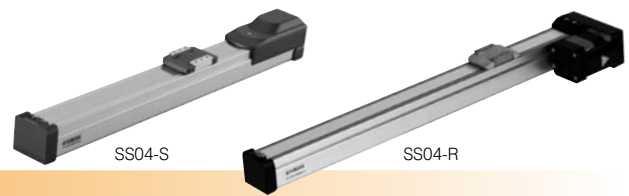


SS04 Slider type

- 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 2}
	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 ^{Note 1} Z: Non-motor side	N: Standard grease C: Clean room grease	50 to 400 (50mm pitch)	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

Robot positioner	I/O
S2: TS-S2 ^{Note 3}	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 4}

SH

Robot positioner	I/O	Battery
SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 4}	B: With battery (Absolute) N: None (Incremental)

SD

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

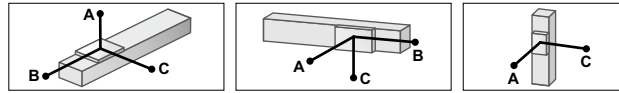
Note 1. If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, refer to the manual.
 Note 2. The robot cable is flexible and resists bending.
 Note 3. See P.498 for DIN rail mounting bracket.
 Note 4. Select this selection when using the gateway function. For details, see P.60.

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	2
Maximum speed (mm/sec)	600	300	100
Maximum payload (kg)	Horizontal 2	Vertical 4	6
Max. pressing force (N)	45	90	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		

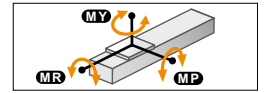
Note 1. Positioning repeatability in one direction.

Allowable overhang ^{Note}



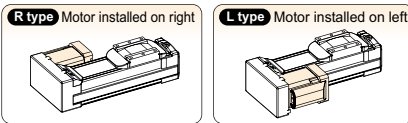
Horizontal installation (Unit: mm)				Wall installation (Unit: mm)				Vertical installation (Unit: mm)			
	A	B	C		A	B	C	Lead 12	A	C	
Lead 12	1kg	807	218	292	1kg	274	204	776	0.5kg	407	408
	2kg	667	107	152	2kg	133	93	611	1kg	204	204
Lead 6	2kg	687	116	169	2kg	149	102	656	1kg	223	223
	3kg	556	76	112	3kg	92	62	516	2kg	107	107
Lead 2	4kg	567	56	84	4kg	63	43	507	2kg	118	118
	4kg	869	61	92	4kg	72	48	829	4kg	53	53
Lead 2	6kg	863	40	60	6kg	39	29	789			

Static loading moment

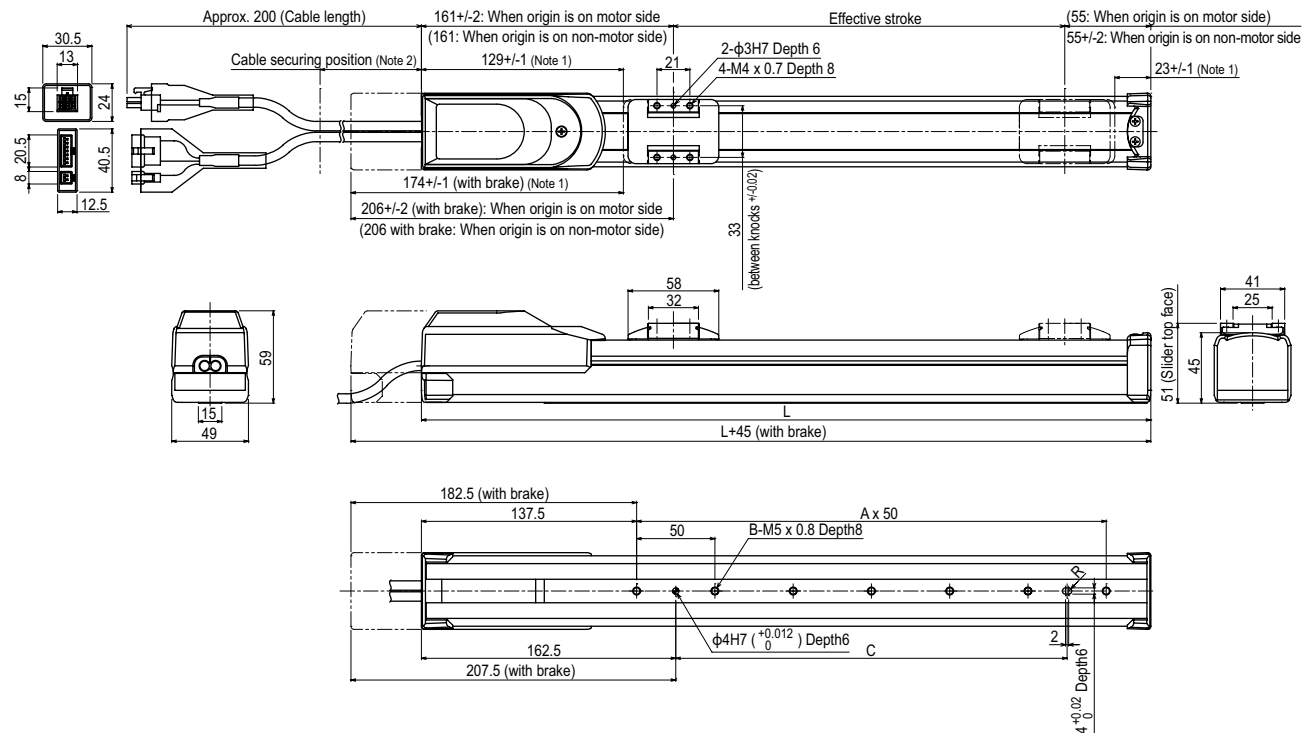


(Unit: N·m)		
MY	MP	MR
16	19	17

Motor installation (Space-saving model)



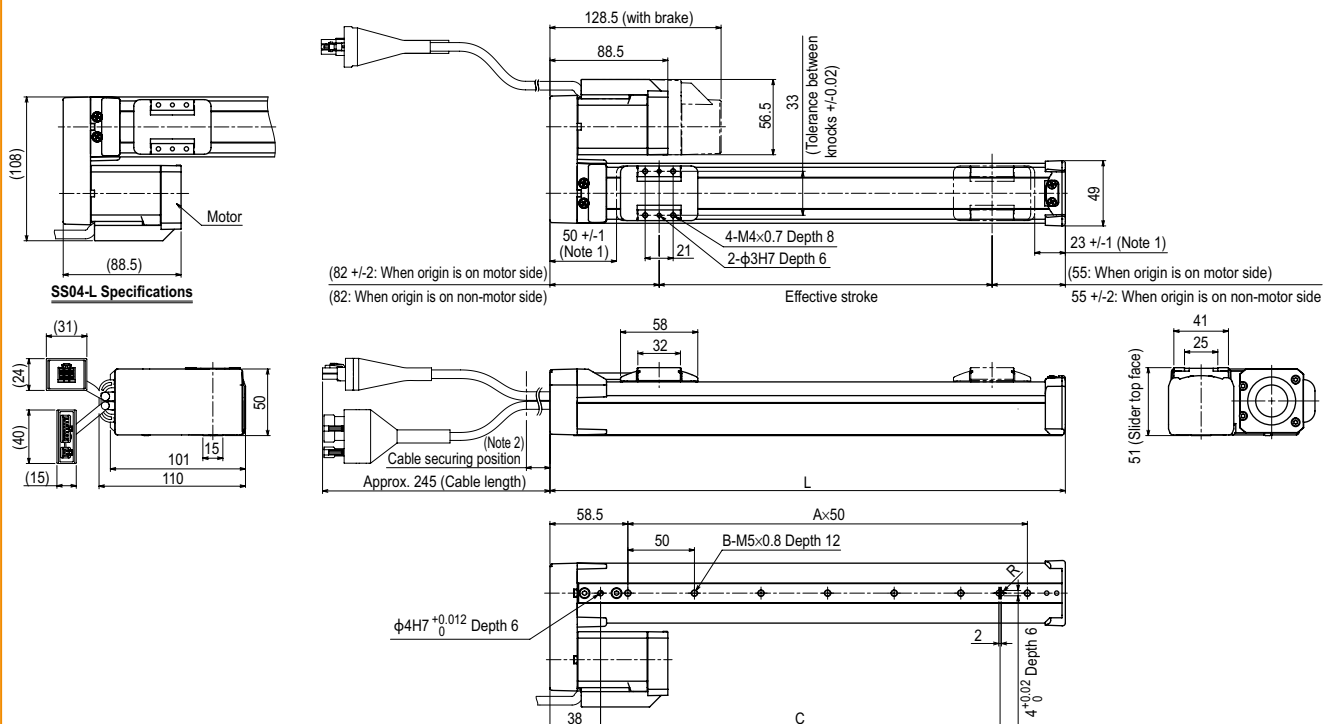
SS04 Straight model S



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.