

STH06

Slide table type



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

Ordering method

STH06

Model	Lead	Model	Brake	Origin position	Bracket plate	Stroke	Cable length
	08: 8mm 16: 16mm	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: No plate H: With plate	50: 50mm 100: 100mm 150: 150mm	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

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

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	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. 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.634 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.96.

Basic specifications

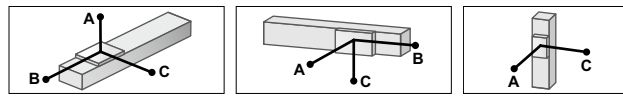
Motor	42 □ Step motor	
Resolution (Pulse/rotation)	20480	
Repeatability (mm)	+/- 0.05	
Drive method	Straight	Slide screw
	Space-saving	Slide screw + belt
Ball screw lead (mm)	8 16	
Maximum speed (mm/sec)	150 400	
Maximum payload (kg)	Horizontal	9 6
	Vertical	4 2
Max. pressing force (N)	180 100	
Stroke (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. 254.

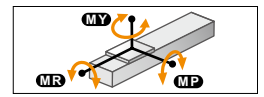
Allowable overhang



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

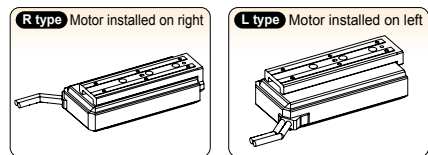
Note. Overhang at travelling service life of 3000km. (Service life is calculated for 100mm stroke models.)

Static loading moment

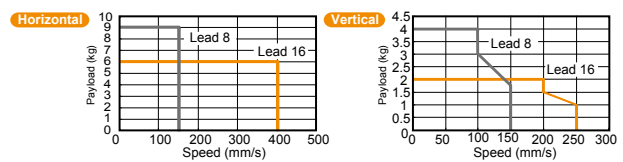


Stroke	(Unit: N-m)		
	MY	MP	MR
50mm	77	77	146
100mm	112	112	177
150mm	155	155	152

Motor installation (Space-saving model)



Speed vs. payload

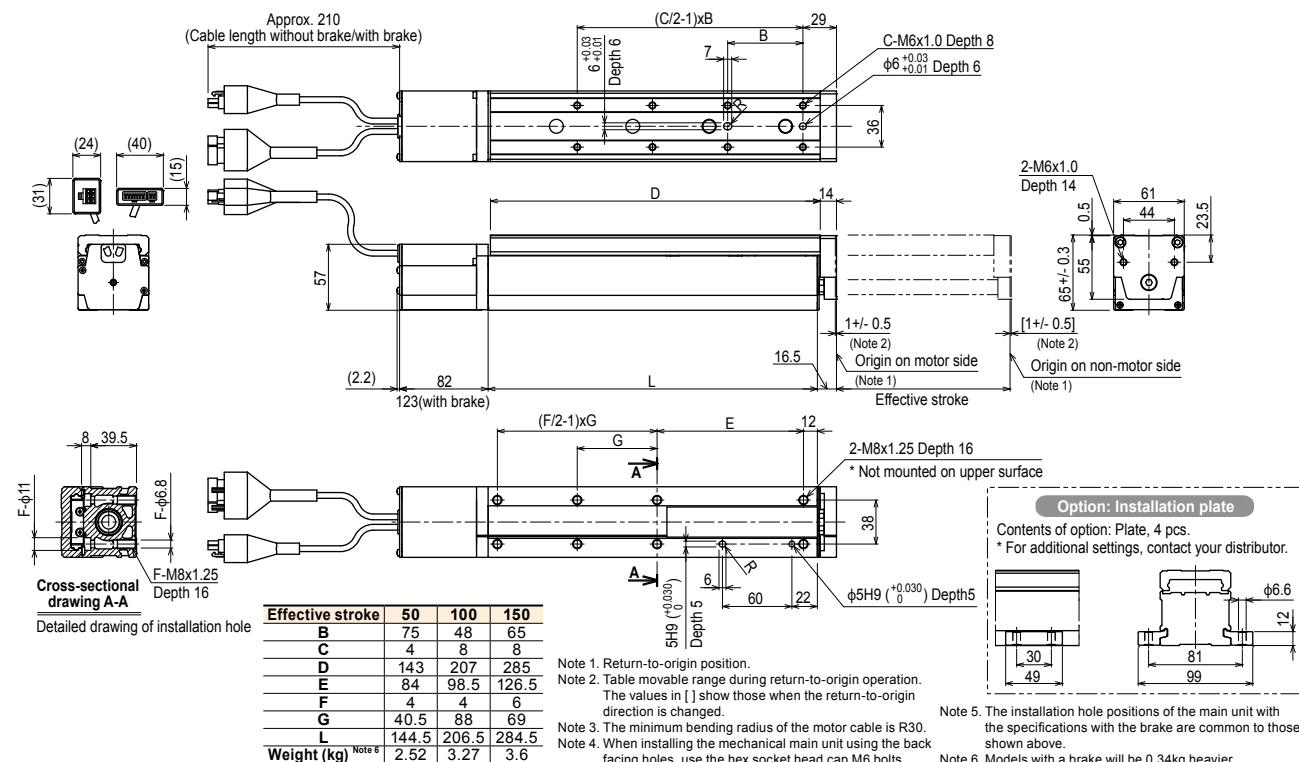


Controller

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

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

STH06 Straight model S



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.

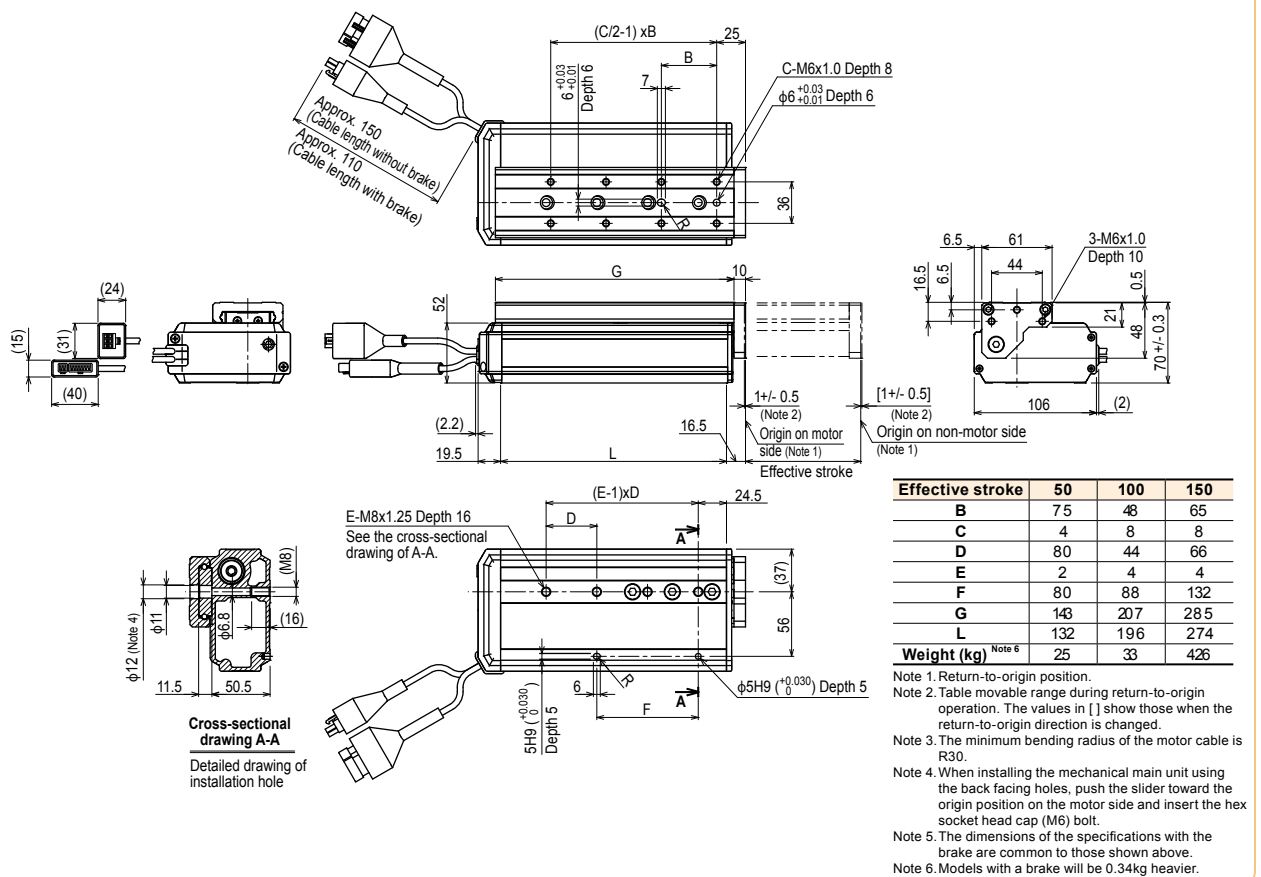
Note 3. The minimum bending radius of the motor cable is R30.

Note 4. When installing the mechanical main unit using the back facing holes, use the hex socket head cap M6 bolts.

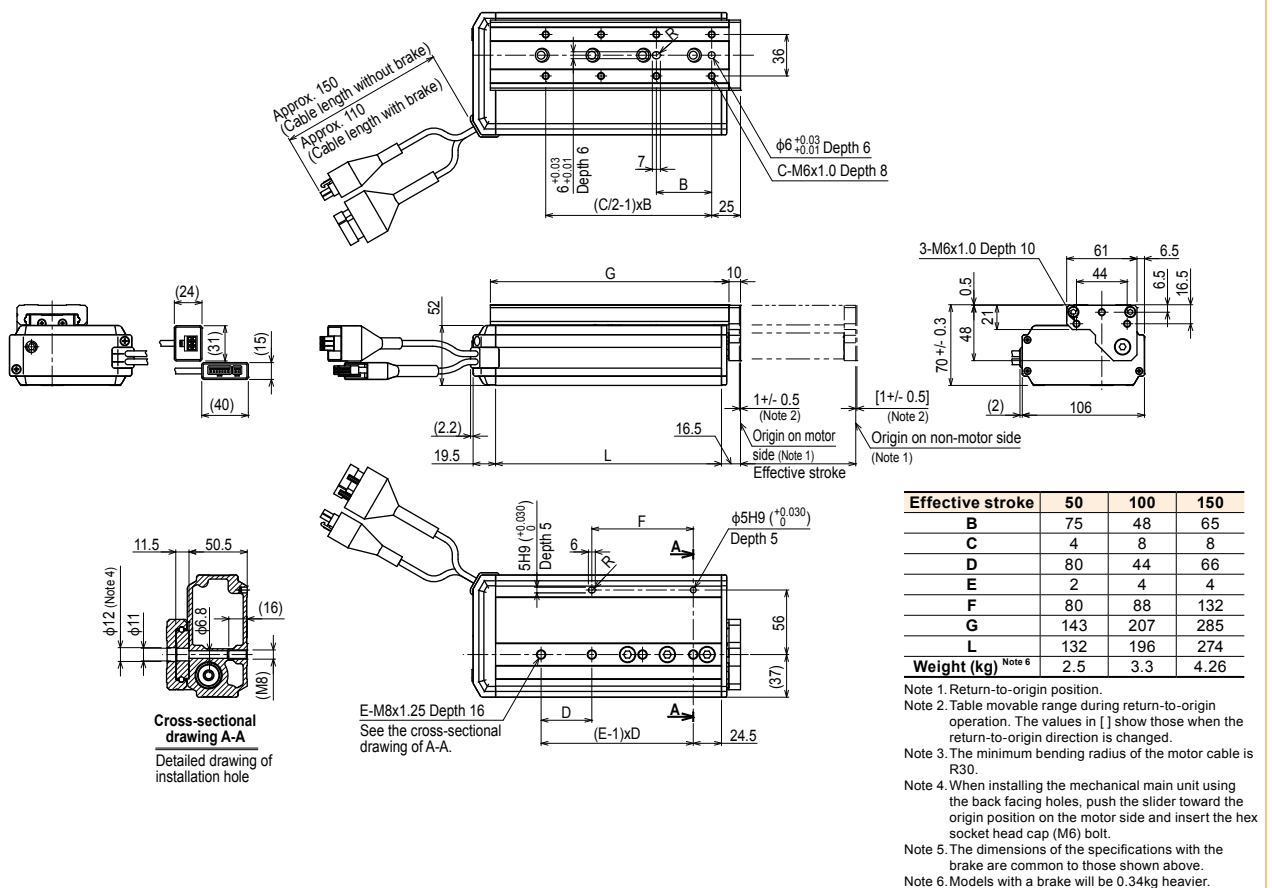
Note 5. The installation hole positions of the main unit with the specifications with the brake are common to those shown above.

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**



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