**STH06**

**Slide table type**

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

### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead screw</th>
<th>Model</th>
<th>Brake</th>
<th>Origin position</th>
<th>Stroke</th>
<th>Cable length</th>
<th>Robot positioner</th>
<th>I/O point trace</th>
</tr>
</thead>
<tbody>
<tr>
<td>S2</td>
<td>Straight</td>
<td>S2</td>
<td>No brake</td>
<td>Straight</td>
<td>1000</td>
<td>1000</td>
<td>TS-SH/TS-SD</td>
<td>EP: EtherNet/IP</td>
</tr>
<tr>
<td></td>
<td></td>
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<td></td>
<td></td>
<td></td>
<td>PT: PROFINET</td>
</tr>
<tr>
<td></td>
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<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>DN: DeviceNet</td>
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<tr>
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<td></td>
<td></td>
<td></td>
<td></td>
<td>CC: CC-Link</td>
</tr>
<tr>
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<td></td>
<td></td>
<td></td>
<td>PN: PNP</td>
</tr>
</tbody>
</table>

### Basic specifications

**Motor**
- 42 [Step motor]

**Resolution (Pulse/rotation)**
- 20480

**Repeatability (mm)**
- +/-0.05

**Drive method**
- Straight
- Slide screw

**Ball screw lead (mm)**
- 8
- 16

**Maximum speed (mm/sec)**
- 200
- 400

**Maximum payload (kg)**
- 9
- 6

**Max. pressing force (N)**
- 180
- 100

**Stroke (mm)**
- 50/100/150

**Minimum outside dimension of body cross-section (mm)**
- W61 x H65
- W108 x H70

**Cable length (mm)**
- Vertical
- 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.

### Motor installation (Space-saving model)

- **S-type** (Motor installed on right)
- **L-type** (Motor installed on left)

### Allowable overhang

**Horizontal installation**
- [Graph]

**Wall installation**
- [Graph]

**Vertical installation**
- [Graph]

**Stroke (mm)**
- MY: 1000
- MP: 1000
- MR: 1500

**Speed vs. payload**

- [Graph]

**Effective stroke**
- 50 mm
- 100 mm
- 150 mm

**Effective stroke (mm/sec)**
- 200
- 400
- 600

**Max. pressing force (N)**
- 4kg
- 6kg
- 9kg

**Maximum payload (kg)**
- 4kg
- 6kg
- 9kg

**Note 1.** Return-to-origin position.

**Note 2.** Moveable range during return-to-origin operation. The values in [ ] show those when the return-to-origin direction is changed.

**Note 3.** The maximum bending radius of the motor cable is 204mm.

**Note 4.** When installing the mechanical main unit saving 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.

### Static loading moment

- [Graph]

- [Graph]

- [Graph]

- [Graph]

### Controller

- **Operation method**
  - TS-S2: PO point command / Remote command
  - TS-SH: Pulse train control

- [Note 1] The robot with the brake cannot use the TS-S2.

### Controller

- [Graph]

- [Graph]

- [Graph]

- [Graph]

- [Graph]

- [Graph]

- [Graph]

- [Graph]