

SSC04

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

Ordering method

SSC04		S						
Model	Lead	Type	Brake	Direction of air coupler installation	Origin position	Stroke	Cable length ^{Note 2}	
	12: 12mm 6: 6mm 2: 2mm	S: Straight	N: With no brake B: With brake	RJ: Right (Standard) LJ: Left	N: Standard ^{Note 1} Z: Non-motor side	50 to 400 (50mm pitch)	1L: 1m 3L: 3m 5L: 5m 10L: 10m	

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.498 for DIN rail mounting bracket.
 Note 4. Select this selection when using the gateway function. For details, see P.60.

Basic specifications

Motor	42 □ Step motor
Repeatability ^{Note 1} (mm)	+/-0.02
Deceleration mechanism	Ball screw φ8 (Class C10)
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
Degree of cleanliness	CLASS 10 ^{Note 2}
Intake air (Nl/min)	Lead 12 Lead 6 Lead 2 50 30 15

Note 1. Positioning repeatability in one direction.
 Note 2. Per 1cf (0.1µm base), when suction blower is used.

S2	I/O	
Robot positioner S2: TS-S2 ^{Note 3}	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 4}	
SH	I/O	Battery
Robot positioner SH: TS-SH	NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 4}	B: With battery (Absolute) N: None (Incremental)
SD	1	
Robot driver SD: TS-SD	I/O cable 1: 1m	

Allowable overhang

Horizontal installation (Unit: mm)				Wall installation (Unit: mm)				Vertical installation (Unit: mm)					
	A	B	C		A	B	C		A	C			
Lead 12	1kg	807	218	292	Lead 12	1kg	274	204	776	Lead 12	0.5kg	407	408
	2kg	667	107	152		2kg	133	93	611		1kg	204	204
Lead 6	2kg	687	116	169	Lead 6	2kg	149	102	656	Lead 6	1kg	223	223
	3kg	556	76	112		3kg	92	62	516		2kg	107	107
	4kg	567	56	84	Lead 4	4kg	63	43	507	Lead 4	2kg	118	118
Lead 2	4kg	869	61	92	Lead 2	4kg	72	48	829	Lead 2	4kg	53	53
	6kg	863	40	60	Lead 2	6kg	39	29	789				

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

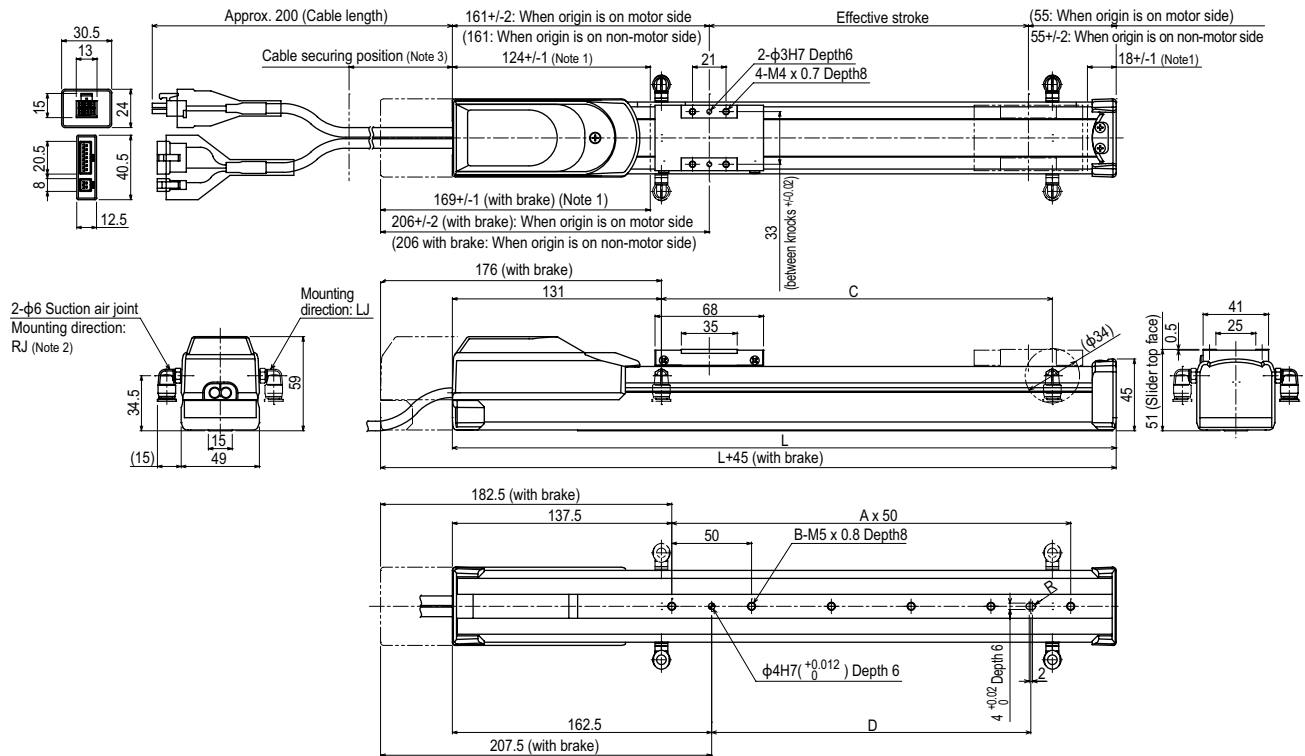
Static loading moment

Static loading moment (Unit: N-m)		
MY	MP	MR
16	19	17

Controller

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

SSC04



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 5}	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. Either right or left can be selected for the suction air joint mounting direction. This drawing shows the RJ (standard) direction.
 Note 3. 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 4. The cable's minimum bend radius is R30.
 Note 5. These are the weights without a brake. The weights are 0.2kg heavier when equipped with a brake.