Robot cable length

Robot cable weight

Weight (Excluding robot cable) Note 4

YK120XG

Standard type: Extra small type

Arm length 120mm
Maximum payload 1kg

■ Ordering method

YK120XG - 50

RCX340-4 Cable

Standard: 2 m Option: 3.5 m, 5 m, 10 m

3.9 kg

0.9 kg (2 m) 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)

Specify various controller setting items. RCX340 ▶ P.636

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		45 mm	75 mm	50 mm	-
specifications	Rotation angle		+/-125 °	+/-145 °	-	+/-360 °
AC servo motor output			30 W	30 W	30 W	30 W
Deceleration mechanism	Transmission method	Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			3.3 m/sec		0.9 m/sec	1700 °/sec
Maximum payload			1.0 kg			
Standard cycle time: with 0.1kg payload Note 2			0.33 sec			
R-axis tolerable moment of inertia Note 3			0.01 kgm²			
User wiring			0.1 sq × 8 wires			
User tubing (Outer diameter)			ф 4 × 2			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 300 Operation using RS-232C communication

Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

Note 1. This is the value at a constant ambient temperature. (X,Y axes)

Note 2. When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

Note 4. The total robot weight is the sum of the robot body weight and the cable weight.

YK120XG The Z-axis upper end stopper is in contact with the base in an Connector for user wiring (No. 1 to 8 usable, socket contact) If the robot enters the inside of R12. the Z-axis upper end stopper may be in contact with the base. So, do not perform such motion. area inside from the inner limit of J.S.T. Mfg Co., Ltd. SM connector SMR-8V-B, pin SYM-001T-P0.6 this working envelope. So, do not perform any motion in this area. (supplied)
Use the YC12 crimping tool. (120)R30 rotational radius) Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy. If attaching wire or tube, make use of these air tubes. For details, refer to "10 When attaching a new user wire or tube" Working envelope in Chapter 3 325 Y-axis origin is at +/-5° with respect to front of 316 (Maximum 322 during arm rotation) 322 robot base 25 (Maximum 120 during arm rotation) When performing return-to-origin, move the axes counterclockwise in advance from the position shown above User tubing 2 (φ4) User tubing 1 (φ4) Cross section A-A User tubing 1 (φ4) User tubing 2 (ф4) R-axis dog 105 105 M3 ground terminal 80 \end stopper Connector for user wiring (No. 1 to 8 usable, socket contact) (Z-axis origin position 20 J.S.T. Mfg Co., Ltd. SM connector SMR-8V-B, pin SYM-001T-P0.6 (supplied)
Use the YC12 crimping machine. 0 90.5 (43)41.5 32 No phase relation between flat spot and R-axis origin 47 User tool installation range ф10h 7 0 0.015 Hollow -φ5.5 through-hole **(b)** Use four M5 mounting bolt. Tapped hole for user 4-M3 x 0.5, depth: 7 Keep enough space for the maintenance work at the rear of the base. R27 (Min. cable bending radius) Details of B Do not move the cable