

SS05H

Slider type



- High lead: Lead 20
- CE compliance
- Origin on the non-motor side is selectable

Ordering method

SS05H

Model	Lead 20: 20mm 12: 12mm 06: 6mm	Model S: Straight model R: Space-saving model (motor installed on right) L: Space-saving model (motor installed on left)	Brake ^{Note 1} N: With no brake B: With brake	Origin position N: Standard Z: Non-motor side	Grease option N: Standard grease C: Clean room grease	Stroke 50 to 800 (50mm pitch)	Cable length ^{Note 2} 1L: 1m 3L: 3m 5L: 5m 10L: 10m	Robot positioner S2: TS-S2 ^{Note 3} SH: TS-SH	I/O NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ GW: No I/O board ^{Note 4}	Battery ^{Note 5} B: With battery (Absolute) N: None (Incremental)
								SD Robot driver SD: TS-SD	1 I/O cable 1: 1m	

Note 1. Brake-equipped models can be selected only when the lead is 12mm or 6mm.
 Note 2. The robot cable is flexible and resists bending.
 Note 3. See P446 for DIN rail mounting bracket.
 Note 4. Select this selection when using the gateway function. For details, see P.439.
 Note 5. 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 φ12 (Class C10)
Maximum motor torque (N·m)	0.47
Ball screw lead (mm)	20 12 6
Maximum speed (mm/sec)	Horizontal 1000 600 300 Vertical - 500 250
Maximum payload (kg)	Horizontal 6 8 12 Vertical - 2 4
Max. pressing force (N)	36 60 120
Stroke (mm)	50 to 800 (50pitch)
Overall length (mm)	Horizontal Stroke+286 Vertical Stroke+306
Maximum outside dimension of body cross-section (mm)	W55 × H56
Cable length (m)	Standard: 1 / Option: 3, 5, 10

Note 1. Positioning repeatability in one direction.
 Note 2. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

Allowable overhang ^{Note}

Horizontal installation (Unit: mm)	Wall installation (Unit: mm)	Vertical installation (Unit: mm)
Lead 20	Lead 20	Lead 12
2kg 599 225 291	2kg 262 203 554	1kg 458 459
4kg 366 109 148	4kg 118 88 309	2kg 224 224
6kg 352 71 104	6kg 71 49 262	2kg 244 245
4kg 500 118 179	4kg 146 96 449	4kg 113 113
6kg 399 79 118	6kg 85 55 334	
8kg 403 56 88	8kg 55 34 305	
6kg 573 83 136	6kg 101 62 519	
8kg 480 61 100	8kg 64 39 413	
10kg 442 47 78	10kg 43 26 355	
12kg 465 39 64	12kg 28 17 338	

Note. Distance from center of slider upper surface to carrier center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).

Static loading moment

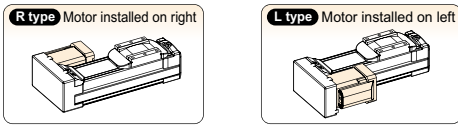
	MY	MP	MR
	32	38	34

(Unit: N·m)

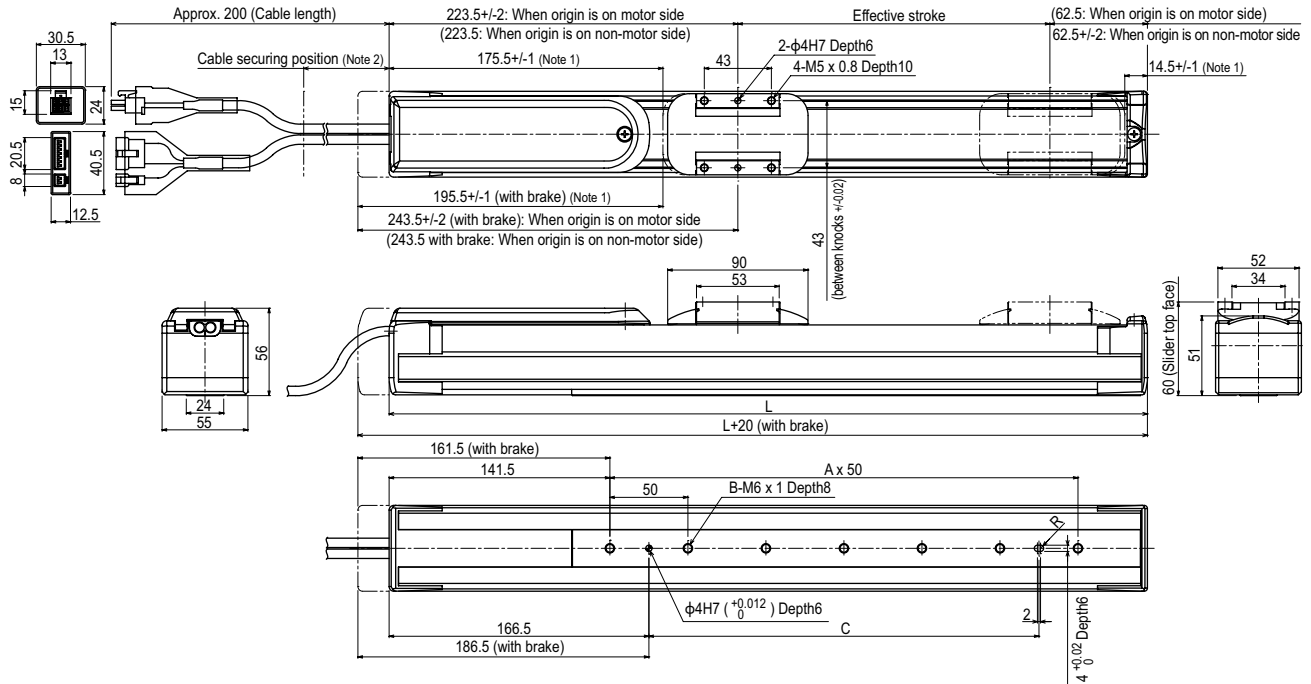
Controller

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

Motor installation (Space-saving model)



SS05H Straight model S



Effective stroke	50	100	150	200	250	300	350	400	450	500	550	600	650	700	750	800
L	336	386	436	486	536	586	636	686	736	786	836	886	936	986	1036	1086
A	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
B	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19
C	100	150	200	250	300	350	400	450	500	500	500	500	500	500	500	500
Weight (kg) ^{Note 4}	2.4	2.6	2.8	3.0	3.2	3.4	3.6	3.8	4.0	4.2	4.4	4.5	4.7	4.9	5.1	5.3
Maximum speed for each stroke ^{Note 5} (mm/sec)																
Lead20																
Lead12 (Horizontal)																
Lead12 (Vertical)																
Lead6 (Horizontal)																
Lead6 (Vertical)																
Speed setting																

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.
 Note 5. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

