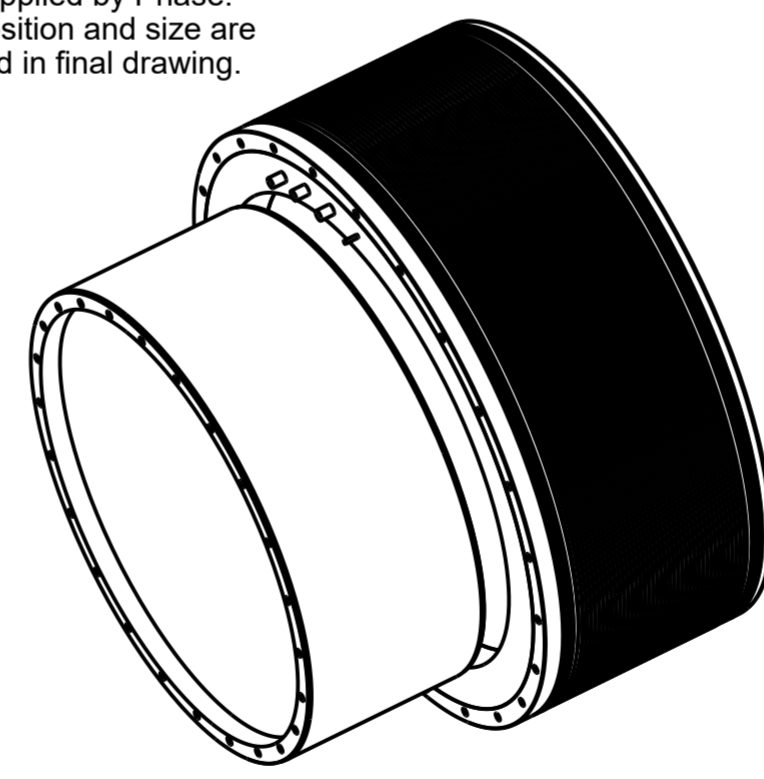


OR supplied by Phase. OR position and size are defined in final drawing.

OR supplied by Phase. OR position and size are defined in final drawing.



SCALE 1:10

NOTE: (*) These dimension can be increased for low polarity motors, and must be confirmed together with detailed datasheet definition.
 (**) Dimensions dependent on the motor winding configuration. General tolerance: geometrical tolerance (ISO 2768-2) class K linear tolerance (ISO 2768-2) class M.
 (***) Suggested position for hydraulic connectors.
 (****) To calculate the minimum number of screws, use follows formulas:
 X (N° Stator screw)= Stack lenght * 0.08
 Y (N° Rotor crews)= Stack lenght * 0.102
 Calculation for screws property class 8.8
 The number of screws can be reduced using higher property classes.

CABLING
To drive power output

Back EMF SEQUENCE
U - V - W
for rotor clockwise rotation
view from cable output
opposite side

Wires Data	
Type Motor	Squid Torque Motor
Power Wires (U,V,W)	Radox (**) mmq
Neutral Wire (K)	1mmq
Sensor Wires	AWG24
Lenght wires	1000 mm

Type: Squid Torque Motor
TK820-xxx-yyy

