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International Market

whatsapp | EN website | Youtube

Domestic Market

Sales Manager | CN website | WeChat

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June 2026

MYACTUATOR®
Professional · Reliable · Innovative

2026 CATALOG

RMD-X V4.1 Series Planetary Actuator For 2026
RMD-X V4 Series Planetary Actuator
RH Series Harmonic Actuator
HM Series Harmonic Mini Actuator
CEM Series Cycloidal Actuator
H Series Hollow Direct Drive Actuator
FL Series Frameless Motor
FLO Series Frameless Motor

Micro Servo · Robot Solutions
All Support Customization





Company Profile

As an innovation-driven micro-power system technology company, ， MYACTUATOR is committed to becoming a globally renowned provider of integrated intelligent power solutions for various robots, accelerating their application across numerous industries and bringing them into households worldwide.

Suzhou Micro Actuator Technology Co., Ltd. was established in 2020 and is a key technology-based enterprise in Suzhou. It has won honors such as "JiangSu Science-based SMEs", "Suzhou Talent Science and Technology Innovation Enterprise, Kunshan Science and Technology Talent Enterprise", and "High-tech Enterprise",etc.

MYACTUATOR currently has more than 90 technical talents of various types, more than 30 technical patents, forming more than 100 product models, with a comprehensive operation area of more than 7,000 square meters, with perfect motor design and development, manufacturing and testing equipment and advanced quality management concepts.



Beijing Branch


Dong Guan Manufacturing Center


Production Base


Myactuator (HQ)

Embodied Robotics Micro Power System Solution

Contents

Company Profile P01
Application Industry P02

Micro Actuator

RMD-X V4.1 Series Planetary Actuator For 2026 P03
RMD-X V4 Series Planetary Actuator P05
RH Series Harmonic Actuator P07
HM Series Harmonic Mini Actuator P09
CEM Series Cycloidal Actuator P11
H Series Hollow Direct Drive Actuator P13
FLSeries Frameless Motor P15
FLO Series Frameless Motor P17

Robot Arm Solution

GP2-51-30-E Gripper P19
GP2-53-120-E Gripper P20
RB-A850-10 Robot Arm P21
RB-C002 Controller P22

Applications

- Robotic Applications
- Healthcare
- Agriculture
- Industrial Automation
- Smart warehousing
- Other industries

RMD-X V4.1 Series Planetary Actuator For 2026

Special Series For Robot

Front and rear installation / Dual outlet / Hollow Design / EtherCAT **V4.1**



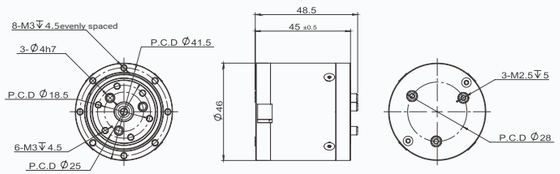
Product Parameters

Parameters	Unit	X2-3	X2-7-L	X4-10-L	X4-36-L	X6-60-L	X8-150	X10-200	X12-320-L
Gear ratio	-	9	28.17	12.5	36	19.612	19.612	20	20
Rated Voltage	V	48	24	24	24	48	48	48	48
Rated Power	W	41.8	37	100	100	320	574	465	900
Rated Torque	N.m	0.9	2.5	4	10.5	20	43.0	60	85
Rated Speed	RPM	444	142	238	83	153	127	74	100
Peak Torque	N.m	3	7	10	34	60	150	200	320
No Load Speed	RPM	666	178	317	111	176	158	80	125
Torque constant	N.m/A	0.6	0.8	0.8	1.9	2.1	2.4	4.6	3.3
Back-EMF Constant	Vdc/Krpm	12	4.3	6	6	16	19.2	24.94	17.9
Efficiency	%	58	63	69.5	63.1	72.7	79.0	74	75
Control Accuracy	Degree	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01
Inertia	Kg.cm²	/	0.17	0.25	/	0.66	1.5	/	12.9
Weight	Kg	0.23	0.26	0.33	0.36	0.78	1.33	1.64	2.28
Communication	—	CAN BUS		EtherCAT & CAN BUS					
Encoder	—	Dual Encoder							
Interface	—	ABS-14BIT/14BIT	ABS-17BIT/18BIT			ABS-17BIT/19BIT			
voltage range	—	—	18-48V The above parameters are based on 24V testing			—			

Installation Drawing

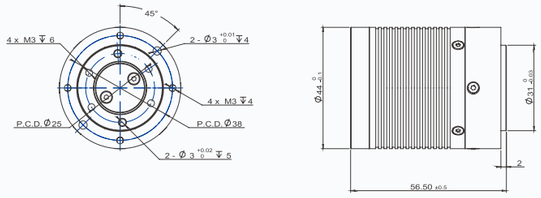
X2-3

RMD-X2-P9-3-C



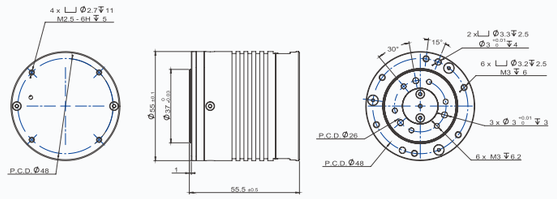
X2-7-L

RMD-X2-P28-7-C-Lite



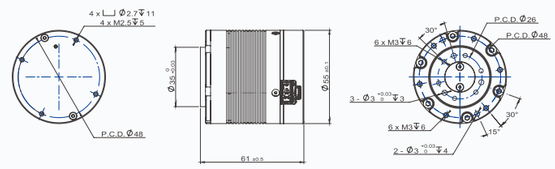
X4-10-L

RMD-X4-P12-10-E-L



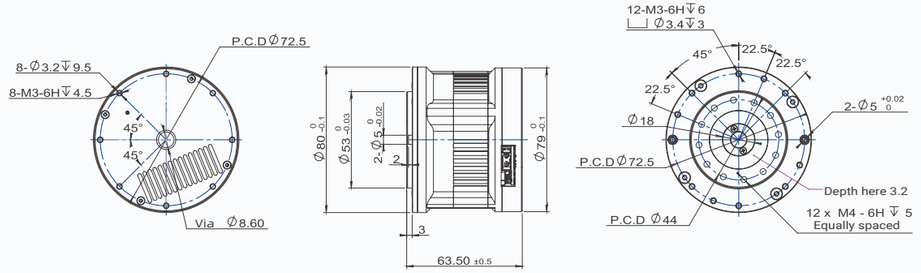
X4-36-L

RMD-X4-P36-36-E-L



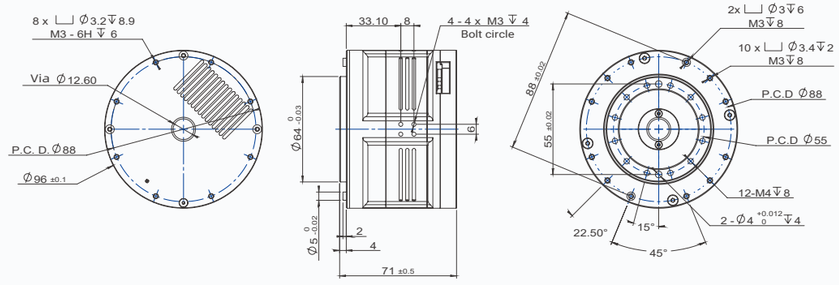
X6-60-L

RMD-X6-P20-60-E-L



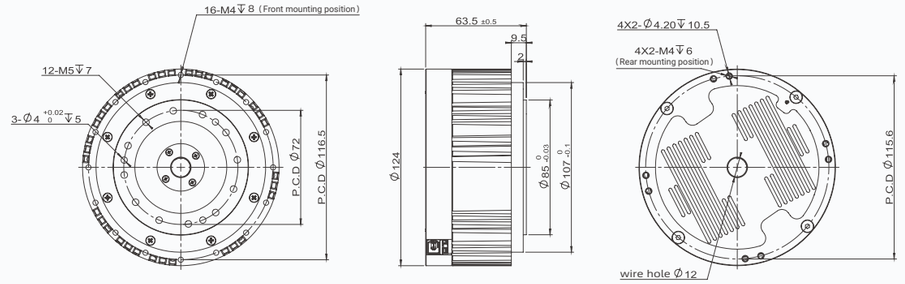
X8-150

RMD-X8-P20-150-E-03



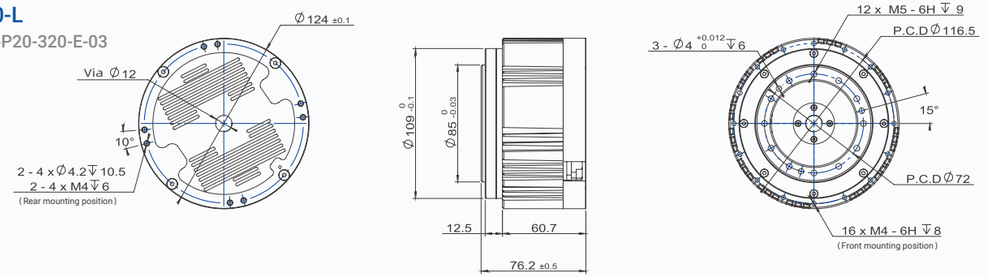
X10-200

RMD-X10-P20-200-E



X12-320-L

RMD-X12-P20-320-E-03



RMD-X V4 Series Planetary Actuator

Special Series For Robot

Dual Encoder / Hollow Design / CAN BUS / EtherCAT **RMD-V4**

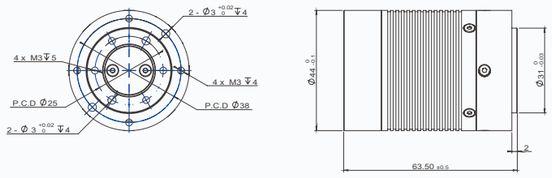


Product Parameters

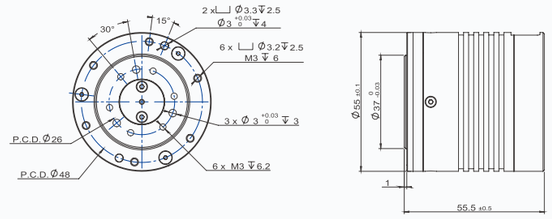
Parameters	Unit	X2-7	X4-10	X4-36	X6-60	X8-32	X8-120	X12-320	X15-450
Gear ratio	-	28.17	12.5	36	19.612	9	19.612	20	20.25
Rated Voltage	V	24	24	24	48	24	48	48	72
Rated Power	W	37	100	100	320	204	574	900	1480
Rated Torque	N.m	2.5	4.0	10.5	20.0	8	43.0	85	145
Rated Speed	RPM	142	238	83	153	244	127	100	98
Peak Torque	N.m	7	10	34	60	32	120	320	450
No Load Speed	RPM	178	317	111	176	277	158	125	108
Torque constant	N.m/A	0.8	0.8	1.9	2.1	1.3	2.4	3.3	5.8
Back-EMF Constant	Vdc/Krpm	4.3	6.0	6.0	16.0	10.9	19.2	17.9	29.9
Efficiency	%	63	69.5	63.1	72.7	82	79.0	75	82.4
Control Accuracy	Degree	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01	<0.01
Inertia	Kg.cm²	0.17	0.25	0.3	0.66	1.43	1.5	12.9	31.6
Weight	Kg	0.26	0.33	0.36	0.82	0.53	1.40	2.37	3.50
Communication	—	EtherCAT & CAN BUS				RS485	EtherCAT & CAN BUS		
Encoder	—	Dual Encoder				Single Encoder	Dual Encoder		
Interface	—	ABS-17BIT/18BIT			ABS-17BIT/17BIT	ABS-18BIT	ABS-17BIT/17BIT		
voltage range	—	18-48V The above parameters are based on 24V testing			—				

Installation Drawing

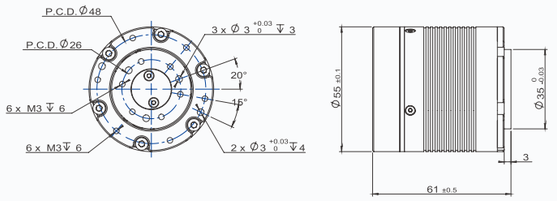
X2-7
RMD-X2-P28-7-E



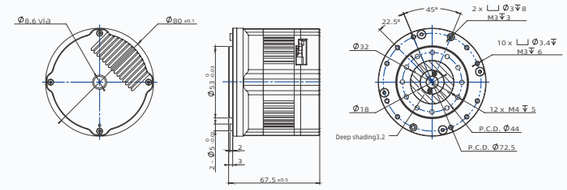
X4-10
RMD-X4-P12-10-E



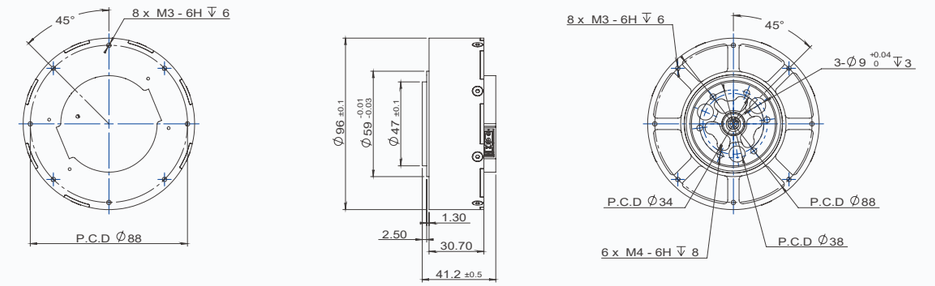
X4-36
RMD-X4-P36-36-E



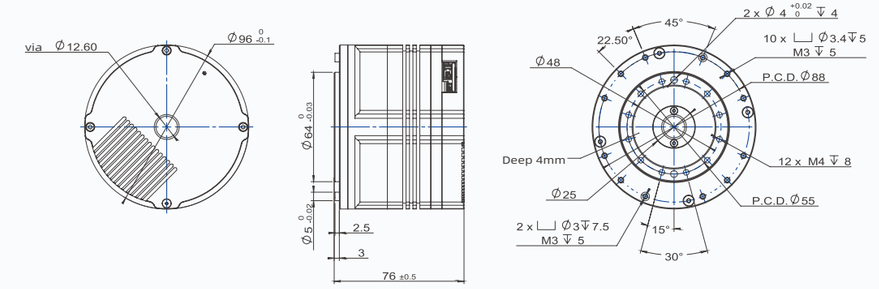
X6-60
RMD-X6-P20-60-E



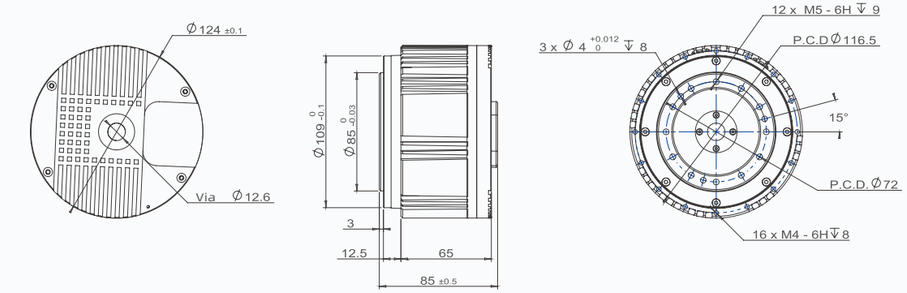
X8-32
RMD-X8-P9-32-R



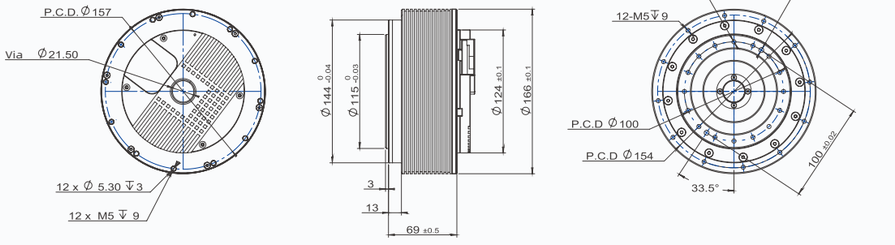
X8-120
RMD-X8-P20-120-E



X12-320
RMD-X12-P20-320-E



X15-150
RMD-X15-P20-450-E



RH Series Harmonic Actuator

Dual Encoder / CAN BUS / EtherCAT **EPS-RH**



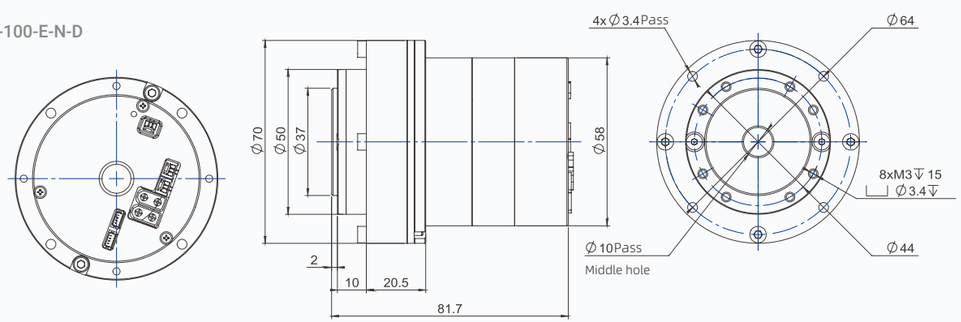
Product Parameters

Parameters		Unit	RH-14	RH-17	RH-20	RH-25	RH-32
Gear ratio		—	50 | 100	50 | 100	50 | 100	50 | 100	50 | 100
Rated Voltage		V	48	48	48	48	48
Rated Power		W	28	91	130	282	282
Rated Torque		N.m	5.5 | 11	17.5 | 35	25 | 50	54 | 108	75 | 150
Rated Speed		RPM	50 | 25	50 | 25	50 | 25	50 | 25	36 | 18
Peak Torque		N.m	14 | 28	27 | 54	40 | 80	78.5 | 157	114.5 | 229
No Load Speed		RPM	60 | 30	60 | 30	60 | 30	60 | 30	40 | 20
Torque constant		N.m/A	2 | 4	3.7 | 7.4	3.65 | 7.3	5.05 | 10.1	3.45 | 6.9
Back-EMF Constant		Vdc/Krpm	19.2	19.2	19.2	19.2	26.7
Efficiency		%	—	—	—	—	—
Control Accuracy		Degree	< 0.01	< 0.01	< 0.01	< 0.01	< 0.01
Inertia	N	kg.cm²	0.11 | 0.29	0.16 | 0.52	0.21 | 0.87	0.51 | 1.94	0.82 | 6.86
	B	kg.cm²	—	0.18 | 0.56	0.24 | 0.95	0.59 | 2.32	2.05 | 8.32
Weight	N	Kg	0.78	1.11	1.45	2.42	4.32
	B	Kg	/	1.28	1.75	2.74	4.74
Communication		—	CAN BUS /EtherCAT				
Encoder		—	Dual Encoder ABS-17bit/ABS-17bit				

Installation Drawing

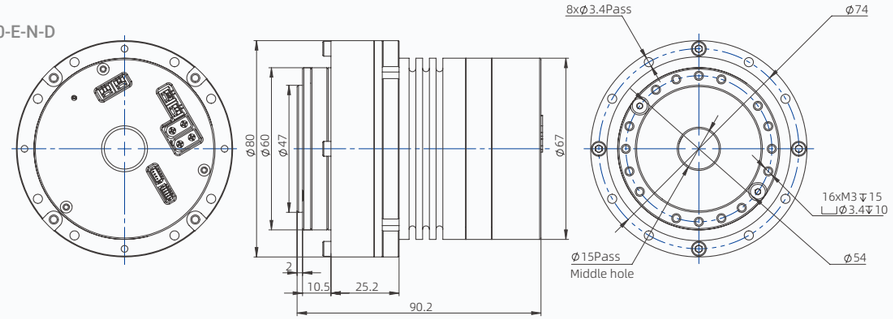
RH-14

EPS-RH-14-100-E-N-D



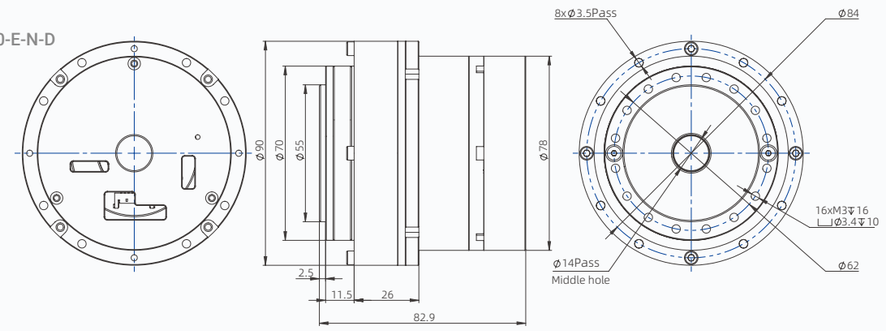
RH-17

EPS-RH-17-100-E-N-D



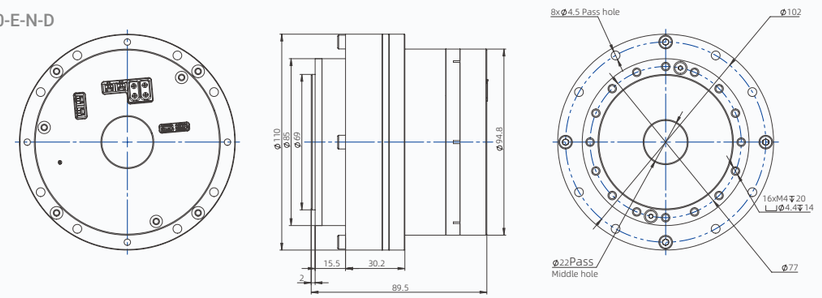
RH-20

EPS-RH-20-100-E-N-D



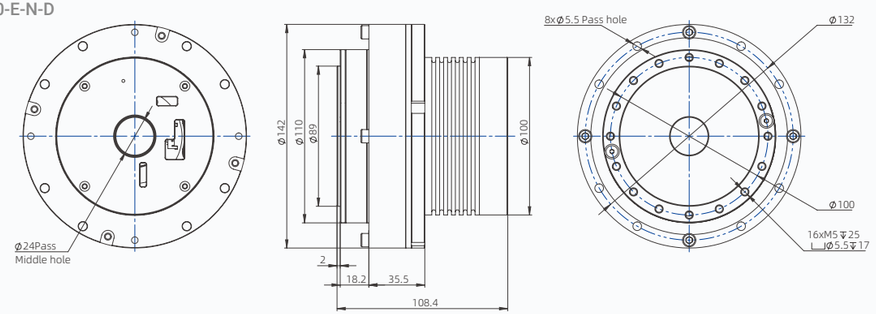
RH-25

EPS-RH-25-100-E-N-D



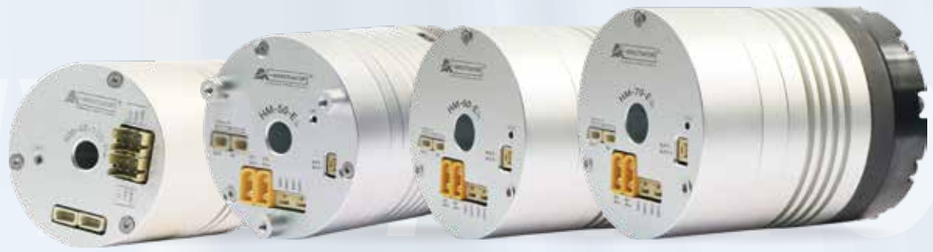
RH-32

EPS-RH-32-100-E-N-D



HM Series Harmonic Mini Actuator

Hollow Design / CAN BUS / Dual encoder **EPS-RH**



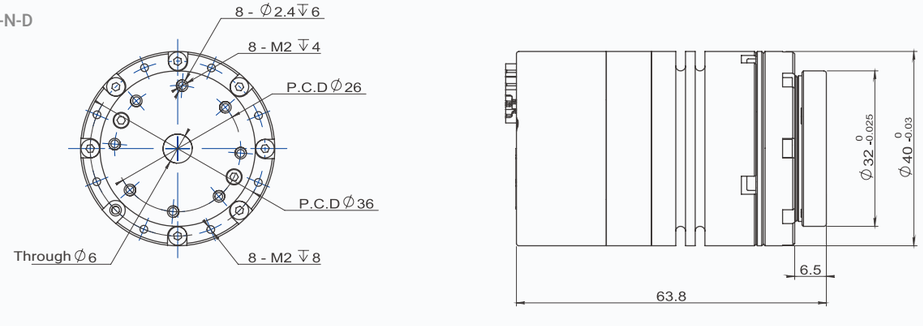
Product Parameters

Parameters	Unit	HM-40	HM-50	HM-60	HM-70
Gear ratio	—	100	80	100	100
Rated Voltage	V	48	48	48	48
No Load Speed	RPM	50	50	25	25
Rated Speed	RPM	30	40	20	20
Rated Torque	N.m	3.5	8	15	26
Rated Power	W	11	33	31	55
Peak Torque	N.m	10	25	37	65
Back-EMF Constant	Vdc/Krpm	16	15	24	24
Torque constant	N.m/A	/	5.84	3	5.17
Efficiency	%	/	/	/	/
Inertia	kg.m²	/	/	/	/
Encoder	—	Dual Encoder			
Interface	—	ABS-17BIT/17BIT			
Repeat Position Accuracy	Degree	<0.01			
Communication	—	CAN BUS	CAN BUS / EtherCAT		
Weight	Kg	0.2	0.4	0.65	0.92

Installation Drawing

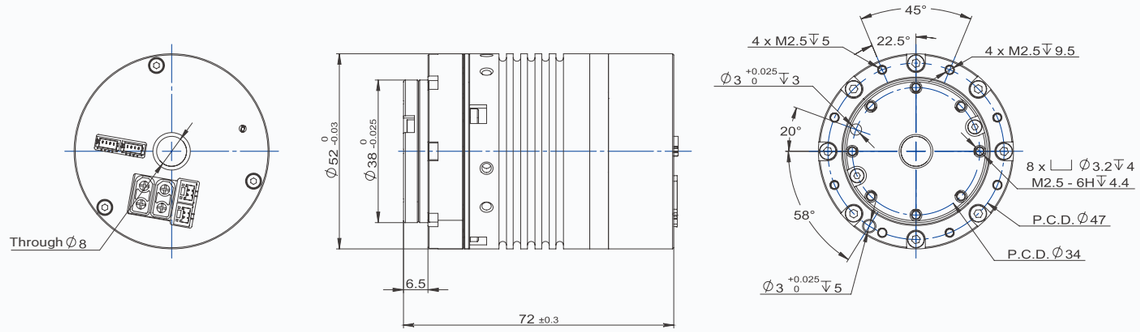
HM-40

EPS-HM-40-100-C-N-D



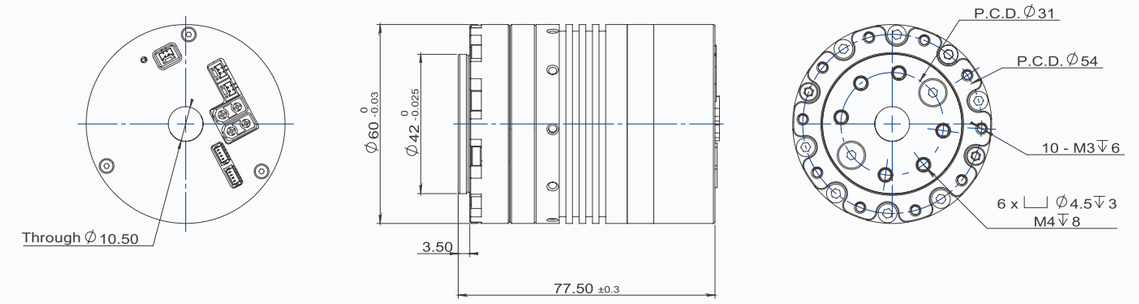
HM-50

EPS-HM-50-80-E-N-D



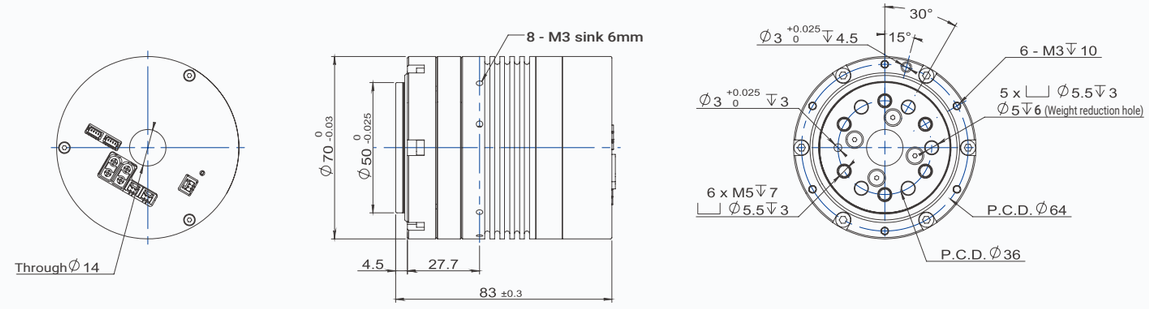
HM-60

EPS-HM-60-100-E-N-D



HM-70

EPS-HM-70-100-E-N-D



CEM Series Cycloid Actuator

Dual Encoder / CAN BUS / EtherCAT **EPS-CEM**



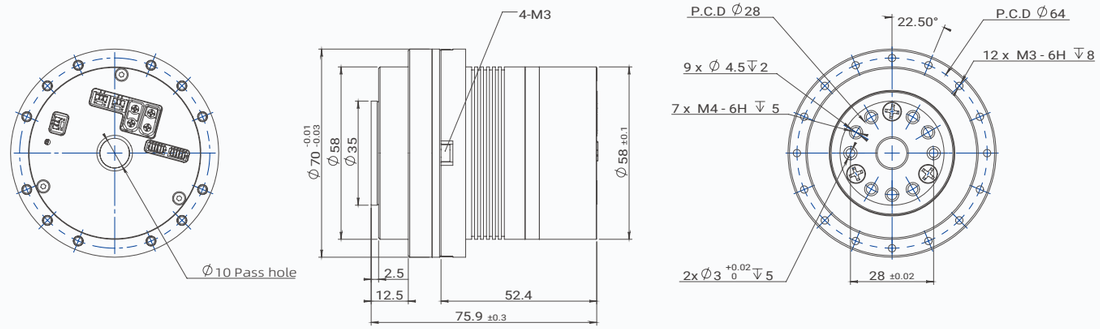
Product Parameters

Parameters	Unit	CEM-15	CEM-25	CEM-45
Gear Ratio	—	30	30	30
Input Voltage	V	48	48	48
No Load Speed	RPM	170	130	100
Rated Speed	RPM	140	100	80
Rated Torque	N.m	9	15	25
Rated Output Power	W	132	157	210
Rated Phase Current	A(rms)	2.3	2.6	5.7
Peak Torque	N.m	15	25	45
Peak Phase Current	A(rms)	6.5	7.2	16.8
Motor Back-EMF Constant	Vdc/Krpm	5.58	8.37	9.77
Module Torque Constant	N.m/A	2.4	3.6	4.2
Motor Phase Resistance	Ω	0.62	0.7	0.25
Motor Phase Inductance	mH	0.43	0.47	0.38
Pole Pair	—	10	10	10
3 Phase Connection	—	Y	Y	Y
Backlash	Arcmin	<5	<5	<5
Max axial load	KN	1	1	1
Max radial load	KN	2	2	2
Inertia	Kg.cm²	0.7	0.7	0.7
Encoder Type	—	ABS-17bit (Input) /17bit (Output)		
Repeat Position Accuracy	Degree	< 0.01	< 0.01	< 0.01
Communication	—	CAN BUS & EtherCAT	CAN BUS & EtherCAT	CAN BUS & EtherCAT
Weight	Kg	0.81	0.94	1.09
Insulation Grade	—	F	F	F

Installation Drawing

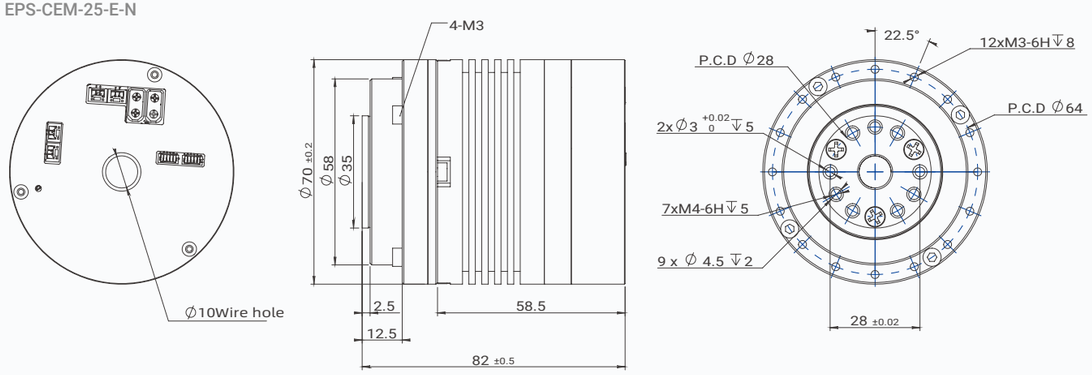
CEM-15

EPS-CEM-15-E-N



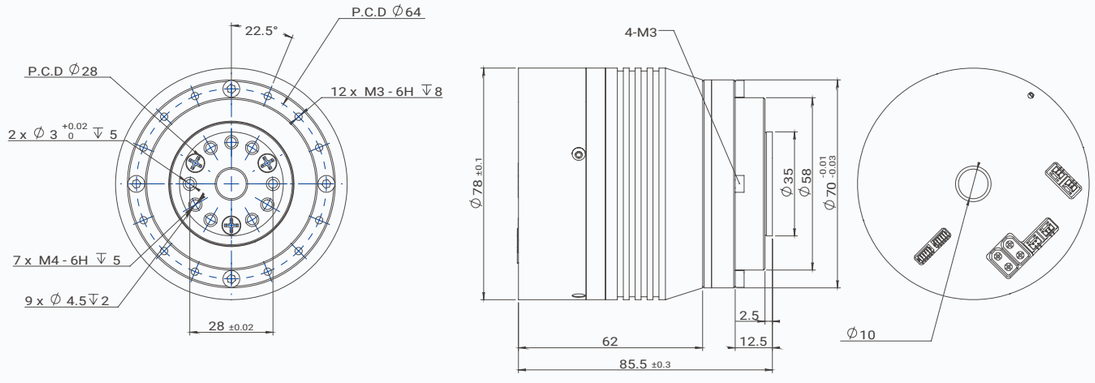
CEM-25

EPS-CEM-25-E-N



CEM-45

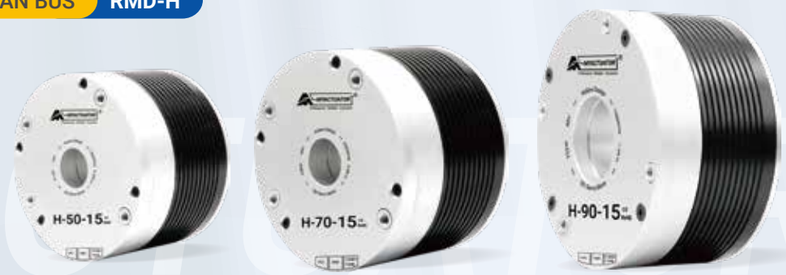
EPS-CEM-45-E-N



H Series Hollow Direct Drive Actuator

Hollow Design / Single Encoder / CAN BUS **RMD-H**

Outer Rotor



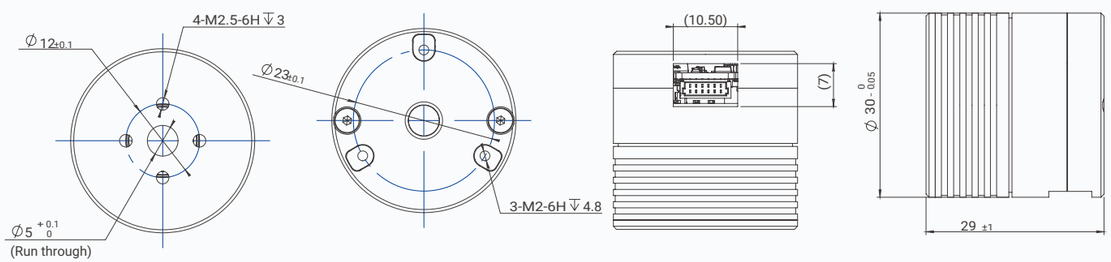
Product Parameters

Parameters	Unit	H-30-08	H-35-10	H-40-15	H-50-15	H-70-15	H-90-15
Rated Voltage	V	24	24	24	24	48	48
Rated Power	W	15	30	47	91.6	200	252
Rated Torque	N.m	0.03	0.1	0.15	0.35	0.8	1.5
Rated Speed	RPM	5000	3000	3000	2500	2400	1600
Peak Torque	N.m	0.1	0.3	0.3	0.9	2	3.75
No Load Speed	RPM	6000	3700	3700	3200	2800	2000
Torque constant	N.m/A	0.03	0.06	0.03	0.07	0.18	0.23
Back-EMF Constant	Vdc/Krpm	4.8	8	8	7.93	17	21.1
Efficiency	%	>60%	>60%	>64%	>83%	>84%	>83%
Control Accuracy	Degree	< 0.01	< 0.01	< 0.01	< 0.01	< 0.01	< 0.01
Inertia	Kg.cm²	0.15	0.23	0.29	0.57	1.80	4.20
Weight	Kg	—	—	0.2	0.24	0.47	0.71
Communication	—	CAN BUS					
Encoder	—	ABS-17bit					

Installation Drawing

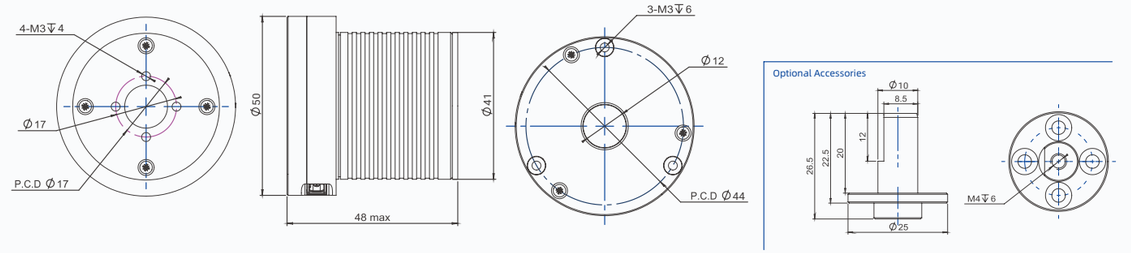
H-30-08

RMD-H-30-08-15-C



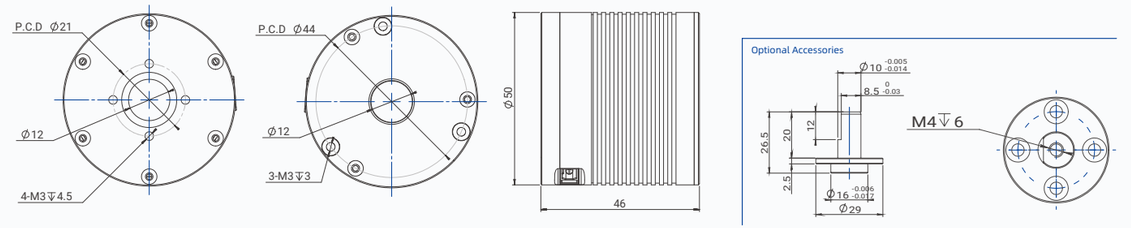
H-40-15

RMD-H-40-15-50-C



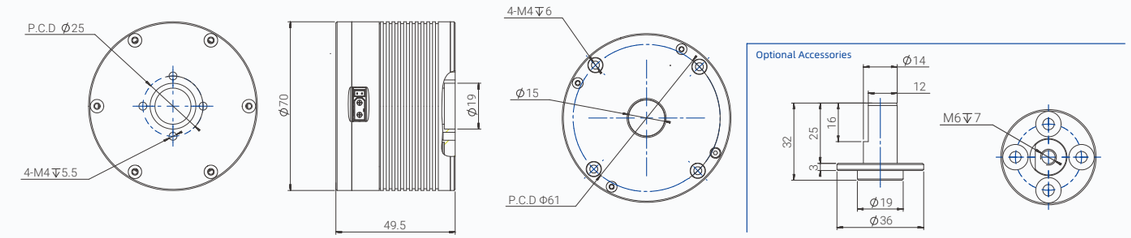
H-50-15

RMD-H-50-15-100-C



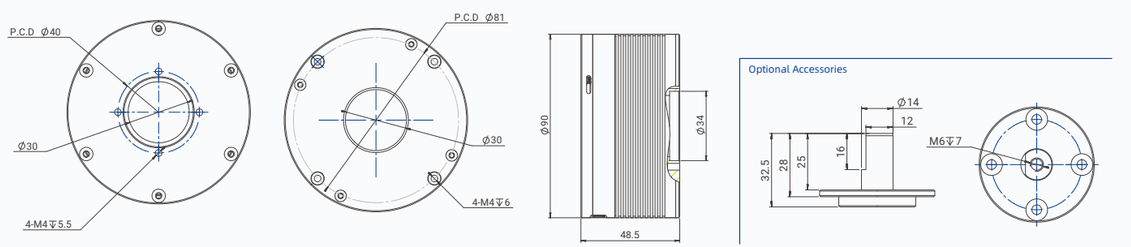
H-70-15

RMD-H-70-15-200-C



H-90-15

RMD-H-90-15-400-C



FL Series Frameless Torque Motor

Hollow Design / High Precision / High Power Density **RMD-FL**



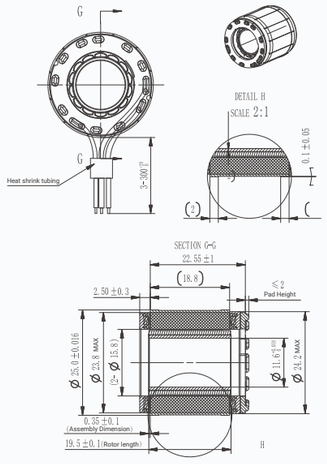
Product Parameters

Parameters	Unit	FL-25-18	FL-38-08	FL-38-12	FL-50-08	FL-50-15	FL-70-10	FL-70-16	FL-85-13	FL-85-23
Input voltage	V	24	48	48	48	48	48	48	48	48
Rated speed	RPM	4000	9000	9970	5200	3800	3500	3000	2400	3500
Rated torque	N.m	0.15	0.1	0.23	0.3	0.51	0.55	1.3	1.3	2
Rated power	W	95.5	94	240	163	203	201	408	408	733
Rated current	A	4.2	2.75	6.1 (REF)	3.9	4.3	4.4	9.2	9.4	14.5
Peak torque	N.m	0.45	0.32	0.47 (REF)	0.96	1.5	1.65	2.6	3.9	6
Torque constant	N.m/A	0.035	0.04	0.04	0.08	0.12	0.12	0.14	0.14	0.14
Encoder type	—	—	Absolute	—	Hall+INC	Hall+INC	Hall+INC	Hall+INC	Hall+INC	Absolute
Weight	kg	0.04	0.05	0.10	0.12	0.16	0.25	0.32	0.46	0.61

Installation Drawing

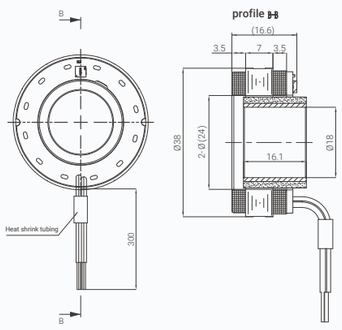
FL-25-18

RMD-FL-25-18-100



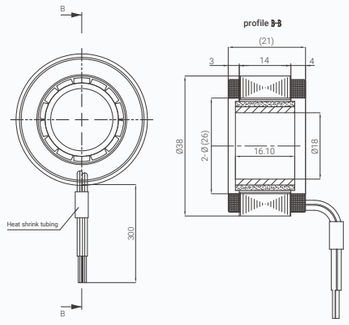
FL-38-08

RMD-FL-38-08-100



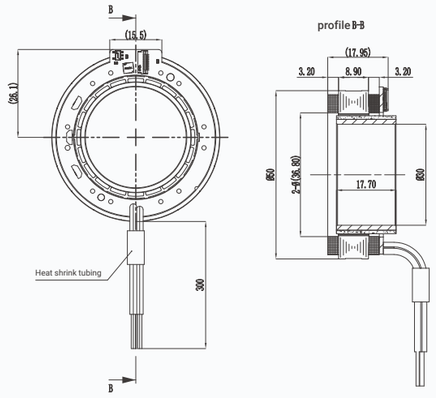
FL-38-12

RMD-FL-38-12-240



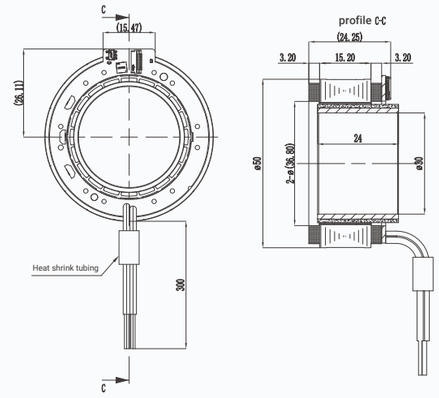
FL-50-08

RMD-FL-38-12-240



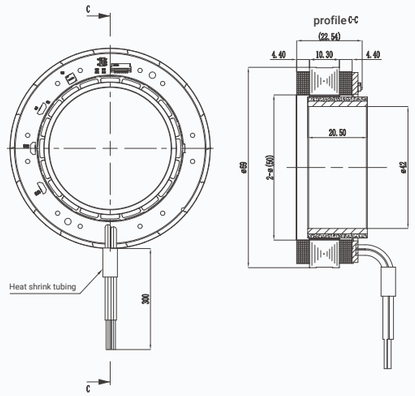
FL-50-15

RMD-FL-50-15-200



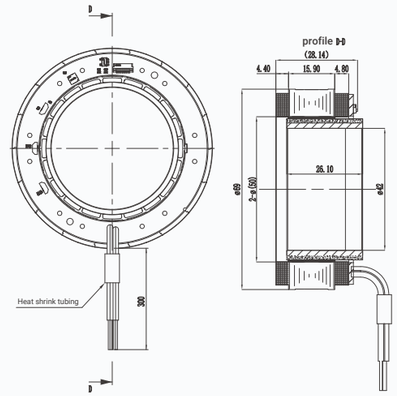
FL-70-10

RMD-FL-70-10-250



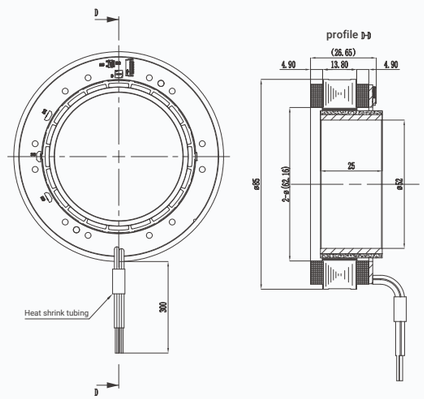
FL-70-16

RMD-FL-70-16-360



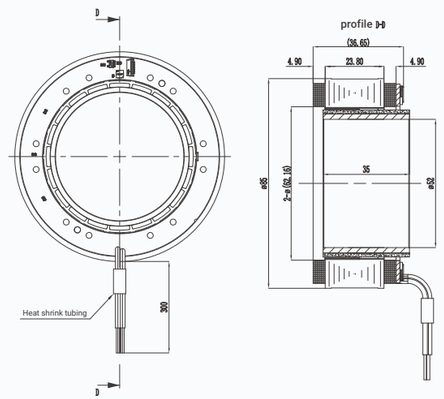
FL-85-13

RMD-FL-85-13-500



FL-85-23

RMD-FL-85-23-750



FLO Series Frameless Torque Motor

Hollow Design / High Precision / High Power Density **RMD-FLO**



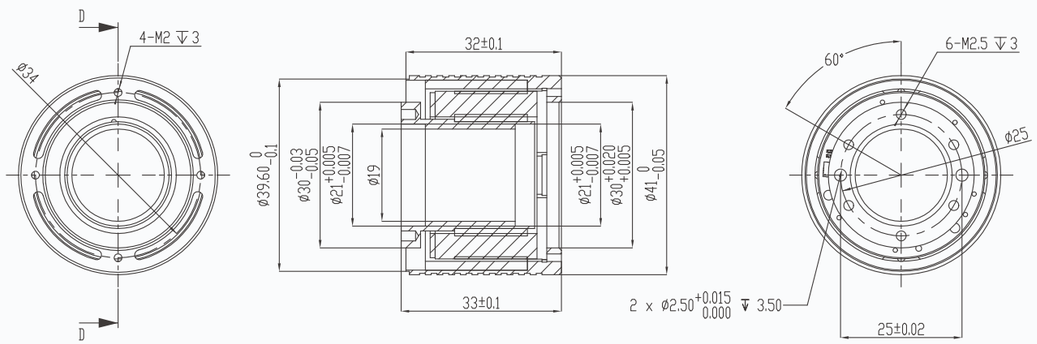
Product Parameters

Parameters	Unit	FLO-40-15	FLO-50-15	FLO-70-15	FLO-90-15
Input voltage	V	24	24	48	48
Rated speed	RPM	3000	2500	2400	1600
Rated torque	N.m	0.15	0.35	0.8	1.5
Rated power	W	47	91.6	200	252
Rated current	A	5.1	4.9	4.4	6.6
Peak torque	N.m	0.3	0.87	2	3.75
Torque constant	N.m/A	0.03	0.07	0.18	0.23
Encoder type	–	Absolute (Multi-pole)	Absolute (Multi-pole)	Absolute (Multi-pole)	Absolute (Multi-pole)
Weight	kg	0.13	0.19	0.33	0.46

Installation Drawing

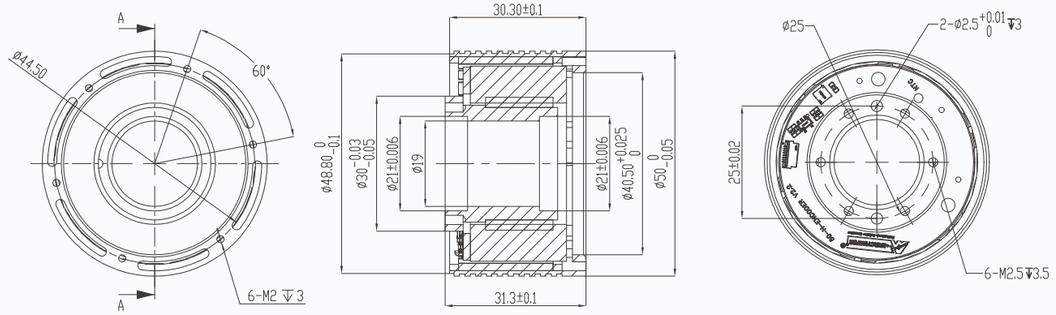
FLO-40-15

RMD-FLO-40-15-50



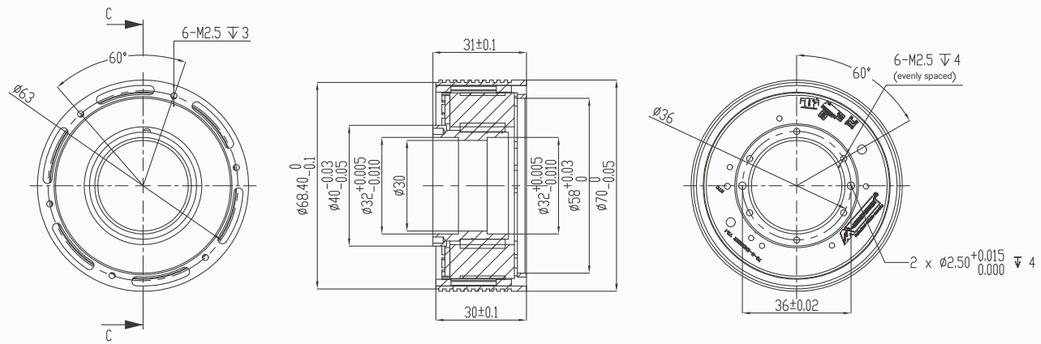
FLO-50-15

RMD-FLO-50-15-100



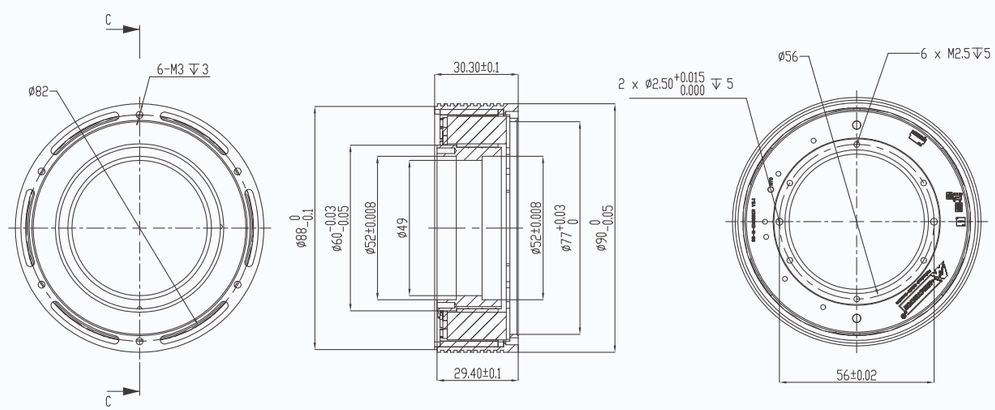
FLO-70-15

RMD-FLO-70-15-200



FLO-90-15

RMD-FLO-90-15-400



GP2-51-90-E Gripper

CAN BUS / EtherCAT | Gripper

Rated Clamping Force
90N

Weight
0.75Kg

Peak Clamping Force
160N

Dimensions
169.8 × 172.67 × 62.5mm

Total Stroke
95mm



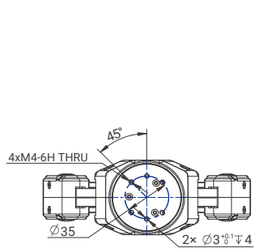
Product Introduction

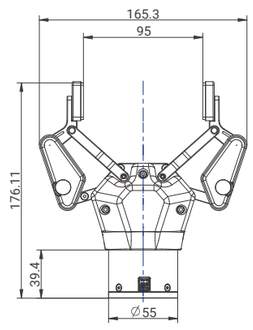
Automatically conforms to the object's contours

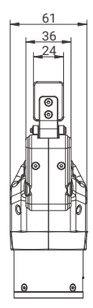
achieving both firm and flexible gripping

EtherCAT / CAN BUS

Installation Drawing







Product Parameters

Gripper Parameters	Value
Rated Grasping Force	90N
Peak Grasping Force	160N
Total Stroke	95mm
Peak Speed:	100 mm/s
Operating Noise	<60dB
Weight	0.75kg
Transmission Method	Planetary gear + screw nut +linkage mechanism
Dimensions	169.8 × 172.67 × 62.5mm

Electrical Parameters	Value
Value	24~48V
Current (24V test)	0.2A (Rated) / 0.89A (peak)
Rated Power (24V test)	4.8W
Communication Interface	CAN BUS / EtherCAT

*Rated grasping force is tested with a gripping stroke of 50mm

GP2-53-120-E Gripper

CAN BUS / EtherCAT | Gripper

Rated Clamping Force
120N

Weight
1.12Kg

Peak Clamping Force
300N

Dimensions
191.5 × 220 × 77 mm

Total Stroke
105mm



Product Introduction

Dexterous Adaptive Grasping

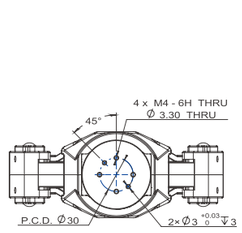
Both Force and Position Programmable

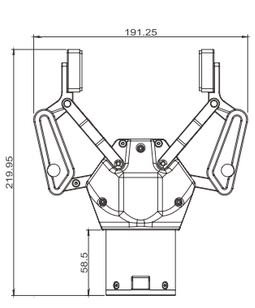
Intelligent Judgment Easy Integration

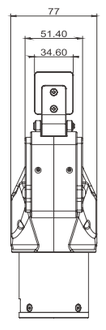
Lightweight Design

Multiple Communication Interfaces

Installation Drawing







Product Parameters

Gripper Parameters	Value
Rated Grasping Force	120N
Peak Grasping Force	300N
Total Stroke	105mm
Operating Noise	<60dB
Weight	1.12kg
Transmission Method	Planetary Gear + Ball Screw Nut + Linkage Mechanism
Dimensions	191.5 × 220 × 77mm

Electrical Parameters	Value
Value	24~48V
Current (24V test)	0.36A (Rated) / 2A (Peak)
Rated Power (24V test)	14.4W
Communication Interface	CAN BUS / EtherCAT

*Rated grasping force is tested with a gripping stroke of 90mm

RB-A850-10 Robot Arm

CAN BUS / EtherCAT | ARM

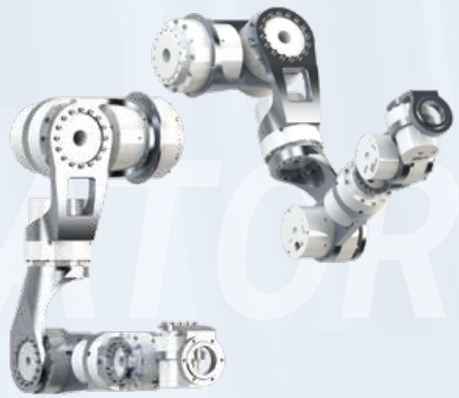
DOF
14 axes

wingspan
850mm

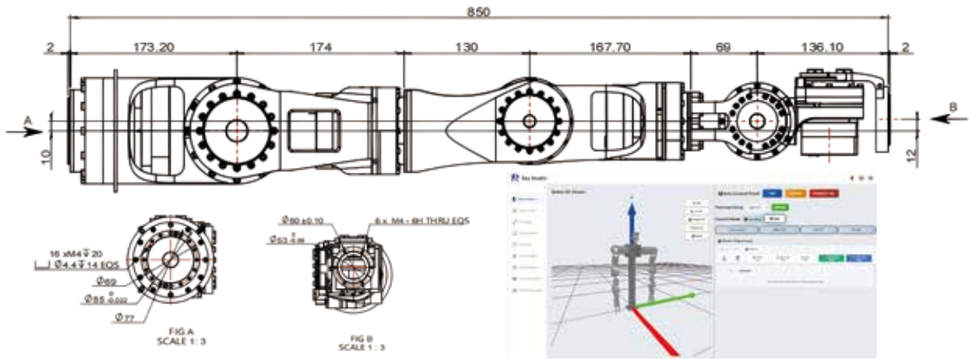
weight
11.2kg

Rated Payload at End
10kg

Repeatability of positioning accuracy
±0.05 mm



Installation Drawing



Product Parameters

Mechanical Parameters	Values
Arm Reach	850 mm
Weight	11.2 kg
Rated Payload	10 kg
Repeatability	±0.05 mm
J1 Range of Motion	±180 °
J2 Range of Motion	-180 ~ 0°
J3 Range of Motion	±180 °
J4 Range of Motion	-135 ~ +90 °（Right arm） -90 ~ +135°（Left arm）
J5 Range of Motion	±180 °
J6 Range of Motion	±90 °
J7 Range of Motion	±90 °

Electrical Parameters	Values
Rated Voltage	48 V
Rated Power	1000 W
Communication	CAN BUS/Ethercat

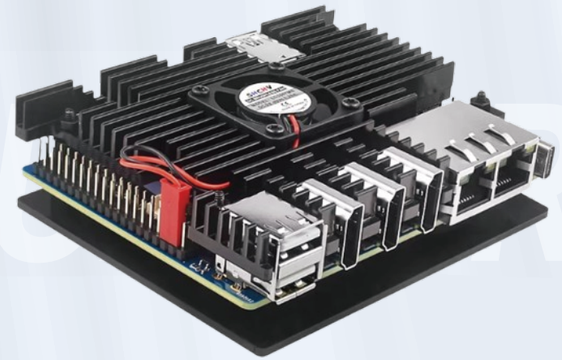
RB-C002 Controller

EtherCAT

High-Speed Networking
Dual 2.5GbE

Real-Time Control
4kHz

Real-Time System
RTOS



Product Introduction

Dual 2.5GbE Network Card + High-Performance Computing

Mature Real-Time Kernel and Master Stack

Pre-Integrated Control Stack

Comprehensive Deliverables

Product Parameters

Parameters	Description
Master Stack	IgH EtherCAT Master
Control Frequency	Up to 4kHz
DC Synchronization	Supported
Slave Type	MyActuator (Pulse Motor)
Real-Time System	Ubuntu + PREEMPT_RT
Network Interface	Dual 2.5GbE Ethernet ports
Hardware Platform	Orange Pi5 PLUS Development Board
Memory	16GB
Storage	64GB sd card
Power Input	DC 5V
Operating Temperature	0°C ~ 45°C
Interface Expansion	USB 3.0, GPIO, UART, I2C, SPI
Software Support	ROS 2, Python, C++