STH06 Slide table type

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

## Ordering method

**STH06**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Model</th>
<th>Lead (mm)</th>
<th>Brake</th>
<th>Origin position</th>
<th>Stroke</th>
<th>Cable length (m)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>W/O brake</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>W/O brake</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**S2**

<table>
<thead>
<tr>
<th>Robot position</th>
<th>Option 1</th>
<th>Option 2</th>
<th>Option 3</th>
<th>Option 4</th>
<th>Option 5</th>
<th>Option 6</th>
</tr>
</thead>
<tbody>
<tr>
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<td></td>
<td></td>
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</tbody>
</table>

**SH**

<table>
<thead>
<tr>
<th>Robot position</th>
<th>Option 1</th>
<th>Option 2</th>
<th>Option 3</th>
<th>Option 4</th>
<th>Option 5</th>
<th>Option 6</th>
</tr>
</thead>
<tbody>
<tr>
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</tbody>
</table>

**SD**

<table>
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<th>Robot position</th>
<th>Option 1</th>
<th>Option 2</th>
<th>Option 3</th>
<th>Option 4</th>
<th>Option 5</th>
<th>Option 6</th>
</tr>
</thead>
<tbody>
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</tr>
</tbody>
</table>

### Basic specifications

**Motor**

- 42 [Step motor]

**Resolution (Pulse/rotation)**

- +/-0.05

**Drive method**

- Space-saving: Slide screw

- Vertical: 4 2

**Max. pressing force (N)**

- 180 100

**Maximum speed (mm/sec)**

- 1000 500

**Maximum payload (kg)**

- 9 6

**Allowable overhang**

- 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. 152.

### Speed vs. payload

**Horizontal installation**

- W: With brake

- Z: Without brake

- H: With plate

**Vertical installation**

- Width: 4 2

**Motor installation (Space-saving model)**

- 1: Motor installed on right

- 2: Motor installed on left

**Controller**

- Operation method:
  - TS-S2: PO point source
  - TS-SH: Remote command
  - TS-SD: Pulse train control

**Note**

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

### Statically applied loading moment

**Stroke**

- MY: 90mm

- MP: 150mm

- MR: 200mm

**Control panel I/O cable**

- 1m

**Allowable overhang**

Note 1. If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, see P. 66.

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. 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.