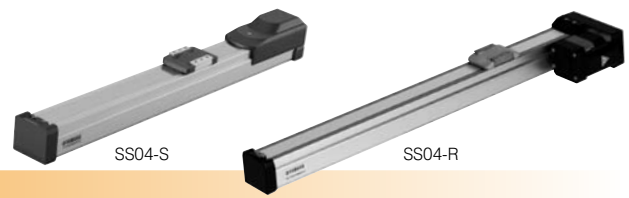


SS04 Slider type

- CE compliance
- Origin on the non-motor side is selectable



Ordering method

SS04

Model	Lead	Model	Brake	Origin position	Grease option	Stroke	Cable length ^{Note 1}	Robot positioner	I/O	Battery ^{Note 4}
	12: 12mm 06: 6mm 02: 2mm	S: Straight model R: Space-saving model (motor installed on right) L: Space-saving model (motor installed on left)	N: With no brake B: With brake	N: Standard Z: Non-motor side	N: Standard grease C: Clean room grease	50 to 400 (50mm pitch)	1L: 1m 3L: 3m 5L: 5m 10L: 10m	S2: TS-S2 ^{Note 2} SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ GW: No I/O board ^{Note 3}	B: With battery (Absolute) N: None (Incremental)

SD	1
Robot driver	I/O cable
SD: TS-SD	f: 1m

Note 1. The robot cable is flexible and resists bending.
 Note 2. See P.446 for DIN rail mounting bracket.
 Note 3. Select this selection when using the gateway function. For details, see P.439.
 Note 4. Select whether or not the battery is provided only when using the TS-SH.

Basic specifications

Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability ^{Note 1} (mm)	±0.02	
Deceleration mechanism	Ball screw φ8 (Class C10)	
Maximum motor torque (N·m)	0.27	
Ball screw lead (mm)	12	6
Maximum speed (mm/sec)	600	300
Maximum payload (kg)	Horizontal	Vertical
	2	4
	1	2
Max. pressing force (N)	45	90
	150	150
Stroke (mm)	50 to 400 (50mm pitch)	
Overall length (mm)	Horizontal	Stroke+216
	Vertical	Stroke+261
Maximum outside dimension of body cross-section (mm)	W49 × H59	
Cable length (m)	Standard: 1 / Option: 3, 5, 10	

Allowable overhang ^{Note}

Horizontal installation (Unit: mm)		Wall installation (Unit: mm)		Vertical installation (Unit: mm)			
	A	B	C		A	C	
Lead 12	1kg	807	218	292	0.5kg	407	408
	2kg	667	107	152	1kg	204	204
Lead 6	2kg	687	116	169	1kg	223	223
	3kg	556	76	112	2kg	107	107
Lead 2	4kg	567	56	84	2kg	118	118
	4kg	869	61	92	4kg	53	53
Lead 6	4kg	863	40	60	6kg	39	29
	6kg	863	40	60	6kg	39	29

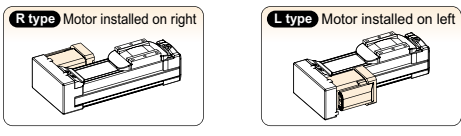
Static loading moment

(Unit: N·m)		
MY	MP	MR
16	19	17

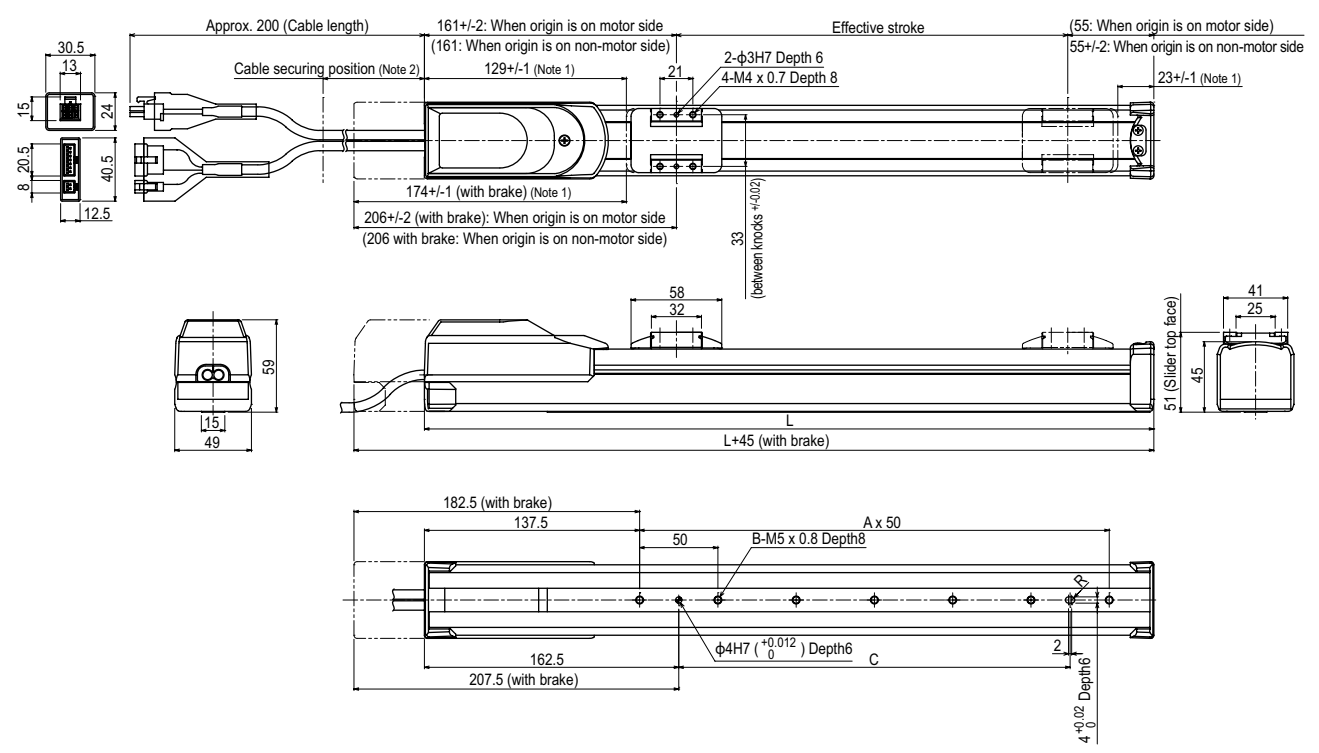
Controller

Controller	Operation method
TS-S2	I/O point trace / Remote command
TS-SH	I/O point trace / Remote command
TS-SD	Pulse train control

Motor installation (Space-saving model)



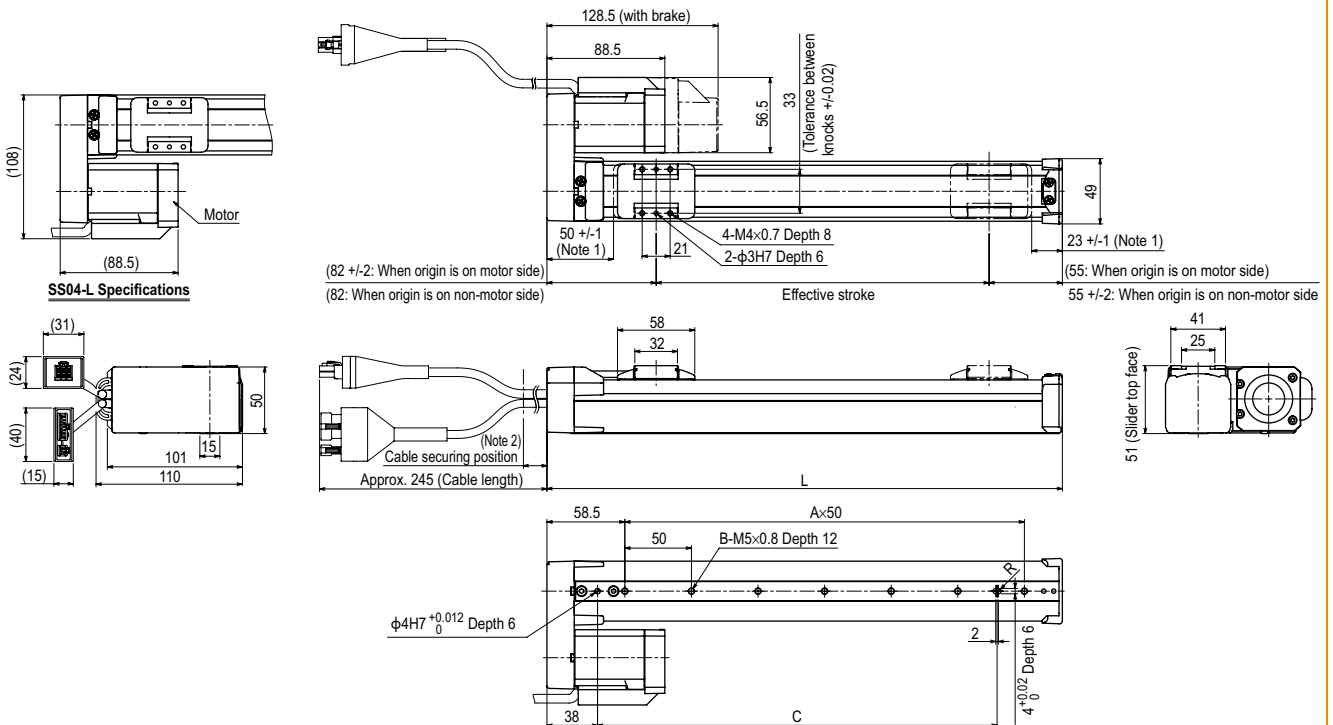
SS04 Straight model S



Effective stroke	50	100	150	200	250	300	350	400
L	266	316	366	416	466	516	566	616
A	2	3	4	5	6	7	8	9
B	3	4	5	6	7	8	9	10
C	50	100	150	200	250	300	350	400
Weight (kg) ^{Note 4}	1.5	1.6	1.7	1.8	2.0	2.1	2.2	2.3

Note 1. Stop positions are determined by the mechanical stoppers at both ends.
 Note 2. Secure the cable with a tie-band 100mm or less from unit's end face to prevent the cable from being subjected to excessive loads.
 Note 3. The cable's minimum bend radius is R30.
 Note 4. These are the weights without a brake. The weights are 0.2kg heavier when equipped with a brake.

SS04 Space-saving model **R** **L**



Effective stroke	50	100	150	200	250	300	350	400
L	187	237	287	337	387	437	487	537
A	2	3	4	5	6	7	8	9
B	3	4	5	6	7	8	9	10
C	100	150	200	250	300	350	400	450
Weight (kg) ^{Note 4}	1.2	1.4	1.5	1.6	1.7	1.8	1.9	2.1

Note 1. Stop positions are determined by the mechanical stoppers at both ends.
 Note 2. Secure the cable with a tie-band 80mm or less from unit's end face to prevent the cable from being subjected to excessive loads.
 Note 3. The cable's minimum bend radius is R30.
 Note 4. These are the weights without a brake. The weights are 0.2kg heavier when equipped with a brake.
 Note 5. The belt cover's left and right sides are asymmetrical. Therefore, if the motor mounting orientation is changed, the cover cannot be attached.