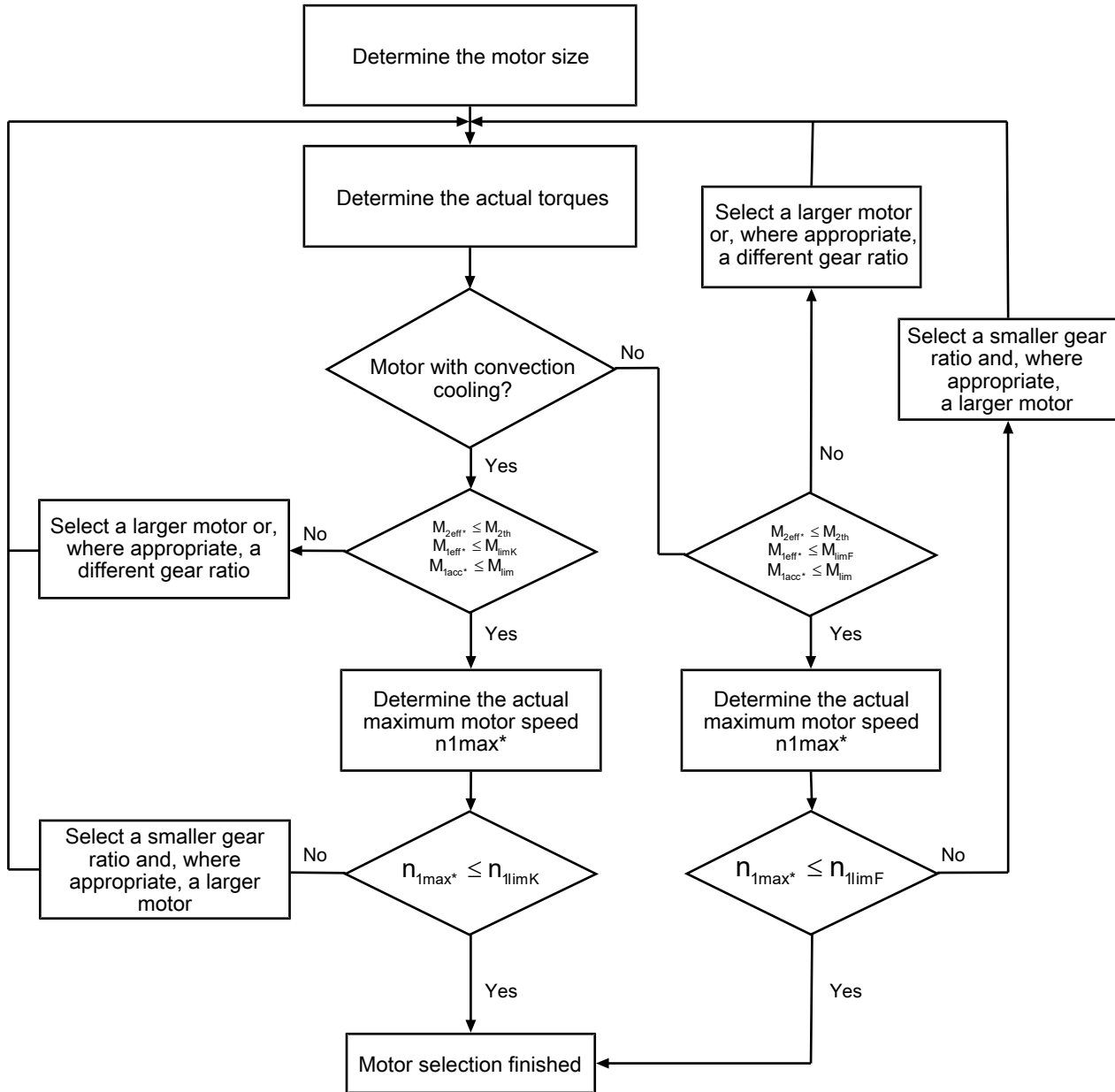


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for fB_T , fB_{op} , fB_t and fB_{ZB} can be found in the corresponding tables in this chapter.

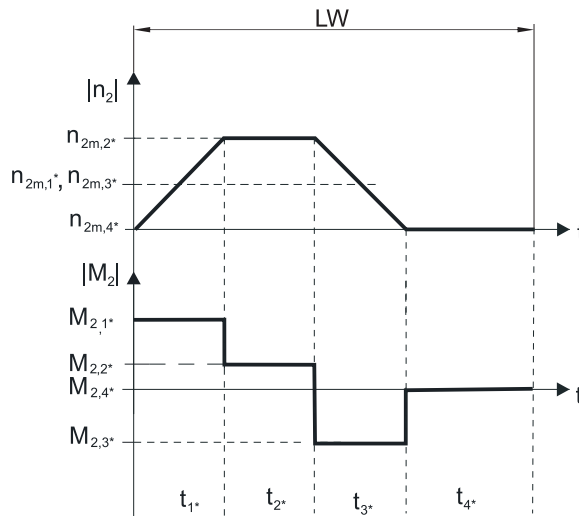
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{limK} and n_{limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:



Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

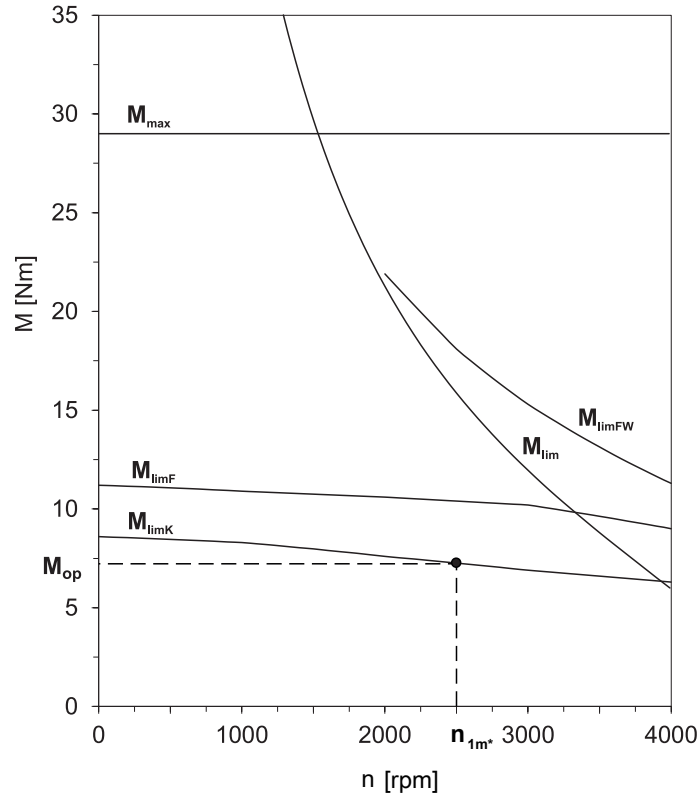
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot athEL \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000} \right)^2$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_r can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2	1.0
EL3, 4, 5, 6	1.1
Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

11.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P2	17.0	500	1200	1300	34	36
P3	17.5	1000	2500	2500	79	79
P4	18.5	1500	4000	4500	146	164
P5	19.5	2300	6500	7000	315	340
P7	23.0	2900	8500	9000	544	576
P8	24.5	4700	13000	18000	852	1179
P9	33.0	6000	18000	27000	1539	2309

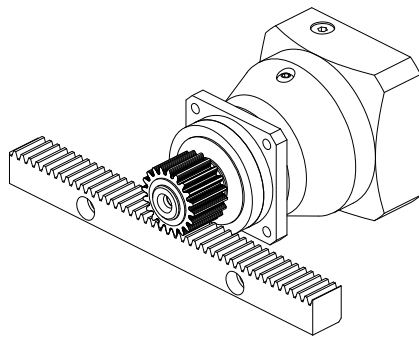


Fig. 1: Recommendation for bearing assignment S (e.g. for straight-cut gearing)

Permitted shaft loads for axially reinforced bearing D

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	20.0	2500	2750	2750	94	94
P4	22.5	4000	4500	5000	182	203
P5	25.5	6000	7000	8000	382	436
P7	29.0	10000	9500	10000	665	700
P8	32.0	15500	15000	18000	1095	1314
P9	44.0	25000	20000	30000	1930	2895

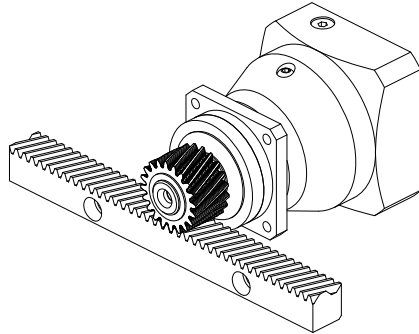


Fig. 2: Recommendation for bearing assignment D (e.g. for helical gearing)

Permitted shaft loads for radially reinforced bearing Z

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
P3	17.5	600	3000	3000	95	95
P4	18.5	1000	5000	5000	183	183
P5	19.5	1600	8000	8000	388	388
P7	23.0	2000	10000	10000	640	640
P8	24.5	3600	18000	18000	1179	1179
P9	33.0	5000	27000	35000	2309	2993

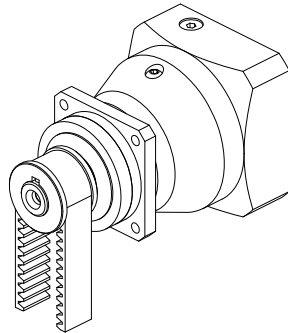


Fig. 3: Recommendation for bearing assignment Z (e.g. for belt drives)

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

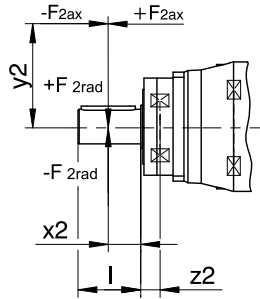


Fig. 4: Force application points

The specified values for $F_{2rad100}$ and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1}| \cdot t_{1^*} + \dots + |n_{2m,n}| \cdot t_{n^*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1}| \cdot t_{1^*} + \dots + |n_{2m,n}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$L_{10h} > 10000$ h with $1 < M_{2kN}/M_{2k^*} < 1.25$

$L_{10h} > 20000$ h with $1.25 < M_{2kN}/M_{2k^*} < 1.5$

$L_{10h} > 30000$ h with $1.5 < M_{2kN}/M_{2k^*}$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

11.6.3 Recommendation for radial shaft seal rings

For a duty cycle $> 60\%$ and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

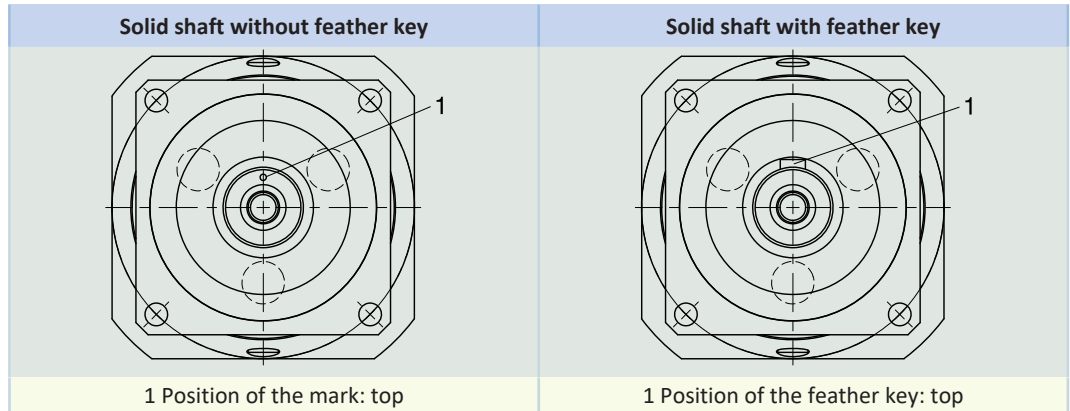
- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

11.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below. The images show the center position of reverse operation. Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Notes

- If you use the solid shaft without a feather key (G), you must note the position of the mark during assembly.
- As an alternative, you can use the solid shaft with a feather key (P). In that case, the feather key functions for position orientation. For a backlash-free connection, also use a clamp.

11.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

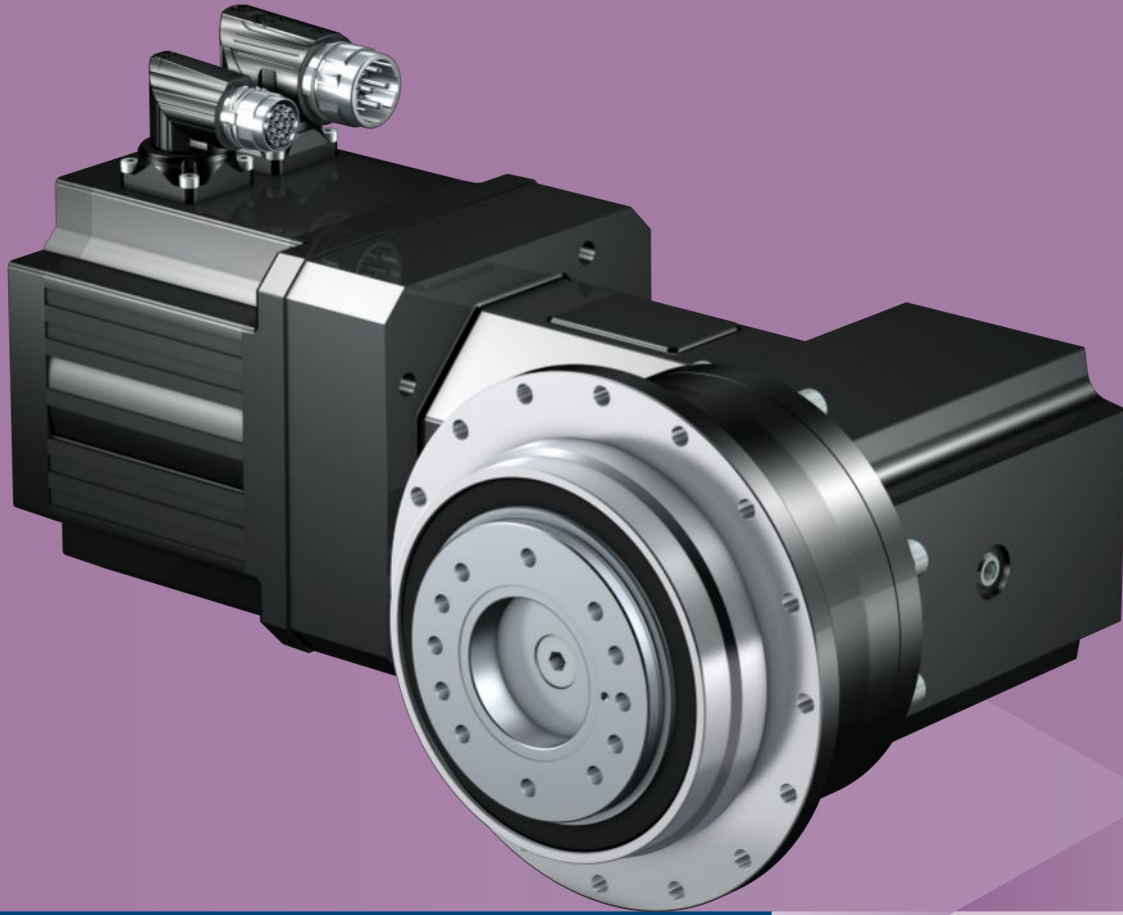
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors P53K – P93K	443360_en

12 PHKX right-angle planetary geared motors

Table of contents

12.1 Overview	336
12.2 Selection tables	337
12.3 Dimensional drawings	351
12.3.1 F shaft design (flange shaft)	352
12.4 Type designation	354
12.5 Product description	355
12.5.1 Input options	355
12.5.2 Installation conditions	355
12.5.3 Mounting positions	355
12.5.4 Lubricants	356
12.5.5 Position of the plug connectors	356
12.5.6 Other product features	356
12.5.7 Direction of rotation	356
12.6 Project configuration	357
12.6.1 Drive selection	358
12.6.2 Permitted shaft loads for the output shaft	362
12.6.3 Recommendation for radial shaft seal rings	363
12.6.4 Reverse operation	364
12.7 Additional documentation	364



12

Right-angle planetary geared motors

PHKX

12.1 Overview

High-performance precision right-angle planetary geared motors

Features

Power density	★★★★★
Backlash	★★★★★
Price category	€€€€
Shaft load	★★★★★
Smooth operation	★★★☆☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★☆☆
Helical gearing	✓
Maintenance-free	✓
Small installation space	✓
Continuous operation without cooling	✓
Stiff output bearings due to pretension	✓
Reinforced output bearing (PH3 – PH5)	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★★★☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	4 – 210
M_{2acc}	26 – 6975 Nm
$\Delta\phi_2$	1 – 6 arcmin
η_{get}	92 – 95 %

12.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to <https://configurator.stoeber.de/en-US/>.

In the case of the version with a reinforced bearing and gear ratios ≤ 5, the maximum permitted input speed n_{1maxZB} is reduced. You can find values at <https://configurator.stoeber.de/en-US/>

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2	M_2	$M_{2,0}$	a_{th}	S	Type	M_{2acc}	M_{2accHT}	M_{2NOT}	i	i_{exakt}	n_{1maxDB}	n_{1maxZB}	J_1	$\Delta\phi_2$	$\Delta\phi_{2red}$	C_2	m	
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]	[Nm]			<small>EL1,2,5,6</small> [rpm]	<small>EL3,4</small> [rpm]	[kgcm ²]	[arcmin]	[arcmin]	[Nm/arcmin]	[kg]	
PH331KX ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 75 \text{ Nm}$)																		
100	26	27	31	1.4	PH331_0100KX301_0030 MF EZ301U	60	60	120	30.00	30/1	3500	3500	6000	0.94	5.0	3.0	7.8	5.0
143	18	19	17	2.4	PH331_0070KX301_0030 MF EZ301U	56	56	150	21.00	21/1	3500	3500	6000	0.94	5.5	3.5	8.4	5.0
143	32	33	30	1.4	PH331_0070KX301_0030 MF EZ302U	75	77	150	21.00	21/1	3500	3500	6000	1.0	5.5	3.5	8.4	5.6
143	41	43	38	1.1	PH331_0070KX301_0030 MF EZ303U	75	77	150	21.00	21/1	3500	3500	6000	1.1	5.5	3.5	8.4	6.1
150	18	18	28	2.0	PH331_0100KX301_0020 MF EZ301U	53	53	120	20.00	20/1	3500	3000	5500	1.0	5.0	3.0	7.8	5.0
150	30	32	48	1.2	PH331_0100KX301_0020 MF EZ302U	60	60	120	20.00	20/1	3500	3000	5500	1.1	5.0	3.0	7.8	5.6
200	13	13	13	3.2	PH331_0050KX301_0030 MF EZ301U	40	40	130	15.00	15/1	3500	3500	6000	0.94	6.0	4.0	6.9	5.0
200	23	24	23	1.9	PH331_0050KX301_0030 MF EZ302U	62	62	130	15.00	15/1	3500	3500	6000	1.0	6.0	4.0	6.9	5.6
200	29	31	29	1.4	PH331_0050KX301_0030 MF EZ303U	62	62	130	15.00	15/1	3500	3500	6000	1.2	6.0	4.0	6.9	6.1
200	40	43	40	1.1	PH331_0050KX301_0030 MF EZ401U	62	62	130	15.00	15/1	3500	3500	6000	1.7	6.0	4.0	6.9	7.5
214	12	13	16	3.7	PH331_0070KX301_0020 MF EZ301U	37	37	150	14.00	14/1	3500	3000	5500	1.0	5.5	3.5	8.4	5.0
214	21	22	27	2.1	PH331_0070KX301_0020 MF EZ302U	66	66	150	14.00	14/1	3500	3000	5500	1.1	5.5	3.5	8.4	5.6
214	27	29	35	1.6	PH331_0070KX301_0020 MF EZ303U	75	77	150	14.00	14/1	3500	3000	5500	1.2	5.5	3.5	8.4	6.1
214	37	40	47	1.2	PH331_0070KX301_0020 MF EZ401U	75	77	150	14.00	14/1	3500	3000	5500	1.7	5.5	3.5	8.4	7.5
300	8.8	9.0	12	4.8	PH331_0050KX301_0020 MF EZ301U	26	26	130	10.00	10/1	3500	3000	5500	1.0	6.0	4.0	6.9	5.0
300	15	16	20	2.8	PH331_0050KX301_0020 MF EZ302U	47	47	130	10.00	10/1	3500	3000	5500	1.1	6.0	4.0	6.9	5.6
300	20	21	27	2.1	PH331_0050KX301_0020 MF EZ303U	62	62	130	10.00	10/1	3500	3000	5500	1.2	6.0	4.0	6.9	6.1
300	26	28	36	1.6	PH331_0050KX301_0020 MF EZ401U	62	62	130	10.00	10/1	3500	3000	5500	1.8	6.0	4.0	6.9	7.5
429	11	11	26	3.7	PH331_0070KX301_0010 MF EZ302U	33	33	150	7.000	7/1	3000	2500	4500	1.3	5.5	3.5	8.4	5.6
429	14	14	33	2.9	PH331_0070KX301_0010 MF EZ303U	46	46	150	7.000	7/1	3000	2500	4500	1.4	5.5	3.5	8.4	6.1
429	19	20	45	2.1	PH331_0070KX301_0010 MF EZ401U	56	56	150	7.000	7/1	3000	2500	4500	2.0	5.5	3.5	8.4	7.5
429	31	34	76	1.3	PH331_0070KX301_0010 MF EZ402U	75	77	150	7.000	7/1	3000	2500	4500	2.7	5.5	3.5	8.4	8.6
600	9.8	10	24	4.0	PH331_0050KX301_0010 MF EZ303U	33	33	115	5.000	5/1	3000	2500	4500	1.5	6.0	4.0	6.9	6.1
600	13	14	32	3.0	PH331_0050KX301_0010 MF EZ401U	40	40	115	5.000	5/1	3000	2500	4500	2.0	6.0	4.0	6.9	7.5
600	22	25	54	1.8	PH331_0050KX301_0010 MF EZ402U	62	62	115	5.000	5/1	3000	2500	4500	2.7	6.0	4.0	6.9	8.6
600	33	41	80	1.2	PH331_0050KX301_0010 MF EZ404U	62	62	115	5.000	5/1	3000	2500	4500	4.1	6.0	4.0	6.9	11
PH331KX ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 75 \text{ Nm}$)																		
200	25	27	33	1.3	PH331_0100KX301_0030 MF EZ301U	60	60	120	30.00	30/1	3500	3500	6000	0.94	5.0	3.0	7.8	5.0
286	18	19	17	2.5	PH331_0070KX301_0030 MF EZ301U	56	56	150	21.00	21/1	3500	3500	6000	0.94	5.5	3.5	8.4	5.0
286	30	33	28	1.5	PH331_0070KX301_0030 MF EZ302U	75	77	150	21.00	21/1	3500	3500	6000	1.0	5.5	3.5	8.4	5.6
286	39	45	36	1.2	PH331_0070KX301_0030 MF EZ303U	75	77	150	21.00	21/1	3500	3500	6000	1.1	5.5	3.5	8.4	6.1
400	13	13	16	2.6	PH331_0050KX301_0030 MF EZ301U	40	40	130	15.00	15/1	3500	3500	6000	0.94	6.0	4.0	6.9	5.0
400	21	24	27	1.6	PH331_0050KX301_0030 MF EZ302U	62	62	130	15.00	15/1	3500	3500	6000	1.0	6.0	4.0	6.9	5.6
400	28	32	35	1.2	PH331_0050KX301_0030 MF EZ303U	62	62	130	15.00	15/1	3500	3500	6000	1.2	6.0	4.0	6.9	6.1
400	33	40	41	1.0	PH331_0050KX301_0030 MF EZ401U	62	62	130	15.00	15/1	3500	3500	6000	1.7	6.0	4.0	6.9	7.5
PH332KX ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 80 \text{ Nm}$)																		
54	48	49	54	1.0	PH332_0280KX301_0020 MF EZ301U	75	75	150	56.00	56/1	3500	3000	5500	1.0	4.5	2.5	12	5.4
60	43	44	49	1.2	PH332_0250KX301_0020 MF EZ301U	80	85	160	50.00	50/1	3500	3000	5500	1.0	4.5	2.5	13	5.4
75	34	35	43	1.3	PH332_0200KX301_0020 MF EZ301U	80	85	160	40.00	40/1	3500	3000	5500	1.0	4.5	2.5	13	5.4
86	30	30	57	1.7	PH332_0350KX301_0010 MF EZ301U	80	85	160	35.00	35/1	3000	2500	4500	1.2	4.5	2.5	13	5.4
PH431KX ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 160 \text{ Nm}$)																		
100	26	27	17	2.8	PH431_0100KX401_0030 MF EZ301U	79	79	230	30.00	30/1	3000	3000	5500	1.6	4.0	2.0	18	9.4
100	45	48	28	1.7	PH431_0100KX401_0030 MF EZ302U	115	115	230	30.00	30/1	3000	3000	5500	1.7	4.0	2.0	18	10
100	59	62	37	1.3	PH431_0100KX401_0030 MF EZ303U	115	115	230	30.00	30/1	3000	3000	5500	1.8	4.0	2.0	18	10
143	18	19	9.7	4.9	PH431_0070KX401_0030 MF EZ301U	56	56	320	21.00	21/1	3000	3000	5500	1.6	4.5	2.5	19	9.4
143	32	33	17	2.9	PH431_0070KX401_0030 MF EZ302U	99	99	320	21.00	21/1	3000	3000	5500	1.7	4.5	2.5	19	10
143	41	43	22	2.2	PH431_0070KX401_0030 MF EZ303U	139	139	320	21.00	21/1	3000	3000	5500	1.9	4.5	2.5	19	10
143	56	60	29	1.6	PH431_0070KX401_0030 MF EZ401U	160	168	320	21.00	21/1	3000	3000	5500	2.4	4.5	2.5	19	12
143	85	93	45	1.1	PH431_0070KX401_0030 MF EZ501U	160	168	320	21.00	21/1	3000	3000	5500	4.4	4.5	2.5	19	13

12.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

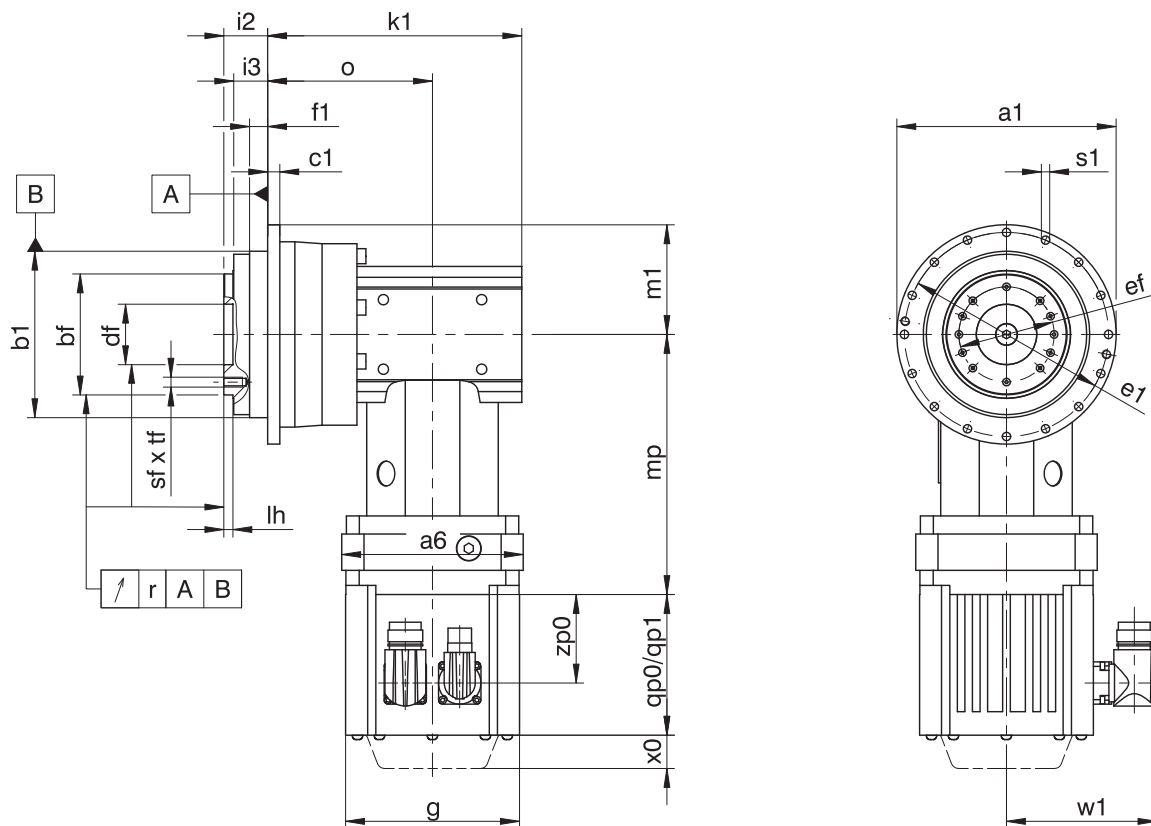
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

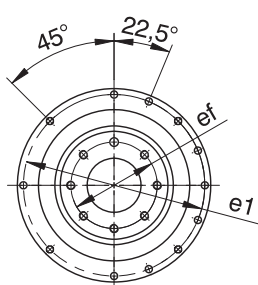
You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

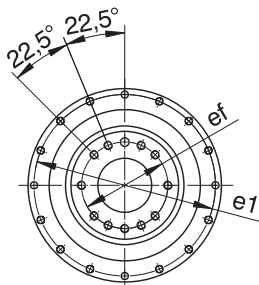
12.3.1 F shaft design (flange shaft)



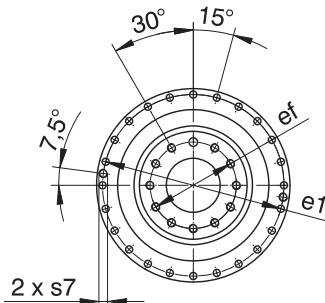
PH3 | PH4



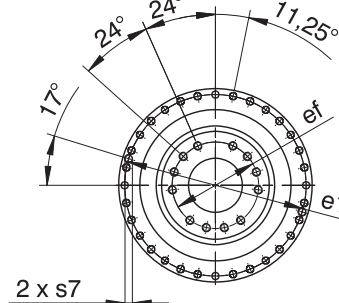
PH5



PH7/PH8



PH9/PH10



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	i2	i3	k1	lh	m1	o	r	Øs1	s7	sf	tf
PH331_KX301_	86	64 _{h7}	40 _{h7}	4	20.0 ^{H6}	79	32	7	19.5	16.5	113.5	4	43.0	73.5	0.020	4.5	-	M5	7
PH332_KX301_	86	64 _{h7}	40 _{h7}	4	20.0 ^{H6}	79	32	7	19.5	16.5	147.0	4	43.0	107.0	0.020	4.5	-	M5	7
PH431_KX401_	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50	10	30.0	24.0	139.0	6	59.0	89.0	0.020	5.5	-	M6	11
PH432_KX301_	118	90 _{h7}	63 _{h7}	7	31.5 ^{H6}	109	50	10	30.0	24.0	161.5	6	59.0	121.5	0.020	5.5	-	M6	11
PH531_KX501_	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63	12	29.0	23.0	168.0	6	72.5	109.0	0.020	5.5	-	M6	11
PH532_KX401_	145	110 _{h7}	80 _{h7}	8	40.0 ^{H6}	135	63	12	29.0	23.0	187.5	6	72.5	137.5	0.020	5.5	-	M6	11
PH731_KX701_	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80	12	38.0	32.0	203.0	6	89.5	129.0	0.025	6.6	-	M8	14
PH732_KX501_	179	140 _{h7}	100 _{h7}	10	50.0 ^{H6}	168	80	12	38.0	32.0	226.0	6	89.5	167.0	0.025	6.6	-	M8	14
PH831_KX701_	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125	15	50.0	42.0	235.5	8	123.5	161.5	0.030	9.0	M10	M10	18
PH832_KX701_	247	200 _{h7}	160 _{h7}	12	80.0 ^{H6}	233	125	15	50.0	42.0	293.0	8	123.5	219.0	0.030	9.0	M10	M10	18
PH942_KX701_	300	255 _{h7}	180 _{h7}	18	90.0 ^{H6}	280	140	20	66.0	55.0	336.0	12	150.0	262.0	0.030	13.5	M8	M16	24
PH1042_KX701_	330	285 _{h7}	200 _{h7}	20	95.0 ^{H6}	310	160	20	75.0	60.0	343.0	10	165.0	269.0	0.040	13.5	M10	M20	28

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0
EZ501U	115	93	147.5	100.0	22	58.5
EZ502U	115	118	172.5	100.0	22	83.5
EZ503U	115	143	197.5	100.0	22	108.5
EZ505U	115	193	247.5	100.0	22	158.5
EZ701U	145	102	161.0	115.0	22	64.0
EZ702U	145	127	186.0	115.0	22	89.0
EZ703U	145	152	211.0	115.0	22	114.0
EZ705U	145	207	266.0	134.0	22	165.0
EZ813U	190	238	315.0	156.5	22	184.0
EZ815U	190	320	397.0	156.5	22	266.0

Dimensions of geared motors

Type	EZ3		EZ4		EZ5		EZ7		EZ8	
	□a6	mp	□a6	mp	□a6	mp	□a6	mp	□a6	mp
PH331_KX301_	75	139.5	100	134.0	-	-	-	-	-	-
PH332_KX301_	75	139.5	-	-	-	-	-	-	-	-
PH431_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	-	-
PH432_KX301_	75	139.5	100	134.0	-	-	-	-	-	-
PH531_KX501_	-	-	120	176.5	120	172.0	140	183.0	-	-
PH532_KX401_	100	151.0	100	145.5	115	150.0	140	153.0	-	-
PH731_KX701_	-	-	-	-	150	214.5	150	217.5	190	242.5
PH732_KX501_	-	-	120	176.5	120	172.0	140	183.0	-	-
PH831_KX701_	-	-	-	-	150	214.5	150	217.5	190	242.5
PH832_KX701_	-	-	-	-	150	214.5	150	217.5	-	-
PH942_KX701_	-	-	-	-	150	214.5	150	217.5	190	242.5
PH1042_KX701_	-	-	-	-	150	214.5	150	217.5	190	242.5

12.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PH	7	3	1	S	F	S	S	0050	KX701VF	0010	MF	EZ703U
----	---	---	---	---	---	---	---	------	---------	------	----	--------

Explanation

Code	Designation	Design
PH	Type	Planetary gearbox
7	Size	7 (example)
3	Generation	Generation 3
4		Generation 4
1	Stages	Single-stage
2		Two-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
V		Reinforced bearing (PH3 – PH5)
S	Backlash	Standard
R		Reduced (PH3 – PH9)
0050	Transmission ratio of output (i x 10)	i = 5 (example)
KX701 VF	Input	KX7 right-angle geared motor (example)
0010	Transmission ratio of input (i x 10)	i = 1 (example)
MF	Motor adapter	Motor adapter with FlexiAdapt coupling
EZ703U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5]
- Mounting position, see the chapter [▶ 12.5.3]
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 12.6.3]
- Position of the plug connectors, see the chapter [▶ 12.5.5]
- For reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 12.6.4]

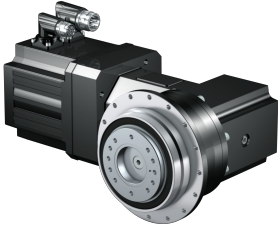
To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1].

12.5 Product description

12.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

12.5.2 Installation conditions

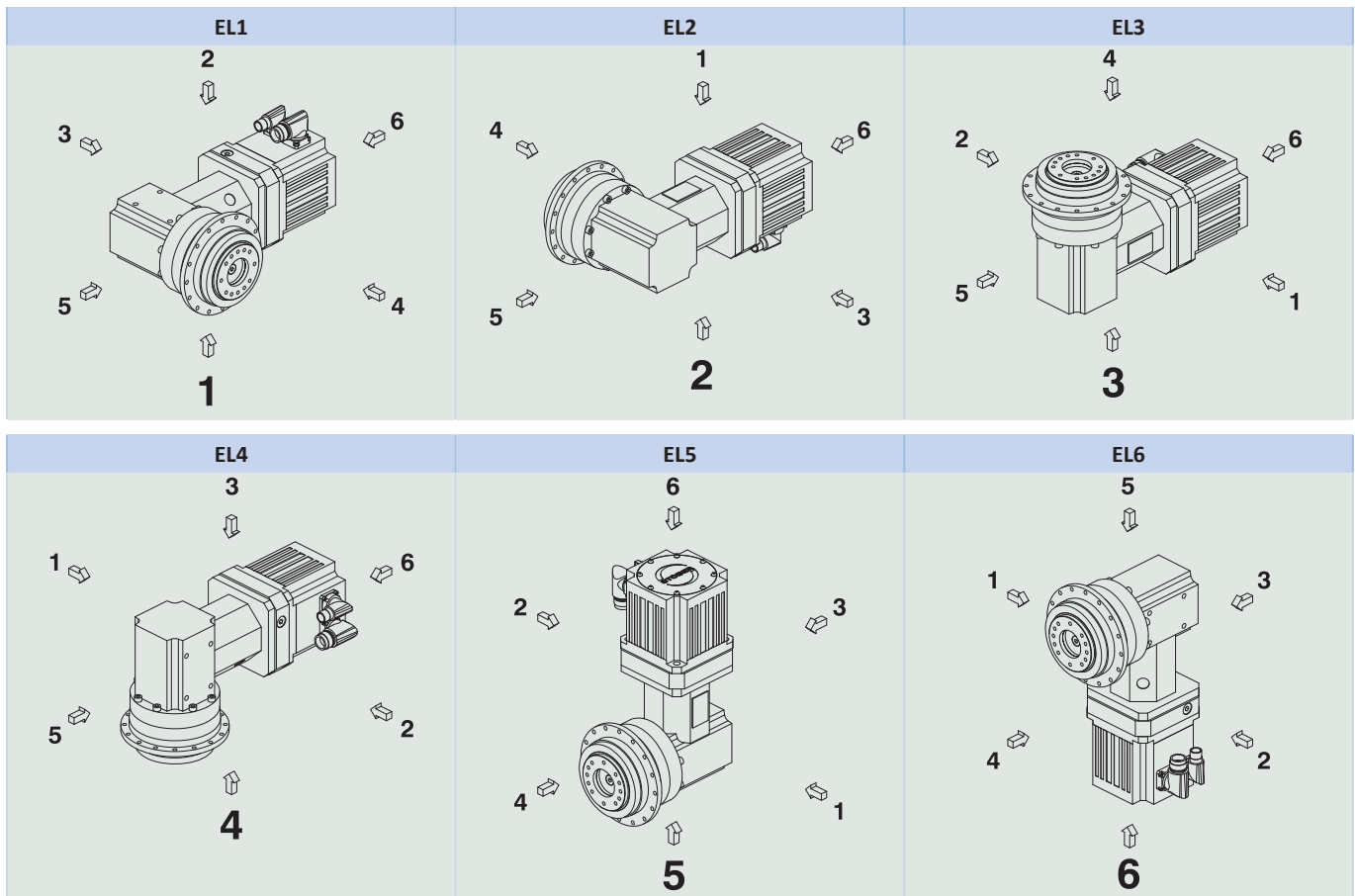
The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b1$. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

12.5.3 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

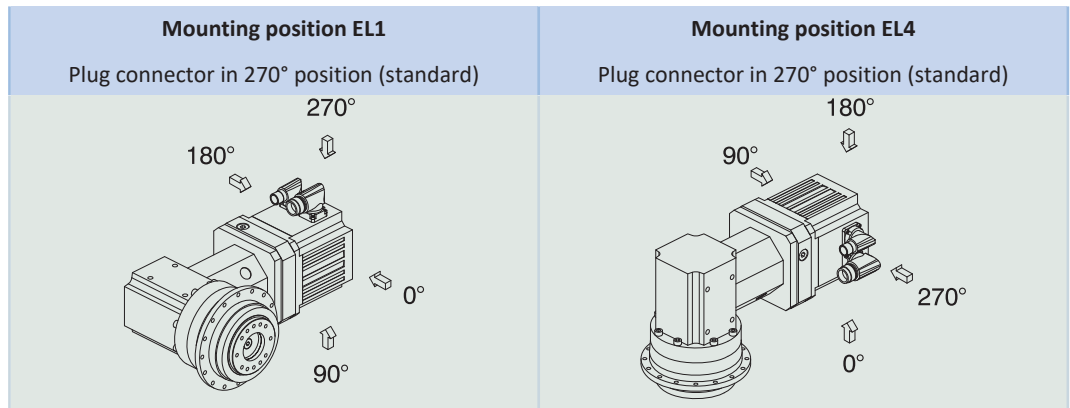
12.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

12.5.5 Position of the plug connectors



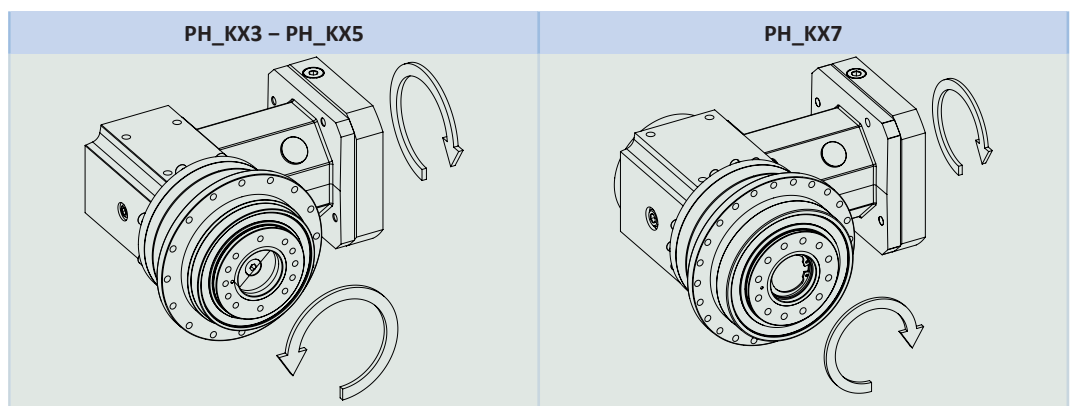
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

12.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	95%
η_{get} three-stage	92%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

12.5.7 Direction of rotation



The figures show mounting position EL1.

¹ Observe the protection class of all the components.

12.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

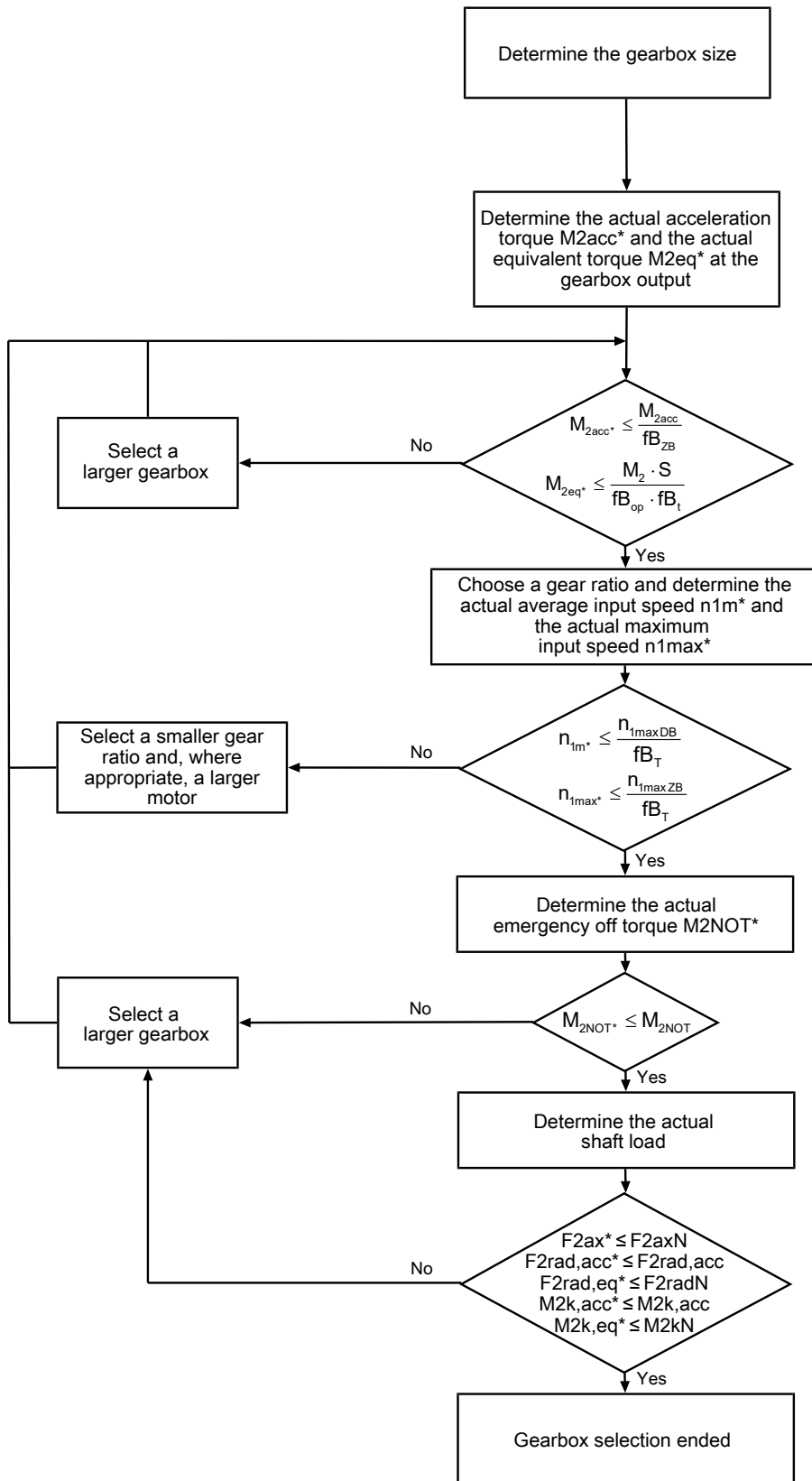
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

12.6.1 Drive selection

Drive selection for gearboxes

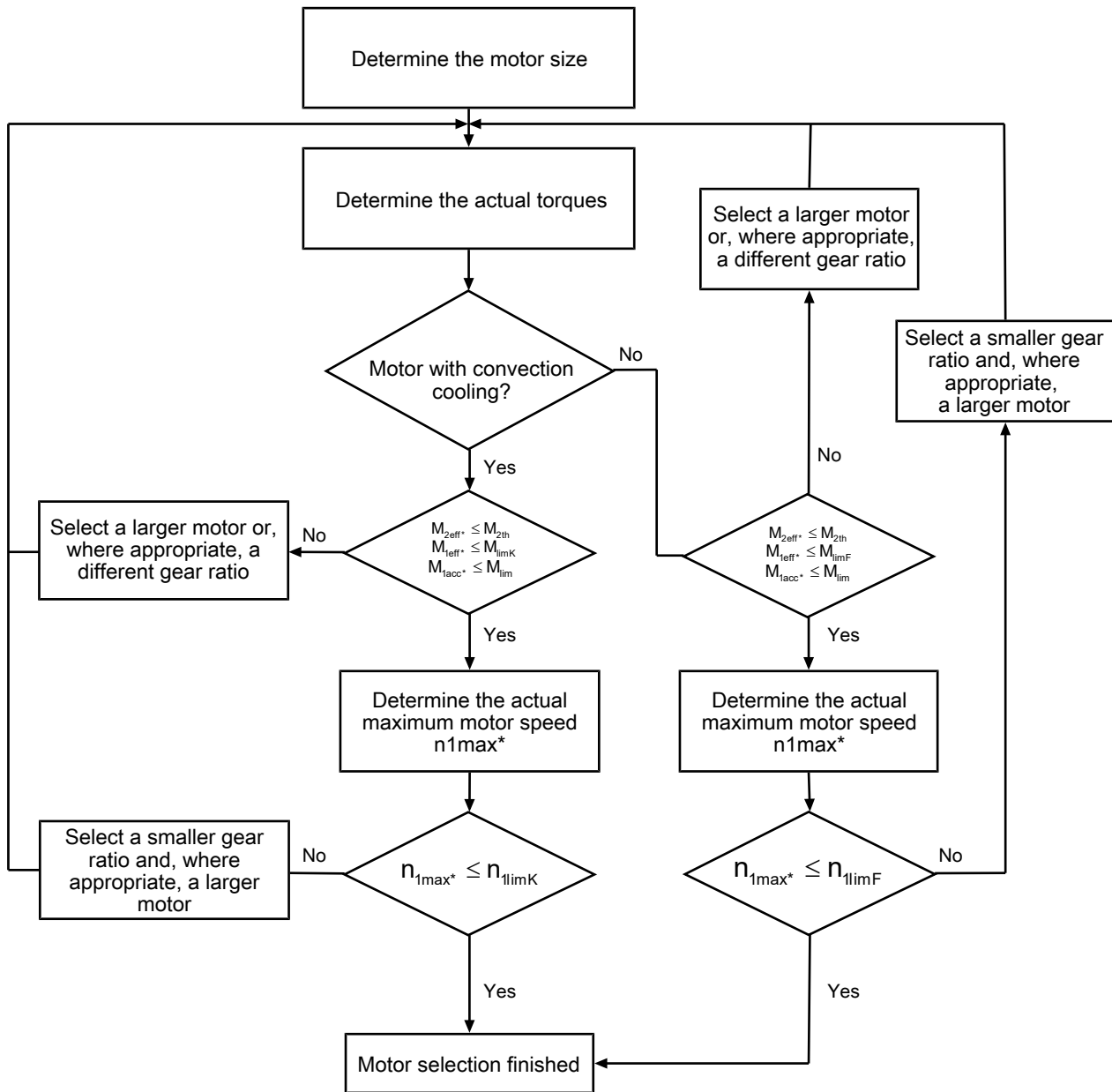


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for fB_T , fB_{op} , fB_t and fB_{ZB} can be found in the corresponding tables in this chapter.

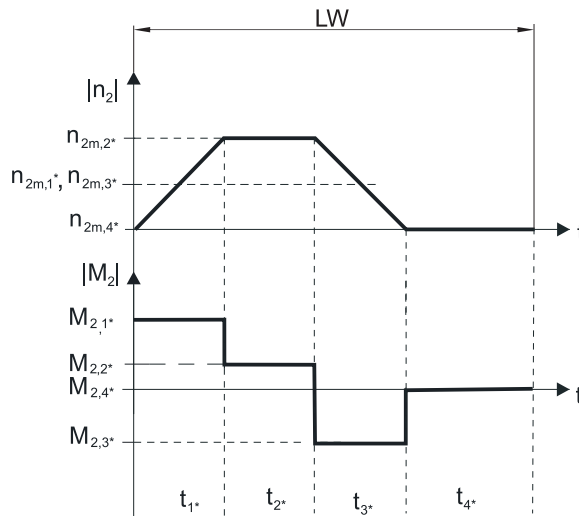
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{limK} and n_{limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:



Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} accordingly or select another geared motor size.)

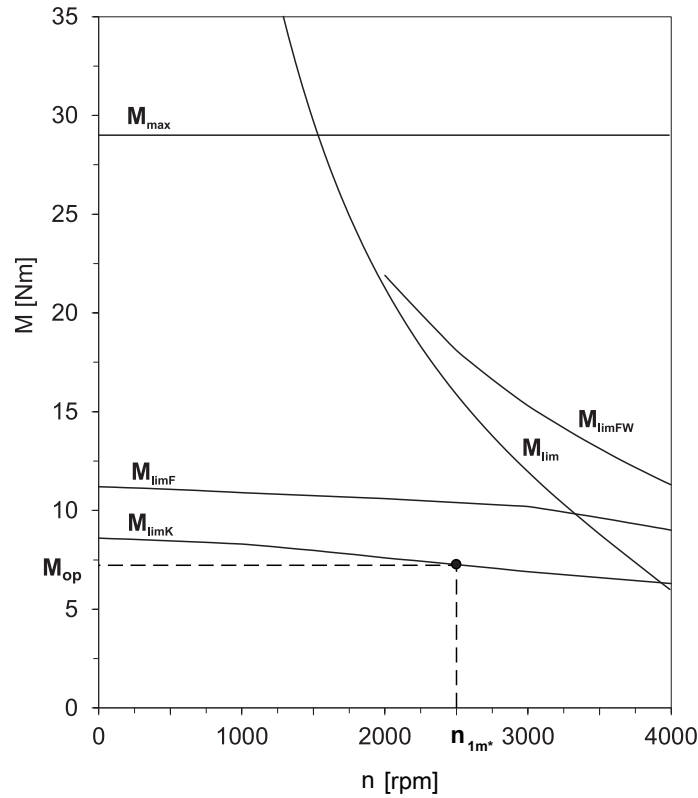
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot a_{thEL} \cdot f_{B_T} \cdot \left(\frac{n_{1m*}}{1000}\right)^3$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2, 5, 6	1.0
EL3, 4	1.1
Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

12.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	62.5	1650	1613	1613	101	101	75
PH4	83.0	2150	3095	3571	257	296	192
PH5	97.0	4150	4536	4897	440	475	429
PH7	86.0	6150	17045	17045	1466	1466	500
PH8	125.5	10050	27778	27778	3486	3486	1550
PH9	155.0	33000	48387	70968	7500	11000	7500
PH10	171.0	50000	51462	73099	8800	12500	9500

Permitted shaft loads for reinforced bearing V

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	66.5	2200	2250	2250	150	150	80
PH4	88.5	2900	4000	4000	354	354	217
PH5	104.0	5000	5500	5500	572	572	478

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100\text{ rpm}$:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

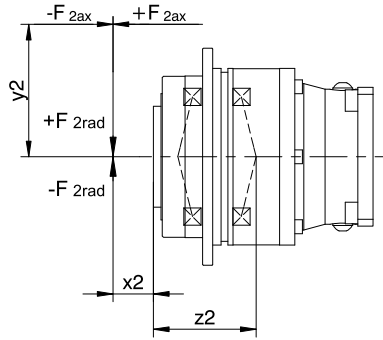


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

12.6.3 Recommendation for radial shaft seal rings

For a duty cycle > 60% and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

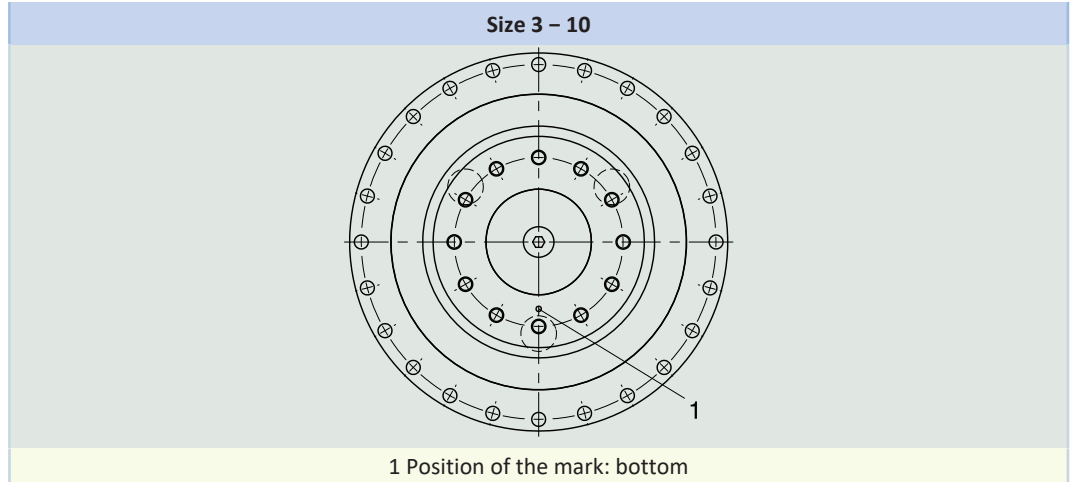
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

12.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

12.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

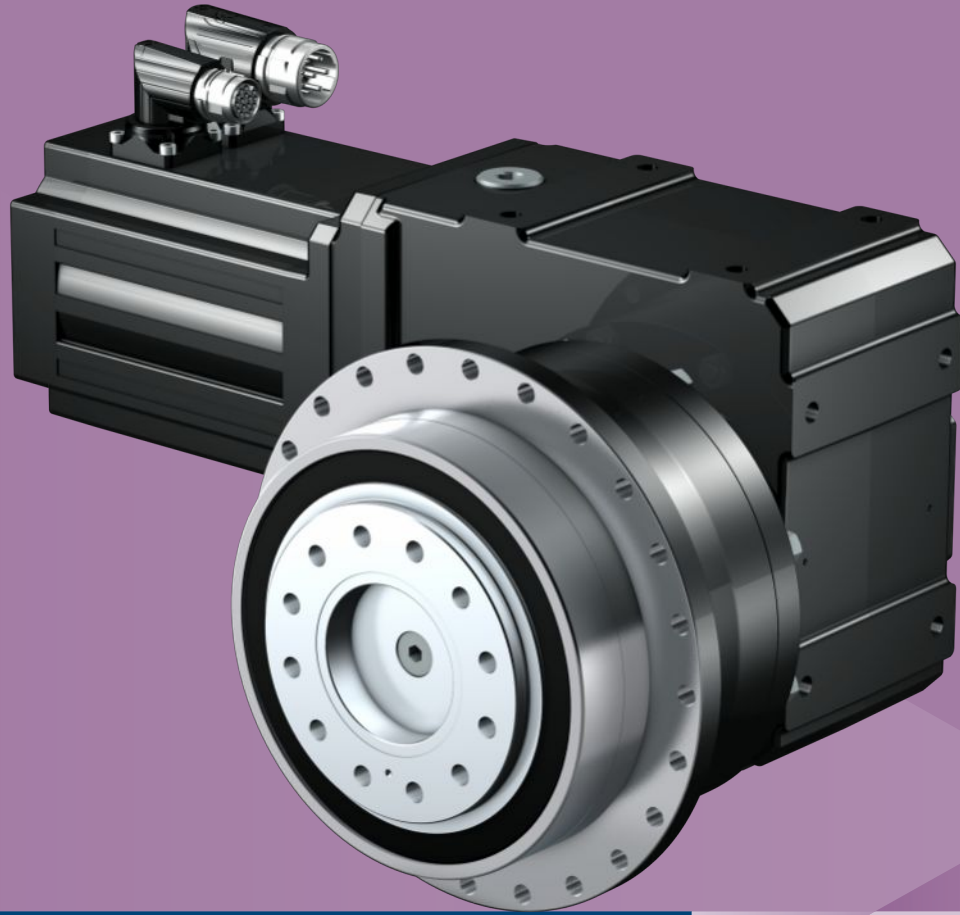
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PH33KX – PH83KX, PH94KX – PH104KX	443359_en

13 PHK right-angle planetary geared motors

Table of contents

13.1 Overview	366
13.2 Selection tables	367
13.3 Dimensional drawings	383
13.3.1 F shaft design (flange shaft)	384
13.4 Type designation	386
13.5 Product description	386
13.5.1 Input options	386
13.5.2 Installation conditions	387
13.5.3 Mounting positions	387
13.5.4 Lubricants	387
13.5.5 Position of the plug connectors	388
13.5.6 Other product features	388
13.5.7 Direction of rotation	388
13.6 Project configuration	389
13.6.1 Drive selection	390
13.6.2 Permitted shaft loads for the output shaft	394
13.6.3 Recommendation for radial shaft seal rings	395
13.6.4 Reverse operation	396
13.7 Additional documentation	396



13

Right-angle planetary geared motors

PHK

13.1 Overview

High-performance precision right-angle planetary geared motors

Features

Power density	★★★★☆
Backlash	★★★★★
Price category	€€€€
Shaft load	★★★★★
Smooth operation	★★★★☆
Torsional stiffness	★★★★☆
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
Continuous operation without cooling	✓
Stiff output bearings due to pretension	✓
Reinforced output bearing (PH3 – PH5)	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	16 – 555
M_{2acc}	89 – 7500 Nm
$\Delta\phi_2$	1.5 – 4.5 arcmin
η_{get}	92 – 93 %

n ₂	M ₂	M _{2,0}	a _{ih}	S	Type	M _{2acc}	M _{2accHT}	M _{2NOT}	i	i _{exakt}	n _{1maxDB}		n _{1maxZB}	Δφ ₂	J ₁	Δφ _{2red}	C ₂	m
											EL1,2	EL3,4,5,6						
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]	[Nm]			[rpm]	[rpm]	[rpm]	[arcmin]	[kgcm ²]	[arcmin]	[Nm/arcmin]	[kg]
PH1041K (n_{MN} = 4500 min⁻¹, M_{2acc,max} = 7500 Nm)																		
12	4245	7016	20	1.2	PH1041_0060K613_0640 EZ703U	7500	–	15000	382.3	391437/1024	3100	3100	4500	4.0	23	–	1210	144
16	2497	4021	15	2.0	PH1041_0060K613_0480 EZ505U	7500	–	14337	286.4	119133/416	3100	3100	4500	4.0	14	–	1210	142
16	3180	5257	19	1.6	PH1041_0060K613_0480 EZ703U	7500	–	14337	286.4	119133/416	3100	3100	4500	4.0	23	–	1210	144
20	2005	3228	14	2.5	PH1041_0060K613_0380 EZ505U	7500	–	13589	229.9	470859/2048	3100	3100	4500	4.0	15	–	1210	142
20	2553	4220	18	2.0	PH1041_0060K613_0380 EZ703U	7500	–	13589	229.9	470859/2048	3100	3100	4500	4.0	24	–	1210	144
20	3460	6330	24	1.4	PH1041_0060K613_0380 EZ705U	7500	–	15000	229.9	470859/2048	3100	3100	4500	4.0	37	–	1210	149
24	1666	2684	13	3.0	PH1041_0060K613_0320 EZ505U	7500	–	12521	191.1	391437/2048	3100	3100	4500	4.0	16	–	1210	142
24	2122	3508	17	2.4	PH1041_0060K613_0320 EZ703U	7500	–	12521	191.1	391437/2048	3100	3100	4500	4.0	25	–	1210	144
24	2877	5262	22	1.7	PH1041_0060K613_0320 EZ705U	7500	–	15000	191.1	391437/2048	3100	3100	4500	4.0	38	–	1210	149

13.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

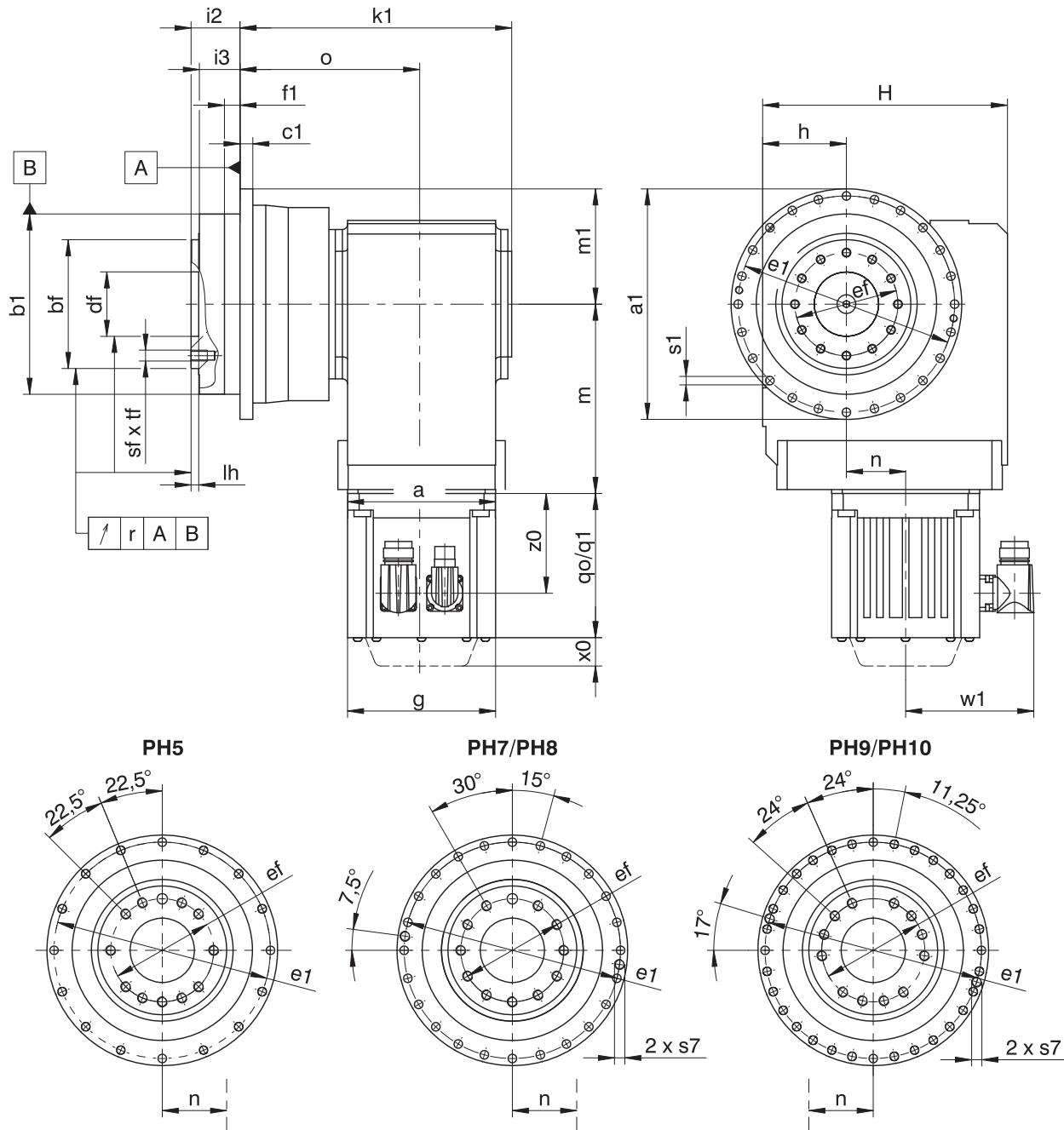
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

13.3.1 F shaft design (flange shaft)



q0 Applies to motors without brake.

q1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	h	H	i2	i3	k1	lh	m1	o	r	Øs1	s7	sf	tf
PH531_K102_	145	110 _{h7}	80 _{h7}	8	40 ^{H6}	135	63	12	60	160	29	23	180.0	6	72.5	124.0	0.020	5.5	–	M6	11
PH731_K102_	179	140 _{h7}	100 _{h7}	10	50 ^{H6}	168	80	12	60	160	38	32	183.0	6	89.5	127.0	0.025	6.6	–	M8	14
PH731_K202_	179	140 _{h7}	100 _{h7}	10	50 ^{H6}	168	80	12	65	190	38	32	211.0	6	89.5	141.0	0.025	6.6	–	M8	14
PH831_K202_	247	200 _{h7}	160 _{h7}	12	80 ^{H6}	233	125	15	65	190	50	42	246.0	8	123.5	176.0	0.030	9.0	M10	M10	18
PH831_K302_	247	200 _{h7}	160 _{h7}	12	80 ^{H6}	233	125	15	75	213	50	42	259.5	8	123.5	183.5	0.030	9.0	M10	M10	18
PH941_K513_	300	255 _{h7}	180 _{h7}	18	90 ^{H6}	280	140	20	160	260	66	55	292.5	12	150.0	196.5	0.030	13.5	M8	M16	24
PH1041_K613_	330	285 _{h7}	200 _{h7}	20	95 ^{H6}	310	160	20	190	310	75	60	318.5	10	165.0	215.0	0.040	13.5	M10	M20	28

Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
PH531_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
PH731_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
PH731_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
PH831_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
PH831_K302_	-	-	-	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
PH941_K513_	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
PH1041_K613_	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0

13.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PH	7	3	1	S	F	S	S	0100	K102VF	0115	EZ302U
----	---	---	---	---	---	---	---	------	--------	------	--------

Explanation

Code	Designation	Design
PH	Type	Planetary gearbox
7	Size	7 (example)
3	Generation	Generation 3
4		Generation 4
1	Stages	Single-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
V		Reinforced bearing (PH3 – PH5)
S	Backlash	Standard
R		Reduced (PH3 – PH9)
0100	Transmission ratio of output (i x 10)	i = 10 (example)
K102VF	Input	K1 right-angle geared motor (example)
0115	Transmission ratio of input (i x 10 rounded)	i = 11.57 (example)
EZ302U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- For a detailed type designation of the motor, see the chapter [▶ 17.5](#)
- For the mounting position, see the chapter [▶ 13.5.3](#)
- Output gearbox side 3 or 4, see the chapter [▶ 13.5.3](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 13.6.3](#)
- Position of the plug connectors, see the chapter [▶ 13.5.5](#)
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 13.6.4](#)

To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

13.5 Product description

13.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

13.5.2 Installation conditions

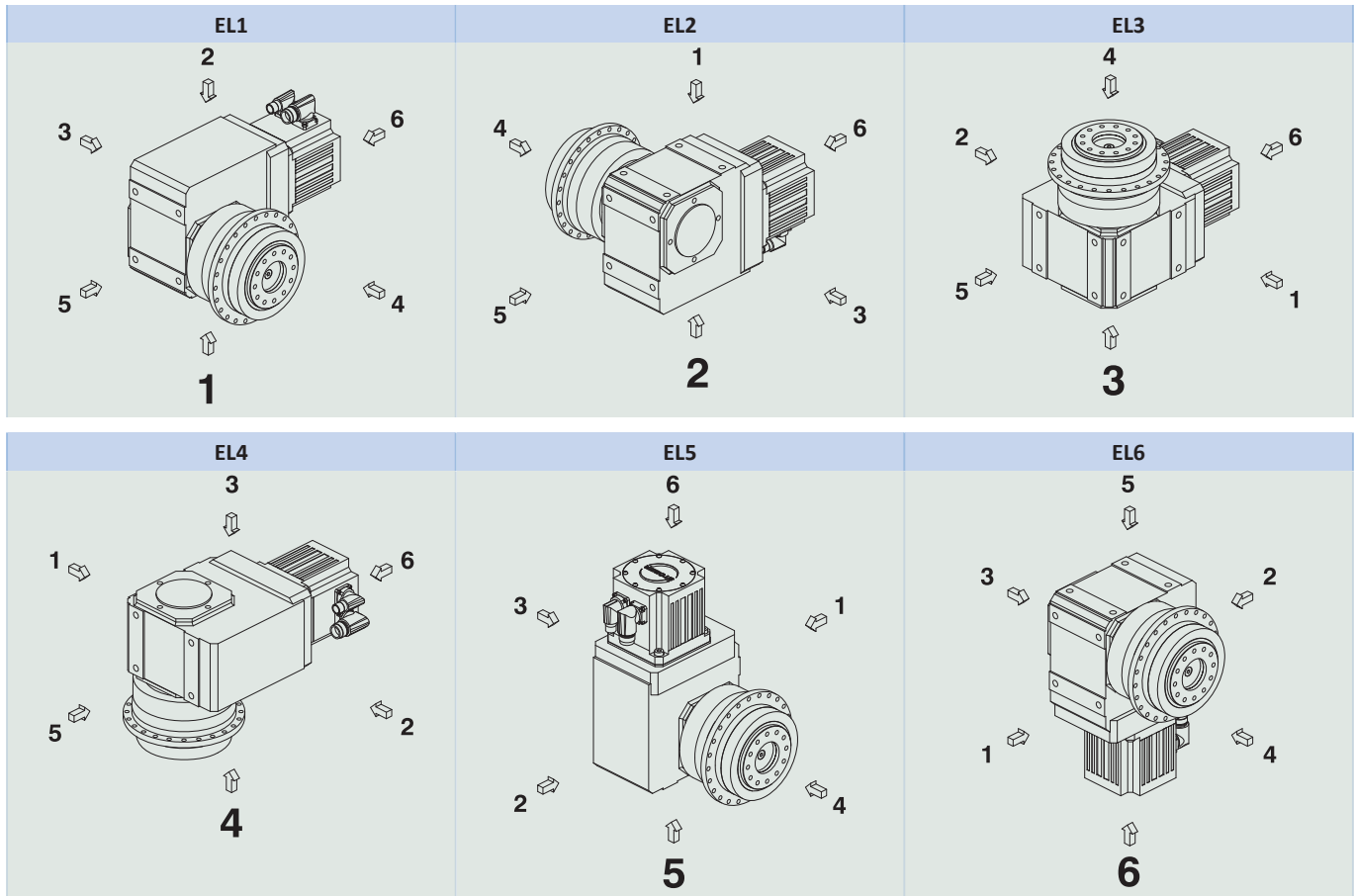
The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b1$. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

13.5.3 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

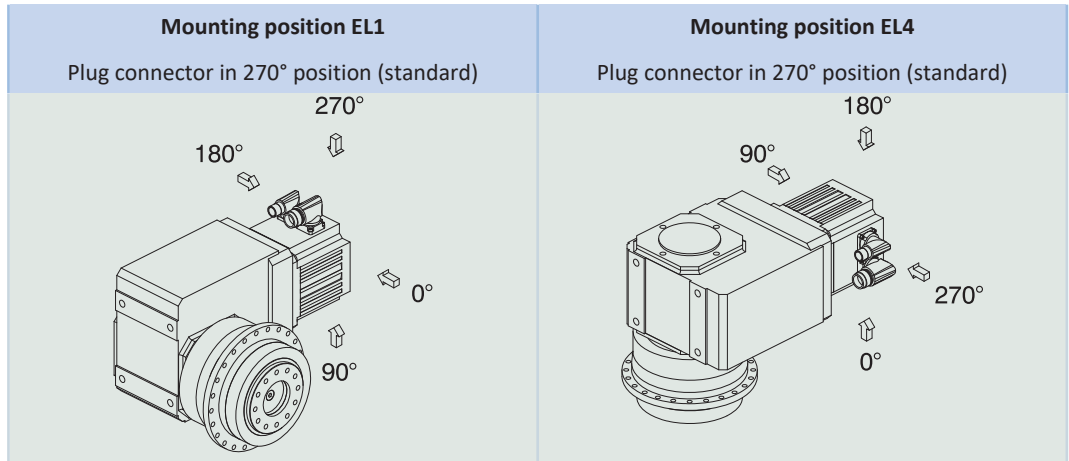
13.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

13.5.5 Position of the plug connectors



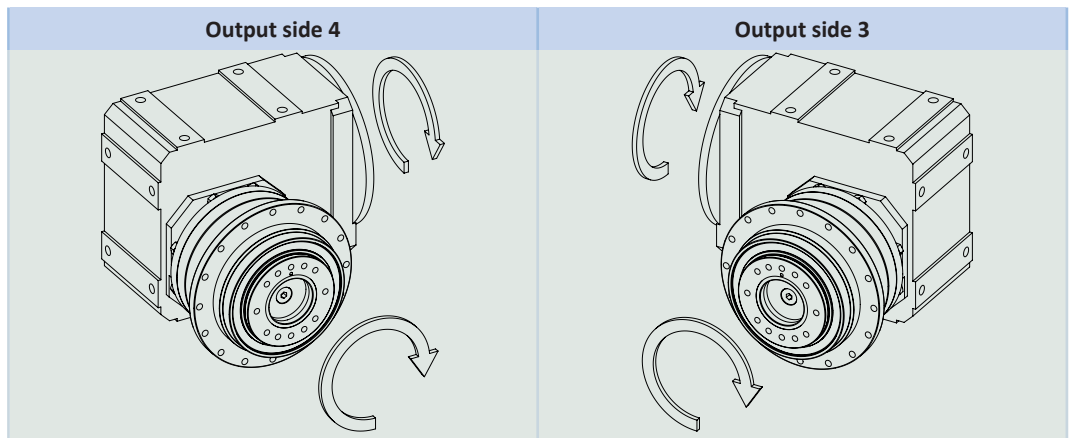
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

13.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} three-stage	93%
η_{get} four-stage	92%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

13.5.7 Direction of rotation



The pictures show mounting position EL1.

¹Observe the protection class of all the components.

13.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

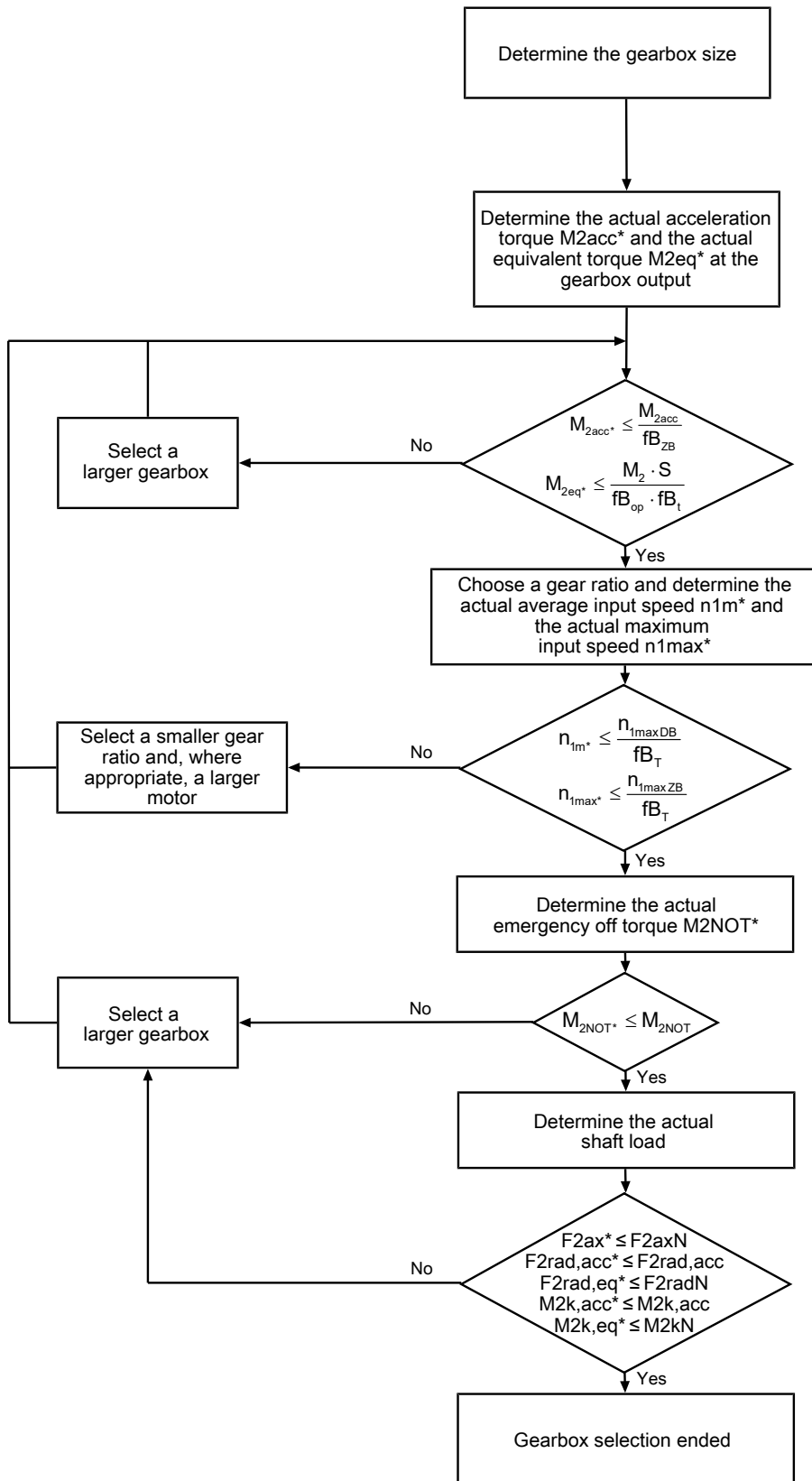
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

13.6.1 Drive selection

Drive selection for gearboxes

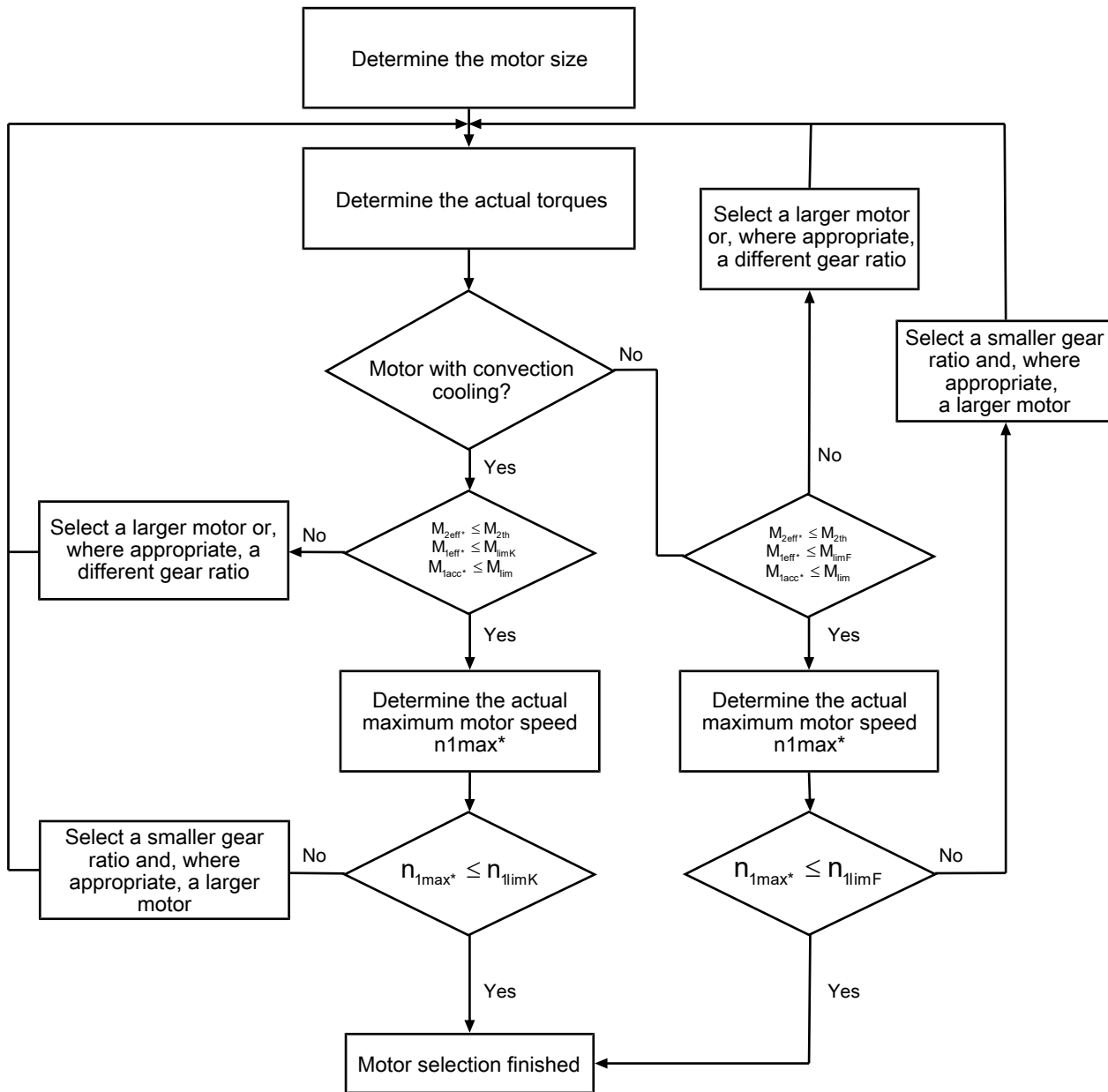


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

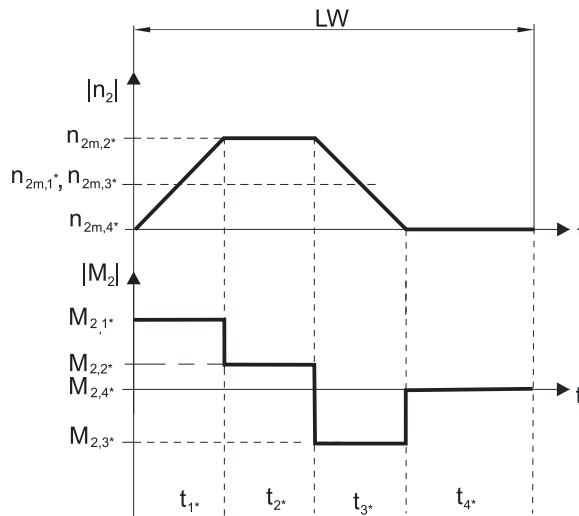
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{limK} and n_{limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:



Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |M_{2,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |M_{2,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

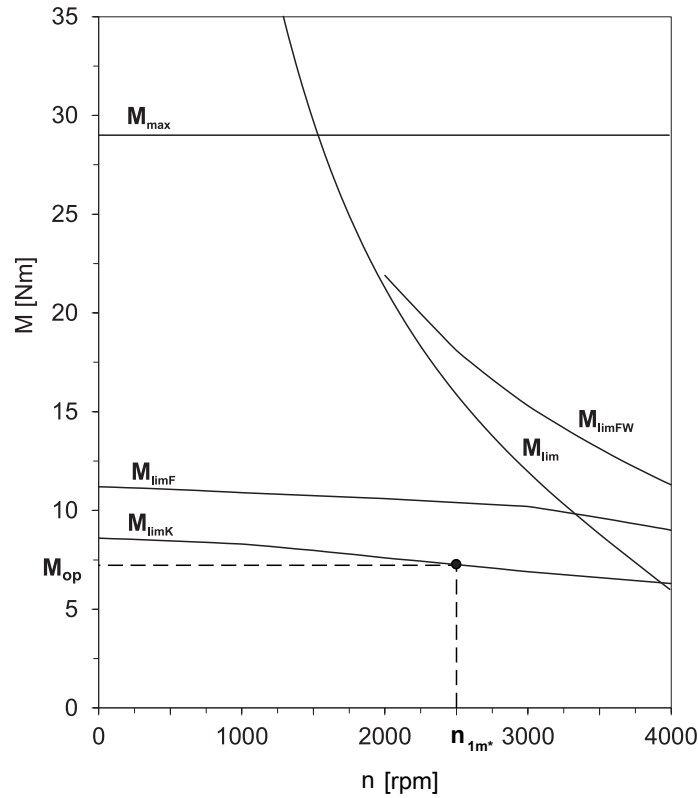
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot athEL \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000} \right)^2$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2	1.0
EL3, 4, 5, 6	1.1
Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

13.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	62.5	1650	1613	1613	101	101	75
PH4	83.0	2150	3095	3571	257	296	192
PH5	97.0	4150	4536	4897	440	475	429
PH7	86.0	6150	17045	17045	1466	1466	500
PH8	125.5	10050	27778	27778	3486	3486	1550
PH9	155.0	33000	48387	70968	7500	11000	7500
PH10	171.0	50000	51462	73099	8800	12500	9500

Permitted shaft loads for reinforced bearing V

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PH3	66.5	2200	2250	2250	150	150	80
PH4	88.5	2900	4000	4000	354	354	217
PH5	104.0	5000	5500	5500	572	572	478

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100\text{ rpm}$:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

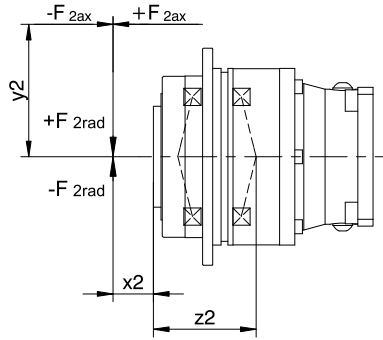


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1*} \cdot |M_{2k,acc,1*}|^3 + \dots + |n_{2m,n}| \cdot t_{n*} \cdot |M_{2k,acc,n*}|^3}{|n_{2m,1}| \cdot t_{1*} + \dots + |n_{2m,n}| \cdot t_{n*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1*} \cdot |F_{2rad,acc,1*}|^3 + \dots + |n_{2m,n}| \cdot t_{n*} \cdot |F_{2rad,acc,n*}|^3}{|n_{2m,1}| \cdot t_{1*} + \dots + |n_{2m,n}| \cdot t_{n*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

13.6.3 Recommendation for radial shaft seal rings

For a duty cycle > 60% and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

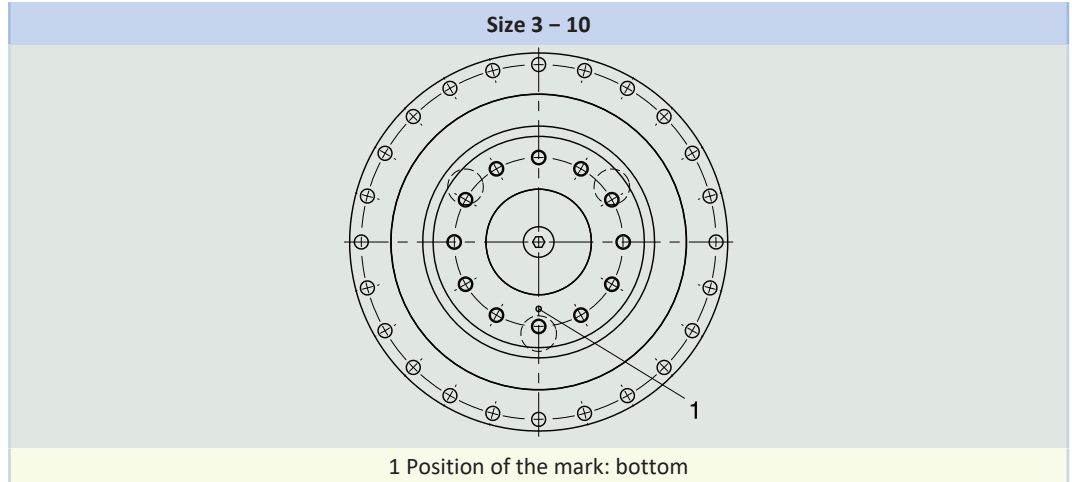
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

13.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

13.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

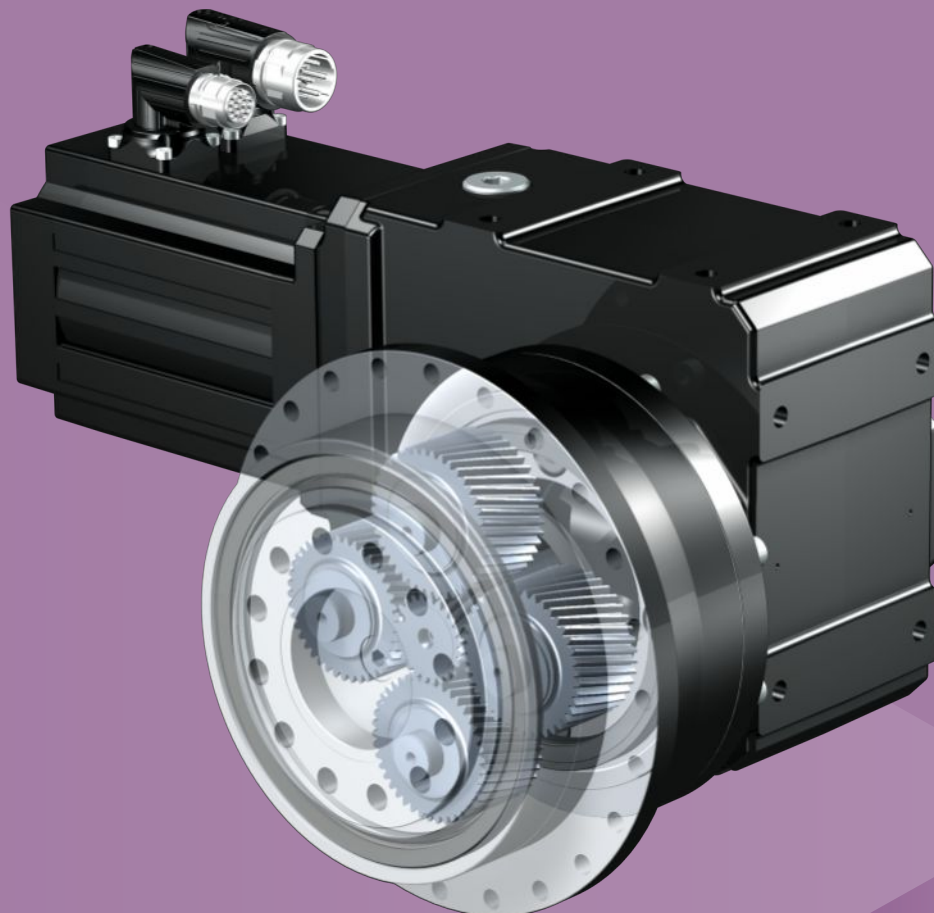
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PH53K – PH83K, PH94K – PH104K	443358_en

14 PHQK right-angle planetary geared motors

Table of contents

14.1 Overview	398
14.2 Selection tables	399
14.3 Dimensional drawings	411
14.3.1 PHQ5 – PHQ10 F shaft design (flange shaft)	412
14.3.2 PHQ11 – PHQ12 F shaft design (flange shaft)	414
14.4 Type designation	416
14.5 Product description	416
14.5.1 Input options	416
14.5.2 Installation conditions	417
14.5.3 Mounting positions	417
14.5.4 Lubricants	417
14.5.5 Position of the plug connectors	418
14.5.6 Other product features	418
14.5.7 Direction of rotation	418
14.6 Project configuration	419
14.6.1 Drive selection	420
14.6.2 Permitted shaft loads for the output shaft	424
14.6.3 Recommendation for radial shaft seal rings	425
14.6.4 Reverse operation	426
14.7 Additional documentation	426



14

Right-angle planetary geared motors

PHQK

14.1 Overview

Quattro-Power precision right-angle planetary geared motors

Features

Power density	★★★★★
Backlash	★★★★★
Price category	€€€€€
Shaft load	★★★★★
Smooth operation	★★★☆☆
Torsional stiffness	★★★★★
Mass moment of inertia	★★★★★
Helical gearing	✓
Maintenance-free	✓
High power density	✓
Continuous operation without cooling	✓
Stiff output bearings due to pretension	✓
Reinforced output bearing (PHQ4 – PHQ5)	✓ (optional)
Compact and highly dynamic due to direct motor attachment	✓

Key ★☆☆☆☆ good | ★★★★★ excellent
 € Economy | €€€€€ Premium

Technical data

i	22 – 2242
M_{2acc}	123 – 43000 Nm
$\Delta\phi_2$	1.5 – 4 arcmin
η_{get}	90 – 93 %

14.2 Selection tables 14 PHQK right-angle planetary geared motors

n ₂	M ₂	M _{2,0}	a _{th}	S	Type	M _{2acc}	M _{2accHT}	M _{2NOT}	i	i _{exakt}	n _{1max}		Δφ ₂	J ₁	Δφ _{2red}	C ₂	m	
											EL1,2	EL3,4,5,6						
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]	[Nm]			[rpm]	[rpm]	[arc min]	[kgcm ²]	[arc min]	[Nm/ arcmin]	[kg]	
PHQ1141K (n_{1N} = 4000 min⁻¹, M_{2acc,max} = 22000 Nm)																		
17	5752	14792	17	2.3	PHQ1141_0060K813_0400 EZ815U	22000	–	44000	240.1	38409/160	2800	2800	4000	4.0	180	–	2623	336
18	5015	8696	16	2.6	PHQ1141_0060K813_0360 EZ813U	22000	–	44000	216.8	8673/40	2800	2800	4000	4.0	117	–	2623	323
18	5196	13361	17	2.5	PHQ1141_0060K813_0360 EZ815U	22000	–	44000	216.8	8673/40	2800	2800	4000	4.0	181	–	2623	336
21	4494	7794	16	2.9	PHQ1141_0060K813_0320 EZ813U	22000	–	44000	194.3	31093/160	2800	2800	4000	4.0	122	–	2623	323
21	4657	11975	16	2.8	PHQ1141_0060K813_0320 EZ815U	22000	–	44000	194.3	31093/160	2800	2800	4000	4.0	185	–	2623	336
23	4059	7040	15	3.2	PHQ1141_0060K813_0290 EZ813U	22000	–	44000	175.5	7021/40	2800	2800	4000	4.0	123	–	2623	323
23	4206	10816	16	3.1	PHQ1141_0060K813_0290 EZ815U	22000	–	44000	175.5	7021/40	2800	2800	4000	4.0	186	–	2623	336
PHQ1241K (n_{1N} = 2000 min⁻¹, M_{2acc,max} = 43000 Nm)																		
3.5	20485	22975	19	1.2	PHQ1241_0060K913_0950 EZ813U	37154	–	56722	572.5	293105/512	2600	2600	3800	4.0	111	–	4665	570
3.6	19517	21890	18	1.3	PHQ1241_0060K914_0920 EZ813U	39537	–	53625	554.1	7199037/12992	2600	2600	3800	4.0	110	–	4665	583
4.4	16103	18061	18	1.6	PHQ1241_0060K913_0750 EZ813U	39283	–	53281	450.0	187209/416	2600	2600	3800	4.0	114	–	4665	570
4.4	23852	28399	26	1.0	PHQ1241_0060K913_0750 EZ815U	39283	–	53281	450.0	187209/416	2600	2600	3800	4.0	177	–	4665	583
5.3	13541	15188	17	1.8	PHQ1241_0060K913_0630 EZ813U	43000	–	80000	378.4	629703/1664	2600	2600	3800	4.0	118	–	4665	570
5.3	20057	23881	25	1.2	PHQ1241_0060K913_0630 EZ815U	43000	–	80000	378.4	629703/1664	2600	2600	3800	4.0	181	–	4665	583
6.8	10507	11784	15	2.4	PHQ1241_0060K913_0490 EZ813U	37726	–	80000	293.6	300669/1024	2600	2600	3800	4.0	125	–	4665	570
6.8	15562	18529	23	1.6	PHQ1241_0060K913_0490 EZ815U	43000	–	80000	293.6	300669/1024	2600	2600	3800	4.0	188	–	4665	583
8.8	8168	9161	14	3.1	PHQ1241_0060K913_0380 EZ813U	29327	–	78148	228.3	584319/2560	2600	2600	3800	4.0	135	–	4665	570
8.8	12098	14404	21	2.1	PHQ1241_0060K913_0380 EZ815U	41896	–	78148	228.3	584319/2560	2600	2600	3800	4.0	198	–	4665	583
10	6895	7734	14	3.6	PHQ1241_0060K913_0320 EZ813U	24759	–	71941	192.7	141825/736	2600	2600	3800	4.0	144	–	4665	570
10	10213	12160	20	2.4	PHQ1241_0060K913_0320 EZ815U	35370	–	71941	192.7	141825/736	2600	2600	3800	4.0	207	–	4665	583
14	5141	5766	12	4.9	PHQ1241_0060K913_0240 EZ813U	18458	–	53625	143.7	266631/1856	2200	2200	3300	4.0	166	–	4665	570
14	7614	9066	18	3.3	PHQ1241_0060K913_0240 EZ815U	26369	–	53625	143.7	266631/1856	2200	2200	3300	4.0	230	–	4665	583
17	6062	7218	17	4.1	PHQ1241_0060K913_0190 EZ815U	20994	–	42705	114.4	915/8	2200	2200	3300	4.0	255	–	4665	583
PHQ1241K (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 39280 Nm)																		
1.3	14989	16812	5.3	1.7	PHQ1241_0060K914_3740 EZ701U	37154	–	56722	2242	13775935/6144	2600	2600	3800	4.0	9.4	–	4665	555
1.3	24306	29167	8.6	1.0	PHQ1241_0060K914_3740 EZ702U	37154	–	56722	2242	13775935/6144	2600	2600	3800	4.0	15	–	4665	558
1.7	11783	13216	4.9	2.1	PHQ1241_0060K914_2940 EZ701U	31845	–	53281	1763	2932941/1664	2600	2600	3800	4.0	9.6	–	4665	555
1.7	19107	22928	8.0	1.3	PHQ1241_0060K914_2940 EZ702U	39283	–	53281	1763	2932941/1664	2600	2600	3800	4.0	15	–	4665	558
2.0	9908	11113	4.7	2.5	PHQ1241_0060K914_2470 EZ701U	26779	–	44775	1482	9865347/6656	2600	2600	3800	4.0	9.9	–	4665	555
2.0	16067	19281	7.6	1.6	PHQ1241_0060K914_2470 EZ702U	33011	–	44775	1482	9865347/6656	2600	2600	3800	4.0	15	–	4665	558
2.0	22092	27850	10	1.1	PHQ1241_0060K914_2470 EZ703U	33011	–	44775	1482	9865347/6656	2600	2600	3800	4.0	23	–	4665	560
2.6	7688	8623	4.6	3.1	PHQ1241_0060K914_1920 EZ701U	20778	–	39634	1150	4710481/4096	2600	2600	3800	4.0	10	–	4665	555
2.6	12467	14960	7.4	1.9	PHQ1241_0060K914_1920 EZ702U	29221	–	39634	1150	4710481/4096	2600	2600	3800	4.0	16	–	4665	558
2.6	17142	21609	10	1.4	PHQ1241_0060K914_1920 EZ703U	29221	–	39634	1150	4710481/4096	2600	2600	3800	4.0	23	–	4665	560
3.4	5976	6703	4.5	3.8	PHQ1241_0060K914_1490 EZ701U	16152	–	35937	894.0	9154331/10240	2600	2600	3800	4.0	11	–	4665	555
3.4	9691	11629	7.3	2.3	PHQ1241_0060K914_1490 EZ702U	26496	–	35937	894.0	9154331/10240	2600	2600	3800	4.0	16	–	4665	558
3.4	13325	16798	10	1.7	PHQ1241_0060K914_1490 EZ703U	26496	–	35937	894.0	9154331/10240	2600	2600	3800	4.0	24	–	4665	560
4.0	5045	5659	4.4	4.3	PHQ1241_0060K914_1260 EZ701U	13636	–	30340	754.7	2221925/2944	2600	2600	3800	4.0	12	–	4665	555
4.0	8181	9818	7.2	2.6	PHQ1241_0060K914_1260 EZ702U	22369	–	30340	754.7	2221925/2944	2600	2600	3800	4.0	17	–	4665	558
4.0	11250	14181	9.9	1.9	PHQ1241_0060K914_1260 EZ703U	22369	–	30340	754.7	2221925/2944	2600	2600	3800	4.0	25	–	4665	560
5.3	6099	7319	8.6	2.7	PHQ1241_0060K914_0940 EZ702U	16676	–	22618	562.7	4177219/7424	2600	2600	3800	4.0	18	–	4665	558
5.3	8387	10572	12	2.0	PHQ1241_0060K914_0940 EZ703U	16676	–	22618	562.7	4177219/7424	2600	2600	3800	4.0	26	–	4665	560

14.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

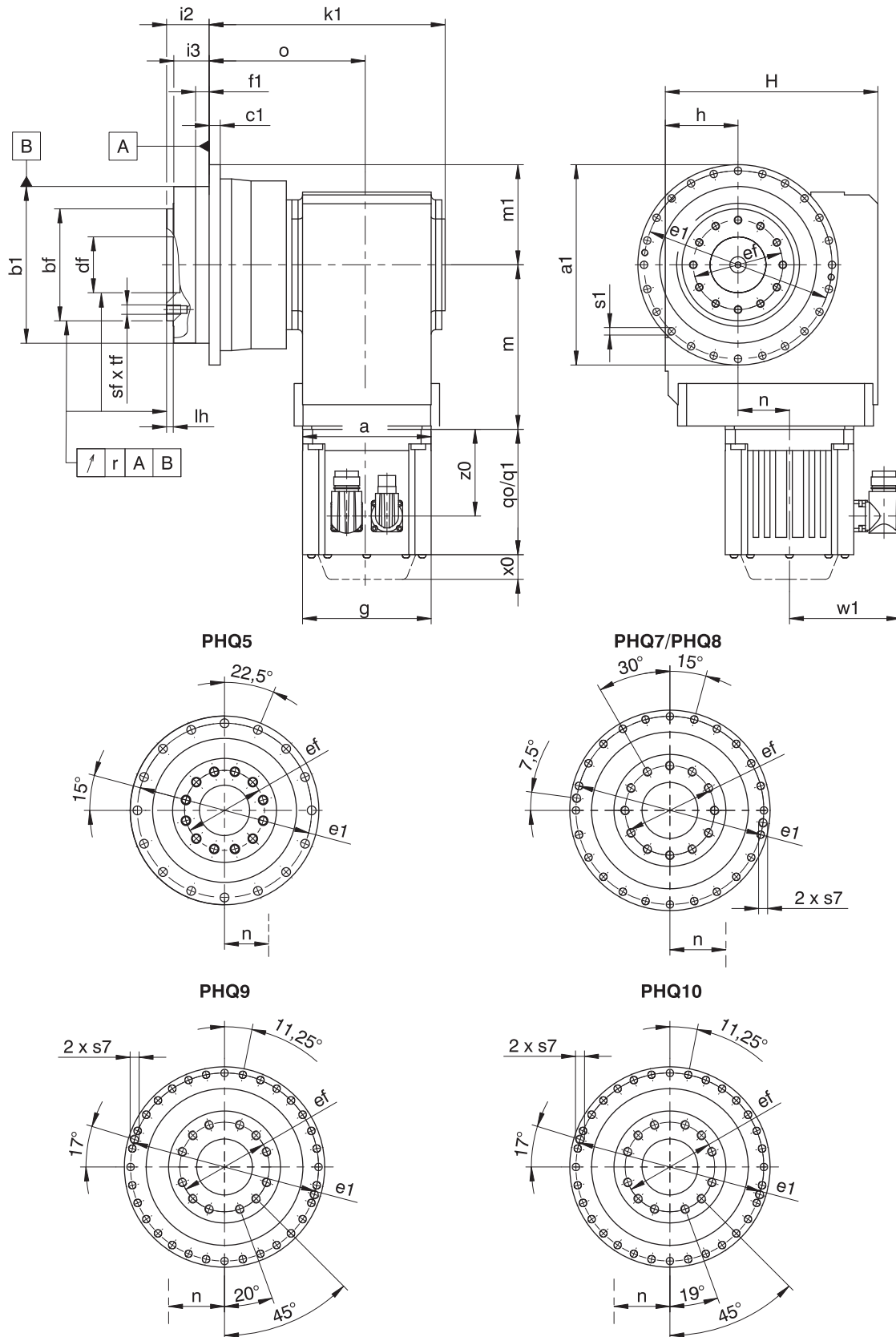
Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

14.3.1 PHQ5 – PHQ10 F shaft design (flange shaft)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	h	H	i2	i3	k1	lh	m1	o	r	Øs1	s7	sf	tf
PHQ531_K102_	145	110 _{h7}	80 _{h7}	8	40 ^{H6}	135	63	12	60	160	29	23	180.0	6	72.5	124.0	0.020	5.5	–	M8	12.0
PHQ731_K202_	179	140 _{h7}	100 _{h7}	10	50 ^{H6}	168	80	12	65	190	38	32	211.0	6	89.5	141.0	0.025	6.6	–	M10	16.0
PHQ831_K402_	247	200 _{h7}	160 _{h7}	12	80 ^{H6}	233	125	15	90	240	50	42	289.0	8	123.5	199.0	0.030	9.0	M10	M12	17.0
PHQ941_K513_	300	255 _{h7}	180 _{h7}	18	90 ^{H6}	280	145	20	160	260	66	55	292.5	12	150.0	196.5	0.030	13.5	M8	M20	28.0
PHQ1041_K713_	330	285 _{h7}	200 _{h7}	20	95 ^{H6}	310	166	20	212	342	75	60	354.5	10	165.0	238.0	0.040	13.5	M10	M24	35.0

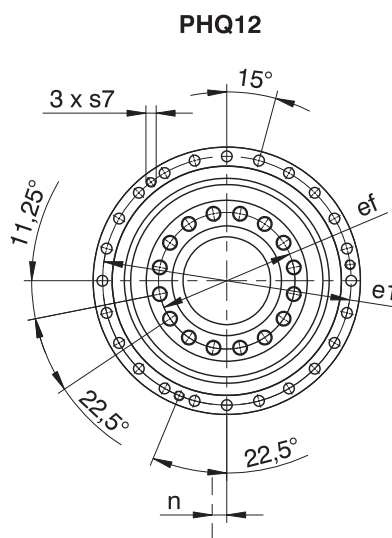
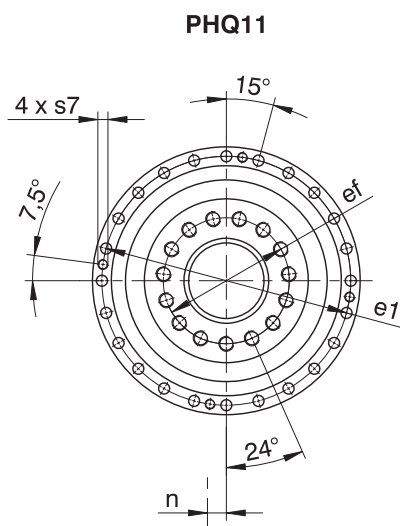
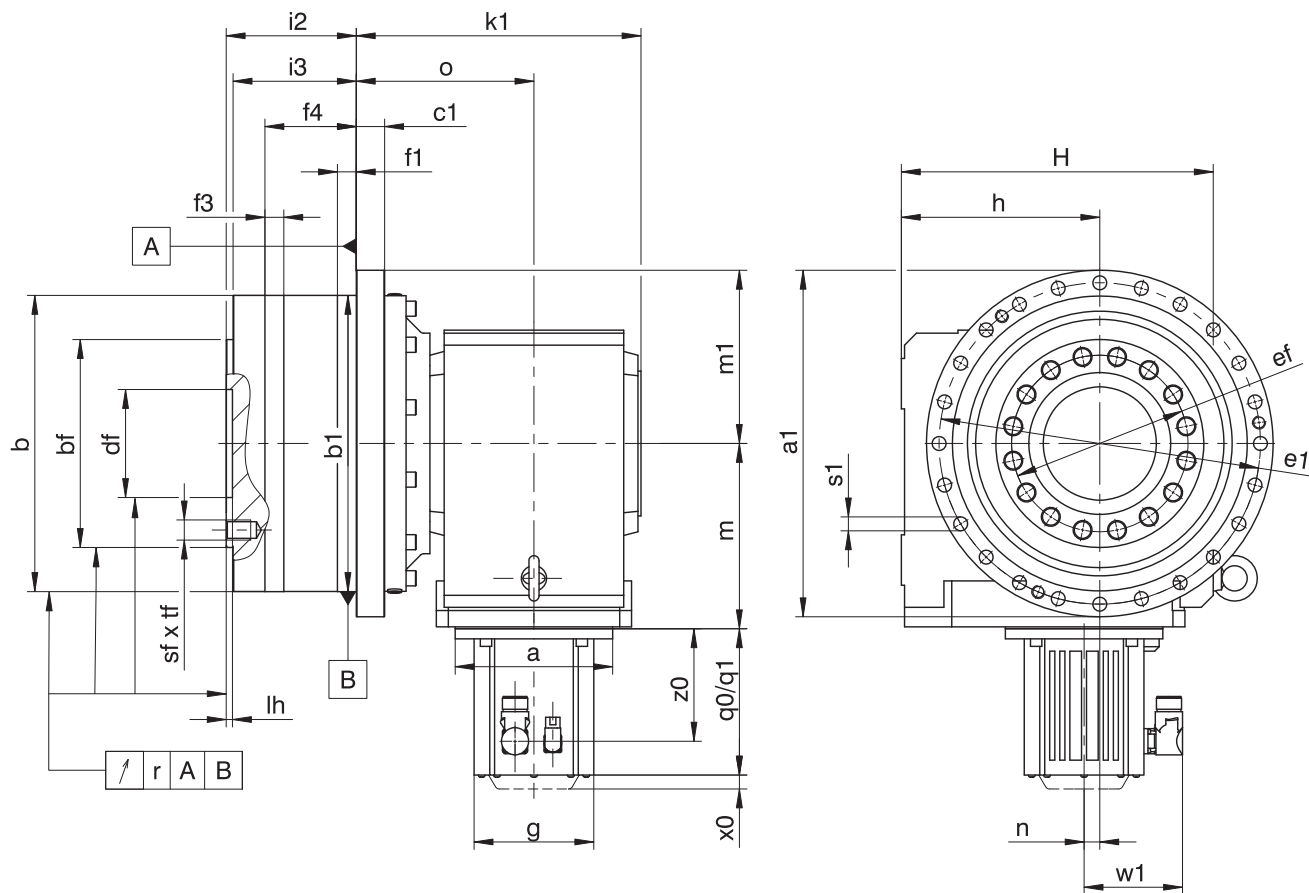
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
PHQ531_K102_	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
PHQ731_K202_	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
PHQ831_K402_	–	–	–	–	–	–	Ø160	187	60.0	□145	189	60.0	□190	192	60.0
PHQ941_K513_	–	–	–	–	–	–	Ø160	172	15.0	□145	174	15.0	□190	177	15.0
PHQ1041_K713_	–	–	–	–	–	–	–	–	–	Ø200	221	20.0	□190	224	20.0

14.3.2 PHQ11 – PHQ12 F shaft design (flange shaft)



q0 Applies to motors without brake.

q1 Applies to motors with brake.

x0 Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	Øa1	Øb	Øb1	Øbf	c1	Ødf	Øe1	Øef	f1	f3	f4	h	H	i2	i3	k1	lh	m1	o	r	Øs1	s7	sf	tf
PHQ1141_K813_	425	365 _{g6}	365 _{h6}	260 _{h7}	32	120 ^{H6}	395	200	30	30	120	265	410	190	180	381.5	10	212.5	236.5	0.040	17.5	M16	M24	35.5
PHQ1241_K913_	550	470 _{g6}	470 _{h6}	330 _{h7}	45	180 ^{H7}	510	280	30	30	145	315	495	206.5	195.5	452.0	10	275.0	282.0	0.040	22.0	M16	M30	47.0
PHQ1241_K914_	550	470 _{g6}	470 _{h6}	330 _{h7}	45	180 ^{H7}	510	280	30	30	145	315	495	206.5	195.5	452.0	10	275.0	282.0	0.040	22.0	M16	M30	47.0

Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ7			EZ8		
	a	m	n	a	m	n
PHQ1141_K813_	∅200	247	24	∅250	249	24
PHQ1241_K913_	–	–	–	∅250	294	25
PHQ1241_K914_	∅200	353	25	∅250	365	25

14.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

PHQ	7	3	1	S	F	S	S	0055	K202VF	0115	EZ401U
-----	---	---	---	---	---	---	---	------	--------	------	--------

Explanation

Code	Designation	Design
PHQ	Type	Planetary gearbox
7	Size	7 (example)
3	Generation	Generation 3
4		Generation 4
1	Stages	Single-stage
S	Housing	Standard
F	Shaft	Flange shaft
S	Bearing	Standard bearing
V		Reinforced bearing (PHQ4 – PHQ5)
S	Backlash	Standard
R		Reduced (PHQ4 – PHQ9)
0055	Transmission ratio of output (i x 10)	i = 5.5 (example)
K202VF	Input	K2 right-angle geared motor (example)
0115	Transmission ratio of input (i x 10 rounded)	i = 11.57 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- For a detailed type designation of the motor, see the chapter [▶ 17.5](#)
- For the mounting position, see the chapter [▶ 14.5.3](#)
- Output gearbox side 3 or 4, see the chapter [▶ 14.5.3](#)
- Radial shaft seal rings at the output made of NBR or FKM (option), see the chapter [▶ 14.6.3](#)
- Position of the plug connectors, see the chapter [▶ 14.5.5](#)
- Reverse operation of the output shaft from $\pm 20^\circ$ to $\pm 90^\circ$ and horizontal installation, see the chapter [▶ 14.6.4](#)

To make selecting your geared motor easy, use our STOEBER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

14.5 Product description

14.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

14.5.2 Installation conditions

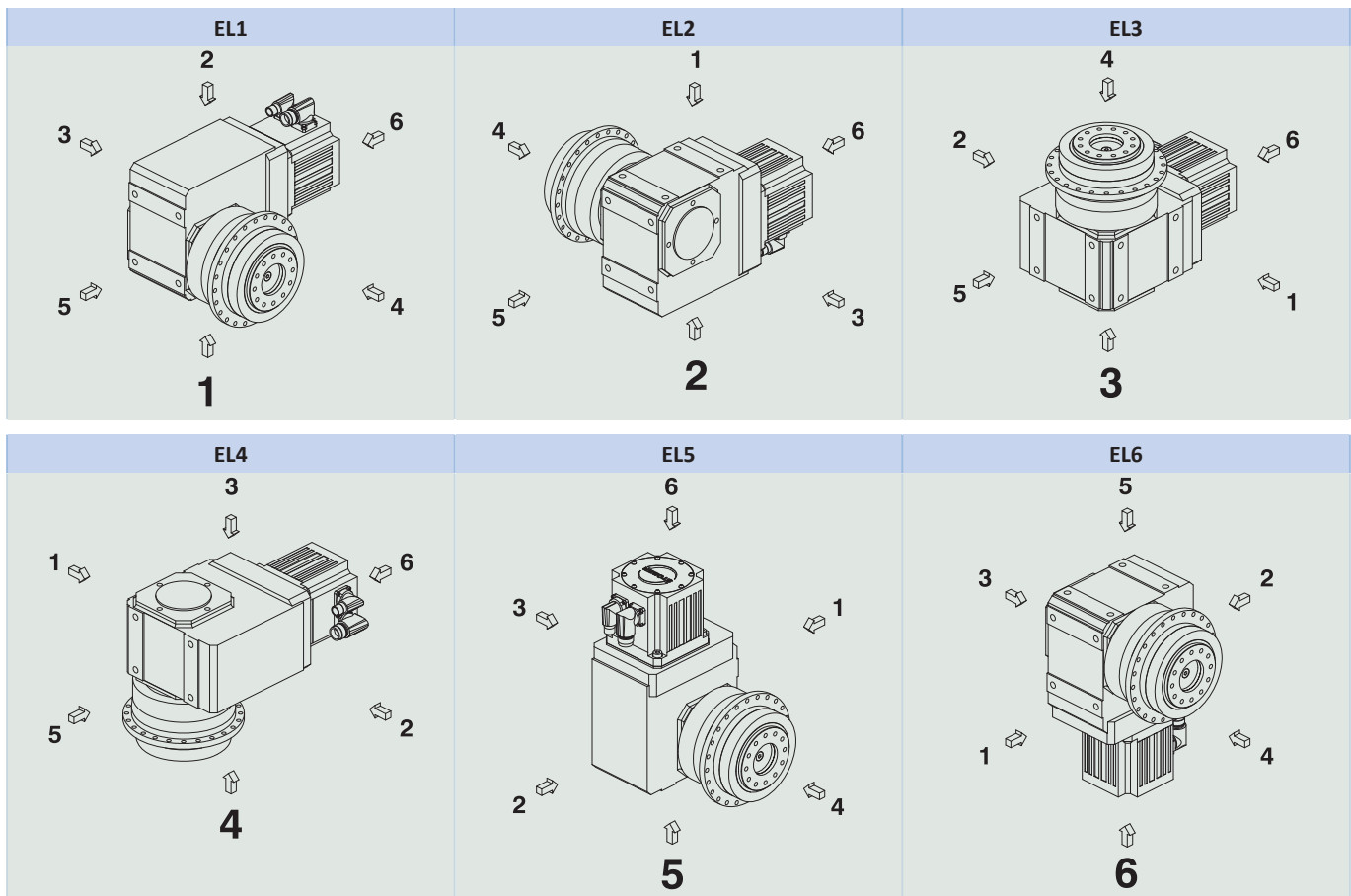
The torque and force values listed in this catalog are valid under the following conditions:

- When the flange shaft and gear housing are fastened on the machine side using screws of strength class 12.9
- When the gear housings are adjusted at pilot $\varnothing b1$, and also at pilot $\varnothing b$ for sizes PHQ11 and PHQ12. The machine-side fit must be H7.
- When the flange shaft is adjusted using the connecting element at pilot $\varnothing bf$ or $\varnothing df$

14.5.3 Mounting positions

The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

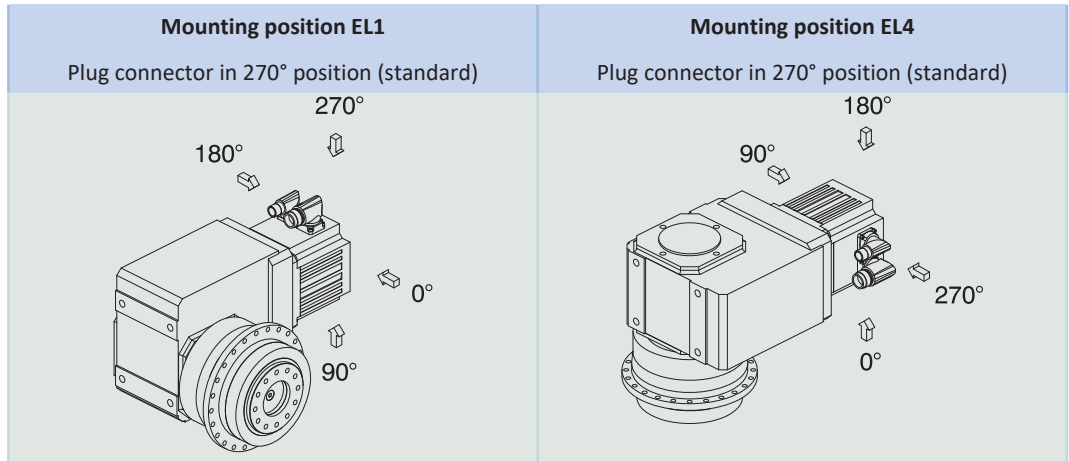
14.5.4 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

14.5.5 Position of the plug connectors



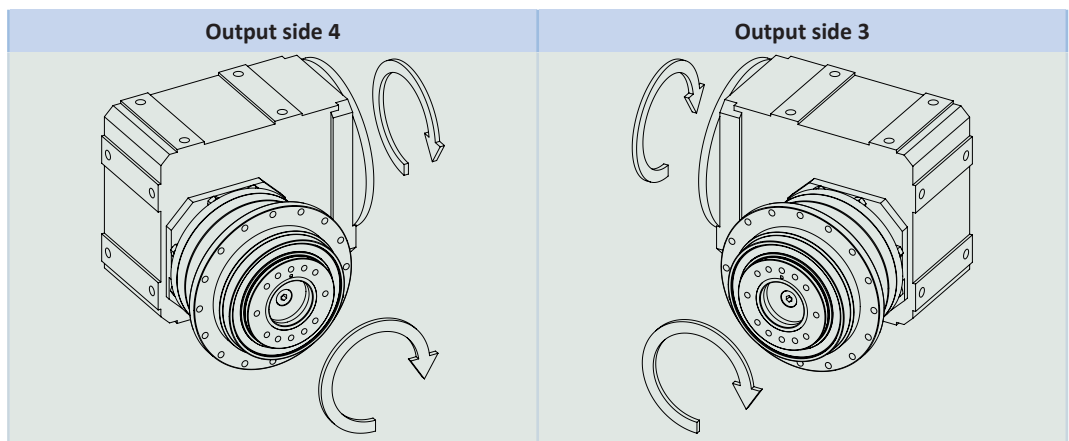
Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

14.5.6 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 90 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} three-stage	93%
η_{get} four-stage	92%
η_{get} five-stage	90%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

14.5.7 Direction of rotation



The pictures show mounting position EL1.

14.6 Project configuration

Project your drives using our SERVOfsoft designing software. Download SERVOfsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

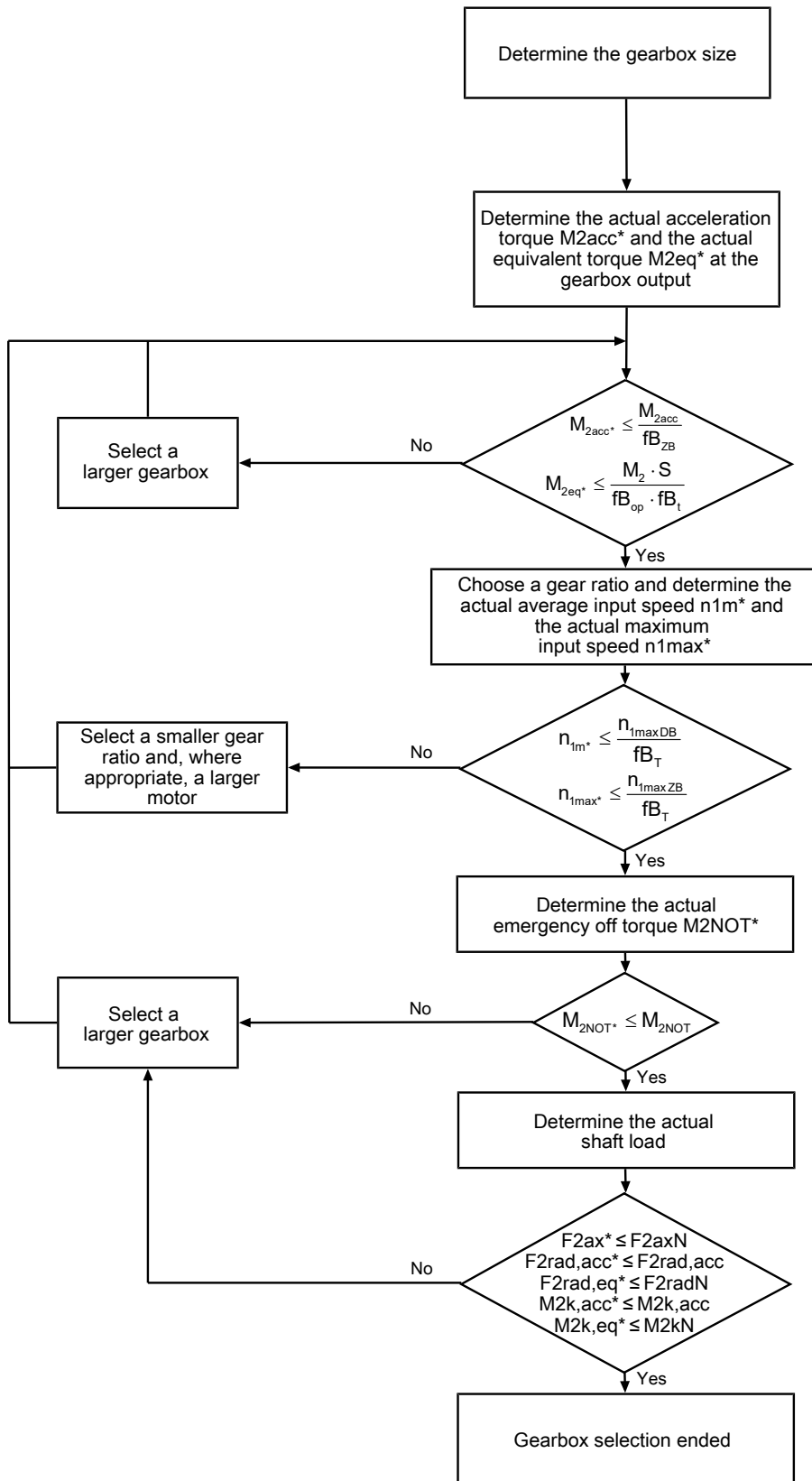
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

14.6.1 Drive selection

Drive selection for gearboxes

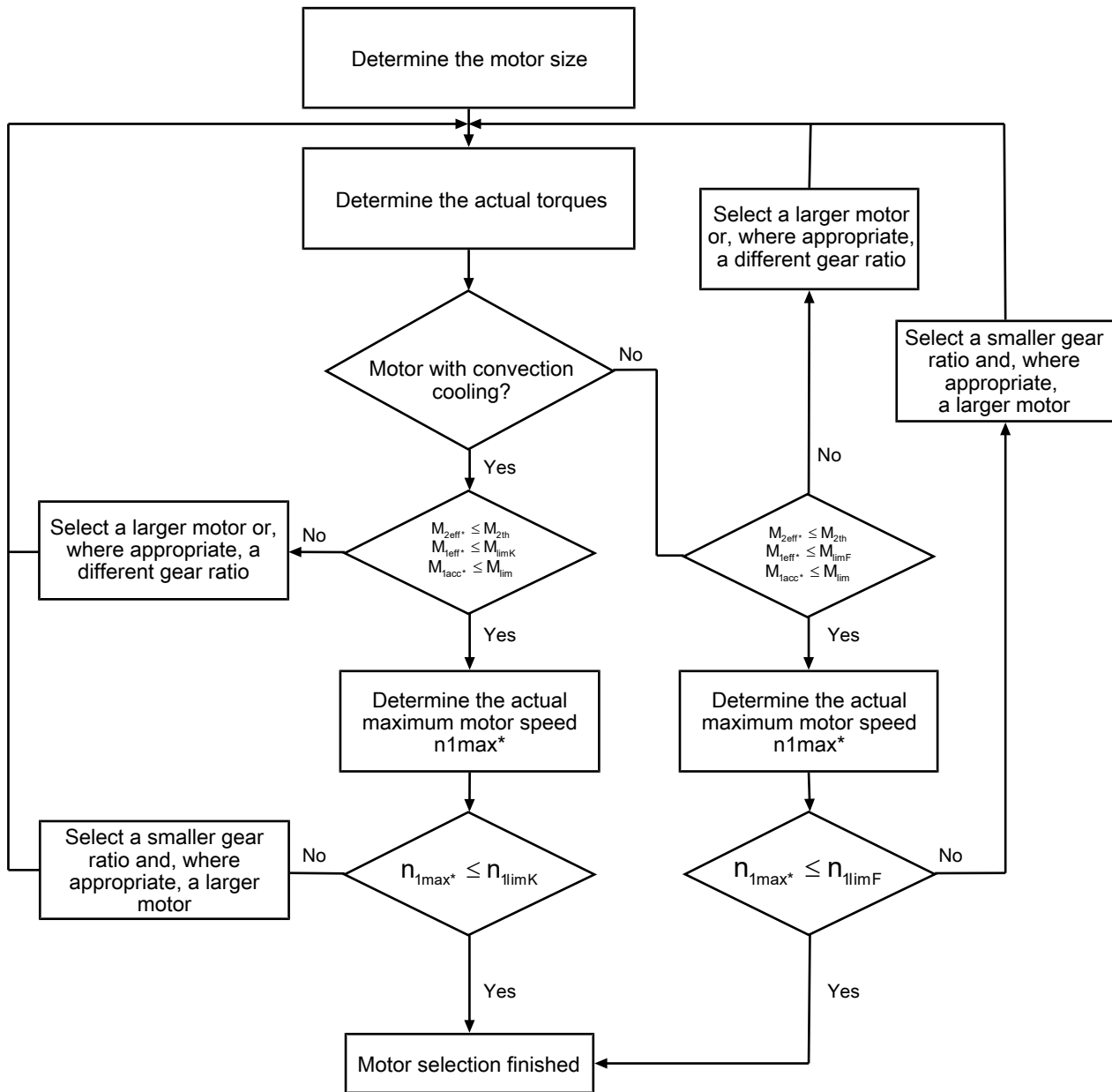


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} (M_{2accHT} for reduced backlash), M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

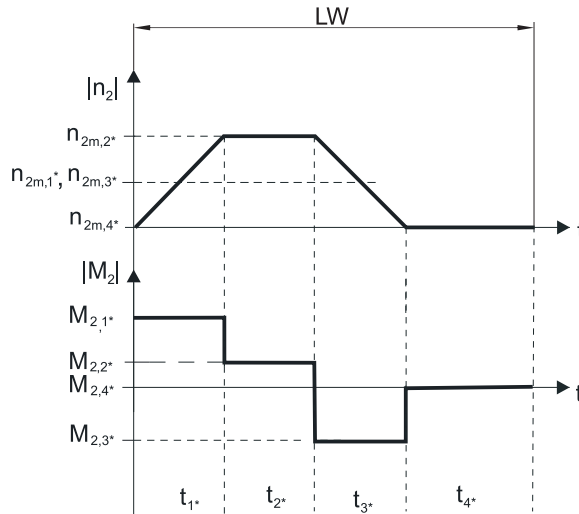
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:



Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot |M_{2,1*}|^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot |M_{2,n*}|^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} accordingly or select another geared motor size.)

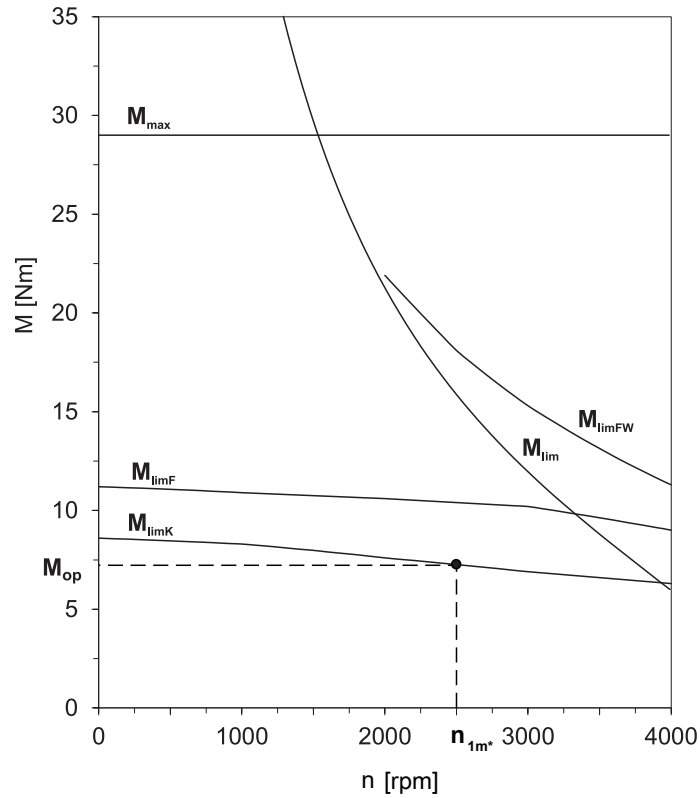
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,93 - \frac{a_{th}}{1000} \cdot athEL \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000}\right)^2$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position	a_{thEL}
EL1, 2	1.0
EL3, 4, 5, 6	1.1
Operating mode	fB_{op}
Uniform continuous operation	1.00
Cyclic operation	1.25
Reversing load cyclic operation	1.40
Run time	fB_t
Daily runtime ≤ 8 h	1.00
Daily runtime ≤ 16 h	1.15
Daily runtime ≤ 24 h	1.20
Cyclic operation	fB_{zB}
≤ 1000 load changes/hour (LW/h)	1.00
> 1000 load changes/hour (LW/h)	1.15

Temperature		f_{B_T}
Motor cooling	Surrounding temperature	
Motor with forced ventilation	$\leq 20\text{ }^\circ\text{C}$	0.9
	$\leq 30\text{ }^\circ\text{C}$	1.0
	$\leq 40\text{ }^\circ\text{C}$	1.15
Motor with convection cooling	$\leq 20\text{ }^\circ\text{C}$	1.0
	$\leq 30\text{ }^\circ\text{C}$	1.1
	$\leq 40\text{ }^\circ\text{C}$	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

14.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100\text{ rpm}$ ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots (housing, flange shaft)

Permitted shaft loads for standard bearing S

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PHQ4	83.0	2150	3095	3929	257	326	192
PHQ5	97.0	4150	4536	4897	440	475	429
PHQ7	86.0	6150	17045	17045	1466	1466	500
PHQ8	125.5	10050	27778	33333	3486	4183	1550
PHQ9	155.0	33000	48387	70968	7500	11000	7500
PHQ10	171.0	50000	51462	73099	8800	12500	9500
PHQ11	231.0	60000	47619	69264	11000	16000	11500
PHQ12	281.0	70000	64057	106761	18000	30000	14000

Permitted shaft loads for reinforced bearing V

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]	C_{2k} [Nm/ arcmin]
PHQ4	88.5	2900	4000	4000	354	354	217
PHQ5	104.0	5000	5500	5500	572	572	478

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100\text{ rpm}$:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100\text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

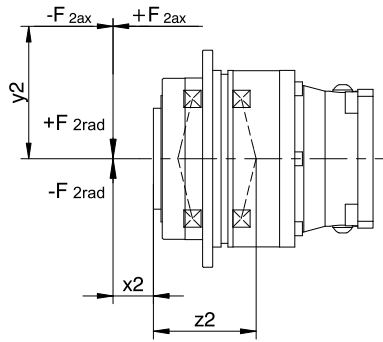


Fig. 1: Force application points

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax100} , $F_{2rad100}$ and M_{2k100} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

The following apply to the bearing service life L_{10h} ($ED_{10} \leq 40\%$):

$$L_{10h} > 10000 \text{ h with } 1 < M_{2kN}/M_{2k^*} < 1.25$$

$$L_{10h} > 20000 \text{ h with } 1.25 < M_{2kN}/M_{2k^*} < 1.5$$

$$L_{10h} > 30000 \text{ h with } 1.5 < M_{2kN}/M_{2k^*}$$

For different duty cycles:

$$L_{10h} > L_{10h(ED_{10}=40\%)} \cdot \frac{40\%}{ED_{10}}$$

14.6.3 Recommendation for radial shaft seal rings

For a duty cycle $> 60\%$ and higher surrounding temperatures, we recommend radial shaft seal rings made of FKM at the output.

Properties:

- Excellent temperature resistance
- High chemical stability
- Very good resistance to aging
- Excellent resistance in oils and greases
- For use in the food, beverage and pharmaceutical industries

Leak-proofness

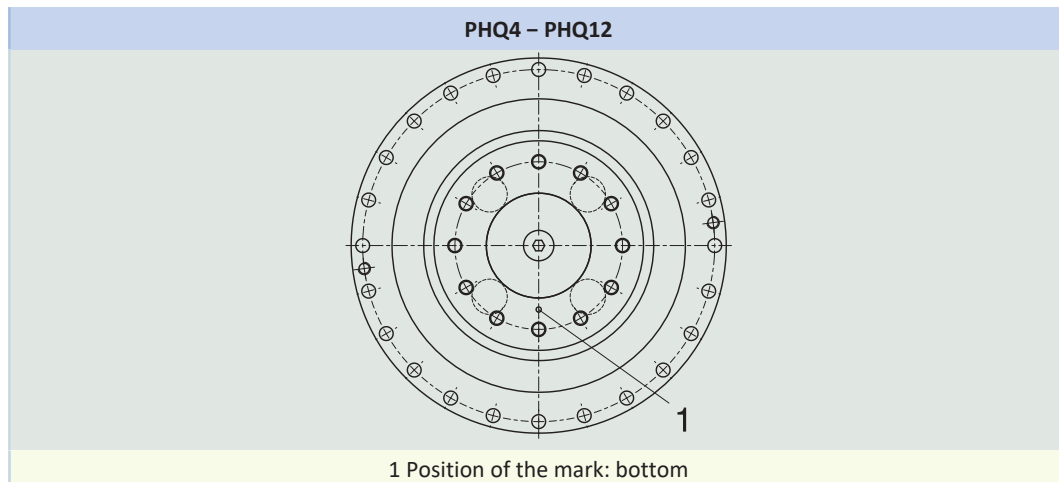
Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

14.6.4 Reverse operation

To ensure lubrication for circulating gearing parts during cyclic reverse operation from $\pm 20^\circ$ to $\pm 90^\circ$ at the output, pay careful attention to the position of the output shaft for the horizontal mounting of the gearbox, as shown in the diagrams below.

The images show the center position of reverse operation.

Cyclic reverse operation $\leq \pm 20^\circ$ on request.



Please note that the hole pattern may be different, depending on the size of the planetary gearbox.

14.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

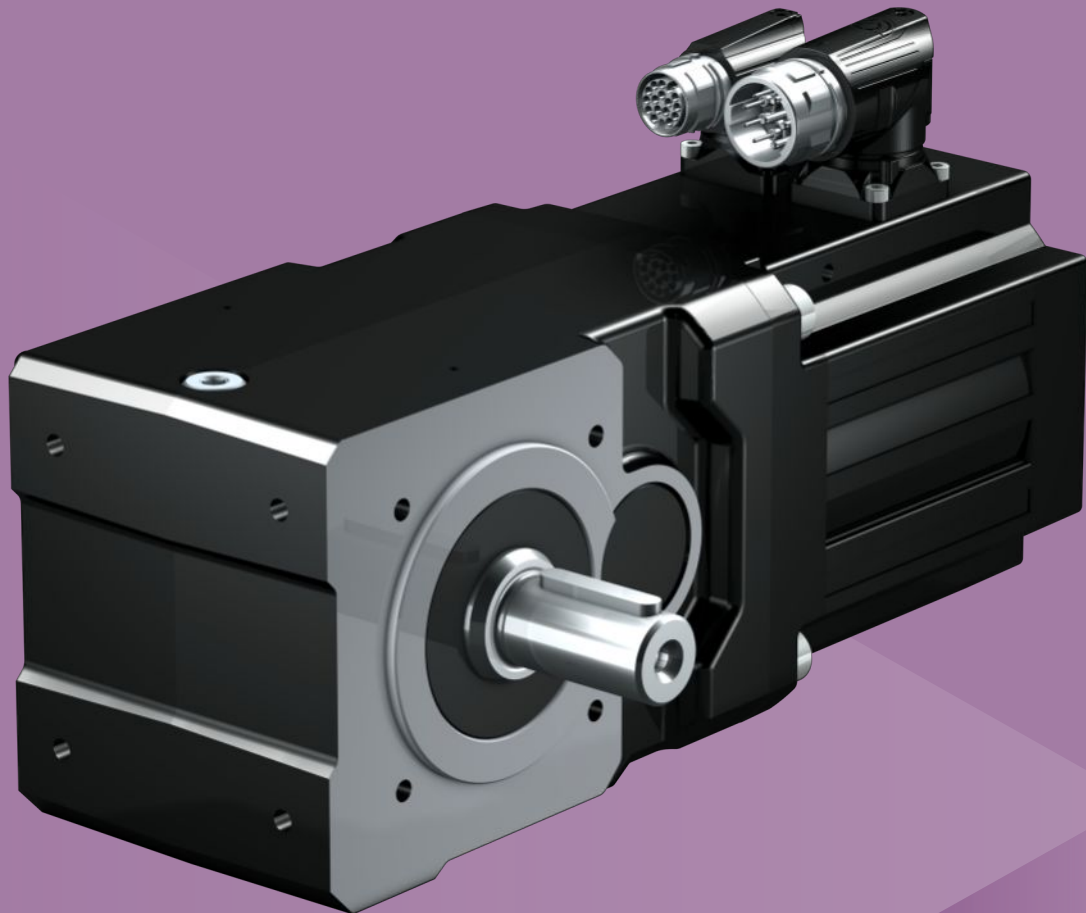
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors PHQ53K – PHQ83K, PHQ94K – PHQ124K	443357_en

15 KL helical bevel geared motors

Table of contents

15.1 Overview	428
15.2 Selection tables	429
15.3 Dimensional drawings	431
15.3.1 A shaft design (hollow shaft), G housing design (pitch circle diameter)	432
15.3.2 A shaft design (hollow shaft), NG housing design (base + pitch circle diameter)	434
15.3.3 Shaft design A (hollow shaft), housing design GD (pitch circle diameter + torque arm bracket)	436
15.3.4 A shaft design (hollow shaft), F housing design (flange)	438
15.3.5 G shaft design (solid shaft without feather key), G housing design (pitch circle diameter).....	440
15.3.6 G shaft design (solid shaft without feather key), NG housing design (base + pitch circle diameter).....	441
15.3.7 G shaft design (solid shaft without feather key), F housing design (flange)	442
15.3.8 P shaft design (solid shaft with feather key), G housing design (pitch circle diameter)	443
15.3.9 P shaft design (solid shaft with feather key), NG housing design (base + pitch circle diameter).....	444
15.3.10 P shaft design (solid shaft with feather key), F housing design (flange)	445
15.3.11 S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter).....	446
15.3.12 S shaft design (hollow shaft with shrink disk), NG housing design (base + pitch circle diameter).....	448
15.3.13 Shaft design S (hollow shaft with shrink ring), housing design GD (pitch circle diameter + torque arm bracket).....	450
15.3.14 S shaft design (hollow shaft with shrink disk), F housing design (flange)	452
15.4 Type designation	454
15.5 Product description.....	454
15.5.1 Input options	454
15.5.2 Housing design	455
15.5.3 Combinatorial shaft/housing design	455
15.5.4 Installation conditions	455
15.5.5 Gearbox sides	456
15.5.6 Lubricants	456
15.5.7 Position of the plug connectors	456
15.5.8 Other product features	456
15.5.9 Direction of rotation.....	457
15.6 Project configuration.....	457
15.6.1 Drive selection.....	458
15.6.2 Permitted shaft loads for the output shaft	462
15.6.3 Radial shaft seal rings.....	464
15.7 Additional documentation	464



15 Helical bevel geared motors

KL

15.1 Overview

Compact helical-gear right-angle geared motors

Features

- Power density ★★★★★
- Backlash ★★★★★
- Price category €
- Shaft load ★★★★★
- Smooth operation ★★★★★
- Torsional stiffness ★★★★★
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free ✓
- Any mounting position ✓
- Small installation space ✓
- FKM seal ring at the input ✓
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	4 – 32
M_{2acc}	10 – 65 Nm
$\Delta\phi_2$	16 – 25 arcmin
η_{get}	97 %

15.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from 0 °C to 40 °C
- Drives with convection-cooled motors (e.g. EZ401U)

For the technical data on drives with forced ventilated motors (e.g. EZ401B), refer to

<https://configurator.stoeber.de/en-US/>.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

n_2 [rpm]	M_2 [Nm]	$M_{2,0}$ [Nm]	a_{th}	S	Type	M_{2acc} [Nm]	M_{2NOT} [Nm]	i	i_{exakt}	n_{1maxDB} [rpm]	n_{1maxZB} [rpm]	J_1 [kgcm ²]	$\Delta\phi_2$ [arcmin]	C_2 [Nm/ arcmin]	m [kg]
KL1 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 30 \text{ Nm}$)															
188	14	15	16	1.7	KL102_0160 EZ301U	30	60	16.00	16/1	4000	6000	0.22	20.0	1.8	6.6
188	25	26	28	1.0	KL102_0160 EZ302U	30	60	16.00	16/1	4000	6000	0.32	20.0	1.8	7.2
375	7.2	7.4	17	2.7	KL102_0080 EZ301U	22	59	8.000	8/1	3500	6000	0.28	20.0	1.8	6.6
375	12	13	29	1.6	KL102_0080 EZ302U	30	59	8.000	8/1	3500	6000	0.38	20.0	1.8	7.2
375	16	17	38	1.2	KL102_0080 EZ303U	30	59	8.000	8/1	3500	6000	0.49	20.0	1.8	7.7
750	3.6	3.7	22	3.6	KL102_0040 EZ301U	11	30	4.000	4/1	3500	6000	0.31	25.0	1.3	6.6
750	6.2	6.5	37	2.1	KL102_0040 EZ302U	19	30	4.000	4/1	3500	6000	0.41	25.0	1.3	7.2
750	8.0	8.5	49	1.6	KL102_0040 EZ303U	22	30	4.000	4/1	3500	6000	0.52	25.0	1.3	7.7
KL1 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 32 \text{ Nm}$)															
188	12	14	11	1.5	KL102_0320 EZ202U	32	64	32.00	32/1	4000	6000	0.15	20.0	1.7	6.5
188	19	21	17	1.0	KL102_0320 EZ203U	32	64	32.00	32/1	4000	6000	0.19	20.0	1.7	6.8
375	6.2	6.8	8.8	3.2	KL102_0160 EZ202U	23	60	16.00	16/1	4000	6000	0.15	20.0	1.8	6.5
375	9.5	11	13	2.1	KL102_0160 EZ203U	30	60	16.00	16/1	4000	6000	0.19	20.0	1.8	6.8
375	14	15	20	1.4	KL102_0160 EZ301U	30	60	16.00	16/1	4000	6000	0.22	20.0	1.8	6.6
750	4.7	5.4	14	3.3	KL102_0080 EZ203U	21	59	8.000	8/1	3500	6000	0.25	20.0	1.8	6.8
750	6.9	7.4	21	2.3	KL102_0080 EZ301U	22	59	8.000	8/1	3500	6000	0.28	20.0	1.8	6.6
750	12	13	35	1.4	KL102_0080 EZ302U	30	59	8.000	8/1	3500	6000	0.38	20.0	1.8	7.2
750	15	17	46	1.0	KL102_0080 EZ303U	30	59	8.000	8/1	3500	6000	0.49	20.0	1.8	7.7
1500	2.4	2.7	18	4.4	KL102_0040 EZ203U	10	30	4.000	4/1	3500	6000	0.29	25.0	1.3	6.8
1500	3.5	3.7	26	3.0	KL102_0040 EZ301U	11	30	4.000	4/1	3500	6000	0.31	25.0	1.3	6.6
1500	5.8	6.5	45	1.8	KL102_0040 EZ302U	19	30	4.000	4/1	3500	6000	0.41	25.0	1.3	7.2
1500	7.6	8.7	58	1.4	KL102_0040 EZ303U	22	30	4.000	4/1	3500	6000	0.52	25.0	1.3	7.7
KL2 ($n_{1N} = 3000 \text{ min}^{-1}$, $M_{2acc,max} = 65 \text{ Nm}$)															
94	29	29	11	1.6	KL202_0320 EZ301U	65	130	32.00	32/1	4000	6000	0.26	16.0	3.2	9.1
188	14	15	9.0	3.5	KL202_0160 EZ301U	43	118	16.00	16/1	4000	6000	0.28	16.0	4.0	9.1
188	25	26	15	2.0	KL202_0160 EZ302U	60	118	16.00	16/1	4000	6000	0.38	16.0	4.0	9.7
188	32	34	20	1.6	KL202_0160 EZ303U	60	118	16.00	16/1	4000	6000	0.49	16.0	4.0	10
188	43	47	27	1.2	KL202_0160 EZ401U	60	120	16.00	16/1	4000	6000	1.0	16.0	4.0	12
375	7.2	7.4	15	3.5	KL202_0080 EZ301U	22	59	8.000	8/1	4000	6000	0.31	20.0	2.4	9.1
375	12	13	26	2.0	KL202_0080 EZ302U	35	59	8.000	8/1	4000	6000	0.41	20.0	2.4	9.7
375	16	17	33	1.6	KL202_0080 EZ303U	35	59	8.000	8/1	4000	6000	0.52	20.0	2.4	10
375	22	23	29	1.8	KL202_0080 EZ401U	60	120	8.000	8/1	3500	6000	1.2	16.0	4.0	12
375	36	40	48	1.1	KL202_0080 EZ402U	60	120	8.000	8/1	3500	6000	1.9	16.0	4.0	13
750	11	12	34	2.6	KL202_0040 EZ401U	33	108	4.000	4/1	3500	6000	1.4	20.0	2.4	12
750	18	20	57	1.5	KL202_0040 EZ402U	53	108	4.000	4/1	3500	6000	2.1	20.0	2.4	13
750	27	33	84	1.0	KL202_0040 EZ404U	53	108	4.000	4/1	3500	6000	3.4	20.0	2.4	15
KL2 ($n_{1N} = 6000 \text{ min}^{-1}$, $M_{2acc,max} = 65 \text{ Nm}$)															
188	28	29	14	1.4	KL202_0320 EZ301U	65	130	32.00	32/1	4000	6000	0.26	16.0	3.2	9.1
375	14	15	11	2.9	KL202_0160 EZ301U	43	118	16.00	16/1	4000	6000	0.28	16.0	4.0	9.1
375	23	26	18	1.7	KL202_0160 EZ302U	60	118	16.00	16/1	4000	6000	0.38	16.0	4.0	9.7
375	30	35	24	1.3	KL202_0160 EZ303U	60	118	16.00	16/1	4000	6000	0.49	16.0	4.0	10
375	36	43	28	1.1	KL202_0160 EZ401U	60	120	16.00	16/1	4000	6000	1.0	16.0	4.0	12
750	6.9	7.4	14	3.7	KL202_0080 EZ301U	22	59	8.000	8/1	4000	6000	0.31	20.0	2.4	9.1
750	12	13	24	2.2	KL202_0080 EZ302U	35	59	8.000	8/1	4000	6000	0.41	20.0	2.4	9.7
750	15	17	32	1.7	KL202_0080 EZ303U	35	59	8.000	8/1	4000	6000	0.52	20.0	2.4	10
750	18	22	30	1.8	KL202_0080 EZ401U	60	120	8.000	8/1	3500	6000	1.2	16.0	4.0	12
750	27	38	45	1.2	KL202_0080 EZ402U	60	120	8.000	8/1	3500	6000	1.9	16.0	4.0	13
1500	8.9	11	35	2.5	KL202_0040 EZ401U	33	108	4.000	4/1	3500	6000	1.4	20.0	2.4	12
1500	14	19	54	1.6	KL202_0040 EZ402U	53	108	4.000	4/1	3500	6000	2.1	20.0	2.4	13

15.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

Tolerances

Axis height in accordance with DIN 747	Tolerance
Up to 50 mm	-0.4 mm
Up to 250 mm	-0.5 mm
Up to 630 mm	-0.6 mm

Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6
Feather keys	DIN 6885-1, high form A

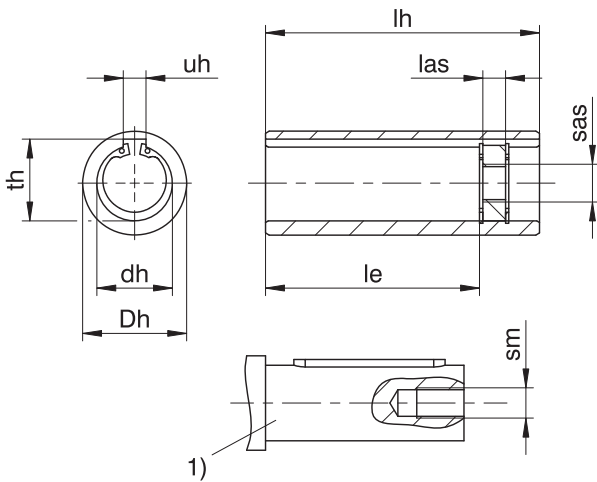
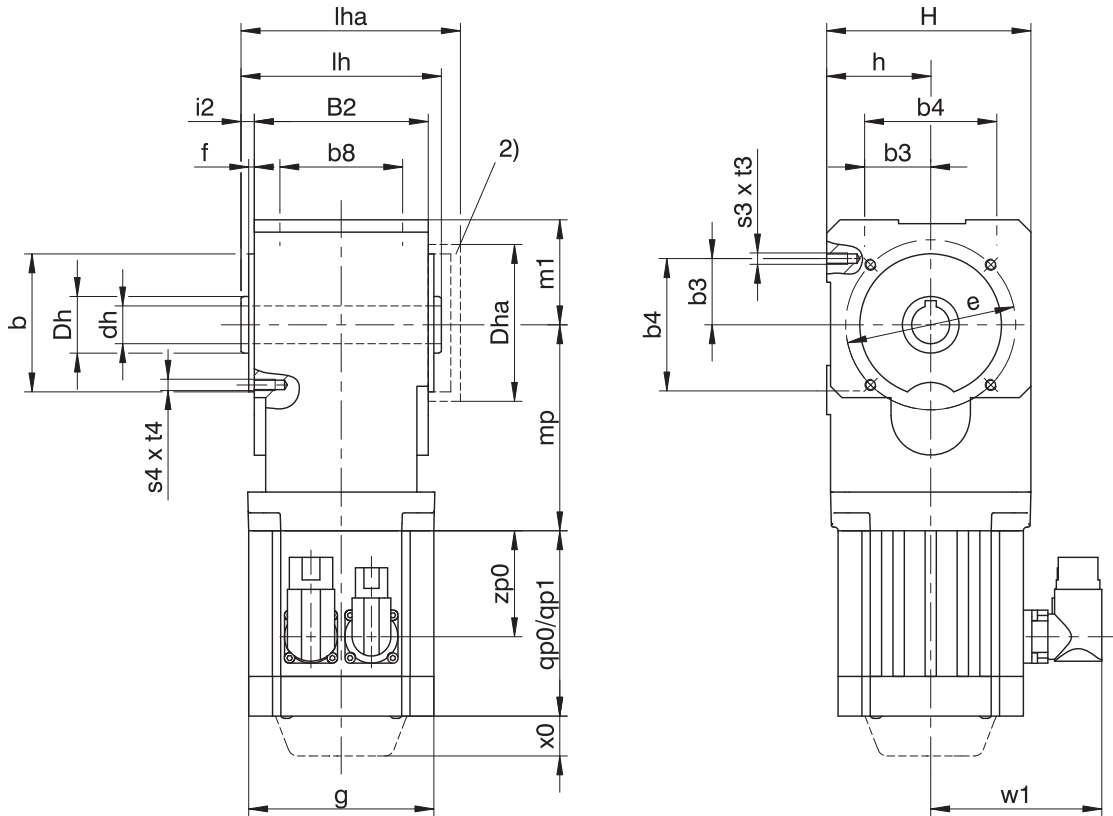
Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

Hollow shaft	Tolerance
Hollow shaft hole fit	ISO G7
Feather keys	DIN 6885-1, high form

Flange	Pilot tolerance
Up to 300 mm	ISO j6
Starting at 350 mm	ISO h6

15.3.1 A shaft design (hollow shaft), G housing design (pitch circle diameter)



- | | | | |
|-----|---|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	Øb	b3	b4	b8	B2	Ødh	Dh	Dha	Øe	f	h	H	i2	le	lh	las	lha	m1	s3	s4	sm	sas	t3	t4	th	uh
KL1	60 _p	27.5	55	50	75	16 ^{H7}	25	70	75	3	46	90	6	60.5	87	12	91	46	M6	M6	M5	M6	11	11	18.3	5 ^{h9}
KL2	75 _p	35.0	70	65	92	20 ^{H7}	30	80	90	3	55	108	7	79.5	106	12	110	55	M6	M6	M6	M8	13	13	22.8	6 ^{h9}

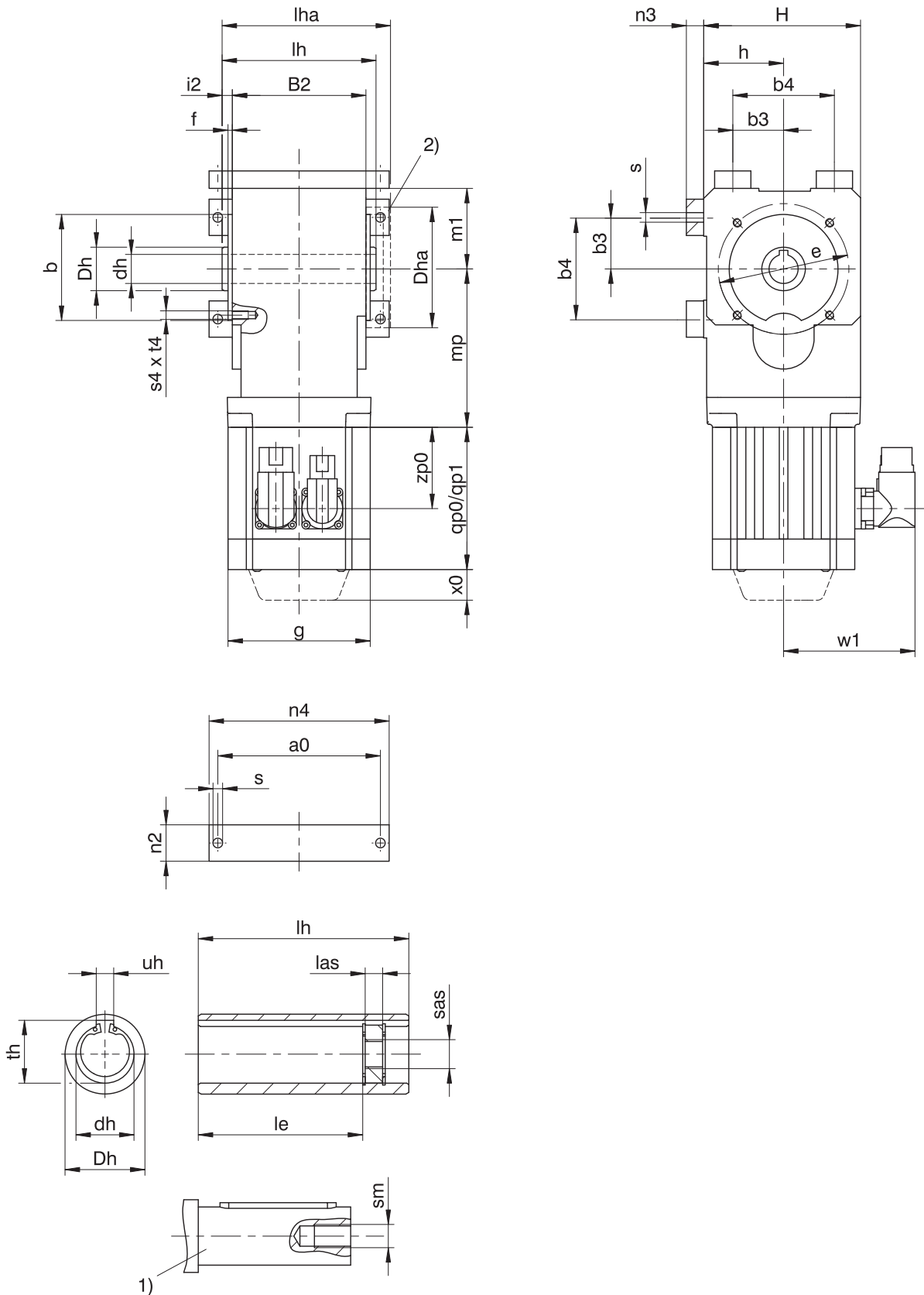
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.3.2 A shaft design (hollow shaft), NG housing design (base + pitch circle diameter)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 E22: Applies only to motors with brake and encoders using an optical or inductive measuring method
 E23 – E28: Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

2) Cover (optional)

Dimensions of gearboxes

Type	a0	Øb	b3	b4	B2	Ødh	Dh	Dha	Øe	f	h	H	i2	le	lh	las	lha	m1	n2	n3	n4	Øs	s4	sm	sas	t4	th	uh
KL1	95	60 _{js}	27.5	55	75	16 ^{H7}	25	70	75	3	46	90	6	60.5	87	12	91	46	20	12	107	6.6	M6	M5	M6	11	18.3	5 ^{h9}
KL2	112	75 _{js}	35.0	70	92	20 ^{H7}	30	80	90	3	55	108	7	79.5	106	12	110	55	25	12	124	6.6	M6	M6	M8	13	22.8	6 ^{h9}

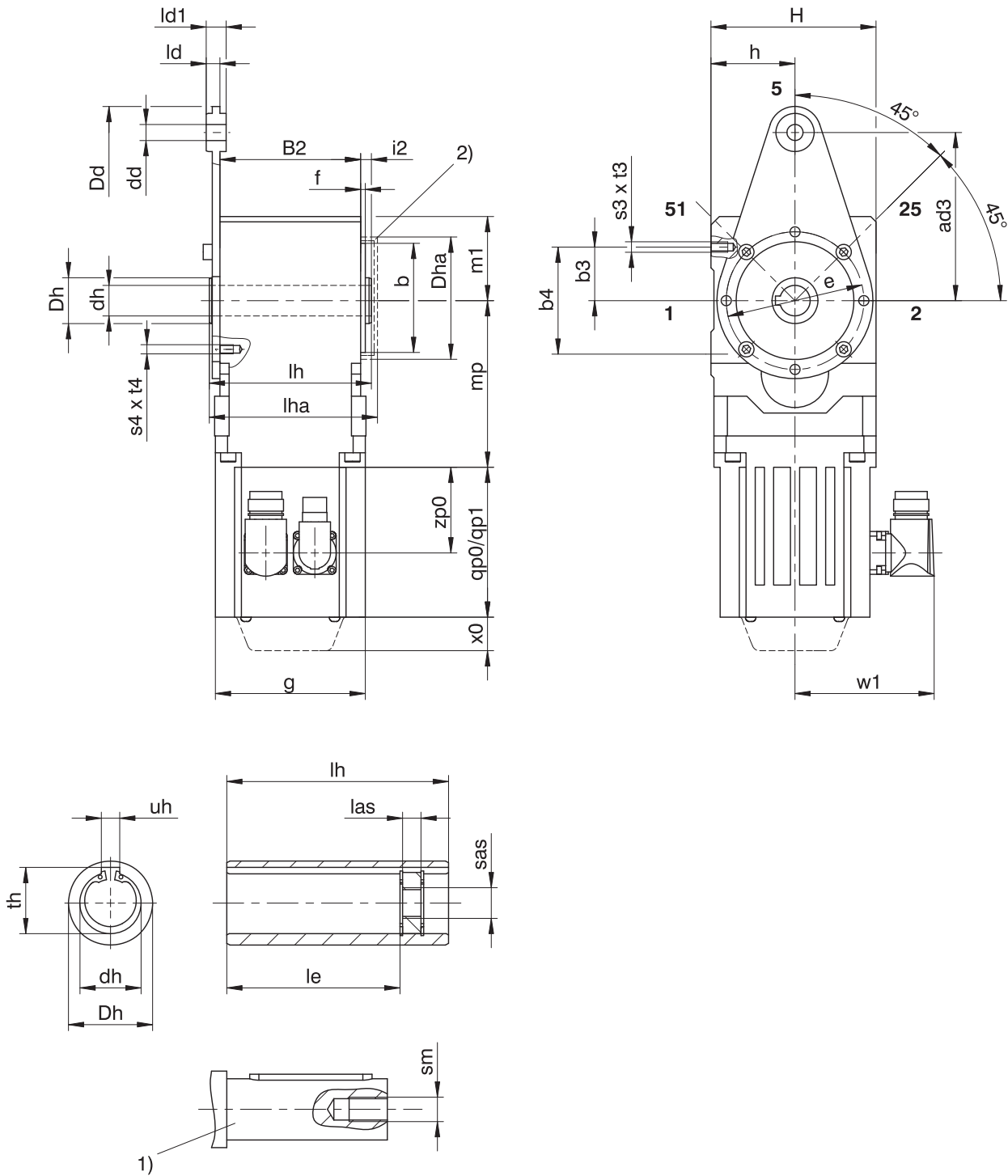
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.3.3 Shaft design A (hollow shaft), housing design GD (pitch circle diameter + torque arm bracket)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 E22: Applies only to motors with brake and encoders using an optical or inductive measuring method
 E23 – E28: Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

2) Cover (optional)

Dimensions of gearboxes

Type	ad3	Øb	b3	b4	B2	Ødd	Ødh	ØDd	ØDh	ØDha	Øe	f	h	H	i2	le	lh	las	ld	ld1	lha	m1	s3	s4	sm	sas	t3	t4	th	uh
KL2	110	75 ₆	35	70	92	10.5	20 ^{H7}	34	30	80	90	3	55	108	7	79.5	106	12	9	13	110	55	M6	M6	M6	M8	13	13	22.8	6 ^{JS9}

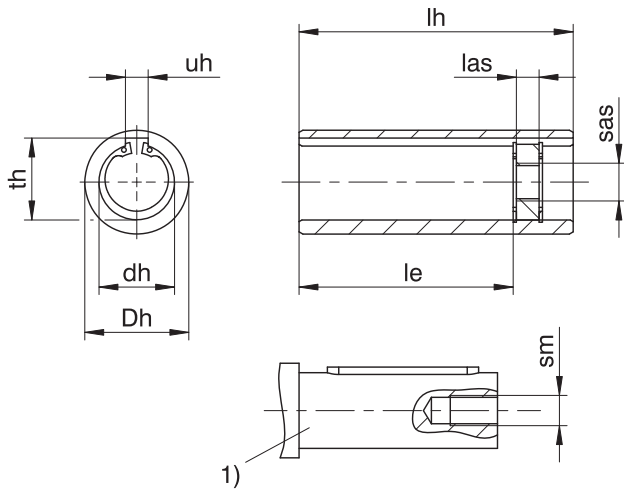
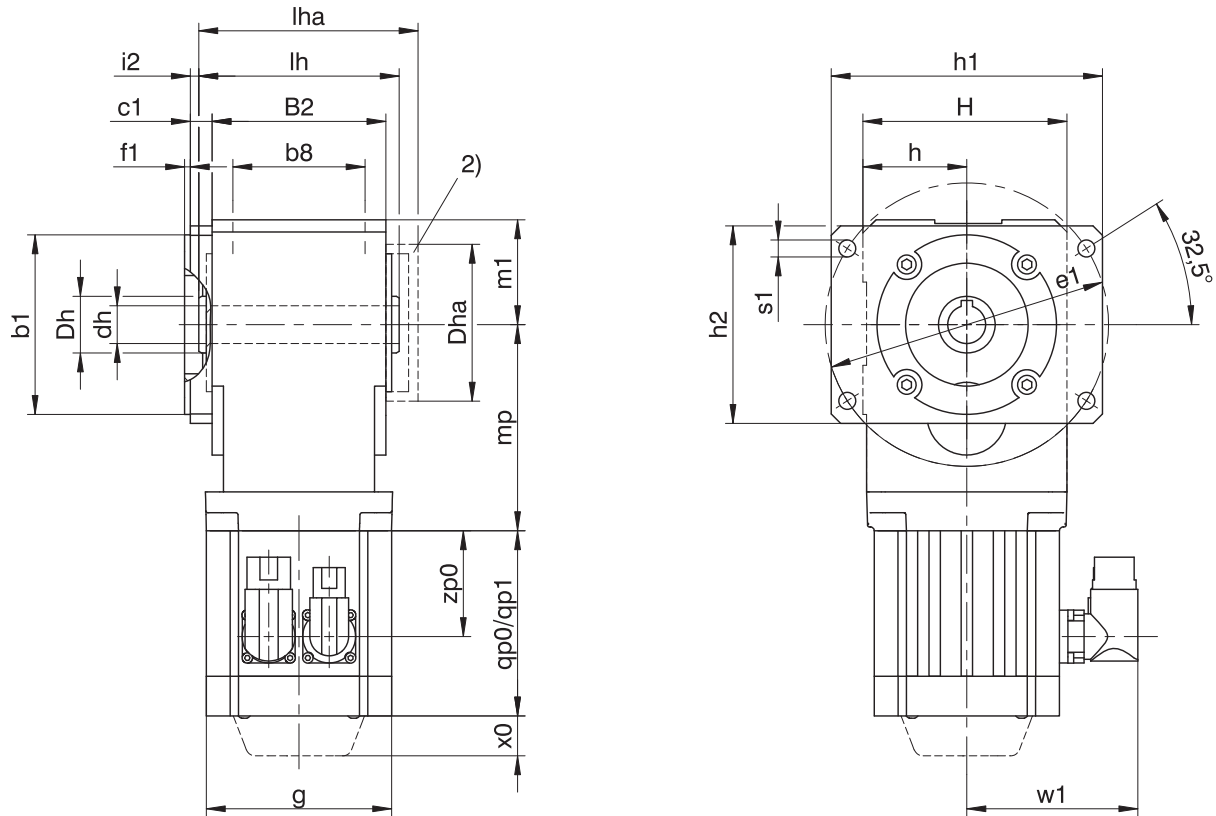
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ3 mp	EZ4 mp
KL202	112.5	109.0

15.3.4 A shaft design (hollow shaft), F housing design (flange)



- | | | | |
|-----|--|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	Øb1	b8	B2	c1	Ødh	Dh	Dha	Øe1	f1	h	h1	h2	H	i2	le	lh	las	lha	m1	Øs1	sm	sas	th	uh
KL1	60 ₆	50	75	11.5	16 ^{H7}	25	70	130	3	46	128.5	88.5	90	5.5	60.5	87	12	91	46	9	M5	M6	18.3	5 ^{H9}
KL2	95 ₆	65	92	11.5	20 ^{H7}	30	80	150	3	55	143.5	104.5	108	4.5	79.5	106	12	110	55	9	M6	M8	22.8	6 ^{H9}

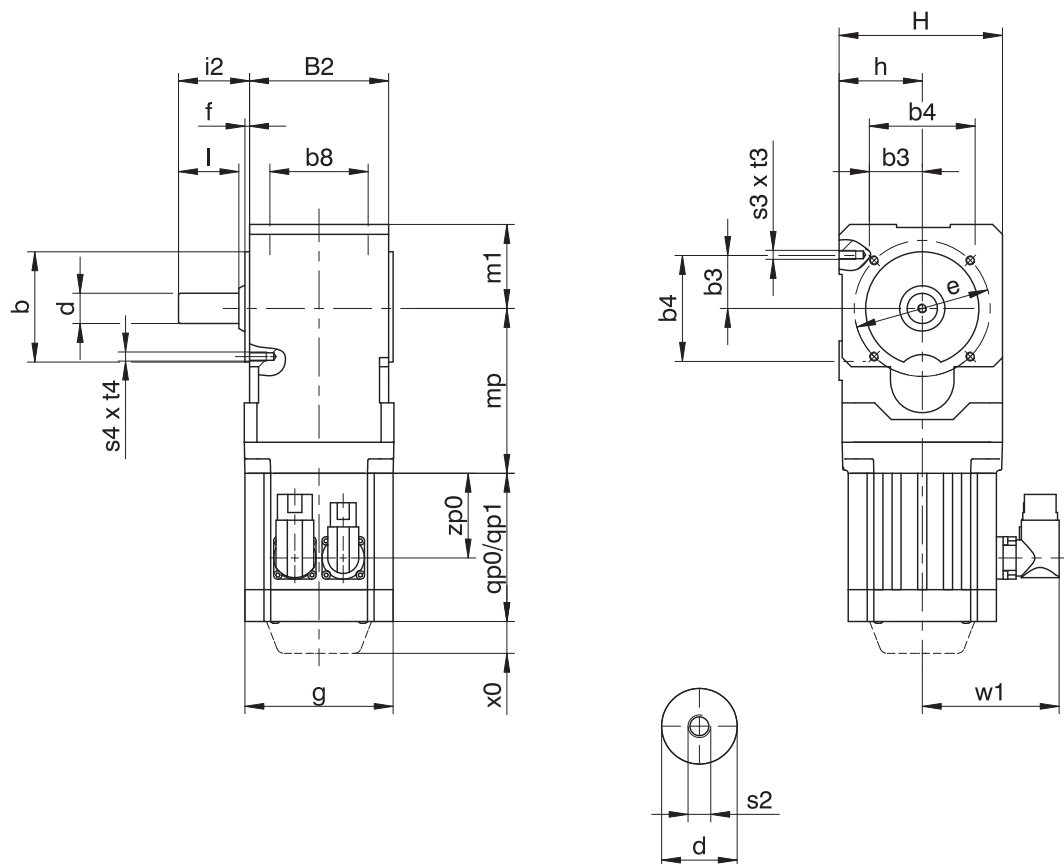
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.3.5 G shaft design (solid shaft without feather key), G housing design (pitch circle diameter)



qp0 Applies to motors without brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

qp1 Applies to motors with brake.

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	$\varnothing b$	b_3	b_4	b_8	B_2	$\varnothing d$	$\varnothing e$	f	h	H	i_2	l	m_1	s_2	s_3	s_4	t_3	t_4
KL1	60 _p	27.5	55	50	75	16 _{k6}	75	3	46	90	38	32	46	M5	M6	M6	11	11
KL2	75 _p	35.0	70	65	92	20 _{k6}	90	3	55	108	47	40	55	M6	M6	M6	13	13

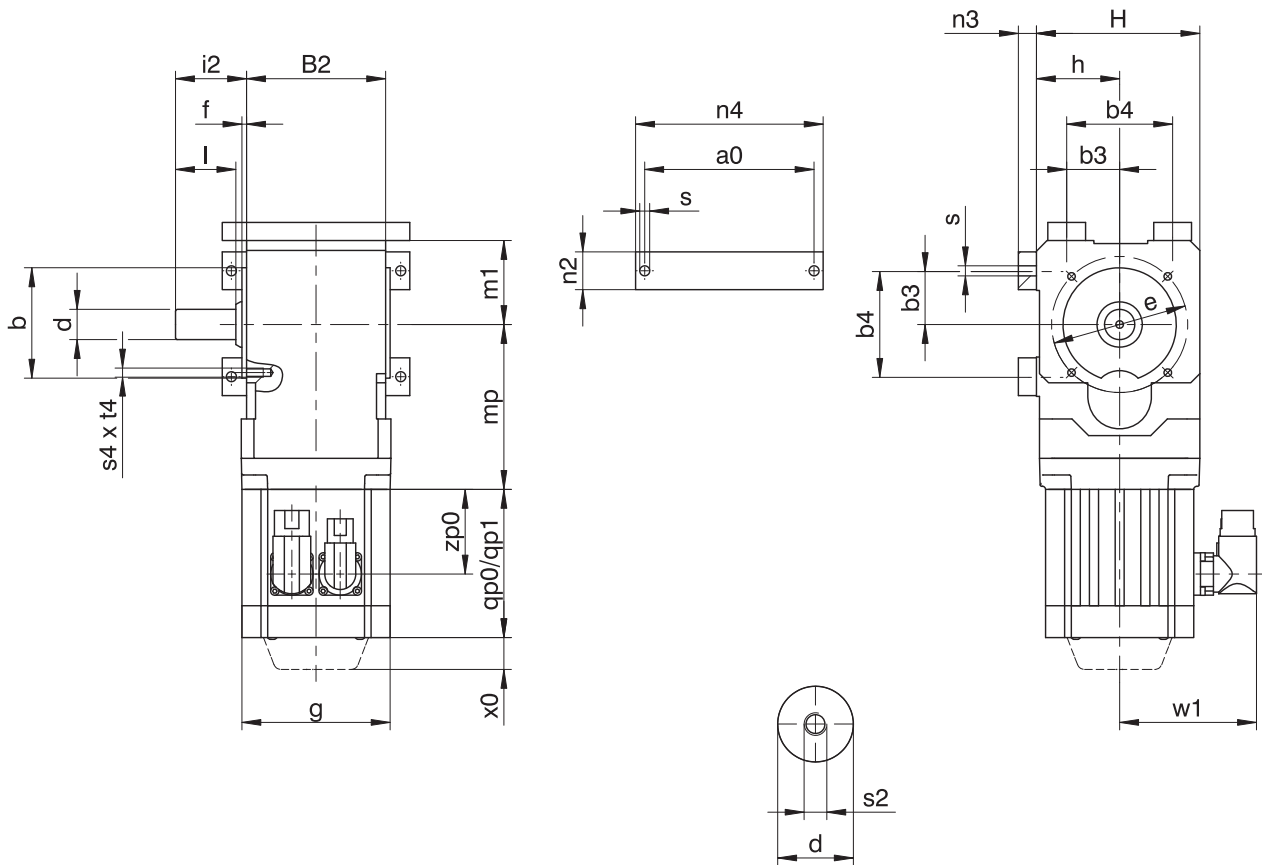
Dimensions of motors

Type	$\square g$	q_{p0}	q_{p1}	w_1	x_0	z_{p0}
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.6 G shaft design (solid shaft without feather key), NG housing design (base + pitch circle diameter)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	a0	Øb	b3	b4	B2	Ød	Øe	f	h	H	i2	l	m1	n2	n3	n4	Øs	s2	s4	t4
KL1	95	60 _f	27.5	55	75	16 ₆	75	3	46	90	38	32	46	20	12	107	6.6	M5	M6	11
KL2	112	75 _f	35.0	70	92	20 ₆	90	3	55	108	47	40	55	25	12	124	6.6	M6	M6	13

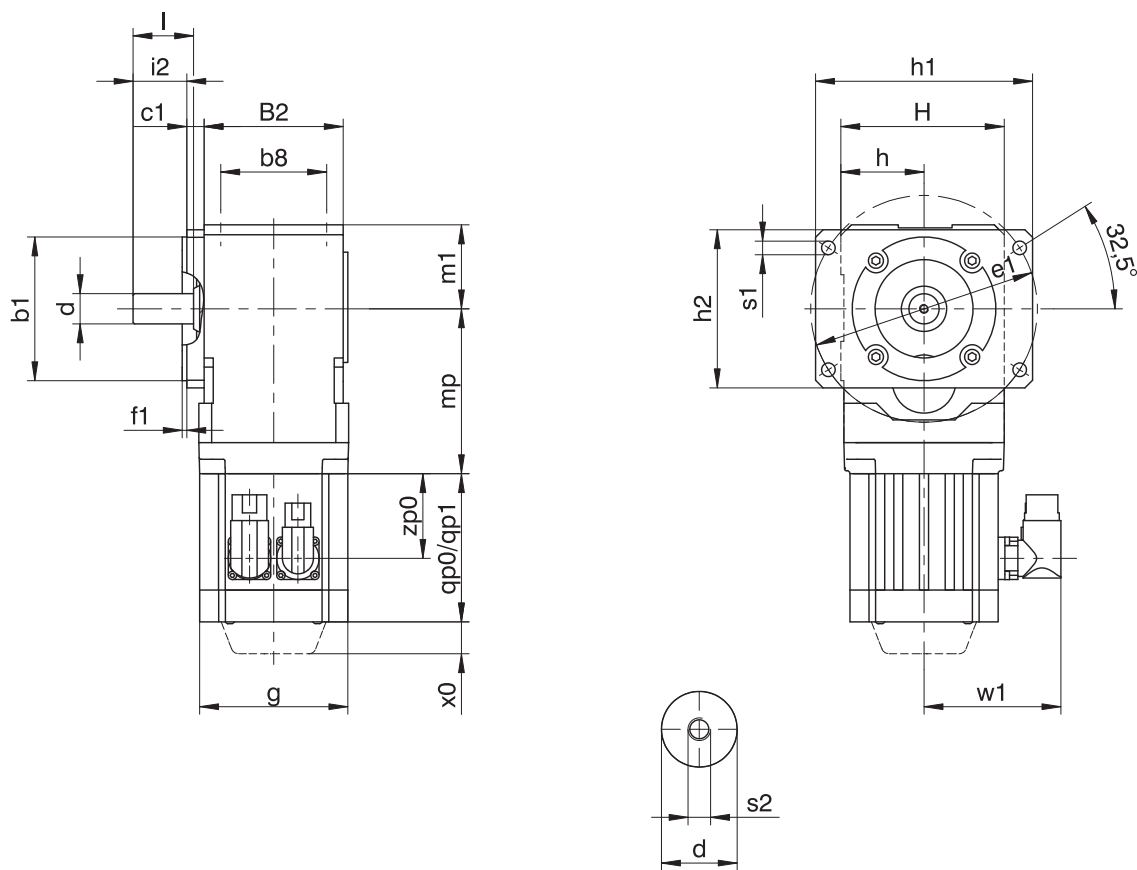
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.7 G shaft design (solid shaft without feather key), F housing design (flange)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	$\varnothing b1$	b8	B2	c1	$\varnothing d$	$\varnothing e1$	f1	h	h1	h2	H	i2	l	m1	$\varnothing s1$	s2
KL1	60 _{f6}	50	75	11.5	16 _{k6}	130	3	46	128.5	88.5	90	26.5	32	46	9	M5
KL2	95 _{f6}	65	92	11.5	20 _{k6}	150	3	55	143.5	104.5	108	35.5	40	55	9	M6

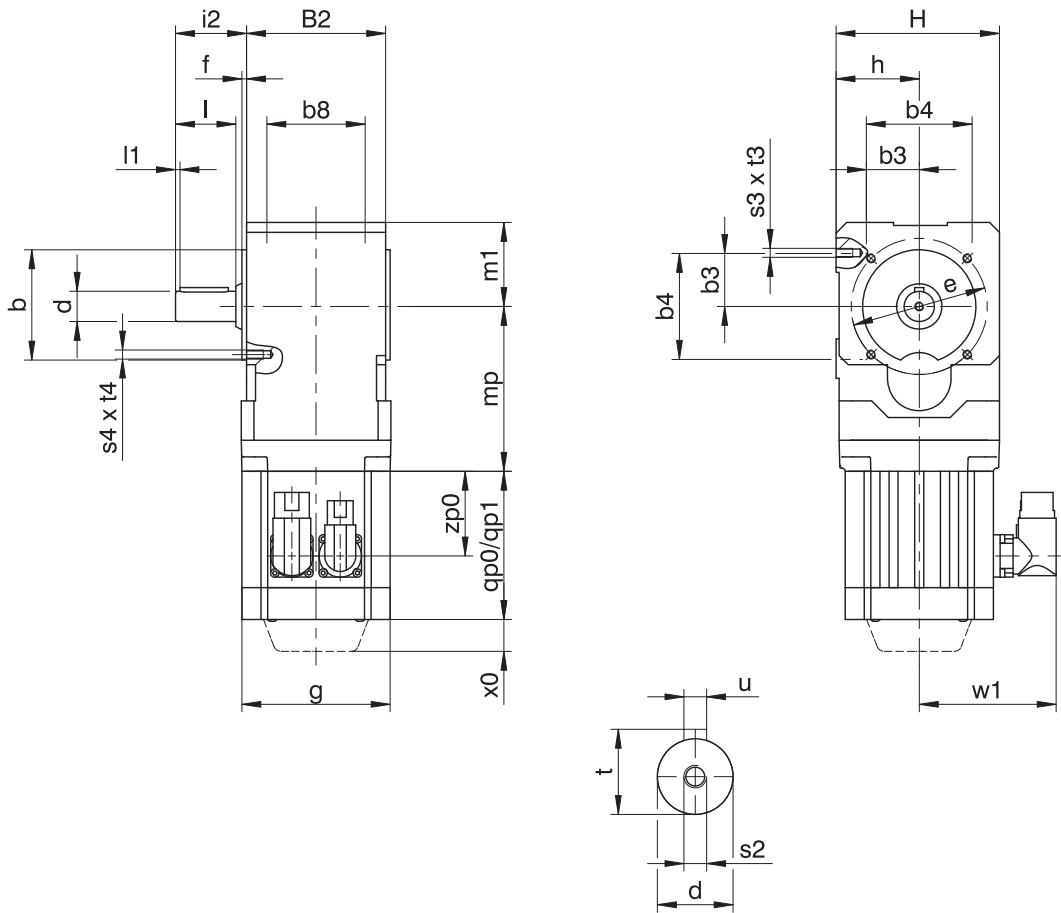
Dimensions of motors

Type	$\square g$	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.8 P shaft design (solid shaft with feather key), G housing design (pitch circle diameter)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using w1 an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	$\varnothing b$	b_3	b_4	b_8	B_2	$\varnothing d$	$\varnothing e$	f	h	H	i_2	l	l_1	m_1	s_2	s_3	s_4	t	t_3	t_4	u
KL1	60 _{je}	27.5	55	50	75	16 _{ke}	75	3	46	90	38	32	3	46	M5	M6	M6	18	11	11	A5×5×22
KL2	75 _{je}	35.0	70	65	92	20 _{ke}	90	3	55	108	47	40	3	55	M6	M6	M6	22.5	13	13	A6×6×32

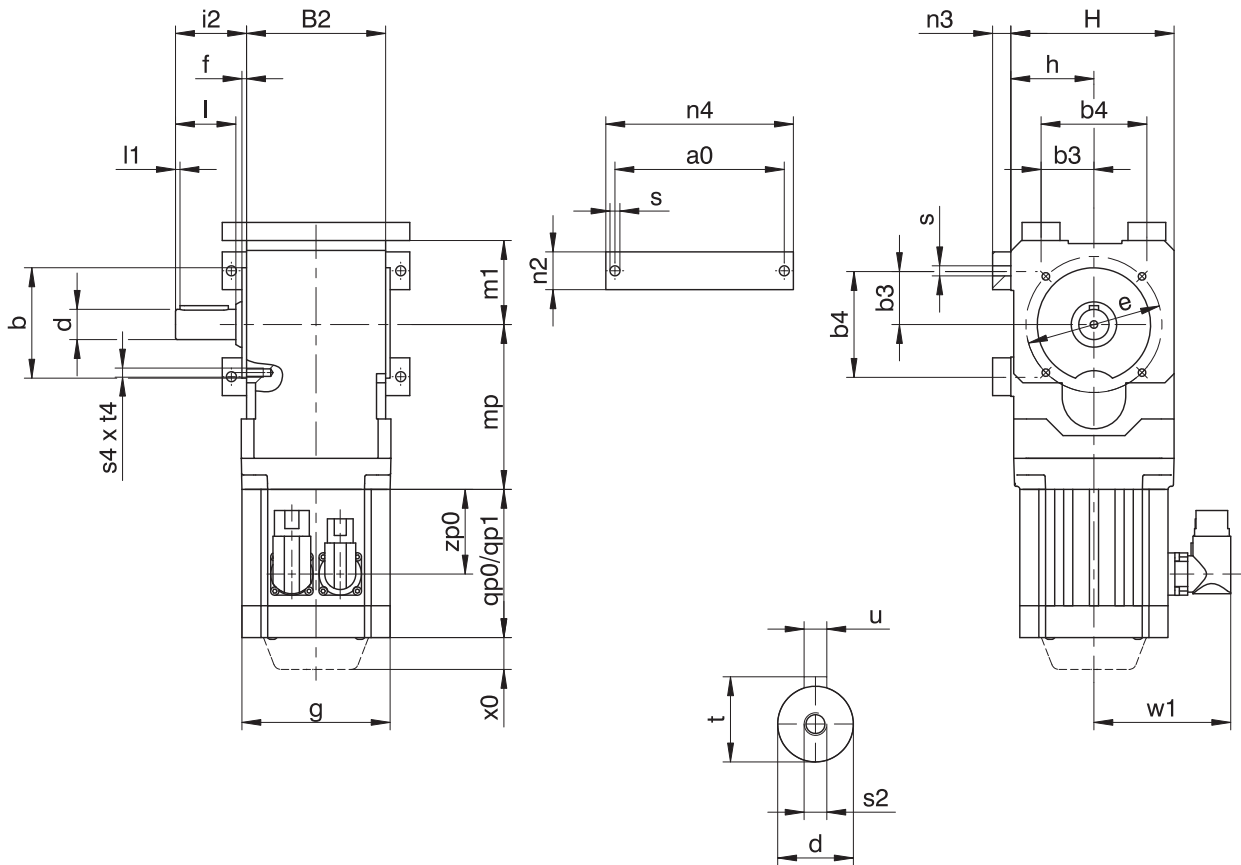
Dimensions of motors

Type	$\square g$	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.9 P shaft design (solid shaft with feather key), NG housing design (base + pitch circle diameter)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	a0	Øb	b3	b4	B2	Ød	Øe	f	h	H	i2	l	l1	m1	n2	n3	n4	Øs	s2	s4	t	t4	u
KL1	95	60 _p	27.5	55	75	16 _{h6}	75	3	46	90	38	32	3	46	20	12	107	6.6	M5	M6	18.0	11	A5×5×22
KL2	112	75 _p	35.0	70	92	20 _{h6}	90	3	55	108	47	40	3	55	25	12	124	6.6	M6	M6	22.5	13	A6×6×32

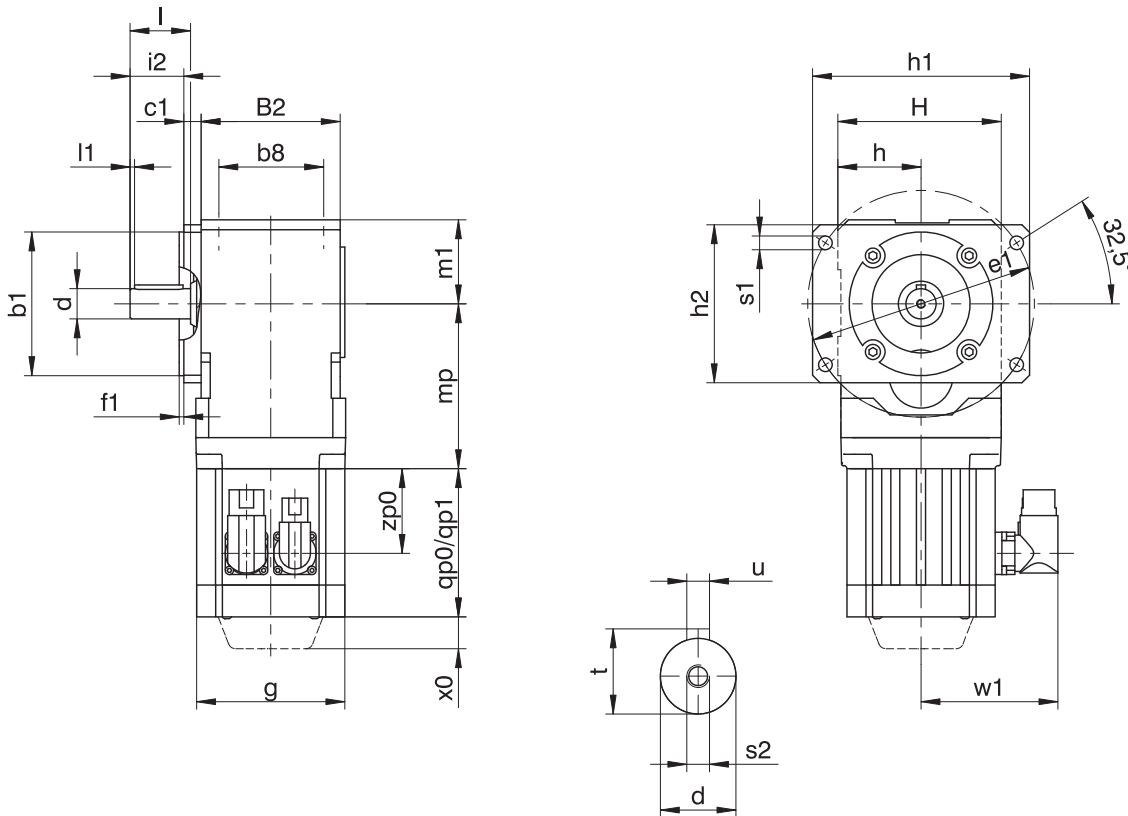
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.10 P shaft design (solid shaft with feather key), F housing design (flange)



qp0 Applies to motors without brake.

qp1 Applies to motors with brake.

x0 EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method

Different for the One Cable Solution (OCS), see the chapter [17.4](#)

Dimensions of gearboxes

Type	$\varnothing b1$	$b8$	$B2$	$c1$	$\varnothing d$	$\varnothing e1$	$f1$	h	$h1$	$h2$	H	$i2$	l	$l1$	$m1$	$\varnothing s1$	$s2$	t	u
KL1	60 ₆	50	75	11.5	16 ₆	130	3	46	128.5	88.5	90	26.5	32	3	46	9	M5	18.0	A5×5×22
KL2	95 ₆	65	92	11.5	20 ₆	150	3	55	143.5	104.5	108	35.5	40	3	55	9	M6	22.5	A6×6×32

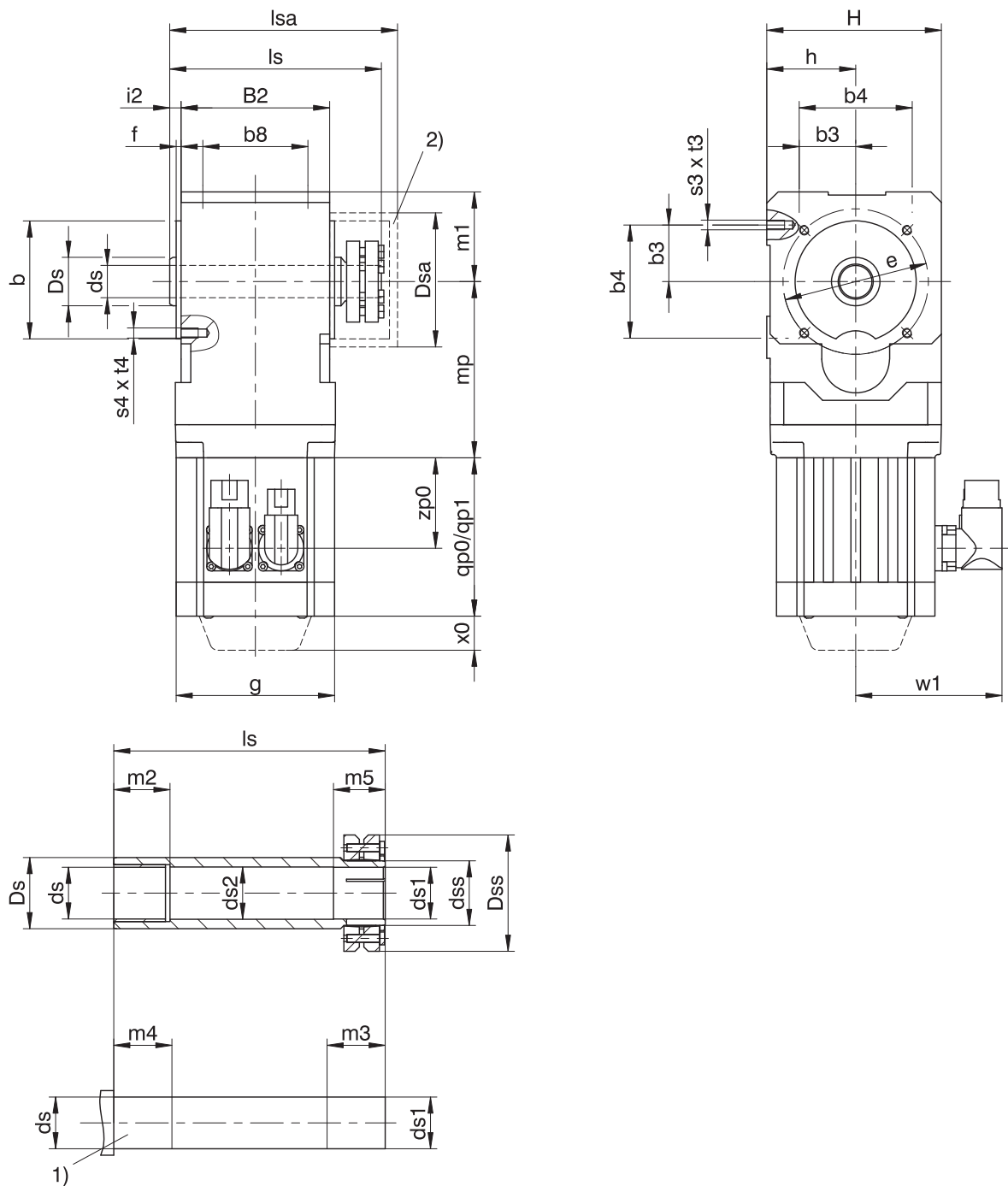
Dimensions of motors

Type	$\square g$	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	-
KL202	-	112.5	109.0

15.3.11 S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter)



- | | | | |
|-----|--|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension ls must meet or exceed the specified value. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	Øb	b3	b4	b8	B2	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe	f	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	s3	s4	t3	t4
KL1	60 _{h6}	27.5	55	50	75	16 ^{H7}	16 _{h6} ^{H7}	17.5	20	25	64	47	75	3	46	90	6	109	114.5	46	17	22	28	23	M6	M6	11	11
KL2	75 _{h6}	35.0	70	65	92	20 ^{H7}	20 _{h6} ^{H7}	21.5	24	30	79	50	90	3	55	108	7	131	139.0	55	22	27	31	26	M6	M6	13	13

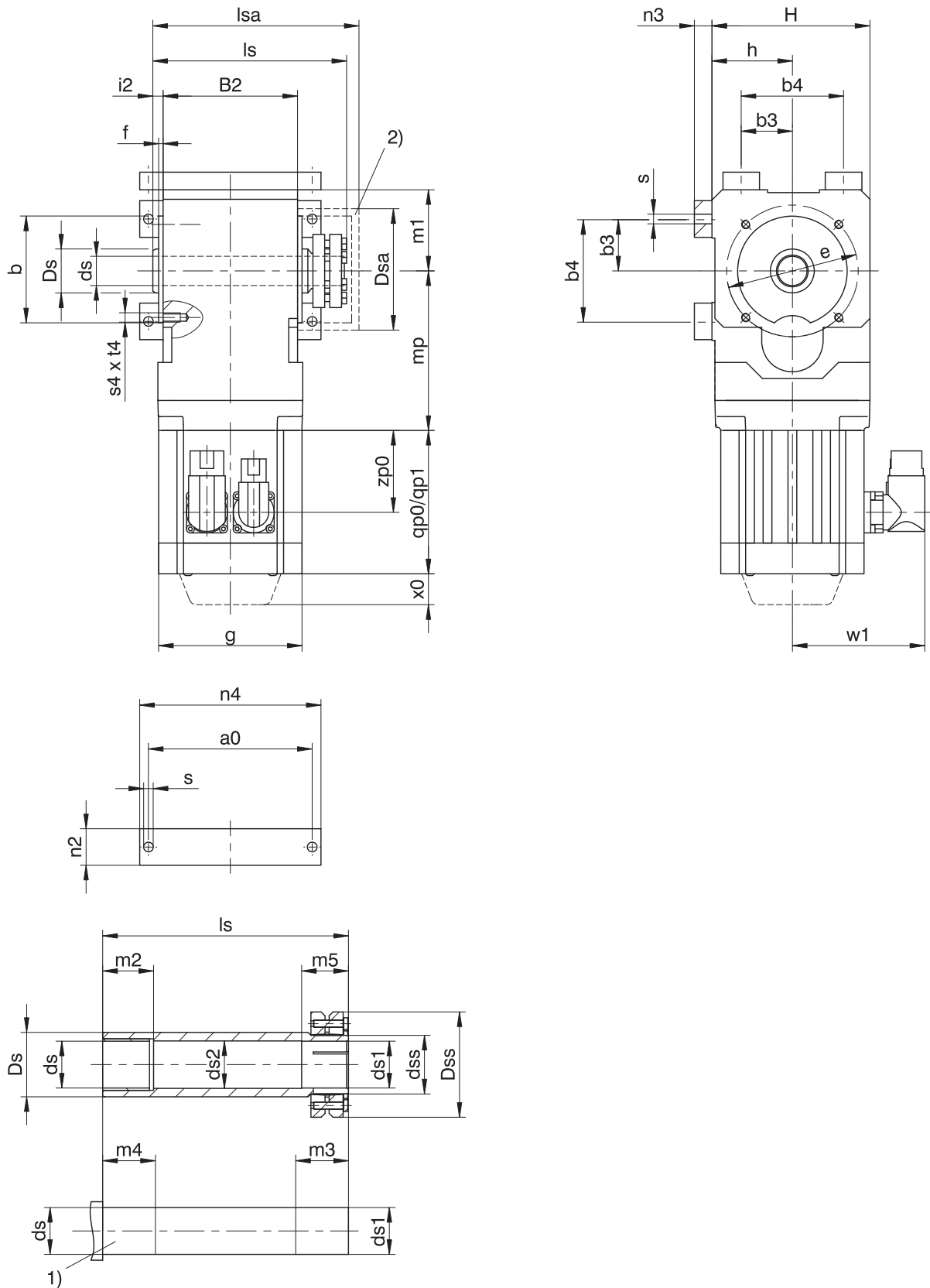
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.3.12 S shaft design (hollow shaft with shrink disk), NG housing design (base + pitch circle diameter)



- | | | | |
|-----|--|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | E22: Applies only to motors with brake and encoders using an optical or inductive measuring method
E23 – E28: Applies to encoders using an optical measuring method | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension ls must meet or exceed the specified value. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	a0	Øb	b3	b4	B2	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe	f	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	n2	n3	n4	Øs	s4	t4
KL1	95	60 _{js}	27.5	55	75	16 ^{H7}	16 _{h6} ^{H7}	17.5	20	25	64	47	75	3	46	90	6	109	114.5	46	17	22	28	23	20	12	107	6.6	M6	11
KL2	112	75 _{js}	35.0	70	92	20 ^{H7}	20 _{h6} ^{H7}	21.5	24	30	79	50	90	3	55	108	7	131	139.0	55	22	27	31	26	25	12	124	6.6	M6	13

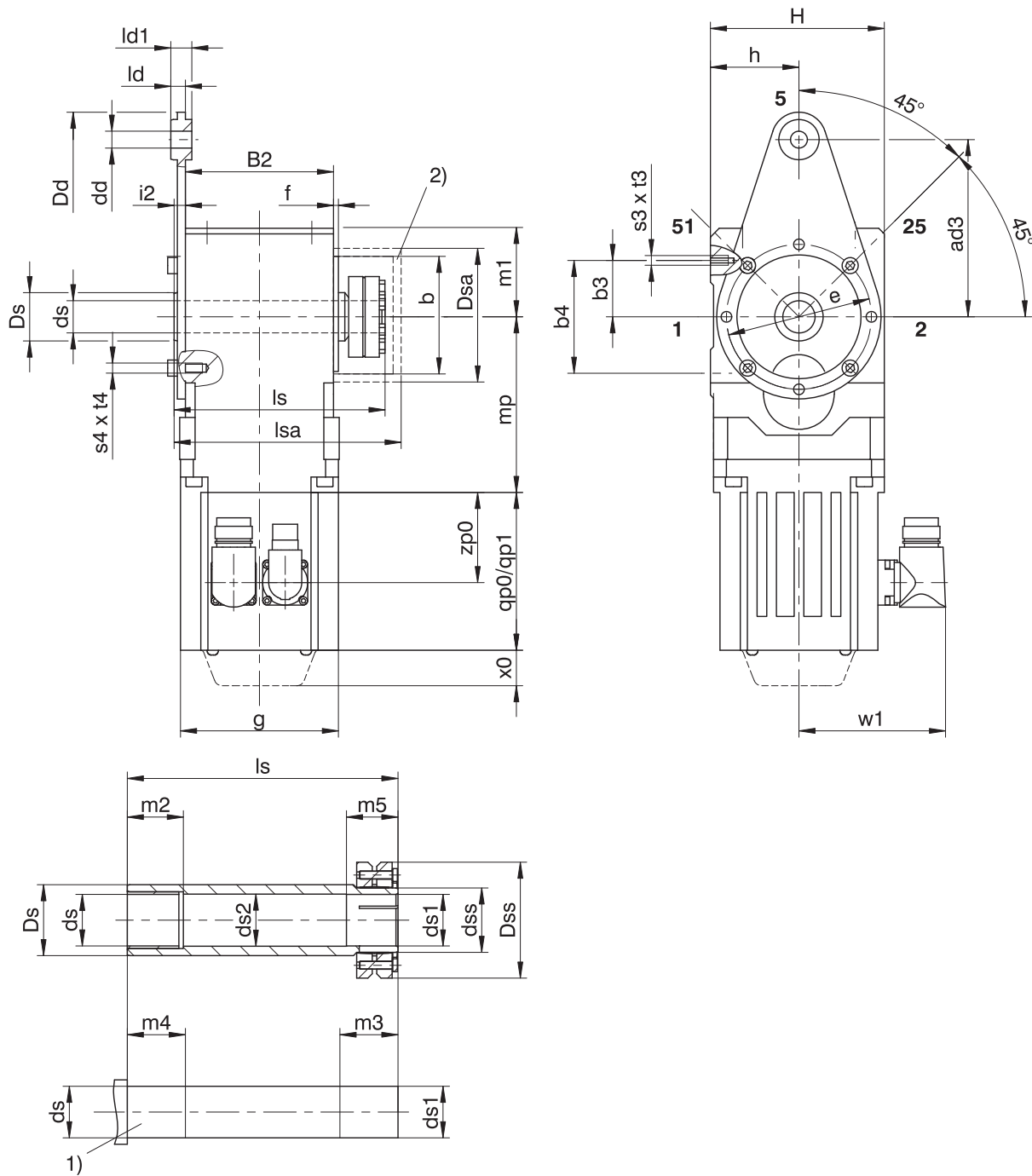
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.3.13 Shaft design S (hollow shaft with shrink ring), housing design GD (pitch circle diameter + torque arm bracket)



- | | | | |
|-----|--|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension ls must meet or exceed the specified value. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	ad3	Øb	b3	b4	B2	Ødd	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe	f	h	H	i2	ld	ld1	ls	lsa	m1	m2	m3	m4	m5	s3	s4	t3	t4
KL2	110	75 _p	35	70	92	10.5	20 ^{H7}	20 _{h6} ^{H7}	21.5	24	30	79	50	90	3	55	108	7	9	13	131	139.0	55	22	27	31	26	M6	M6	13	13

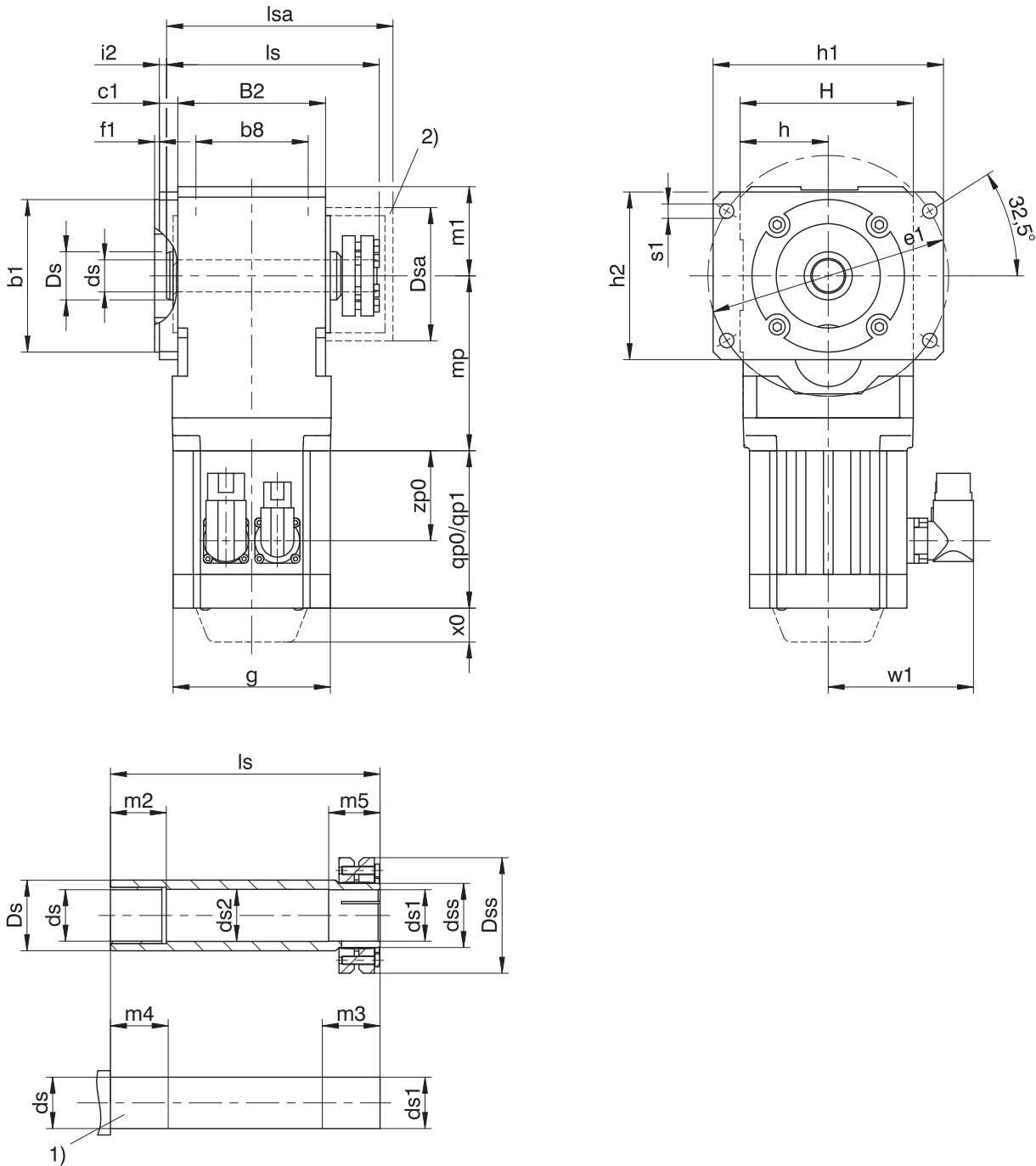
Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ3 mp	EZ4 mp
KL202	112.5	109.0

15.3.14 S shaft design (hollow shaft with shrink disk), F housing design (flange)



- | | | | |
|-----|--|-----|--|
| qp0 | Applies to motors without brake. | qp1 | Applies to motors with brake. |
| x0 | EZ2: Applies only to motors with brake and encoders using an optical or inductive measuring method
EZ3 – EZ8: Applies to encoders using an optical measuring method | | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension l_s must meet or exceed the specified value. | 2) | Cover (optional) |

Dimensions of gearboxes

Type	Øb1	b8	B2	c1	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe1	f1	h	h1	h2	H	i2	ls	lsa	m1	m2	m3	m4	m5	Øs1
KL1	60 _{j6}	50	75	11.5	16 ^{H7}	16 _{h6} ^{H7}	17.5	20	25	64	47	130	3	46	128.5	88.5	90	5.5	109	114.5	46	17	22	28	23	9
KL2	95 _{j6}	65	92	11.5	20 ^{H7}	20 _{h6} ^{H7}	21.5	24	30	79	50	150	3	55	143.5	104.5	108	4.5	131	139.0	55	22	27	31	26	9

Dimensions of motors

Type	□g	qp0	qp1	w1	x0	zp0
EZ202U	55	141	150.0	47.0	25	86.0
EZ203U	55	159	168.0	47.0	25	104.0
EZ301U	72	90	130.0	55.5	21	54.5
EZ302U	72	112	152.0	55.5	21	76.5
EZ303U	72	134	174.0	55.5	21	98.5
EZ401U	98	98	146.5	91.0	22	56.0
EZ402U	98	123	171.5	91.0	22	81.0
EZ404U	98	173	221.5	91.0	22	131.0

Dimensions of geared motors

Type	EZ2 mp	EZ3 mp	EZ4 mp
KL102	78.5	95.5	–
KL202	–	112.5	109.0

15.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

KL	2	0	2	P	G	0080	EZ401U
----	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
KL	Type	Helical bevel gearbox
2	Size	2 (example)
0	Generation	Generation 0
2	Stages	Two-stage
A	Shaft	Hollow shaft with keyway
S		Hollow shaft with shrink ring
G		Solid shaft without feather key
P		Solid shaft with feather key
G	Housing	Pitch circle diameter
F		Flange
NG		Foot + pitch circle diameter
GD		Pitch circle diameter + torque arm bracket
0080	Transmission ratio (i x 10)	i = 8 (example)
EZ401U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Attachment of solid shaft: gearbox side 3 or 4; solid shaft on both sides
- Attachment of hollow shaft with keyway: insertion side 3 or 4
- Attachment of hollow shaft with shrink ring: shrink ring on gearbox side 3 or 4
- Attachment of foot plates: gearbox side 1 or 5
- Attachment of flange: gearbox side 3 or 4
- Pitch circle diameter: gearbox side 3 or 4
- The position of the plug connectors, see the chapter [▶ 15.5.7](#)

An explanation of the gearbox sides can be found in the chapter [▶ 15.5.5](#).

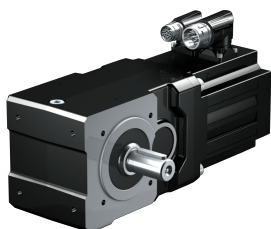
To make selecting your geared motor easy, use our STOEGER Configurator at <https://configurator.stoeber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

15.5 Product description

15.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

LM Lean motor

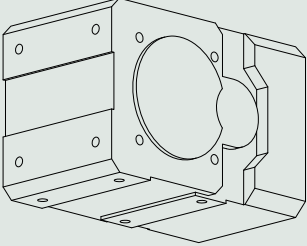
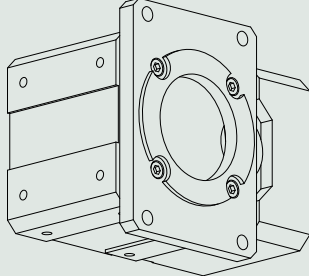
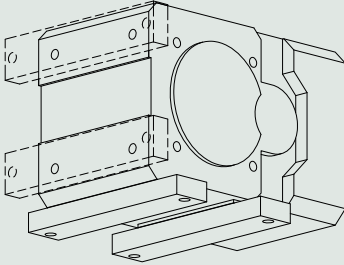
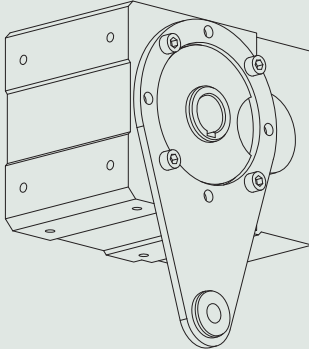


Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

15.5.2 Housing design

	Pitch circle diameter G	Flange F	Foot + pitch circle diameter NG	Pitch circle diameter + torque arm bracket GD
				
	G	F	NG	GD
KL1	✓	✓	✓	-
KL2	✓	✓	✓	✓

15.5.3 Combinatorial shaft/housing design

Shaft design	Code	Housing design			
		G	F	NG	GD
Hollow shaft with keyway	A	AG	AF	ANG	AGD
Hollow shaft with shrink ring	S	SG	SF	SNG	SGD
Solid shaft without feather key	G	GG	GF	GNG	-
Solid shaft with feather key	P	PG	PF	PNG	-

15.5.4 Installation conditions

Hollow shaft

The hollow shaft hole tolerance is ISO H7. The tolerance of the machine shaft must be ISO k6.

Take care to align the machine shaft with the gearbox hollow shaft when attaching the gearbox.

Maximum deviation ≤ 0.03 mm.

For simpler assembly and disassembly of the machine shaft, the hollow shafts are equipped with a spiral groove (as a grease deposit).

A hardened, threaded keeper plate is included in the scope of delivery. You also have the option to order the hollow shaft without a keeper plate.

Hollow shaft with shrink ring

The tolerance of the hollow shaft hole is ISO H7.

The machine shaft must be ISO h9.

Select a material for the machine shaft with a permitted surface pressure of $p \geq 325$ N/mm².

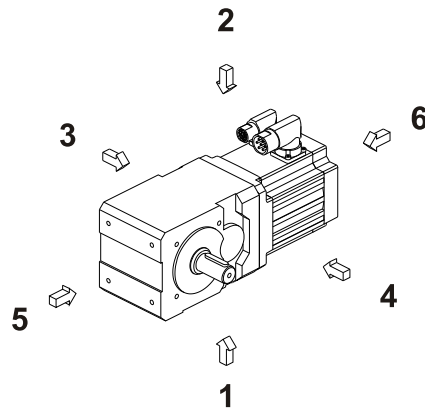
Possible materials:

- C45E +QT
- 42CrMo4

Fastening the gearboxes on the machine side using the pitch circle diameter

The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 10.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

15.5.5 Gearbox sides



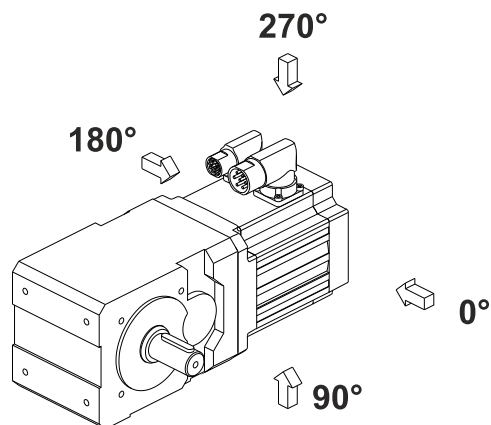
The numbers identify the gearbox sides.

15.5.6 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate.

You will receive lubricants for use in the food industry upon request.

15.5.7 Position of the plug connectors



In the standard version, the plug connectors are attached in the 270° position.

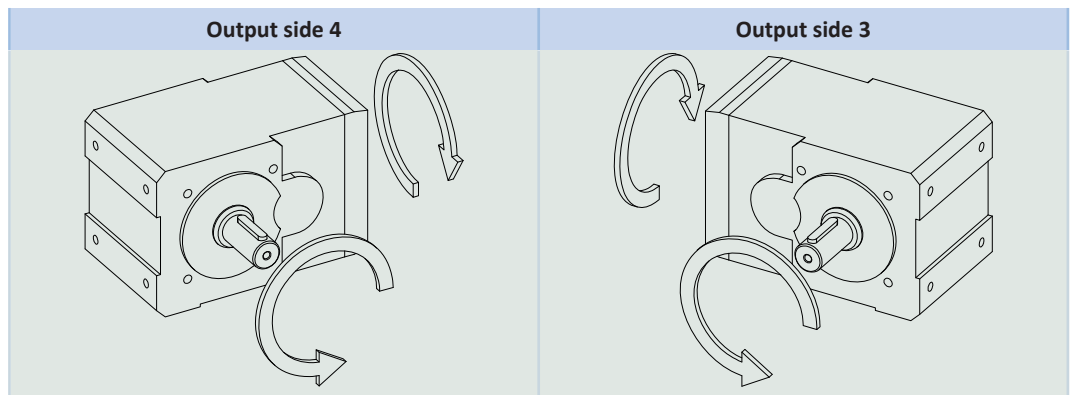
Indicate variations for your geared motor in the order.

15.5.8 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 80 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	97%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

15.5.9 Direction of rotation

Solid shaft (P and G), solid shaft on both sides (P and G), hollow shaft with keyway (A)

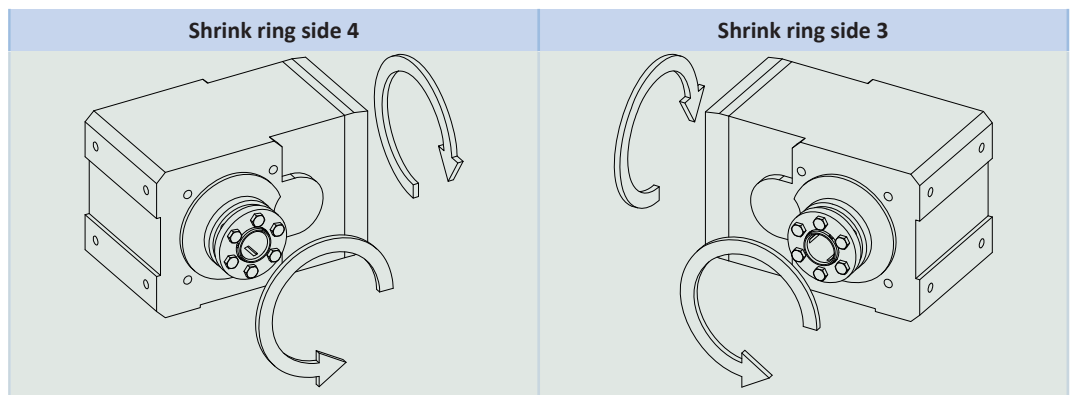


The specified directions of rotation also apply to gearboxes with hollow shaft (A) if the entry side of the machine shaft corresponds to the side of the solid shaft that is shown.

The direction of rotation for the shaft design of a solid shaft on both sides corresponds to the direction of rotation for output side 4.

The pictures show mounting position EL1.

Hollow shaft with shrink ring (S)



The pictures show mounting position EL1.

15.6 Project configuration

Project your drives using our SERVOSOFT designing software. Download SERVOSOFT free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

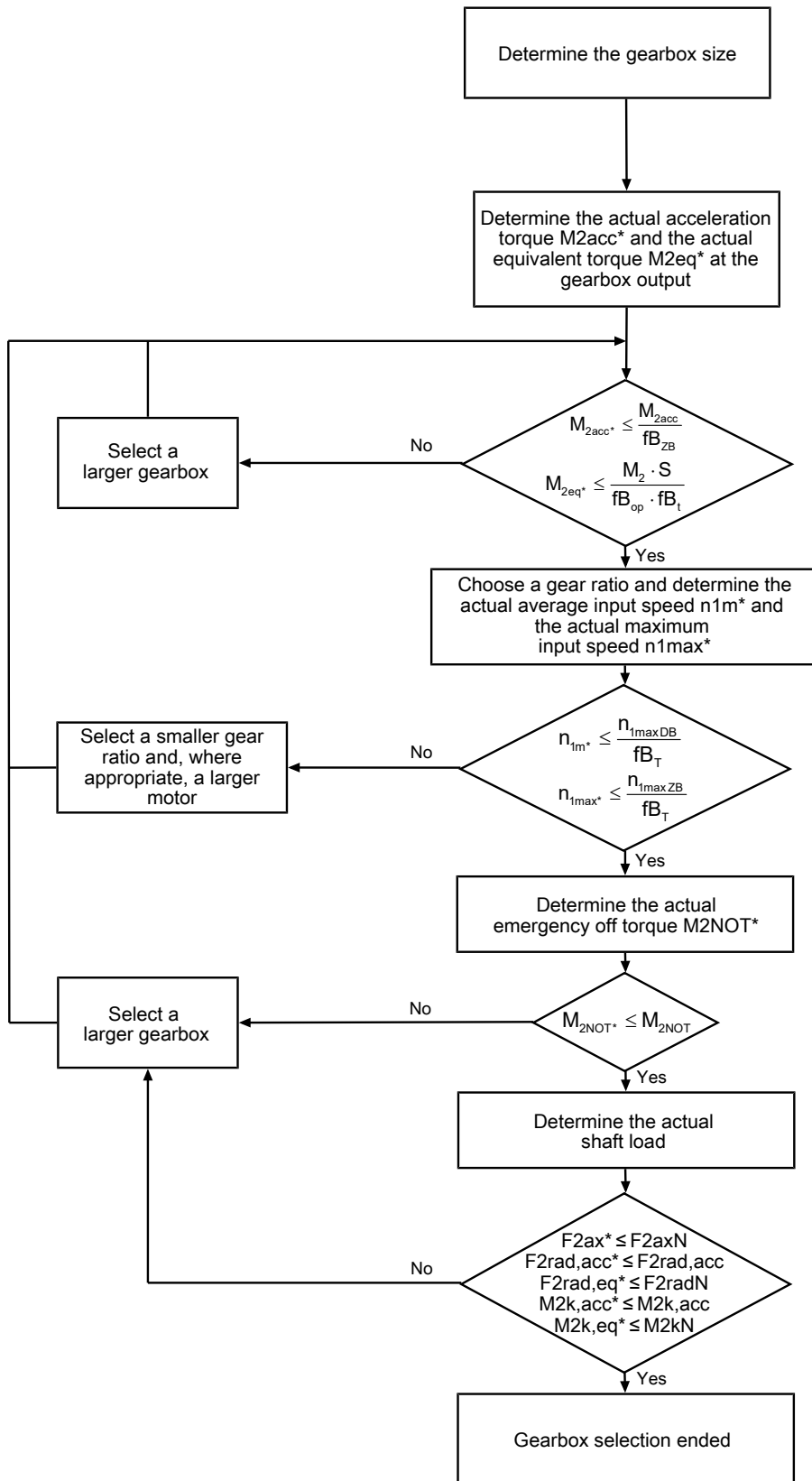
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

15.6.1 Drive selection

Drive selection for gearboxes

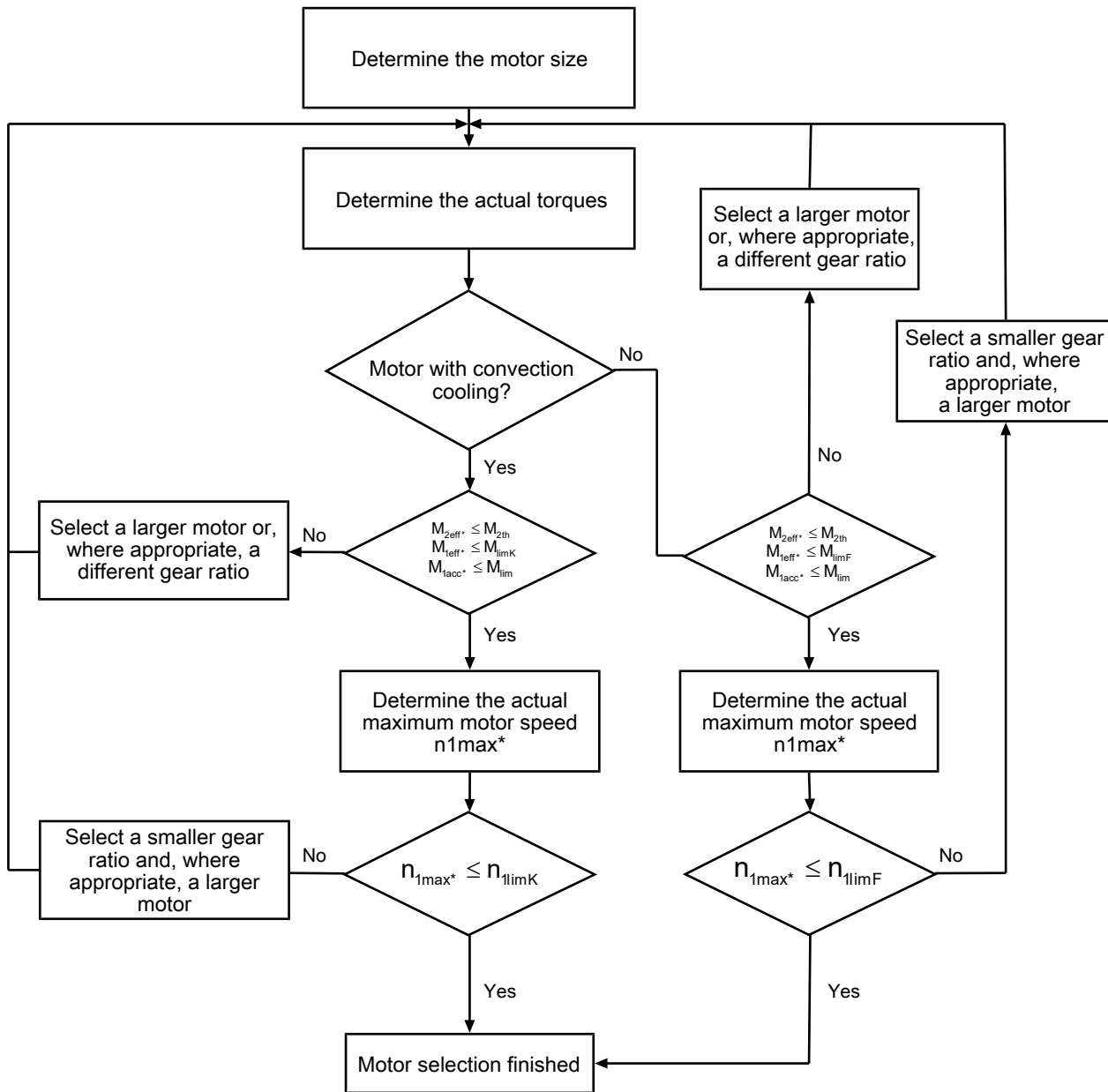


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for f_{B_T} , $f_{B_{op}}$, f_{B_t} and $f_{B_{ZB}}$ can be found in the corresponding tables in this chapter.

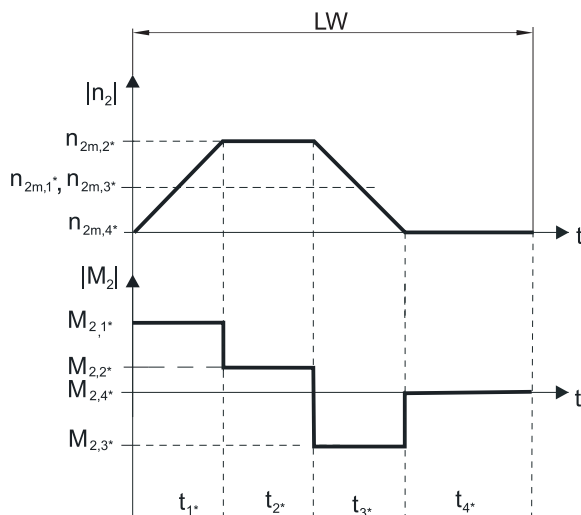
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} , accordingly or select another geared motor size.)

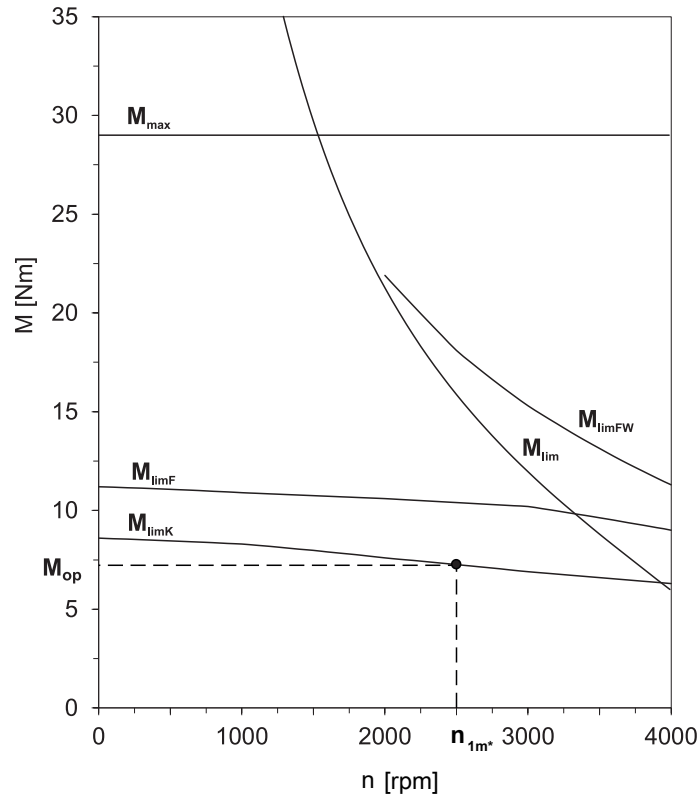
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,9 - \frac{a_{th}}{1000} \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000} \right)^2$$

Refer to the selection tables for the values of i and a_{th} .

The values for fB_T can be found in the corresponding table in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.25
Reversing load cyclic operation		1.40
Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20
Cyclic operation		fB_{zB}
≤ 1000 load changes/hour (LW/h)		1.00
> 1000 load changes/hour (LW/h)		1.15
Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

15.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 100$ rpm ($F_{2axN} = F_{2ax100}$; $F_{2radN} = F_{2rad100}$; $M_{2kN} = M_{2k100}$)
- Only if radial forces on the gearbox are stabilized by its pilots for the pitch circle diameter and flange housing design

15.6.2.1 G and P shaft designs

Permitted shaft loads for G and P shaft designs (solid shaft)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KL1	20.0	380	1900	1900	68	68
KL2	22.0	560	2800	2800	118	118

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

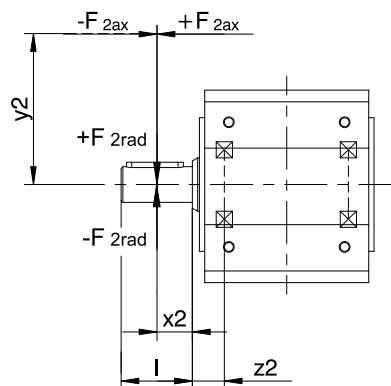


Fig. 1: Force application points for solid shaft

The specified values for $F_{2rad100}$ refer to force application on the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

15.6.2.2 A and S shaft design

Permitted shaft loads for A shaft design (hollow shaft with keyway)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KL1	18.5	250	1250	1250	43	43
KL2	22.0	560	2800	2800	118	118

Permitted shaft loads for S shaft design (hollow shaft with shrink ring)

Type	z_2 [mm]	F_{2ax100} [N]	$F_{2rad100}$ [N]	$F_{2rad,acc}$ [N]	M_{2k100} [Nm]	$M_{2k,acc}$ [Nm]
KL1	18.5	250	1250	1250	43	43
KL2	22.0	560	2800	2800	118	118

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 100$ rpm:

$$F_{2axN} = \frac{F_{2ax100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad F_{2radN} = \frac{F_{2rad100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}} \quad M_{2kN} = \frac{M_{2k100}}{\sqrt[3]{\frac{n_{2m^*}}{100 \text{ rpm}}}}$$

The values for F_{2ax100} , $F_{2rad100}$ and M_{2k100} can be found in the table "Permitted shaft loads" in this chapter.

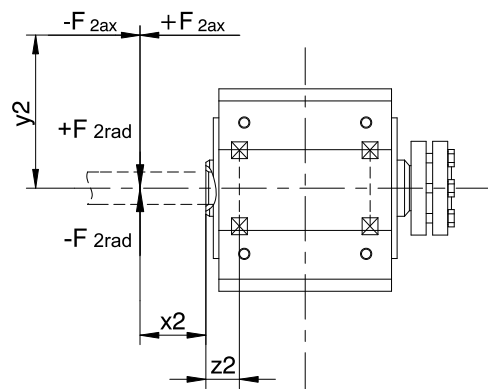


Fig. 2: Force application points for hollow shaft

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

15.6.3 Radial shaft seal rings

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

15.7 Additional documentation

Additional documentation related to the product can be found at <http://www.stoeber.de/en/downloads/>

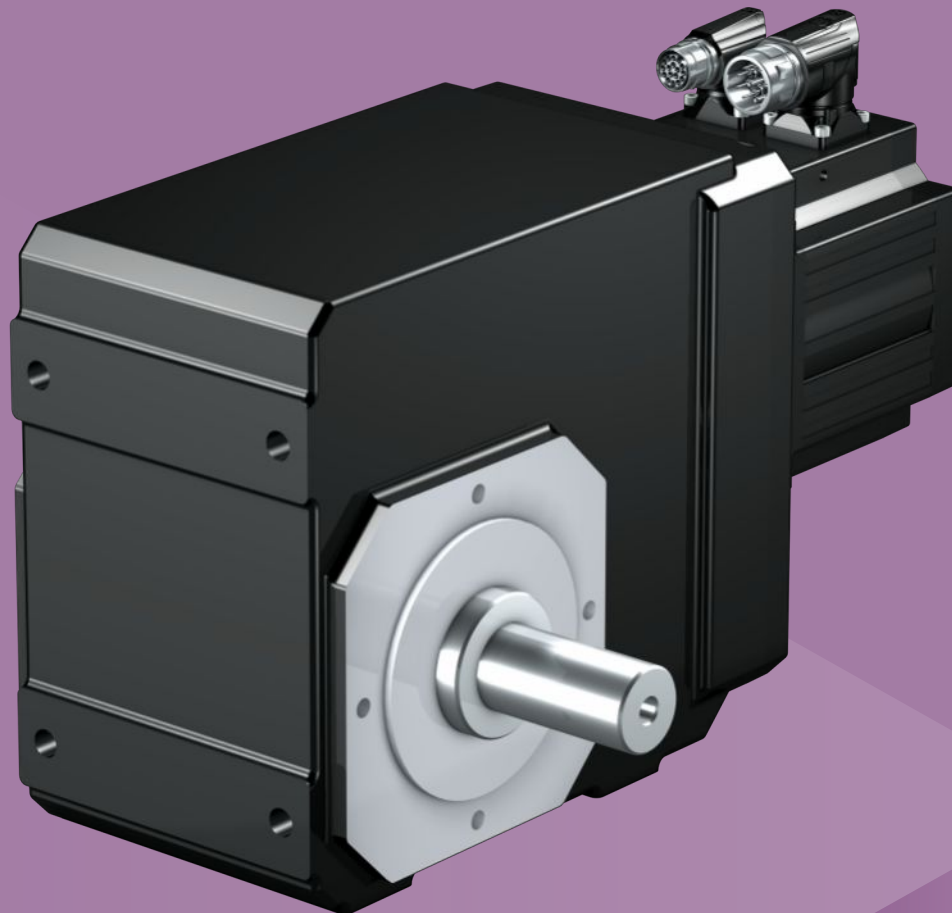
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors KL	443363_en
Operating manual for EZ synchronous servo motors	443032_en

16 K helical bevel geared motors

Table of contents

16.1 Overview	466
16.2 Selection tables	467
16.3 Dimensional drawings	493
16.3.1 A shaft design (hollow shaft), G housing design (pitch circle diameter)	494
16.3.2 A shaft design (hollow shaft), NG housing design (base + pitch circle diameter)	496
16.3.3 A shaft design (hollow shaft), GD housing design (pitch circle diameter + torque arm bracket).....	498
16.3.4 A shaft design (hollow shaft), NGD housing design (foot + pitch circle diameter + torque arm bracket).....	502
16.3.5 A shaft design (hollow shaft), F housing design (round flange)	504
16.3.6 A shaft design (hollow shaft), NF housing design (base + round flange).....	508
16.3.7 S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter).....	512
16.3.8 S shaft design (hollow shaft with shrink disk), NG housing design (base + pitch circle diameter).....	514
16.3.9 S shaft design (hollow shaft with shrink ring), GD housing design (pitch circle diameter + torque arm bracket)	518
16.3.10 S shaft design (hollow shaft with shrink ring), NGD housing design (foot + pitch circle diameter + torque arm bracket) ..	522
16.3.11 S shaft design (hollow shaft with shrink disk), F housing design (round flange).....	524
16.3.12 S shaft design (hollow shaft with shrink disk), NF housing design (base + round flange)	528
16.3.13 V shaft design (solid shaft), G housing design (pitch circle diameter).....	532
16.3.14 V shaft design (solid shaft), NG housing design (base + pitch circle diameter).....	534
16.3.15 V shaft design (solid shaft), F housing design (round flange).....	536
16.3.16 V shaft design (solid shaft), NF housing design (base + round flange)	538
16.3.17 Oil expansion tank	540
16.4 Type designation	541
16.5 Product description.....	542
16.5.1 Input options	542
16.5.2 Housing design	543
16.5.3 Combinatorial shaft/housing design	544
16.5.4 Installation conditions	544
16.5.5 Mounting positions	545
16.5.6 Lubricants	546
16.5.7 Position of the plug connectors	547
16.5.8 Other product features	547
16.5.9 Maintenance	547
16.5.10 Direction of rotation.....	548
16.6 Project configuration.....	549
16.6.1 Drive selection.....	550
16.6.2 Permitted shaft loads for the output shaft	554
16.6.3 Radial shaft seal rings.....	556
16.6.4 Oil expansion tank.....	556
16.7 Additional documentation	557



16

Helical bevel geared motors

K

16.1 Overview

Highly rigid helical-gear right-angle geared motor

Features

- Power density ★★★★★
- Backlash ★★★★★
- Price category €€
- Shaft load ★★★★★
- Smooth operation ★★★★★
- Torsional stiffness ★★★★★
- Mass moment of inertia ★★★★★
- Helical gearing ✓
- Maintenance-free (K1 – K4) ✓
- FKM seal ring at the input ✓
- Reinforced output bearing (K5 – K8) ✓ (on request)
- Compact and highly dynamic due to direct motor attachment ✓

Key ★☆☆☆☆ good | ★★★★★ excellent

€ Economy | €€€€€ Premium

Technical data

i	4 – 381
M_{2acc}	23 – 12750 Nm
$\Delta\phi_2$	1.5 – 12 arcmin
η_{get}	94 – 97 %

16.2 Selection tables 16 K helical bevel geared motors

n ₂	M ₂	M _{2,0}	a _{th}	S	Type	M _{2acc}	M _{2NOT}	i	i _{exakt}	n _{1max}		J ₁	Δφ ₂	Δφ _{2redII}	Δφ _{2redI}	C ₂	m	
										EL1,2	EL3,4,5,6							
[rpm]	[Nm]	[Nm]				[Nm]	[Nm]			[rpm]	[rpm]	[rpm]	[kgcm ²]	[arcmin]	[arcmin]	[arcmin]	[Nm/arcmin]	[kg]
K9 (n_{1N} = 2000 min⁻¹, M_{2acc,max} = 7700 Nm)																		
41	1824	2046	9.6	3.8	K913_0490 EZ813U	6550	13787	48.94	100223/2048	2600	2500	3800	124	10.0	5.0	-	379	295
41	2702	3217	14	2.6	K913_0490 EZ815U	7700	13787	48.94	100223/2048	2600	2500	3800	187	10.0	5.0	-	379	308
53	1418	1590	8.9	4.9	K913_0380 EZ813U	5092	12504	38.04	194773/5120	2600	2500	3800	134	10.0	5.0	-	379	295
53	2100	2501	13	3.3	K913_0380 EZ815U	7274	12504	38.04	194773/5120	2600	2500	3800	197	10.0	5.0	-	379	308
62	1773	2111	13	3.9	K913_0320 EZ815U	6141	11511	32.12	47275/1472	2600	2500	3800	207	10.0	5.0	-	379	308
84	1322	1574	13	4.8	K913_0240 EZ815U	4578	8580	23.94	88877/3712	2200	2100	3300	228	10.0	5.0	-	379	308
K9 (n_{1N} = 3000 min⁻¹, M_{2acc,max} = 6820 Nm)																		
8.0	2602	2919	4.9	1.8	K914_3740 EZ701U	6450	9076	373.7	13775935/36864	2600	2500	3800	9.4	10.0	5.0	-	379	280
8.0	4220	5064	7.9	1.1	K914_3740 EZ702U	6450	9076	373.7	13775935/36864	2600	2500	3800	15	10.0	5.0	-	379	283
10	2046	2294	4.7	2.2	K914_2940 EZ701U	5529	8525	293.8	977647/3328	2600	2500	3800	9.6	10.0	5.0	-	379	280
10	3317	3981	7.7	1.4	K914_2940 EZ702U	6820	8525	293.8	977647/3328	2600	2500	3800	15	10.0	5.0	-	379	283
12	1720	1929	4.7	2.5	K914_2470 EZ701U	4649	7164	247.0	3288449/13312	2600	2500	3800	9.9	10.0	5.0	-	379	280
12	2789	3347	7.6	1.6	K914_2470 EZ702U	5731	7164	247.0	3288449/13312	2600	2500	3800	15	10.0	5.0	-	379	283
12	3835	4835	10	1.1	K914_2470 EZ703U	5731	7164	247.0	3288449/13312	2600	2500	3800	23	10.0	5.0	-	379	285
16	1335	1497	4.6	3.1	K914_1920 EZ701U	3607	6341	191.7	4710481/24576	2600	2500	3800	10	10.0	5.0	-	379	280
16	2164	2597	7.4	1.9	K914_1920 EZ702U	5073	6341	191.7	4710481/24576	2600	2500	3800	16	10.0	5.0	-	379	283
16	2976	3752	10	1.4	K914_1920 EZ703U	5073	6341	191.7	4710481/24576	2600	2500	3800	23	10.0	5.0	-	379	285
20	1038	1164	4.5	3.8	K914_1490 EZ701U	2804	5750	149.0	9154331/61440	2600	2500	3800	11	10.0	5.0	-	379	280
20	1682	2019	7.3	2.3	K914_1490 EZ702U	4600	5750	149.0	9154331/61440	2600	2500	3800	16	10.0	5.0	-	379	283
20	2313	2916	10	1.7	K914_1490 EZ703U	4600	5750	149.0	9154331/61440	2600	2500	3800	24	10.0	5.0	-	379	285
24	876	982	4.4	4.3	K914_1260 EZ701U	2367	4854	125.8	2221925/17664	2600	2500	3800	12	10.0	5.0	-	379	280
24	1420	1704	7.2	2.6	K914_1260 EZ702U	3883	4854	125.8	2221925/17664	2600	2500	3800	17	10.0	5.0	-	379	283
24	1953	2462	9.9	1.9	K914_1260 EZ703U	3883	4854	125.8	2221925/17664	2600	2500	3800	25	10.0	5.0	-	379	285
32	1059	1271	8.6	2.7	K914_0940 EZ702U	2895	3619	93.78	4177219/44544	2600	2500	3800	18	10.0	5.0	-	379	283
32	1456	1835	12	2.0	K914_0940 EZ703U	2895	3619	93.78	4177219/44544	2600	2500	3800	26	10.0	5.0	-	379	285
K10 (n_{1N} = 2000 min⁻¹, M_{2acc,max} = 12750 Nm)																		
8.4	8711	9770	12	1.1	K1014_2370 EZ813U	12750	15937	237.4	49383/208	2500	2300	3500	108	10.0	5.0	-	725	517
13	5463	6127	12	1.6	K1014_1490 EZ813U	10621	13276	148.9	30969/208	2500	2300	3500	111	10.0	5.0	-	725	517
13	8091	9634	17	1.1	K1014_1490 EZ815U	10621	13276	148.9	30969/208	2500	2300	3500	174	10.0	5.0	-	725	529

16.3 Dimensional drawings

In this chapter you can find the dimensions of the geared motors.

There is a dimensional drawing for every possible shaft/housing design, each with the tables for gearbox dimensions, motor dimensions and geared motor dimensions.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

Combination options and the dimensions of forced ventilated geared motors can also be found at <https://configurator.stoeber.de/en-US/>.

Tolerances

Axis height in accordance with DIN 747	Tolerance
Up to 50 mm	-0.4 mm
Up to 250 mm	-0.5 mm
Up to 630 mm	-0.6 mm

Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6
Feather keys	DIN 6885-1, high form A

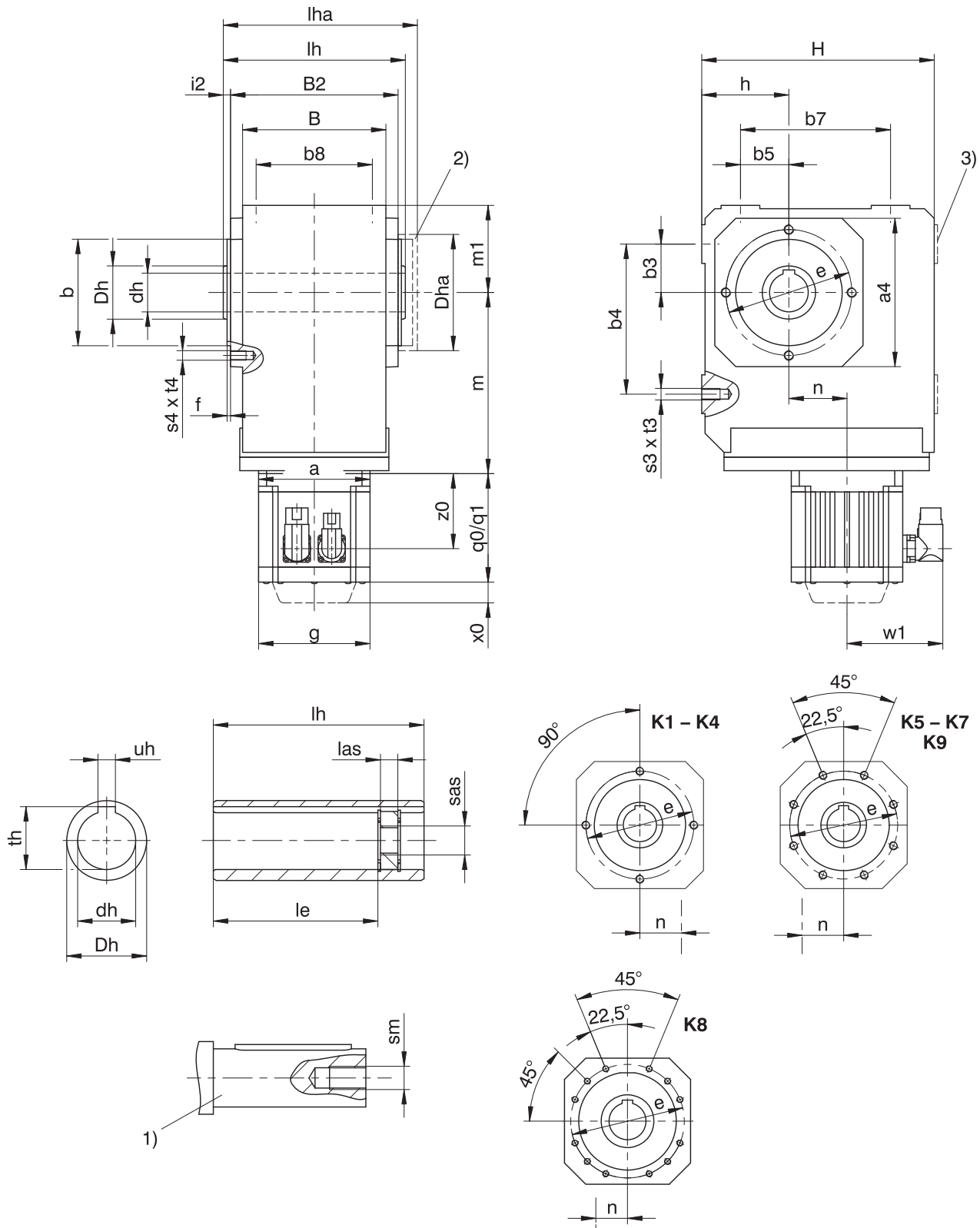
Hollow shaft	Tolerance
Hollow shaft hole fit	ISO H7
Feather keys	DIN 6885-1, high form K1 \varnothing 30: DIN 6885-3, low form

Flange	Pilot tolerance
Up to 300 mm	ISO j6
Starting at 350 mm	ISO h6

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

16.3.1 A shaft design (hollow shaft), G housing design (pitch circle diameter)



- q_0 Applies to motors without brake.
- x_0 Applies to encoders using an optical measuring method
- 1) The length of the machine shaft must be at least $2.2 \times \varnothing d_h$ and the length of the feather key must be at least $2 \times \varnothing d_h$.
- 3) Only for K1 (other sizes on request)

- q_1 Applies to motors with brake.
- w_1 Different for the One Cable Solution (OCS), see the chapter [▶ 17.4](#)
- 2) Cover (optional)

Dimensions of gearboxes

Type	□a4	∅b	b3	b4	b5	b7	b8	B	B2	∅dh	∅Dh	Dha	∅e	f	h	H	i2	le	lh	las	lha	m1	s3	s4	sm	sas	t3	t4	th	uh
K1	105	75 ₆	30	90	30	90	70	90	106	20 ^{H7}	40	□105	90	3.0	60	160	7.0	98.0	120	12	127.0	60	M8	M8	M6	M8	13	13	22.8	6 ^{JS9}
K1	105	75 ₆	30	90	30	90	70	90	106	25 ^{H7}	40	□105	90	3.0	60	160	7.0	98.0	120	12	127.0	60	M8	M8	M10	M12	13	13	28.3	8 ^{JS9}
K1	105	75 ₆	30	90	30	90	70	90	106	30 ^{H7}	40	□105	90	3.0	60	160	7.0	93.5	120	12	127.0	60	M8	M8	M10	M12	13	13	32.0	8 ^{JS9}
K2	116	82 ₆	35	115	35	115	90	115	134	30 ^{H7}	45	□116	100	3.0	65	190	7.0	121.5	148	12	156.0	65	M10	M8	M10	M12	16	13	33.3	8 ^{JS9}
K3	132	95 ₆	40	130	40	130	105	130	146	35 ^{H7}	50	□132	115	3.0	75	213	7.0	125.0	160	12	168.0	75	M10	M8	M12	M16	16	13	38.3	10 ^{JS9}
K4	152	110 ₆	50	155	50	155	120	148	173	40 ^{H7}	55	□152	130	3.5	90	240	7.5	157.0	188	12	197.5	90	M12	M10	M16	M20	19	16	43.3	12 ^{JS9}
K5	145	110 ₆	40	140	100	140	125	160	185	50 ^{H7}	65	□145	130	3.5	160	260	7.5	164.0	200	12	209.5	100	M16	M10	M16	M20	26	16	53.8	14 ^{JS9}
K6	180	140 ₆	50	160	110	160	130	168	200	50 ^{H7}	70	∅183	165	3.5	190	310	7.5	179.0	215	12	224.5	120	M16	M10	M16	M20	26	16	53.8	14 ^{JS9}
K7	195	155 ₆	55	180	125	180	145	190	226	60 ^{H7}	85	∅205	185	3.5	212	342	8.0	214.0	242	12	252.0	125	M20	M12	M20	M24	33	19	64.4	18 ^{JS9}
K8	226	185 ₆	75	240	165	240	185	235	282	70 ^{H7}	100	∅184	215	4.0	265	410	9.0	263.0	300	20	311.0	145	M24	M12	M20	M24	38	19	74.9	20 ^{JS9}
K9	280	230 ₆	95	280	185	280	225	285	330	90 ^{H7}	120	∅230	265	5.0	315	495	10.0	302.0	350	26	361.0	180	M30	M16	M24	M30	48	26	95.4	25 ^{JS9}

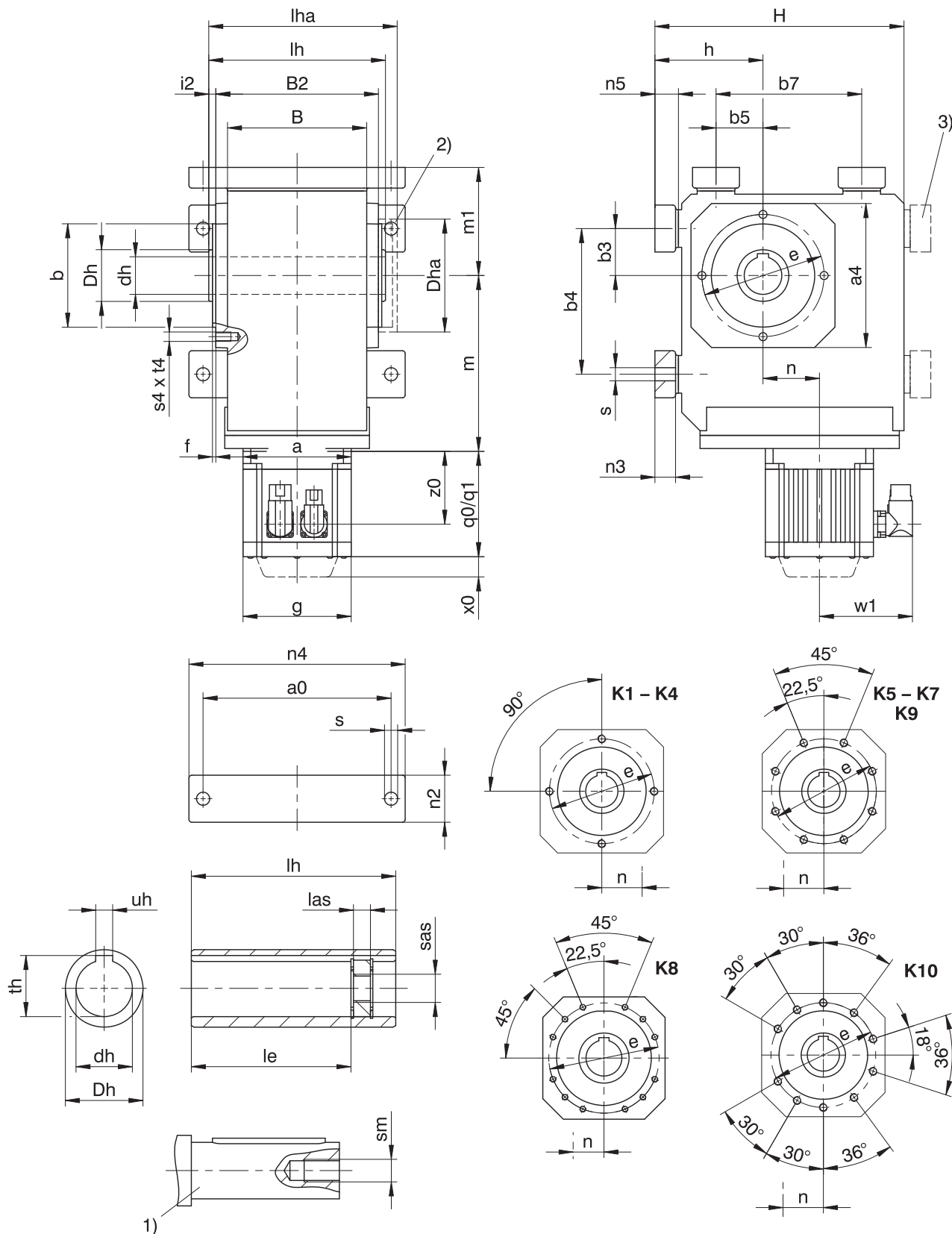
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.2 A shaft design (hollow shaft), NG housing design (base + pitch circle diameter)



- | | | | |
|-------|---|-------|--|
| q_0 | Applies to motors without brake. | q_1 | Applies to motors with brake. |
| x_0 | Applies to encoders using an optical measuring method | w_1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | The length of the machine shaft must be at least 2.2 x $\varnothing d_h$ and the length of the feather key must be at least 2 x $\varnothing d_h$. | 2) | Cover (optional) |
| 3) | Only for K1 (other sizes on request) | | |

Dimensions of gearboxes

Type	a0	□a4	∅b	b3	b4	b5	b7	B	B2	∅dh	∅Dh	Dha	∅e	f	h	H	i2	le	lh	las	lha	m1	n2	n3	n4	n5	∅s	s4	sm	sas	t4	th	uh
K1	115	105	75 _{f6}	30	90	30	90	90	106	20 ^{H7}	40	□105	90	3.0	75	175	7.0	98.0	120	12	127.0	75	30	13	140	15	9.0	M8	M6	M8	13	22.8	6 ^{JS9}
K1	115	105	75 _{f6}	30	90	30	90	90	106	25 ^{H7}	40	□105	90	3.0	75	175	7.0	98.0	120	12	127.0	75	30	13	140	15	9.0	M8	M10	M12	13	28.3	8 ^{JS9}
K1	115	105	75 _{f6}	30	90	30	90	90	106	30 ^{H7}	40	□105	90	3.0	75	175	7.0	93.5	120	12	127.0	75	30	13	140	15	9.0	M8	M10	M12	13	32.0	8 ^{JS9}
K2	155	116	82 _{f6}	35	115	35	115	115	134	30 ^{H7}	45	□116	100	3.0	88	213	7.0	121.5	148	12	156.0	88	40	20	185	23	11.0	M8	M10	M12	13	33.3	8 ^{JS9}
K3	170	132	95 _{f6}	40	130	40	130	130	146	35 ^{H7}	50	□132	115	3.0	98	236	7.0	125.0	160	12	168.0	98	45	20	200	23	11.0	M8	M12	M16	13	38.3	10 ^{JS9}
K4	200	152	110 _{f6}	50	155	50	155	148	173	40 ^{H7}	55	□152	130	3.5	115	265	7.5	157.0	188	12	197.5	115	50	22	230	25	14.0	M10	M16	M20	16	43.3	12 ^{JS9}
K5	200	145	110 _{f6}	40	140	100	140	160	185	50 ^{H7}	65	□145	130	3.5	190	290	7.5	164.0	200	12	209.5	130	60	27	240	30	18.0	M10	M16	M20	16	53.8	14 ^{JS9}
K6	210	180	140 _{f6}	50	160	110	160	168	200	50 ^{H7}	70	∅183	165	3.5	220	340	7.5	179.0	215	12	224.5	150	65	27	250	30	18.5	M10	M16	M20	16	53.8	14 ^{JS9}
K7	241	195	155 _{f6}	55	180	125	180	190	226	60 ^{H7}	85	∅205	185	3.5	250	380	8.0	214.0	242	12	252.0	163	70	35	290	38	23.0	M12	M20	M24	19	64.4	18 ^{JS9}
K8	300	226	185 _{f6}	75	240	165	240	235	282	70 ^{H7}	100	∅184	215	4.0	310	455	9.0	263.0	300	20	311.0	190	85	41	360	45	27.0	M12	M20	M24	19	74.9	20 ^{JS9}
K9	360	280	230 _{f6}	95	280	185	280	285	330	90 ^{H7}	120	∅230	265	5.0	365	545	10.0	302.0	350	26	361.0	230	95	46	430	50	31.0	M16	M24	M30	26	95.4	25 ^{JS9}
K10	330	340	250 _{h6}	115	350	265	420	400	356	100 ^{H7}	130	∅200	300	20.0	420	636	27.0	361.0	410	26	441.0	270	120	-	400	45	39.0	M20	M24	M30	33	106.4	28 ^{JS9}

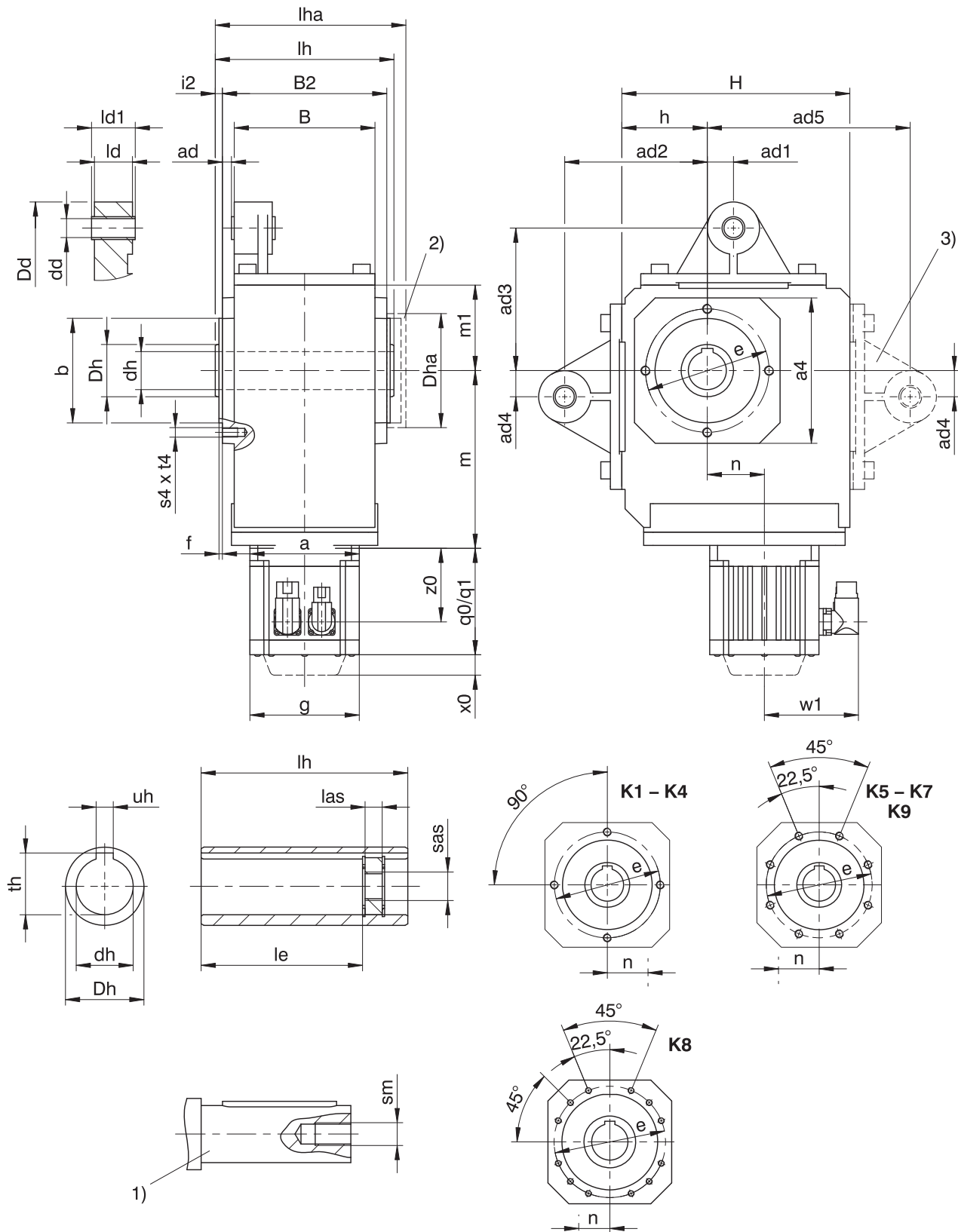
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0
K1014	-	-	-	-	-	-	-	-	-	-	-	-	∅250	450	28.0

16.3.3 A shaft design (hollow shaft), GD housing design (pitch circle diameter + torque arm bracket)



q_0 Applies to motors without brake.

x_0 Applies to encoders using an optical measuring method

1) The length of the machine shaft must be at least $2.2 \times \varnothing dh$ and the length of the feather key must be at least $2 \times \varnothing dh$.

q_1 Applies to motors with brake.

w_1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

2) Cover (optional)

- 3) Only for K1 (other sizes on request) – If you brace the gearboxes without the torque arm brackets provided by the manufacturer for this purpose, the dimensions for ad2 and ad3 must meet the specified value.

Dimensions of gearboxes

Type	□a4	ad	ad1	ad2	ad3	ad4	ad5	Øb	B	B2	Ødd	Ødh	ØDd	ØDh	Dha	Øe	f
K1	105	6.0	15.0	90	90	15.0	130	75 _{f6}	90	106	12 ^{H9}	20 ^{H7}	43	40	□105	90	3.0
K1	105	6.0	15.0	90	90	15.0	130	75 _{f6}	90	106	12 ^{H9}	25 ^{H7}	43	40	□105	90	3.0
K1	105	6.0	15.0	90	90	15.0	130	75 _{f6}	90	106	12 ^{H9}	30 ^{H7}	43	40	□105	90	3.0
K2	116	6.5	22.5	100	100	22.5	–	82 _{f6}	115	134	16 ^{H9}	30 ^{H7}	45	45	□116	100	3.0
K3	132	5.0	25.0	120	120	25.0	–	95 _{f6}	130	146	16 ^{H9}	35 ^{H7}	45	50	□132	115	3.0
K4	152	9.5	27.5	150	150	27.5	–	110 _{f6}	148	173	20 ^{H9}	40 ^{H7}	55	55	□152	130	3.5
K5	145	9.5	30.0	250	190	30.0	–	110 _{f6}	160	185	20 ^{H9}	50 ^{H7}	58	65	□145	130	3.5
K6	180	13.0	30.0	250	180	30.0	–	140 _{f6}	168	200	20 ^{H9}	50 ^{H7}	58	70	Ø183	165	3.5
K7	195	15.0	35.0	300	213	35.0	–	155 _{f6}	190	226	20 ^{H9}	60 ^{H7}	68	85	Ø205	185	3.5
K8	226	17.0	45.0	350	230	45.0	–	185 _{f6}	235	282	24 ^{H9}	70 ^{H7}	72	100	Ø184	215	4.0
K9	280	16.0	45.0	450	315	45.0	–	230 _{f6}	285	330	24 ^{H9}	90 ^{H7}	75	120	Ø230	265	5.0

Dimensions of gearboxes

Type	h	H	i2	ld	ld1	le	lh	las	lha	m1	s4	sm	sas	t4	th	uh
K1	60	160	7.0	24	28	98.0	120	12	127.0	60	M8	M6	M8	13	22.8	6 ^{JS9}
K1	60	160	7.0	24	28	98.0	120	12	127.0	60	M8	M10	M12	13	28.3	8 ^{JS9}
K1	60	160	7.0	24	28	93.5	120	12	127.0	60	M8	M10	M12	13	32.0	8 ^{JS9}
K2	65	190	7.0	32	38	121.5	148	12	156.0	65	M8	M10	M12	13	33.3	8 ^{JS9}
K3	75	213	7.0	32	38	125.0	160	12	168.0	75	M8	M12	M16	13	38.3	10 ^{JS9}
K4	90	240	7.5	40	46	157.0	188	12	197.5	90	M10	M16	M20	16	43.3	12 ^{JS9}
K5	160	260	7.5	40	46	164.0	200	12	209.5	100	M10	M16	M20	16	53.8	14 ^{JS9}
K6	190	310	7.5	40	46	179.0	215	12	224.5	120	M10	M16	M20	16	53.8	14 ^{JS9}
K7	212	342	8.0	64	70	214.0	242	12	252.0	125	M12	M20	M24	19	64.4	18 ^{JS9}
K8	265	410	9.0	102	115	263.0	300	20	311.0	145	M12	M20	M24	19	74.9	20 ^{JS9}
K9	315	495	10.0	102	115	302.0	350	26	361.0	180	M16	M24	M30	26	95.4	25 ^{JS9}

Dimensions of motors

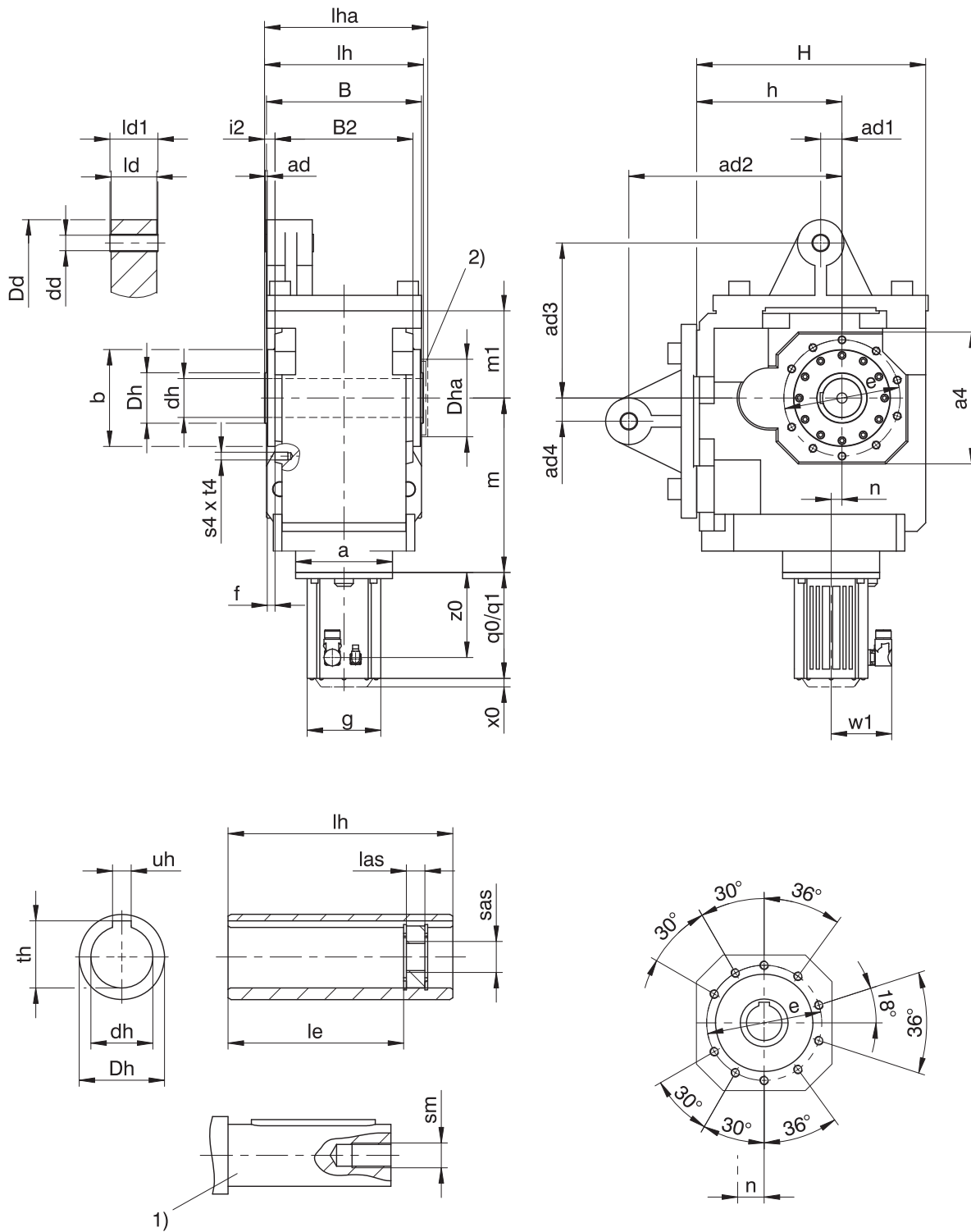
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.4 A shaft design (hollow shaft), NGD housing design (foot + pitch circle diameter + torque arm bracket)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

- If you brace the gearboxes without the torque arm brackets provided by the manufacturer for this purpose, the dimensions for $ad2$ and $ad3$ must meet the specified value.

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

2) Cover (optional)

Dimensions of gearboxes

Type	$\square a_4$	ad	ad1	ad2	ad3	ad4	$\varnothing b$	B	B2	$\varnothing dd$	$\varnothing dh$	$\varnothing Dd$	$\varnothing Dh$	Dha	$\varnothing e$	f
K10	340	5	60	550	400	55	250_{h6}	400	356	40^{H9}	100^{H7}	120	130	$\varnothing 200$	300	20

Dimensions of gearboxes

Type	h	H	i2	ld	ld1	le	lh	las	lha	m1	s4	sm	sas	t4	th	uh
K10	375	591	27	118	124	361	410	26	441	225	M20	M24	M30	33	106.4	28^{JS9}

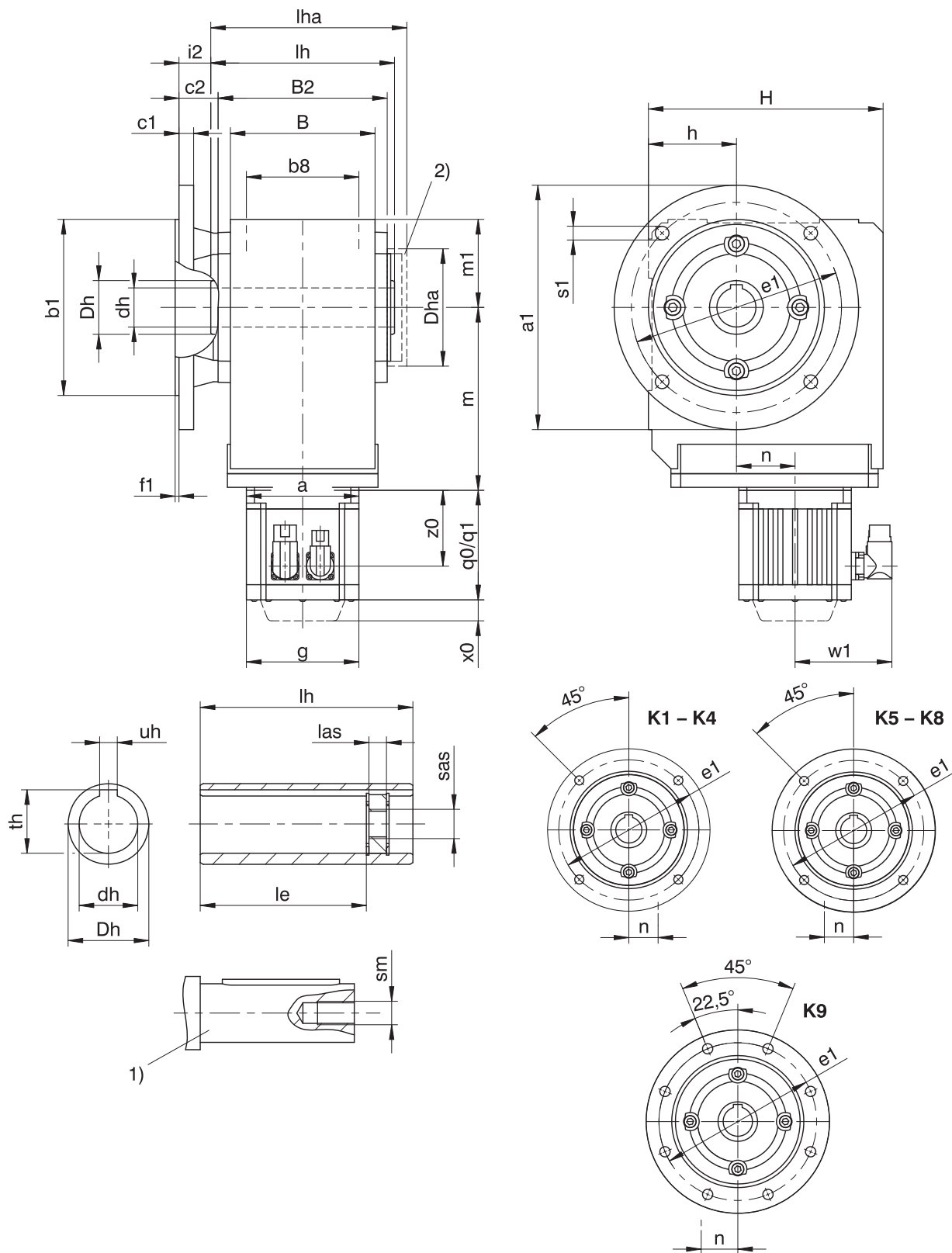
Dimensions of motors

Type	$\square g$	q0	q1	w1	x0	z0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ8		
	a	m	n
K1014	$\varnothing 250$	450	28.0

16.3.5 A shaft design (hollow shaft), F housing design (round flange)



q_0 Applies to motors without brake.

x_0 Applies to encoders using an optical measuring method

1) The length of the machine shaft must be at least 2.2 x $\varnothing dh$ and the length of the feather key must be at least 2 x $\varnothing dh$.

q_1 Applies to motors with brake.

w_1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

2) Cover (optional)

Dimensions of gearboxes

Type	Øa1	Øb1	b8	B	B2	c1	c2	Ødh	ØDh	Dha	Øe1	f1	h	H	i2	le	lh	las	lha	m1	Øs1	sm	sas	th	uh
K1	160	110 _{js}	70	90	106	10	32.0	20 ^{H7}	40	□105	130	3.5	60	160	25.0	98.0	120	12	127.0	60	9	M6	M8	22.8	6 ^{JS9}
K1	160	110 _{js}	70	90	106	10	32.0	25 ^{H7}	40	□105	130	3.5	60	160	25.0	98.0	120	12	127.0	60	9	M10	M12	28.3	8 ^{JS9}
K1	160	110 _{js}	70	90	106	10	32.0	30 ^{H7}	40	□105	130	3.5	60	160	25.0	93.5	120	12	127.0	60	9	M10	M12	32.0	8 ^{JS9}
K2	200	130 _{js}	90	115	134	12	32.0	30 ^{H7}	45	□116	165	3.5	65	190	25.0	121.5	148	12	156.0	65	11	M10	M12	33.3	8 ^{JS9}
K3	200	130 _{js}	105	130	146	14	38.0	35 ^{H7}	50	□132	165	3.5	75	213	31.0	125.0	160	12	168.0	75	11	M12	M16	38.3	10 ^{JS9}
K4	250	180 _{js}	120	148	173	15	40.0	40 ^{H7}	55	□152	215	4.0	90	240	32.5	157.0	188	12	197.5	90	14	M16	M20	43.3	12 ^{JS9}
K5	250	180 _{js}	125	160	185	15	39.5	50 ^{H7}	65	□145	215	4.0	160	260	32.0	164.0	200	12	209.5	100	14	M16	M20	53.8	14 ^{JS9}
K6	300	230 _{js}	130	168	200	17	36.0	50 ^{H7}	70	Ø183	265	4.0	190	310	28.5	179.0	215	12	224.5	120	14	M16	M20	53.8	14 ^{JS9}
K7	350	250 _{h6}	145	190	226	18	44.0	60 ^{H7}	85	Ø205	300	5.0	212	342	36.0	214.0	242	12	252.0	125	18	M20	M24	64.4	18 ^{JS9}
K8	400	300 _{h6}	185	235	282	20	45.0	70 ^{H7}	100	Ø184	350	5.0	265	410	36.0	263.0	300	20	311.0	145	18	M20	M24	74.9	20 ^{JS9}
K9	450	350 _{h6}	225	285	330	23	50.0	90 ^{H7}	120	Ø230	400	5.0	315	495	40.0	302.0	350	26	361.0	180	18	M24	M30	95.4	25 ^{JS9}

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _{js}	10	115	3.0	9
K2	160	110 _{js}	12	130	3.5	9
K3	160	110 _{js}	14	130	3.5	9
K3	250	180 _{js}	14	215	4.0	14
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

Dimensions of motors

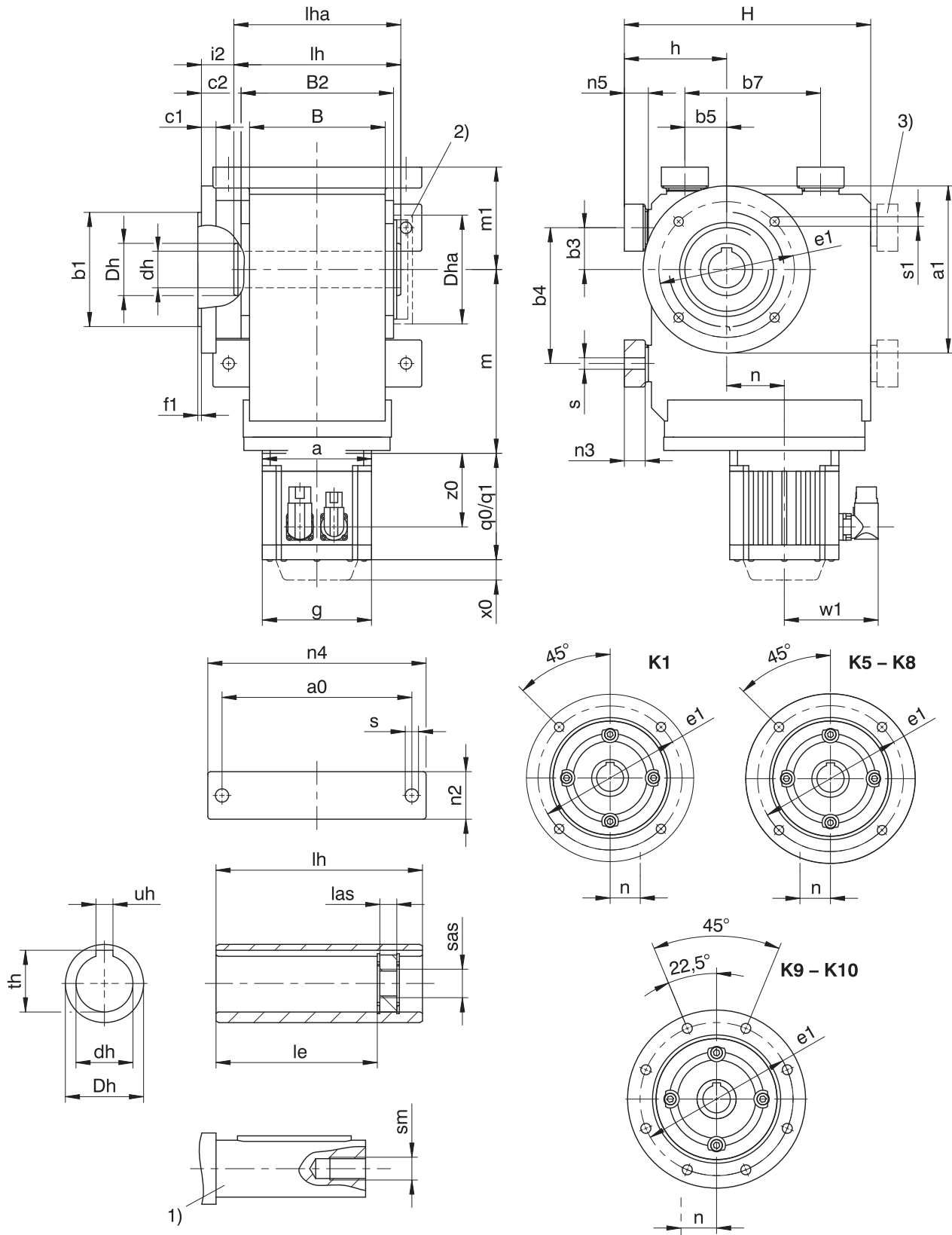
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.6 A shaft design (hollow shaft), NF housing design (base + round flange)



- | | | | |
|------|---|------|--|
| $q0$ | Applies to motors without brake. | $q1$ | Applies to motors with brake. |
| $x0$ | Applies to encoders using an optical measuring method | $w1$ | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | The length of the machine shaft must be at least 2.2 x $\varnothing d_h$ and the length of the feather key must be at least 2 x $\varnothing d_h$. | 2) | Cover (optional) |
| 3) | Only for K1 (other sizes on request) | | |

Dimensions of gearboxes

Type	a0	Øa1	Øb1	b3	b4	b5	b7	B	B2	c1	c2	Ødh	ØDh	Dha	Øe1	f1	h
K1	115	160	110 _f	30	90	30	90	90	106	10	32.0	20 ^{H7}	40	□105	130	3.5	75
K1	115	160	110 _f	30	90	30	90	90	106	10	32.0	25 ^{H7}	40	□105	130	3.5	75
K1	115	160	110 _f	30	90	30	90	90	106	10	32.0	30 ^{H7}	40	□105	130	3.5	75
K5	200	250	180 _f	40	140	100	140	160	185	15	39.5	50 ^{H7}	65	□145	215	4.0	190
K6	210	300	230 _f	50	160	110	160	168	200	17	36.0	50 ^{H7}	70	Ø183	265	4.0	220
K7	241	350	250 _{h6}	55	180	125	180	190	226	18	44.0	60 ^{H7}	85	Ø205	300	5.0	250
K8	300	400	300 _{h6}	75	240	165	240	235	282	20	45.0	70 ^{H7}	100	Ø184	350	5.0	310
K9	360	450	350 _{h6}	95	280	185	280	285	330	23	50.0	90 ^{H7}	120	Ø230	400	5.0	365
K10	330	550	450 _{h6}	115	350	265	420	400	356	25	78.0	100 ^{H7}	130	Ø200	500	5.0	420

Dimensions of gearboxes

Type	H	i2	le	lh	las	lha	m1	n2	n3	n4	n5	Øs	Øs1	sm	sas	th	uh
K1	175	25.0	98.0	120	12	127.0	75	30	13	140	15	9.0	9	M6	M8	22.8	6 ^{JS9}
K1	175	25.0	98.0	120	12	127.0	75	30	13	140	15	9.0	9	M10	M12	28.3	8 ^{JS9}
K1	175	25.0	93.5	120	12	127.0	75	30	13	140	15	9.0	9	M10	M12	32.0	8 ^{JS9}
K5	290	32.0	164.0	200	12	209.5	130	60	27	240	30	18.0	14	M16	M20	53.8	14 ^{JS9}
K6	340	28.5	179.0	215	12	224.5	150	65	27	250	30	18.5	14	M16	M20	53.8	14 ^{JS9}
K7	380	36.0	214.0	242	12	252.0	163	70	35	290	38	23.0	18	M20	M24	64.4	18 ^{JS9}
K8	455	36.0	263.0	300	20	311.0	190	85	41	360	45	27.0	18	M20	M24	74.9	20 ^{JS9}
K9	545	40.0	302.0	350	26	361.0	230	95	46	430	50	31.0	18	M24	M30	95.4	25 ^{JS9}
K10	636	51.0	361.0	410	26	441.0	270	120	-	400	45	39.0	18	M24	M30	106.4	28 ^{JS9}

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _f	10	115	3.0	9
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

Dimensions of motors

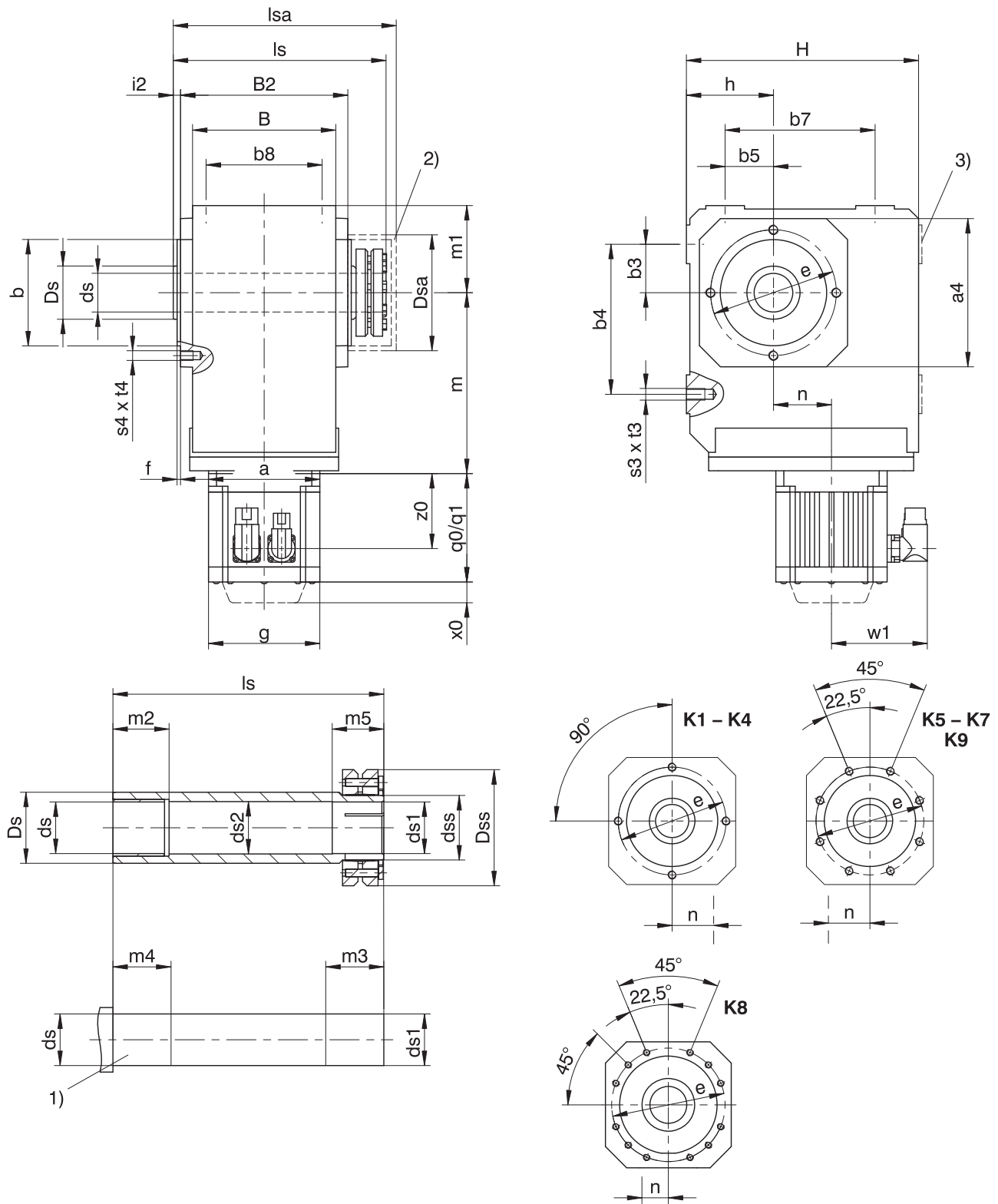
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0
K1014	-	-	-	-	-	-	-	-	-	-	-	-	∅250	450	28.0

16.3.7 S shaft design (hollow shaft with shrink disk), G housing design (pitch circle diameter)



- | | | | |
|----|--|----|--|
| q0 | Applies to motors without brake. | q1 | Applies to motors with brake. |
| x0 | Applies to encoders using an optical measuring method. | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension ls must meet or exceed the specified value. | 2) | Cover (optional) |
| 3) | Only for K1 (other sizes on request) | | |

Dimensions of gearboxes

Type	□a4	∅b	b3	b4	b5	b7	b8	B	B2	∅ds	∅ds1	∅ds2	∅dss	∅Ds	∅Dsa	∅Dss	∅e	f	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	s3	s4	t3	t4
K1	105	75 _{h6}	30	90	30	90	70	90	106	25 _{h9}	25 _{h9} ^{H7}	25.5	30	40	80.0	60	90	3.0	60	160	7.0	149	163	60	20	34	25	29	M8	M8	13	13
K2	116	82 _{h6}	35	115	35	115	90	115	134	30 _{h9}	30 _{h9} ^{H7}	30.5	36	45	88.0	72	100	3.0	65	190	7.0	178	193	65	25	39	30	34	M10	M8	16	13
K3	132	95 _{h6}	40	130	40	130	105	130	146	35 _{h9}	35 _{h9} ^{H7}	35.5	44	50	101.0	80	115	3.0	75	213	7.0	190	206	75	30	39	35	34	M10	M8	16	13
K4	152	110 _{h6}	50	155	50	155	120	148	173	40 _{h9}	40 _{h9} ^{H7}	40.5	50	55	114.0	88	130	3.5	90	240	7.5	220	243	90	40	39	45	34	M12	M10	19	16
K5	145	110 _{h6}	40	140	100	140	125	160	185	50 _{h9}	50 _{h9} ^{H7}	50.5	62	65	116.0	106	130	3.5	160	260	7.5	237	254	100	40	44	45	39	M16	M10	26	16
K6	180	140 _{h6}	50	160	110	160	130	168	200	50 _{h9}	50 _{h9} ^{H7}	50.5	62	70	128.0	106	165	3.5	190	310	7.5	254	276	120	40	45	45	40	M16	M10	26	16
K7	195	155 _{h6}	55	180	125	180	145	190	226	60 _{h6}	60 _{h6} ^{H7}	62.0	75	85	161.5	138	185	3.5	212	342	8.0	278	314	125	40	45	45	40	M20	M12	33	19
K8	226	185 _{h6}	75	240	165	240	185	235	282	70 _{h6}	70 _{h6} ^{H7}	72.0	90	100	193.0	155	215	4.0	265	410	9.0	352	378	145	50	60	60	50	M24	M12	38	19
K9	280	230 _{h6}	95	280	185	280	225	285	330	90 _{h6}	90 _{h6} ^{H7}	92.0	120	120	244.0	200	265	5.0	315	495	10.0	418	428	180	60	70	70	60	M30	M16	48	26

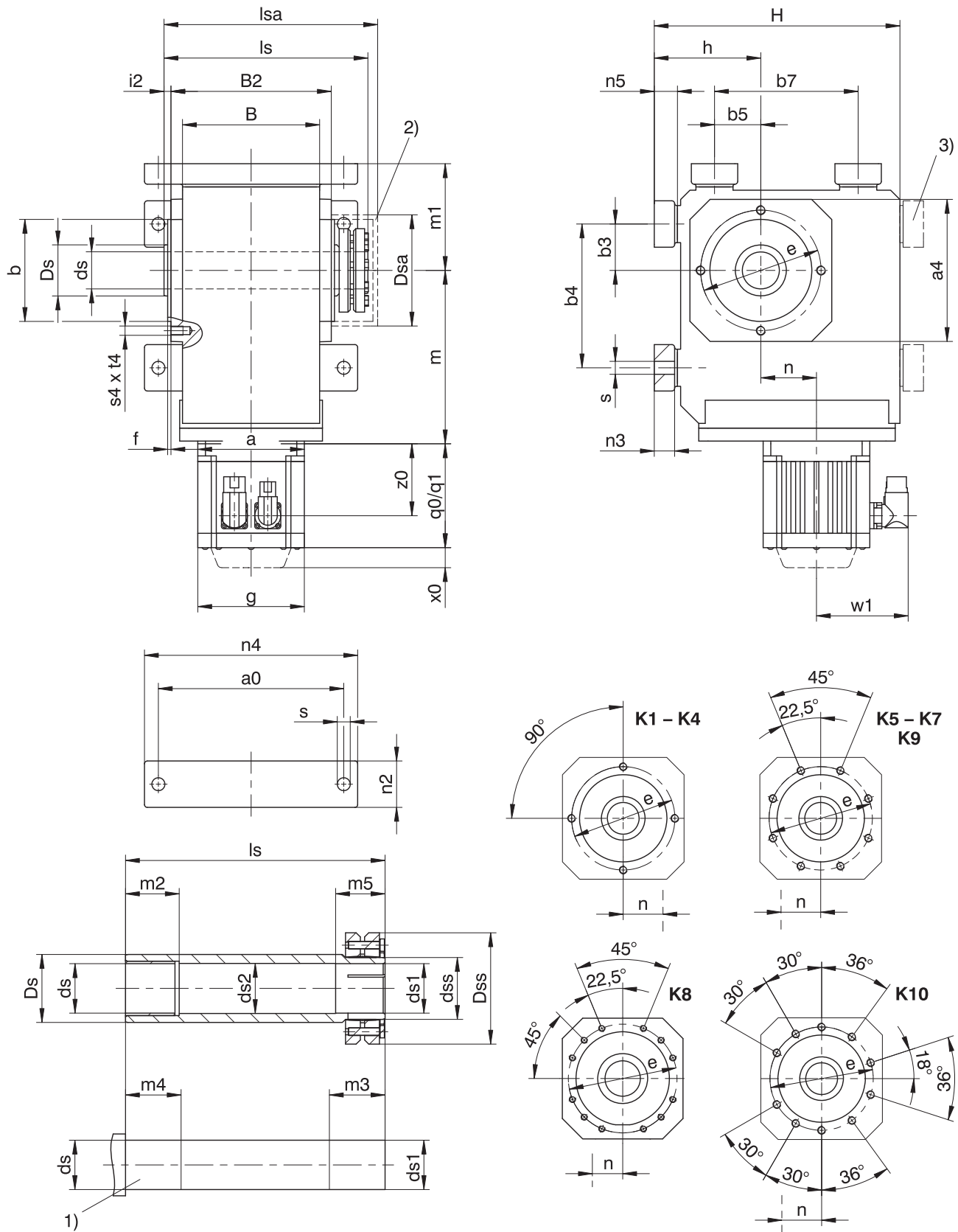
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.8 S shaft design (hollow shaft with shrink disk), NG housing design (base + pitch circle diameter)



- q0 Applies to motors without brake.
- q1 Applies to motors with brake.
- x0 Applies to encoders using an optical measuring method.
- w1 Different for the One Cable Solution (OCS), see the chapter [▶ 17.4](#)
- 1) Machine shaft: The dimension l_s must meet or exceed the specified value.
- 2) Cover (optional)
- 3) Only for K1 (other sizes on request)

Dimensions of gearboxes

Type	a0	a4	Øb	b3	b4	b5	b7	B	B2	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa
K1	115	105	75 _{j6}	30	90	30	90	90	106	25 _{h9}	25 _{h7}	25.5	30	40	80.0
K2	155	116	82 _{j6}	35	115	35	115	115	134	30 _{h9}	30 _{h7}	30.5	36	45	88.0
K3	170	132	95 _{j6}	40	130	40	130	130	146	35 _{h9}	35 _{h7}	35.5	44	50	101.0
K4	200	152	110 _{j6}	50	155	50	155	148	173	40 _{h9}	40 _{h7}	40.5	50	55	114.0
K5	200	145	110 _{j6}	40	140	100	140	160	185	50 _{h9}	50 _{h7}	50.5	62	65	116.0
K6	210	180	140 _{j6}	50	160	110	160	168	200	50 _{h9}	50 _{h7}	50.5	62	70	128.0
K7	241	195	155 _{j6}	55	180	125	180	190	226	60 _{h6}	60 _{h7}	62.0	75	85	161.5
K8	300	226	185 _{j6}	75	240	165	240	235	282	70 _{h6}	70 _{h7}	72.0	90	100	193.0
K9	360	280	230 _{j6}	95	280	185	280	285	330	90 _{h6}	90 _{h7}	92.0	120	120	244.0
K10	330	340	250 _{h6}	115	350	265	420	400	356	100 _{h6}	100 _{h7}	102.0	130	130	274.0

Dimensions of gearboxes

Type	ØDss	Øe	f	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	n2	n3	n4	n5	Øs	s4	t4
K1	60	90	3.0	75	175	7.0	149	163	75	20	34	25	29	30	13	140	15	9.0	M8	13
K2	72	100	3.0	88	213	7.0	178	193	88	25	39	30	34	40	20	185	23	11.0	M8	13
K3	80	115	3.0	98	236	7.0	190	206	98	30	39	35	34	45	20	200	23	11.0	M8	13
K4	88	130	3.5	115	265	7.5	220	243	115	40	39	45	34	50	22	230	25	14.0	M10	16
K5	106	130	3.5	190	290	7.5	237	254	130	40	44	45	39	60	27	240	30	18.0	M10	16
K6	106	165	3.5	220	340	7.5	254	276	150	40	45	45	40	65	27	250	30	18.5	M10	16
K7	138	185	3.5	250	380	8.0	278	314	163	40	45	45	40	70	35	290	38	23.0	M12	19
K8	155	215	4.0	310	455	9.0	352	378	190	50	60	60	50	85	41	360	45	27.0	M12	19
K9	200	265	5.0	365	545	10.0	418	428	230	60	70	70	60	95	46	430	50	31.0	M16	26
K10	215	300	20.0	420	636	27.0	483	497	270	60	80	70	70	120	–	400	45	39.0	M20	33

Dimensions of motors

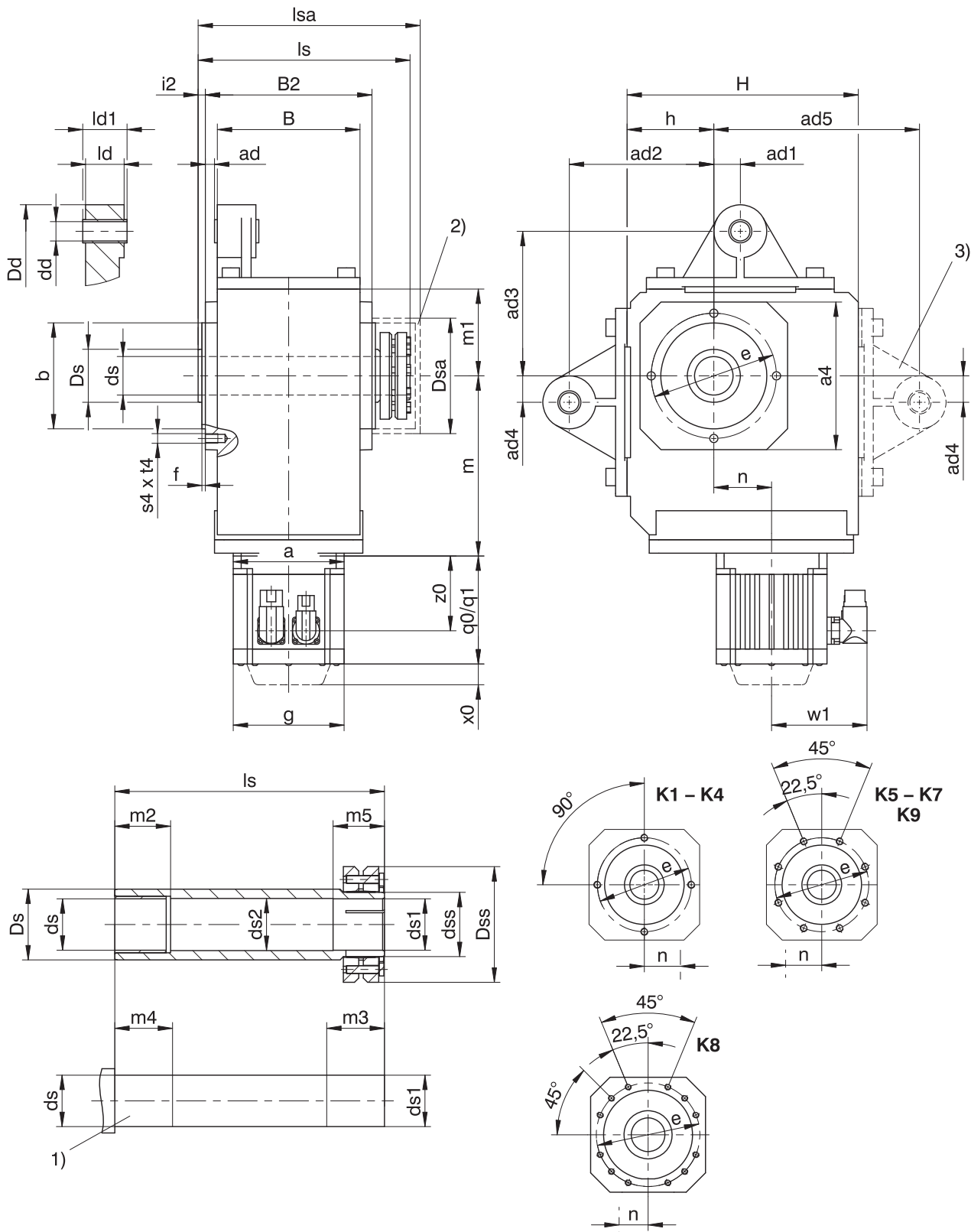
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0
K1014	-	-	-	-	-	-	-	-	-	-	-	-	∅250	450	28.0

16.3.9 S shaft design (hollow shaft with shrink ring), GD housing design (pitch circle diameter + torque arm bracket)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

1) Machine shaft: The dimension Is must meet or exceed the specified value.

3) Only for K1 (other sizes on request)

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

2) Cover (optional)

- If you brace the gearboxes without the torque arm brackets provided by the manufacturer for this purpose, the dimensions for $ad2$ and $ad3$ must meet the specified value.

Dimensions of gearboxes

Type	□a4	ad	ad1	ad2	ad3	ad4	ad5	Øb	B	B2	Ødd	Øds	Øds1	Øds2	Ødss	ØDd	ØDs	ØDsa
K1	105	6.0	15.0	90	90	15.0	130	75 _{j6}	90	106	12 ^{H9}	25 _{h9}	25 _{h9} ^{H7}	25.5	30	43	40	80.0
K2	116	6.5	22.5	100	100	22.5	–	82 _{j6}	115	134	16 ^{H9}	30 _{h9}	30 _{h9} ^{H7}	30.5	36	45	45	88.0
K3	132	5.0	25.0	120	120	25.0	–	95 _{j6}	130	146	16 ^{H9}	35 _{h9}	35 _{h9} ^{H7}	35.5	44	45	50	101.0
K4	152	9.5	27.5	150	150	27.5	–	110 _{j6}	148	173	20 ^{H9}	40 _{h9}	40 _{h9} ^{H7}	40.5	50	55	55	114.0
K5	145	9.5	30.0	250	190	30.0	–	110 _{j6}	160	185	20 ^{H9}	50 _{h9}	50 _{h9} ^{H7}	50.5	62	58	65	116.0
K6	180	13.0	30.0	250	180	30.0	–	140 _{j6}	168	200	20 ^{H9}	50 _{h9}	50 _{h9} ^{H7}	50.5	62	58	70	128.0
K7	195	15.0	35.0	300	213	35.0	–	155 _{h6}	190	226	20 ^{H9}	60 _{h6}	60 _{h6} ^{H7}	62.0	75	68	85	161.5
K8	226	17.0	45.0	350	230	45.0	–	185 _{h6}	235	282	24 ^{H9}	70 _{h6}	70 _{h6} ^{H7}	72.0	90	72	100	193.0
K9	280	16.0	45.0	450	315	45.0	–	230 _{h6}	285	330	24 ^{H9}	90 _{h6}	90 _{h6} ^{H7}	92.0	120	75	120	244.0

Dimensions of gearboxes

Type	ØDss	Øe	f	h	H	i2	ld	ld1	ls	lsa	m1	m2	m3	m4	m5	s4	t4
K1	60	90	3.0	60	160	7.0	24	28	149	163	60	20	34	25	29	M8	13
K2	72	100	3.0	65	190	7.0	32	38	178	193	65	25	39	30	34	M8	13
K3	80	115	3.0	75	213	7.0	32	38	190	206	75	30	39	35	34	M8	13
K4	88	130	3.5	90	240	7.5	40	46	220	243	90	40	39	45	34	M10	16
K5	106	130	3.5	160	260	7.5	40	46	237	254	100	40	44	45	39	M10	16
K6	106	165	3.5	190	310	7.5	40	46	254	276	120	40	45	45	40	M10	16
K7	138	185	3.5	212	342	8.0	64	70	278	314	125	40	45	45	40	M12	19
K8	155	215	4.0	265	410	9.0	102	115	352	378	145	50	60	60	50	M12	19
K9	200	265	5.0	315	495	10.0	102	115	418	428	180	60	70	70	60	M16	26

Dimensions of motors

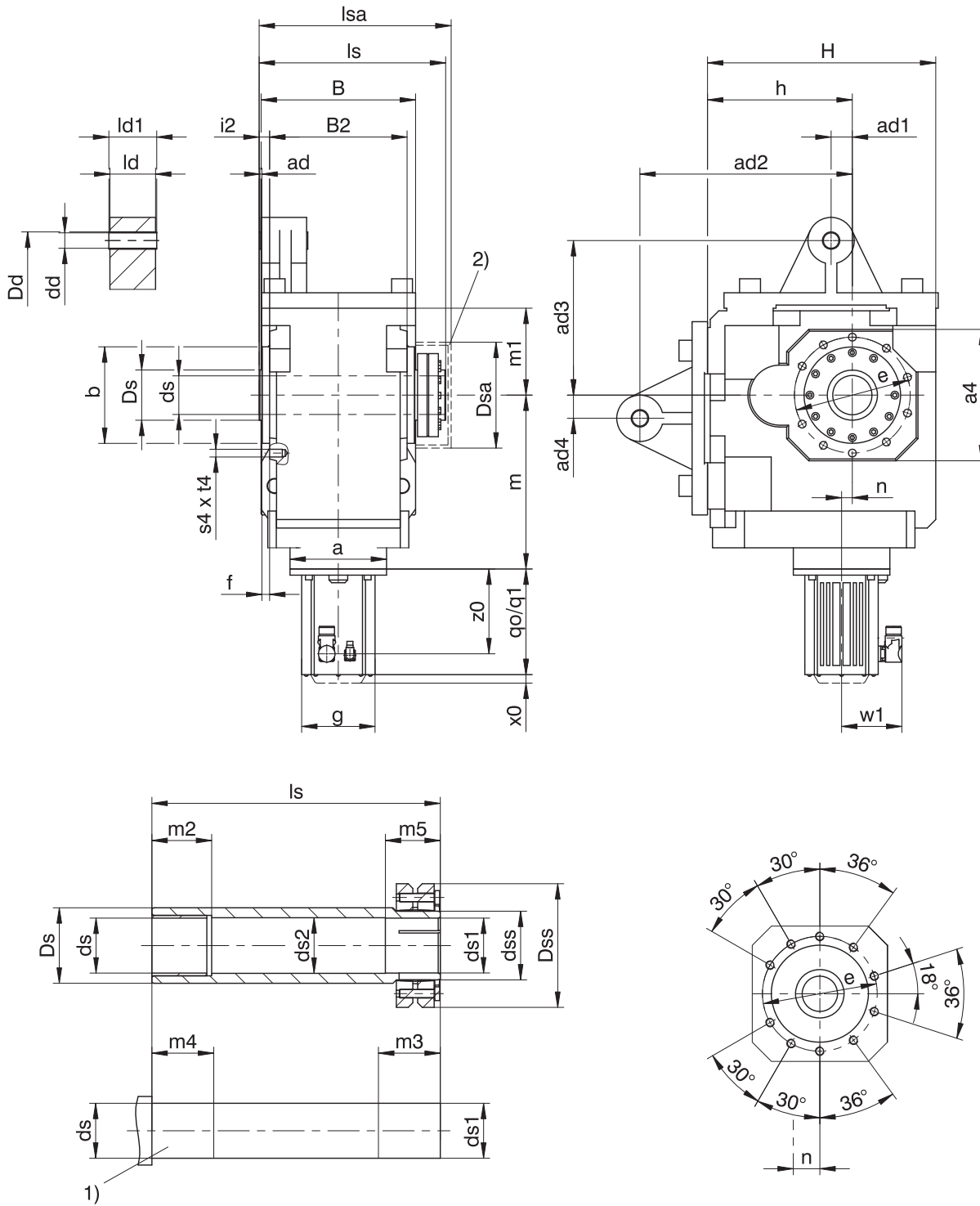
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.10 S shaft design (hollow shaft with shrink ring), NGD housing design (foot + pitch circle diameter + torque arm bracket)



- | | | | |
|-------|---|-------|--|
| q_0 | Applies to motors without brake. | q_1 | Applies to motors with brake. |
| x_0 | Applies to encoders using an optical measuring method. | w_1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension l_s must meet or exceed the specified value. | 2) | Cover (optional) |
| - | If you brace the gearboxes without the torque arm brackets provided by the manufacturer for this purpose, the dimensions for ad_2 and ad_3 must meet the specified value. | | |

Dimensions of gearboxes

Type	□a4	ad	ad1	ad2	ad3	ad4	Øb	B	B2	Ødd	Øds	Øds1	Øds2	Ødss	ØDd	ØDs	ØDsa
K10	340	5	55	550	400	60	250 _{h6}	400	356	40 ^{H9}	100 _{h6}	100 _{h6} ^{H7}	102	130	120	130	274

Dimensions of gearboxes

Type	ØDss	Øe	f	h	H	i2	ld	ld1	ls	lsa	m1	m2	m3	m4	m5	s4	t4
K10	215	300	20	375	591	27	118	124	483	497	225	60	80	70	70	M20	33

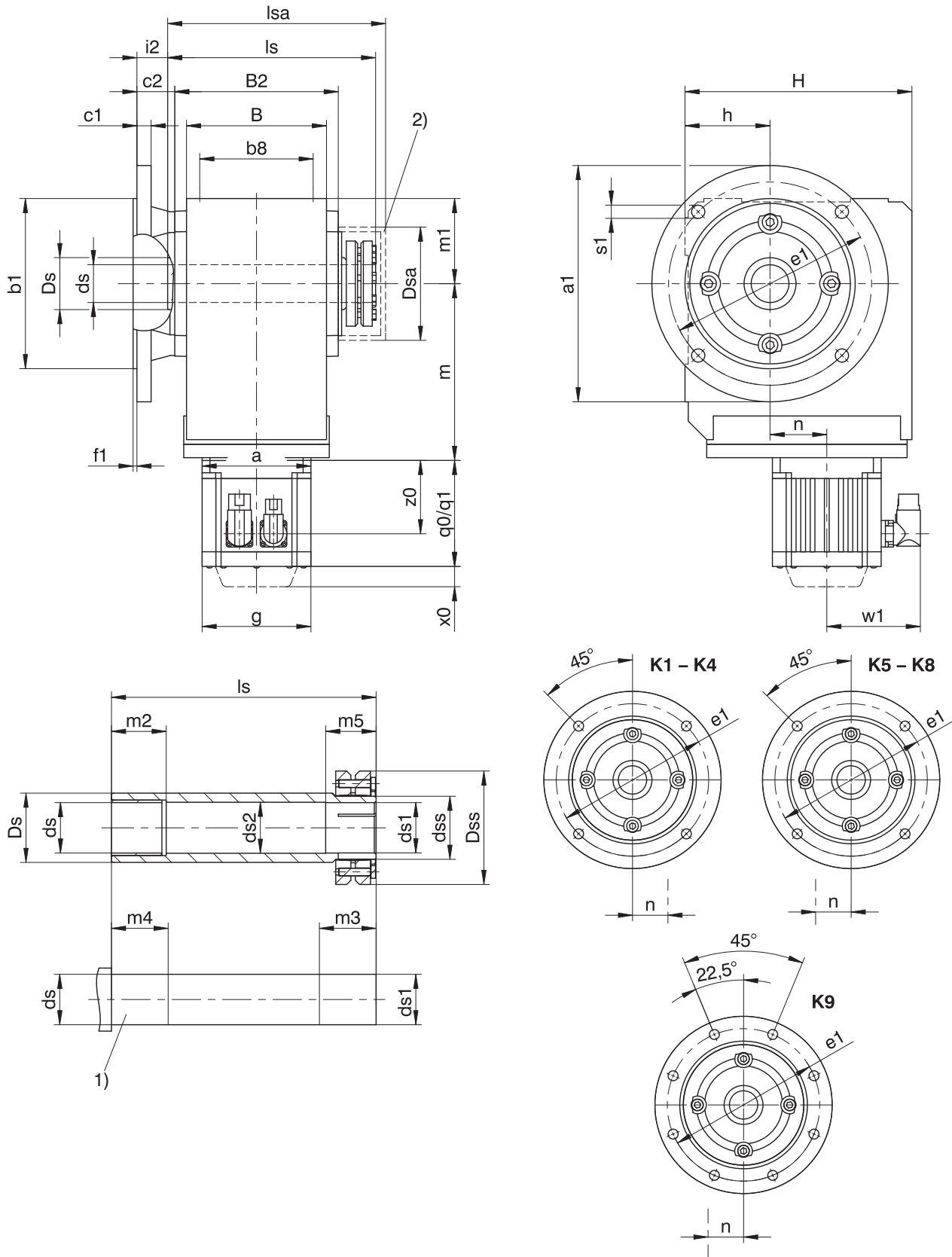
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ8		
	a	m	n
K1014	Ø250	450	28.0

16.3.11 S shaft design (hollow shaft with shrink disk), F housing design (round flange)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

1) Machine shaft: The dimension l_s must meet or exceed the specified value.

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

2) Cover (optional)

Dimensions of gearboxes

Type	Øa1	Øb1	b8	B	B2	c1	c2	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss	Øe1	f1	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	Øs1
K1	160	110 _{f6}	70	90	106	10	32.0	25 _{h9}	25 _{h9} ^{H7}	25.5	30	40	80.0	60	130	3.5	60	160	25.0	149	163	60	20	34	25	29	9
K2	200	130 _{f6}	90	115	134	12	32.0	30 _{h9}	30 _{h9} ^{H7}	30.5	36	45	88.0	72	165	3.5	65	190	25.0	178	193	65	25	39	30	34	11
K3	200	130 _{f6}	105	130	146	14	38.0	35 _{h9}	35 _{h9} ^{H7}	35.5	44	50	101.0	80	165	3.5	75	213	31.0	190	206	75	30	39	35	34	11
K4	250	180 _{f6}	120	148	173	15	40.0	40 _{h9}	40 _{h9} ^{H7}	40.5	50	55	114.0	88	215	4.0	90	240	32.5	220	243	90	40	39	45	34	14
K5	250	180 _{f6}	125	160	185	15	39.5	50 _{h9}	50 _{h9} ^{H7}	50.5	62	65	116.0	106	215	4.0	160	260	32.0	237	254	100	40	44	45	39	14
K6	300	230 _{f6}	130	168	200	17	36.0	50 _{h9}	50 _{h9} ^{H7}	50.5	62	70	128.0	106	265	4.0	190	310	28.5	254	276	120	40	45	45	40	14
K7	350	250 _{h6}	145	190	226	18	44.0	60 _{h6}	60 _{h6} ^{H7}	62.0	75	85	161.5	138	300	5.0	212	342	36.0	278	314	125	40	45	45	40	18
K8	400	300 _{h6}	185	235	282	20	45.0	70 _{h6}	70 _{h6} ^{H7}	72.0	90	100	193.0	155	350	5.0	265	410	36.0	352	378	145	50	60	60	50	18
K9	450	350 _{h6}	225	285	330	23	50.0	90 _{h6}	90 _{h6} ^{H7}	92.0	120	120	244.0	200	400	5.0	315	495	40.0	418	428	180	60	70	70	60	18

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _{f6}	10	115	3.0	9
K2	160	110 _{f6}	12	130	3.5	9
K3	160	110 _{f6}	14	130	3.5	9
K3	250	180 _{f6}	14	215	4.0	14
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

Dimensions of motors

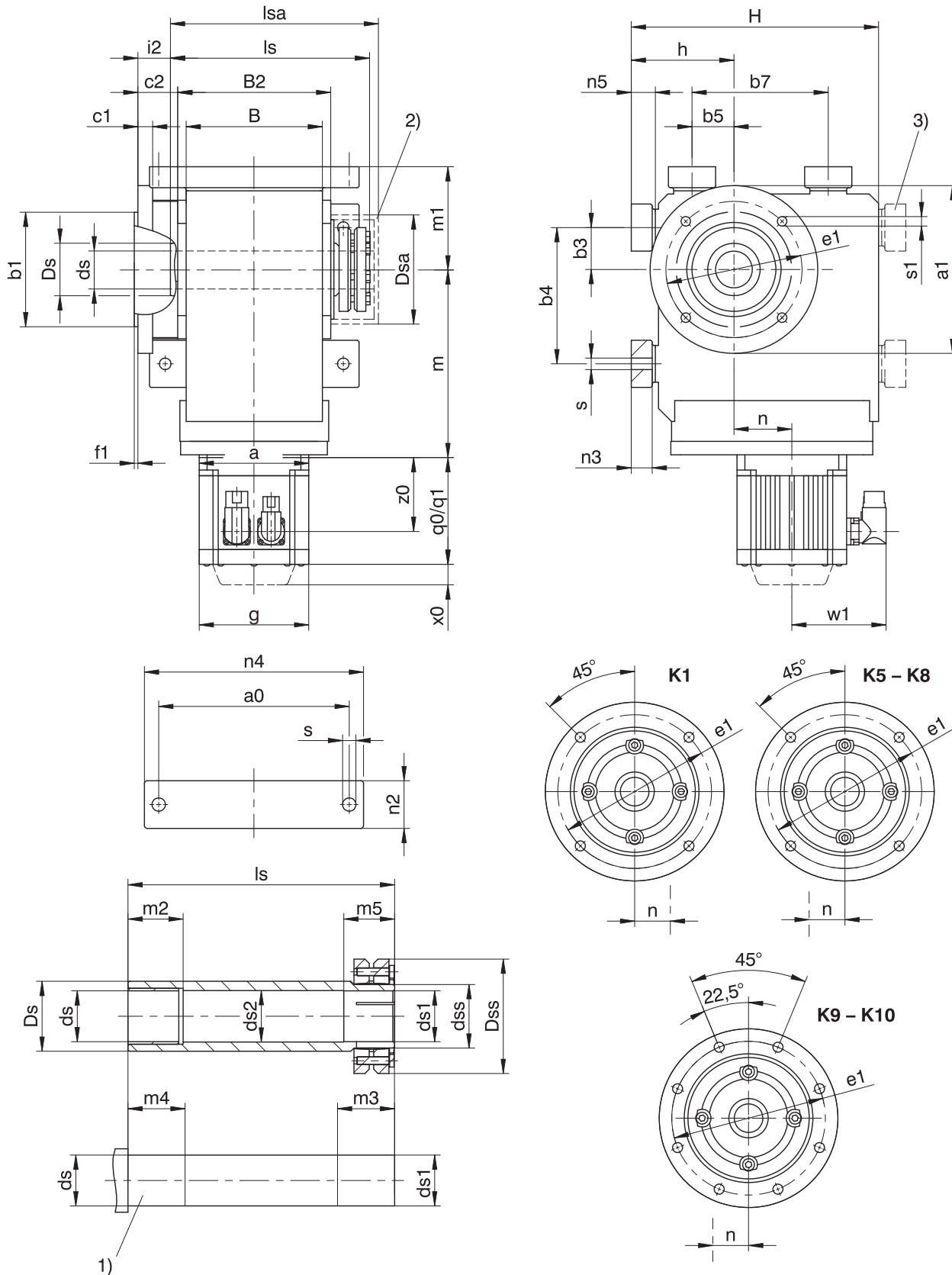
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.12 S shaft design (hollow shaft with shrink disk), NF housing design (base + round flange)



- | | | | |
|----|--|----|--|
| q0 | Applies to motors without brake. | q1 | Applies to motors with brake. |
| x0 | Applies to encoders using an optical measuring method. | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 1) | Machine shaft: The dimension ls must meet or exceed the specified value. | 2) | Cover (optional) |
| 3) | Only for K1 (other sizes on request) | | |

Dimensions of gearboxes

Type	a0	Øa1	Øb1	b3	b4	b5	b7	B	B2	c1	Øds	Øds1	Øds2	Ødss	ØDs	ØDsa	ØDss
K1	115	160	110 _{j6}	30	90	30	90	90	106	10	25 _{h9}	25 _{h9} ^{H7}	25.5	30	40	80.0	60
K5	200	250	180 _{j6}	40	140	100	140	160	185	15	50 _{h9}	50 _{h9} ^{H7}	50.5	62	65	116.0	106
K6	210	300	230 _{j6}	50	160	110	160	168	200	17	50 _{h9}	50 _{h9} ^{H7}	50.5	62	70	128.0	106
K7	241	350	250 _{h6}	55	180	125	180	190	226	18	60 _{h6}	60 _{h6} ^{H7}	62.0	75	85	161.5	138
K8	300	400	300 _{h6}	75	240	165	240	235	282	20	70 _{h6}	70 _{h6} ^{H7}	72.0	90	100	193.0	155
K9	360	450	350 _{h6}	95	280	185	280	285	330	23	90 _{h6}	90 _{h6} ^{H7}	92.0	120	120	244.0	200
K10	330	550	450 _{h6}	115	350	265	420	400	356	25	100 _{h6}	100 _{h6} ^{H7}	102.0	130	130	274.0	215

Dimensions of gearboxes

Type	Øe1	f1	h	H	i2	ls	lsa	m1	m2	m3	m4	m5	n2	n3	n4	n5	Øs	Øs1
K1	130	3.5	75	175	25.0	149	163	75	20	34	25	29	30	13	140	15	9.0	9
K5	215	4.0	190	290	32.0	237	254	130	40	44	45	39	60	27	240	30	18.0	14
K6	265	4.0	220	340	28.5	254	276	150	40	45	45	40	65	27	250	30	18.5	14
K7	300	5.0	250	380	36.0	278	314	163	40	45	45	40	70	35	290	38	23.0	18
K8	350	5.0	310	455	36.0	352	378	190	50	60	60	50	85	41	360	45	27.0	18
K9	400	5.0	365	545	40.0	418	428	230	60	70	70	60	95	46	430	50	31.0	18
K10	500	5.0	420	636	51.0	483	497	270	60	80	70	70	120	–	400	45	39.0	18

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _{j6}	10	115	3.0	9
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

Dimensions of motors

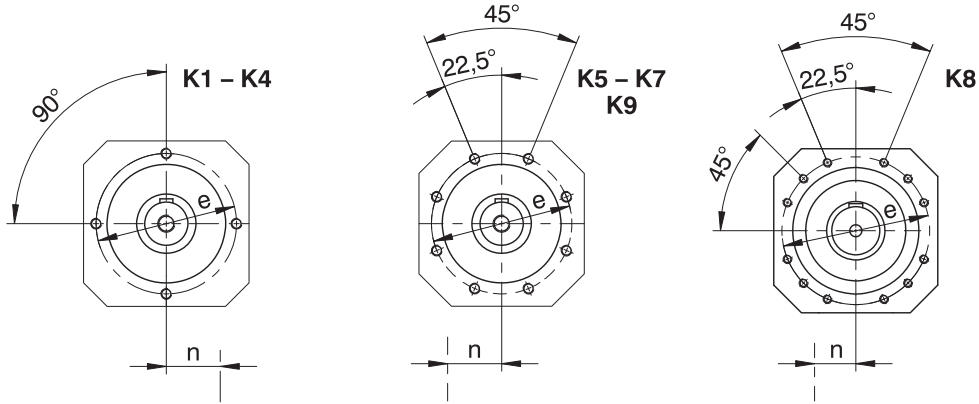
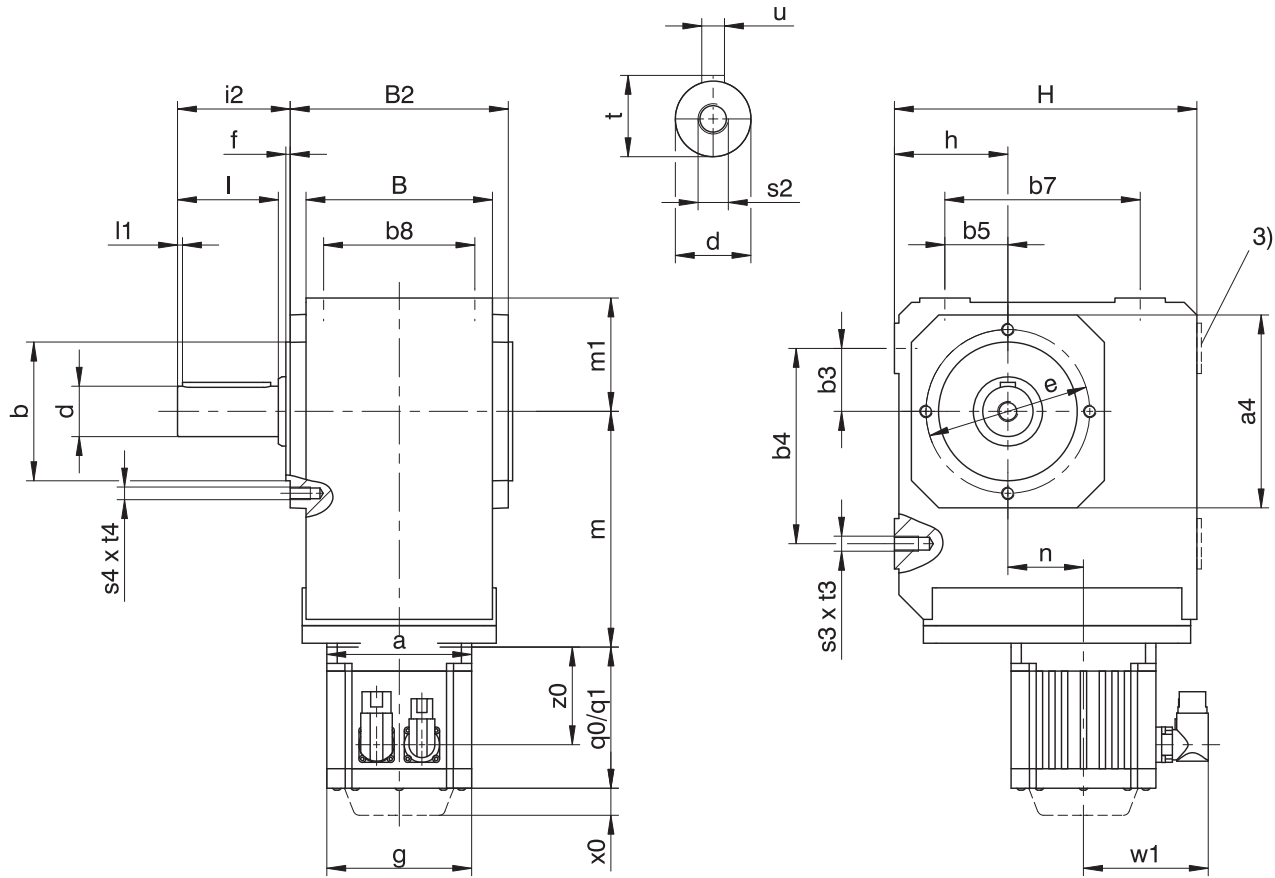
Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

The dimensions a, m and n can be found on the next page.

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0
K1014	-	-	-	-	-	-	-	-	-	-	-	-	∅250	450	28.0

16.3.13 V shaft design (solid shaft), G housing design (pitch circle diameter)



q0 Applies to motors without brake.

x0 Applies to encoders using an optical measuring method.

3) Only for K1 (other sizes on request)

- K1 - K9: Solid shaft on both sides available.

q1 Applies to motors with brake.

w1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

- K1 - K4: Solid shaft without feather key available, on request starting at K5.

Dimensions of gearboxes

Type	□a4	∅b	b3	b4	b5	b7	b8	B	B2	∅d	∅e	f	h	H	i2	l	l1	m1	s2	s3	s4	t	t3	t4	u
K1	105	75 _g	30	90	30	90	70	90	106	25 _{k6}	90	3.0	60	160	62.0	50	4	60	M10	M8	M8	28.0	13	13	A8×7×40
K2	116	82 _g	35	115	35	115	90	115	134	30 _{k6}	100	3.0	65	190	68.0	60	4	65	M10	M10	M8	33.0	16	13	A8×7×50
K3	132	95 _g	40	130	40	130	105	130	146	30 _{k6}	115	3.0	75	213	69.0	60	4	75	M10	M10	M8	33.0	16	13	A8×7×50
K4	152	110 _g	50	155	50	155	120	148	173	40 _{k6}	130	3.5	90	240	89.5	80	4	90	M16	M12	M10	43.0	19	16	A12×8×70
K5	145	110 _g	40	140	100	140	125	160	185	45 _{k6}	130	3.5	160	260	129.5	90	4	100	M16	M16	M10	48.5	26	16	A14×9×80
K6	180	140 _g	50	160	110	160	130	168	200	50 _{k6}	165	3.5	190	310	136.0	100	4	120	M16	M16	M10	53.5	26	16	A14×9×90
K7	195	155 _g	55	180	125	180	145	190	226	60 _{m6}	185	3.5	212	342	164.0	120	4	125	M20	M20	M12	64.0	33	19	A18×11×110
K8	226	185 _g	75	240	165	240	185	235	282	70 _{m6}	215	4.0	265	410	185.0	140	5	145	M20	M24	M12	74.5	38	19	A20×12×125
K9	280	230 _g	95	280	185	280	225	285	330	90 _{m6}	265	5.0	315	495	220.0	170	8	180	M24	M30	M16	95.0	48	26	A25×14×140

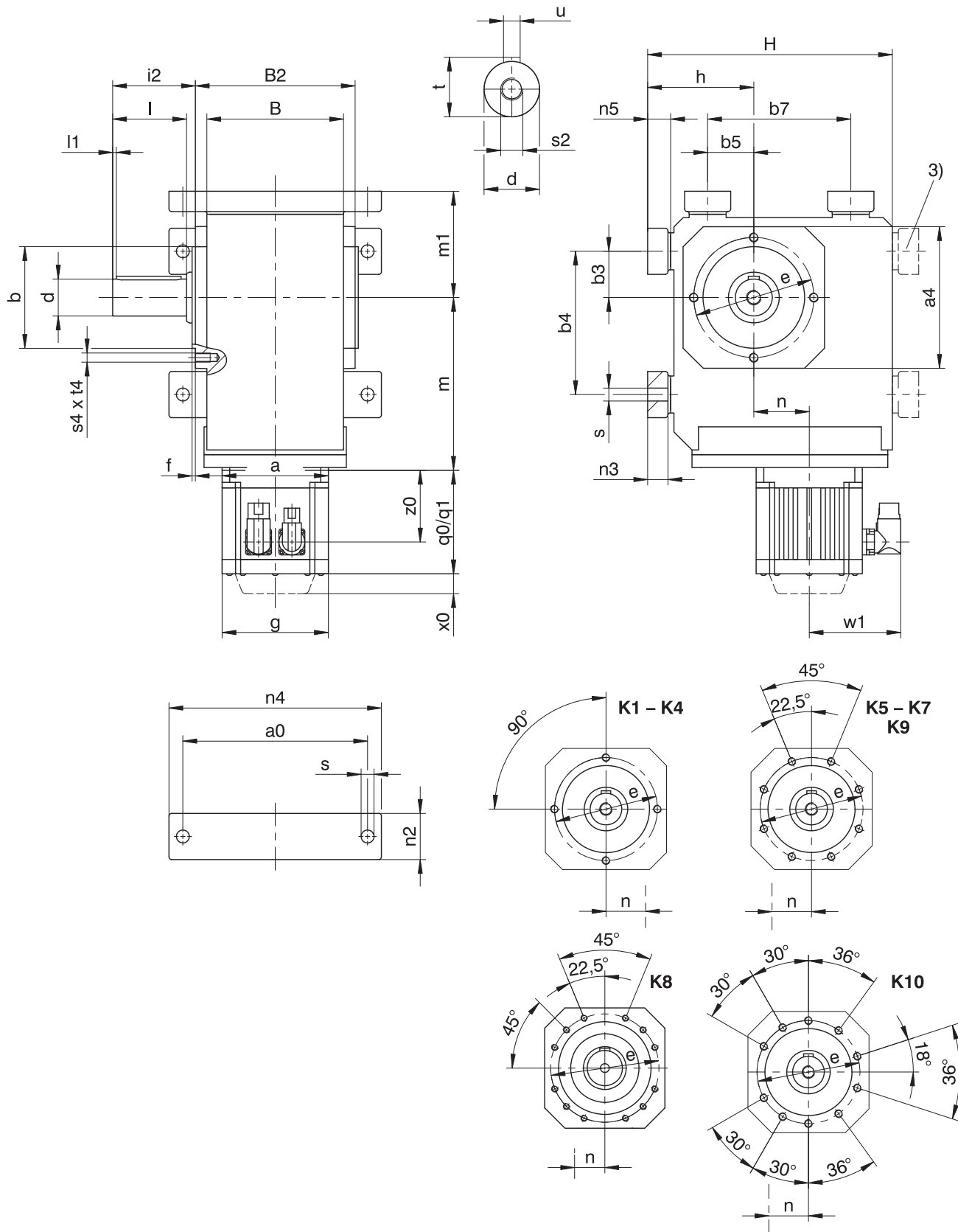
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	∅140	180	46.0	∅140	180	46.0	-	-	-	-	-	-	-	-	-
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	∅160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	∅160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	∅200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	∅160	263	20.0	∅200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	∅200	247	24.0	∅250	249	24.0
K814	-	-	-	-	-	-	-	-	-	∅200	308	24.0	∅250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	∅250	294	25.0
K914	-	-	-	-	-	-	-	-	-	∅200	353	25.0	∅250	365	25.0

16.3.14 V shaft design (solid shaft), NG housing design (base + pitch circle diameter)



- q0 Applies to motors without brake.
- x0 Applies to encoders using an optical measuring method.
- 3) Only for K1 (other sizes on request)
- K1 – K10: Solid shaft on both sides available.
- q1 Applies to motors with brake.
- w1 Different for the One Cable Solution (OCS), see the chapter [▶ 17.4](#)
- K1 – K4: Solid shaft without feather key available, on request starting at K5.

Dimensions of gearboxes

Type	a0	□a4	∅b	b3	b4	b5	b7	B	B2	∅d	∅e	f	h	H	i2	l	l1	m1	n2	n3	n4	n5	∅s	s2	s4	t	t4	u
K1	115	105	75 ₆	30	90	30	90	90	106	25 ₆	90	3.0	75	175	62.0	50	4	75	30	13	140	15	9.0	M10	M8	28.0	13	A8×7×40
K2	155	116	82 ₆	35	115	35	115	115	134	30 ₆	100	3.0	88	213	68.0	60	4	88	40	20	185	23	11.0	M10	M8	33.0	13	A8×7×50
K3	170	132	95 ₆	40	130	40	130	130	146	30 ₆	115	3.0	98	236	69.0	60	4	98	45	20	200	23	11.0	M10	M8	33.0	13	A8×7×50
K4	200	152	110 ₆	50	155	50	155	148	173	40 ₆	130	3.5	115	265	89.5	80	4	115	50	22	230	25	14.0	M16	M10	43.0	16	A12×8×70
K5	200	145	110 ₆	40	140	100	140	160	185	45 ₆	130	3.5	190	290	129.5	90	4	130	60	27	240	30	18.0	M16	M10	48.5	16	A14×9×80
K6	210	180	140 ₆	50	160	110	160	168	200	50 ₆	165	3.5	220	340	136.0	100	4	150	65	27	250	30	18.5	M16	M10	53.5	16	A14×9×90
K7	241	195	155 ₆	55	180	125	180	190	226	60 ₆	185	3.5	250	380	164.0	120	4	163	70	35	290	38	23.0	M20	M12	64.0	19	A18×11×110
K8	300	226	185 ₆	75	240	165	240	235	282	70 ₆	215	4.0	310	455	185.0	140	5	190	85	41	360	45	27.0	M20	M12	74.5	19	A20×12×125
K9	360	280	230 ₆	95	280	185	280	285	330	90 ₆	265	5.0	365	545	220.0	170	8	230	95	46	430	50	31.0	M24	M16	95.0	26	A25×14×140
K10	330	340	250 ₆	115	350	265	420	400	356	110 ₆	300	20.0	420	636	240.0	210	15	270	120	–	400	45	39.0	M24	M20	116.0	33	A28×16×180

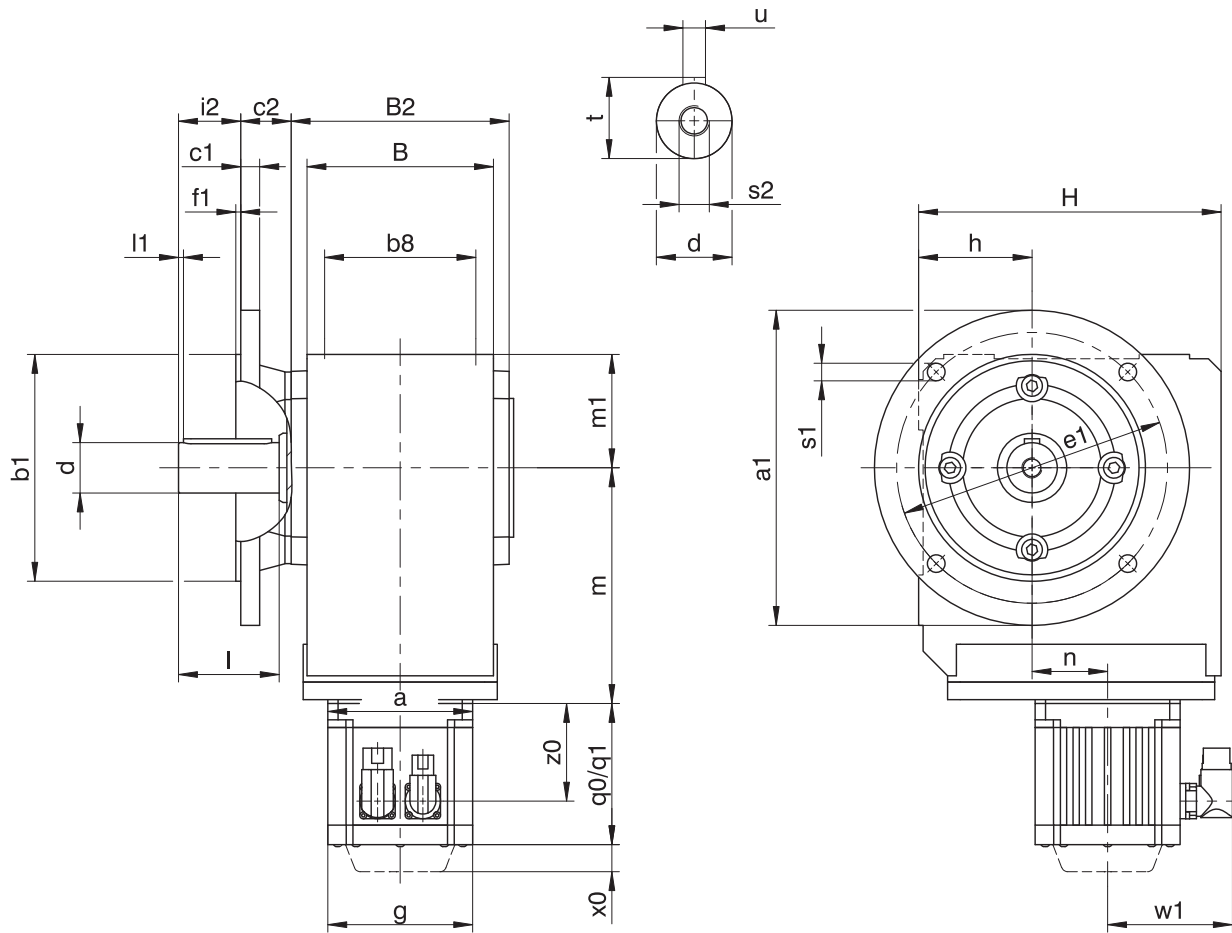
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	–	–	–
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	–	–	–
K203	∅140	180	46.0	∅140	180	46.0	–	–	–	–	–	–	–	–	–
K302	∅140	163	52.5	∅140	163	52.5	□115	167	52.5	□145	169	52.5	–	–	–
K303	∅140	200	52.5	∅140	200	52.5	∅160	210	16.0	–	–	–	–	–	–
K402	–	–	–	–	–	–	∅160	187	60.0	□145	189	60.0	□190	192	60.0
K403	∅140	220	60.0	∅140	220	60.0	∅160	230	23.0	–	–	–	–	–	–
K513	–	–	–	–	–	–	∅160	172	15.0	□145	174	15.0	□190	177	15.0
K514	–	–	–	–	–	–	∅160	215	15.0	–	–	–	–	–	–
K613	–	–	–	–	–	–	∅160	191	18.0	∅200	193	18.0	□190	196	18.0
K614	–	–	–	–	–	–	∅160	234	18.0	–	–	–	–	–	–
K713	–	–	–	–	–	–	–	–	–	∅200	221	20.0	□190	224	20.0
K714	–	–	–	–	–	–	∅160	263	20.0	∅200	283	20.0	–	–	–
K813	–	–	–	–	–	–	–	–	–	∅200	247	24.0	∅250	249	24.0
K814	–	–	–	–	–	–	–	–	–	∅200	308	24.0	∅250	320	5.0
K913	–	–	–	–	–	–	–	–	–	–	–	–	∅250	294	25.0
K914	–	–	–	–	–	–	–	–	–	∅200	353	25.0	∅250	365	25.0
K1014	–	–	–	–	–	–	–	–	–	–	–	–	∅250	450	28.0

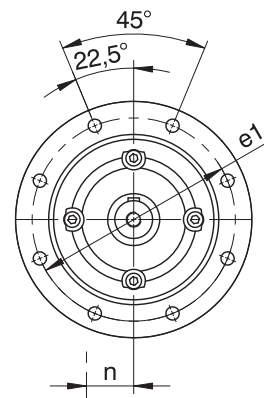
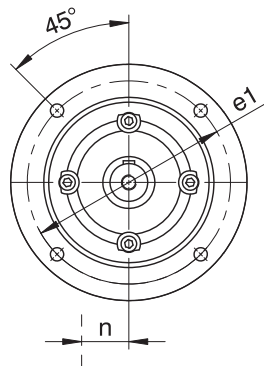
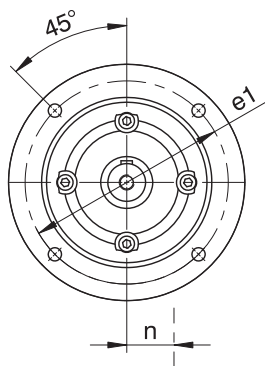
16.3.15 V shaft design (solid shaft), F housing design (round flange)



K1 – K4

K5 – K8

K9



q_0 Applies to motors without brake.

q_1 Applies to motors with brake.

x_0 Applies to encoders using an optical measuring method.

w_1 Different for the One Cable Solution (OCS), see the chapter [17.4](#)

– K1 – K4: Solid shaft without feather key available, on request starting at K5.

– K1 – K9: Solid shaft on both sides available.

Dimensions of gearboxes

Type	$\varnothing a_1$	$\varnothing b_1$	b_8	B	B_2	c_1	c_2	$\varnothing d$	$\varnothing e_1$	f_1	h	H	i_2	l	l_1	m_1	$\varnothing s_1$	s_2	t	u
K1	160	110 _{h6}	70	90	106	10	32.0	25 _{h6}	130	3.5	60	160	30.0	50	4	60	9	M10	28.0	A8×7×40
K2	200	130 _{h6}	90	115	134	12	32.0	30 _{h6}	165	3.5	65	190	36.0	60	4	65	11	M10	33.0	A8×7×50
K3	200	130 _{h6}	105	130	146	14	38.0	30 _{h6}	165	3.5	75	213	31.0	60	4	75	11	M10	33.0	A8×7×50
K4	250	180 _{h6}	120	148	173	15	40.0	40 _{h6}	215	4.0	90	240	49.5	80	4	90	14	M16	43.0	A12×8×70
K5	250	180 _{h6}	125	160	185	15	39.5	45 _{h6}	215	4.0	160	260	90.0	90	4	100	14	M16	48.5	A14×9×80
K6	300	230 _{h6}	130	168	200	17	36.0	50 _{h6}	265	4.0	190	310	100.0	100	4	120	14	M16	53.5	A14×9×90
K7	350	250 _{h6}	145	190	226	18	44.0	60 _{h6}	300	5.0	212	342	120.0	120	4	125	18	M20	64.0	A18×11×110
K8	400	300 _{h6}	185	235	282	20	45.0	70 _{h6}	350	5.0	265	410	140.0	140	5	145	18	M20	74.5	A20×12×125
K9	450	350 _{h6}	225	285	330	23	50.0	90 _{h6}	400	5.0	315	495	170.0	170	8	180	18	M24	95.0	A25×14×140

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _{f6}	10	115	3.0	9
K2	160	110 _{f6}	12	130	3.5	9
K3	160	110 _{f6}	14	130	3.5	9
K3	250	180 _{f6}	14	215	4.0	14
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

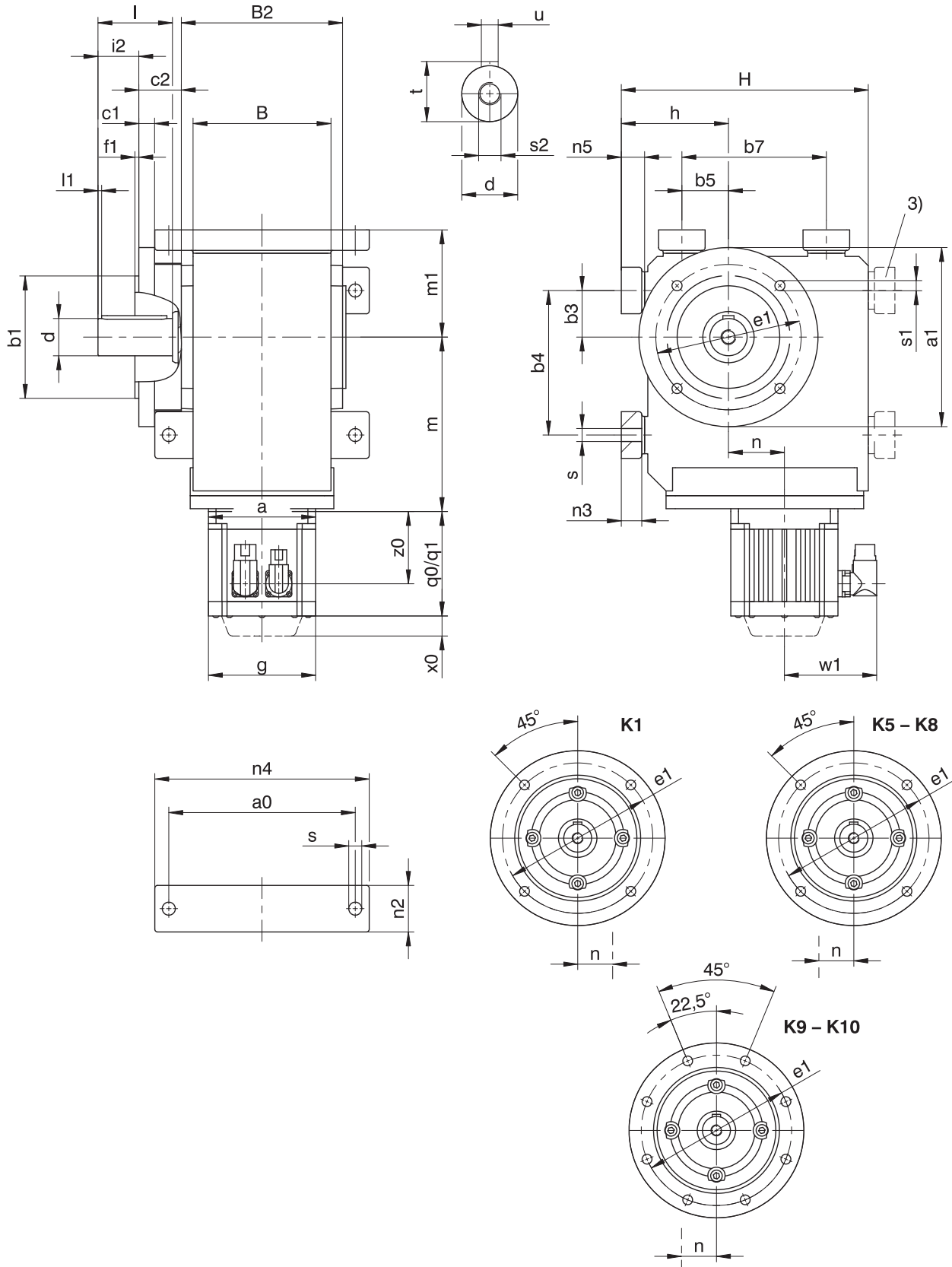
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K202	□72	143	46.0	□98	143	46.0	□115	147	46.0	□145	149	46.0	-	-	-
K203	Ø140	180	46.0	Ø140	180	46.0	-	-	-	-	-	-	-	-	-
K302	Ø140	163	52.5	Ø140	163	52.5	□115	167	52.5	□145	169	52.5	-	-	-
K303	Ø140	200	52.5	Ø140	200	52.5	Ø160	210	16.0	-	-	-	-	-	-
K402	-	-	-	-	-	-	Ø160	187	60.0	□145	189	60.0	□190	192	60.0
K403	Ø140	220	60.0	Ø140	220	60.0	Ø160	230	23.0	-	-	-	-	-	-
K513	-	-	-	-	-	-	Ø160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	Ø160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	Ø160	191	18.0	Ø200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	Ø160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	Ø200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	Ø160	263	20.0	Ø200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	Ø200	247	24.0	Ø250	249	24.0
K814	-	-	-	-	-	-	-	-	-	Ø200	308	24.0	Ø250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	Ø250	294	25.0
K914	-	-	-	-	-	-	-	-	-	Ø200	353	25.0	Ø250	365	25.0

16.3.16 V shaft design (solid shaft), NF housing design (base + round flange)



- | | | | |
|----|--|----|--|
| q0 | Applies to motors without brake. | q1 | Applies to motors with brake. |
| x0 | Applies to encoders using an optical measuring method. | w1 | Different for the One Cable Solution (OCS), see the chapter 17.4 |
| 3) | Only for K1 (other sizes on request) | - | K1 – K4: Solid shaft without feather key available, on request starting at K5. |
| - | K1 – K10: Solid shaft on both sides available. | | |

Dimensions of gearboxes

Type	a0	Øa1	Øb1	b3	b4	b5	b7	B	B2	c1	c2	Ød	Øe1	f1	h	H	i2	l	l1	m1	n2	n3	n4	n5	Øs	Øs1	s2	t	u
K1	115	160	110 _{js}	30	90	30	90	90	106	10	32.0	25 _{ks}	130	3.5	75	175	30.0	50	4	75	30	13	140	15	9.0	9	M10	28.0	A8×7×40
K5	200	250	180 _{js}	40	140	100	140	160	185	15	39.5	45 _{ks}	215	4.0	190	290	90.0	90	4	130	60	27	240	30	18.0	14	M16	48.5	A14×9×80
K6	210	300	230 _{js}	50	160	110	160	168	200	17	36.0	50 _{ks}	265	4.0	220	340	100.0	100	4	150	65	27	250	30	18.5	14	M16	53.5	A14×9×90
K7	241	350	250 _{h6}	55	180	125	180	190	226	18	44.0	60 _{m6}	300	5.0	250	380	120.0	120	4	163	70	35	290	38	23.0	18	M20	64.0	A18×11×110
K8	300	400	300 _{h6}	75	240	165	240	235	282	20	45.0	70 _{m6}	350	5.0	310	455	140.0	140	5	190	85	41	360	45	27.0	18	M20	74.5	A20×12×125
K9	360	450	350 _{h6}	95	280	185	280	285	330	23	50.0	90 _{m6}	400	5.0	365	545	170.0	170	8	230	95	46	430	50	31.0	18	M24	95.0	A25×14×140
K10	330	550	450 _{h6}	115	350	265	420	400	356	25	78.0	110 _{m6}	500	5.0	420	636	210.0	210	15	270	120	-	400	45	39.0	18	M24	116.0	A28×16×180

Dimensions of additional round flanges

Type	Øa1	Øb1	c1	Øe1	f1	Øs1
K1	140	95 _{js}	10	115	3.0	9
K8	350	250 _{h6}	18	300	5.0	18
K8	450	350 _{h6}	20	400	5.0	18

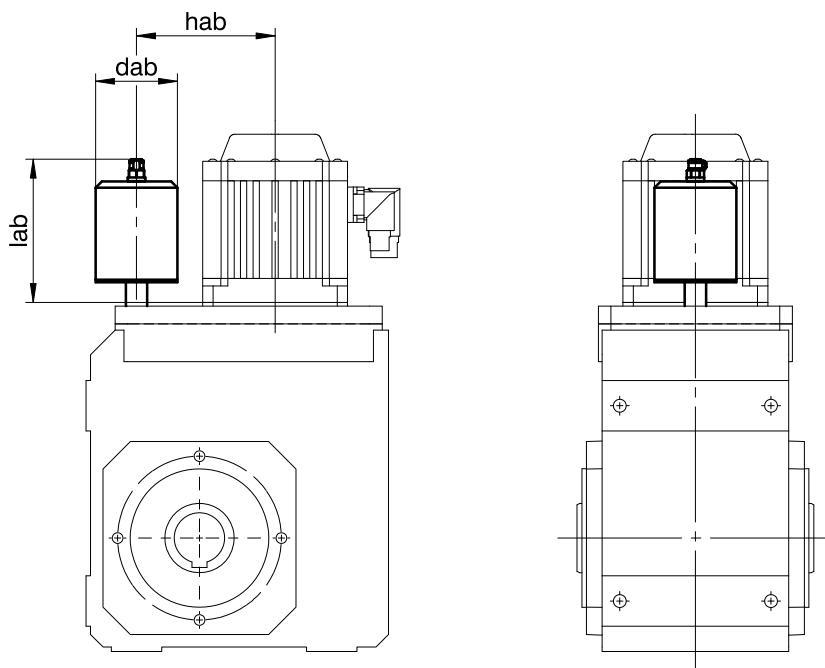
Dimensions of motors

Type	□g	q0	q1	w1	x0	z0
EZ301U	72	114.0	154.0	55.5	21	78.5
EZ302U	72	136.0	176.0	55.5	21	100.5
EZ303U	72	158.0	198.0	55.5	21	122.5
EZ401U	98	118.5	167.0	91.0	22	76.5
EZ402U	98	143.5	192.0	91.0	22	101.5
EZ404U	98	193.5	242.0	91.0	22	151.5
EZ501U	115	112.0	166.5	100.0	22	77.5
EZ502U	115	137.0	191.5	100.0	22	102.5
EZ503U	115	162.0	216.5	100.0	22	127.5
EZ505U	115	212.0	266.5	100.0	22	177.5
EZ701U	145	125.0	184.0	115.0	22	87.0
EZ702U	145	150.0	209.0	115.0	22	112.0
EZ703U	145	175.0	234.0	115.0	22	137.0
EZ705U	145	230.0	289.0	134.0	22	188.0
EZ813U	190	273.5	350.5	156.5	22	219.5
EZ815U	190	355.5	432.5	156.5	22	301.5

Dimensions of geared motors

Type	EZ3			EZ4			EZ5			EZ7			EZ8		
	a	m	n	a	m	n	a	m	n	a	m	n	a	m	n
K102	□72	124	36.0	□98	124	36.0	□115	128	36.0	□145	130	36.0	-	-	-
K513	-	-	-	-	-	-	Ø160	172	15.0	□145	174	15.0	□190	177	15.0
K514	-	-	-	-	-	-	Ø160	215	15.0	-	-	-	-	-	-
K613	-	-	-	-	-	-	Ø160	191	18.0	Ø200	193	18.0	□190	196	18.0
K614	-	-	-	-	-	-	Ø160	234	18.0	-	-	-	-	-	-
K713	-	-	-	-	-	-	-	-	-	Ø200	221	20.0	□190	224	20.0
K714	-	-	-	-	-	-	Ø160	263	20.0	Ø200	283	20.0	-	-	-
K813	-	-	-	-	-	-	-	-	-	Ø200	247	24.0	Ø250	249	24.0
K814	-	-	-	-	-	-	-	-	-	Ø200	308	24.0	Ø250	320	5.0
K913	-	-	-	-	-	-	-	-	-	-	-	-	Ø250	294	25.0
K914	-	-	-	-	-	-	-	-	-	Ø200	353	25.0	Ø250	365	25.0
K1014	-	-	-	-	-	-	-	-	-	-	-	-	Ø250	450	28.0

16.3.17 Oil expansion tank



Dimensions

Type	EZ5			EZ7			EZ8		
	dab	hab	lab	dab	hab	lab	dab	hab	lab
K513	65	122.0	113.5	65	122.0	113.5	65	170.0	163.5
K613	65	148.5	116.5	65	148.5	116.5	65	150.5	111.5
K713	-	-	-	65	170.0	114.5	65	170.0	112.0
K813	-	-	-	73	205.0	129.5	73	205.0	129.5
K913	-	-	-	-	-	-	73	255.0	129.5

More information can be found in Chapter [▶ 16.6.4](#)

16.4 Type designation

This chapter shows you an explanation of the type designation with the associated options.

Additional ordering information not included in the type designation can be found at the end of the chapter.

Example code

K	4	0	2	A	G	0560	EZ501U
---	---	---	---	---	---	------	--------

Explanation

Code	Designation	Design
K	Type	Helical bevel gearbox
4	Size	4 (example)
0	Generation	Generation 0
1		Generation 1
2	Stages	Two-stage
3		Three-stage
4		Four-stage
A	Shaft	Hollow shaft with keyway
S		Hollow shaft with shrink ring
V		Solid shaft
G	Housing	Pitch circle diameter
F		Round flange
NG		Foot + pitch circle diameter
NF		Foot + round flange
GD		Pitch circle diameter + torque arm bracket
NGD		Foot + pitch circle diameter + torque arm bracket
0560	Transmission ratio (i x 10 rounded)	i = 55.71 (example)
EZ501U	Motor	EZ synchronous servo motor

To complete the type designation, also specify the following in your order:

- A detailed type designation of the motor, see the chapter [▶ 17.5](#)
- Mounting position, see the chapter [▶ 16.5.5](#)
- Attachment of solid shaft: gearbox side 3 or 4; solid shaft on both sides
- Attachment of hollow shaft with keyway: entry side 3 or 4
- Attachment of hollow shaft with shrink ring: shrink ring on gearbox side 3 or 4
- Attachment of foot plates: gearbox side 1 or 5 (for K1, also on gear side 2)
- Attachment of flange: gearbox side 3 or 4
- Pitch circle diameter: gearbox side 3 or 4
- Attachment of torque arm bracket: torque arm bracket on gearbox side 1 or 5 (for K1, also on gearbox side 2), eye on gearbox side 3 or 4
- Position of the plug connectors, see the chapter [▶ 16.5.7](#)
- Oil expansion tank (option, recommended for gearboxes in mounting position EL5), see the chapter [▶ 16.6.4](#)
- Backlash: Standard/class II/class I. Backlash class II and class I for an additional charge.

For an explanation of the gearbox sides, see the chapter [▶ 16.5.5](#).

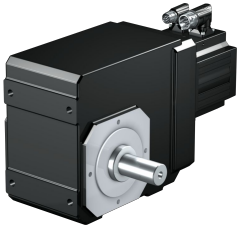
To make selecting your geared motor easy, use our STOBBER Configurator at <https://configurator.stoerber.de/en-US/>.

You can find a detailed description of the nameplate in the chapter [▶ 17.5.1](#).

16.5 Product description

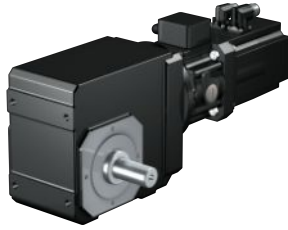
16.5.1 Input options

EZ synchronous servo motor



Catalog ID 442437_en

MB motor adapter +
EZ synchronous servo motor



Catalog ID 443311_en

LM Lean motor

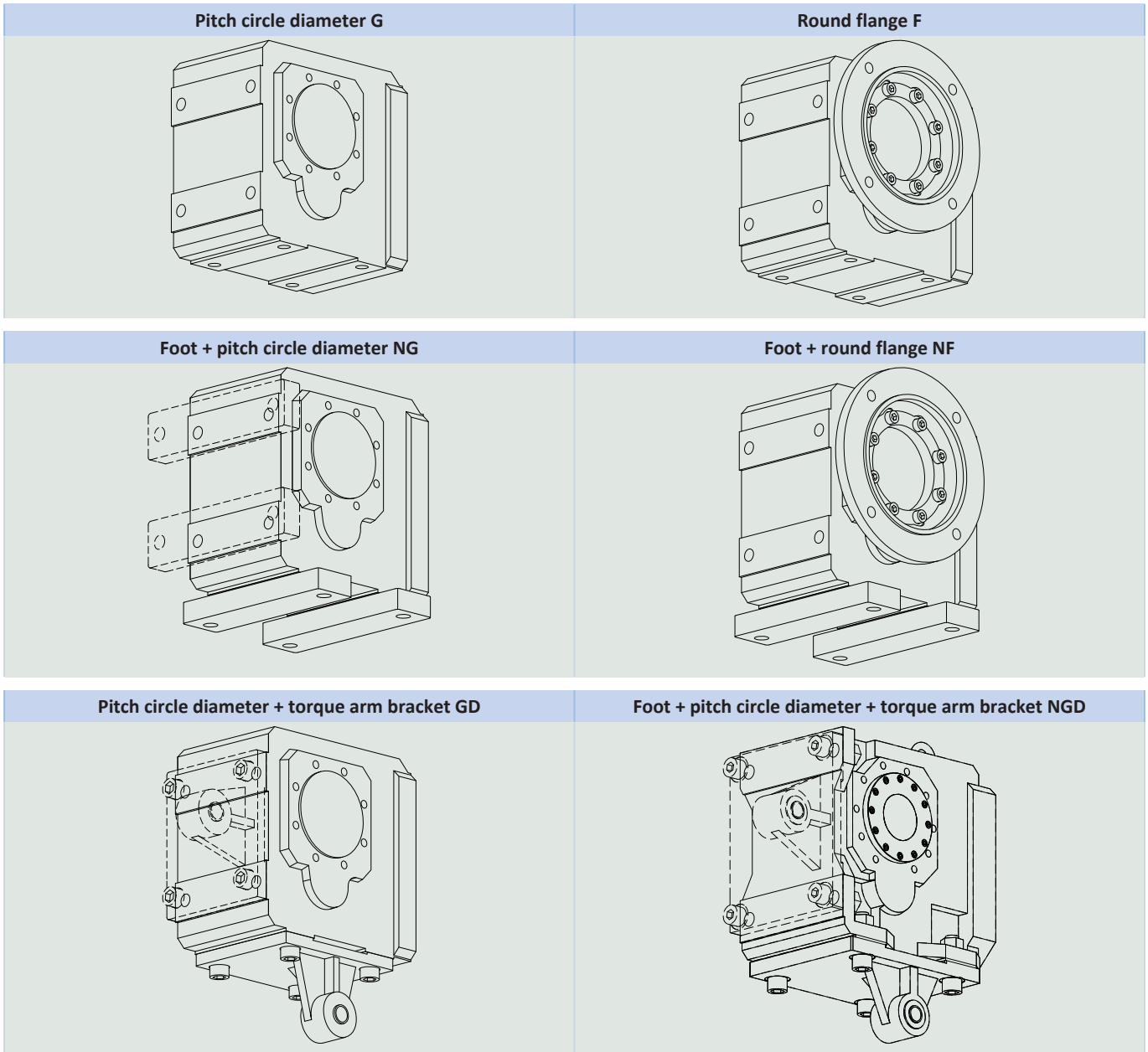


Catalog ID 443016_en

The corresponding catalogs can be found at <http://www.stoeber.de/en/downloads/>

Enter the ID of the catalog in the Search term field.

16.5.2 Housing design



	G	F	NG	NF	GD	NGD
K1	✓	✓	✓	✓	✓	-
K2	✓	✓	✓	-	✓	-
K3	✓	✓	✓	-	✓	-
K4	✓	✓	✓	-	✓	-
K5	✓	✓	✓	✓	✓	-
K6	✓	✓	✓	✓	✓	-
K7	✓	✓	✓	✓	✓	-
K8	✓	✓	✓	✓	✓	-
K9	✓	✓	✓	✓	✓	-
K10	-	-	✓	✓	-	✓

16.5.3 Combinatorial shaft/housing design

Shaft design	Housing design						
	Code	G	F	NG	NF	GD	NGD
Hollow shaft with keyway	A	AG	AF	ANG	ANF	AGD	ANGD
Hollow shaft with shrink ring	S	SG	SF	SNG	SNF	SGD	SNGD
Solid shaft ¹⁾	V	VG	VF	VNG	VNF	–	–

¹⁾ Gearboxes in sizes K1 – K10 come with a solid shaft with feather key as standard. Gearboxes in sizes K1 – K4 can be ordered with the option of a solid shaft without feather key. Only upon request starting at size K5.

16.5.4 Installation conditions

Hollow shaft

The hollow shaft hole tolerance is ISO H7. The tolerance of the machine shaft must be ISO k6.

Take care to align the machine shaft with the gearbox hollow shaft when attaching the gearbox.

Maximum deviation ≤ 0.03 mm.

For simpler assembly and disassembly of the machine shaft, the hollow shafts are equipped with a spiral groove (as a grease deposit).

A hardened, threaded keeper plate is included in the scope of delivery. You also have the option to order the hollow shaft without a keeper plate.

Hollow shaft with shrink ring

The tolerance of the hollow shaft hole is ISO H7.

The machine shaft must be executed as follows:

Gearbox type	Tolerance
K1 to K6	ISO h9
K7 to K10	ISO h6

Select a material for the machine shaft with a permitted surface pressure of $p \geq 325$ N/mm².

Possible materials:

- C45E +QT
- 42CrMo4

Fastening the gearboxes on the machine side using the pitch circle diameter

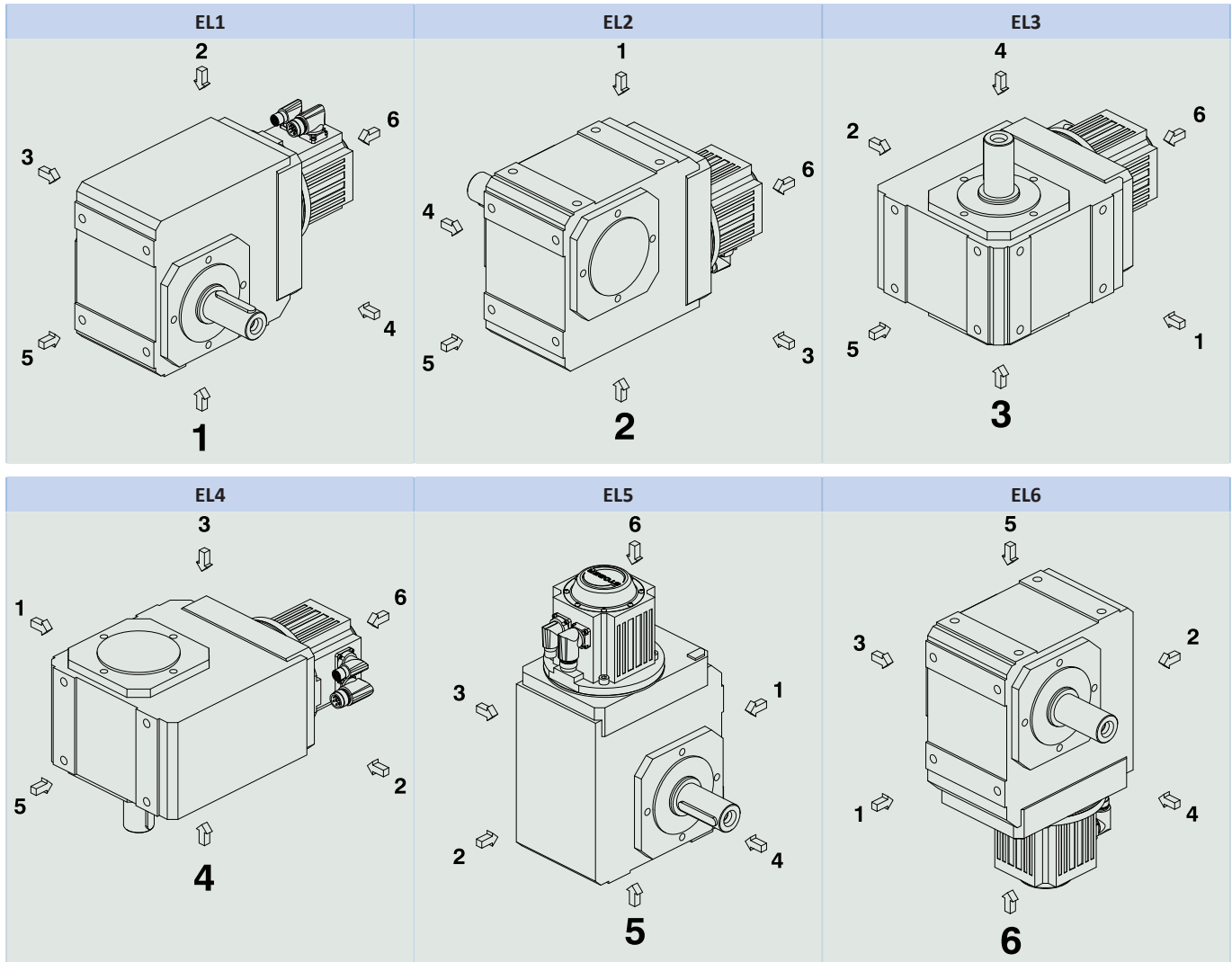
The specified torques and forces only apply when gearboxes are fastened on the machine side using screws of strength class 10.9. In addition, the gear housings must be adjusted at the pilot. The machine-side fit must be H7.

16.5.5 Mounting positions

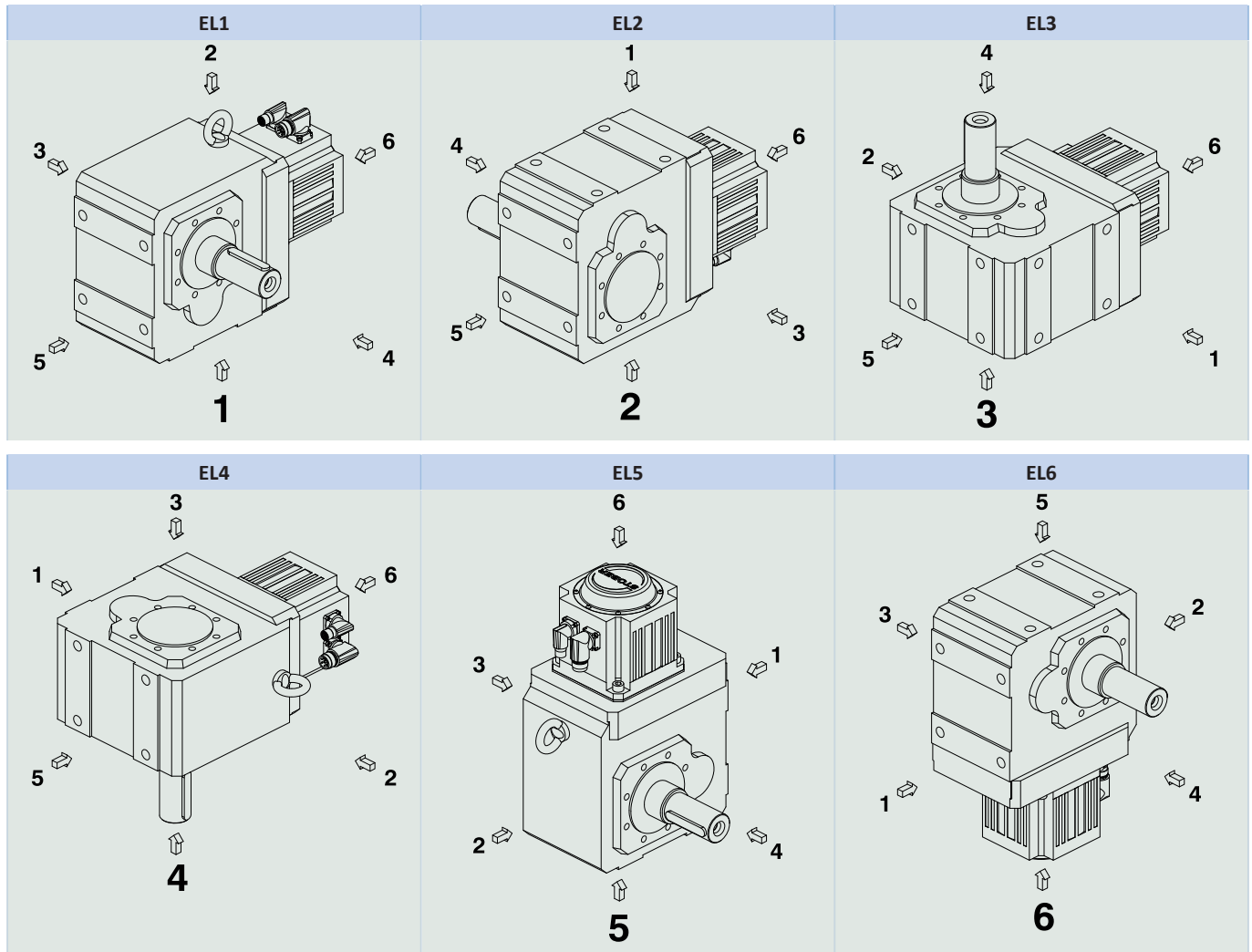
The following table shows the standard mounting positions.

The numbers identify the gearbox sides. The mounting position is defined by the gearbox side facing downwards.

Mounting positions for gearbox sizes K1 – K4



Mounting positions for gearbox sizes K5 – K10



Since the lubricant filling volume of the gearbox depends on the mounting position, the mounting position must be specified when ordering.

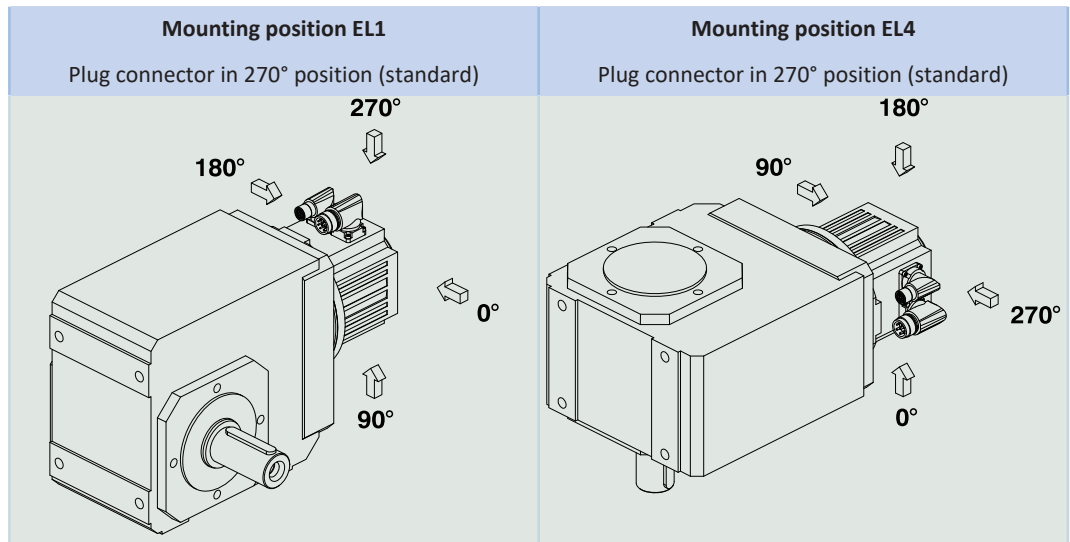
16.5.6 Lubricants

STOBER fills the gearboxes with the amount and type of lubricant specified on the nameplate. The filling volume and the structure of the gearboxes depend on the mounting position.

Only install the gearboxes in the intended mounting position! Reposition the gearboxes only after consulting STOBER. Otherwise, STOBER assumes no liability for the gearboxes.

You will receive lubricants for use in the food industry upon request.

16.5.7 Position of the plug connectors



Indicate variations for your geared motor in the order.

Note that the plug connector position rotates along with the geared motor if the geared motor is in another mounting position.

16.5.8 Other product features

Feature	Value
Max. permitted gearbox temperature (on the surface of the gearbox)	≤ 80 °C
Paint	Black RAL 9005
Explosion-proof design in accordance with (ATEX) Directive 2014/34/EU (optional)	Not available
Efficiency:	
η_{get} two-stage	97%
η_{get} three-stage	96%
η_{get} four-stage	94%
Protection class:¹	
Gearbox	IP65
Motor	IP56, optionally IP66

16.5.9 Maintenance

The instructions for maintenance can be found in the operating manual, ID 443364_en, at <http://www.stoeber.de/en/downloads/>. Enter the ID of the documentation in the Search... field.

Ventilation

Air release valves are fitted as a standard feature and independently of installation position for gearbox sizes K5 to K10.

For the position and dimensions of the air release valve, refer to the 3D model.

Download the 3D model at <https://configurator.stoeber.de/en-US/>.

¹ Observe the protection class of all the components.

16.5.10 Direction of rotation

Solid shaft (V), solid shaft on both sides (V), hollow shaft with keyway (A)

Type	Output side 4	Output side 3
K102 – K402		
K203 – K403		
K513 – K1013		
K514 – K1014		

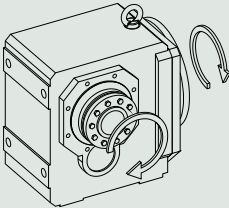
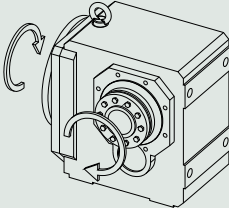
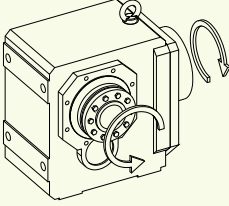
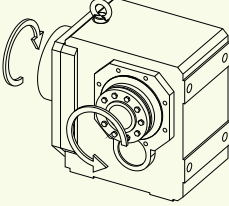
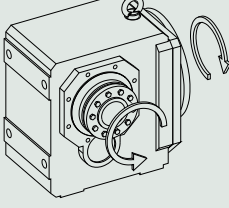
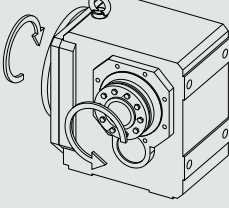
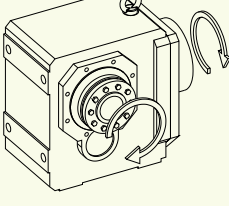
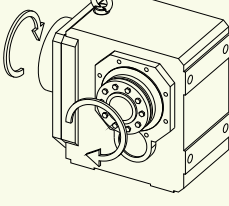
The specified directions of rotation also apply to gearboxes with hollow shaft (A) if the entry side of the machine shaft corresponds to the side of the solid shaft that is shown.

The direction of rotation for the shaft design of a solid shaft on both sides corresponds to the direction of rotation for output side 4.

The pictures show mounting position EL1.

Hollow shaft with shrink ring (S)

Type	Shrink ring side 4	Shrink ring side 3
K102 – K402		
K203 – K403		

Type	Shrink ring side 4	Shrink ring side 3
K513 – K813		
K514 – K814		
K913 – K1013		
K914 – K1014		

The pictures show mounting position EL1.

16.6 Project configuration

Project your drives using our SERVOSOFT designing software. Download SERVOSOFT free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

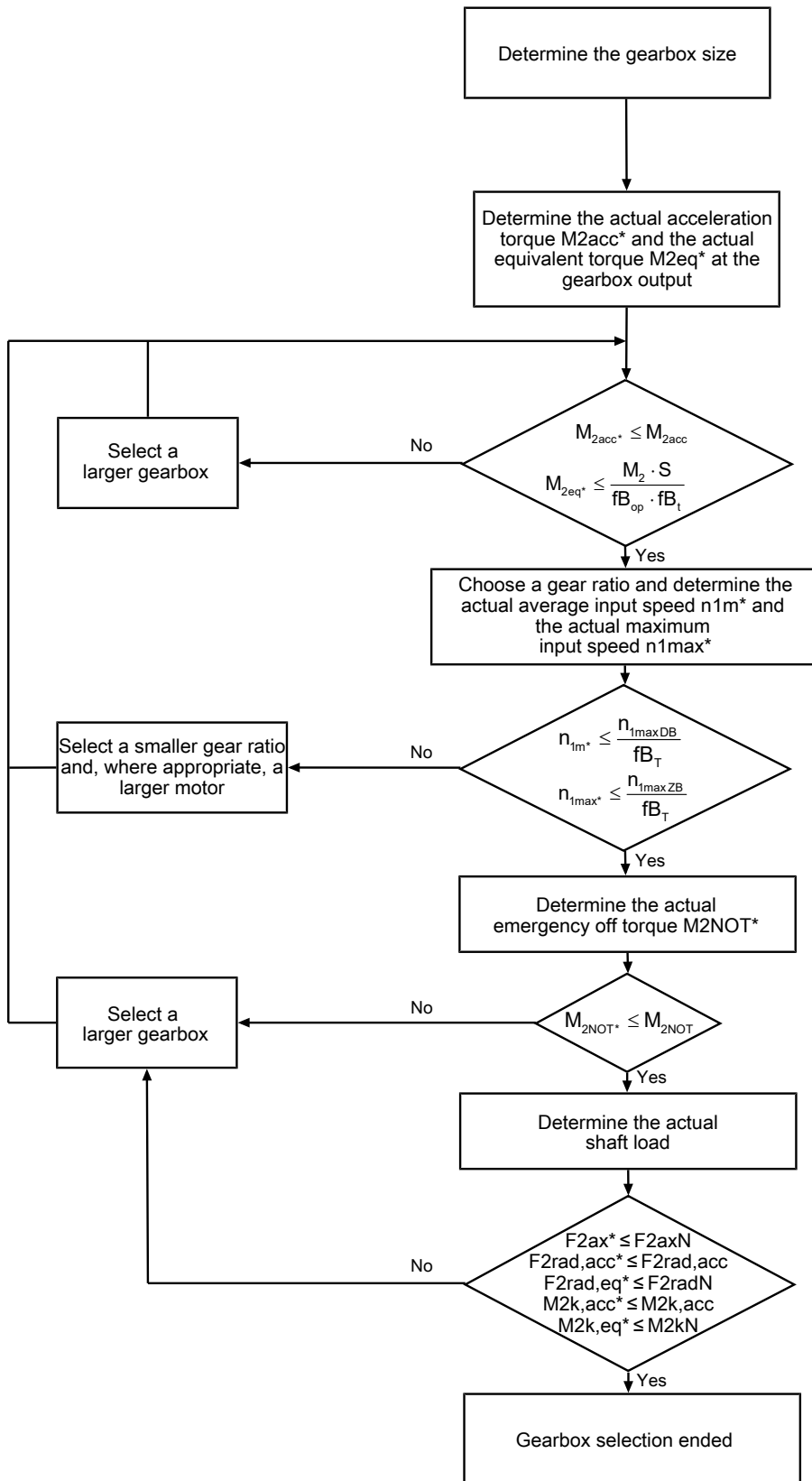
In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

16.6.1 Drive selection

Drive selection for gearboxes

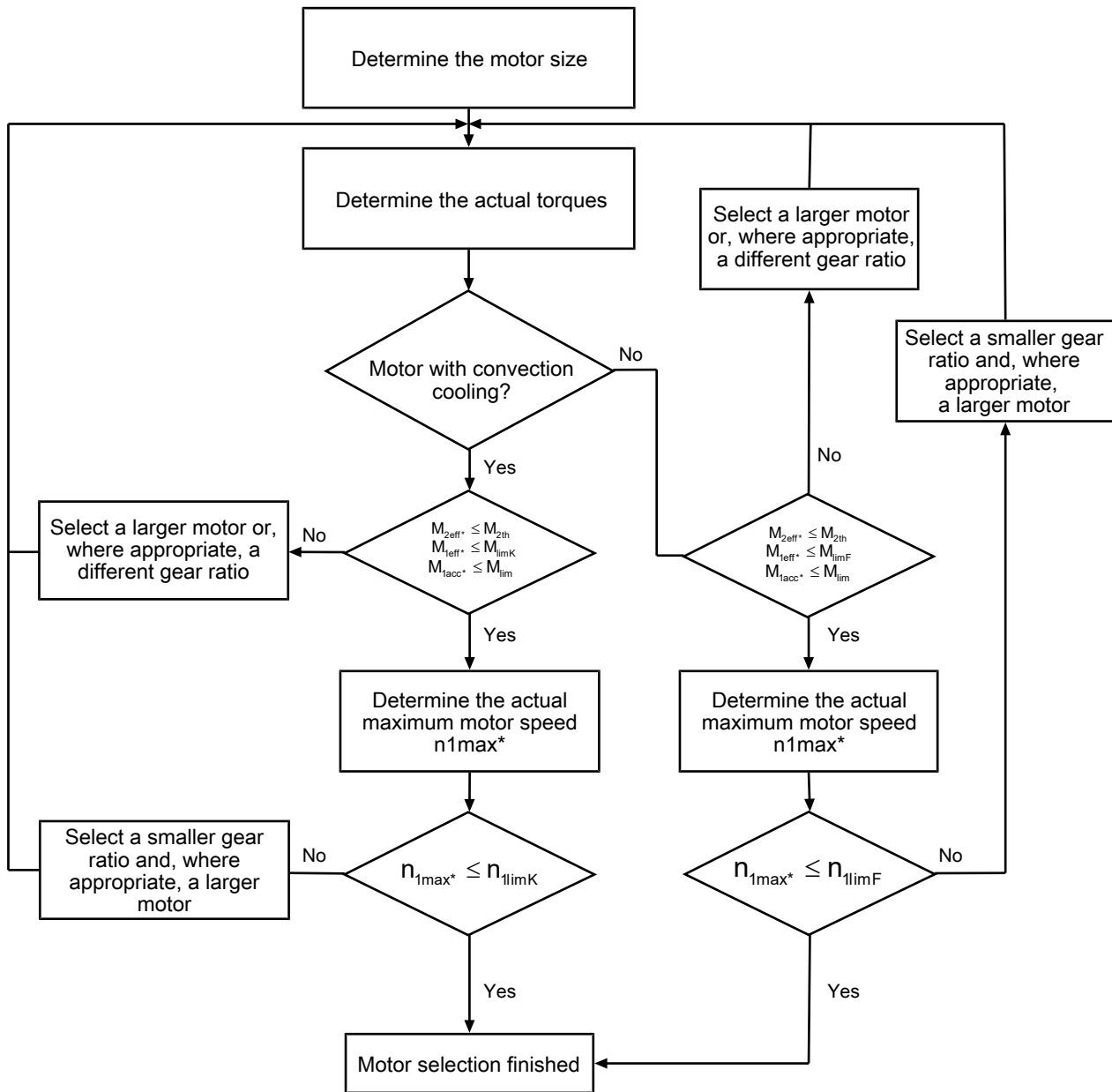


Calculate the forces and tilting torques in the chapter Permitted shaft loads.

Refer to the selection tables for the values for i , n_{1maxDB} , n_{1maxZB} , M_{2acc} , M_{2NOT} , M_2 and S .

The values for fb_T , fb_{op} and fb_t can be found in the corresponding tables in this chapter.

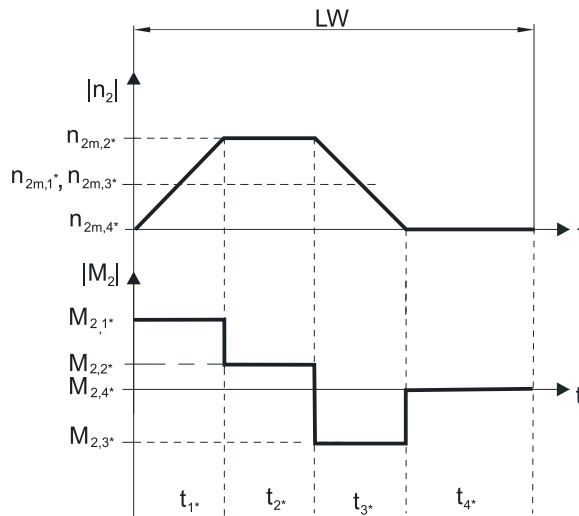
Drive selection for motors



The value for M_{lim} , M_{limK} , M_{limF} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations are based on a representation of the power taken from the output based in accordance with the following example:


Calculation of the actual maximum acceleration torques

$$M_{2acc*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

$$M_{1acc*} = \frac{M_{2acc*}}{i \cdot \eta_{get}} + J_1 \cdot \frac{\Delta n_1}{9,55 \cdot \Delta t}$$

Calculation of the actual average input speed

$$n_{1m*} = n_{2m*} \cdot i$$

$$n_{2m*} = \frac{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}{t_{1*} + \dots + t_{n*}}$$

If $t_{1*} + \dots + t_{3*} \geq 6$ min, calculate n_{2m*} without the rest phase t_{4*} .

The values for the ratio i can be found in the selection tables.

Calculation of the actual effective torque

$$M_{2eff*} = \sqrt{\frac{t_{1*} \cdot M_{2,1*}^2 + \dots + t_{n*} \cdot M_{2,n*}^2}{t_{1*} + \dots + t_{n*}}}$$

Calculation of the actual emergency off torque

$$M_{2NOT*} = J_{tot} \cdot \frac{\Delta n_2}{9,55 \cdot \Delta t} + M_{L*}$$

Calculation of the actual equivalent torque

$$M_{2eq*} = \sqrt[3]{\frac{|n_{2m,1*}| \cdot t_{1*} \cdot M_{2,1*}^3 + \dots + |n_{2m,n*}| \cdot t_{n*} \cdot M_{2,n*}^3}{|n_{2m,1*}| \cdot t_{1*} + \dots + |n_{2m,n*}| \cdot t_{n*}}}$$

Calculation of the thermal limit torque

Calculate the thermal limit torque M_{2th} for a duty cycle $ED_{10} > 50\%$ and the actual average input speed n_{1m*} . (At $K_{mot,th} \leq 0$ you must reduce the average input speed n_{1m*} accordingly or select another geared motor size.)

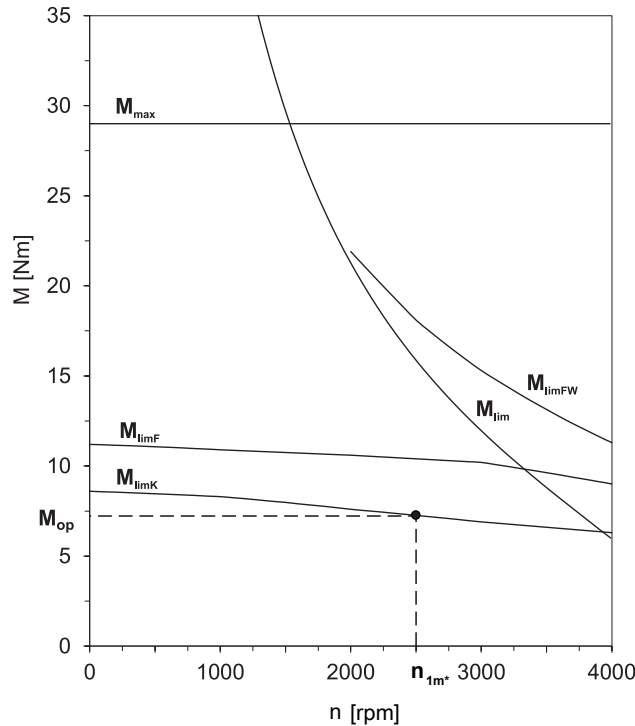
$$M_{2th} = M_{op} \cdot i \cdot K_{mot,th}$$

$$K_{mot,th} = 0,95 - \frac{a_{th}}{1000} \cdot athEL \cdot fB_T \cdot \left(\frac{n_{1m*}}{1000} \right)^2$$

The values for i and a_{th} can be found in the selection tables.

The values for a_{thEL} and fB_T can be found in the corresponding tables in this chapter.

The value for the torque of the motor at operating point M_{op} with the determined average input speed n_{1m^*} can be found in the motor characteristic curve in the chapter [▶ 17.3]. Note the size, nominal speed n_N and cooling type of the motor. The figure below shows an example of reading the torque M_{op} of a motor with convection cooling at the operating point.



Operating factors

Parameter a_{thEL}

Mounting position		a_{thEL}
EL1, 2		1.0
EL3, 4, 5, 6		1.1

Operating mode		fB_{op}
Uniform continuous operation		1.00
Cyclic operation		1.25
Reversing load cyclic operation		1.40

Run time		fB_t
Daily runtime ≤ 8 h		1.00
Daily runtime ≤ 16 h		1.15
Daily runtime ≤ 24 h		1.20

Temperature		fB_T
Motor cooling	Surrounding temperature	
Motor with forced ventilation	≤ 20 °C	0.9
	≤ 30 °C	1.0
	≤ 40 °C	1.15
Motor with convection cooling	≤ 20 °C	1.0
	≤ 30 °C	1.1
	≤ 40 °C	1.25

Notes

- The maximum permitted gearbox temperature (see the "Other product features" chapter) must not be exceeded. Doing so may result in damage to the geared motor.
- For braking from full speed (for example when the power fails or when setting up the machine), note the permitted gearbox torques (M_{2acc} , M_{2NOT}) in the selection tables.

16.6.2 Permitted shaft loads for the output shaft

The values specified in the tables apply to the permitted shaft loads:

- For shaft dimensions in accordance with the catalog
- For output speeds $n_{2m^*} \leq 20$ rpm ($F_{2axN} = F_{2ax20}$; $F_{2radN} = F_{2rad20}$; $M_{2kN} = M_{2k20}$)
- Only if radial forces on the gearbox are stabilized by its pilots for the pitch circle diameter and flange housing design

16.6.2.1 V shaft design

Permitted shaft loads for V shaft design (solid shaft)

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
K1	40.0	1900	5000	5000	325	325
K2	42.0	2100	6000	6000	430	430
K3	45.0	2400	7000	7000	525	525
K4	52.0	3500	11200	11200	1050	1050
K5	72.0	3500	13450	13450	1580	1580
K6	72.0	4000	16000	16000	1960	1960
K7	85.0	5500	22000	22000	3200	3200
K8	60.0	7250	29000	29000	3800	3800
K9	87.0	16500	65000	65000	11200	11200
K10	84.0	25000	80000	80000	15200	15200

Reduced values apply in the case of a V shaft design (solid shaft) in conjunction with an NF housing design (foot + round flange):

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
K10	132.0	25000	64000	64000	15200	15200

For the V solid shaft design on both sides, the values for F_{2rad20} and M_{2k20} must be multiplied by a factor of 0.7.

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 20$ rpm:

$$F_{2axN} = \frac{F_{2ax20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

The values for F_{2ax20} , F_{2rad20} and M_{2k20} can be found in the table "Permitted shaft loads" in this chapter.

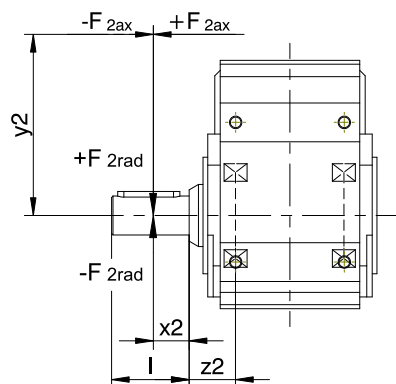


Fig. 1: Force application points for solid shaft

The specified values for F_{2rad20} and $F_{2rad,acc}$ refer to an application of force at the center of the output shaft: $x_2 = l/2$.

Shaft dimensions can be found in the "Dimensional drawings" chapter.

The following applies to other force application points:

$$M_{2k,acc^*} = \frac{2 \cdot F_{2ax^*} \cdot y_2 + F_{2rad,acc^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |M_{2k,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |M_{2k,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

$$F_{2rad,eq^*} = \sqrt[3]{\frac{|n_{2m,1^*}| \cdot t_{1^*} \cdot |F_{2rad,acc,1^*}|^3 + \dots + |n_{2m,n^*}| \cdot t_{n^*} \cdot |F_{2rad,acc,n^*}|^3}{|n_{2m,1^*}| \cdot t_{1^*} + \dots + |n_{2m,n^*}| \cdot t_{n^*}}}$$

16.6.2.2 A and S shaft design

Permitted shaft loads for A shaft design (hollow shaft with keyway)

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
K1	40.0	1900	5000	5000	240	240
K2	42.0	2100	6000	6000	310	310
K3	45.0	2400	7000	7000	380	380
K4	52.0	3500	11200	11200	740	740
K5	39.0	2500	13450	13450	1000	1000
K6	42.0	3000	16000	16000	1300	1300
K7	45.0	4100	22000	22000	2100	2100
K8	50.0	5300	29000	29000	2600	2600
K9	56.0	7000	65000	65000	3600	3600
K10	56.0	9000	80000	80000	5000	5000

Permitted shaft loads for S shaft design (hollow shaft with shrink ring)

Type	z_2 [mm]	F_{2ax20} [N]	F_{2rad20} [N]	$F_{2rad,acc}$ [N]	M_{2k20} [Nm]	$M_{2k,acc}$ [Nm]
K1	40.0	1900	5000	5000	240	240
K2	42.0	2100	6000	6000	310	310
K3	45.0	2400	7000	7000	380	380
K4	52.0	3500	11200	11200	740	740
K5	39.0	2500	13450	13450	1000	1000
K6	42.0	3000	16000	16000	1300	1300
K7	45.0	4100	22000	22000	2100	2100
K8	50.0	5300	29000	29000	2600	2600
K9	56.0	7000	65000	65000	3600	3600
K10	56.0	9000	80000	80000	5000	5000

For other output speeds, download diagrams at <https://configurator.stoeber.de/en-US/>.

The following applies to output speeds $n_{2m^*} > 20$ rpm:

$$F_{2axN} = \frac{F_{2ax20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

$$F_{2radN} = \frac{F_{2rad20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

$$M_{2kN} = \frac{M_{2k20}}{\sqrt[3]{\frac{n_{2m^*}}{20 \text{ rpm}}}}$$

The values for F_{2ax20} , F_{2rad20} and M_{2k20} can be found in the table "Permitted shaft loads" in this chapter.

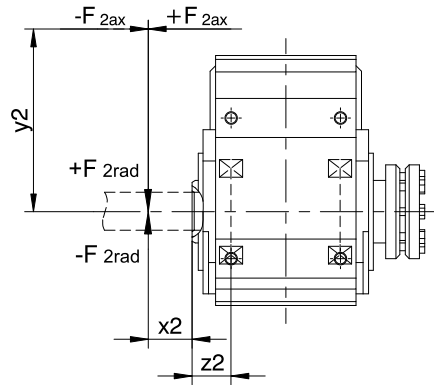


Fig. 2: Force application points for hollow shaft

You can determine the permitted radial forces from the permitted tilting torque M_{2kN} and $M_{2k,acc}$. The actual radial forces may not exceed the permitted radial forces. The permitted radial forces pertain to the shaft end ($x_2 = 0$).

$$M_{2k,acc} = \frac{2 \cdot F_{2ax} \cdot y_2 + F_{2rad,acc} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

In the event of EMERGENCY OFF operation (max. 1000 load changes), you can multiply the permitted forces and torques for F_{2ax20} , F_{2rad20} and M_{2k20} by a factor of two.

Also note the calculation for equivalent values:

$$M_{2k,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_1 \cdot |M_{2k,acc,1}|^3 + \dots + |n_{2m,n}| \cdot t_n \cdot |M_{2k,acc,n}|^3}{|n_{2m,1}| \cdot t_1 + \dots + |n_{2m,n}| \cdot t_n}}$$

$$F_{2rad,eq} = \sqrt[3]{\frac{|n_{2m,1}| \cdot t_1 \cdot |F_{2rad,acc,1}|^3 + \dots + |n_{2m,n}| \cdot t_n \cdot |F_{2rad,acc,n}|^3}{|n_{2m,1}| \cdot t_1 + \dots + |n_{2m,n}| \cdot t_n}}$$

16.6.3 Radial shaft seal rings

Leak-proofness

Our gearboxes are equipped with high-quality radial shaft seal rings and checked for leaks. However, a leak cannot be fully ruled out over the length of use of a gearbox. If you use a gearbox with goods incompatible with the lubricant, you must take measures to prevent direct contact with the gearbox lubricant in case of a leak.

16.6.4 Oil expansion tank

The gearboxes have a higher fill level in mounting position EL5. The oil expansion tank prevents oil from escaping out of the gearbox.

Notes

- We recommend using an oil expansion tank in mounting position EL5 (additional cost) for fast running gearboxes with an input speed $n_1 > 1750$ rpm and gear ratios $i < 20$.
- It is not possible to use an oil expansion tank if the plug connector is at 90°!
- The oil expansion tank can only be used with certain sizes; see the chapter [▶ 16.3.17](#)

16.7 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

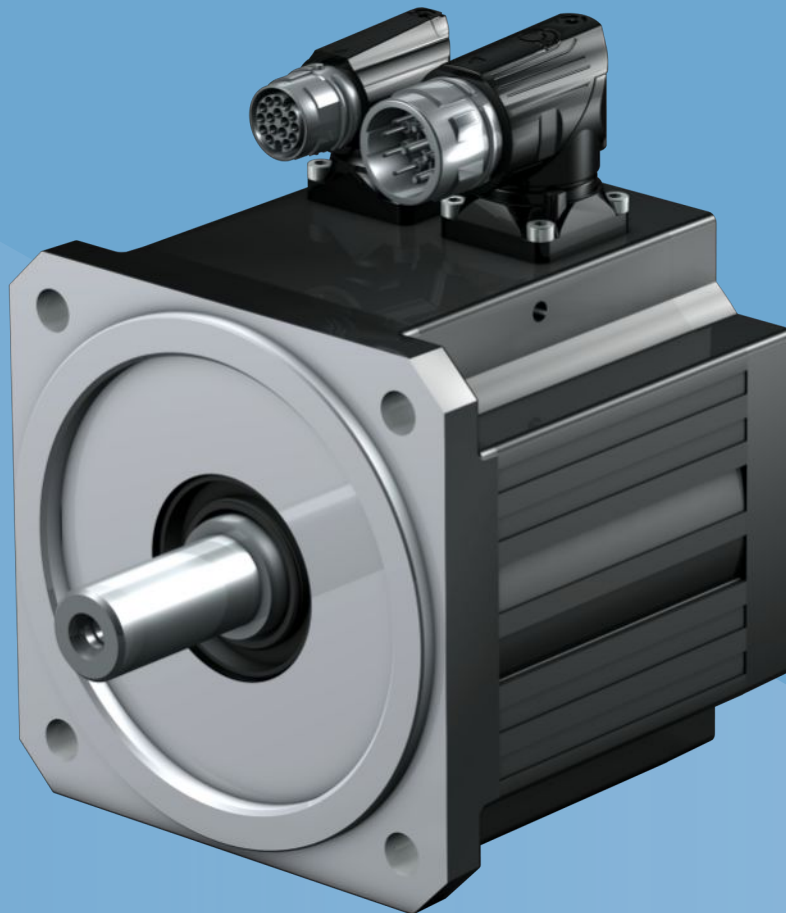
Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual gearboxes, geared motors K	443364_en
Operating manual for EZ synchronous servo motors	443032_en

17 EZ synchronous servo motors

Table of contents

17.1 Overview	560
17.2 Selection tables	561
17.2.1 EZ motors with convection cooling	562
17.2.2 EZ motors with forced ventilation	563
17.3 Torque/speed curves	564
17.4 Dimensional drawings	574
17.4.1 EZ2 – EZ3 motors with convection cooling (One Cable Solution)	574
17.4.2 EZ2 – EZ3 motors with convection cooling	575
17.4.3 EZ4 – EZ7 motors with convection cooling (One Cable Solution)	576
17.4.4 EZ4 – EZ8 motors with convection cooling	577
17.4.5 EZ4 – EZ7 motors with forced ventilation (One Cable Solution)	578
17.4.6 EZ4 – EZ8 motors with forced ventilation	579
17.5 Type designation	580
17.5.1 Nameplate	581
17.6 Product description	582
17.6.1 General features	582
17.6.2 Electrical features	582
17.6.3 Ambient conditions	582
17.6.4 Encoders	583
17.6.5 Temperature sensor	585
17.6.6 Cooling	587
17.6.7 Holding brake	588
17.6.8 Connection method	590
17.7 Project configuration	596
17.7.1 Drive selection	597
17.7.2 Permitted shaft loads	598
17.7.3 Derating	600
17.8 Further information	601
17.8.1 Directives and standards	601
17.8.2 Identifiers and test symbols	601
17.8.3 Additional documentation	601



17 Synchronous servo motors

EZ

17.1 Overview

Synchronous servo motors with tooth winding

Features

- High dynamics ✓
- Short length ✓
- Super compact due to tooth-coil winding method with the highest possible copper fill factor ✓
- Backlash-free holding brake (optional) ✓
- Electronic nameplate for fast and reliable commissioning ✓
- Convection cooling or forced ventilation (optional) ✓
- Optical, inductive EnDat absolute encoders or resolvers ✓
- Elimination of referencing with multi-turn absolute encoders (optional) ✓
- One Cable Solution (OCS) with EnDat 3 encoder (optional) ✓
- Rotatable plug connectors¹ with quick-lock ✓

¹The plug connectors can be pivoted up to 10 times at a specific angle. They cannot be rotated repeatedly.

Torques

M_N	0.4 – 91 Nm
M_0	0.44 – 100 Nm

17.2 Selection tables

The technical data specified in the selection tables applies to:

- Installation altitudes up to 1000 m above sea level
- Surrounding temperatures from -15 °C to $+40\text{ °C}$
- Operation on a STOBBER drive controller
- DC link voltage $U_{zk} = \text{DC } 540\text{ V}$
- Coating: RAL 9005 Jet black, matte

In addition, the technical data applies to an uninsulated design with the following thermal mounting conditions:

Type	Dimensions of steel mounting flange (thickness x width x height)	Convection surface area Steel mounting flange
EZ2 – EZ5	23 x 210 x 275 mm	0.14 m ²
EZ7 – EZ8	28 x 300 x 400 mm	0.3 m ²

Note the differing ambient conditions in Chapter [▶ 17.7.3](#)

Formula symbols

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

Observe the additional information on the following formula symbols:

- I_0 = RMS value of the line-to-line current when stall torque M_0 is generated (tolerance $\pm 5\%$).
- I_{\max} = RMS value of the short-term maximum permitted line-to-line current when maximum torque M_{\max} is generated (tolerance $\pm 5\%$). Exceeding I_{\max} may lead to irreversible damage (demagnetization) of the rotor.
- I_N = RMS value of the line-to-line current when nominal torque M_N is generated at the nominal point (tolerance $\pm 5\%$).
- M_0 = Torque that a motor is continuously able to deliver at a speed of 10 rpm (tolerance $\pm 5\%$). At a speed of 0 rpm, a minor continuous torque has to be taken into account. Contact your STOBBER customer advisor for such an application.

17.2.1 EZ motors with convection cooling

Type	K_{EM} [V/1000 min ⁻¹]	n_N [rpm]	M_N [Nm]	I_N [A]	$K_{M,N}$ [Nm/A]	P_N [kW]	M_0 [Nm]	I_0 [A]	K_{M0} [Nm/A]	M_R [Nm]	M_{max} [Nm]	I_{max} [A]	R_{U-V} [Ω]	L_{U-V} [mH]	T_{el} [ms]	J_{dyn} [kgcm ²]	m_{dyn} [kg]
EZ202U	40	6000	0.40	0.99	0.41	0.25	0.44	1.03	0.45	0.03	1.48	3.48	26.00	15.80	0.61	0.13	1.43
EZ203U	40	6000	0.61	1.54	0.40	0.38	0.69	1.64	0.44	0.03	2.70	5.80	13.20	10.30	0.76	0.17	1.67
EZ301U	40	6000	0.89	1.93	0.46	0.56	0.95	2.02	0.49	0.04	2.80	12.7	11.70	39.80	3.40	0.19	1.50
EZ301U	40	3000	0.93	1.99	0.47	0.29	0.95	2.02	0.49	0.04	2.80	12.7	11.70	39.80	3.40	0.19	1.50
EZ302U	42	6000	1.50	3.18	0.47	0.94	1.68	3.48	0.49	0.04	5.00	17.8	4.50	18.70	4.16	0.29	2.10
EZ302U	86	3000	1.59	1.60	0.99	0.50	1.68	1.67	1.03	0.04	5.00	8.55	17.80	75.00	4.21	0.29	2.10
EZ303U	55	6000	1.96	3.17	0.62	1.2	2.25	3.55	0.65	0.04	7.00	16.9	4.90	21.10	4.31	0.40	2.60
EZ303U	109	3000	2.07	1.63	1.27	0.65	2.19	1.71	1.30	0.04	7.00	8.25	20.30	68.70	5.24	0.40	2.60
EZ401U	47	6000	2.30	4.56	0.50	1.4	2.80	5.36	0.53	0.04	8.50	33.0	1.94	11.52	5.94	0.93	4.00
EZ401U	96	3000	2.80	2.74	1.02	0.88	3.00	2.88	1.06	0.04	8.50	16.5	6.70	37.70	5.63	0.93	4.00
EZ402U	60	6000	3.50	5.65	0.62	2.2	4.90	7.43	0.66	0.04	16.0	43.5	1.20	8.88	7.40	1.63	5.10
EZ402U	94	3000	4.70	4.40	1.07	1.5	5.20	4.80	1.09	0.04	16.0	26.5	3.00	21.80	7.26	1.63	5.10
EZ404U	78	6000	5.80	7.18	0.81	3.6	8.40	9.78	0.86	0.04	29.0	51.0	0.89	7.07	7.94	2.98	7.20
EZ404U	116	3000	6.90	5.80	1.19	2.2	8.60	6.60	1.31	0.04	29.0	35.0	1.85	15.00	8.11	2.98	7.20
EZ501U	68	6000	3.40	4.77	0.71	2.1	4.40	5.80	0.77	0.06	16.0	31.0	2.10	12.10	5.76	2.90	5.00
EZ501U	97	3000	4.30	3.74	1.15	1.4	4.70	4.00	1.19	0.06	16.0	22.0	3.80	23.50	6.18	2.90	5.00
EZ502U	72	6000	5.20	7.35	0.71	3.3	7.80	9.80	0.80	0.06	31.0	59.0	0.76	5.60	7.37	5.20	6.50
EZ502U	121	3000	7.40	5.46	1.36	2.3	8.00	5.76	1.40	0.06	31.0	33.0	2.32	16.80	7.24	5.20	6.50
EZ503U	84	6000	6.20	7.64	0.81	3.9	10.6	11.6	0.92	0.06	43.0	63.5	0.62	5.00	8.06	7.58	8.00
EZ503U	119	3000	9.70	6.90	1.41	3.1	11.1	7.67	1.46	0.06	43.0	41.0	1.25	10.00	8.00	7.58	8.00
EZ505U	103	4500	9.50	8.94	1.06	4.5	15.3	13.4	1.15	0.06	67.0	73.0	0.50	4.47	8.94	12.2	10.9
EZ505U	141	3000	13.5	8.80	1.53	4.2	16.0	10.0	1.61	0.06	67.0	52.0	0.93	8.33	8.96	12.2	10.9
EZ701U	76	6000	5.20	6.68	0.78	3.3	7.90	9.38	0.87	0.24	20.0	31.0	0.87	8.13	9.34	8.50	8.30
EZ701U	95	3000	7.40	7.20	1.03	2.3	8.30	8.00	1.07	0.24	20.0	25.0	1.30	12.83	9.87	8.50	8.30
EZ702U	82	6000	7.20	8.96	0.80	4.5	14.3	16.5	0.88	0.24	41.0	60.5	0.34	3.90	11.47	13.7	10.8
EZ702U	133	3000	12.0	8.20	1.46	3.8	14.4	9.60	1.53	0.24	41.0	36.0	1.00	11.73	11.73	13.7	10.8
EZ703U	99	4500	12.1	11.5	1.05	5.7	20.0	17.8	1.14	0.24	65.0	78.0	0.36	4.42	12.28	21.6	12.8
EZ703U	122	3000	16.5	11.4	1.45	5.2	20.8	14.0	1.50	0.24	65.0	62.0	0.52	6.80	13.08	21.6	12.8
EZ705U	106	4500	16.4	14.8	1.11	7.7	30.0	25.2	1.20	0.24	104	114	0.22	2.76	12.55	34.0	18.3
EZ705U	140	3000	21.3	14.2	1.50	6.7	30.2	19.5	1.56	0.24	104	87.0	0.33	4.80	14.55	34.0	18.3
EZ813U	117	4000	25.2	19.8	1.27	11	43.7	32.8	1.34	0.30	140	130	0.13	1.20	9.09	104	35.8
EZ813U	239	2000	39.0	14.9	2.62	8.1	43.7	16.5	2.67	0.30	140	64.9	0.69	5.10	7.41	104	35.8
EZ815U	117	4000	26.1	20.9	1.25	11	67.1	50.3	1.34	0.30	200	169	0.04	0.72	18.00	167	48.4
EZ815U	239	2000	57.8	21.5	2.68	12	68.8	25.2	2.74	0.30	200	92.4	0.40	3.63	9.08	167	48.4

17.2.2 EZ motors with forced ventilation

Type	K_{EM} [V/1000 min ⁻¹]	n_N [rpm]	M_N [Nm]	I_N [A]	$K_{M,N}$ [Nm/A]	P_N [kW]	M_0 [Nm]	I_0 [A]	K_{M0} [Nm/A]	M_R [Nm]	M_{max} [Nm]	I_{max} [A]	R_{U-V} [Ω]	L_{U-V} [mH]	T_{el} [ms]	J_{dyn} [kgcm ²]	m_{dyn} [kg]
EZ401B	47	6000	2.90	5.62	0.52	1.8	3.50	6.83	0.52	0.04	8.50	33.0	1.94	11.52	5.94	0.93	5.40
EZ401B	96	3000	3.40	3.40	1.00	1.1	3.70	3.60	1.04	0.04	8.50	16.5	6.70	37.70	5.63	0.93	5.40
EZ402B	60	6000	5.10	7.88	0.65	3.2	6.40	9.34	0.69	0.04	16.0	43.5	1.20	8.88	7.40	1.63	6.50
EZ402B	94	3000	5.90	5.50	1.07	1.9	6.30	5.80	1.09	0.04	16.0	26.5	3.00	21.80	7.26	1.63	6.50
EZ404B	78	6000	8.00	9.98	0.80	5.0	10.5	12.0	0.88	0.04	29.0	51.0	0.89	7.07	7.94	2.98	8.60
EZ404B	116	3000	10.2	8.20	1.24	3.2	11.2	8.70	1.29	0.04	29.0	35.0	1.85	15.00	8.11	2.98	8.60
EZ501B	68	6000	4.50	6.70	0.67	2.8	5.70	7.50	0.77	0.06	16.0	31.0	2.10	12.10	5.76	2.90	7.00
EZ501B	97	3000	5.40	4.70	1.15	1.7	5.80	5.00	1.17	0.06	16.0	22.0	3.80	23.50	6.18	2.90	7.00
EZ502B	72	6000	8.20	11.4	0.72	5.2	10.5	13.4	0.79	0.06	31.0	59.0	0.76	5.60	7.37	5.20	8.50
EZ502B	121	3000	10.3	7.80	1.32	3.2	11.2	8.16	1.38	0.06	31.0	33.0	2.32	16.80	7.24	5.20	8.50
EZ503B	84	6000	10.4	13.5	0.77	6.5	14.8	15.9	1.07	0.06	43.0	63.5	0.62	5.00	8.06	7.58	10.0
EZ503B	119	3000	14.4	10.9	1.32	4.5	15.9	11.8	1.35	0.06	43.0	41.0	1.25	10.00	8.00	7.58	10.0
EZ505B	103	4500	16.4	16.4	1.00	7.7	22.0	19.4	1.14	0.06	67.0	73.0	0.50	4.47	8.94	12.2	12.9
EZ505B	141	3000	20.2	13.7	1.47	6.4	23.4	14.7	1.60	0.06	67.0	52.0	0.93	8.33	8.96	12.2	12.9
EZ701B	76	6000	7.50	10.6	0.71	4.7	10.2	12.4	0.84	0.24	20.0	31.0	0.87	8.13	9.34	8.50	11.2
EZ701B	95	3000	9.70	9.50	1.02	3.1	10.5	10.0	1.07	0.24	20.0	25.0	1.30	12.83	9.87	8.50	11.2
EZ702B	82	6000	12.5	16.7	0.75	7.9	19.3	22.1	0.89	0.24	41.0	60.5	0.34	3.90	11.47	13.7	13.7
EZ702B	133	3000	16.6	11.8	1.41	5.2	19.3	12.9	1.51	0.24	41.0	36.0	1.00	11.73	11.73	13.7	13.7
EZ703B	99	4500	19.8	20.3	0.98	9.3	27.2	24.2	1.13	0.24	65.0	78.0	0.36	4.42	12.28	21.6	15.7
EZ703B	122	3000	24.0	18.2	1.32	7.5	28.0	20.0	1.41	0.24	65.0	62.0	0.52	6.80	13.08	21.6	15.7
EZ705B	106	4500	27.7	25.4	1.09	13	39.4	32.8	1.21	0.24	104	114	0.22	2.76	12.55	34.0	21.2
EZ705B	140	3000	33.8	22.9	1.48	11	41.8	26.5	1.59	0.24	104	87.0	0.33	4.80	14.55	34.0	21.2
EZ813B	117	4000	49.5	38.1	1.30	21	62.9	46.6	1.36	0.30	140	130	0.13	1.20	9.09	104	41.8
EZ813B	239	2000	57.3	21.9	2.62	12	61.6	22.9	2.71	0.30	140	64.9	0.69	5.10	7.41	104	41.8
EZ815B	117	4000	73.6	56.2	1.31	31	90.8	65.0	1.40	0.30	200	169	0.04	0.72	18.00	167	54.4
EZ815B	239	2000	91.0	33.7	2.70	19	100	36.3	2.76	0.30	200	92.4	0.40	3.63	9.08	167	54.4

17.3 Torque/speed curves

Torque/speed curves depend on the nominal speed and/or winding design of the motor and the DC link voltage of the drive controller that is used. The following torque/speed curves apply to the DC link voltage DC 540 V.

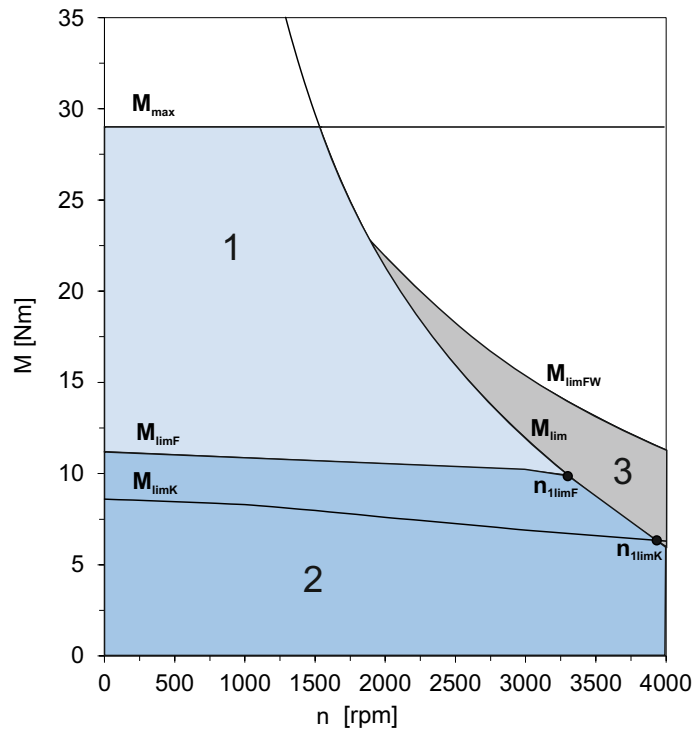
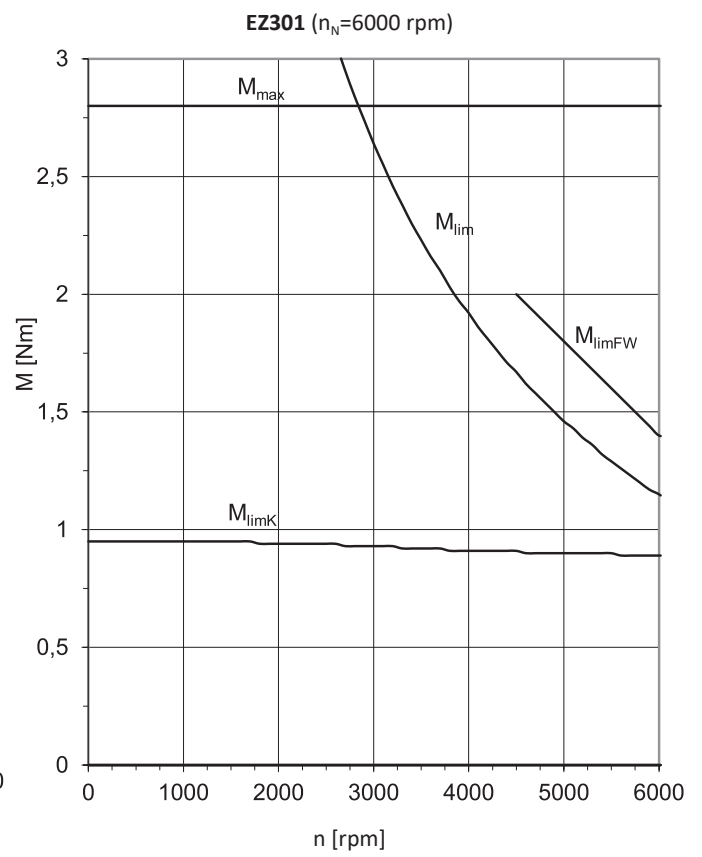
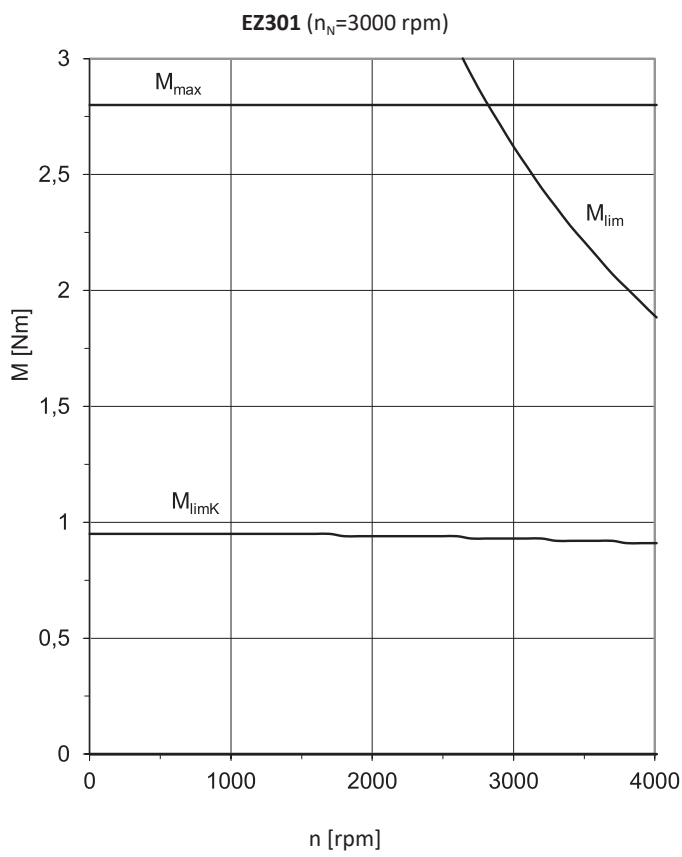
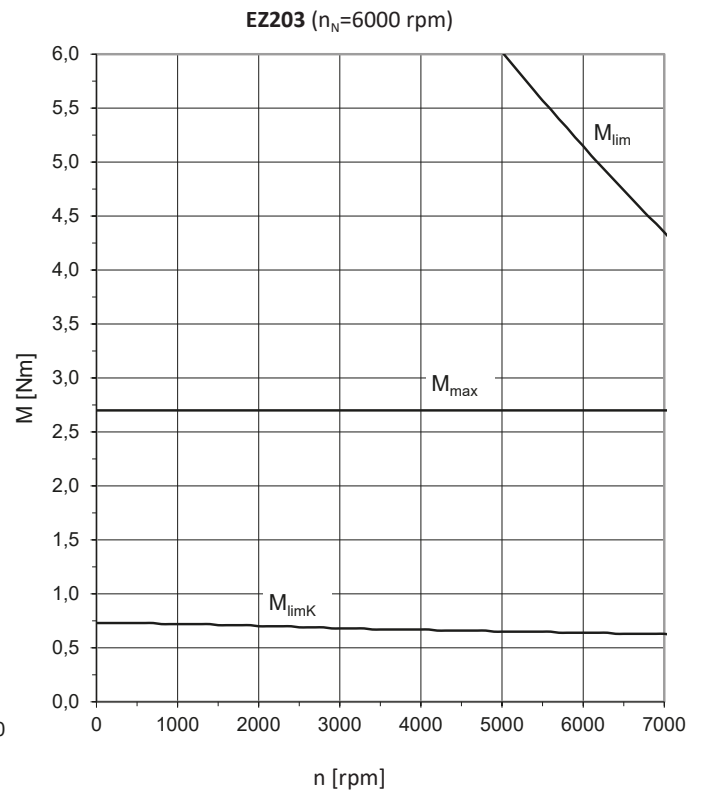
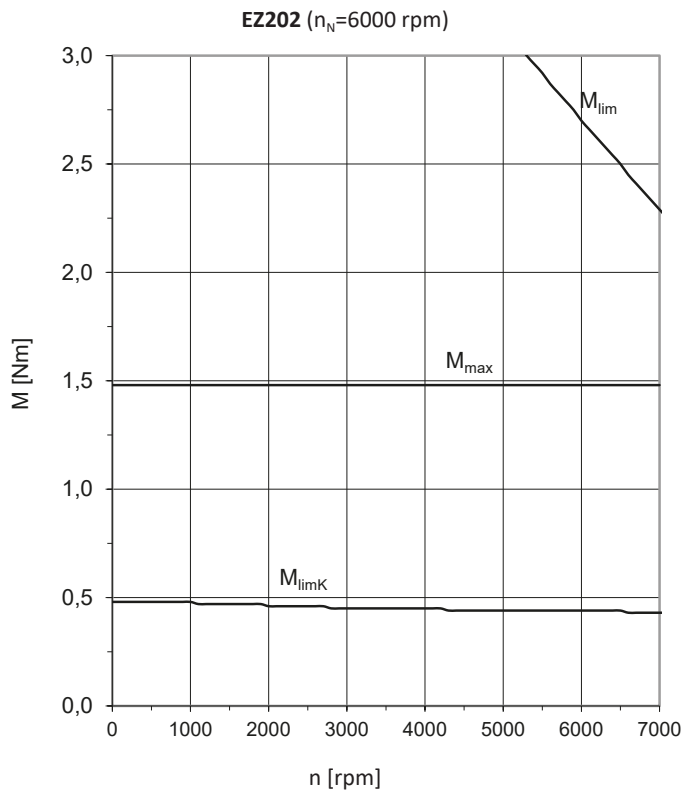
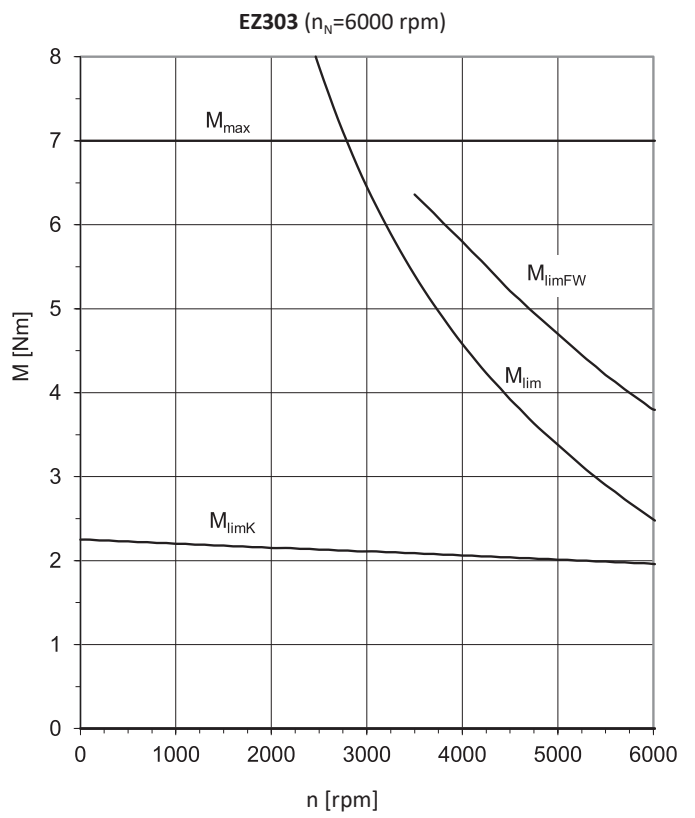
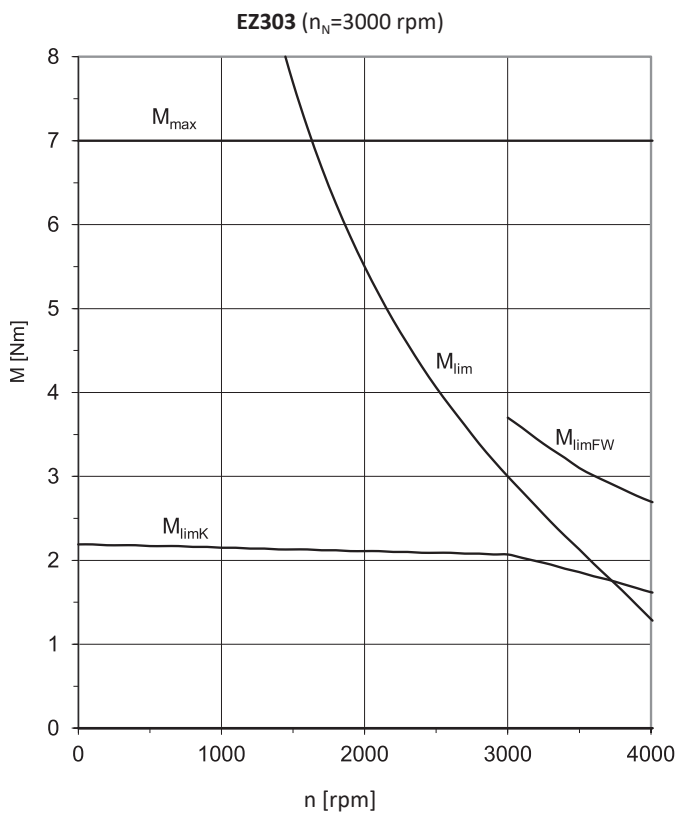
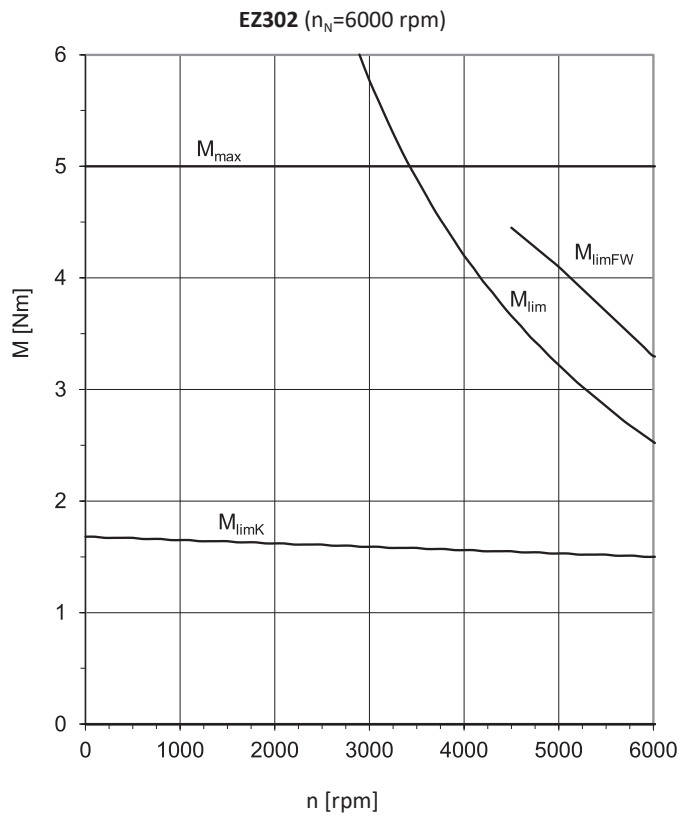
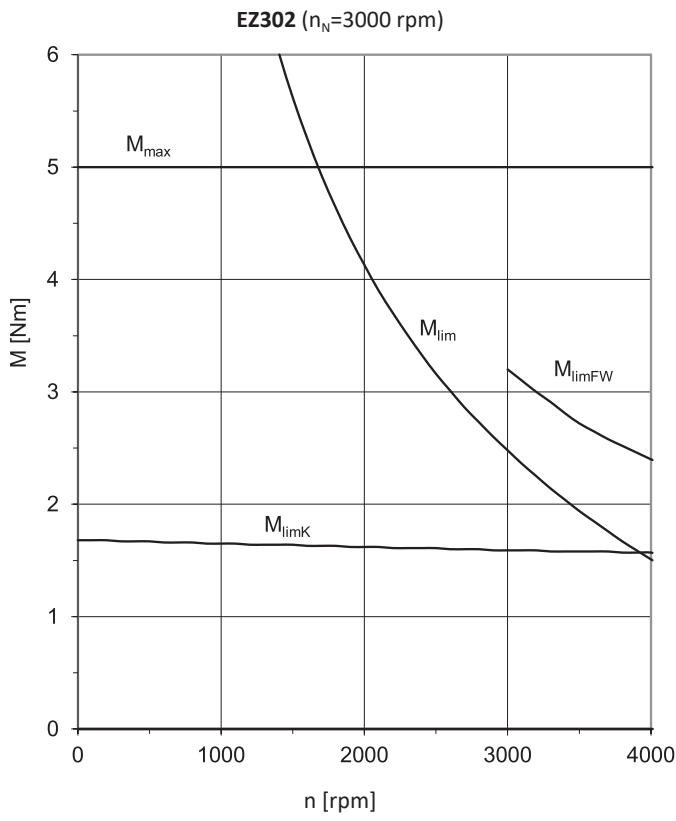


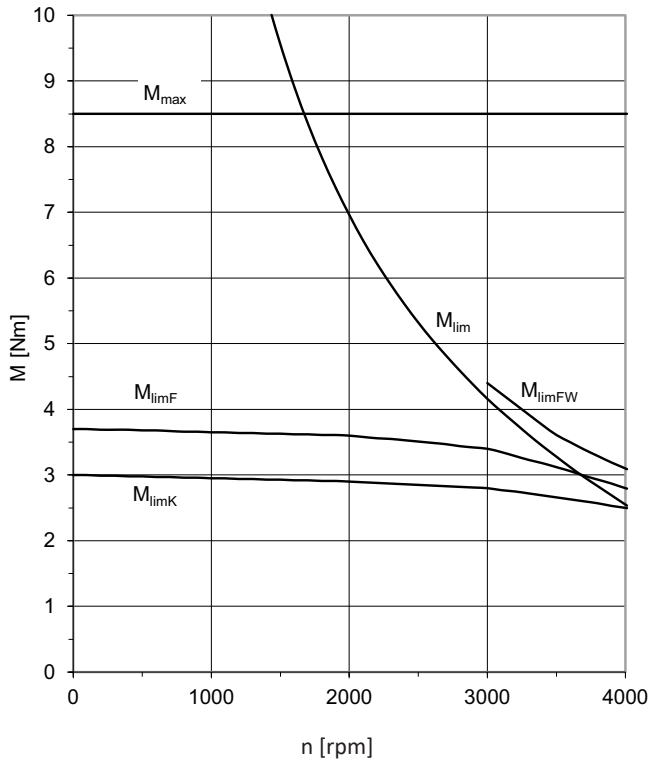
Fig. 1: Explanation of a torque/speed curve

- | | |
|---|---|
| <p>1 Torque range for brief operation ($ED_{10} < 100\%$) with $\Delta\vartheta = 100$ K</p> | <p>2 Torque range for continuous operation with constant load (S1 mode, $ED_{10} = 100\%$) with $\Delta\vartheta = 100$ K</p> |
| <p>3 Field weakening range (can be used only with operation on STOBBER drive controllers)</p> | |

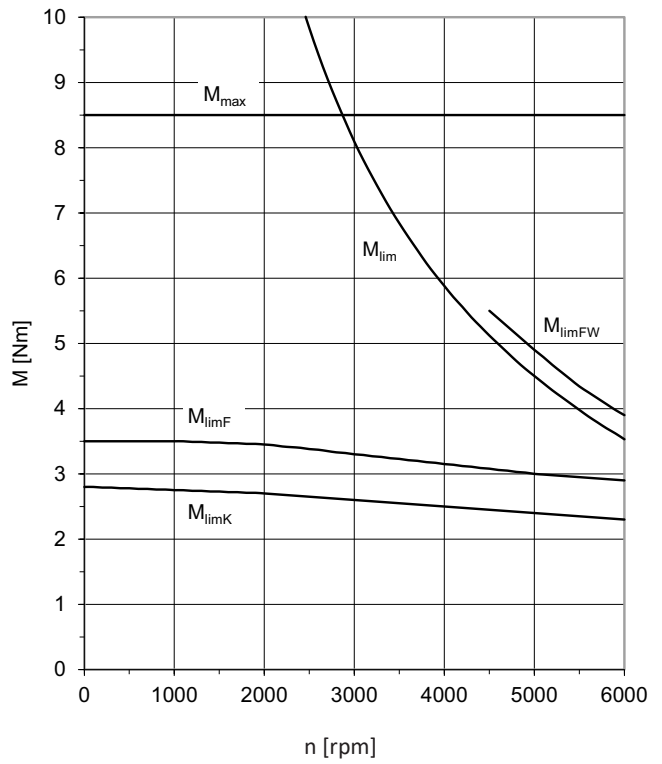




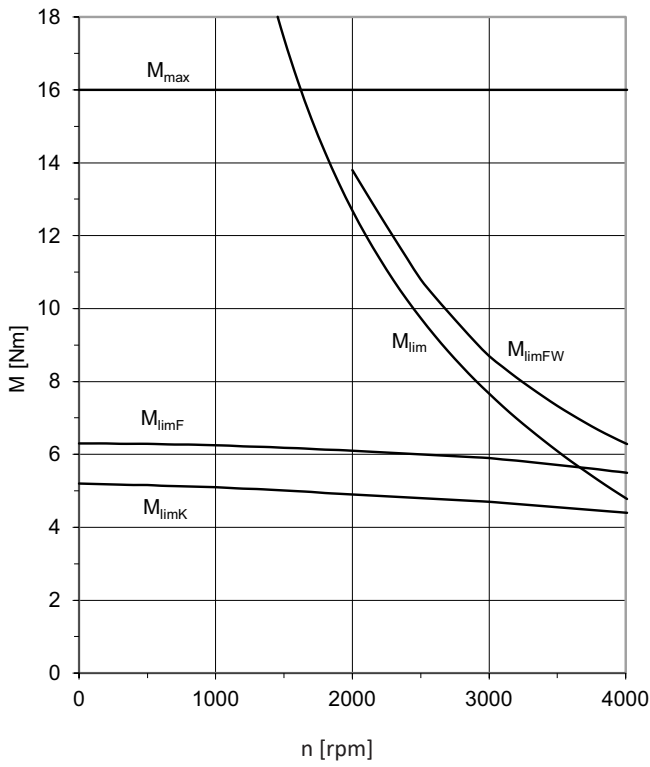
EZ401 ($n_N=3000$ rpm)



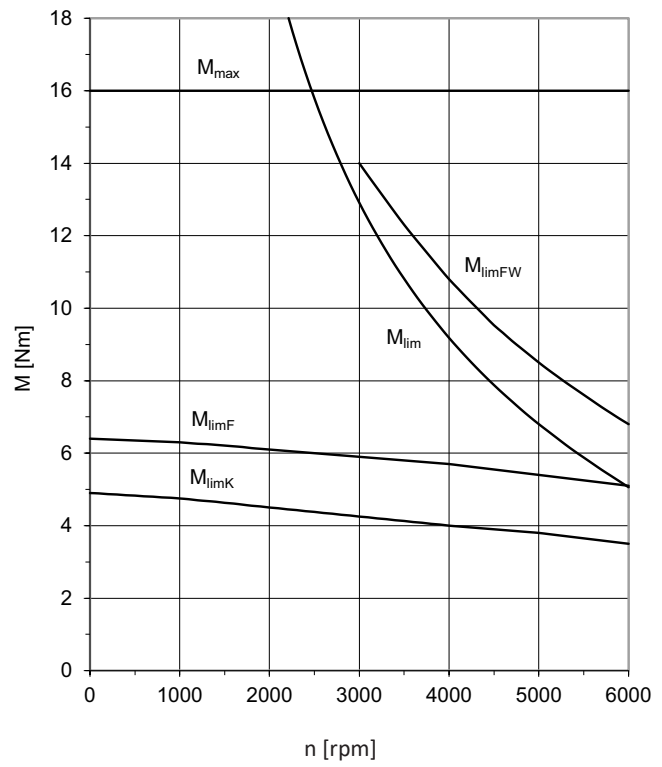
EZ401 ($n_N=6000$ rpm)



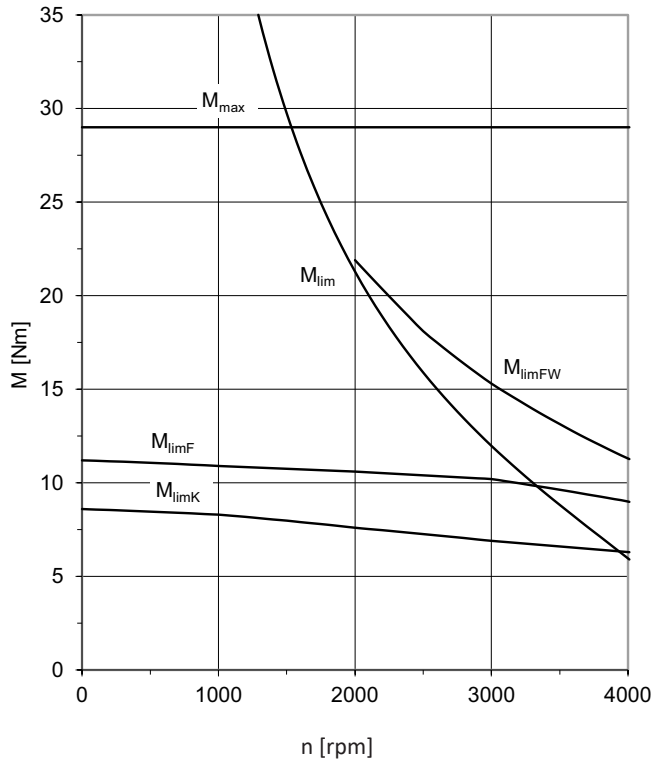
EZ402 ($n_N=3000$ rpm)



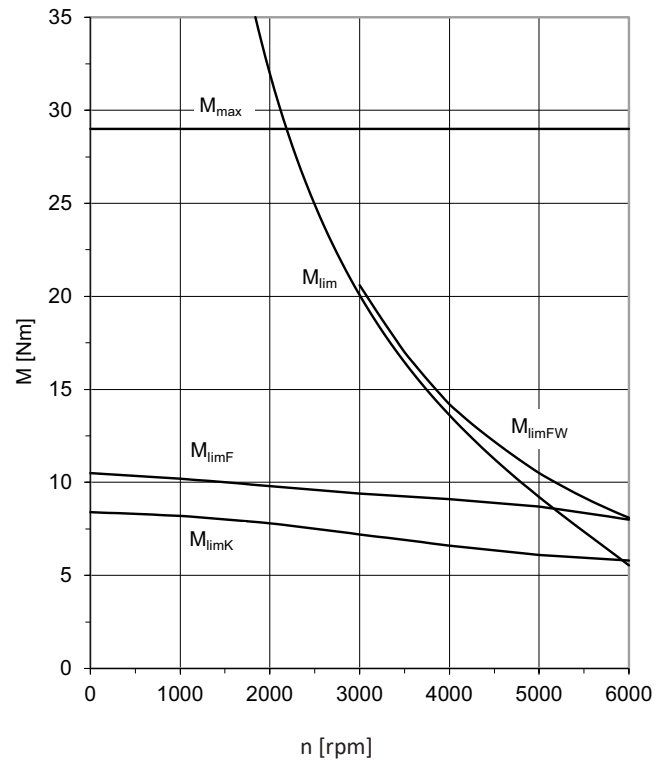
EZ402 ($n_N=6000$ rpm)



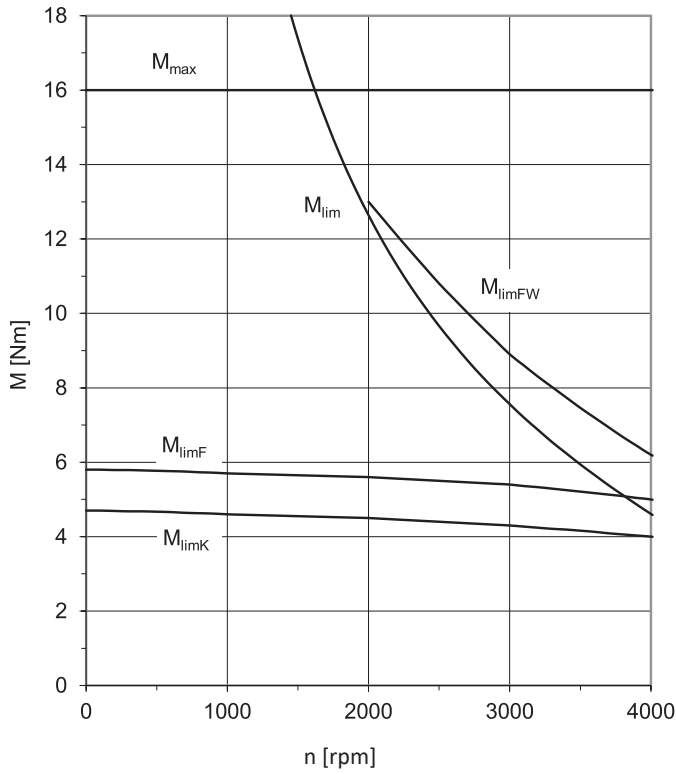
EZ404 ($n_N=3000$ rpm)



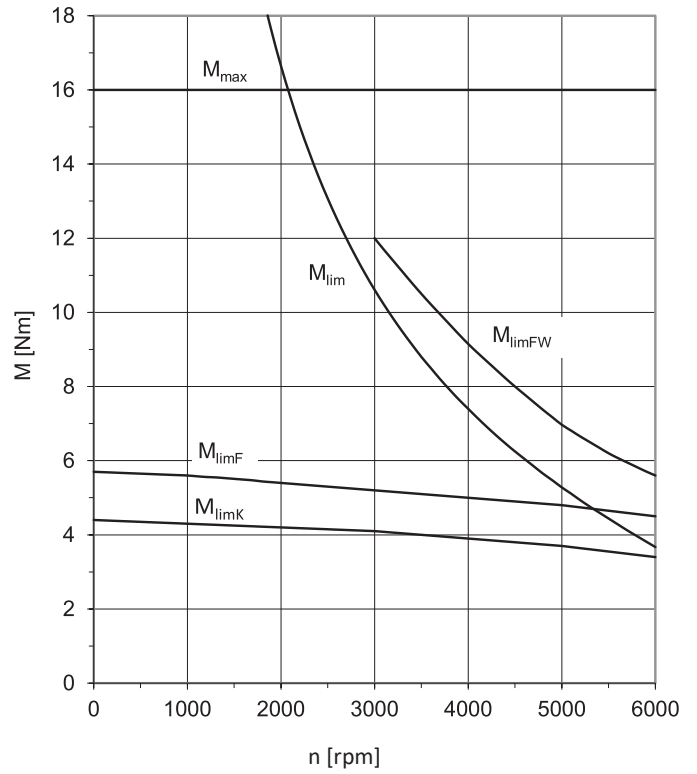
EZ404 ($n_N=6000$ rpm)

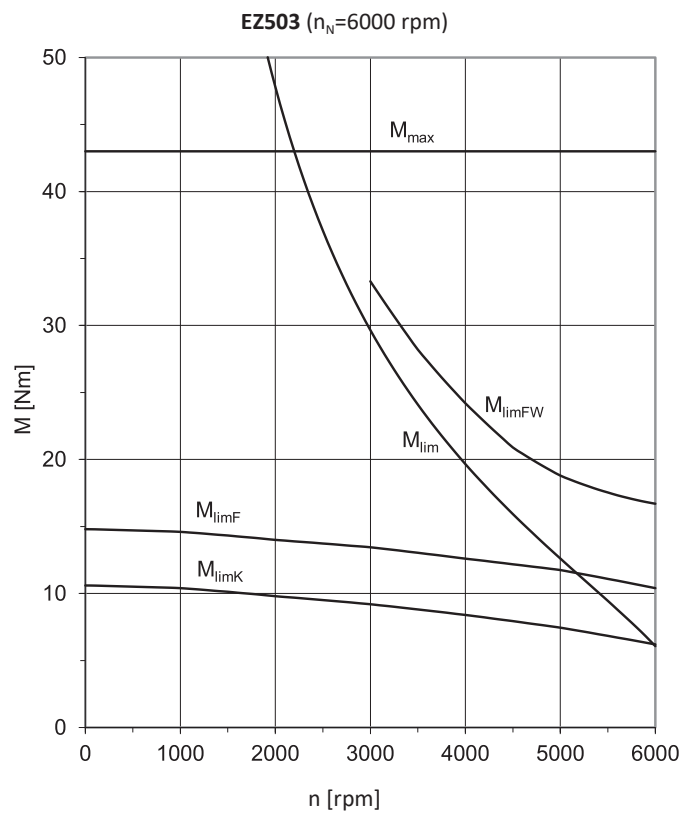
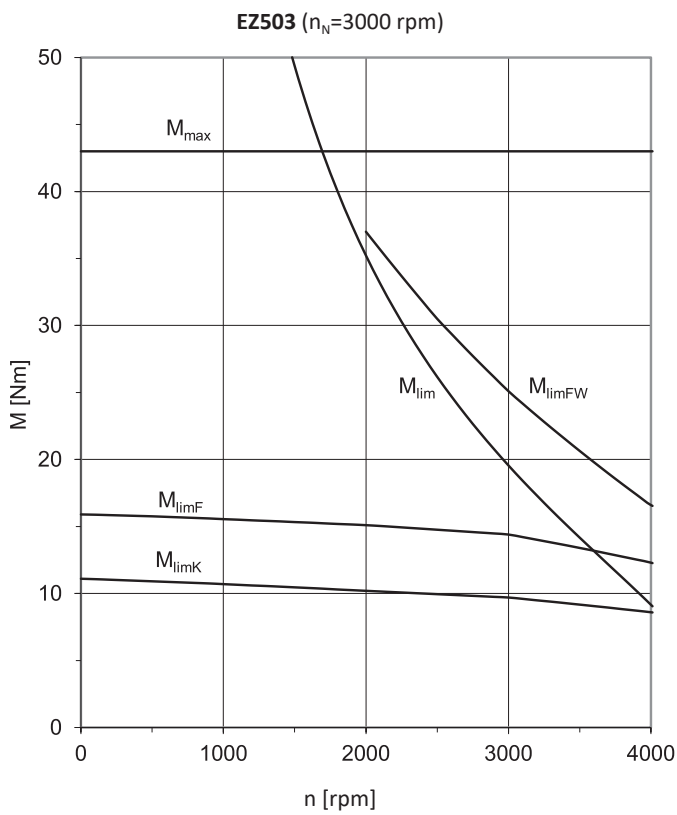
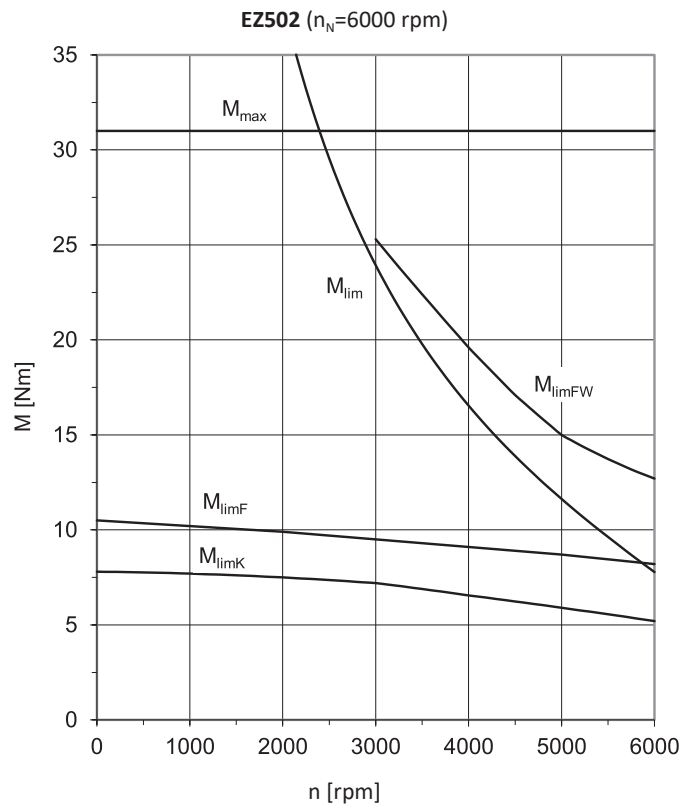
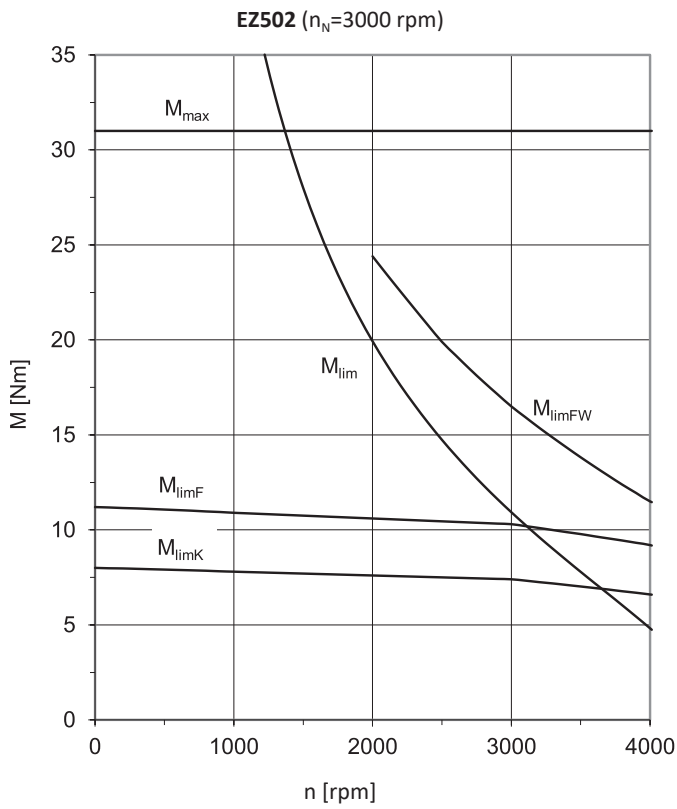


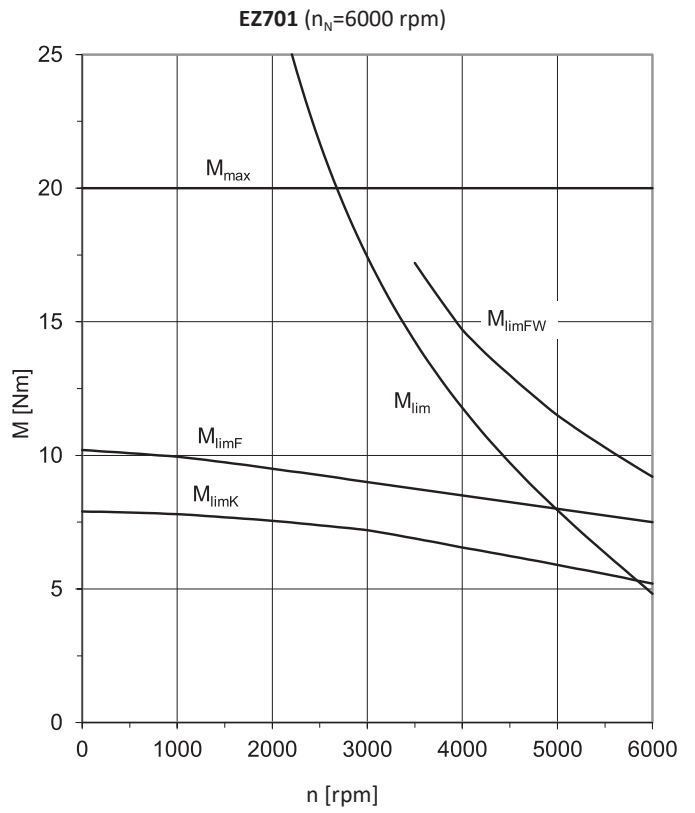
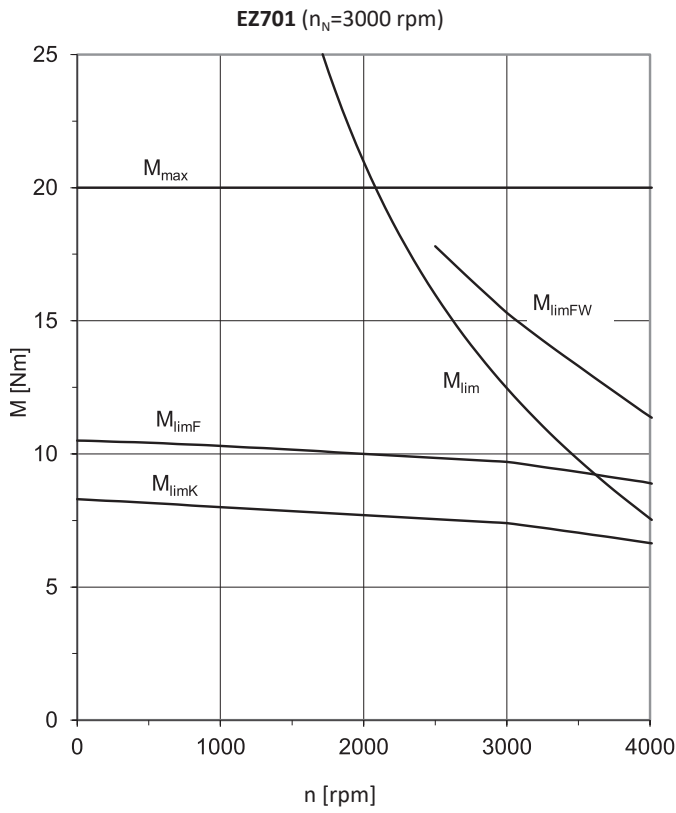
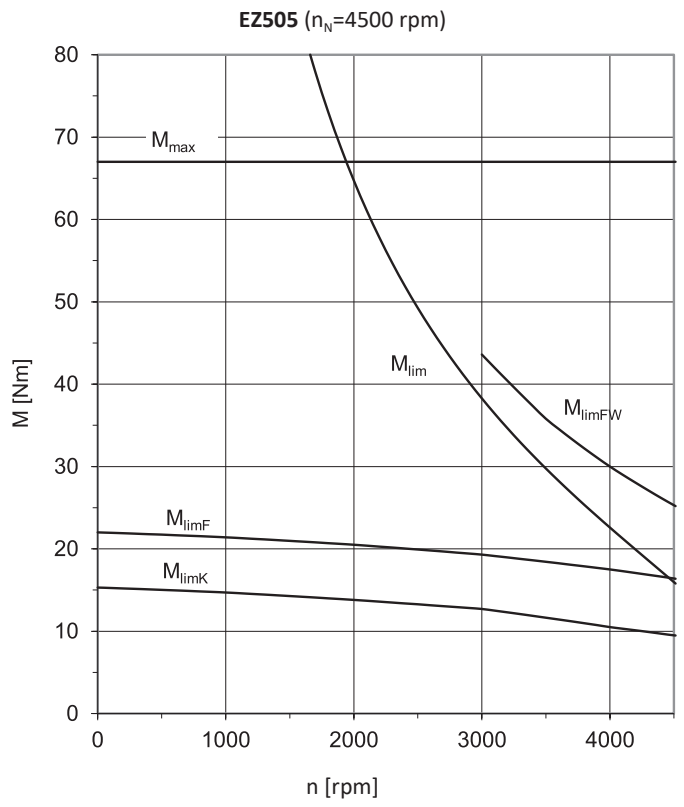
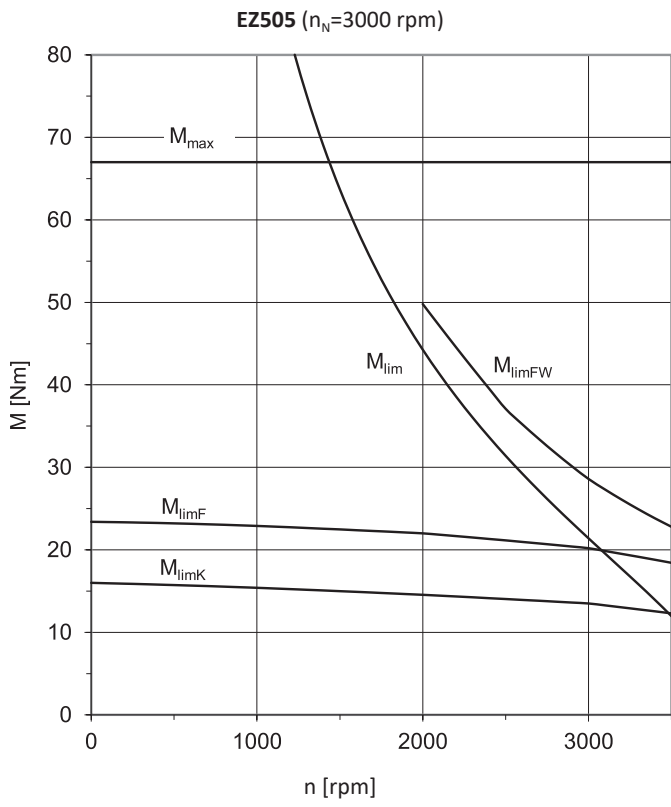
EZ501 ($n_N=3000$ rpm)

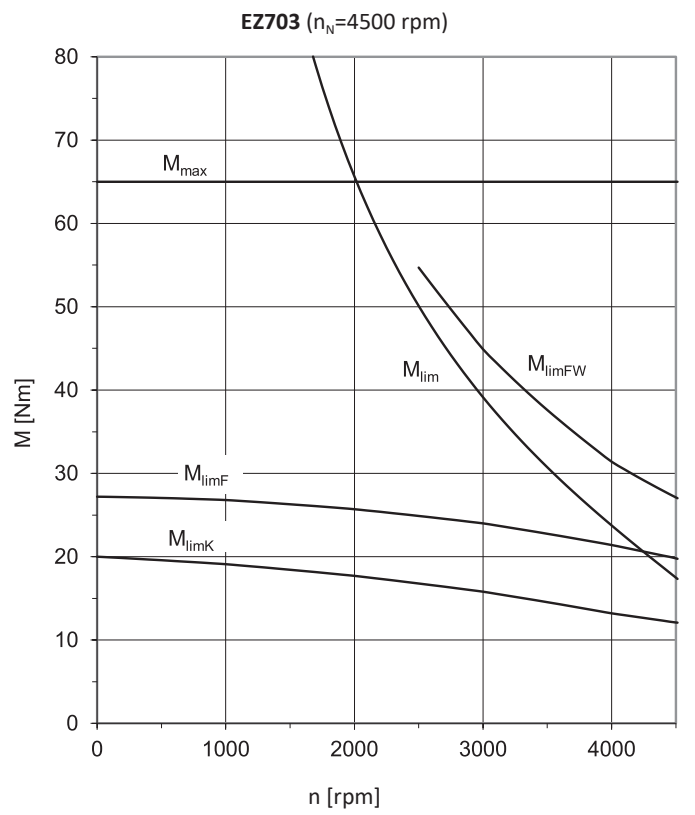
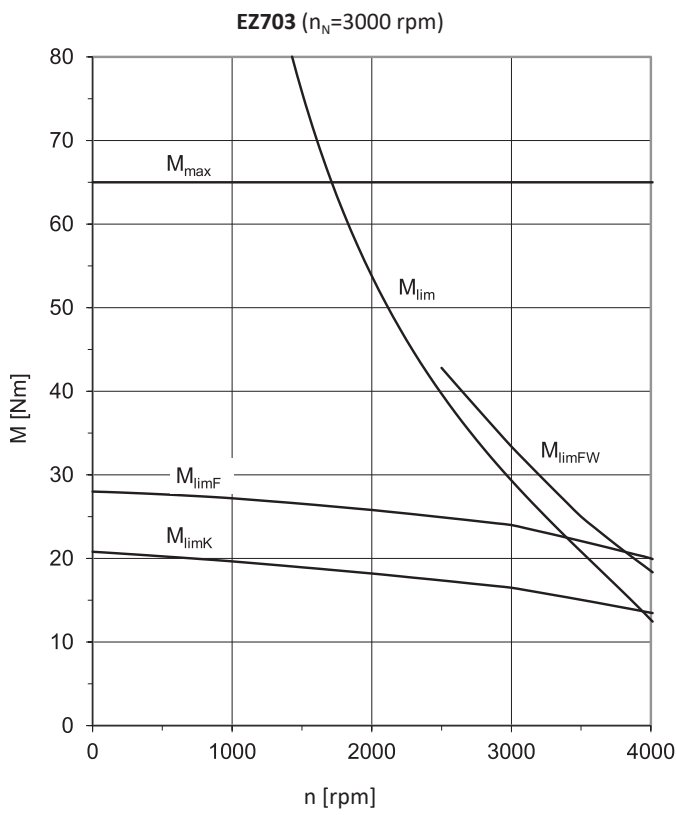
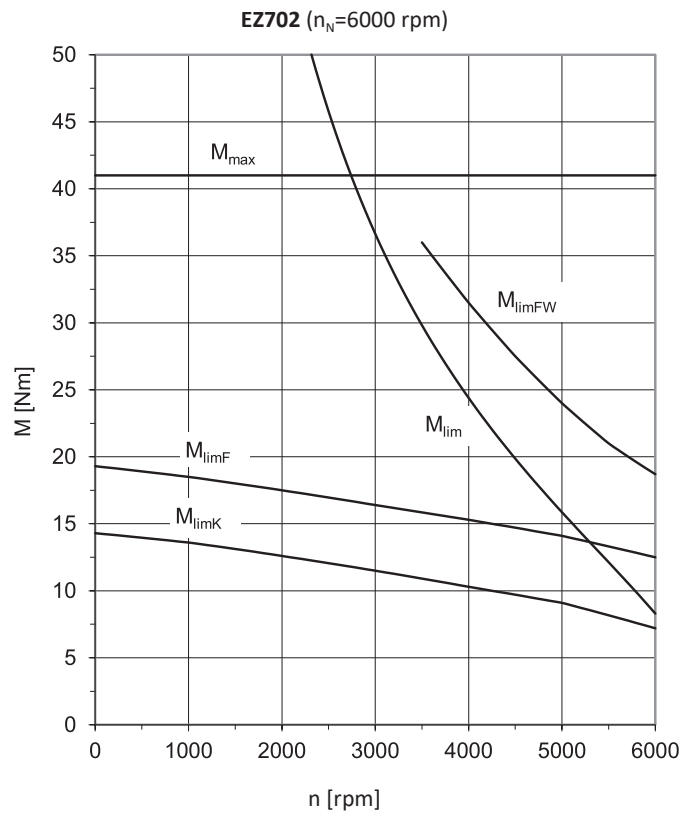
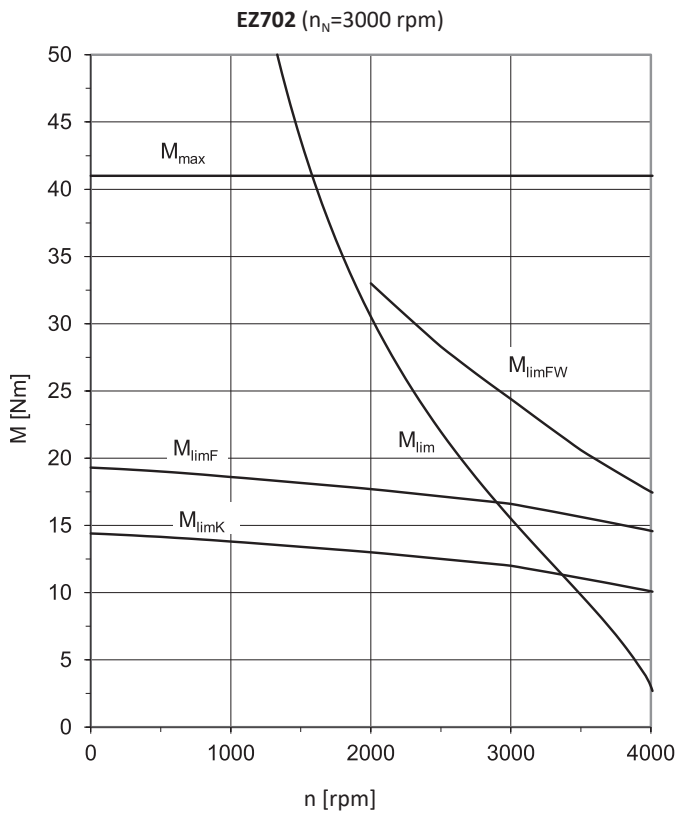


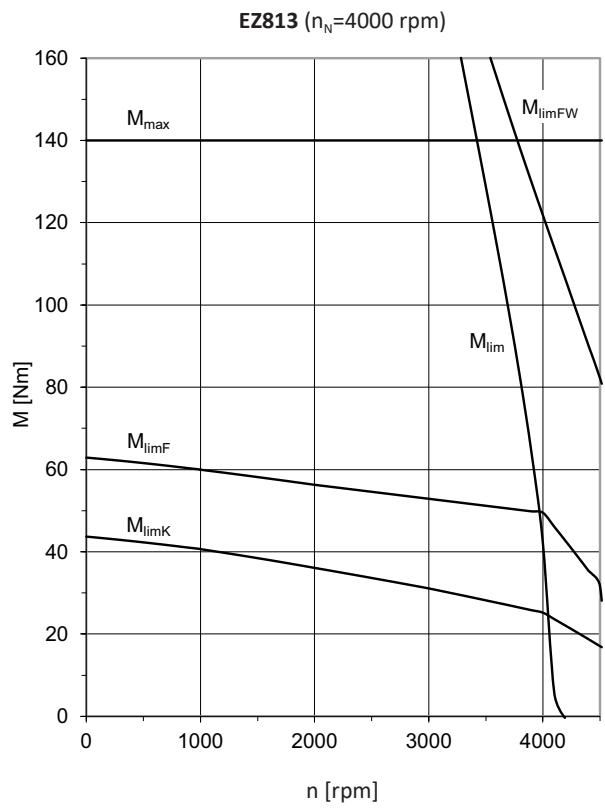
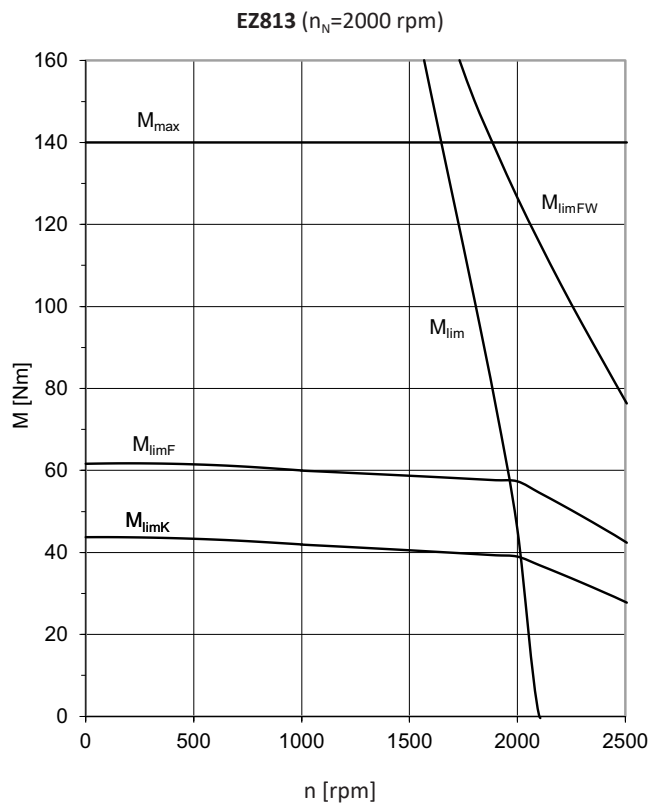
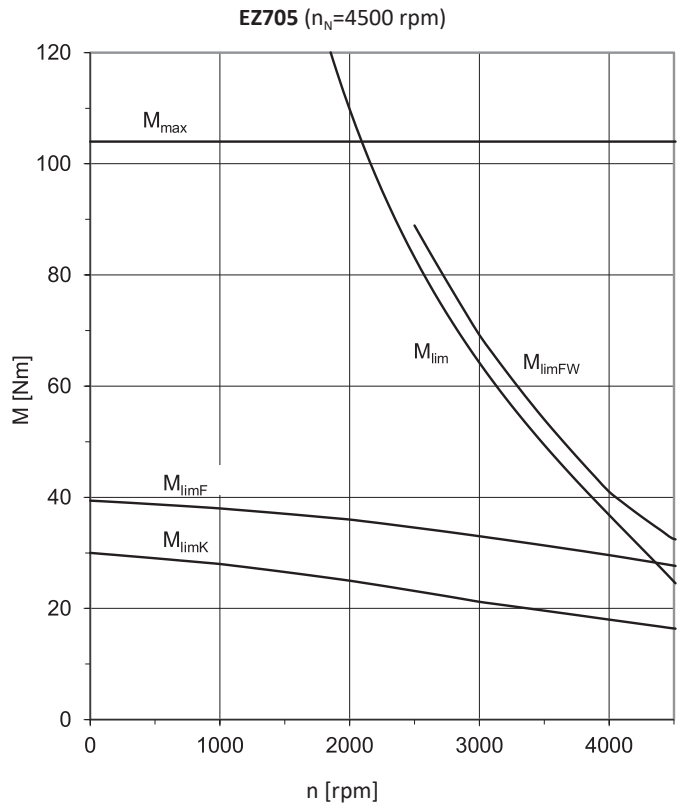
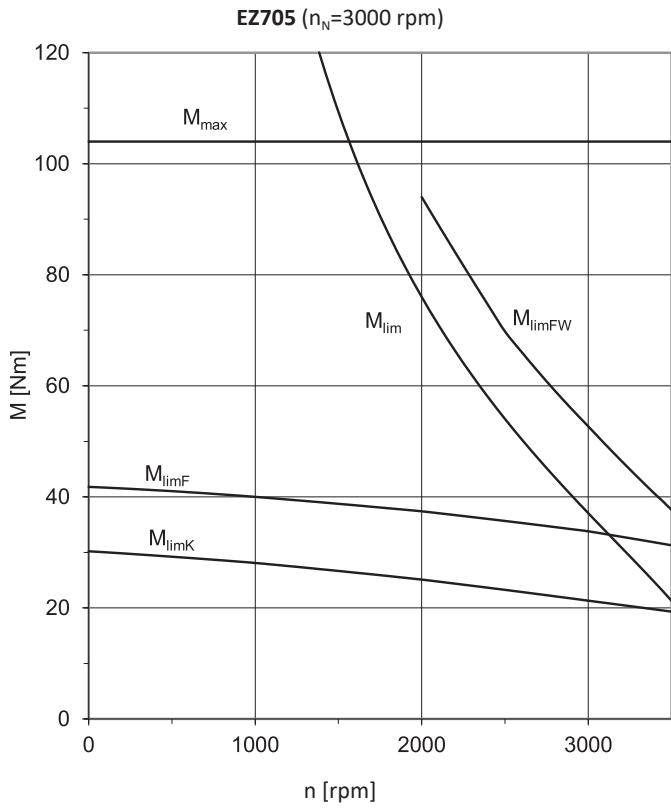
EZ501 ($n_N=6000$ rpm)

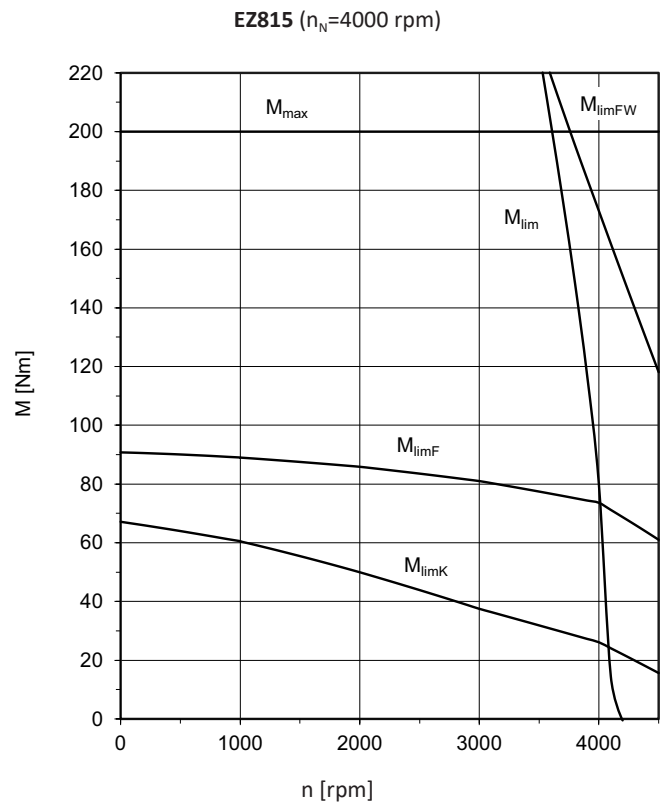
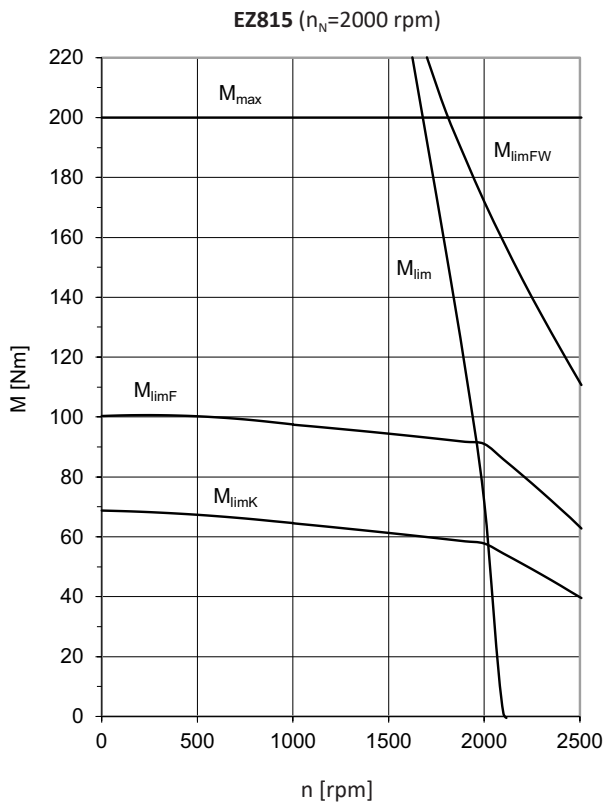












17.4 Dimensional drawings

In this chapter, you can find the dimensions of the motors.

Dimensions can exceed the specifications of ISO 2768-mK due to casting tolerances or accumulation of individual tolerances.

We reserve the right to make dimensional changes due to ongoing technical development.

You can download 3D models of our standard drives at <https://configurator.stoeber.de/en-US/>.

In this chapter, the dimensions p1 and w1 for standard motor designs are presented. In designs for connection to drive controllers of third-party manufacturers, dimensions p1 and w1 may differ. You can find more details at <https://configurator.stoeber.de/en-US/>.

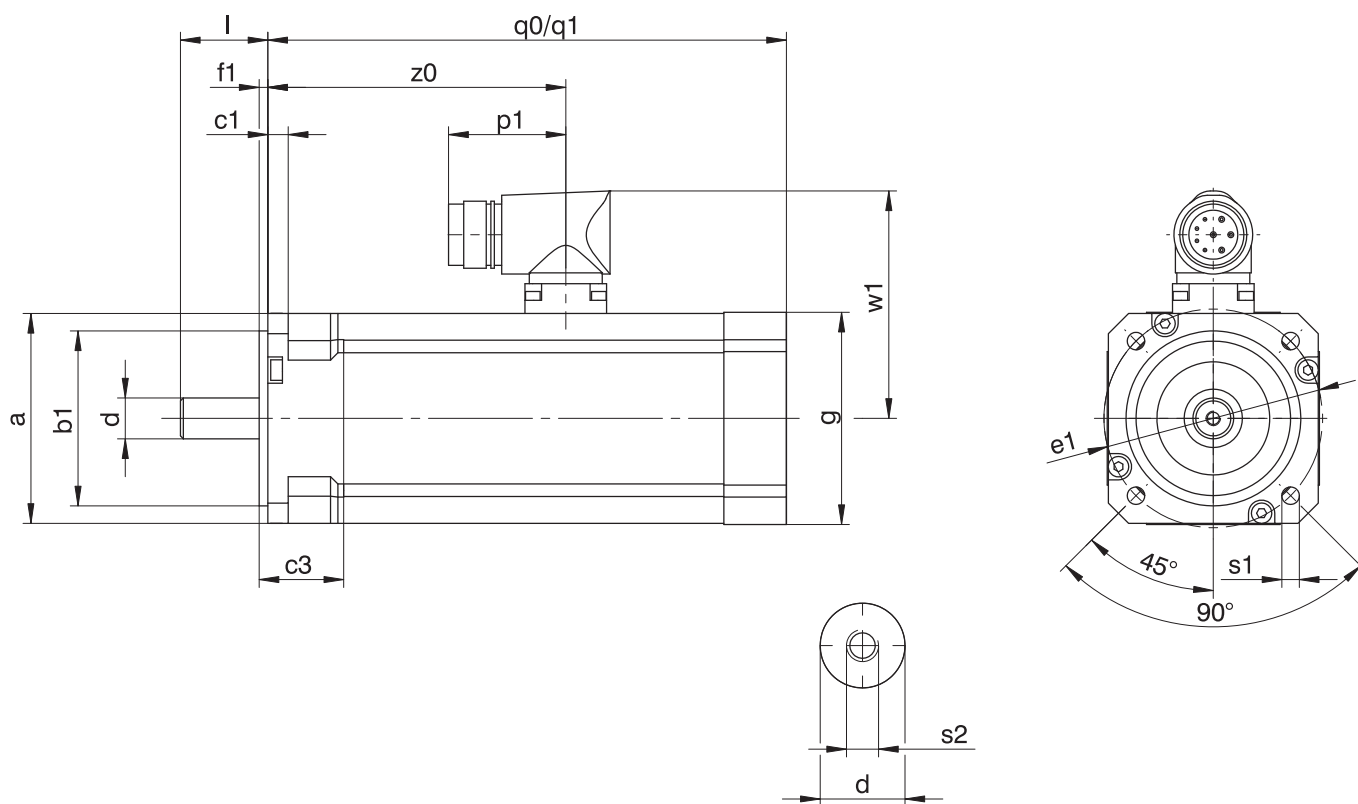
Tolerances

Solid shaft	Tolerance
Shaft \varnothing fit \leq 50 mm	DIN 748-1, ISO k6
Shaft \varnothing fit $>$ 50 mm	DIN 748-1, ISO m6

Centering holes in solid shafts in accordance with DIN 332-2, DR shape

Thread size	M4	M5	M6	M8	M10	M12	M16	M20	M24
Thread depth [mm]	10	12.5	16	19	22	28	36	42	50

17.4.1 E22 – E23 motors with convection cooling (One Cable Solution)

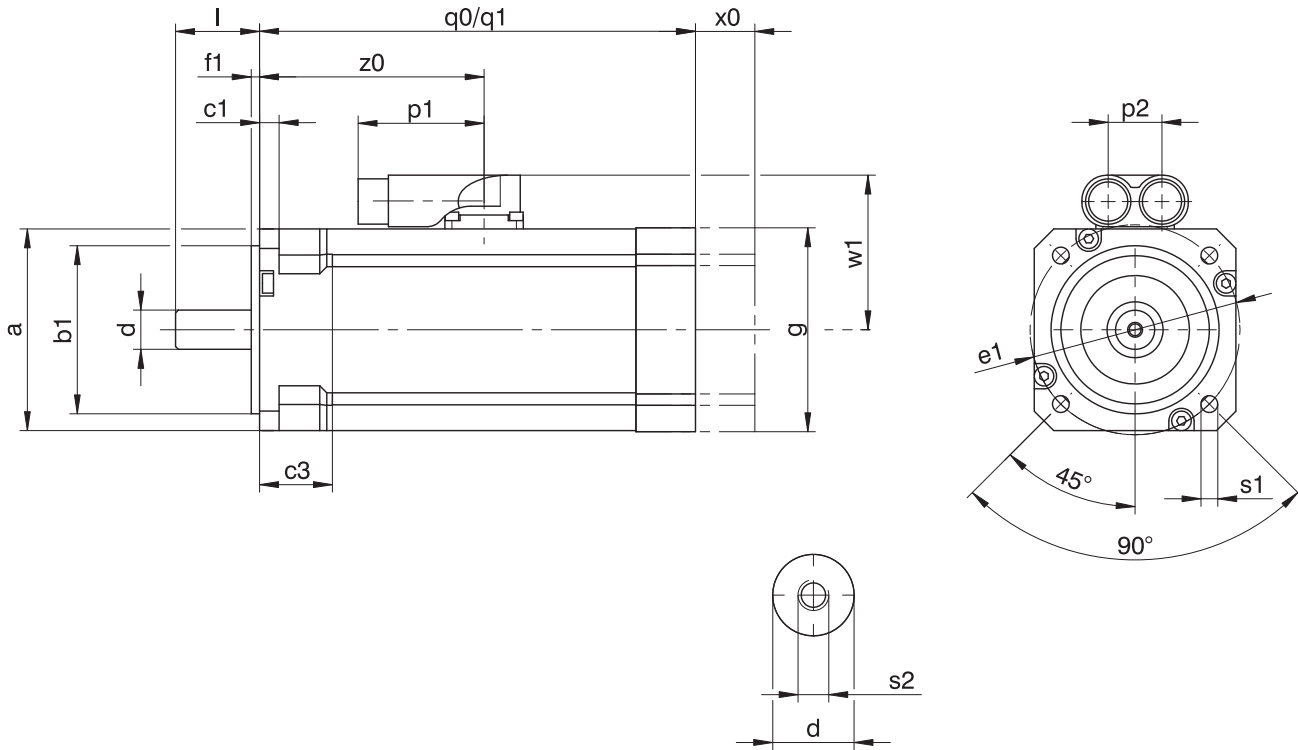


q0 Applies to motors without holding brake

q1 Applies to motors with holding brake

Type	□a	∅b1	c1	c3	∅d	∅e1	f1	□g	l	p1	q0	q1	∅s1	s2	w1	z0
EZ202U	55	40 _β	7	7	9 _{k6}	63	3.5	55	20	40	148	182	5.8	M4	69.5	93.0
EZ203U	55	40 _β	7	7	9 _{k6}	63	3.5	55	20	40	166	200	5.8	M4	69.5	111.0
EZ301U	72	60 _β	7	26	14 _{k6}	75	3.0	72	30	40	116	156	6.0	M5	78.0	80.5
EZ302U	72	60 _β	7	26	14 _{k6}	75	3.0	72	30	40	138	178	6.0	M5	78.0	102.5
EZ303U	72	60 _β	7	26	14 _{k6}	75	3.0	72	30	40	160	200	6.0	M5	78.0	124.5

17.4.2 EZ2 – EZ3 motors with convection cooling



q0 Applies to motors without holding brake

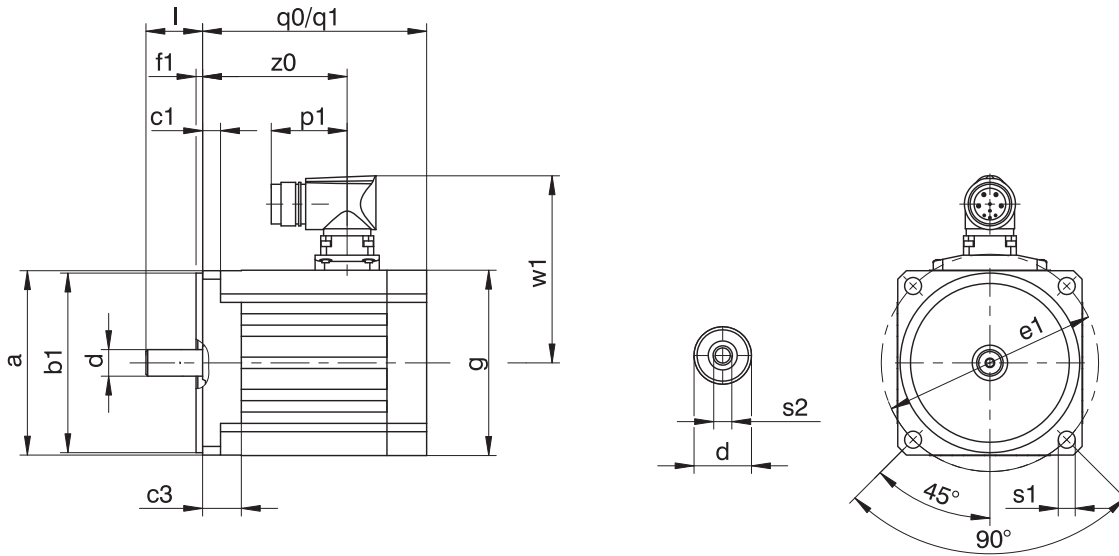
q1 Applies to motors with holding brake

x0 EZ2: Applies only to motors with holding brake and encoders using an optical or inductive measuring method

EZ3: Applies to encoders using an optical measuring method

Type	$\square a$	$\varnothing b1$	c1	c3	$\varnothing d$	$\varnothing e1$	f1	$\square g$	l	p1	p2	q0	q1	$\varnothing s1$	s2	w1	x0	z0
EZ202U	55	40_{j6}	7	7	9_{k6}	63	3.5	55	20	45	19	148	157	5.8	M4	47.0	25	93.0
EZ203U	55	40_{j6}	7	7	9_{k6}	63	3.5	55	20	45	19	166	175	5.8	M4	47.0	25	111.0
EZ301U	72	60_{j6}	7	26	14_{k6}	75	3.0	72	30	45	19	116	156	6.0	M5	55.5	21	80.5
EZ302U	72	60_{j6}	7	26	14_{k6}	75	3.0	72	30	45	19	138	178	6.0	M5	55.5	21	102.5
EZ303U	72	60_{j6}	7	26	14_{k6}	75	3.0	72	30	45	19	160	200	6.0	M5	55.5	21	124.5

17.4.3 EZ4 – EZ7 motors with convection cooling (One Cable Solution)

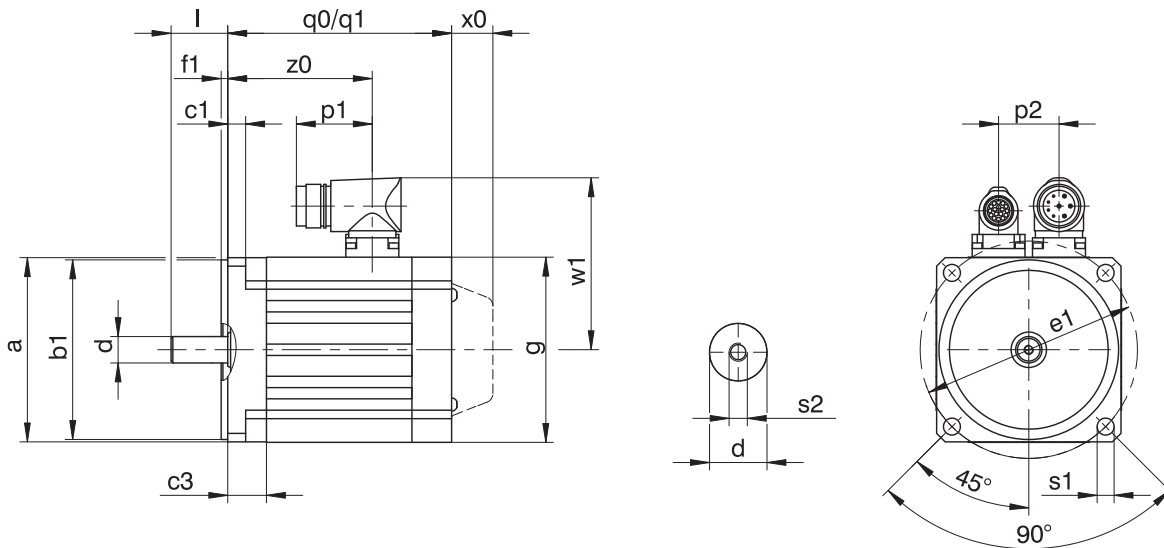


q0 Applies to motors without holding brake

q1 Applies to motors with holding brake

Type	$\square a$	$\varnothing b_1$	c_1	c_3	$\varnothing d$	$\varnothing e_1$	f_1	$\square g$	l	p_1	q0	q1	$\varnothing s_1$	s_2	w_1	z_0
EZ401U	98	95 _{j6}	9.5	20.5	14 _{k6}	115	3.5	98	30	40	118.5	167.0	9	M5	99	76.5
EZ402U	98	95 _{j6}	9.5	20.5	19 _{k6}	115	3.5	98	40	40	143.5	192.0	9	M6	99	101.5
EZ404U	98	95 _{j6}	9.5	20.5	19 _{k6}	115	3.5	98	40	40	193.5	242.0	9	M6	99	151.5
EZ501U	115	110 _{j6}	10.0	16.0	19 _{k6}	130	3.5	115	40	40	109.0	163.5	9	M6	110	74.5
EZ502U	115	110 _{j6}	10.0	16.0	19 _{k6}	130	3.5	115	40	40	134.0	188.5	9	M6	110	99.5
EZ503U	115	110 _{j6}	10.0	16.0	24 _{k6}	130	3.5	115	50	40	159.0	213.5	9	M8	110	124.5
EZ505U	115	110 _{j6}	10.0	16.0	24 _{k6}	130	3.5	115	50	40	209.0	263.5	9	M8	110	174.5
EZ701U	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	121.0	180.0	11	M8	125	83.0
EZ702U	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	146.0	205.0	11	M8	125	108.0
EZ703U	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	171.0	230.0	11	M8	125	133.0
EZ705U	145	130 _{j6}	10.0	19.0	32 _{k6}	165	3.5	145	58	40	226.0	285.0	11	M12	125	184.0

17.4.4 EZ4 – EZ8 motors with convection cooling



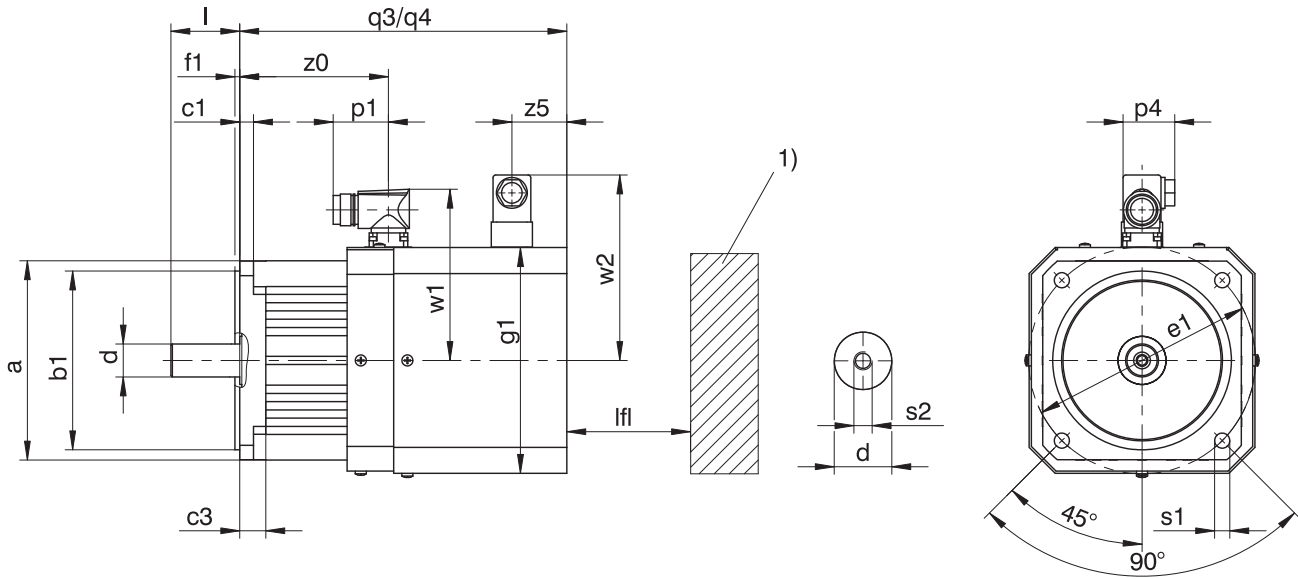
q_0 Applies to motors without holding brake

q_1 Applies to motors with holding brake

x_0 Applies to encoders based on an optical measuring method

Type	$\square a$	$\varnothing b_1$	c_1	c_3	$\varnothing d$	$\varnothing e_1$	f_1	$\square g$	l	p_1	p_2	q_0	q_1	$\varnothing s_1$	s_2	w_1	x_0	z_0
EZ401U	98	95 _{f6}	9.5	20.5	14 _{k6}	115	3.5	98	30	40	32	118.5	167.0	9.0	M5	91.0	22	76.5
EZ402U	98	95 _{f6}	9.5	20.5	19 _{k6}	115	3.5	98	40	40	32	143.5	192.0	9.0	M6	91.0	22	101.5
EZ404U	98	95 _{f6}	9.5	20.5	19 _{k6}	115	3.5	98	40	40	32	193.5	242.0	9.0	M6	91.0	22	151.5
EZ501U	115	110 _{f6}	10.0	16.0	19 _{k6}	130	3.5	115	40	40	36	109.0	163.5	9.0	M6	100.0	22	74.5
EZ502U	115	110 _{f6}	10.0	16.0	19 _{k6}	130	3.5	115	40	40	36	134.0	188.5	9.0	M6	100.0	22	99.5
EZ503U	115	110 _{f6}	10.0	16.0	24 _{k6}	130	3.5	115	50	40	36	159.0	213.5	9.0	M8	100.0	22	124.5
EZ505U	115	110 _{f6}	10.0	16.0	24 _{k6}	130	3.5	115	50	40	36	209.0	263.5	9.0	M8	100.0	22	174.5
EZ701U	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	42	121.0	180.0	11.0	M8	115.0	22	83.0
EZ702U	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	42	146.0	205.0	11.0	M8	115.0	22	108.0
EZ703U	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	145	50	40	42	171.0	230.0	11.0	M8	115.0	22	133.0
EZ705U	145	130 _{f6}	10.0	19.0	32 _{k6}	165	3.5	145	58	71	42	226.0	285.0	11.0	M12	134.0	22	184.0
EZ813U	190	180 _{f6}	15.0	25.0	38 _{k6}	215	3.5	190	80	71	60	263.0	340.0	13.5	M12	156.5	22	209.0
EZ815U	190	180 _{f6}	15.0	25.0	38 _{k6}	215	3.5	190	80	71	60	345.0	422.0	13.5	M12	156.5	22	291.0

17.4.5 EZ4 – EZ7 motors with forced ventilation (One Cable Solution)



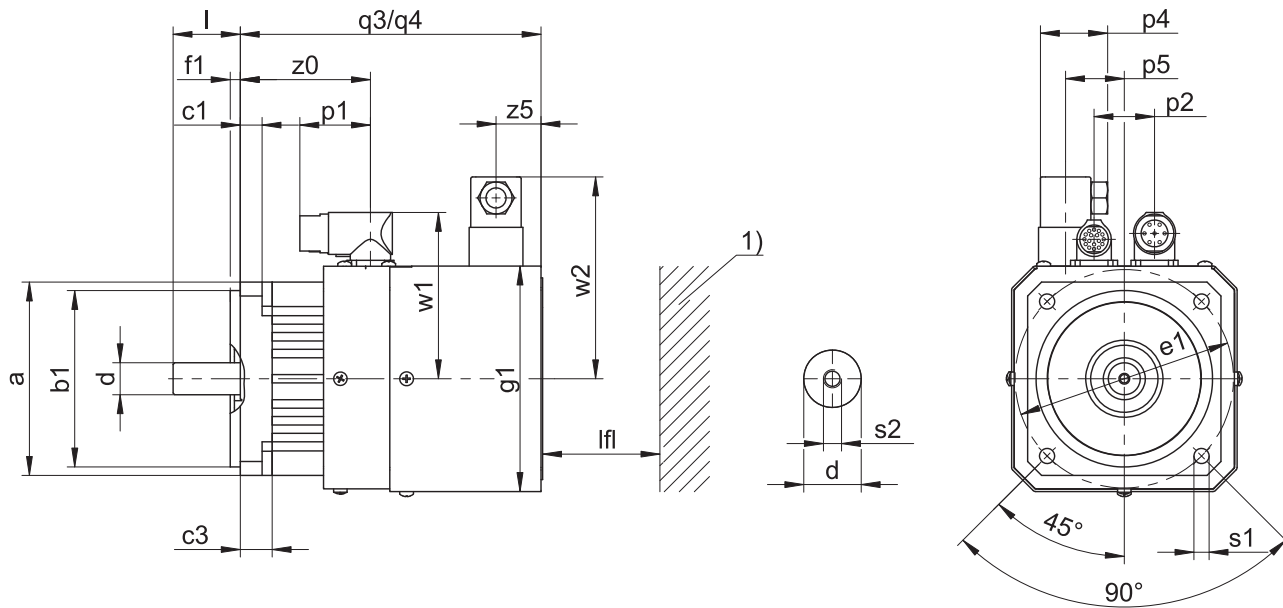
q3 Applies to motors without holding brake

q4 Applies to motors with holding brake

1) Machine wall

Type	□a	∅b1	c1	c3	∅d	∅e1	f1	□g1	l	lfl _{min}	p1	p4	q3	q4	∅s1	s2	w1	w2	z0	z5
EZ401B	98	95 _{j6}	9.5	20.5	14 _{k6}	115	3.5	118	30	20	40	37.5	175	224	9.0	M5	99	111	76.5	25
EZ402B	98	95 _{j6}	9.5	20.5	19 _{k6}	115	3.5	118	40	20	40	37.5	200	249	9.0	M6	99	111	101.5	25
EZ404B	98	95 _{j6}	9.5	20.5	19 _{k6}	115	3.5	118	40	20	40	37.5	250	299	9.0	M6	99	111	151.5	25
EZ501B	115	110 _{j6}	10.0	16.0	19 _{k6}	130	3.5	135	40	20	40	37.5	179	234	9.0	M6	110	120	74.5	25
EZ502B	115	110 _{j6}	10.0	16.0	19 _{k6}	130	3.5	135	40	20	40	37.5	204	259	9.0	M6	110	120	99.5	25
EZ503B	115	110 _{j6}	10.0	16.0	24 _{k6}	130	3.5	135	50	20	40	37.5	229	284	9.0	M8	110	120	124.5	25
EZ505B	115	110 _{j6}	10.0	16.0	24 _{k6}	130	3.5	135	50	20	40	37.5	279	334	9.0	M8	110	120	174.5	25
EZ701B	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	37.5	213	272	11.0	M8	125	134	83.0	40
EZ702B	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	37.5	238	297	11.0	M8	125	134	108.0	40
EZ703B	145	130 _{j6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	37.5	263	322	11.0	M8	125	134	133.0	40

17.4.6 EZ4 – EZ8 motors with forced ventilation



q3 Applies to motors without holding brake

q4 Applies to motors with holding brake

1) Machine wall

Type	□a	∅b1	c1	c3	∅d	∅e1	f1	□g1	l	lfl _{min}	p1	p2	p4	p5	q3	q4	∅s1	s2	w1	w2	z0	z5
EZ401B	98	95 _{f6}	9.5	20.5	14 _{k6}	115	3.5	118	30	20	40	32	37.5	0	175	224	9.0	M5	91.0	111	76.5	25
EZ402B	98	95 _{f6}	9.5	20.5	19 _{k6}	115	3.5	118	40	20	40	32	37.5	0	200	249	9.0	M6	91.0	111	101.5	25
EZ404B	98	95 _{f6}	9.5	20.5	19 _{k6}	115	3.5	118	40	20	40	32	37.5	0	250	299	9.0	M6	91.0	111	151.5	25
EZ501B	115	110 _{f6}	10.0	16.0	19 _{k6}	130	3.5	135	40	20	40	36	37.5	0	179	234	9.0	M6	100.0	120	74.5	25
EZ502B	115	110 _{f6}	10.0	16.0	19 _{k6}	130	3.5	135	40	20	40	36	37.5	0	204	259	9.0	M6	100.0	120	99.5	25
EZ503B	115	110 _{f6}	10.0	16.0	24 _{k6}	130	3.5	135	50	20	40	36	37.5	0	229	284	9.0	M8	100.0	120	124.5	25
EZ505B	115	110 _{f6}	10.0	16.0	24 _{k6}	130	3.5	135	50	20	40	36	37.5	0	279	334	9.0	M8	100.0	120	174.5	25
EZ701B	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	42	37.5	0	213	272	11.0	M8	115.0	134	83.0	40
EZ702B	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	42	37.5	0	238	297	11.0	M8	115.0	134	108.0	40
EZ703B	145	130 _{f6}	10.0	19.0	24 _{k6}	165	3.5	165	50	30	40	42	37.5	0	263	322	11.0	M8	115.0	134	133.0	40
EZ705B	145	130 _{f6}	10.0	19.0	32 _{k6}	165	3.5	165	58	30	71	42	37.5	0	318	377	11.0	M12	134.0	134	184.0	40
EZ813B	190	180 _{f6}	15.0	25.0	38 _{k6}	215	3.5	215	80	30	71	60	37.5	62	363	440	13.5	M12	156.5	160	209.0	40
EZ815B	190	180 _{f6}	15.0	25.0	38 _{k6}	215	3.5	215	80	30	71	60	37.5	62	445	522	13.5	M12	156.5	160	291.0	40

17.5 Type designation

The type designation of a geared motor is composed of the type designation of the gearbox and motor. This chapter describes the type designation of the motor. The type designation of the gearbox is explained in the respective gearbox chapter.

Example code

EZ	4	0	1	U
----	---	---	---	---

Explanation

Code	Designation	Design
EZ	Type	Synchronous servo motor
4	Size	4 (example)
0	Generation	Generation 0
1		Generation 1
1	Length	1 (example)
U	Cooling ²	Convection cooling
B		Forced ventilation

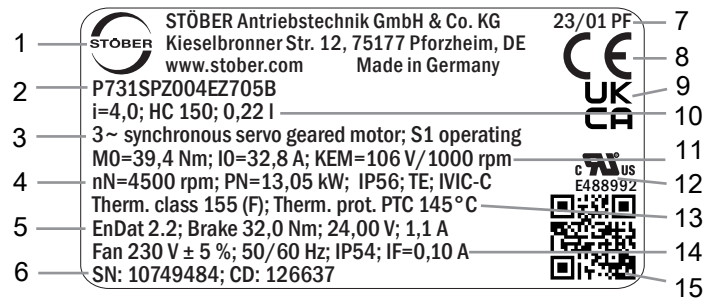
To complete the type designation, also specify the following in your order:

- Code of the drive controller, see the chapter [▶ 17.6.4.6]
- Code of the encoder, see the chapter [▶ 17.6.4]
- With or without holding brake (option), see the chapter [▶ 17.6.7]
- Voltage constant K_{EM} , see the chapter [▶ 17.2]

To make selecting your motor easy, use our STOBBER Configurator at <https://configurator.stoeber.de/en-US/>.

17.5.1 Nameplate

The nameplate of a P731_EZ705 synchronous servo geared motor is explained as an example in this chapter.



Line	Value	Description
1	STÖBER Antriebstechnik GmbH + Co. KG	Logo and address of the manufacturer
2	P731SPZ004EZ705B	Type designation of the geared motor
3	3~ synchronous servo geared motor S1 operating	Geared motor type: three-phase synchronous servo geared motor Operating mode
4	nN=4500 rpm PN=13.05 kW IP56 TE IVIC-C	Nominal speed Nominal power Protection class of the motor Protection class in accordance with UL1004 Impulse voltage insulation class
5	EnDat 2.2 Brake 32.0 Nm 24.00 V 1.1 A	Encoder interface Holding brake (optional) Static braking torque at 100 °C Nominal voltage (DC) of the holding brake Nominal current of the holding brake at 20 °C
6	SN: 10749484 CD: 126637	Serial number of the motor Customer-specific data
7	23/01 PF	Date of manufacture (year/calendar week) Place of manufacture (abbreviation)
8	CE	CE mark
9	UKCA	UKCA mark
10	i=4.0 HC 150 0.22 l	Gear ratio of the gearbox Lubricant specification Lubricant fill volume
11	M0=39.4 Nm I0=32.8 A KEM=106 V/1000 rpm	Stall torque Stall current Voltage constant
12	cURus E488992	cURus test symbol, registered under UL number E488992
13	Therm. class 155 (F) Therm. prot. PTC 145 °C	Thermal class Type of temperature sensor
14	Fan 230 V ± 5%; 50/60 Hz IP54 IF = 0.10 A	Forced ventilation unit (option) Nominal voltage of the forced ventilation unit Protection class of the forced ventilation unit Nominal current of the forced ventilation unit
15	QR code	Link to product information

17.6 Product description

17.6.1 General features

Feature	Description
Design	IM B5, IM V1, IM V3 in accordance with EN 60034-7
Protection class	IP56 / IP66 (option)
Thermal class	155 (F) in accordance with EN 60034-1 (155 °C, heating $\Delta\vartheta = 100$ K)
Surface	Matte black as per RAL 9005
Cooling	IC 410 convection cooling (IC 416 convection cooling with forced ventilation units, optional)
Bearing	Rolling bearing with lifetime lubrication and non-contact sealing
Sealing	Radial shaft seal rings made of FKM (A side)
Shaft	Shaft without feather key, diameter quality k6
Radial runout	Normal tolerance class in accordance with IEC 60072-1
Concentricity	Normal tolerance class in accordance with IEC 60072-1
Axial runout	Normal tolerance class in accordance with IEC 60072-1
Vibration intensity	A in accordance with EN 60034-14
Noise level	Limit values in accordance with EN 60034-9

17.6.2 Electrical features

General electrical features of the motor are described in this chapter. You can find more details in Chapter [▶ 17.2](#).

Feature	Description
DC link voltage	DC 540 V (max. 750 V) on STOBBER drive controllers
Winding	Three-phase
Circuit	Star, center not led through
Protection class	I (protective grounding) in accordance with EN 61140
Impulse voltage insulation class (IVIC)	C in accordance with DIN EN 60034-18-41 (inverter connection voltage 0 – 480 V \pm 10%)
Number of pole pairs	2 (EZ2) 5 (EZ3) 7 (EZ4/EZ5/EZ7) 4 (EZ81)

17.6.3 Ambient conditions

Standard ambient conditions for transport, storage and operation of the motor are described in this chapter. Information about differing ambient conditions can be found in the chapter [▶ 17.7.3](#).

Feature	Description
Surrounding temperature for transport/storage	–30 °C to +85 °C
Surrounding temperature for operation	–15 °C to +40 °C
Relative humidity	5% to 95%, no condensation
Installation altitude	\leq 1000 m above sea level
Shock load	\leq 50 m/s ² (5 g), 6 ms in accordance with EN 60068-2-27

Notes

- STOBBER synchronous servo motors are not suitable for potentially explosive atmospheres.
- Secure the power cables close to the motor so that vibrations of the cable do not place impermissible loads on the motor plug connector.
- Note that the braking torques of the holding brake (optional) may be reduced by shock loading.
- At operating temperatures below 0 °C, note that the discs of the holding brake (optional) may ice up.
- Also take into consideration the shock load of the motor due to output units (such as gearboxes and pumps) which are coupled with the motor.

17.6.4 Encoders

STOBER synchronous servo motors can be designed with different encoder models. The following chapters include information for choosing the optimal encoder for your application.

17.6.4.1 Encoder measuring method selection tool

The following table offers a selection tool for an encoder measuring method that is optimally suited for your application.

Feature	Absolute encoder		Resolvers
Measuring method	Optical	Inductive	Electromagnetic
Temperature resistance	★★☆	★★★	★★★
Vibration strength and shock resistance	★★☆	★★★	★★★
System accuracy	★★★	★★☆	★★☆
Safety-related position measuring system for use in safety-oriented applications	√ ³	√ ⁴	–
Elimination of referencing with multi-turn design (optional)	✓	✓	–
Simple commissioning with electronic nameplate	✓	✓	–

Key: ★☆☆ = satisfactory, ★★☆ = good, ★★★ = very good

17.6.4.2 Selection tool for EnDat interface

The following table offers a selection tool for the EnDat interface of absolute encoders.

Feature	EnDat 2.1	EnDat 2.2	EnDat 3
Short cycle times	★★☆	★★★	★★★
Transfer of additional information along with the position value	–	✓	✓
Expanded power supply range	★★☆	★★★	★★★
One Cable Solution (OCS)	–	–	✓

Key: ★★☆ = good, ★★★ = very good

17.6.4.3 EnDat 3 encoders

EnDat 3 is a robust, purely digital protocol that functions with minimal connection lines. EnDat 3 facilitates the One Cable Solution, which allows the connection lines between the encoder and drive controller to be routed along in the motor's power cable.

The One Cable Solution offers the following advantages:

- Significantly reduced wiring effort by eliminating the encoder cable
- For cable lengths up to 50 m, a choke between the drive controller and motor is not necessary
- Extended safety functions possible (up to SIL 2 / category 3, PL d)
- Significantly reduced space requirements by eliminating the encoder plug connector
- Transmission of measured values from the temperature sensor using the EnDat 3 protocol

A motor with an EnDat 3 encoder can be operated only on a SB6, SC6 or SI6 drive controller from STOBER.

The EnDat 3 encoder has the following features:

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 3 EQI 1131 Safety	S7	Inductive	4096	19 bit	524288	> 100	≤ 15 × 10 ⁻⁹

³ The EnDat 2.1 EQN 1125 encoder does not have FS certification from the manufacturer. However, the mechanical attachment complies with the specifications for FS devices.

⁴ Not for EnDat 2.2 ECI 1118-G2 encoders

17.6.4.4 EnDat 2 encoders

In this chapter, you can find detailed technical data for encoder models that can be selected with EnDat interface.

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQI 1131 Safety	S2	Inductive	4096	19 bit	524288	> 100	$\leq 15 \times 10^{-9}$
EnDat 2.2 ECI 1118-G2	C5	Inductive	–	18 bit	262144	> 76	$\leq 1.5 \times 10^{-6}$
EnDat 2.2 EQN 1135 Safety	S3	Optical	4096	23 bit	8388608	> 100	$\leq 15 \times 10^{-9}$

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$
EnDat 2.1 ECI 1118-G3	C2	Inductive	–	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$
EnDat 2.1 EQI 1130-G3	Q2	Inductive	4096	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- MTTF = Average time before dangerous failure. MTTF values greater than 100 years were reduced in accordance with DIN EN ISO 13849.
- PFH = Probability of a dangerous failure per hour.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

17.6.4.5 Resolver

In this chapter, you can find detailed technical data for the resolver that can be installed as an encoder in a STOBBER motor.

Feature	Description
Code	R0
Number of poles	2
Input voltage $U_{1\text{eff}}$	7 V \pm 5%
Input frequency f_1	10 kHz
Output voltage $U_{2,S1-S3}$	$K_{tr} \cdot U_{R1-R2} \cdot \cos \theta$
Output voltage $U_{2,S2-S4}$	$K_{tr} \cdot U_{R1-R2} \cdot \sin \theta$
Transformation ratio K_{tr}	0.5 \pm 5%
Electrical fault	± 10 arcmin
MTTF	> 100 years
PFH	$\leq 10^{-9}$

17.6.4.6 Possible combinations with drive controllers

The following table shows the options for combining STOBER drive controllers with selectable encoder models.

Drive controller		SB6			SC6			SI6			SD6	
Drive controller code		BC	BD	BE	AU	AV	BA	AP	AQ	BB	AD	AE
Connection plan ID		443376	443377	443378	443052	443053	443174	442771	442772	443175	442450	442451
Encoder	Encoder code											
EnDat 3 EQI 1131 Safety	S7	–	✓	–	–	–	✓	–	–	✓	–	–
EnDat 2.2 EQI 1131 Safety	S2	✓	–	–	✓	–	–	✓	–	–	✓	–
EnDat 2.2 EQN 1135 Safety	S3	✓	–	–	✓	–	–	✓	–	–	✓	–
EnDat 2.2 ECI 1118-G2	C5	✓	–	–	✓	–	–	✓	–	–	✓	–
EnDat 2.1 EQN 1125	Q4	–	–	✓	–	–	–	–	–	–	–	✓
EnDat 2.1 ECI 1118-G3	C2	–	–	✓	–	–	–	–	–	–	–	✓
Resolvers	R0	–	–	✓	–	✓	–	–	✓	–	–	✓

Notes

- In Chapter [\[▶ 18\]](#), you can find information about options for connecting STOBER synchronous servo motors to drive controllers from other manufacturers.

17.6.5 Temperature sensor

In this chapter, you can find technical data for the temperature sensors that are installed in STOBER synchronous servo motors for implementing thermal winding protection. To prevent damage to the motor, always monitor the temperature sensor with appropriate devices that will turn off the motor if the maximum permitted winding temperature is exceeded.

Some encoders feature integrated temperature monitoring, the warning and switch-off thresholds of which may overlap with the corresponding values set for the temperature sensor in the drive controller. In some cases, this may result in an instance where an encoder with internal temperature monitoring forces the motor to shut down, even before the motor has reached its nominal data.

Information about the electrical connection of the temperature sensor can be found in the chapter [\[▶ 17.6.8\]](#).

17.6.5.1 PTC thermistor

The PTC thermistor is installed as a standard temperature sensor in STOBBER synchronous servo motors.

The PTC thermistor is a triple thermistor in accordance with DIN 44082 that can be used for monitoring the temperature of each winding phase. The resistance values in the following table and curve refer to a single thermistor in accordance with DIN 44081. These values must be multiplied by 3 for a triple thermistor in accordance with DIN 44082.

Feature	Description
Nominal response temperature ϑ_{NAT}	145 °C ± 5 K
Resistance R -20 °C up to $\vartheta_{NAT} - 20$ K	≤ 250 Ω
Resistance R with $\vartheta_{NAT} - 5$ K	≤ 550 Ω
Resistance R with $\vartheta_{NAT} + 5$ K	≥ 1330 Ω
Resistance R with $\vartheta_{NAT} + 15$ K	≥ 4000 Ω
Operating voltage	≤ DC 7.5 V
Thermal response time	< 5 s
Thermal class	155 (F) in accordance with EN 60034-1 (155 °C, heating $\Delta\vartheta = 100$ K)

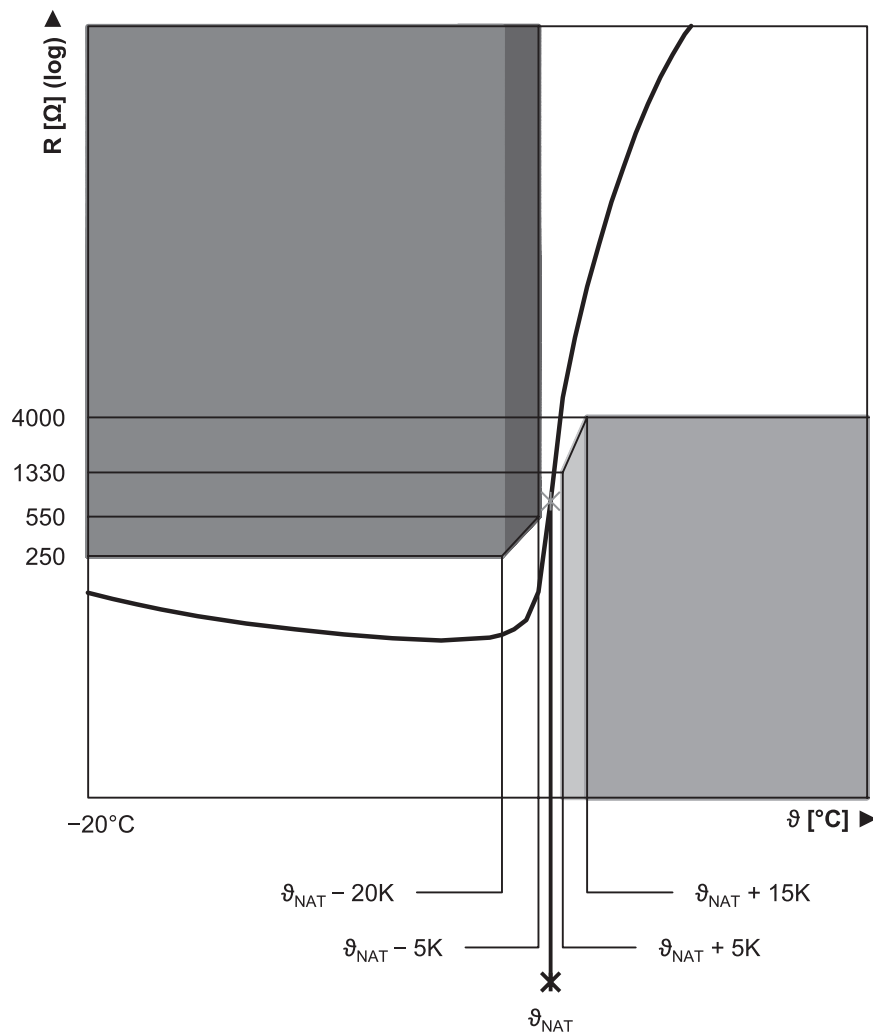


Fig. 2: PTC thermistor curve (single thermistor)

17.6.5.2 Pt1000 temperature sensor

STOBER synchronous servo motors are available in versions with a Pt1000 temperature sensor. The Pt1000 is a temperature-dependent resistor that has a resistance curve with a linear relationship with temperature. As a result, the Pt1000 allows for measurements of the winding temperature. These measurements are limited to one phase of the motor winding, however. In order to adequately protect the motor from exceeding the maximum permitted winding temperature, use a i^2t model in the drive controller to monitor the winding temperature.

Pt1000 temperature sensors can also be used with the One Cable Solution.

Avoid exceeding the specified measurement current so that the measured values are not falsified due to self-heating of the temperature sensor.

Feature	Description
Measurement current (constant)	2 mA
Resistance R for $\vartheta = 0\text{ °C}$	1000 Ω
Resistance R for $\vartheta = 80\text{ °C}$	1300 Ω
Resistance R for $\vartheta = 150\text{ °C}$	1570 Ω

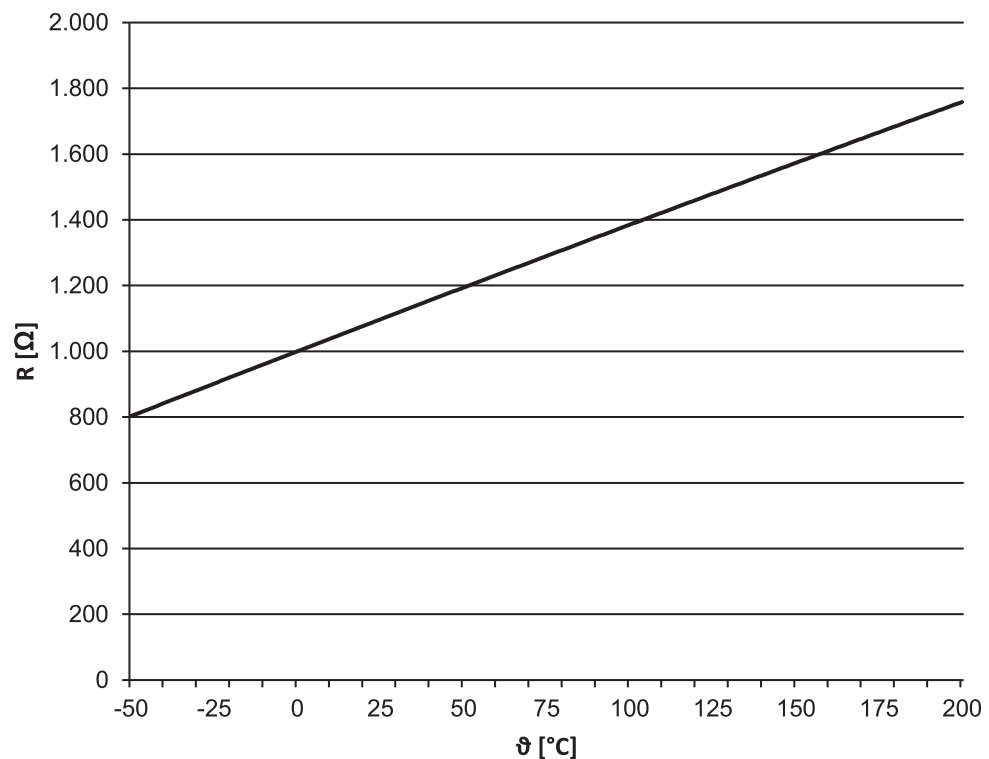


Fig. 3: Pt1000 temperature sensor characteristic curve

17.6.6 Cooling

A synchronous servo motor in the standard version is cooled by convection cooling (IC 410 in accordance with EN 60034-6). Optionally, forced ventilation can be used to cool the motor.

17.6.6.1 Forced ventilation


STOBER synchronous servo motors offer the option of being cooled with forced ventilation in order to increase performance data while maintaining the same size. Retrofitting with a forced ventilation unit is also possible in order to optimize the drive at a later date. When retrofitting, check whether the conductor cross-section of the power cable of the motor must be increased. Also take into account the dimensions of the forced ventilation unit.

The performance data for motors with forced ventilation can be found in the chapter [▶ 17.2](#) and the dimensional drawings in the chapter [▶ 17.4](#).

Technical data

Motor	Forced ventilation unit	$U_{N,F}$ [V]	$I_{N,F}$ [A]	$P_{N,F}$ [W]	q_{VF} [m ³ /h]	$L_{pA,F}$ [dB(A)]	m_F [kg]	Protection class
EZ4_B	FL4	230 V ± 5%, 50/60 Hz	0.07	10	59	41	1.4	IP44
EZ5_B	FL5		0.10	14	160	45	1.9	IP54
EZ7_B	FL7		0.10	14	160	45	2.9	IP54
EZ8_B	FL8		0.20	26	420	54	5.0	IP55

Terminal assignment for forced ventilation unit plug connectors

Connection diagram	Pin	Connection
	1	L1 (phase)
	2	N (neutral conductor)
	3	PE (grounding conductor)
	⊕	PE (grounding conductor)

17.6.7 Holding brake

STOBER synchronous servo motors can be equipped with a backlash-free holding brake using permanent magnets in order to secure the motor shaft when at a standstill. The holding brake engages automatically if the voltage drops.

The holding brake is designed for a high number of operations (B_{10} = 10 million operations, B_{10d} = 20 million operations).

Nominal voltage of permanent magnet holding brake: DC 24 V ± 5%, smoothed.

Observe the following during project configuration:

- The holding brake is designed to keep the motor shaft from moving. Activate braking processes during operation using the corresponding electrical functions of the drive controller. In exceptional circumstances, the holding brake can be used for braking from full speed (following a power failure or when setting up the machine). The maximum permitted work done by friction $W_{B,Rmax/h}$ may not be exceeded.
- Note that the braking torque M_{Bdyn} may initially be up to 50% less when braking from full speed. As a result, the braking effect has a delayed action and braking distances become longer.
- Regularly perform a brake test to ensure the functional safety of the brakes. Details can be found in the documentation of the motor and the drive controller.
- Connect a varistor of type S14 K35 (or comparable) in parallel to the brake coil to protect your machine from switching surges. (Not necessary for connecting the holding brake to STOBER drive controllers of the 5th and 6th generation with a BRS/BRM brake module).
- The holding brake of the motor does not offer adequate safety for persons in the hazardous area of gravity-loaded vertical axes. Therefore take additional measures to minimize risk, e.g. by providing a mechanical substructure for maintenance work.
- Take into consideration voltage losses in the connection cables that connect the voltage source to the holding brake connections.
- The holding torque of the brake can be reduced by shock loading. Information about shock loading can be found in the chapter [▶ 17.6.3].
- At operating temperatures from -15 °C to 0 °C, a cold holding brake in the released state may cause operating noises. As the temperature of the holding brake increases, these noises decrease such that operating noises are not heard when using holding brake at operating temperature in the released state.

Calculation of work done by friction per braking process

$$W_{B,R/B} = \frac{J_{tot} \cdot n^2}{182.4} \cdot \frac{M_{Bdyn}}{M_{Bdyn} \pm M_L}, \quad M_{Bdyn} > M_L$$

The sign of M_L is positive if the movement runs vertically upwards or horizontally and it is negative if the movement runs vertically down.

Calculation of the stop time

$$t_{dec} = 2.66 \cdot t_{1B} + \frac{n \cdot J_{tot}}{9.55 \cdot M_{Bdyn}}$$

Switching behavior

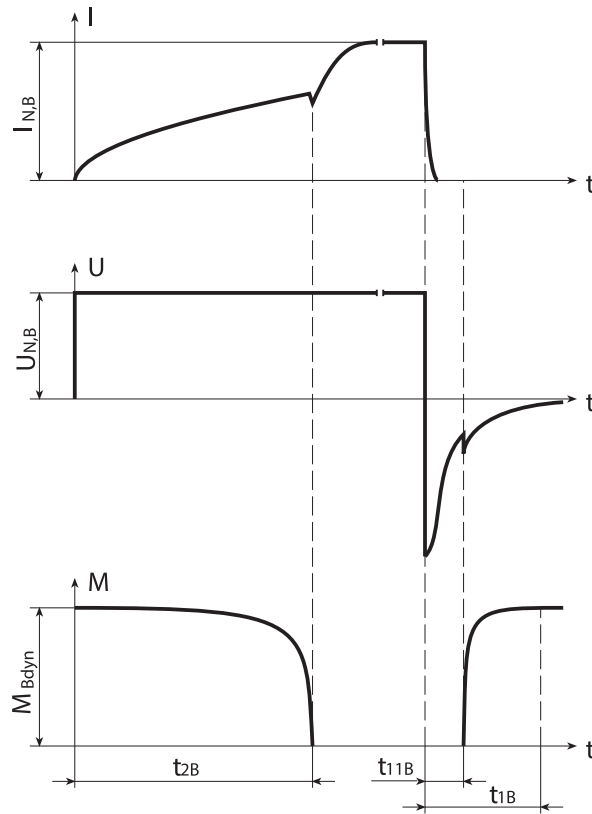


Fig. 4: Holding brake – Switching behavior

Technical data

Type	M _{Bstat} [Nm]	M _{Bdyn} [Nm]	I _{N,B} [A]	W _{B,Rmax/h} [kJ/h]	N _{Bstop}	J _{Bstop} [kgcm ²]	W _{B,Rlim} [kJ]	t _{2B} [ms]	t _{11B} [ms]	t _{1B} [ms]	x _{B,N} [mm]	ΔJ _B [kgcm ²]	Δm _B [kg]
EZ202	1.2	1.0	0.36	3.0	45000	0.310	70	10	2.0	5	0.15	0.03	0.25
EZ203	1.2	1.0	0.38	3.0	36000	0.390	70	10	2.0	5	0.15	0.03	0.25
EZ301	2.5	2.3	0.51	6.0	48000	0.752	180	25	3.0	20	0.20	0.19	0.55
EZ302	4.0	3.8	0.50	8.5	38000	0.952	180	44	4.0	26	0.30	0.19	0.55
EZ303	4.0	3.8	0.50	8.5	30000	1.17	180	44	4.0	26	0.30	0.19	0.55
EZ401	4.0	3.8	0.50	8.5	16000	2.24	180	44	4.0	26	0.30	0.19	0.76
EZ402	8.0	7.0	0.75	8.5	13500	4.39	300	40	2.0	20	0.30	0.57	0.97
EZ404	8.0	7.0	0.75	8.5	8500	7.09	300	40	2.0	20	0.30	0.57	0.97
EZ501	8.0	7.0	0.75	8.5	8700	6.94	300	40	2.0	20	0.30	0.57	1.19
EZ502	8.0	7.0	0.80	8.5	5200	11.5	300	40	2.0	20	0.30	0.57	1.19
EZ503	15	12	1.0	11.0	5900	18.6	550	60	5.0	30	0.30	1.72	1.62
EZ505	15	12	1.0	11.0	4000	27.8	550	60	5.0	30	0.30	1.72	1.62
EZ701	15	12	1.0	11.0	5400	20.5	550	60	5.0	30	0.30	1.74	1.94
EZ702	15	12	1.0	11.0	3600	30.9	550	60	5.0	30	0.30	1.74	1.94
EZ703	32	28	1.1	25.0	5200	54.6	1400	100	5.0	25	0.40	5.68	2.81
EZ705	32	28	1.1	25.0	3500	79.4	1400	100	5.0	25	0.40	5.68	2.81
EZ813	65	35	1.7	45.0	4500	200	2250	200	10	50	0.40	16.5	5.40
EZ815	115	70	2.1	65.0	7000	376	6500	190	12	65	0.50	55.5	8.40


17.6.8 Connection method

The following chapters describe the connection technology of STOBBER synchronous servo motors in the standard version on STOBBER drive controllers. You can find further information relating to the drive controller type that was specified in your order in the connection plan that is delivered with every synchronous servo motor.

In Chapter [▶ 18](#), you can find information about options for connecting STOBBER synchronous servo motors to drive controllers from other manufacturers.

17.6.8.1 Connection of the motor housing to the grounding conductor system

Connect the motor housing to the machine's grounding conductor system to protect persons.

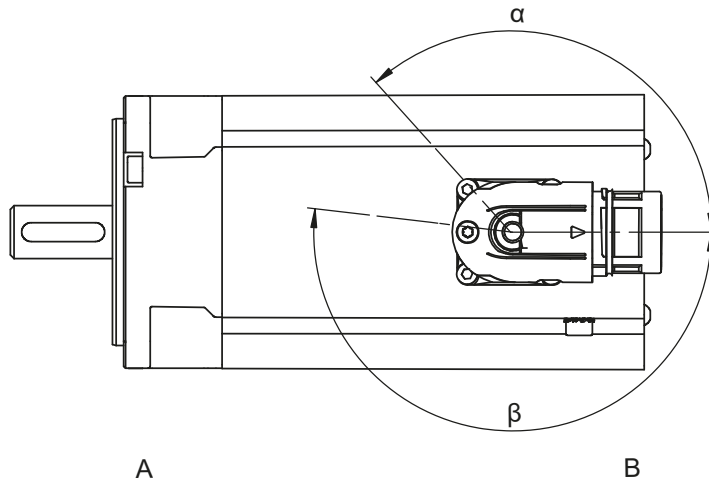
All attachment parts required for the connection of the grounding conductor to the motor housing are delivered with the motor. The grounding screw of the motor is identified with the symbol  in accordance with IEC 60417-DB. The cross-section of the grounding conductor has to be at least as large as the cross-section of the lines in the power connection.

17.6.8.2 Plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector. For motors with forced ventilation, avoid collisions between the motor connection cables and the plug connector of the forced ventilation unit. In the event of a collision, rotate the plug connectors of the motor by the required angle. Details on the position of the plug connector for the forced ventilation unit can be found in the chapter [\[17.4.5\]](#).

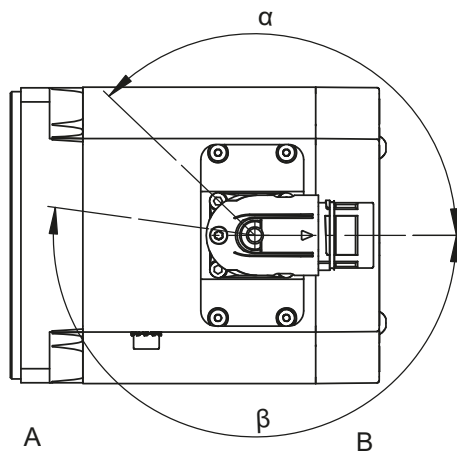
The figures represent the position of the plug connectors upon delivery.

Turning ranges of plug connectors (EZ2 – EZ3 motors)



A	Attachment or output side of the motor	B	Not output side
---	--	---	-----------------

Turning ranges of plug connectors (EZ4 – EZ7 motors)



A	Attachment or output side of the motor	B	Not output side
---	--	---	-----------------

Plug connector features

Motor type	Size	Connection	Turning range	
			α	β
EZ2 – EZ5, EZ701 – EZ703, EZ705U	con.23	Quick-lock	130°	190°

Notes

- The number after "con." indicates the approximate external thread diameter of the plug connector in mm (for example, con.23 designates a plug connector with an external thread diameter of about 23 mm).

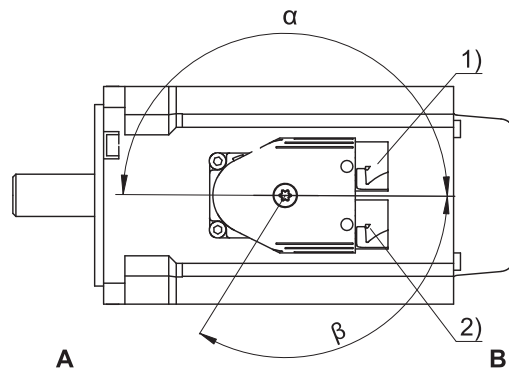
17.6.8.3 Plug connectors

STOBER The standard version of synchronous servo motors is equipped with rotatable quick-lock plug connectors⁵. Details can be found in this chapter.

For motors with forced ventilation, avoid collisions between the motor connection cables and the plug connector of the forced ventilation unit. In the event of a collision, rotate the plug connectors of the motor by the required angle. Details on the position of the plug connector for the forced ventilation unit can be found in the chapter [▶ 17.4.6].

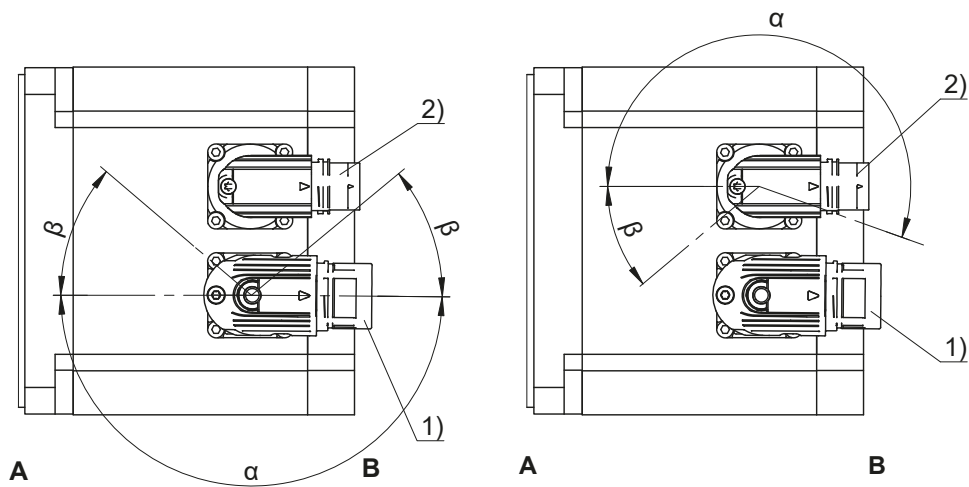
The figures represent the position of the plug connectors upon delivery.

Turning ranges of plug connectors (EZ2 – EZ3 motors)



- | | | | |
|---|--|---|------------------------|
| 1 | Power plug connector | 2 | Encoder plug connector |
| A | Attachment or output side of the motor | B | Not output side |

Turning ranges of plug connectors (EZ4 – EZ8 motors)



- | | | | |
|---|--|---|------------------------|
| 1 | Power plug connector | 2 | Encoder plug connector |
| A | Attachment or output side of the motor | B | Not output side |

⁵The connectors can be pivoted up to 10 times at a specific angle. They cannot be rotated repeatedly.

Power plug connector features

Motor type	Size	Connection	Turning range	
			α	β
EZ2, EZ3	con.15	Quick-lock	180°	120°
EZ4, EZ5, EZ701, EZ702, EZ703	con.23	Quick-lock	180°	40°
EZ705, EZ8	con.40	Quick-lock	180°	40°

Encoder plug connector features

Motor type	Size	Connection	Turning range	
			α	β
EZ2, EZ3	con.15	Quick-lock	180°	120°
EZ4, EZ5, EZ7, EZ8	con.17	Quick-lock	190°	35°

Notes

- The number after "con." indicates the approximate external thread diameter of the plug connector in mm (for example, con.23 designates a plug connector with an external thread diameter of about 23 mm).
- In turning range β , the power or encoder plug connectors can be turned only if doing so does not cause them to collide.
- For the EZ2/EZ3 motor, the power and encoder plug connectors are mechanically connected and can only be turned together.

17.6.8.4 Terminal assignment for plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector.

The temperature sensor of the motor is connected to the encoder internally. The measured values from the temperature sensor are transmitted via the EnDat 3 protocol of the encoder.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	E	P_SD -
	F	
	G	1BD1 (brake +)
	H	P_SD +
	L	1BD2 (brake -)
	⊕	PE (grounding conductor)

17.6.8.5 Connection assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.15

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
	3	1BD1 (brake +)
	4	1BD2 (brake -)
	5 ⊕	PE (grounding conductor)

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	3	1V1 (V phase)
	4	1W1 (W phase)
	A	1BD1 (brake +)
	B	1BD2 (brake -)
	C	1TP1 (temperature sensor +)
	D	1TP2 (temperature sensor -)
	⊕	PE (grounding conductor)

Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
	⊕	PE (grounding conductor)


17.6.8.6 Connection assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

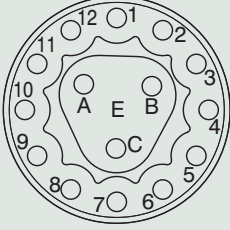
EnDat 2.2 digital encoder, plug connector size con.15

Connection diagram	Pin	Connection
	1	Clock +
	2	Up sense
	3	
	4	
	5	Data -
	6	Data +
	7	
	8	Clock -
	9	
	10	0 V GND
	11	
	12	Up +


EnDat 2.2 digital encoder, plug connector size con.17

Connection diagram	Pin	Connection
	1	Clock +
	2	Up sense
	3	
	4	
	5	Data -
	6	Data +
	7	
	8	Clock -
	9	
	10	0 V GND
	11	
	12	Up +

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.15

Connection diagram	Pin	Connection
	1	Up sense
	2	0 V sense
	3	Up +
	4	Clock +
	5	Clock -
	6	0 V GND
	7	B + (Sin +)
	8	B - (Sin -)
	9	Data +
	10	A + (Cos +)
	11	A - (Cos -)
	12	Data -
A		
B		
C		

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.17

Connection diagram	Pin	Connection
	1	Up sense
	2	
	3	
	4	0 V sense
	5	
	6	
	7	Up +
	8	Clock +
	9	Clock -
	10	0 V GND
	11	
	12	B + (Sin +)
	13	B - (Sin -)
	14	Data +
	15	A + (Cos +)
	16	A - (Cos -)
	17	Data -

Resolver, plug connector size con.15

Connection diagram	Pin	Connection
	1	S3 Cos +
	2	S1 Cos -
	3	S4 Sin +
	4	S2 Sin -
	5	
	6	
	7	R2 Ref +
	8	R1 Ref -
	9	
	10	
	11	
	12	

Resolver, plug connector size con.17

Connection diagram	Pin	Connection
	1	S3 Cos +
	2	S1 Cos -
	3	S4 Sin +
	4	S2 Sin -
	5	
	6	
	7	R2 Ref +
	8	R1 Ref -
	9	
	10	
	11	
	12	

17.7 Project configuration

Project your drives using our SERVOnsoft designing software. Download SERVOnsoft free of charge after registration at <https://www.stoeber.de/en/services/info-servosoft/>.

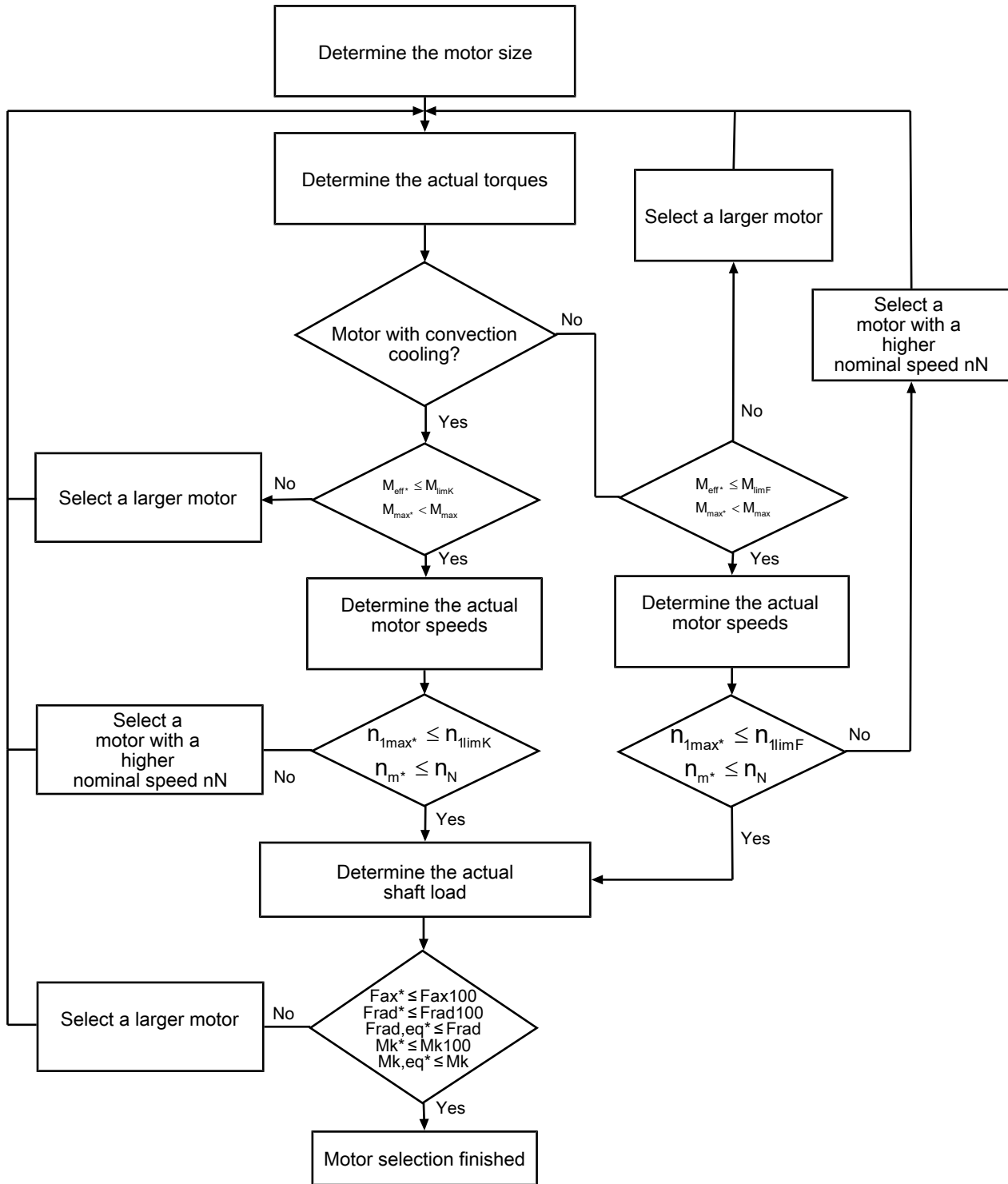
It is the most convenient and reliable method of drive selection, as the entire torque/speed curve of the application is displayed and evaluated here in the curve of the geared motor.

In this chapter, only limit values for specific operating points can be taken into consideration for manual drive selection.

An explanation of the formula symbols can be found in Chapter [▶ 20.1](#).

The formula symbols for values actually present in the application are marked with *.

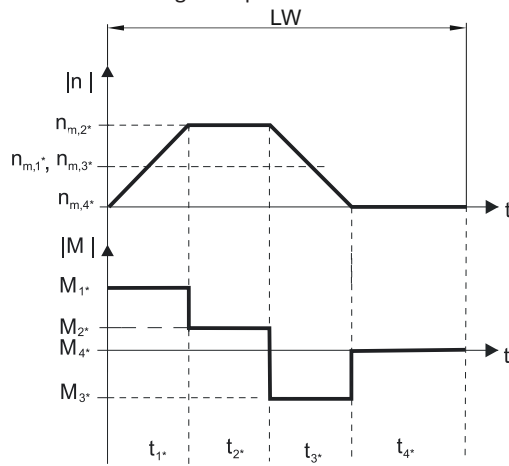
17.7.1 Drive selection



The value for M_{lim} , M_{limK} , M_{limF} , M_{max} , n_{1limK} and n_{1limF} can be found in the motor characteristic curve in the chapter [17.3](#). Note the size, nominal speed n_N and cooling type of the motor.

Example of cyclic operation

The following calculations refer to a representation of the power delivered at the motor shaft in accordance with the following example:



Calculation of the actual average input speed

$$n_{m^*} = \frac{|n_{m,1^*}| \cdot t_{1^*} + \dots + |n_{m,n^*}| \cdot t_{n^*}}{t_{1^*} + \dots + t_{n^*}}$$

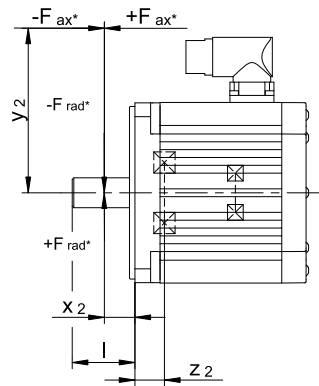
If $t_{1^*} + \dots + t_{3^*} \geq 6 \text{ min}$, determine n_{m^*} without the rest phase t_{4^*} .

Calculation of the actual effective torque

$$M_{\text{eff}^*} = \sqrt{\frac{t_{1^*} \cdot M_{1^*}^2 + \dots + t_{n^*} \cdot M_{n^*}^2}{t_{1^*} + \dots + t_{n^*}}}$$

17.7.2 Permitted shaft loads

This chapter contains information about the maximum permitted shaft loads of the output shaft of the motor.



Type	z_2 [mm]	F_{ax100} [N]	F_{rad100} [N]	M_{k100} [Nm]
EZ202	12.0	250	750	20
EZ203	12.0	250	750	20
EZ301	24.0	350	1000	39
EZ302	24.0	350	1000	39
EZ303	24.0	350	1000	39
EZ401	19.5	550	1800	62
EZ402	19.5	550	1800	71
EZ404	19.5	550	1800	71
EZ501	19.5	750	2000	79
EZ502	19.5	750	2400	95
EZ503	19.5	750	2400	107
EZ505	19.5	750	2400	107
EZ701	24.5	1300	3500	173
EZ702	24.5	1300	4200	208
EZ703	24.5	1300	4200	208
EZ705	24.5	1300	4200	225
EZ813	28.5	1750	5600	384
EZ815	28.5	1750	5600	384

The values for permitted shaft loads specified in the table apply:

- For shaft dimensions in accordance with the catalog
- A force applied at the center of the output shaft: $x_2 = l / 2$ (shaft dimensions can be found in the chapter [▶ 17.4](#))
- Output speeds $n_{m^*} \leq 100$ rpm ($F_{ax} = F_{ax100}$; $F_{rad} = F_{rad100}$; $M_k = M_{k100}$)

The following applies to output speeds $n_{m^*} > 100$ rpm:

$$F_{ax} = \frac{F_{ax100}}{\sqrt[3]{\frac{n_{m^*}}{100 \text{ rpm}}}} \quad F_{rad} = \frac{F_{rad100}}{\sqrt[3]{\frac{n_{m^*}}{100 \text{ rpm}}}} \quad M_k = \frac{M_{k100}}{\sqrt[3]{\frac{n_{m^*}}{100 \text{ rpm}}}}$$

The following applies to other force application points:

$$M_{k^*} = \frac{2 \cdot F_{ax^*} \cdot y_2 + F_{rad^*} \cdot (x_2 + z_2)}{1000}$$

For applications with multiple axial and/or radial forces, you must add the forces as vectors.

Also note the calculation for equivalent values:

$$M_{k,eq^*} = \sqrt[3]{\frac{|n_{m,1^*}| \cdot t_{1^*} \cdot |M_{k,1^*}|^3 + \dots + |n_{m,n^*}| \cdot t_{n^*} \cdot |M_{k,n^*}|^3}{|n_{m,1^*}| \cdot t_{1^*} + \dots + |n_{m,n^*}| \cdot t_{n^*}}}$$

$$F_{rad,eq^*} = \sqrt[3]{\frac{|n_{m,1^*}| \cdot t_{1^*} \cdot |F_{rad,1^*}|^3 + \dots + |n_{m,n^*}| \cdot t_{n^*} \cdot |F_{rad,n^*}|^3}{|n_{m,1^*}| \cdot t_{1^*} + \dots + |n_{m,n^*}| \cdot t_{n^*}}}$$

17.7.3 Derating

If you use the motor under ambient conditions that differ from the standard ambient conditions, the nominal torque M_N of the motor is reduced. In this chapter, you can find information for calculating the reduced nominal torque.

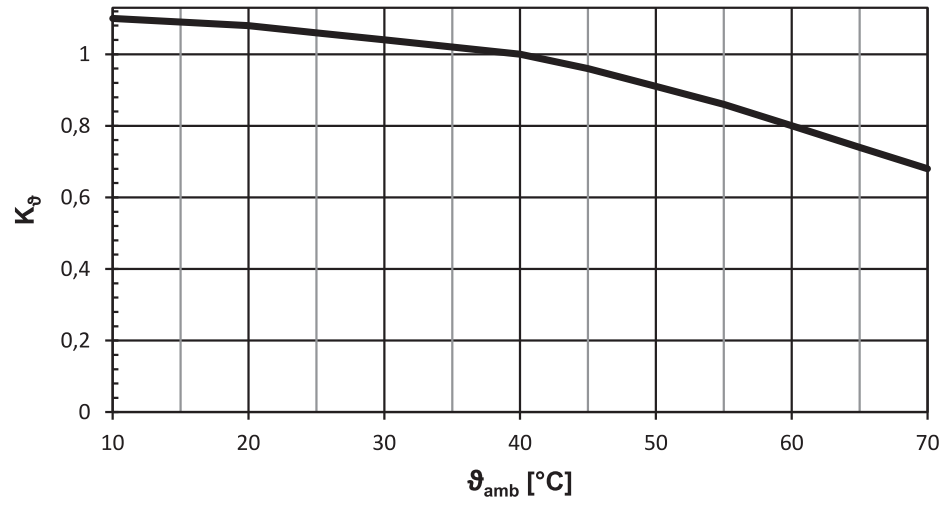


Fig. 5: Derating depending on the surrounding temperature

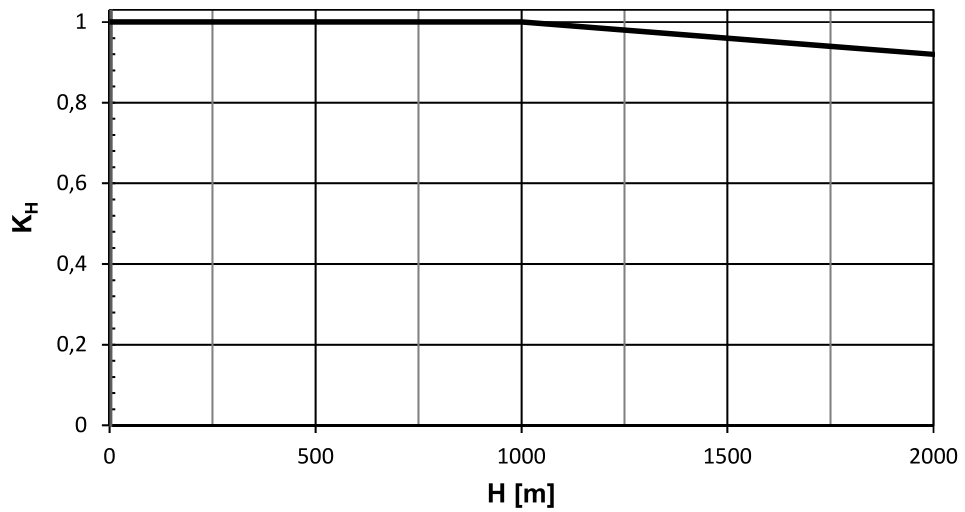


Fig. 6: Derating depending on the installation height

Calculation

If surrounding temperature $\vartheta_{amb} > 40$ °C:

$$M_{Nred} = M_N \cdot K_\theta$$

If installation altitude $H > 1000$ m above sea level:

$$M_{Nred} = M_N \cdot K_H$$

If the surrounding temperature $\vartheta_{amb} > 40$ °C and installation altitude $H > 1000$ m above sea level:

$$M_{Nred} = M_N \cdot K_H \cdot K_\theta$$

17.8 Further information

17.8.1 Directives and standards

STOBER synchronous servo motors meet the requirements of the following directives and standards:

- (Low Voltage) Directive 2014/35/EU
- EN 60034-1: 2010 + Cor.:2010
- EN 60034-5: 2020
- EN 60034-6:1993

17.8.2 Identifiers and test symbols

STOBER synchronous servo motors have the following identifiers and test symbols:



CE mark: The product meets the requirements of EU directives.



UKCA mark: The product meets the requirements of UK directives.



cURus test symbol "Servo and Stepper Motors – Component"; registered under UL number E488992 with Underwriters Laboratories USA.

17.8.3 Additional documentation

Additional documentation related to the product can be found at

<http://www.stoeber.de/en/downloads/>

Enter the ID of the documentation in the Search term field.

Documentation	ID
Operating manual for EZ synchronous servo motors	443032_en

18 Connecting to drive controllers of third-party manufacturers

Table of contents

18.1	General notes	605
18.1.1	Nominal data	605
18.1.2	Plug connectors (One Cable Solution)	606
18.1.3	Plug connectors	607
18.1.4	Connection cables	608
18.2	Connection to B&R drive controllers	609
18.2.1	Encoders	609
18.2.2	Resolver	609
18.2.3	Possible combinations with drive controllers	610
18.2.4	Connection assignment of the power plug connector	610
18.2.5	Connection assignment of the encoder plug connector	611
18.2.6	Terminal assignment for plug connectors (One Cable Solution)	612
18.3	Connection to Control Techniques drive controllers	613
18.3.1	Encoder	613
18.3.2	Resolver	613
18.3.3	Possible combinations with drive controllers	614
18.3.4	Terminal assignment of the power plug connector	614
18.3.5	Terminal assignment of the encoder plug connector	615
18.3.6	Terminal assignment for plug connectors (One Cable Solution)	616
18.4	Connection to Siemens drive controllers	617
18.4.1	Encoders	617
18.4.2	Resolver	617
18.4.3	Possible combinations with drive controllers	618
18.4.4	Connection assignment of the power plug connector	618
18.4.5	Connection assignment of the encoder plug connector	619
18.5	Connection to Kollmorgen drive controllers	620
18.5.1	Encoders	620
18.5.2	Resolver	620
18.5.3	Possible combinations with drive controllers	621
18.5.4	Connection assignment of the power plug connector	621
18.5.5	Connection assignment of the encoder plug connector	622
18.6	Connection to Bosch drive controllers	623
18.6.1	Encoders	623
18.6.2	Possible combinations with drive controllers	623
18.6.3	Connection assignment of the power plug connector	624
18.6.4	Connection assignment of the encoder plug connector	625
18.7	Connection to Beckhoff drive controllers	626
18.7.1	Encoders	626
18.7.2	Possible combinations with drive controllers	627
18.7.3	Terminal assignment of 8-pin power plug connector	627

18.7.4	Terminal assignment of 9-pin power plug connector	628
18.7.5	Connection assignment of the encoder plug connector	628
18.7.6	Terminal assignment for plug connectors (One Cable Solution).....	629
18.8	Connection to Allen-Bradley drive controllers	630
18.8.1	Encoders.....	630
18.8.2	Possible combinations with drive controllers	631
18.8.3	Terminal assignment of the power plug connector	631
18.8.4	Terminal assignment of the encoder plug connector	632
18.8.5	Terminal assignment for plug connectors (One Cable Solution).....	633

18.1 General notes

STOBER synchronous servo motors are designed for connection to STOBER drive controllers in the standard version. STOBER offers an extensive assortment of high-quality, trusted power and encoder connection cables for this purpose. However, STOBER synchronous servo motors can also be operated on drive controllers from third-party manufacturers. Notes and information for this purpose can be found in the following chapters. You can find all other information about STOBER synchronous servo motors in the chapter [\[17 \]](#).

18.1.1 Nominal data

Nominal data for synchronous servo motors specified in the selection tables of this catalog were calculated for connecting to STOBER drive controllers. Note that this nominal data may change when STOBER synchronous servo motors are connected to drive controllers of third-party manufacturers. The following drive controller plug connectors are determining factors here:

- f_{2PU}
- $f_{PWM,PU}$
- U_{ZK}
- Compensation of the field weakening range.

The maximum achievable speed of a synchronous servo motor depends on the number of pole pairs (p) of the synchronous servo motor and, if applicable, on the restriction of f_{2PU} by Regulation (EC) No. 428/2009 (EC Dual Use Regulation). Details are shown in the figure below.

Some encoders feature integrated temperature monitoring, the warning and switch-off thresholds of which may overlap with the corresponding values set for the thermal winding protection in the drive controller. In some cases, this may result in an instance where an encoder with internal temperature monitoring forces the motor to shut down, even before the motor has reached its nominal data.

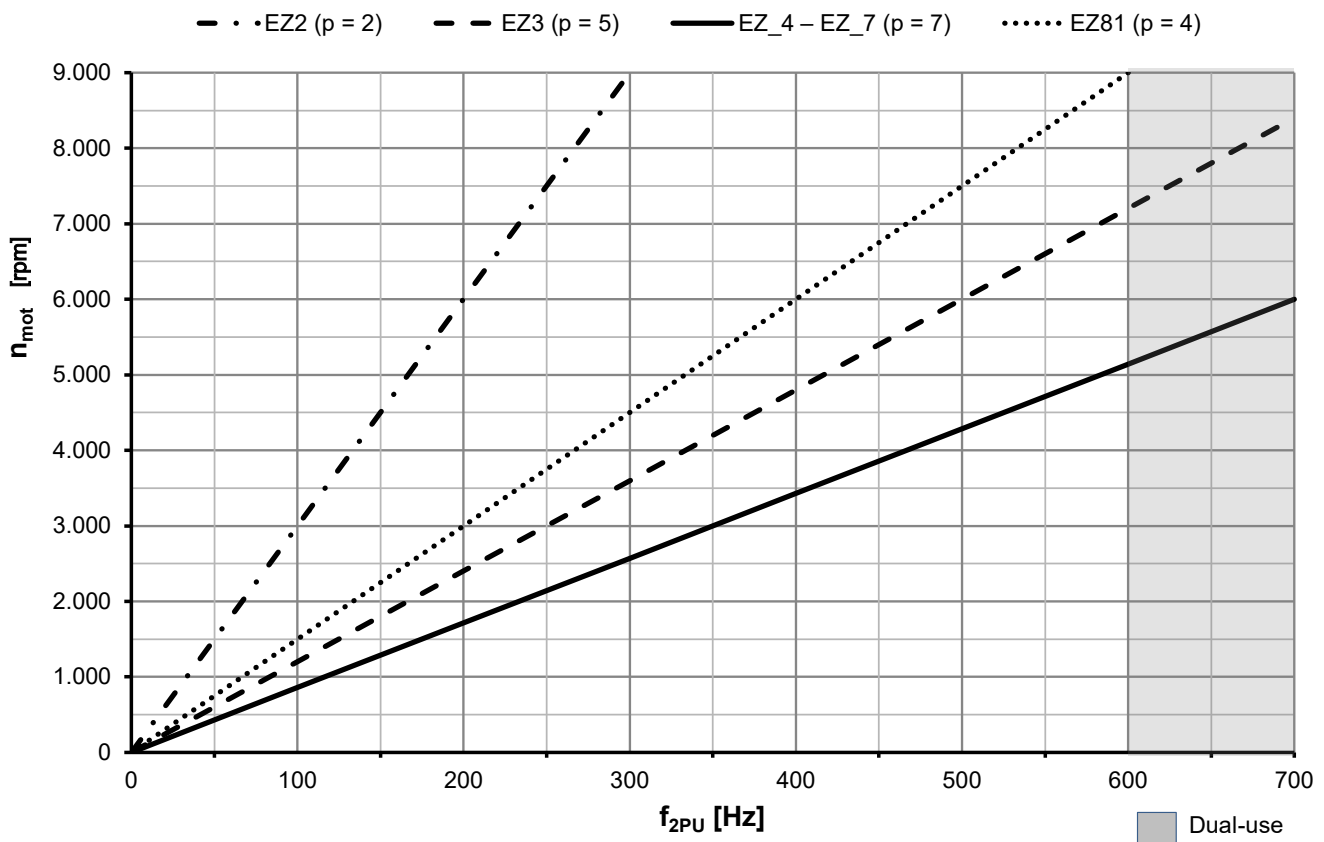


Fig. 1: Speed/frequency graph for EZ motors

18.1.2 Plug connectors (One Cable Solution)

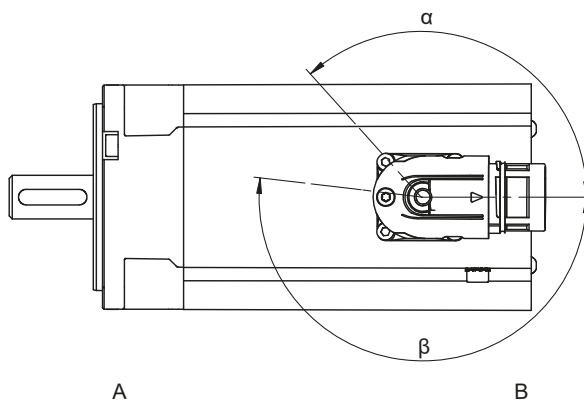
The One Cable Solution option is available for B&R, Control Techniques, Beckhoff, and Allen-Bradley drive controllers.

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector.

For motors with forced ventilation, avoid collisions between the motor connection cables and the plug connector of the forced ventilation unit. In the event of a collision, rotate the plug connectors of the motor by the required angle. Details on the position of the plug connector for the forced ventilation unit can be found in the chapter [▶ 17.4.5].

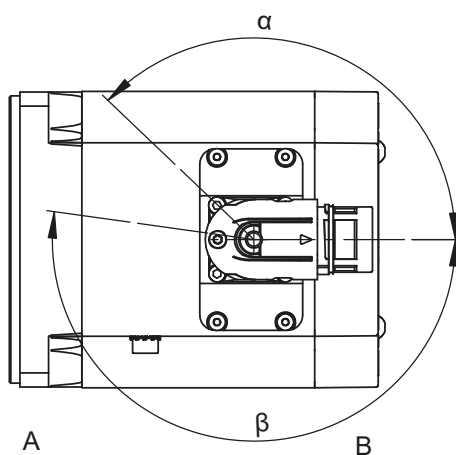
The figures represent the position of the plug connectors upon delivery.

Turning ranges of plug connectors (EZ2 – EZ3 motors)



A	Attachment or output side of the motor	B	Not output side
---	--	---	-----------------

Turning ranges of plug connectors (EZ4 – EZ7 motors)



A	Attachment or output side of the motor	B	Not output side
---	--	---	-----------------

Features of B&R/Beckhoff plug connectors

Motor type	Size	Connection	Turning range	
			α	β
EZ2 – EZ5, EZ701 – EZ703, EZ705U, EZ705B (n _N =3000 rpm)	con.23	Quick-lock	130°	190°

Features of Allen-Bradley plug connectors

Motor type	Size	Connection	Turning range	
			α	β
EZ3 – EZ5, EZ701 – EZ703, EZ705U (n _N =3000 rpm)	con.23	Quick-lock	130°	190°
EZ705U (n _N =4500 rpm), EZ705B, EZ813U	con.40	Quick-lock	130°	190°

Notes

- The number after "con." indicates the approximate external thread diameter of the plug connector in mm (for example, con.23 designates a plug connector with an external thread diameter of about 23 mm).

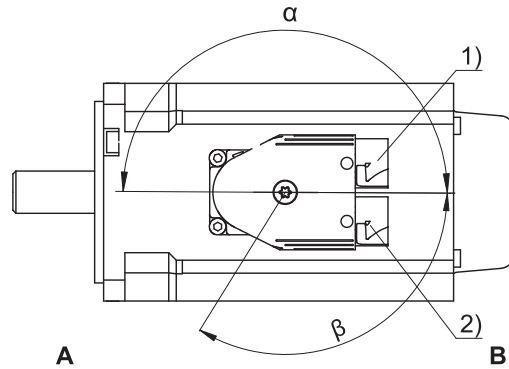
18.1.3 Plug connectors

In the standard version, STÖBER synchronous servo motors are equipped with rotatable plug connectors¹ for power and encoder connections. You can find detailed technical information about the plug connectors at <http://www.intercontec.biz>.

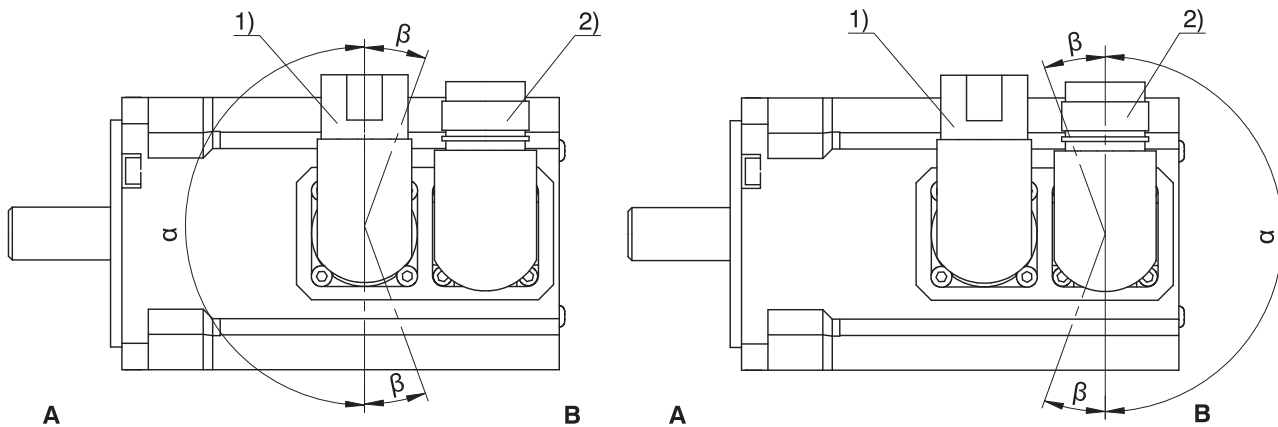
For motors with forced ventilation, avoid collisions between the motor connection cables and the plug connector of the forced ventilation unit. In the event of a collision, rotate the plug connectors of the motor by the required angle. Details on the position of the plug connector for the forced ventilation unit can be found in the chapter [▶ 17.4.6].

The figures represent the position of the plug connectors upon delivery.

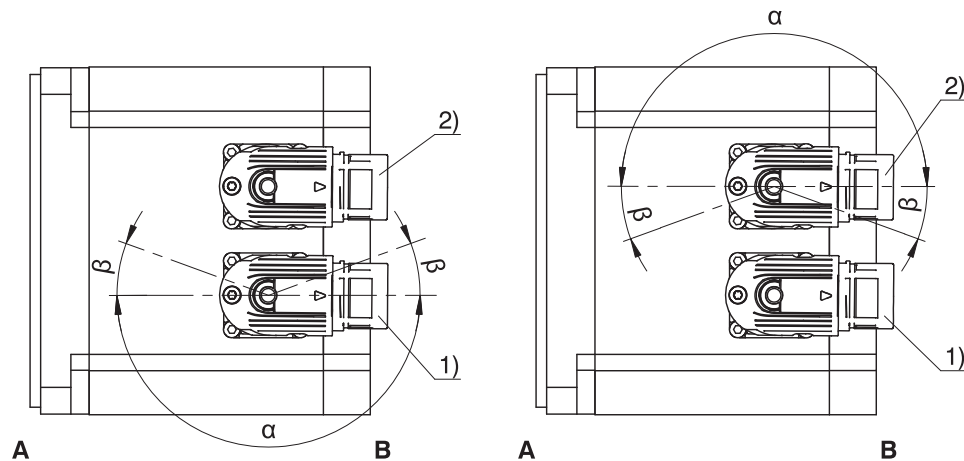
Turning ranges of con.15 ytec plug connectors (motors EZ2 – EZ3, EZ401, EZ402) for connection to B&R drive controllers (drive controller code GY)



Turning ranges of plug connectors (EZ2 – EZ3 motors)



Turning ranges of plug connectors (EZ4 – EZ8 motors)



- | | | | |
|---|--|---|------------------------|
| 1 | Power plug connector | 2 | Encoder plug connector |
| A | Attachment or output side of the motor | B | Not output side |

¹The connectors can be pivoted up to 10 times at a specific angle. They cannot be rotated repeatedly.

Power plug connector features

Motor type	Size	Connection	Turning range	
			α	β
EZ2 – EZ3, EZ401, EZ402	con.15 ²	Quick-lock (ytec)	180°	140°
EZ2 – EZ5, EZ701 – EZ703	con.23	Quick-lock	180°	40°
EZ705, EZ8	con.40	Quick-lock	180°	40°

Encoder plug connector features

Motor type	Size	Connection	Turning range	
			α	β
EZ2 – EZ3, EZ401, EZ402	con.15 ³	Quick-lock (ytec)	180°	140°
EZ404, EZ5, EZ7, EZ8	con.15 ⁴	Quick-lock (itec)	180°	20°
EZ2 – EZ8	con.15 ⁵	Quick-lock (itec)	180°	20°
EZ2 – EZ8	con.23	Quick-lock	180°	20°

Notes

- In turning range β , the power or encoder plug connectors can be turned only if doing so does not cause them to collide.
- The number after "con." indicates the approximate external thread diameter of the plug connector in mm (for example, con.23 designates a plug connector with an external thread diameter of about 23 mm).
- With ytec plug connectors, the power and encoder plug connectors are mechanically connected and can only be turned together.

18.1.4 Connection cables

The plug connectors and terminal assignment of STOBBER synchronous servo motors are designed for connecting to drive controllers from third-party manufacturers in a way that allows you to connect the original cable of the respective manufacturer. Keep the following information regarding cable quality and design in mind.

- Because the original cable from Bosch cannot be used, STOBBER offers suitable cables for this purpose. More detailed information is available from your STOBBER customer consultant.
- Ensure that the cable quality and cable design is suitable for the ambient conditions at the installation location.

You can find more detailed information on our cables in the connection method manual, ID 443101.

Enter the ID of the manual in the Search term field at <http://www.stoeber.de/en/downloads/>.

² Only for connection to B&R ACOPOS P3 with EnDat 2.2 (drive controller code GY)

³ Only for connection to B&R ACOPOS P3 with EnDat 2.2 (drive controller code GY)

⁴ Only for connection to B&R ACOPOS P3 with EnDat 2.2 (drive controller code GY)

⁵ Only for connection to B&R ACOPOSmulti with EnDat 2.2 (drive controller code GG)

18.2 Connection to B&R drive controllers

This chapter contains the information for connecting STOBBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBBER drive controllers. You can find all other information about STOBBER synchronous servo motors in the chapter [▶ 17].

STOBBER has taken the following measures to minimize the effort of commissioning STOBBER motors connected to B&R drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- The electronic nameplate of the motor was designed to be compatible with the B&R controllers.
- Parameter lists are available on request at systemsupport@stoeber.de.

More information on commissioning EZ motors connected to B&R drive controllers can be found in the 443184_en document in the download area on the STOBBER website.

18.2.1 Encoders

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQI 1131 Safety	S2	Inductive	4096	19 bit	524288	> 100	$\leq 15 \times 10^{-9}$
EnDat 2.2 EQN 1135 Safety	S3	Optical	4096	23 bit	8388608	> 100	$\leq 15 \times 10^{-9}$
EnDat 2.2 ECI 1118-G2	C5	Inductive	–	18 bit	262144	> 76	$\leq 1.5 \times 10^{-6}$

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$
EnDat 2.1 ECI 1118-G3	C2	Inductive	–	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$
EnDat 2.1 EQI 1130-G3	Q2	Inductive	4096	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.2.2 Resolver

In this chapter, you can find detailed technical data for the resolver that can be installed as an encoder in a STOBBER motor.

Feature	Description
Code	R0
Number of poles	2
Input voltage $U_{1\text{eff}}$	$7 \text{ V} \pm 5\%$
Input frequency f_1	10 kHz
Output voltage $U_{2,S1-S3}$	$K_{tr} \cdot U_{R1-R2} \cdot \cos \theta$
Output voltage $U_{2,S2-S4}$	$K_{tr} \cdot U_{R1-R2} \cdot \sin \theta$
Transformation ratio K_{tr}	$0.5 \pm 5\%$
Electrical fault	$\pm 10 \text{ arcmin}$
MTTF	> 100 years
PFH	$\leq 10^{-9}$

18.2.3 Possible combinations with drive controllers

The following table shows the possible combinations of STOBER synchronous servo motors with drive controllers from B&R depending on the encoder model.

Drive controller		ACOPOS Standard EnDat 2.1/re- solver	ACOPOSmulti EnDat 2.1/re- solver	ACOPOSmulti EnDat 2.2	ACOPOS P3 EnDat 2.2	ACOPOS P3 OCS EnDat 2.2	ACOPOSmulti OCS EnDat 2.2
Drive controller code		FG	FV	GG	GY	GP	GV
Connection plan ID		442313	442444	442677	443095	443022	443092
Encoder	Encoder code						
EnDat 2.2 EQI 1131 Safety	S2	–	–	EZ	EZ	EZ	EZ
EnDat 2.2 EQN 1135 Safety	S3	–	–	EZ	EZ	EZ	EZ
EnDat 2.2 ECI 1118-G2	C5	–	–	EZ	EZ	–	–
EnDat 2.1 EQN 1125	Q4	EZ	EZ	–	–	–	–
EnDat 2.1 ECI 1118-G3	C2	–	EZ	–	–	–	–
EnDat 2.1 EQI 1130-G3	Q2	–	EZ	–	–	–	–
Resolvers	R0	EZ	EZ	–	–	–	–

The encoder and drive controller codes are a part of the type designation of the motor.

18.2.4 Connection assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.15

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
	3	1BD1 (brake +)
	4	1BD2 (brake -)
5		
⊕	PE (grounding conductor)	

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	3	1W1 (W phase)
	4	1V1 (V phase)
	A	1TP1 (temperature sensor +)
	B	1TP2 (temperature sensor -)
	C	1BD1 (brake +)
	D	1BD2 (brake -)
	⊕	PE (grounding conductor)

Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
	⊕	PE (grounding conductor)

18.2.5 Connection assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.2 digital encoder, plug connector size con.15

Connection diagram	Pin	Connection
	1	Up +
	2	Data +
	3	Data -
	4	Clock +
	5	Clock -
	6	
	7	0 V GND
	8	
	9	
	10	
	11	
	12	

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

Connection diagram	Pin	Connection
	1	Up sense
	2	
	3	
	4	0 V sense
	5	
	6	
	7	Up +
	8	Clock +
	9	Clock -
	10	0 V GND
	11	
	12	B + (Sin +)
	13	B - (Sin -)
	14	Data +
	15	A + (Cos +)
	16	A - (Cos -)
	17	Data -

Resolver, plug connector size con.23

Connection diagram	Pin	Connection
	1	
	2	
	3	S4 Sin +
	4	S1 Cos -
	5	R2 Ref +
	6	
	7	S2 Sin -
	8	S3 Cos +
	9	R1 Ref -
	10	
	11	
	12	

18.2.6 Terminal assignment for plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector. The temperature sensor of the motor is connected to the encoder internally. The measured values from the temperature sensor are transmitted via the log of the encoder.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	D	
	1	Up +
	2	0 V GND
	3	Data +
	4	Data -
	5	Clock +
	6	Clock -
7	1BD2 (brake -)	
8	1BD1 (brake +)	
⊕	PE (grounding conductor)	

a) Coaxial shield to which the shield of the encoder cores is connected

18.3 Connection to Control Techniques drive controllers

This chapter contains the information for connecting STOBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBER drive controllers. You can find all other information about STOBER synchronous servo motors in the chapter [▶ 17].

STOBER has taken the following measures to minimize the effort of commissioning STOBER motors connected to Control Techniques drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- Parameter lists are available on request at systemsupport@stoerber.de.

18.3.1 Encoder

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQI 1131 Safety	S2	Inductive	4096	19 bit	524288	> 100	$\leq 15 \times 10^{-9}$
EnDat 2.2 EQN 1135 Safety	S3	Optical	4096	23 bit	8388608	> 100	$\leq 15 \times 10^{-9}$

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$
EnDat 2.1 ECI 1118-G3	C2	Inductive	–	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$
EnDat 2.1 EQI 1130-G3	Q2	Inductive	4096	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.3.2 Resolver

In this chapter, you can find detailed technical data for the resolver that can be installed as an encoder in a STOBER motor.

Feature	Description
Code	R0
Number of poles	2
Input voltage $U_{1\text{eff}}$	$7 \text{ V} \pm 5\%$
Input frequency f_1	10 kHz
Output voltage $U_{2,S1-S3}$	$K_{tr} \cdot U_{R1-R2} \cdot \cos \theta$
Output voltage $U_{2,S2-S4}$	$K_{tr} \cdot U_{R1-R2} \cdot \sin \theta$
Transformation ratio K_{tr}	$0.5 \pm 5\%$
Electrical fault	$\pm 10 \text{ arcmin}$
MTTF	> 100 years
PFH	$\leq 10^{-9}$

18.3.3 Possible combinations with drive controllers

The following table shows the possible combinations of STOBER synchronous servo motors with drive controllers from Control Techniques depending on the encoder model.

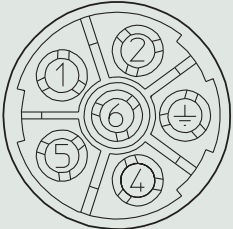
Drive controller		Unidrive EnDat 2.1/Resolver	Digitax OCS EnDat 2.2
Drive controller code		GE	HH
Connection plan ID		442555	443177
Encoder	Encoder code		
EnDat 2.2 EQI 1131 Safety	S2	–	EZ
EnDat 2.2 EQN 1135 Safety	S3	–	EZ
EnDat 2.1 EQN 1125	Q4	EZ	–
EnDat 2.1 ECI 1118-G3	C2	EZ	–
EnDat 2.1 EQI 1130-G3	Q2	EZ	–
Resolvers	R0	EZ	–

The encoder and drive controller codes are a part of the type designation of the motor.

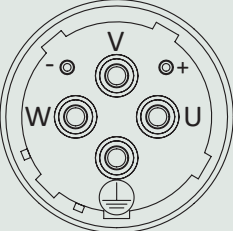
18.3.4 Terminal assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	2	1V1 (V phase)
	4	1W1 (W phase)
	5	1BD1 (brake +)
	6	1BD2 (brake –)
	⊕	PE (grounding conductor)

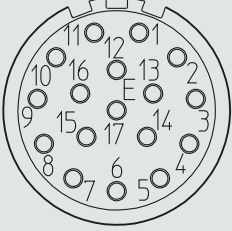
Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake –)
	⊕	PE (grounding conductor)

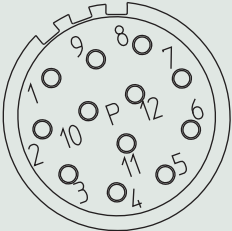
18.3.5 Terminal assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

Connection diagram	Pin	Connection
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
	3	
	4	
	5	
	6	
	7	
	8	Clock +
	9	Clock -
	10	A + (Cos +)
	11	Data +
	12	Data -
	13	A - (Cos -)
	14	B + (Sin +)
	15	B - (Sin -)
	16	Up +
	17	0 V GND

Resolver, plug connector size con.23

Connection diagram	Pin	Connection
	1	R2 Ref +
	2	R1 Ref -
	3	S3 Cos +
	4	S1 Cos -
	5	S4 Sin +
	6	S2 Sin -
	7	1TP1 (temperature sensor +)
	8	1TP2 (temperature sensor -)
	9	
	10	
	11	
	12	

18.3.6 Terminal assignment for plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector. The temperature sensor of the motor is connected to the encoder internally. The measured values from the temperature sensor are transmitted via the log of the encoder.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	D	
	1	Up +
	2	0 V GND
	3	Data +
	4	Data -
	5	Clock +
	6	Clock -
7	1BD2 (brake -)	
8	1BD1 (brake +)	
⊕	PE (grounding conductor)	

a) Coaxial shield to which the shield of the encoder cores is connected

18.4 Connection to Siemens drive controllers

This chapter contains the information for connecting STOBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBER drive controllers. You can find all other information about STOBER synchronous servo motors in the chapter [▶ 17].

STOBER has taken the following measures to minimize the effort of commissioning STOBER motors connected to SINAMICS S120 drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- Parameter lists are available on request at systemsupport@stoerber.de.

More information on commissioning EZ motors connected to SINAMICS S120 drive controllers can be found in the 443232_en document in the download area on the STOBER website.

18.4.1 Encoders

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$

Notes

- The encoder code is a part of the type designation of the motor.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.4.2 Resolver

In this chapter, you can find detailed technical data for the resolver that can be installed as an encoder in a STOBER motor.

Feature	Description
Code	R0
Number of poles	2
Input voltage $U_{1\text{eff}}$	$7 \text{ V} \pm 5\%$
Input frequency f_1	10 kHz
Output voltage $U_{2,S1-S3}$	$K_{tr} \cdot U_{R1-R2} \cdot \cos \theta$
Output voltage $U_{2,S2-S4}$	$K_{tr} \cdot U_{R1-R2} \cdot \sin \theta$
Transformation ratio K_{tr}	$0.5 \pm 5\%$
Electrical fault	$\pm 10 \text{ arcmin}$
MTTF	> 100 years
PFH	$\leq 10^{-9}$

18.4.3 Possible combinations with drive controllers

The following table shows the possible combinations of STOBER synchronous servo motors with drive controllers from Siemens depending on the encoder model.

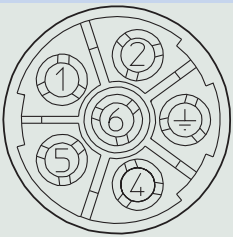

Drive controller		SINAMICS S120
Drive controller code		FJ
Connection plan ID		442315
Encoder	Encoder code	
EnDat 2.1 EQN 1125	Q4	EZ
Resolvers	R0	EZ

The encoder and drive controller codes are a part of the type designation of the motor.

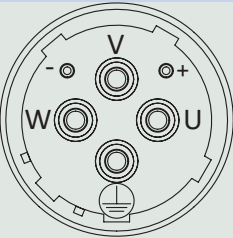

18.4.4 Connection assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	2	1V1 (V phase)
	4	1BD1 (brake +)
	5	1BD2 (brake -)
	6	1W1 (W phase)
		PE (grounding conductor)

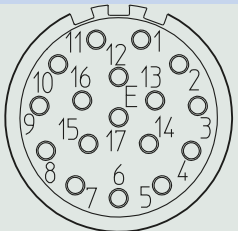
Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
		PE (grounding conductor)

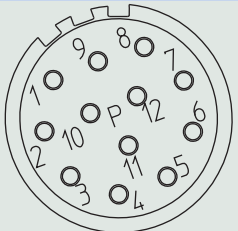
18.4.5 Connection assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

Connection diagram	Pin	Connection
	1	A + (Cos +)
	2	A - (Cos -)
	3	Data +
	4	
	5	Clock +
	6	
	7	0 V GND
	8	1TP1 (temperature sensor +)
	9	1TP2 (temperature sensor -)
	10	Up +
	11	B + (Sin +)
	12	B - (Sin -)
	13	Data -
	14	Clock -
	15	0 V sense
	16	Up sense
	17	

Resolver, plug connector size con.23

Connection diagram	Pin	Connection
	1	S4 Sin +
	2	S2 Sin -
	3	
	4	
	5	
	6	
	7	R1 Ref -
	8	1TP1 (temperature sensor +)
	9	1TP2 (temperature sensor -)
	10	R2 Ref +
	11	S3 Cos +
	12	S1 Cos -

18.5 Connection to Kollmorgen drive controllers

This chapter contains the information for connecting STOBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBER drive controllers. You can find all other information about STOBER synchronous servo motors in the chapter [▶ 17].

STOBER has taken the following measures to minimize the effort of commissioning STOBER motors connected to Kollmorgen drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- Parameter lists are available on request at systemsupport@stoerber.de.

More information on commissioning EZ motors connected to Kollmorgen drive controllers can be found in the 443236_en document in the download area on the STOBER website.

18.5.1 Encoders

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQI 1131 Safety	S2	Inductive	4096	19 bit	524288	> 100	$\leq 15 \times 10^{-9}$

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.5.2 Resolver

In this chapter, you can find detailed technical data for the resolver that can be installed as an encoder in a STOBER motor.

Feature	Description
Code	R0
Number of poles	2
Input voltage $U_{1\text{eff}}$	$7 \text{ V} \pm 5\%$
Input frequency f_1	10 kHz
Output voltage $U_{2,S1-S3}$	$K_{tr} \cdot U_{R1-R2} \cdot \cos \theta$
Output voltage $U_{2,S2-S4}$	$K_{tr} \cdot U_{R1-R2} \cdot \sin \theta$
Transformation ratio K_{tr}	$0.5 \pm 5\%$
Electrical fault	$\pm 10 \text{ arcmin}$
MTTF	> 100 years
PFH	$\leq 10^{-9}$

18.5.3 Possible combinations with drive controllers

The following table shows the possible combinations of STOBER synchronous servo motors with drive controllers from Kollmorgen depending on the encoder model.

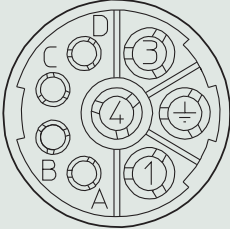
Drive controller		Servostar S300-700
Drive controller code		EnDat 2.2/EnDat 2.1/resolver FE
Connection plan ID		442311
Encoder	Encoder code	
EnDat 2.2 EQI 1131 Safety	S2	EZ
EnDat 2.1 EQN 1125	Q4	EZ
Resolvers	R0	EZ

The encoder and drive controller codes are a part of the type designation of the motor.

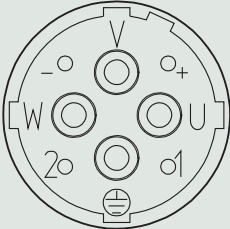
18.5.4 Connection assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	3	1W1 (W phase)
	4	1V1 (V phase)
	A	1BD1 (brake +)
	B	1BD2 (brake -)
	C	
	D	
	⊕	PE (grounding conductor)

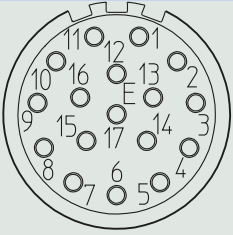
Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
	1	
	2	
	⊕	PE (grounding conductor)

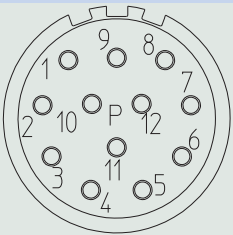
18.5.5 Connection assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

Connection diagram	Pin	Connection
	1	B - (Sin -)
	2	0 V GND
	3	A - (Cos -)
	4	Up +
	5	Data +
	6	
	7	1TP1 (temperature sensor +)
	8	Clock +
	9	B + (Sin +)
	10	0 V sense
	11	A + (Cos +)
	12	Up sense
	13	Data -
	14	1TP2 (temperature sensor -)
	15	Clock -
	16	
	17	

Resolver, plug connector size con.23

Connection diagram	Pin	Connection
	1	
	2	1TP1 (temperature sensor +)
	3	S4 Sin +
	4	S3 Cos +
	5	R2 Ref +
	6	1TP2 (temperature sensor -)
	7	S2 Sin -
	8	S1 Cos -
	9	R1 Ref -
	10	
	11	
	12	

18.6 Connection to Bosch drive controllers

This chapter contains the information for connecting STOBBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBBER drive controllers. You can find all other information about STOBBER synchronous servo motors in the chapter [▶ 17].

STOBBER has taken the following measures to minimize the effort of commissioning STOBBER motors connected to IndraDrive C/Cs drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- Parameter lists are available on request at systemsupport@stoeber.de.

More information on commissioning EZ motors connected to IndraDrive C/Cs drive controllers can be found in the 443235_en document in the download area on the STOBBER website.

18.6.1 Encoders

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$
EnDat 2.1 ECI 1118-G3	C2	Inductive	–	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$
EnDat 2.1 EQI 1130-G3	Q2	Inductive	4096	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$

Encoders with HIPERFACE interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
SKM36	H1	Optical	4096	12 bit	4096	Sin/cos 128	> 100	$\leq 5.4 \times 10^{-7}$

Notes

- The encoder code is a part of the type designation of the motor.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.6.2 Possible combinations with drive controllers

The following table shows the possible combinations of STOBBER synchronous servo motors with drive controllers from Bosch depending on the encoder model.

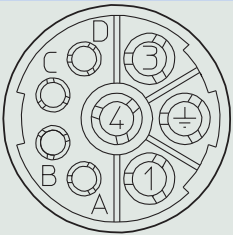
Drive controller	IndraDrive C/Cs EnDat 2.1/HIPERFACE
Drive controller code	FW
Connection plan ID	442445
Encoder	Encoder code
EnDat 2.1 EQN 1125	Q4
EnDat 2.1 ECI 1118-G3	C2
EnDat 2.1 EQI 1130-G3	Q2
SKM36	H1
	EZ

The encoder and drive controller codes are a part of the type designation of the motor.

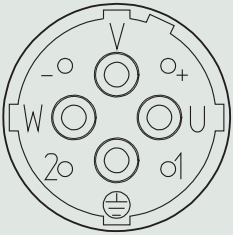
18.6.3 Connection assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	3	1V1 (V phase)
	4	1W1 (W phase)
	A	1BD1 (brake +)
	B	1BD2 (brake -)
	C	1TP1 (temperature sensor +)
	D	1TP2 (temperature sensor -)
⊕	PE (grounding conductor)	

Plug connector size con.40

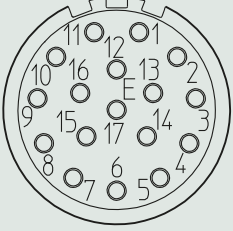
Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
⊕	PE (grounding conductor)	

18.6.4 Connection assignment of the encoder plug connector

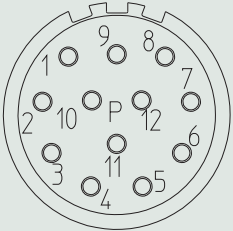
The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

This terminal assignment only applies to the IndraDrive C/Cs drive controller.

Connection diagram	Pin	Connection
	1	Up sense
	2	
	3	
	4	0 V sense
	5	
	6	
	7	Up +
	8	Clock +
	9	Clock -
	10	0 V GND
	11	
	12	B + (Sin +)
	13	B - (Sin -)
	14	Data +
	15	A + (Cos +)
	16	A - (Cos -)
	17	Data -

HIPERFACE encoder, plug connector size con.23

Connection diagram	Pin	Connection
	1	Us
	2	0 V GND
	3	REFSIN
	4	REFCOS
	5	Data +
	6	Data -
	7	+ SIN
	8	+ COS
	9	
	10	
	11	
	12	

18.7 Connection to Beckhoff drive controllers

This chapter contains the information for connecting STOBBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBBER drive controllers. You can find all other information about STOBBER synchronous servo motors in the chapter [▶ 17].

STOBBER has taken the following measures to minimize the effort of commissioning STOBBER motors connected to AX5000 and AX8000 drive controllers and avoiding errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- Parameter lists are available on request at systemsupport@stoeber.de.

More information on commissioning EZ motors connected to Beckhoff drive controllers can be found in the 443185_en document in the download area on the STOBBER website.

18.7.1 Encoders

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQI 1131 Safety	S2	Inductive	4096	19 bit	524288	> 100	$\leq 15 \times 10^{-9}$
EnDat 2.2 EQN 1135 Safety	S3	Optical	4096	23 bit	8388608	> 100	$\leq 15 \times 10^{-9}$

Encoders with EnDat 2.1 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	Periods per revolution	MTTF [years]	PFH [h]
EnDat 2.1 EQN 1125	Q4	Optical	4096	13 bit	8192	Sin/cos 512	> 57	$\leq 2 \times 10^{-6}$
EnDat 2.1 EQI 1130-G3	Q2	Inductive	4096	18 bit	262144	Sin/cos 16	> 100	$\leq 6 \times 10^{-7}$

Encoders with HIPERFACE DSL interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EDM35	H6	Optical	4096	20 bit	1048576	> 100	$\leq 31 \times 10^{-9}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.7.2 Possible combinations with drive controllers

The following table shows the possible combinations of STOBER synchronous servo motors with drive controllers from Beckhoff depending on the encoder model.

Drive controller		AX5000 8-pin ⁶ EnDat 2.1	AX8000/5000 OCS 9-pin ⁷ HIPERFACE DSL	AX5000 9-pin ⁸ EnDat 2.1	AX8000 9-pin ⁹ EnDat 2.2
Drive controller code		FM	HK	HN	HO
Connection plan ID		442318	443393	443451	443452
Encoder	Encoder code				
EnDat 2.2 EQI 1131 Safety	S2				EZ
EnDat 2.2 EQN 1135 Safety	S3				EZ
EnDat 2.1 EQN 1125	Q4	EZ		EZ	
EnDat 2.1 EQI 1130- G3	Q2			EZ	
EDM35	H6		EZ		

The encoder and drive controller codes are a part of the type designation of the motor.

18.7.3 Terminal assignment of 8-pin power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	1	1U1 (U phase)
	3	1W1 (W phase)
	4	1V1 (V phase)
	A	1BD1 (brake +)
	B	1BD2 (brake -)
	C	1TP1 (temperature sensor +)
	D	1TP2 (temperature sensor -)
	⊕	PE (grounding conductor)

Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	1BD1 (brake +)
	-	1BD2 (brake -)
	1	1TP1 (temperature sensor +)
	2	1TP2 (temperature sensor -)
⊕	PE (grounding conductor)	

⁶Design of the power connector

⁷Design of the power connector

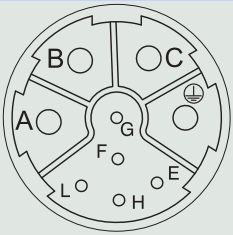
⁸Design of the power connector

⁹Design of the power connector

18.7.4 Terminal assignment of 9-pin power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

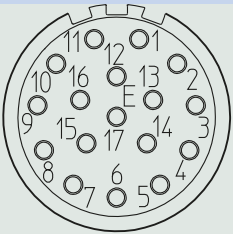
Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	E	1TP2 (temperature sensor -)
	F	
	G	1BD1 (brake +)
	H	1TP1 (temperature sensor +)
	L	1BD2 (brake -)
	⊕	PE (grounding conductor)

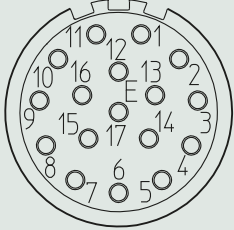
18.7.5 Connection assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the type of encoder installed and the size of the motor.

EnDat 2.2 digital encoder, plug connector size con.23

Connection diagram	Pin	Connection
	1	
	2	0 V GND
	3	
	4	Up +
	5	Data +
	6	
	7	
	8	Clock +
	9	
	10	0 V sense
	11	
	12	Up sense
	13	Data -
	14	
	15	Clock -
	16	
	17	

EnDat 2.1 encoder with sin/cos incremental signals, plug connector size con.23

Connection diagram	Pin	Connection
	1	B - (Sin -)
	2	0 V GND
	3	A - (Cos -)
	4	Up +
	5	Data +
	6	
	7	
	8	Clock +
	9	B + (Sin +)
	10	0 V sense
	11	A + (Cos +)
	12	Up sense
	13	Data -
	14	
	15	Clock -
	16	
	17	

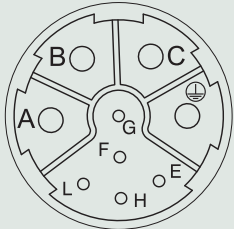

18.7.6 Terminal assignment for plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector.

The size of the plug connector depends on the size of the motor.

The temperature sensor of the motor is connected to the encoder internally. The measured values from the temperature sensor are transmitted via the log of the encoder.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	E	DSL- (L)
	F	DSL shield
	G	1BD1
	H	DSL+ (H)
	L	1BD2
		PE (grounding conductor)

18.8 Connection to Allen-Bradley drive controllers

This chapter contains the information for connecting STOBBER synchronous servo motors to drive controllers of the above-named manufacturer which differs from connecting to STOBBER drive controllers. You can find all other information about STOBBER synchronous servo motors in the chapter [▶ 17].

The STOBBER EZ geared motors can be parameterized to Kinetix 5500/5700/6500 drive controllers fully automatically. EZ motors without an attached gearbox and other STOBBER series are excluded.

STOBBER has taken the following measures to minimize the effort of commissioning STOBBER motors connected to Allen-Bradley drive controllers and avoid errors during parameterization:

- The commutation offset of the motor was set so that calibration by the customer is not necessary.
- The electronic nameplate of the motor was designed to be compatible with the Kinetix 5500/5700/6500.
- STOBBER tests the motor connected to Allen-Bradley drive controllers before delivery to the customer.
- Parameter lists are available on request at systemsupport@stoeber.de.

More information on commissioning EZ motors connected to Allen-Bradley drive controllers can be found in the 443244_en document in the download area on the STOBBER website.

18.8.1 Encoders

Information

The safety functionality of the encoders cannot be used in combination with Allen-Bradley drive controllers because, for applications with safety functionality, Allen-Bradley only permits its own motors.

Encoders with EnDat 2.2 interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EnDat 2.2 EQN 1135 Safety	S3	Optical	4096	23 bit	8388608	> 100	$\leq 15 \times 10^{-9}$

Encoders with HIPERFACE DSL interface

Encoder model	Code	Measuring method	Recordable revolutions	Resolution	Position values per revolution	MTTF [years]	PFH [h]
EDM35	H6	Optical	4096	20 bit	1048576	> 100	$\leq 31 \times 10^{-9}$

Notes

- The encoder code is a part of the type designation of the motor.
- Safety = Safety-related position measuring system for use in safety-oriented applications.
- Multiple revolutions of the motor shaft can be recorded only using multi-turn encoders.

18.8.2 Possible combinations with drive controllers

The following table shows the possible combinations of STÖBER motors and geared motors with drive controllers from Allen-Bradley depending on the encoder model.

Information

The safety functionality of the encoders cannot be used in combination with Allen-Bradley drive controllers because, for applications with safety functionality, Allen-Bradley only permits its own motors.

Drive controller		KINETIX 5500 OCS	KINETIX 5700 OCS	KINETIX 5700	KINETIX 6500
		HIPERFACE DSL	HIPERFACE DSL	EnDat 2.2	EnDat 2.2
Drive controller code		HB	GD	HA	GC
Connection plan ID		443169	442449	443096	442448
Encoder	Encoder code				
EnDat 2.2 EQN	S3	–	–	EZ	EZ
1135 Safety					
EDM35	H6	EZ	EZ	–	–

The encoder and drive controller codes are a part of the type designation of the motor.

18.8.3 Terminal assignment of the power plug connector

The size and connection diagram of the power plug connector depend on the size of the motor.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	F	MBRK + (1BD1)
	G	MBRK – (1BD2)
	E	
	H	
	L	
		PE (grounding conductor)

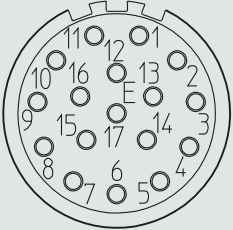
Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	+	MBRK + (1BD1)
	-	MBRK – (1BD2)
	1	
	2	
		PE (grounding conductor)

18.8.4 Terminal assignment of the encoder plug connector

The size and terminal assignment of the encoder plug connectors depend on the model of encoder installed and the size of the motor.

EnDat 2.2 digital encoder, plug connector size con.23

Connection diagram	Pin	Connection
	1	
	2	
	3	
	4	
	5	DATA +
	6	DATA -
	7	CLK + (Clock +)
	8	CLK - (Clock -)
	9	EPWR_5V (Up +)
	10	ECOM (0 V)
	11	
	12	
	13	TS + (1TP1)
	14	TS - (1TP2)
	15	
	16	
	17	

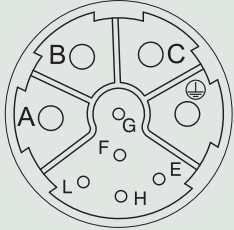
18.8.5 Terminal assignment for plug connectors (One Cable Solution)

In the One Cable Solution design, the power and encoder lines are connected using a shared plug connector.

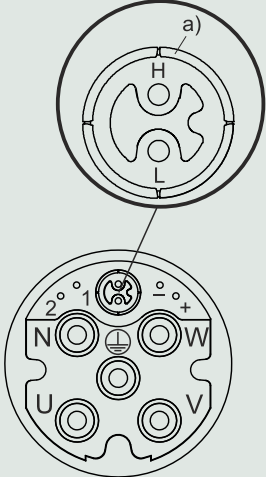
The size of the plug connector depends on the size of the motor.

The temperature sensor of the motor is connected to the encoder internally. The measured values from the temperature sensor are transmitted via the log of the encoder.

Plug connector size con.23

Connection diagram	Pin	Connection
	A	1U1 (U phase)
	B	1V1 (V phase)
	C	1W1 (W phase)
	E	DATA + (DSL +)
	F	MBRK + (1BD1)
	G	MBRK - (1BD2)
	H	DATA - (DSL -)
	L	
	⊕	PE (grounding conductor)

Plug connector size con.40

Connection diagram	Pin	Connection
	U	1U1 (U phase)
	V	1V1 (V phase)
	W	1W1 (W phase)
	N	
	+	
	-	
	1	MBRK + (1BD1)
	2	MBRK - (1BD2)
	H	DATA - (DSL -)
	L	DATA + (DSL +)
⊕	PE (grounding conductor)	

a) Coaxial shield to which the DSL shield is connected



24

19 Close to customers around the world

Service Network

You can rely on our strong partners when it comes to service. They guide you through commissioning and offer expert technical advice.

International Service Network

Thanks to our large and long-standing international network, we offer worldwide service and continuous support. In over 40 countries. Put your trust in our expertise.

Service hotline

+49 7231 582-3000 We are available around the clock.

Do you value international availability and global service? We are here for you.

STOBER AUSTRIA

www.stoerber.at
+43 7613 7600-0
sales@stoerber.at

STOBER FRANCE

www.stoerber.fr
+33 478 98 91 80
sales@stoerber.fr

STOBER ITALY

www.stoerber.it
+39 02 93909570
sales@stoerber.it

STOBER KOREA

www.stoerber.kr
+82 10 5681 6298
sales@stoerber.kr

STOBER SWITZERLAND

www.stoerber.ch
+41 56 496 96 50
sales@stoerber.ch

STOBER TURKEY

www.stoerber.com
+90 216 510 2290
sales-turkey@stoerber.com

STOBER USA

www.stoerber.com
+1 606 759 5090
sales@stoerber.com

STOBER CHINA

www.stoerber.cn
+86 512 5320 8850
sales@stoerber.cn

STOBER Germany

www.stoerber.de
+49 7231 582-0
sales@stoerber.de

STOBER JAPAN

www.stoerber.co.jp
+81-3-5875-7583
sales@stoerber.co.jp

STOBER SWEDEN

www.stoerber.com
+46 702 394 675
neil.arstad@stoerber.de

STOBER TAIWAN

www.stoerber.tw
+886 4 2358 6089
sales@stoerber.tw

STOBER UK

www.stoerber.co.uk
+44 1543 458 858
sales@stoerber.co.uk

20 Appendix

Table of contents

20.1 Symbols in formulas	636
20.2 Trademarks	641
20.3 Sales terms and delivery conditions	641

20.1 Symbols in formulas

The formula symbols for values actually present in the application are marked with *.

Symbol	Unit	Explanation
a_{th}	–	Parameter for calculating $K_{mot,th}$
a_{thEL}	–	Parameters for calculating $K_{mot,th}$ (dependent on the mounting position)
B_{10}	–	Number of cycles after which 10% of components have failed
B_{10D}	–	Number of cycles until 10% of components have failed dangerously
C_2	Nm/ arcmin	Torsional stiffness relative to the gearbox output
C_{2k}	Nm/arcmin	Tilting stiffness
C_{dyn}	N	Dynamic bearing load rating
ΔJ_B	kgcm ²	Additive mass moment of inertia of a motor with brake
Δm_B	kg	Additive weight of a motor with brake
Δn_1	rpm	Speed difference at the input
Δn_2	rpm	Speed difference at the output
$\Delta \phi_2$	arcmin	Backlash at the output shaft with a blocked input
$\Delta \phi_{2red}$	arcmin	Reduced backlash at the output shaft with a blocked input
$\Delta \phi_{2redI}$	arcmin	Reduced backlash (backlash class I) at the output shaft with a blocked input
$\Delta \phi_{2redII}$	arcmin	Reduced backlash (backlash class II) at the output shaft with a blocked input
Δt	s	Timespan
$\Delta \vartheta$	K	Temperature difference
η_{lget}	%	Efficiency of the gearbox at nominal torque
η_{lgt}	%	Efficiency of the screw drive
ED_{10}	%	Duty cycle based on 10 minutes
F_{2ax}^*	N	Actual axial force at the gearbox output
F_{2ax100}	N	Permitted axial force at the gearbox output for $n_{2m}^* \leq 100$ rpm (without radial force)
F_{2ax20}	N	Permitted axial force at the gearbox output for $n_{2m}^* \leq 20$ rpm (without radial force)
$F_{2ax,eq}^*$	N	Actual equivalent axial force on the gearbox output
F_{2axN}	N	Permitted nominal axial force at the gearbox output (without radial force)
f_{2PU}	Hz	Output frequency of the power unit
$f_{PWM,PU}$	kHz	Frequency of the pulse width modulation of the power unit
F_{2rad}^*	N	Actual radial force on the gearbox output
$F_{2rad100}$	N	Permitted radial force at the gearbox output for $n_{2m}^* \leq 100$ rpm
F_{2rad20}	N	Permitted radial force on the gearbox output for $n_{2m}^* \leq 20$ rpm
$F_{2rad,acc}$	N	Permitted radial acceleration force at the gearbox output
$F_{2rad,acc}^*$	N	Radial acceleration force present at the gearbox output
$F_{2rad,acc,1}^*$	N	Radial acceleration force present at the gearbox output in the first time period
$F_{2rad,acc,n}^*$	N	Radial acceleration force present at the gearbox output in the nth time period
$F_{2rad,eq}^*$	N	Actual equivalent force at the gearbox output
F_{2radN}	N	Permitted nominal radial force at the gearbox output
F_{ax}	N	Permitted axial force on the output
F_{ax}^*	N	Actual axial force on the output
$F_{ax,1}^* - F_{ax,n}^*$	N	Actual axial force in the respective time segment
$F_{ax,1}^* - F_{ax,n}^*$	N	Actual axial force in the respective time segment
F_{ax100}	N	Permitted axial force on the output for $n_m^* \leq 100$ rpm
F_{ax300}	N	Permitted axial force on the output for $n_m^* \leq 300$ rpm
$F_{ax,eff}^*$	N	Actual effective axial force on the output
$F_{ax,ss}$	N	Axial force that can be transmitted by the shrink ring
fB_{op}	–	Operating mode operating factor
fB_t	–	Runtime operating factor
fB_T	–	Temperature operating factor
fB_{zB}	–	Operating factor for cyclic operation
F_{rad}	N	Permitted radial force on the output

Symbol	Unit	Explanation
F_{rad*}	N	Actual radial force on the output
F_{rad100}	N	Permitted radial force on the output for $n_{m*} \leq 100$ rpm
F_{rad300}	N	Permitted radial force on the output for $n_{m*} \leq 300$ rpm
$F_{rad,eq*}$	N	Actual equivalent radial force at the output
H	m	Installation altitude above sea level
i	–	Gear ratio
i_{exact}	–	Mathematically exact gear ratio
I	A	Current
I_0	A	Stall current
I_{max}	A	Maximum current
I_N	A	Nominal current
$I_{N,B}$	A	Nominal current of the brake at 20 °C
$I_{N,F}$	A	Nominal current of the forced ventilation unit
J_1	kgcm ²	Mass moment of inertia relative to the gearbox input
J_{Bstop}	kgcm ²	Reference mass moment of inertia when braking from full speed: $J_{Bstop} = J_{dyn} \times 2$
J_{dyn}	kgcm ²	Mass moment of inertia of a motor in dynamic operation
J_{tot}	kgm ²	Total mass moment of inertia (based on the motor shaft)
K_{EM}	V/1000 rpm	Voltage constant: peak value of the induced voltage between the phases U, V, W of the motor at operating temperature at a speed of 1000 rpm
K_H	–	Derating factor for installation altitude
K_{MO}	Nm/A	Torque constant: ratio of the stall torque and frictional torque to the stall current; $K_{MO} = (M_0 + M_R) / I_0$ (tolerance $\pm 10\%$)
$K_{M,N}$	Nm/A	Torque constant: ratio of the nominal torque M_N to the nominal current I_N ; $K_{M,N} = M_N / I_N$ (tolerance $\pm 10\%$)
$K_{mot,th}$	–	Factor for determining the thermal limit torque
K_θ	–	Derating factor for surrounding temperature
l	mm	Length of the output shaft
L_{10}	–	Nominal bearing service life for a survival probability of 90% in 10^6 rollovers
L_{10h}	h	Bearing service life
$L_{pA,F}$	dB(A)	Noise level of the forced ventilation unit in the optimal operating range
L_{U-V}	mH	Winding inductance of a motor between two phases (determined in a resonant circuit)
LW	-	Load change: A load change (LW) corresponds to an acceleration and a deceleration.
m	kg	Weight (for gearboxes without lubricant)
M	Nm	Torque
M	Nm	Absolute value of torque
M_0	Nm	Stall torque: The continuous torque the motor is able to deliver at a speed of 10 rpm (tolerance $\pm 5\%$)
$M_{1*} - M_{4*}$	Nm	Actual torque of the motor in the respective time segment (1 to 4)
M_{1acc*}	Nm	Actual acceleration torque at the gearbox input
M_{1eff*}	Nm	Actual effective torque at the gearbox input
M_2	Nm	Torque at the gearbox output
M_2	Nm	Absolute value of torque on the output
$M_{2,0}$	Nm	Stall torque on the gearbox output
$M_{2,1*} - M_{2,4*}$	Nm	Actual torque in the respective time segment (1 to 4)
$M_{2,n*}$	Nm	Actual torque in the n-th time segment
M_{2acc}	Nm	Maximum permitted acceleration torque on the gearbox output
M_{2acc*}	Nm	Actual acceleration torque on the gearbox output
$M_{2acc,max}$	Nm	Maximum permitted acceleration torque of a group of geared motors whose size and nominal torque n_{1N} are the same
M_{2accHT}	Nm	Maximum permitted acceleration torque on the gearbox output with reduced backlash
M_{2eff*}	Nm	Actual effective torque on the gearbox output
M_{2eq*}	Nm	Equivalent torque present on the gearbox output
M_{2k*}	Nm	Actual tilting torque on the gearbox output
M_{2k100}	Nm	Permitted tilting torque on the gearbox output for $n_{2m*} \leq 100$ rpm

Symbol	Unit	Explanation
M_{2k20}	Nm	Permitted tilting torque on the gearbox output for $n_{2m^*} \leq 20$ rpm
$M_{2k,acc}$	Nm	Permitted acceleration tilting torque at the gearbox output
M_{2k,acc^*}	Nm	Acceleration tilting torque present at the gearbox output
M_{2k,eq^*}	Nm	Actual equivalent tilting torque on the gearbox output
M_{2kN}	Nm	Permitted nominal tilting torque at the gearbox output
M_{2max}	Nm	Maximum torque at the gearbox output
M_{2NOT}	Nm	Gearbox emergency off torque on the gearbox output for max. 1000 load changes
		Without consideration of the maximum torque of the motor
M_{2NOT^*}	Nm	Actual emergency off torque for the gearbox on the gearbox output
M_{2th}	Nm	Thermal limit torque on the gearbox output
M_{Bdyn}	Nm	Dynamic braking torque at 100 °C
M_{Bstat}	Nm	Static braking torque of the motor brake at 100 °C
m_{dyn}	kg	Weight of a motor in dynamic operation
M_{eff^*}	Nm	Actual effective torque of the motor
m_F	kg	Weight of the forced ventilation unit
M_k	Nm	Permitted tilting torque on the output
M_{k^*}	Nm	Actual tilting torque on the output
$M_{k,1^*} - M_{k,n^*}$	Nm	Actual tilting torque of the motor in the respective time segment
M_{k,eq^*}	Nm	Actual equivalent tilting torque at the output
M_{k100}	Nm	Permitted tilting torque on the output for $n_{m^*} \leq 100$ rpm
M_{k300}	Nm	Permitted tilting torque on the output for $n_{m^*} \leq 300$ rpm
M_L	Nm	Load torque
M_{L^*}	Nm	Actual load torque
M_{lim}	Nm	Torque limit without field weakening
M_{limF}	Nm	Torque curve of the motor with forced ventilation in continuous operation
M_{limFW}	Nm	Torque limit with field weakening (applies to operation on STOBBER drive controllers only)
M_{limK}	Nm	Torque curve of the motor with convection cooling in continuous operation
M_{max}	Nm	Maximum torque: the maximum permitted torque the motor is able to deliver over a short period (when accelerating or decelerating) (tolerance $\pm 10\%$)
M_{max^*}	Nm	Actual maximum torque
M_{n^*}	Nm	Actual torque of the motor in the n-th time segment
M_N	Nm	Nominal torque: the maximum torque of a motor in S1 mode at nominal speed n_N (tolerance $\pm 5\%$)
		You can calculate other torque values as follows: $M_{N^*} = K_{M0} \cdot I^* - M_R$.
M_{Nred}	Nm	Reduced nominal torque of the motor
M_{op}	Nm	Torque of motor at the operating point from the motor characteristic curve at n_{1m^*}
M_R	Nm	Frictional torque (of the bearings and seals) of a motor at winding temperature $\Delta\vartheta = 100$ K
n	rpm	Speed
$ n $	rpm	Absolute value of speed
n_{1limF}	rpm	Intersection of torque curve M_{lim} and torque curve with forced ventilation M_{limF}
n_{1limK}	rpm	Intersection of torque curve M_{lim} and torque curve with convection cooling M_{limK}
n_{1m^*}	rpm	Actual average input speed
n_{1max}	rpm	Maximum permitted input speed
n_{1max^*}	rpm	Actual maximum input speed
n_{1maxDB}	min^{-1}	Maximum permitted input speed of the gearbox in continuous operation (at surrounding temperature of 20 °C)
$n_{1maxDBEL1,2}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL1, EL2 (at surrounding temperature of 20 °C)
$n_{1maxDBEL1,2,3,4}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL1, EL2, EL3, EL4 (at surrounding temperature of 20 °C)

Symbol	Unit	Explanation
$n_{1\max\text{DBEL}1,2,5,6}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL1, EL2, EL5, EL6 (at surrounding temperature of 20 °C)
$n_{1\max\text{DBEL}3,4}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL3, EL4 (at surrounding temperature of 20 °C)
$n_{1\max\text{DBEL}3,4,5,6}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL3, EL4, EL5, EL6 (at surrounding temperature of 20 °C)
$n_{1\max\text{DBEL}5,6}$	rpm	Maximum permitted input speed of the gearbox in continuous operation Mounting positions EL5, EL6 (at surrounding temperature of 20 °C)
$n_{1\max\text{ZB}}$	min ⁻¹	Maximum permitted input speed of the gearbox in cyclic operation (at surrounding temperature of 20 °C)
n_{1N}	rpm	Nominal speed at the gearbox input
n_2	rpm	Speed at the gearbox output
$ n_2 $	rpm	Absolute value of output speed
n_{2,m^*}	rpm	Actual average output speed
$n_{2m,1^*} - n_{2m,4^*}$	rpm	Actual average output speed in the respective time segment (1 to 4)
n_{2m,n^*}	rpm	Actual average output speed in the n-th time segment
N_{Bstop}	–	Permitted number of braking processes from full speed ($n = 3000$ rpm) with J_{Bstop} ($M_L = 0$). The following applies if the values of n and J_{Bstop} differ: $N_{\text{Bstop}} = W_{\text{B,Rlim}} / W_{\text{B,R/B}}$.
n_{m^*}	rpm	Actual average motor speed
$n_{m,1^*} - n_{m,4^*}$	rpm	Actual average speed of the motor in the respective time segment (1 to 4)
n_{m,n^*}	rpm	Actual average speed of the motor in the n-th time segment
n_{mot}	rpm	Speed of the motor
n_N	rpm	Nominal speed: The speed for which the nominal torque M_N is specified
p	–	Number of pole pairs
P_N	kW	Nominal power: the power the motor is able to deliver long term in S1 mode at the nominal point (tolerance $\pm 5\%$)
$P_{N,F}$	W	Nominal output of the forced ventilation unit
P_{st}	mm	Pitch of the screw drive
R_{U-V}	Ω	Winding resistance of a motor between two phases at a winding temperature of 20 °C
q_{VF}	m ³ /h	Delivery capacity of the forced ventilation unit in open air
S	–	Service factor: Quotient of the nominal torque from the gearbox and the motor without consideration for thermal limiting performance. Represents a value for the reserve of the geared motor.
t	s	Time
$t_{1^*} - t_{4^*}$	s	Duration of the respective time segment (1 to 4)
t_{1B}	ms	Linking time: time from when the current is turned off until the nominal braking torque is reached
t_{11B}	ms	Response delay: time from when the current is turned off until the torque increases
t_{2B}	ms	Release time (also: disengagement time) of the brake; time span from when the current is switched off until the brake is completely released
t_{dec}	ms	Stop time
T_{el}	ms	Electrical time constant: ratio of the winding inductance to the winding resistance of a motor: $T_{\text{el}} = L_{U-V} / R_{U-V}$
t_{n^*}	s	Duration of the n-th time segment
ϑ_{amb}	°C	Surrounding temperature
U	V	Voltage
$U_{N,B}$	V	Nominal voltage of brake
$U_{N,F}$	V	Nominal voltage of the forced ventilation unit
U_{2K}	V	DC link voltage: characteristic value of a drive controller
v_{ax}	mm/s	Axial velocity
v_{ax,m^*}	mm/s	Actual average axial velocity

Symbol	Unit	Explanation
$v_{ax,m1*} - v_{ax,mn*}$	mm/s	Actual average axial velocity in the respective time segment
$W_{B,R/B}$	J	Work done by friction for braking
$W_{B,Rlim}$	kJ	Work done by friction until wear limit is reached
$W_{B,Rmax/h}$	kJ/h	Maximum permitted work done by friction per hour with individual braking
x_2	mm	Distance of the shaft shoulder to the force application point
$x_{B,N}$	mm	Nominal air gap of brake
y_2	mm	Distance of the shaft axis to the axial force application point
z_2	mm	Distance of the shaft shoulder to the middle of the output bearing

20.2 Trademarks

The following names used in connection with the device, its optional equipment and its accessories are trademarks or registered trademarks of other companies:

ACOPOS®	ACOPOS® is a registered trademark of ABB Asea Brown Boveri Ltd., Switzerland.
ALLEN-BRADLEY®	ALLEN-BRADLEY® is a registered trademark of Rockwell Automation, Inc., USA.
Control Techniques®	Control Techniques® is a registered trademark of Nidec Control Techniques Limited, UK.
DRIVE-CLiQ®, EnDat®	DRIVE-CLiQ® is a registered trademark of Siemens AG, Germany. EnDat® and the EnDat® logo are registered trademarks of Dr. Johannes Heidenhain GmbH, Germany.
HIPERFACE®	HIPERFACE® and the HIPERFACE DSL® logo are registered trademarks of SICK AG, Germany.
IndraDrive®	IndraDrive® is a registered trademark of Bosch Rexroth AG, Germany.
INTERCONTEC®	INTERCONTEC® is a registered trademark of TE Connectivity Industrial GmbH, Germany.
RINGFEDER®	RINGFEDER® is a registered trademark of VBG GROUP TRUCK EQUIPMENT GmbH, Germany.
SERVOSTAR®	SERVOSTAR® is a registered trademark of Kollmorgen Corporation, USA.
SINAMICS®	SINAMICS® is a registered trademark of Siemens AG, Germany.

All other trademarks not listed here are the property of their respective owners.

Products that are registered as trademarks are not specially indicated in this documentation. Existing property rights (patents, trademarks, protection of utility models) are to be observed.

20.3 Sales terms and delivery conditions

You can find our current sales terms and delivery conditions at <http://www.stoeber.de/en/gtc>.



STÖBER Antriebstechnik GmbH + Co. KG
Kieselbronner Strasse 12
75177 Pforzheim
Germany
Phone: +49 7231 582-0
mail@stoeber.de
www.stober.com

Service hotline:
+49 7231 582-3000



STÖBER