

Table Top Robot TTA Series

Improved Tabletop Robot for Cell Production Applications, Featuring Significantly Higher Payload, Maximum Speed and Rigidity!



1. Significantly Higher Payload and Maximum Speed

		Conventional model	TTA
Maximum payload (kg)	Workpart side (X-axis)	10	20
	Tool side (Z-axis)	2	5
Maximum speed (mm/sec)	X-axis	300	800
	Y-axis	300	800
	Z-axis	300	400

➔ Up to 2.5 times

➔ Up to 2.6 times

2. Stores Much More Programs and Positions

The larger memory lets you store much more programs and positions. The additional data recovery function makes sure the original data can be restored should writing to a FLASH drive fails due to a power failure.

	Conventional model	TTA
Number of programs	64	255
Number of program steps	6,000	9,999
Number of multi-tasking programs	16	16
Number of display languages	2 (Japanese/English)	2 (Japanese/English)
Number of positions	3,000	30,000 (*1)

➔ 4 times more

➔ 10 times more

*1: 10,000 points can be backed up in the system memory.

3. Three Times As Many I/O Points As Conventional Models

When the standard I/O slot isn't enough, up to two additional expansion I/O slots can be installed.

Inputs/outputs

16 points/16 points ➔ Up to 48 points/48 points (*)

(*)When the expansion I/O slot (coming soon) is added

3 times more

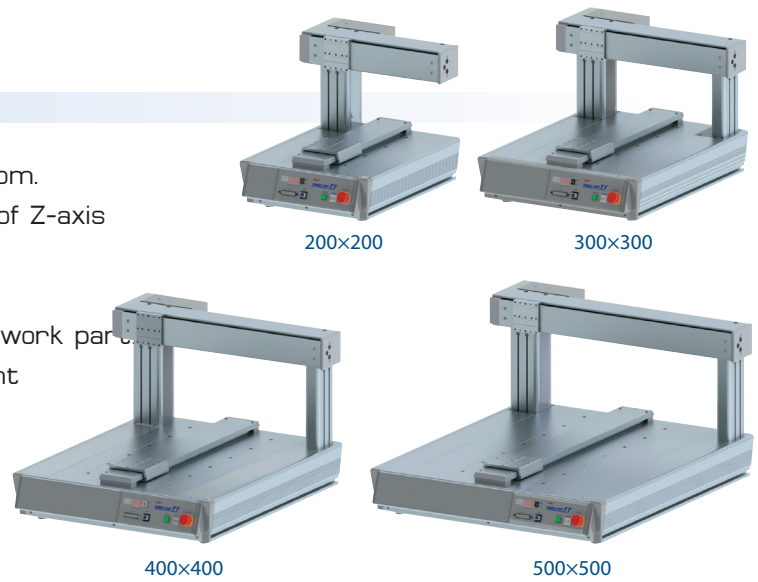
Supporting field networks



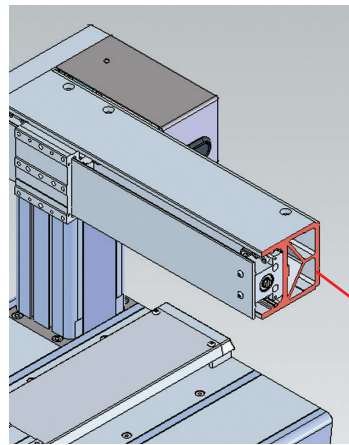
4. More Variations

Four operating ranges are available to choose from. The 3-axis specification is available in two types of Z-axis strokes: 100mm and 150mm. You can select a model ideal for the size of your work part. Additional options let you change the Y-axis height and position.

* You can also custom-order 4-axis robots.



5. Greater Bending Rigidity is Achieved by Integrating the Structure of the Y-axis Base with the Mounting Bracket.

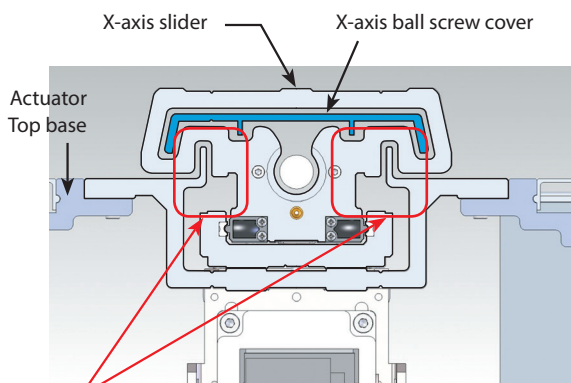


Bending rigidity at least 1.5 times higher than the conventional model

Y-axis base & mounting bracket in one Integral Structure

6. Labyrinth Structure to Suppress Intrusion of Foreign Matter into X-axis

The X-axis opening is structured as a labyrinth in order to make it difficult for foreign matter dropping onto the actuator (such as screws, molten metal, dust, etc.) to enter the X-axis. This expands the types of work environment supported.



Labyrinth structure

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