

STH04

Slide table type

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

Ordering method

STH04

Model	Lead	Model	Brake	Origin position	Bracket plate	Stroke	Cable length
	05: 5mm 10: 10mm	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	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

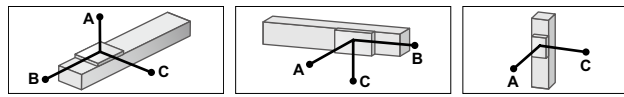
- Note 1. For the space saving models (R and L), the specifications with brake are applicable to only 100mm strokes.
 Note 2. If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, refer to the manual.
 Note 3. Space-saving models (R and L) with the plate cannot be selected.
 Note 4. The robot cable is flexible and resists bending.
 Note 5. See P.498 for DIN rail mounting bracket.
 Note 6. The robot with the brake cannot use the TS-SD.
 Note 7. Select this selection when using the gateway function. For details, see P.60.

Basic specifications

Motor	28 □ Step motor	
Resolution (Pulse/rotation)	4096	
Repeatability (mm)	+/-0.05	
Drive method	Straight	Slide screw
	Space-saving	Slide screw + belt
Ball screw lead (mm)	5 10	
Maximum speed (mm/sec)	200 400	
Maximum payload (kg)	Horizontal	6 4
	Vertical	2 1
Max. pressing force (N)	55 30	
Stroke (mm)	50/100	
Maximum outside dimension of body cross-section (mm)	Straight	W45 × H46
	Space-saving	W74.5 × H51
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



Horizontal installation (Unit: mm)	A			B			C		
	2kg	3kg	4kg	2kg	3kg	4kg	2kg	3kg	4kg
Lead 10	1534	949	656	611	374	255	415	255	175
Lead 5	1534	656	415	611	255	175	415	255	175
Lead 5	656	415	255	175	137	95	175	137	95

Wall installation (Unit: mm)	A			B			C		
	2kg	3kg	4kg	2kg	3kg	4kg	2kg	3kg	4kg
Lead 10	435	263	177	595	359	241	1504	920	629
Lead 5	435	177	123	595	1504	629	1504	629	337
Lead 5	123	91	61	123	337	241	629	337	241

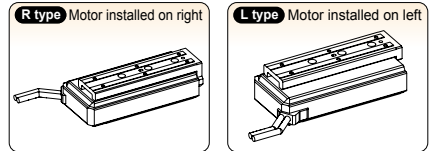
Vertical installation (Unit: mm)	A		C	
	0.5kg	0.75kg	1kg	1.5kg
Lead 10	2000	1568	1165	771
Lead 5	2000	1165	771	574
Lead 5	1165	771	574	574

- Note. Overhang at travelling service life of 3000km.
 (Service life is calculated for 75mm stroke models.)

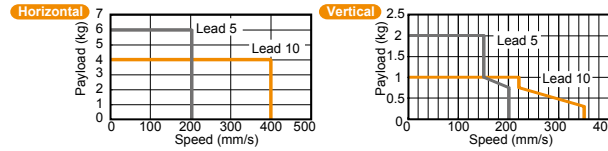
Static loading moment

Stroke	M			48
	MY	MP	MR	
50mm	26	26	26	
100mm	43	43	43	

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.

STH04 Straight model S

Effective stroke	50	100
B	40	44
C	6	8
D	116.5	191.5
E	65	85
G	39.5	88.5
L	122	191
Weight (kg)	1.25	1.7

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

Cross-sectional drawing A-A
 Detailed drawing of installation hole

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 M5 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 0.11kg heavier.

