

STH06

Slide table type



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

Ordering method

STH06

Model	Lead 08: 8mm 16: 16mm	Model S: Straight model R: Space-saving model (motor installed on right) L: Space-saving model (motor installed on left)	Brake N: With no brake B: With brake	Origin position N: Standard ^{Note 1} Z: Non-motor side	Bracket plate ^{Note 2} N: No plate H: With plate	Stroke 50: 50mm 100: 100mm 150: 150mm	Cable length ^{Note 3} 1K: 1m 3K: 3m 5K: 5m 10K: 10m
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S2

Robot positioner S2: TS-S2 ^{Note 4}	I/O NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 5}
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SH

Robot positioner SH: TS-SH	I/O NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 5}	Battery B: With battery (Absolute) N: None (Incremental)
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SD

Robot driver SD: TS-SD ^{Note 5}	I/O cable I: 1m
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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. Space-saving models (R and L) with the plate cannot be selected.

Note 3. The robot cable is flexible and resists bending.

Note 4. See P.498 for DIN rail mounting bracket.

Note 5. The robot with the brake cannot use the TS-SD.

Note 6. Select this selection when using the gateway function. For details, see P.60.

Basic specifications

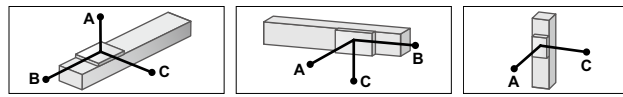
Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability ^{Note 1} (mm)	+/- 0.05	
Drive method	Straight	Slide screw
	Space-saving	Slide screw + belt
Ball screw lead (mm)	8 16	
Maximum speed ^{Note 2} (mm/sec)	150 400	
Maximum payload (kg)	Horizontal	9 6
	Vertical	4 2
Max. pressing force (N)	180 100	
Stroke (mm)	50/100/150	
Maximum outside dimension of body cross-section (mm)	Straight	W61 × H65
	Space-saving	W108 × H70
Cable length (m)	Standard: 1 / Option: 3, 5, 10	

Note 1. Positioning repeatability in one direction.

Note 2. The maximum speed needs to be changed in accordance with the payload.

See the "Speed vs. payload" graph shown on the right. For details, see P. 128.

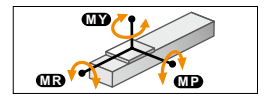
Allowable overhang



Lead	Horizontal installation (Unit: mm)			Wall installation (Unit: mm)			Vertical installation (Unit: mm)				
	A	B	C	A	B	C	A	B	C		
Lead 16	2kg	3000	2123	1436	2kg	1500	2091	3000	1kg	3000	3000
	4kg	2493	1001	680	4kg	710	975	2443	1.5kg	2458	2457
	6kg	1571	627	428	6kg	440	603	1524	2kg	1837	1837
Lead 8	3kg	3000	1375	932	3kg	979	1347	3000	2kg	1837	1837
	6kg	1571	627	428	6kg	440	603	1524	3kg	1217	1216
	9kg	956	378	260	9kg	260	355	912	4kg	907	906

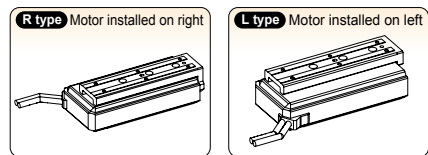
Note. Overhang at travelling service life of 3000km. (Service life is calculated for 100mm stroke models.)

Static loading moment

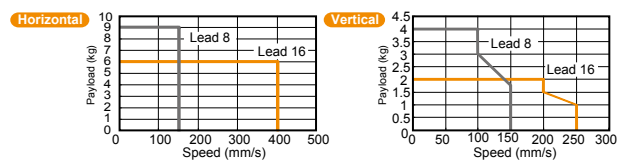


Stroke	MY	MP	MR
50mm	77	77	146
100mm	112	112	177
150mm	155	155	152

Motor installation (Space-saving model)



Speed vs. payload



Controller

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

Note. The robot with the brake cannot use the TS-SD.

STH06 Straight model S

Approx. 210
(Cable length without brake/with brake)

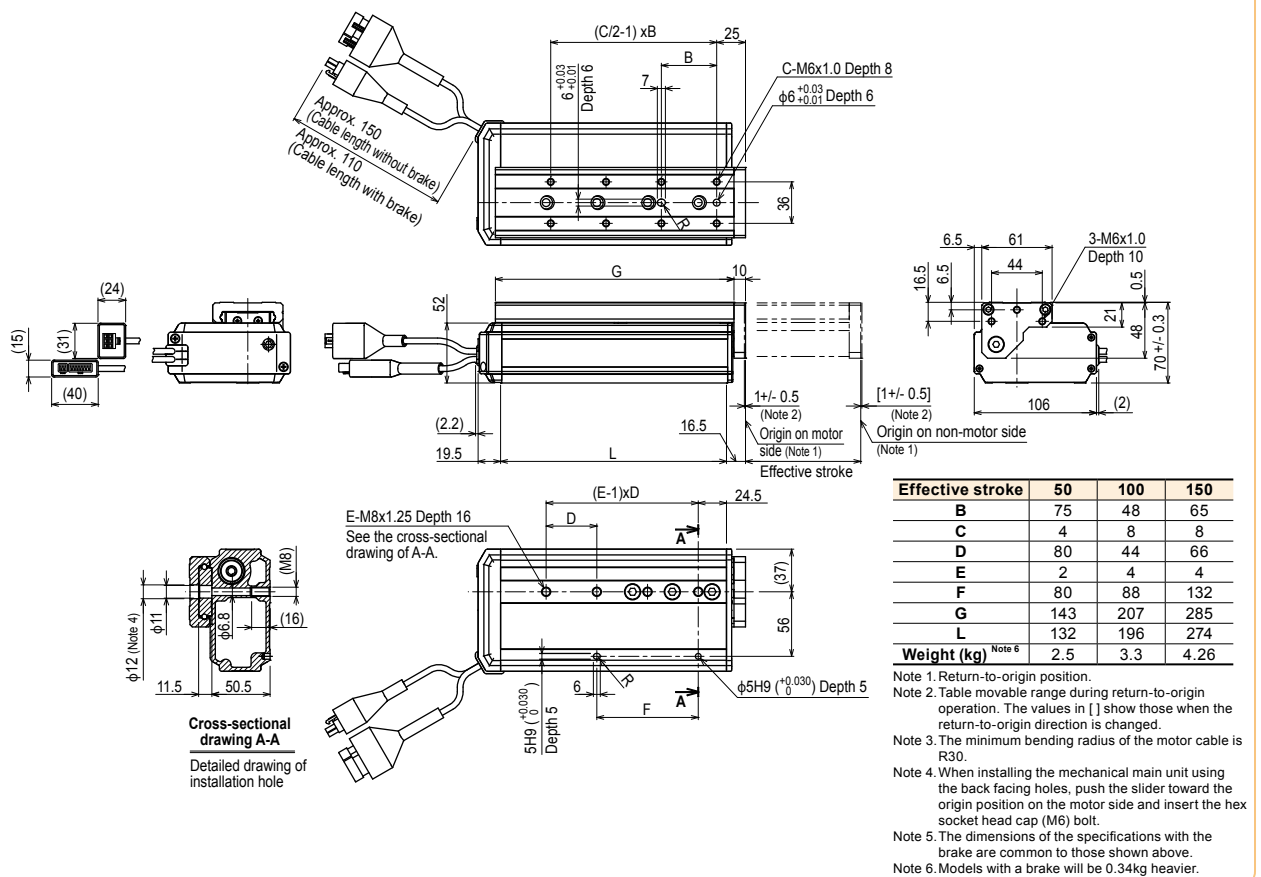
Effective stroke

Effective stroke	50	100	150
B	75	48	65
C	4	8	8
D	143	207	285
E	84	98.5	126.5
F	4	4	6
G	40.5	88	69
L	144.5	206.5	284.5
Weight (kg) ^{Note 6}	2.52	3.27	3.6

Option: Installation plate
Contents of option: Plate, 4 pcs.
* For additional settings, contact your distributor.

Note 1. Return-to-origin position.
Note 2. Table movable range during return-to-origin operation. The values in [] show those when the return-to-origin direction is changed.
Note 3. The minimum bending radius of the motor cable is R30.
Note 4. When installing the mechanical main unit using the back facing holes, use the hex socket head cap M6 bolts.
Note 5. The installation hole positions of the main unit with the specifications with the brake are common to those shown above.
Note 6. Models with a brake will be 0.34kg heavier.

STH06 Space-saving model (motor installed on right) **R**



STH06 Space-saving model (motor installed on left) **L**

