SS04 Slider type

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

SS04-S   SS04-R

■ Ordering method

| SS04 - | | | | | | | | | S2 | | SH | | SD | 1 |

Model
Lead
12: 12mm
06: 6mm
02: 2mm

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

Grease option
N: Standard grease
C: Clean room grease

Stroke
50 to 400 (50mm pitch)

Cable length Note 2
1K: 1m
3K: 3m
5K: 5m
10K: 10m

S2
Robot positioner
S2: TS-S2 Note 3

I/O
NP: NPN
PN: PNP
CC: CC-Link
DN: DeviceNet™
EP: EtherNet/IP™
PT: PROFINET
GW: No I/O board Note 4

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 4

Battery
B: With battery (Absolute)
N: None (Incremental)

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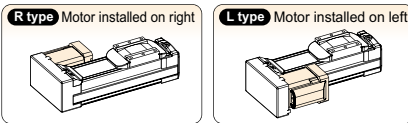
1
I/O cable
1: 1m

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.522 for DIN rail mounting bracket.
Note 4. Select this selection when using the gateway function. For details, see P.66.
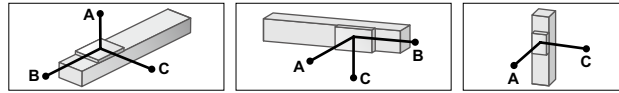
■ Basic specifications

Motor	42 □ Step motor		
Resolution (Pulse/rotation)	20480		
Repeatability Note 1 (mm)	+/-0.02		
Deceleration mechanism	Ball screw φ8		
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	4	6
Vertical	1	2	4
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.

■ Motor installation (Space-saving model)

R type Motor installed on right   **L type** Motor installed on left

■ Allowable overhang Note

Horizontal installation (Unit: mm)			
	A	B	C
Lead 12 1kg	807	218	292
Lead 12 2kg	667	107	152
Lead 6 2kg	687	116	169
Lead 6 3kg	556	76	112
Lead 6 4kg	567	56	84
Lead 2 4kg	869	61	92
Lead 2 6kg	863	40	60

Wall installation (Unit: mm)			
	A	B	C
Lead 12 1kg	274	204	776
Lead 12 2kg	133	93	611
Lead 6 2kg	149	102	656
Lead 6 3kg	92	62	516
Lead 6 4kg	63	43	507
Lead 2 4kg	72	48	829
Lead 2 6kg	39	29	789

Vertical installation (Unit: mm)		
	A	C
Lead 12 0.5kg	407	408
Lead 12 1kg	204	204
Lead 6 1kg	223	223
Lead 6 2kg	107	107
Lead 2 2kg	118	118
Lead 2 4kg	53	53

Note. Distance from center of slider upper surface to carrier center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 400mm stroke models).
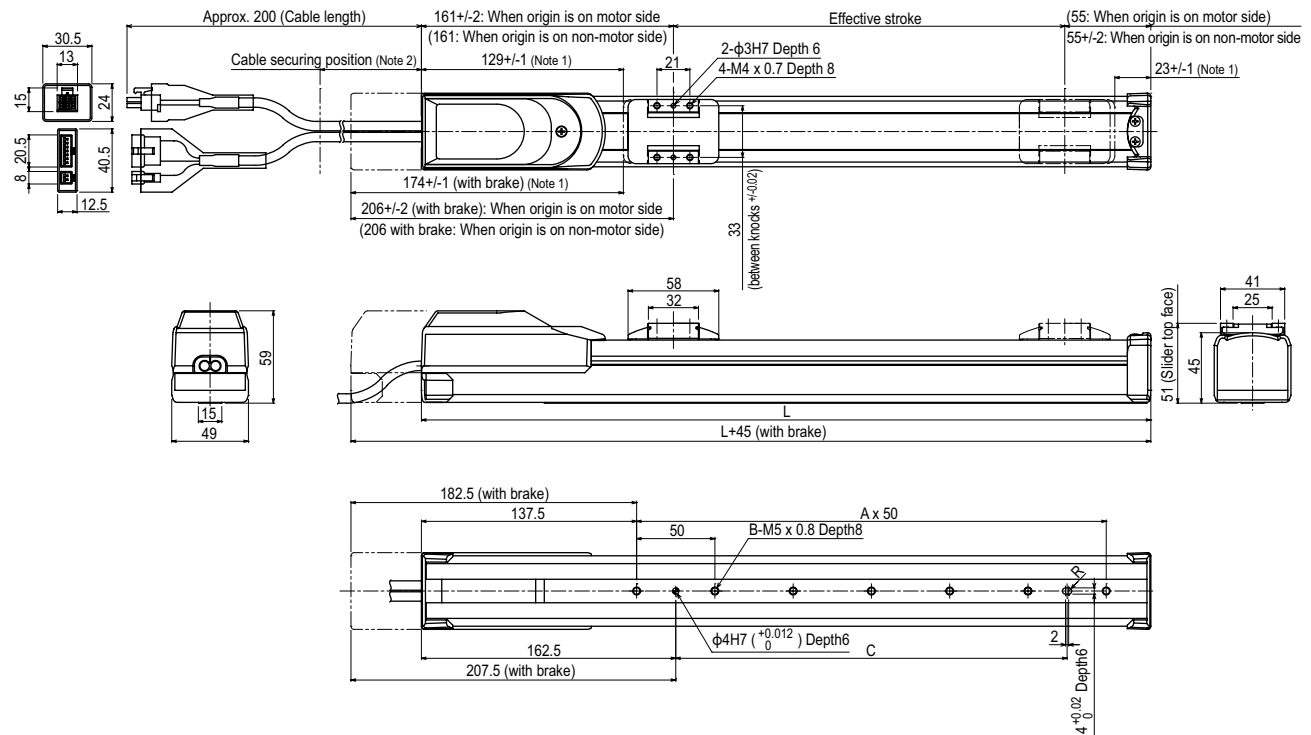
■ Static loading moment

		(Unit: N·m)
MY	MP	MR
16	19	17

■ Controller

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

SS04 Straight model S

Approx. 200 (Cable length)

161+/-2: When origin is on motor side
(161: When origin is on non-motor side)

Effective stroke

(55: When origin is on motor side)
55+/-2: When origin is on non-motor side

Cable securing position (Note 2)

129+/-1 (Note 1)

21

2-φ3H7 Depth 6
4-M4 x 0.7 Depth 8

23+/-1 (Note 1)

30.5
13
15
24
8
20.5
40.5
12.5

174+/-1 (with brake) (Note 1)
206+/-2 (with brake): When origin is on motor side
(206 with brake: When origin is on non-motor side)

33 (between knocks +0.02/0)

59
15
49

58
32

L
L+45 (with brake)

41
25
51 (Slider top face)
45

182.5 (with brake)
137.5
50
B-M5 x 0.8 Depth8

A x 50

162.5
207.5 (with brake)

φ4H7 (+0.012/0) Depth6   C

2
4 +0.02/0 Depth6

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.

Controller   TS-S2 ▶ 514 | TS-SH ▶ 514 | TS-SD ▶ 524

YA — Articulated robots

LCM100 — Linear conveyor modules

Robonity — Motor-less single axis actuator

TRANSERVO — Compact single-axis robots

FLIP-X — Single-axis robots

PHASER — Linear motor single-axis robots

XY-X — Cartesian robots

YK-X — SCARA robots

YP-X — Pick & place robots

CLEAN

CONTROLLER

INFORMATION

SS04　Space-saving model　R　L

SS04-L Specifications

128.5 (with brake)
88.5
56.5
33 (Tolerance between knocks +/-0.02)
49
50 +/-1 (Note 1)
21
4-M4×0.7 Depth 8
2-φ3H7 Depth 6
23 +/-1 (Note 1)
(82 +/-2: When origin is on motor side)
(82: When origin is on non-motor side)
(55: When origin is on motor side)
55 +/-2: When origin is on non-motor side
Effective stroke

(31)
(24)
(40)
(15)
50
15
101
110
58
32
(Note 2)
Cable securing position
Approx. 245 (Cable length)
L
41
25
51 (Slider top face)

58.5
50
A×50
B-M5×0.8 Depth 12
φ4H7 +0.012/0 Depth 6
2
4 +0.02/0 Depth 6
38
C
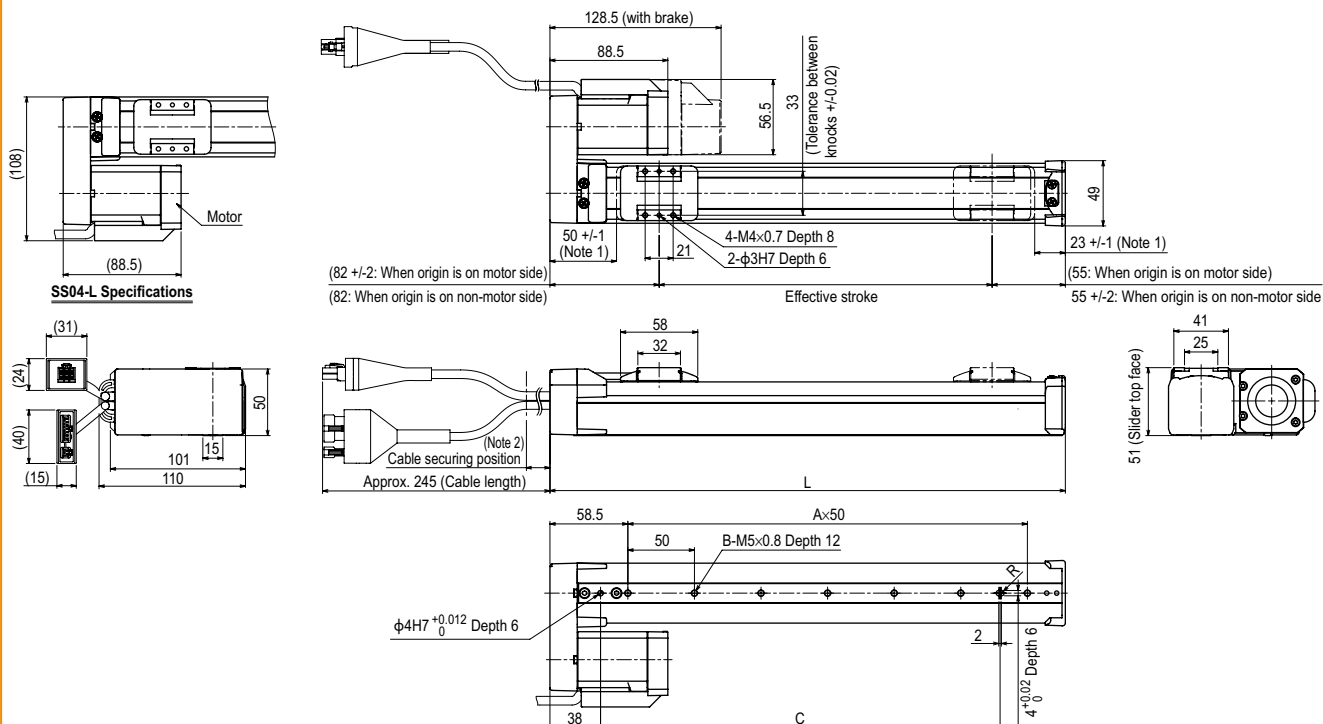
Effective stroke	50	100	150	200	250	300	350	400
L	187	237	287	337	387	437	487	537
A	2	3	4	5	6	7	8	9
B	3	4	5	6	7	8	9	10
C	100	150	200	250	300	350	400	450
Weight (kg) Note 4	1.2	1.4	1.5	1.6	1.7	1.8	1.9	2.1

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.

YA | Articulated robots
LCM100 | Linear conveyor modules
Robonity | Motor-less single axis actuator
TRANSERVO | Compact single-axis robots
FLIP-X | Single-axis robots
PHASER | Linear motor single-axis robots
XY-X | Cartesian robots
YK-X | SCARA robots
YP-X | Pick & place robots
CLEAN
CONTROLLER
INFORMATION

SS05 Slider type

SS05-S

SS05-R

● High lead: Lead 20   ● CE compliance   ● Origin on the non-motor side is selectable

■ Ordering method

SS05 –

Model	Lead	Model	Brake Note 1	Origin position	Grease option	Stroke	Cable length Note 3
	20: 20mm 12: 12mm 06: 6mm	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 2 Z: Non-motor side	N: Standard grease C: Clean room grease	50 to 800 (50mm pitch)	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

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

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 5	B: With battery (Absolute) N: None (Incremental)

SD   1

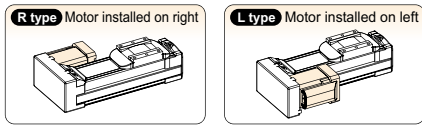| Robot driver	I/O cable
SD: TS-SD	1: 1m

Note 1. Brake-equipped models can be selected only when the lead is 12mm or 6mm.
Note 2. 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 3. The robot cable is flexible and resists bending.
Note 4. See P.522 for DIN rail mounting bracket.
Note 5. Select this selection when using the gateway function. For details, see P.66.
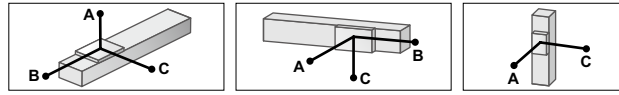
■ Basic specifications

Motor		42 □ Step motor
Resolution (Pulse/rotation)		20480
Repeatability Note 1 (mm)		+/-0.02
Deceleration mechanism		Ball screw φ12
Maximum motor torque (N·m)		0.27
Ball screw lead (mm)		20 / 12 / 6
Maximum speed Note 2 (mm/sec)		1000 / 600 / 300
Maximum payload (kg)	Horizontal	4 / 6 / 10
	Vertical	– / 1 / 2
Max. pressing force (N)		27 / 45 / 90
Stroke (mm)		50 to 800 (50mm pitch)
Overall length (mm)	Horizontal	Stroke+230
	Vertical	Stroke+270
Maximum outside dimension of body cross-section (mm)		W55 × H56
Cable length (m)		Standard: 1 / Option: 3, 5, 10

Note 1. Positioning repeatability in one direction.
Note 2. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

■ Allowable overhang Note

A, B, C diagrams

Horizontal installation (Unit: mm)

		A	B	C
Lead 20	2kg	413	139	218
	4kg	334	67	120
Lead 12	4kg	347	72	139
	6kg	335	47	95
Lead 6	4kg	503	78	165
	8kg	332	37	79
	10kg	344	29	62

Wall installation (Unit: mm)

		A	B	C
Lead 20	2kg	192	123	372
	4kg	92	51	265
Lead 12	4kg	109	57	300
	6kg	63	31	263
Lead 6	4kg	134	63	496
	6kg	76	35	377
	8kg	47	22	355

Vertical installation (Unit: mm)

		A	C
Lead 12	0.5kg	578	579
	1kg	286	286
Lead 6	1kg	312	312
	2kg	148	148

Note. Distance from center of slider upper surface to carrier center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).

■ Static loading moment

MY, MP, MR diagram

		(Unit: N·m)
MY	**MP**	**MR**
25	33	30

■ Controller

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

SS05   Straight model   S

Approx. 200 (Cable length)
Cable securing position (Note 2)
30.5 / 13 / 15 / 24 / 8 / 20.5 / 40.5 / 12.5

178+/-2: When origin is on motor side
(178: When origin is on non-motor side)
140+/-1 (Note 1)
34
2-φ4H7 Depth 6
4-M4 x 0.7 Depth8
180+/-1 (with brake) (Note 1)
218+/-2 (with brake): When origin is on motor side
(218 with brake: When origin is on non-motor side)
70 / 42
42 (between knocks +/-0.02)

Effective stroke
52+/-2: When origin is on motor side
(52: When origin is on non-motor side)
14+/-1 (Note 1)

56 / 24 / 55
L
L+40 (with brake)

141.5 (with brake)
101.5
50
B-M6 x 1 Depth8
126.5
166.5 (with brake)
A x 50
φ4H7 ($^{+0.012}_{0}$) Depth6
C
2
4 $^{+0.02}_{0}$ Depth6

50 / 34 / 57 (Slider top face) / 51

Effective stroke	50	100	150	200	250	300	350	400	450	500	550	600	650	700	750	800
L	280	330	380	430	480	530	580	630	680	730	780	830	880	930	980	1030
A	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
B	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19
C	100	150	200	250	300	350	400	450	500	500	500	500	500	500	500	500
Weight (kg) Note 4	2.1	2.3	2.5	2.7	2.8	3.0	3.2	3.4	3.6	3.8	4.0	4.2	4.4	4.6	4.8	5.0
Maximum speed for each stroke Note 5 (mm/sec) — Lead20	1000												933	833	733	633
Lead12	600												560	500	440	380
Lead6	300												280	250	220	190
Speed setting	–												93%	83%	73%	63%

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.
Note 5. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

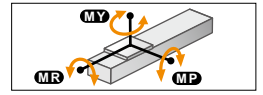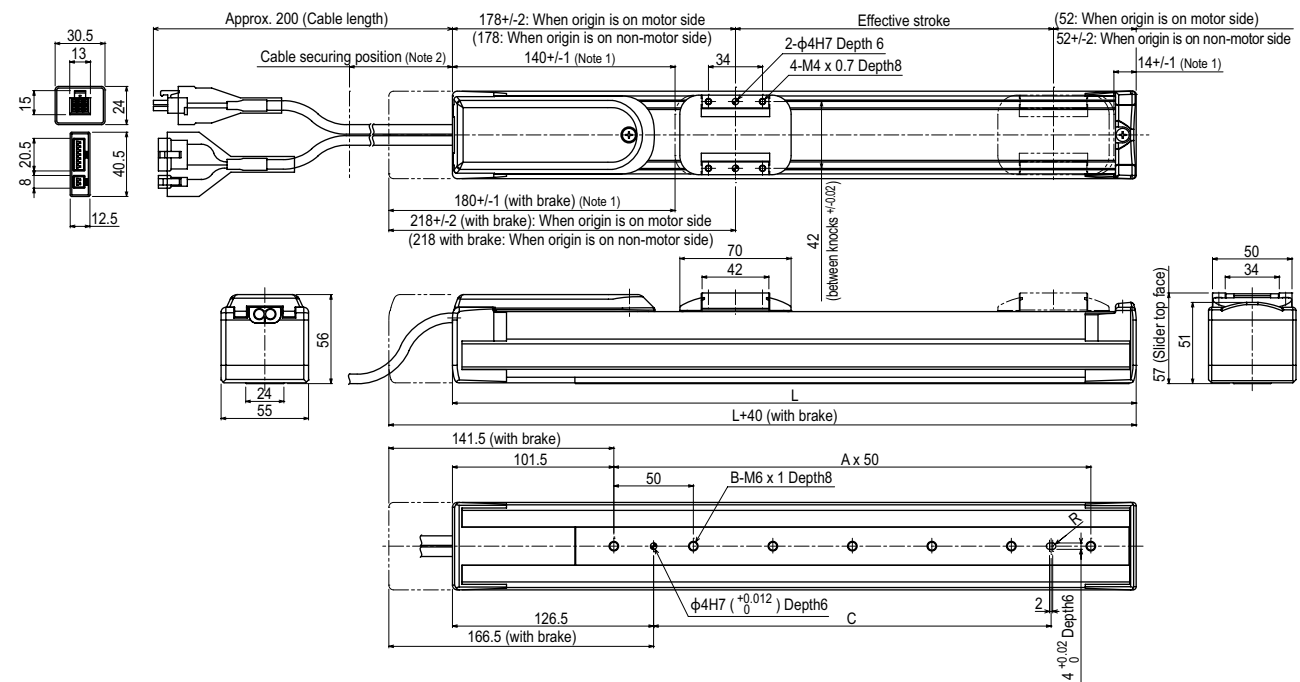## ■ Motor installation (Space-saving model)

R type | Motor installed on right
L type | Motor installed on left

SS05

YA — Articulated robots

LCM100 — Linear conveyor modules

Robonity — Motor-less single axis actuator

TRANSERVO — Compact single-axis robots

FLIP-X — Single-axis robots

PHASER — Linear motor single-axis robots

XY-X — Cartesian robots

YK-X — SCARA robots

YP-X — Pick & place robots

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INFORMATION

SS05　Space-saving model　R　L

(113)

Motor

(88.5)

SS05-L Specifications

(31)

(24)

(40)

(15)

104　24

113

55

128.5 (with brake)

88.5

56.5

42

(Tolerance between knocks +/-0.02)

55

56.5 +/-1 (Note 1)

34

4-M4×0.7 Depth 8

2-φ4H7 Depth 6

94.5 +/-2: When origin is on motor side

(94.5: When origin is on non-motor side)

Effective stroke

14 +/-1 (Note 1)

(52: When origin is on motor side)

52 +/-2: When origin is on non-motor side

70

42

Cable securing position (Note 2)

Approx. 245 (Cable length)

L

50

34

57 (Slider top face)

68

50

A×50

B-M6×1.0 Depth 12

φ4H7 $^{+0.012}_{0}$ Depth 6

Depth 6

2

$^{+0.02}_{0}$

4

42

C

Effective stroke		50	100	150	200	250	300	350	400	450	500	550	600	650	700	750	800
L		196.5	246.5	296.5	346.5	396.5	446.5	496.5	546.5	596.5	646.5	696.5	746.5	796.5	846.5	896.5	946.5
A		2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17
B		3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
C		100	150	200	250	300	350	400	450	500	500	500	500	500	500	500	500
Weight (kg) Note 4		1.6	1.8	2.0	2.2	2.4	2.6	2.8	3.0	3.2	3.4	3.6	3.8	4.0	4.1	4.3	4.5
Maximum speed for each stroke Note 5 (mm/sec)	Lead20	1000												933	833	733	633
	Lead12	600												560	500	440	380
	Lead6	300												280	250	220	190
	Speed setting	–												93%	83%	73%	63%

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. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

Note 6. The belt cover's left and right sides are asymmetrical. Therefore, if the motor mounting orientation is changed, the cover cannot be attached.

Controller　TS-S2 ▶ 514 | TS-SH ▶ 514 | TS-SD ▶ 524

YA | Articulated robots
LCM100 | Linear conveyor modules
Robonity | Motor-less single axis actuator
TRANSERVO | Compact single-axis robots
FLIP-X | Single-axis robots
PHASER | Linear motor single-axis robots
XY-X | Cartesian robots
YK-X | SCARA robots
YP-X | Pick & place robots
CLEAN
CONTROLLER
INFORMATION

SS05H Slider type

SS05H-S
SS05H-R

● High lead: Lead 20   ● CE compliance   ● Origin on the non-motor side is selectable

■ Ordering method

SS05H – [ ] [ ] [ ] [ ] [ ] [ ] [ ]

Model	Lead	Model	Brake Note 1	Origin position	Grease option	Stroke	Cable length Note 3
SS05H	20: 20mm 12: 12mm 06: 6mm	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 2 Z: Non-motor side	N: Standard grease C: Clean room grease	50 to 800 (50mm pitch)	1K: 1m 3K: 3m 5K: 5m 10K: 10m

S2

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

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 5	B: With battery (Absolute) N: None (Incremental)

SD   1

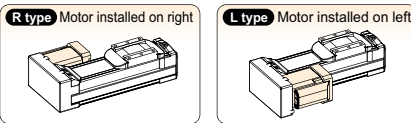| Robot driver	I/O cable
SD: TS-SD	1: 1m

Note 1. Brake-equipped models can be selected only when the lead is 12mm or 6mm.
Note 2. 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 3. The robot cable is flexible and resists bending.
Note 4. See P.522 for DIN rail mounting bracket.
Note 5. Select this selection when using the gateway function. For details, see P.66.

■ Basic specifications

Motor	42 □ Step motor		
Resolution (Pulse/rotation)	20480		
Repeatability Note 1 (mm)	+/-0.02		
Deceleration mechanism	Ball screw φ12		
Maximum motor torque (N·m)	0.47		
Ball screw lead (mm)	20	12	6
Maximum speed Note 2 Horizontal (mm/sec)	1000	600	300
Vertical	–	500	250
Maximum payload (kg) Horizontal	6	8	12
Vertical	–	2	4
Max. pressing force (N)	36	60	120
Stroke (mm)	50 to 800 (50pitch)		
Overall length Horizontal (mm)	Stroke+286		
Vertical	Stroke+306		
Maximum outside dimension of body cross-section (mm)	W55 × H56		
Cable length (m)	Standard: 1 / Option: 3, 5, 10		

Note 1. Positioning repeatability in one direction.
Note 2. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

■ Motor installation (Space-saving model)

R type Motor installed on right
L type Motor installed on left

■ Allowable overhang Note

Horizontal installation (Unit: mm)			
	A	B	C
Lead 20 2kg	599	225	291
4kg	366	109	148
6kg	352	71	104
Lead 12 4kg	500	118	179
6kg	399	79	118
8kg	403	56	88
Lead 6 6kg	573	83	136
8kg	480	61	100
10kg	442	47	78
12kg	465	39	64

Wall installation		(Unit: mm)	
	A	B	C
Lead 20 2kg	262	203	554
4kg	118	88	309
6kg	71	49	262
Lead 12 4kg	146	96	449
6kg	85	55	334
8kg	55	34	305
Lead 6 6kg	101	62	519
8kg	64	39	413
10kg	43	26	355
12kg	28	17	338

Vertical installation (Unit: mm)		
	A	C
Lead 12 1kg	458	459
2kg	224	224
Lead 6 2kg	244	245
4kg	113	113

Note. Distance from center of slider upper surface to carrier center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).

■ Static loading moment

MY MP MR

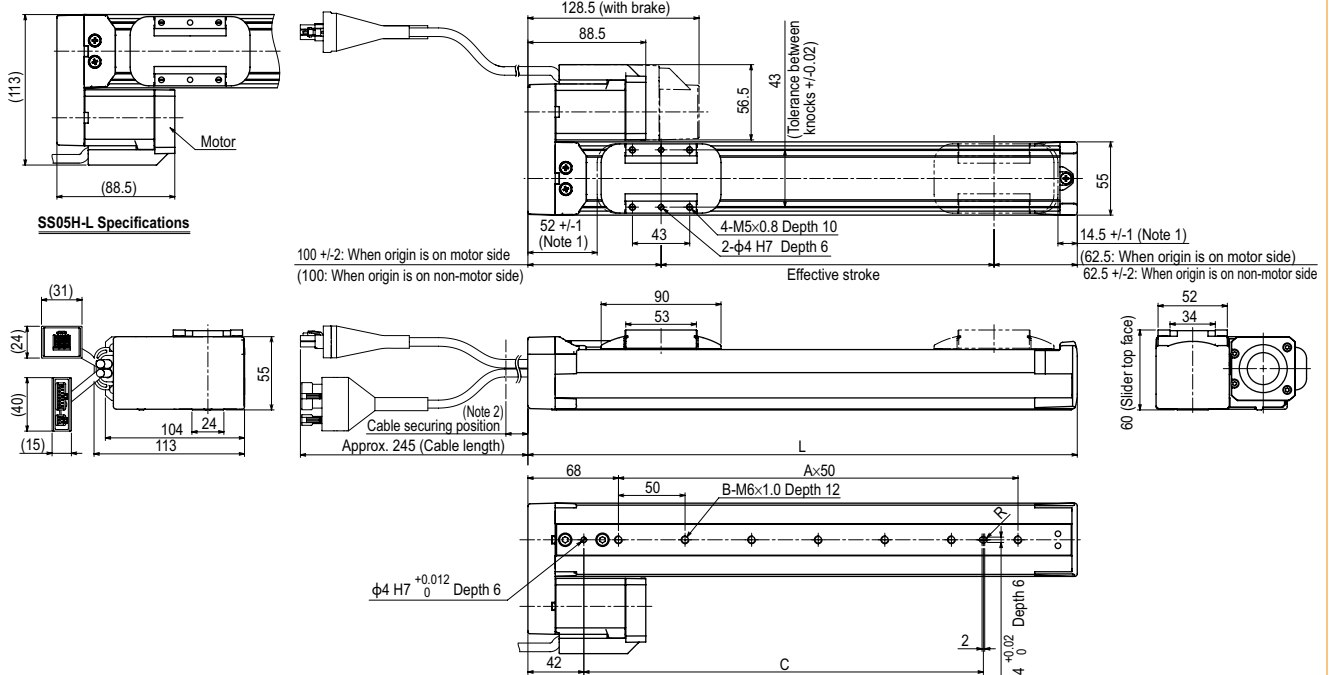|		(Unit: N·m)
MY	MP	MR
32	38	34

■ Controller

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

SS05H Straight model S

Approx. 200 (Cable length)
223.5+/-2: When origin is on motor side
(223.5: When origin is on non-motor side)
Effective stroke
(62.5: When origin is on motor side)
62.5+/-2: When origin is on non-motor side
Cable securing position (Note 2)
175.5+/-1 (Note 1)
43
2-φ4H7 Depth6
4-M5 x 0.8 Depth10
14.5+/-1 (Note 1)
30.5
13
15
24
8 20.5
40.5
12.5
195.5+/-1 (with brake) (Note 1)
243.5+/-2 (with brake): When origin is on motor side
(243.5 with brake: When origin is on non-motor side)
90
53
43 (between knocks +/-0.02)
56
24
55
L
L+20 (with brake)
52
34
60 (Slider top face)
51
161.5 (with brake)
141.5
50
A x 50
B-M6 x 1 Depth8
φ4H7 (+0.012 / 0) Depth6
2
4 +0.02 / 0 Depth6
166.5
186.5 (with brake)
C
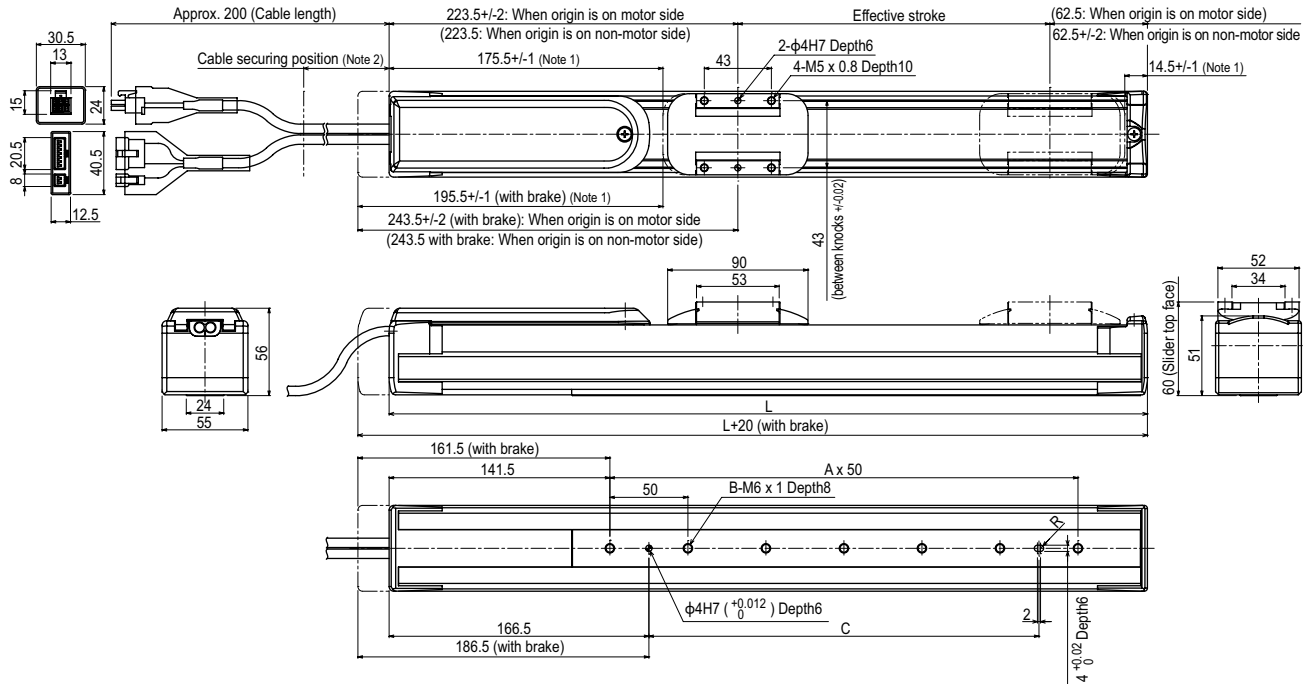
Effective stroke	50	100	150	200	250	300	350	400	450	500	550	600	650	700	750	800
L	336	386	436	486	536	586	636	686	736	786	836	886	936	986	1036	1086
A	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
B	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19
C	100	150	200	250	300	350	400	450	500	500	500	500	500	500	500	500
Weight (kg) Note 4	2.4	2.6	2.8	3.0	3.2	3.4	3.6	3.8	4.0	4.2	4.4	4.5	4.7	4.9	5.1	5.3
Maximum speed for each stroke Note 5 (mm/sec) Lead20	1000												933	833	733	633
Lead12 (Horizontal)	600												560	500	440	380
Lead12 (Vertical)	500														440	380
Lead6 (Horizontal)	300												280	250	220	190
Lead6 (Vertical)	250														220	190
Speed setting	–												93%	83%	73%	63%

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.
Note 5. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

SS05H

YA Articulated robots

LCM100 Linear conveyor modules

Robonity Motor-less single axis actuator

TRANSERVO Compact single-axis robots

FLIP-X Single-axis robots

PHASER Linear motor single-axis robots

XY-X Cartesian robots

YK-X SCARA robots

YP-X Pick & place robots

CLEAN

CONTROLLER

INFORMATION

SS05H Space-saving model R L

SS05H-L Specifications

Effective stroke	50	100	150	200	250	300	350	400	450	500	550	600	650	700	750	800
L	212.5	262.5	312.5	362.5	412.5	462.5	512.5	562.5	612.5	662.5	712.5	762.5	812.5	862.5	912.5	962.5
A	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17
B	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18
C	100	150	200	250	300	350	400	450	500	500	500	500	500	500	500	500
Weight (kg) Note 4	1.7	1.9	2.1	2.3	2.5	2.7	2.8	3.0	3.2	3.4	3.6	3.8	4.0	4.2	4.4	4.6
Maximum speed for each stroke Note 5 (mm/sec) Lead20	1000													933	833	733	633
Lead12 (Horizontal)	600													560	500	440	380
Lead12 (Vertical)	500															440	380
Lead6 (Horizontal)	300													280	250	220	190
Lead6 (Vertical)	250															220	190
Speed setting	–												93%	83%	73%	63%

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. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
Note 6. The belt cover's left and right sides are asymmetrical. Therefore, if the motor mounting orientation is changed, the cover cannot be attached.