

**“tough tech for tough environments”**

## **PA-R-250-8 servo-actuator**

**Pegasus**

Actuators GmbH

### **data sheet - technical specifications**

#### **Supply data:**

Operating voltage: 18V - 32V

Operating voltage typical: 24V

Standby current: 40mA

#### **Input signal:**

PWM signal, TTL level (standard)

PWM signal, differential (RS485 transceiver) (optional)

or RS485 data protocol (optional)

#### **PWM parameter:**

Frame rate: 2,6 - 1000ms

Valid pulse length: 1,0 - 2,0ms

left / center / right: 1,0ms - 1,5ms - 2,0ms

#### **Position feedback:**

analog, differential: 0-5V

Scale factor: 27.78 mV/deg.

#### **Performance data:**

Stall torque: > 500Ncm (> 710 oz-in.)

Rated torque<sup>\*\*</sup>: 300Ncm (425 oz-in.)

Speed at rated torque: 125°/sec.

No load speed: 205°/sec.

Gear train backlash: < 0,5°

Travel angle: ± 90° (-5%)

Maximum travel angle (optional): ± 170° (-5%)

Slip clutch lock out momentum: 500Ncm (710 oz-in.) +20%

Peak current - short time: 1760mA

Stall current - continuous: 780mA (limited)

Minimum detectable signal step: max 0,25µsec. (adjustable)

Weight: 285g (10,05 oz)



<sup>\*\*</sup>according to specifications of Pegasus Actuators GmbH  
(please inquire the test-specifications)

#### **Environmental data:**

Axial load on output shaft: < 100N

Lateral load on output shaft: < 300N

Operating temperature: -40°C - +70°C (-40°F - +158°F)

Storage temperature: -40°C - +80°C (-40°F - +176°F)

#### **Environmental specifications:**

Vibration test: IEC 68-2-6 / EN 60068-2-6

Shock test: IEC 68-2-32

Protection class: IP67

**“tough tech for tough environments”**

## PA-R-250-8 servo-actuator

### data sheet - technical specifications

#### Main components:

**Case:** IP67 water and dust protected with solid vertical and horizontal 4-point fixation.  
material: CNC machined aluminum, bead blasted and anodized.

**Gear train:** hardened steel spur gear type, 6 ball races with rigid output shaft (optional with slip clutch output shaft), output shaft with defined alignment.

**Motor:** Neodym-magnet BLDC motor, double ball raced.

**Amplifier:** digital positioning controller

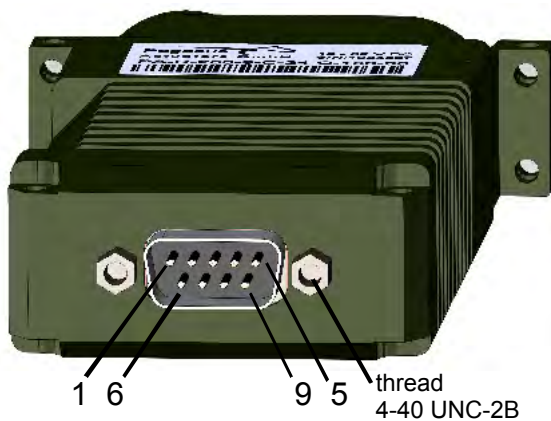
#### Sensor travel angle:

mechanical: 360° (no end stops)

electrical - (standard):  $\pm 45^\circ$

electrical - (optional):  $\pm 170^\circ$

**Connector:** D-Sub male, 9-pin, IP 67



Pin	PWM / TTL	PWM differential	RS485
1	Signal input A	Signal input A	Signal input A
2	NC	Signal input B	Signal input B
3	Pos. feedback A	Pos. feedback A	Pos. feedback A
4	NC	NC	NC
5	Case ground	Case ground	Case ground
6	Power input	Power input	Power input
7	Power return	Power return	Power return
8	NC	NC	NC
9	Pos. feedback B	Pos. feedback B	Pos. feedback B

**Connector:** Glenair Mighty Mouse Series 801, 7-pin, IP67



Pin	PWM / TTL	PWM differential	RS485
1	Signal input A	Signal input A	Signal input A
2	NC	Signal input B	Signal input B
3	Pos. feedback A	Pos. feedback A	Pos. feedback A
4	Power return	Power return	Power return
5	Case ground	Case ground	Case ground
6	Power input	Power input	Power input
7	Pos. feedback B	Pos. feedback B	Pos. feedback B