

SCARA ROBOTS

SERIES

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& drip-proof type

YK-X SPECIFICATION SHEET

Typ	Type Model			Arm length (mm) and XY axis resultant maximum speed (m/s)												Standard Maximum cycle time payload	R-axis tolerable moment of	Completely beltless	Detailed				
		model	12	0 150	180	22	0 2	50	300	350	400	500	600	700	800	900	1000	1200	(sec) Note 1	(kg)	inertia (kgm²)	structure Note 2	info page
Orbit	2	YK350TW				5.	6												0.32	5.0	0.005 (Rated) 0.05 (Maximum)		P.494
ō≥	3	YK500TW					6	.8											0.29	5.0	0.005 (Rated) 0.05 (Maximum)		P.496
anyl type	_ پ	YK120XG	3.	3															0.33	1.0	0.01	•	P.498
ed small type	2	YK150XG		3.4															0.33	1.0	0.01	•	P.499
	sma	YK180XG		3.3															0.33	1.0	0.01	•	P.500
1	Extra	YK180X		3.3															0.39	1.0	0.01	•	P.501
	_	YK220X			3.4														0.42	1.0	0.01	•	P.502
		YK250XG			4.5														0.43	5.0	0.05	•	P.503
1		YK350XG				5.	6												0.44	5.0	0.05	•	P.505
	Small	/K400XE-4					6.0												0.41	4.0	0.05		P.507
		YK400XG					6.1												0.45	5.0	0.05	•	P.508
	,	YK500XGL					5	.1											0.48	5.0	0.05	•	P.510
٦		YK500XG					7	6											0.42	10.0	0.30	•	P.512
Standard	g \	/K510XE-10					7	8											0.38	10.0	0.30		P.513
Sta	Medium type	YK600XGL						4.	9										0.54	5.0	0.05	•	P.514
1	Medi	YK600XG						8.4	4										0.43	10.0	0.30	•	P.516
	- 1	/K610XE-10						8.	6										0.39	10.0	0.30		P.517
	1	YK600XGH						7.	7										0.47	20.0	1.0	•	P.518
	1	YK700XGL							9.2										0.50	10.0	0.30	•	P.519
	Y	/K710XE-10		9.5															0.42	10.0	0.30		P.520
	ا ۾	YK700XG		8.4														0.42	20.0	1.0	•	P.521	
1	Large type	YK800XG		9.2													0.48	20.0	1.0	•	P.522		
-	La La	YK900XG	9.9															0.49	20.0	1.0	•	P.523	
	,	YK1000XG	10.6															0.49	20.0	1.0	•	P.524	
	ŀ	YK1200X 7.4												0.91	50.0	2.45		P.525					
	_	YK300XGS		4.4													0.49	5.0	0.05	•	P.526		
e e	,	YK400XGS		6.1														0.49	5.0	0.05	•	P.528	
se typ	,	YK500XGS				_	7	6											0.45	10.0	0.3	•	P.530
Wall mount / inverse type	,	YK600XGS						8.4	4										0.46	10.0	0.3	•	P.531
nt / ii	,	YK700XGS				-		_	8.4										0.42	20.0	1.0	•	P.532
mon	ļ	YK800XGS							9	.2									0.48	20.0	1.0	•	P.533
Wall	H	YK900XGS				-		_		9.9									0.49	20.0	1.0	•	P.534
	H	YK1000XGS								10	0.6								0.49	20.0	1.0	•	P.535
	-	YK250XGP			4.5														0.50	4.0	0.05	•	P.536
	H	YK350XGP				5.	6												0.52	4.0	0.05	•	P.538
	H	YK400XGP					6.1	=		_									0.50	4.0	0.05	•	P.540
/be		YK500XGLP						.1											0.66	4.0	0.05	•	P.542
oof ty	,	YK500XGP				_		6											0.55	10.0	0.3	•	P.544
Dust-proof & drip-proof type	,	YK600XGLP						4.	9										0.71	4.0	0.05	•	P.545
& dri	,	YK600XGP																	0.56	10.0	0.3	•	P.547
roof		/K600XGHP															0.57	18.0	1.0	•	P.548		
ust-p	,	YK700XGP							8.4										0.52	20.0	1.0	•	P.549
۵		YK800XGP								.2									0.58	20.0	1.0	•	P.550
	H	YK900XGP								9.9									0.59	20.0	1.0	•	P.551
	H	/K1000XGP									0.6								0.59	20.0	1.0	•	P.552
Note		The standard	d C	cle time	is mo	2611	red	nde	the f	_	_	ndition	18					ш					1.002

During back and forth movement 25mm vertically and 100mm horizontally (extra small type)
 During back and forth movement 25mm vertically and 300mm horizontally (small type / medium type / large type)

Note 2. Maintains high accuracy over long periods because the beltless structure drastically cuts down on wasted motion.

Operation is also nearly maintenance-free for long periods with no worries about belt breakage, stretching or deterioration over time.

& drip-proof type

Robot ordering method description

In the order format for the YAMAHA SCARA robots YK-X series, the notation (letters/numbers) for the mechanical section is shown linked to the controller section notation.

[Example]

■ Mechanical ➤ YK250XG

- Z-axis stroke ▷ 150mm
- Hollow shaft ▷ With hollow shaft
- Cable length ≥ 3.5m

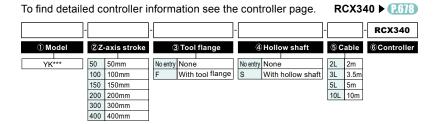
Ordering method

YK250XG-150-F-S-3L-RCX340

Mechanical section

Controller section

■ Controller ► RCX340



Note 1. Available only for the master.

Robot ordering method terminology

① Model	Enter the robot unit model.				
② Z-axis stroke	Select the Z axis stroke. The stroke varies with the model you select so see that model's page to confirm the specifications.				
③ Tool flange	Tool flange option for easy mounting of a tool to the tip. No entry: None F: With tool flange				
④ Hollow shaft	Hollow shaft option for easy routing of air tubes and harness wires. No entry: None S: With hollow shaft				
⑤ Cable	Select the length of the robot cable connecting the robot and controller. 2L: 2m (Note 1) 3L: 3.5m 5L: 5m 10L: 10m Note 1. Only selectable for YK120XG, YK150XG, YYK150XG, YK150XG, YK150XG, YK150XG, YK150XG, YK150XG, YK150XG, YY				
6 Controller	Select the RCX340.				

YK350TV

Orbit type

Arm length 350mm
Maximum payload 5kg

■ Ordering method

YK350TW- 130

Tool flange - Hollow shaft No entry: None
F: With tool flange
S: With hollow shaft

RCX340-4 Cable

Safety - Option A - Option B - Option C - Option D - Option E - Abset standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifi	cations							
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		175 mm	175 mm	130 mm	-		
specifications	Rotation angl	le	+/-225 °	+/-225 °	-	+/-720 °		
AC servo mot	or output		750 W	400 W	200 W	105 W		
Deceleration	Transmission	Motor to speed reducer	Timing belt	Direct-coupled	Timing belt	Timing belt		
mechanism	method	Speed reducer to output		Direct-coupled		l illing belt		
Repeatability	Note 1		+/-0.0	01 mm	+/-0.01 mm	+/-0.01 °		
Maximum spe	ed		5.6 r	n/sec	1.5 m/sec	3000 °/sec		
Maximum pay	load Note 2		5 kg					
Standard cycl	e time: with 1k	g payload ^{Note 3}	0.32 sec					
R-axis tolerab	le moment of	Rated	0.005 kgm ²					
inertia Note 4		Maximum	0.05 kgm²					
User wiring			0.15 sq × 8 wires					
User tubing (C	Outer diameter	r)	φ6×2					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m					
Weight			26 kg					

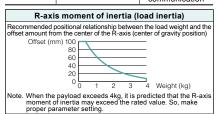
Note 1. This is the value at a constant ambient temperature

Note 2. Tool flange specifications (option) are 4 kg.

Note 3. When moving a 1 kg load back and forth 300mm horizontally and 25mm vertically (rough positioning arch motion).

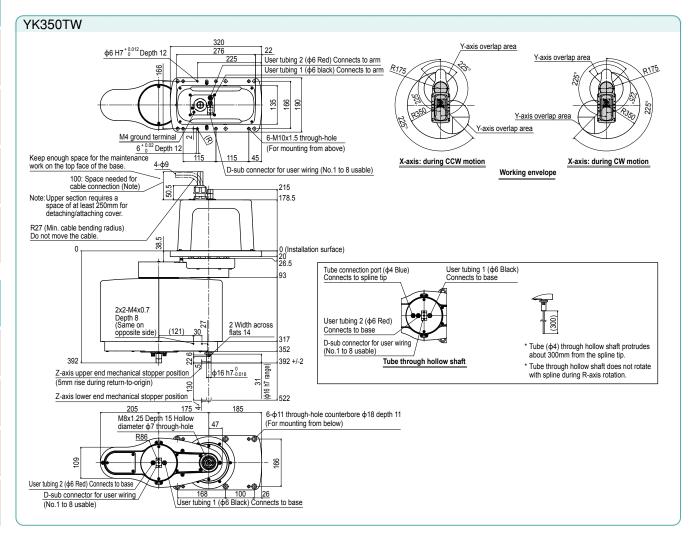
Note 4. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

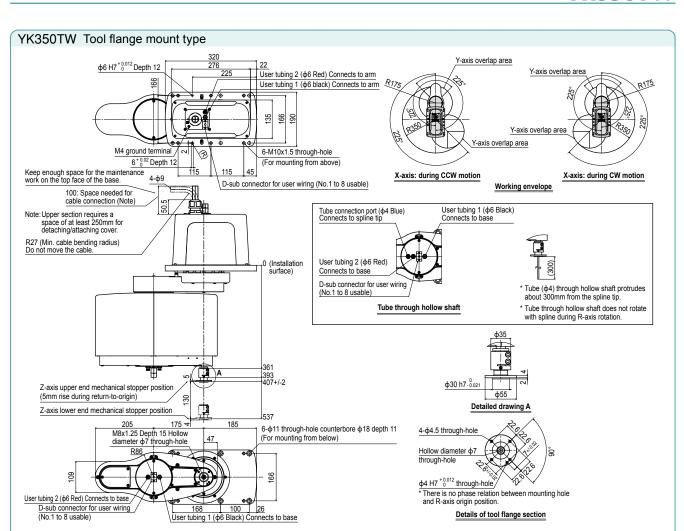
■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 2500 Operation using RS-232C communication



To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

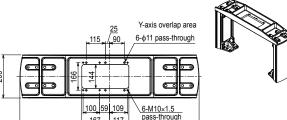


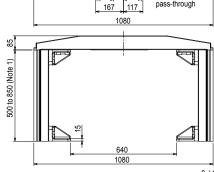


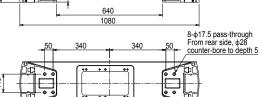
■ Dedicated mounting bracket for the YK-TW <BASE POST ASSY.>

The YK-TW can be easily installed on top of a customer-provided stand.

External diagram for the YK350TW







The mounting bracket is assembled by the customer. Refer to the included assembly diagram for assembly.

Note 1. Identical to the height of the robot mounting surface The height of the stand can be selected at a 50 mm pitch.

Height (mm)	Model	Unit weight (kg)
500	KDU-M6100-P0	46
550	KDU-M6100-50	48
600	KDU-M6100-R0	50
650	KDU-M6100-60	51
700	KDU-M6100-S0	54
750	KDU-M6100-70	55
800	KDU-M6100-T0	57
850	KDU-M6100-80	59

Note, YK350TW and YK500TW are parts in common.

Note. The top plate by itself weighs 19 kg.

Bolts supplied with the controller

1	1	M16 x Pitch 2.0 x Length 45 [Hexagonal socket head bolt]	8 pcs. (For securing the installation base)
2	2	Washer for M16 bolt [Plate thickness 3 mm, Outside diameter φ26, Inside diameter φ16]	8 pcs.
3	3	M10 × Pitch 1.5 × Length 30	6 pcs. (Bolts used to secure the SCARA main body from the bottom surface.)
4	1	M10 × Pitch 1.5 × Length 40	6 pcs. (Bolts used to secure the SCARA main body from the top surface.)

Note. Only either 3 or 4 is used.



Orbit type

Arm length 500mm
Maximum payload 5kg

■ Ordering method

YK500TW-130

Tool flange - Hollow shaft No entry: None
F: With tool flange
S: With hollow shaft

RCX340-4

Cable

Safety Option A Option B Option C Option D Option E Absorbandard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifi	cations							
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		250 mm	250 mm	130 mm	-		
specifications	Rotation angl	le	+/-225 °	+/-225 °	-	+/-720 °		
AC servo mot	or output		750 W	400 W	200 W	105 W		
Deceleration	Transmission	Motor to speed reducer	Timing belt	Direct-coupled	Timing belt	Timing belt		
mechanism	method	Speed reducer to output		Direct-coupled		i iiiiiig beit		
Repeatability	Note 1		+/-0.0	15 mm	+/-0.01 mm	+/-0.01 °		
Maximum spe	ed		6.8 r	n/sec	1.5 m/sec	3000 °/sec		
Maximum pay	load Note 2		5 kg					
Standard cycl	e time: with 1k	g payload ^{Note 3}	0.29 sec					
R-axis tolerab	le moment of	Rated	0.005 kgm²					
inertia Note 4		Maximum						
User wiring			0.15 sq × 8 wires					
User tubing (C	Outer diameter	r)	φ6×2					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m					
Weight			27 kg					

Note 1. This is the value at a constant ambient temperature

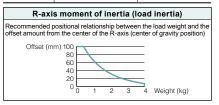
Note 2. For the option specifications (tool flange mount type), the maximum payload becomes 4 kg.

Note 3. For the option specifications (tool flange mount type), the maximum payload becomes 4 kg.

Note 3. When moving a 1 kg load back and forth 300 mm horizontally and 25 mm vertically (rough positioning arch motion).

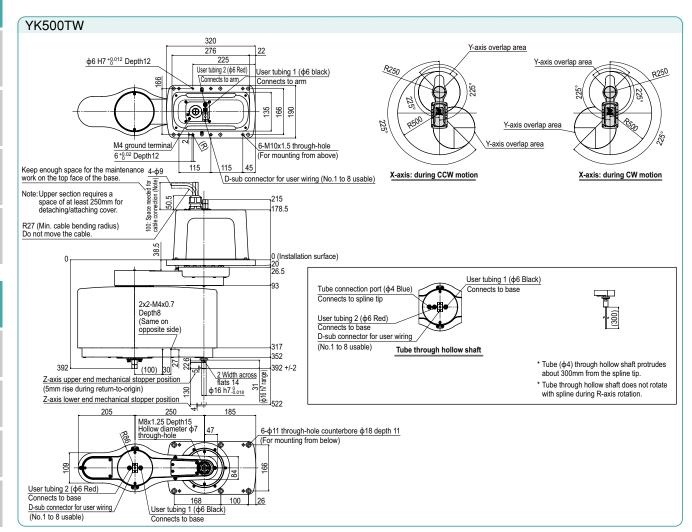
Note 4. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

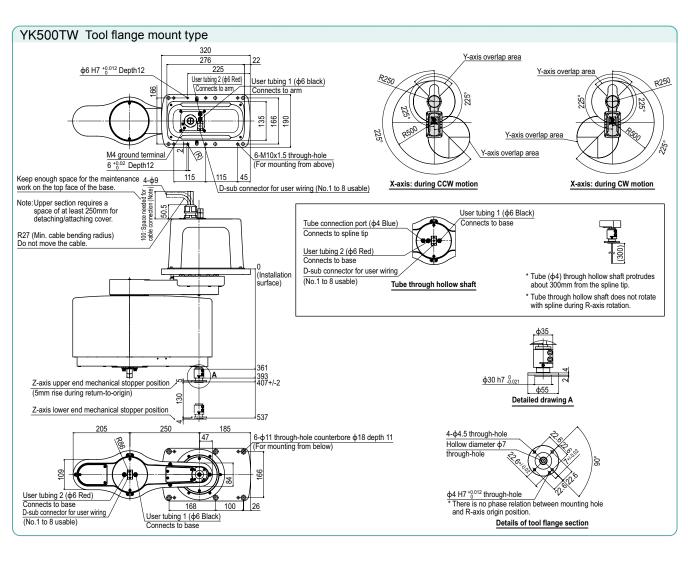
■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 2500 Operation using RS-232C communication



Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

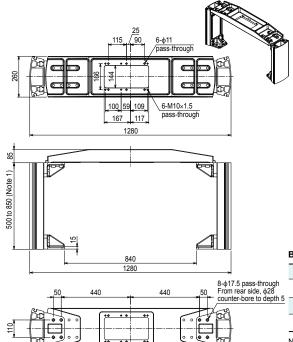




■ Dedicated mounting bracket for the YK-TW <BASE POST ASSY.>

The YK-TW can be easily installed on top of a customer-provided stand.

External diagram for the YK500TW



The mounting bracket is assembled by the customer. Refer to the included assembly diagram for assembly.

Note 1. Identical to the height of the robot mounting surface.

The height of the stand can be selected at a 50 mm pitch.

Height (mm)	Model	Unit weight (kg)
500	KDU-M6100-P0	46
550	KDU-M6100-50	48
600	KDU-M6100-R0	50
650	KDU-M6100-60	51
700	KDU-M6100-S0	54
750	KDU-M6100-70	55
800	KDU-M6100-T0	57
850	KDU-M6100-80	59
850	KDU-M6100-80	59

Bolts supplied with the controller

1	M16 x Pitch 2.0 x Length 45 [Hexagonal socket head bolt]	8 pcs. (For securing the installation base)
2	Washer for M16 bolt [Plate thickness 3 mm, Outside diameter φ26, Inside diameter φ16]	8 pcs.
3	M10 × Pitch 1.5 × Length 30	6 pcs. (Bolts used to secure the SCARA main body from the bottom surface.)
4	M10 × Pitch 1.5 × Length 40	6 pcs. (Bolts used to secure the SCARA main body from the top surface.)

Note. Only either 3 or 4 is used.

YK120XG

Standard type: Extra small type

Arm length 120mm
Maximum payload 1kg

Cable

■ Ordering method

YK120XG - 50

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

■ Specifications								
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		45 mm	75 mm	50 mm	-		
specifications	Rotation angl	le	+/-125 °	+/-145 °	-	+/-360 °		
AC servo mot	or output		30 W	30 W	30 W	30 W		
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled			
mechanism	method	Speed reducer to output		Direct-o	coupled			
Repeatability	Note 1		+/-0.0)1 mm	+/-0.01 mm	+/-0.004 °		
Maximum spe	ed		3.3 n	1700 °/sec				
Maximum pay	load		1.0 kg					
Standard cycl	e time: with 0.1	lkg payload Note 2	0.33 sec					
R-axis tolerab	le moment of	inertia ^{Note 3}	0.01 kgm ²					
User wiring			0.1 sq × 8 wires					
User tubing (C	Outer diameter	r)	ф 4 × 2					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable le	ength		Standard: 2 m Option: 3.5 m, 5 m, 10 m					
Weight (Exclu	ding robot cal	ble) Note 4	3.9 kg					
Robot cable w	reight		0.9 kg (2 m) 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)					

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

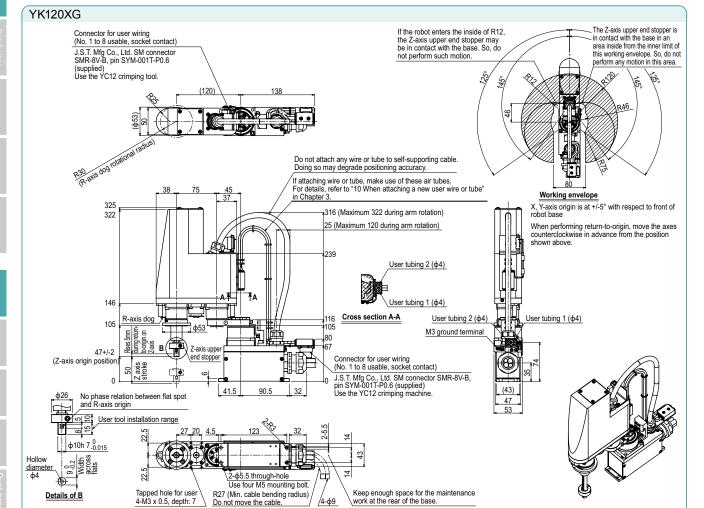
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

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.



YK150XG Standard type: Extra small type

■ Ordering method

YK150XG - 50

Arm length 150mm
Maximum payload 1kg

Cable

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

■ Controller

_			
_	١	•	

■ Specifications X-axis Y-axis Z-axis R-axis Arm length 75 mm 75 mm 50 mm specifications Rotation angle +/-125 +/-145 ° +/-360 ° 30 W 30 W 30 W 30 W AC servo motor output Deceleration Transmission Motor to speed reduce Direct-coupled mechanism method Speed reducer to output Direct-coupled +/-0.01 mm Repeatability +/-0.01 mm +/-0.004° Maximum speed 3.4 m/sec 0.9 m/sec 1700 °/sec Maximum payload 1.0 kg 0.33 sec Standard cycle time: with 0.1kg payload Note 2 R-axis tolerable moment of inertia Note 3 0.01 kgm 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) Robot cable length Standard: 2 m Option: 3.5 m, 5 m, 10 m Weight (Excluding robot cable) Note 4 4.0 kg Robot cable weight $0.9 \text{ kg } (2 \text{ m}) \ 1.5 \text{ kg } (3.5 \text{ m}) \ 2.1 \text{ kg } (5 \text{ m}) \ 4.2 \text{ kg } (10 \text{ m})$

Programming / I/O point trace / Remote command / RCX340 300 Operation using RS-232C communication

Controller | Power capacity (VA) | Operation method

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

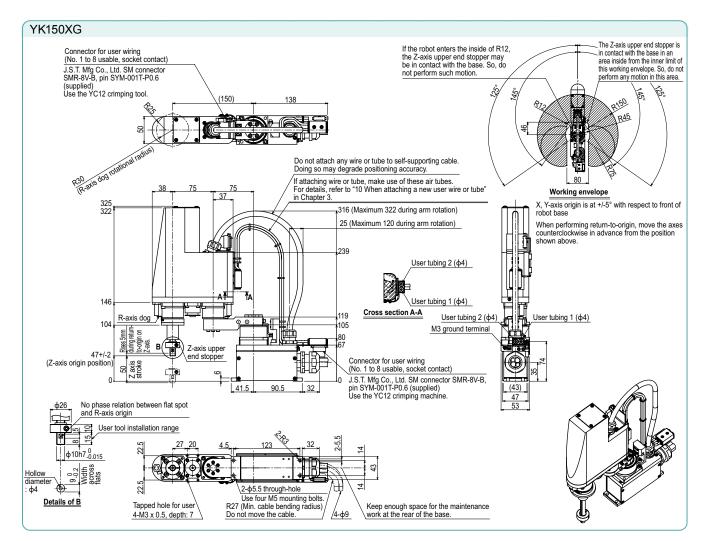
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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.



YK180XG

Standard type: Extra small type

Arm length 180mm
Maximum payload 1kg

■ Ordering method

YK180XG - 50

RCX340-4 Cable

Option B - Option C (OP.B) (OP.C)

Specify various controller setting items. RCX340 ▶ P.678

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		105 mm	75 mm	50 mm	-
specifications	Rotation ang	le	+/-125 °	+/-145 °	-	+/-360 °
AC servo mot	or output		30 W	30 W	30 W	30 W
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled	
mechanism	method	Speed reducer to output		Direct-	coupled	
Repeatability	Note 1		+/-0.0	+/-0.01 mm		+/-0.004 °
Maximum spe	ed		3.3 m/sec		0.9 m/sec	1700 °/sec
Maximum pay	load		1.0 kg			
Standard cycl	e time: with 0.	lkg payload ^{Note 2}	0.33 sec			
R-axis tolerab	le moment of	inertia Note 3	0.01 kgm²			
User wiring			0.1 sq × 8 wires			
User tubing (0	Outer diamete	r)	ф 4 × 2			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 2 m Option: 3.5 m, 5 m, 10 m			
Weight (Excluding robot cable) Note 4			4.1 kg			
Robot cable w	/eight		0.9 kg (2 m) 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)			
Maria de Trada de de la						

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 500 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.

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No phase relation between flat spot and R-axis origin User tool installation range

22.5

Tapped hole for user

4-M3 x 0.5, depth: 7

Controller

ф10h 7 0 0.015 9-0.2 Width across flats

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.

YK180XG The Z-axis upper end stopper is in contact with the base in an area inside from the inner limit of this working envelope. So, do not perform any motion in this area. Connector for user wiring (No. 1 to 8 usable, socket contact)
J.S.T. Mfg Co., Ltd. SM connector
SMR-8V-B, pin SYM-001T-P0.6 (supplied)
Use the YC12 crimping tool. (180)Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy. 80 38 105 f attaching wire or tube, make use of these air tubes. Working envelope 37 Y-axis origin is at +/-5° with respect to front of

R30 Raxis dog roti For details, refer to "10 When attaching a new user wire or tube" in Chapter 3.

316 (Maximum 322 during arm rotation) 325 322 10 (Maximum 120 during arm rotation) 239 User tubing 2 (φ4) User tubing 1 (φ4) Cross section A-A 146 User tubing 2 (φ4) 104 105 M3 ground terminal Rises 5mm during retum-to-origin on Z-axis. 47+/-2 end stopper (Z-axis origin position Connector for user wiring 20 (No. 1 to 8 usable, socket contact) 41.5 90.5

J.S.T. Mfg Co., Ltd. SM connector SMR-8V-B, pin SYM-0017-P0.6 (supplied)
Use the YC12 crimping machine.

Keep enough space for the maintenance **/4-ф9**

robot base

User tubing 1 (φ4)

When performing return-to-origin, move the axes counterclockwise in advance from the position

RCX340 ► 678

2-¢5.5 through-hole Use four M5 mounting bolts.

R27 (Min. cable bending radius)

Do not move the cable

Hollow diameter : φ4

-₩

Details of B

Arm length 180mm
Maximum payload 1kg

YK180X

■ Ordering method

YK180X - 100

RCX340-4 Cable

3L: 3.5m Specify various controller setting items. RCX340 ▶ P.678

■ Specifications X-axis Y-axis Z-axis R-axis Arm length 71 mm 109 mm 100 mm specifications Rotation angle +/-120 +/-140 ° +/-360 ° 50 W 30 W 30 W 30 W AC servo motor output Deceleration Transmission Motor to speed reduce Direct-coupled mechanism method Speed reducer to output Direct-coupled Repeatability +/-0.01 mm +/-0.01 mm +/-0.004° Maximum speed 3.3 m/sec 0.7 m/sec 1700 °/sec Maximum payload 1.0 kg 0.39 sec Standard cycle time: with 0.1kg payload Note 2 R-axis tolerable moment of inertia No 0.01 kgm User wiring 0.1 sq × 6 wires User tubing (Outer diameter) ф3×2 Travel limit 1.Soft limit 2.Mechanical stopper (X,Y,Z axis) Robot cable length Standard: 3.5 m Option: 5 m, 10 m Weight (Excluding robot cable) Note 4 5.5 kg Robot cable weight 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)

Controller | Power capacity (VA) | Operation method Programming / I/O point trace / Remote command / RCX340 500 Operation using RS-232C communication

■ Controller

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

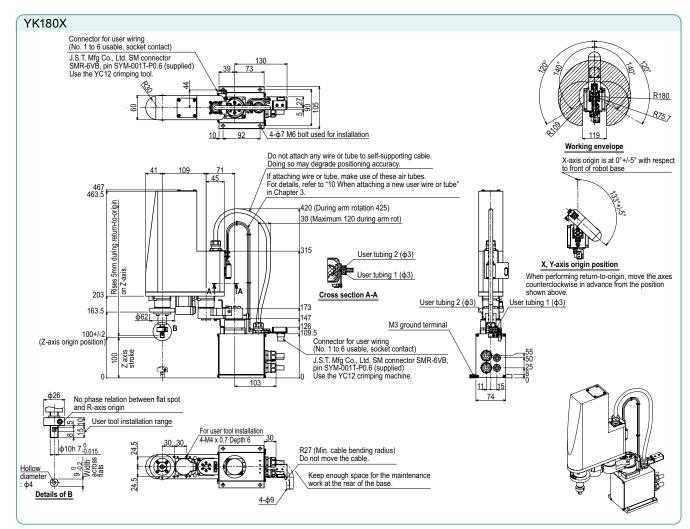
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

Note 1. This is the value at a constant ambient temperature.

Note 2. When reciprocating 100mm in horizontal and 25mm in vertical directions.

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



YK220X

Standard type: Extra small type

Arm length 220mm
Maximum payload 1kg

■ Ordering method

YK220X-100

RCX340-4

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		111 mm	109 mm	100 mm	-	
specifications	Rotation ang	le	+/-120 °	+/-140 °	-	+/-360 °	
AC servo mot	or output		50 W	30 W	30 W	30 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability	Note 1		+/-0.01 mm +/-0.01		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		3.4 m/sec 0.7 m/sec 1700 °			1700 °/sec	
Maximum pay	load		1.0 kg				
Standard cycl	e time: with 0.1	lkg payload Note 2	0.42 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}		0.01	kgm²		
User wiring			0.1 sq × 6 wires				
User tubing (C	Outer diameter	r)	ф 3 × 2				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length		Standard: 3.5 m Option: 5 m, 10 m					
Weight (Exclu	ding robot cal	ble) Note 4	5.5 kg				
Robot cable w	eight		1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)			0 m)	

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 500 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.

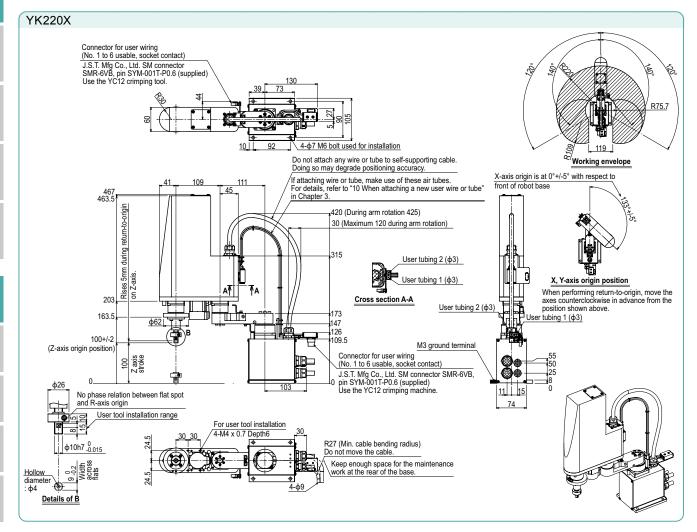
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

Note 1. This is the value at a constant ambient temperature.

Note 2. When reciprocating 100mm in horizontal and 25mm in vertical directions.

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



Controller

YK250XG

Arm length 250mm
Maximum payload 5kg

■ Ordering method

YK250XG - 150

Tool flange - Hollow shaft No entry: None
F: With tool flange

No entry: None
S: With hollow shaft

Cable

RCX340-4

Standard type: Small type

Specify various controller setting items. RCX340 ▶ P.678

■ Controller

RCX340

Controller Power capacity (VA) Operation method

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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

Our robot manuals (installation manuals) can be downloaded from our website at the address below

https://global.yamaha-motor.com/business/robot/

1000

Programming / I/O point trace / Remote command /

Operation using RS-232C communication

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

Weight

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

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

Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg

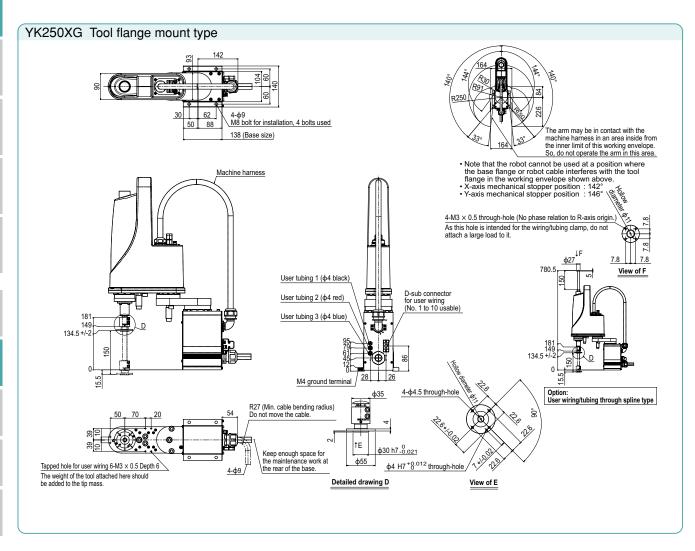
Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		100 mm	150 mm	150 mm	-
specifications	Rotation ang	le	+/-140 °	+/-144 °	-	+/-360 °
AC servo mot	or output		200 W	150 W	50 W	100 W
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled	
	method	Speed reducer to output	Direct-coupled			
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum spe			4.5 n	n/sec	1.1 m/sec	1020 °/sec
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)			
Standard cycl	e time: with 2k	g payload Note 2	0.43 sec			
R-axis tolerat	le moment of	inertia ^{Note 3}	0.05 kgm² (0.5 kgfcms²)			
User wiring			0.2 sq × 10 wires			
User tubing (Outer diameter)			φ 4 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m			

YK250XG 142 8 8 me? lg User tubing 1 (\$\phi4\$ black) 62 30 4-φ9 M8 bolt for installation, 4 bolts used User tubing 2 (\$\phi4\$ red) 50 88 User tubing 3 (\$\phi4\$ blue) 138 (Base size) The arm may be in contact with the machine harness in an area inside from the inner limit of this working envelope. D-sub connector for user wiring (No. 1 to 10 usable) Cross section B-B 129 Maximum 280 during arm rotation So, do not operate the arm in this area. Note that the robot cannot be used at a position where the base flange or robot cable interferes with the spline in the working envelope shown above.

X-axis mechanical stopper position: 142°

Y-axis mechanical stopper position: 146° 100 Machine 661 Maximum 660 during arm rotation 614 $4\text{-M3} \times 0.5$ through-hole (No phase relation to R-axis origin.) As this hole is intended for the wiring/tubing clamp, do not 468 attach a large load to it. 428 7.8 ф27 7.8 7.8 780.5 57 View of F User tubing 1 (φ4 black) D-sub connector for user wiring (No. 1 to 10 usable) User tubing 2 (ф4 red) User tubing 3 (\$4 blue) 183 AV. 138 5+/-2 ф16 h7-0.018 ф35 User tool installation 120 138.5 +/-2 range 20 Z-axis lower end M4 ground terminal mechanical stopper position Z-axis upper end mechanical stopper position 4mm rise during Z-axis return-to-origin Option: User wiring/tubing through spline type across flat 15 70 R27 (Min. cable bending radius) Width Do not move the cable Keep enough space for the maintenance work at the rear of the base. Cross section A-A Tapped hole for user wiring 6-M3 × 0.5 Depth 6 **4-φ9**/ The weight of the tool attack added to the tip mass.

18.5 kg



YK350XG - 150

RCX340-4

YK350XG

Cable

Controller | Power capacity (VA) | Operation method

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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

Our robot manuals (installation manuals) can be

downloaded from our website at the address below

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1000

Programming /

I/O point trace /

Remote command /

Operation using RS-232C

communication

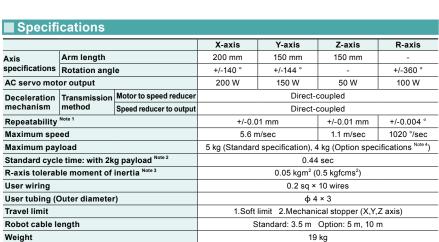
Tool flange - Hollow shaft No entry: None
F: With tool flange

No entry: None
S: With hollow shaft

Specify various controller setting items. RCX340 ▶ **P.678**

■ Controller

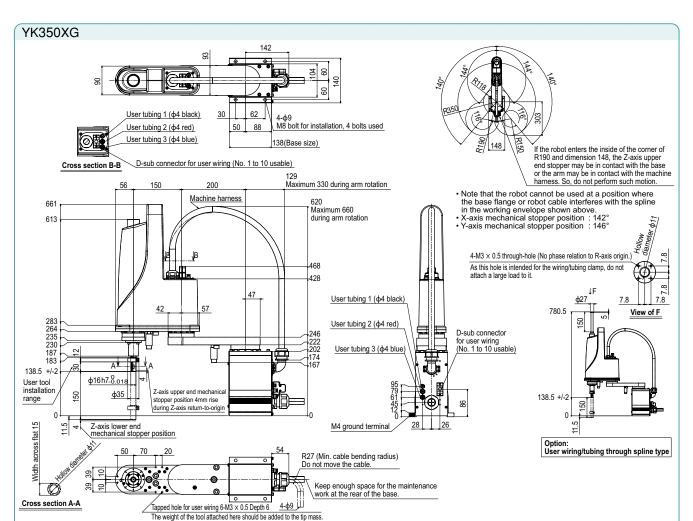
RCX340



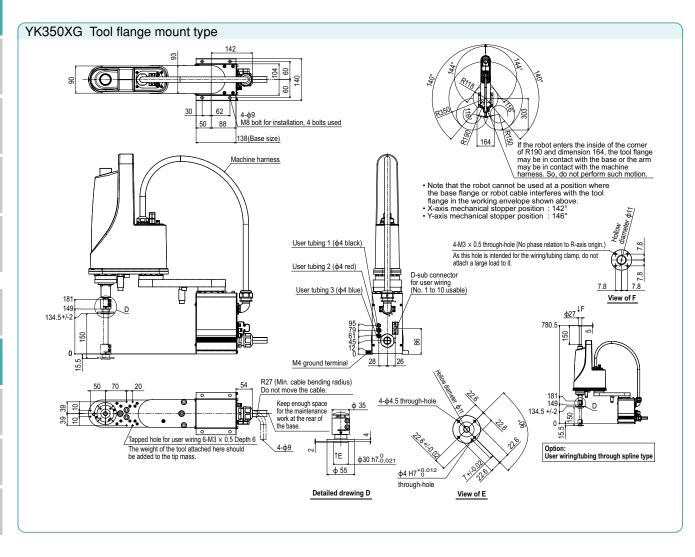
Note 1. This is the value at a constant ambient temperature. (X,Y axes)

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.



Dust-proof
t/ & drip-proof



Standard type: Small type

OLOW COST HIGH PERFORMANCE MODEL

Arm length 400mm
Maximum payload 4kg

■ Ordering method

YK400XE- 4

150

No entry: None S: With hollow shaft

No entry: None BS: With brake release switch

RCX340-4

RCX340 ▶ P.678

Specify various controller setting items.

Specii	ications					1
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		225 mm	175 mm	150 mm	-
specifications	Rotation ang	le	+/-132 °	+/-150 °	-	+/-360 °
AC servo mot	or output		200 W	100 W	100 W	100 W
Deceleration	Transmission	Motor to speed reducer	Direct-coupled		Timing belt	
mechanism	method	Speed reducer to output	Direct-coupled		Timing belt	
Repeatability	Repeatability Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.01 °
Maximum spe	ed		6 m/sec		1.1 m/sec	2600 °/sec
Maximum pay	load		4 kg (Standard specification, Option specifications Note 4), 3 kg (Option specifications Note 5)			
Standard cycl	e time: with 2k	g payload Note 2	0.41 sec			
R-axis tolerat	ole moment of	inertia ^{Note 3}	0.05 kgm ²			
User wiring			0.2 sq × 10 wires			
User tubing (Outer diameter)			ф 4 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m			

Weight

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

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions and performing the coarse positioning arch operation.

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

Note 4. Maximum payload of the standard or option specifications (brake release switch type) is 4 kg.

Note 5. Maximum payload of the option specifications (user wiring/tubing through shaft type) is 3 kg

■ Controller						
Controller	Power capacity (VA)	Operation method				
RCX340	1000	Programming / I/O point trace / Remote command / Operation using RS-232C communication				

Note. The movement range can be restricted by adding the X- and Y-axis mechanical stoppers. (The maximum movement range was set at shipment.)

See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a standard coordinate with high accuracy.

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

VK400XE-4
YK400XE-4 4-M3 x 0.5 through-hole (No phase relation to R-axis origin.) As this hole is intended for the wiring/tubing clamp, do not attach a large load to it. 48 175 225 Maximum 350 during arm rotation View of B Working envelope 48 175 225 Maximum 350 during arm rotation Numbers 1 to 10 are usable.) Nota: User wiring connector (Numbers 1 to 10 are usable.) Nota:
Option User wiring/tubing through shaft type See 1 Compared to the state of the s
10mm rise during 174.3 return-to-origin return-to-origin 124.77+/2 (Z-axis origin position) Z-axis lower end mechanical stopper position Z-axis lower end mechanical stopper position Standard type Standard type User tubing 1 (44 black) 134
Tapped hole for user wiring: 6-M4 × 0.7 Depth 8 The weight of the tool attached here should be added to the tip mass. XY-axis origin position When performing return-to-origin, move the X-axis and Y-axis counterclockwise and clockwise, respectively in advance from the position shown above. Keep enough space for the maintenance work at the rear of the base. Note 1: J.S.T. Mfg. Co.,Ltd. SM connector: SMR-11V-B Pin: SYM-001T-P0.6 is attached. Use AP-K2N for the crimping machine.

17 kg

YK400XG

Standard type: Small type

Arm length 400mm
Maximum payload 5kg

■ Ordering method

YK400XG - 150

Tool flange - Hollow shaft No entry: None
F: With tool flange
S: With hollow shaft RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		250 mm	150 mm	150 mm	-
specifications	Rotation angl	le	+/-140 °	+/-144 °	-	+/-360 °
AC servo mot	or output		200 W	150 W	50 W	100 W
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled	
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		6.1 m/sec		1.1 m/sec	1020 °/sec
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)			
Standard cycl	e time: with 2k	g payload Note 2	0.45 sec			
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm² (0.5 kgfcms²)			
User wiring			0.2 sq × 10 wires			
User tubing (C	Outer diameter	r)	φ 4 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			19.5 kg			

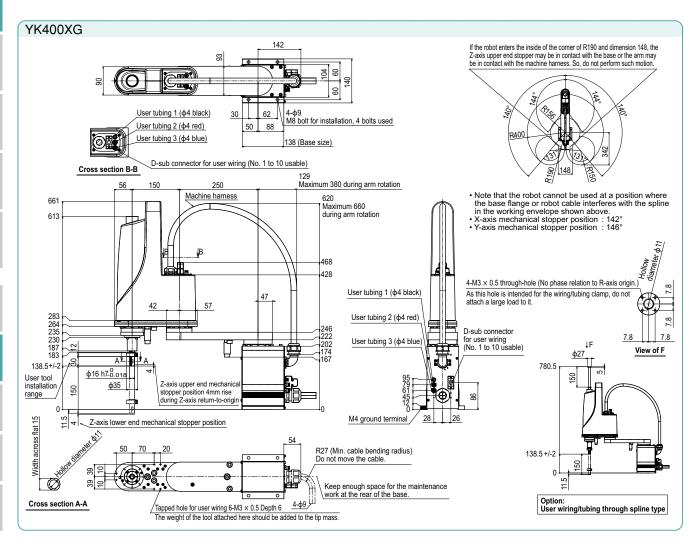
Note 1. This is the value at a constant ambient temperature. (X,Y axes) Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings. Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg ■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

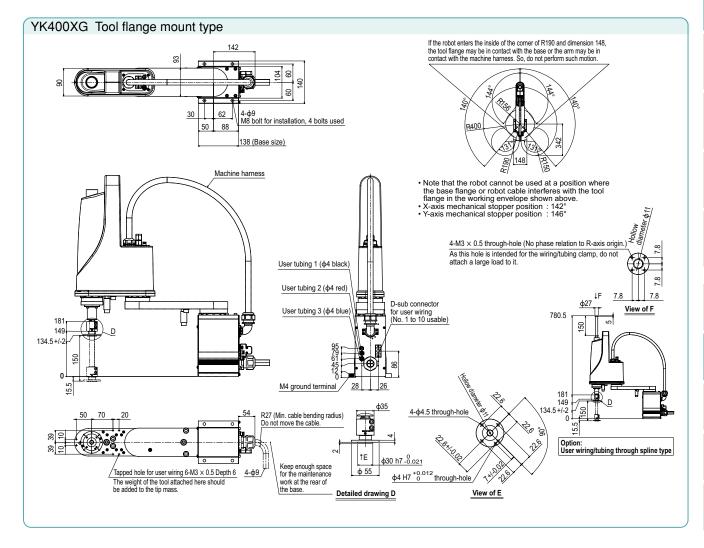
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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Controller



YK500XGI

Standard type: Medium type

Arm length 500mm
Maximum payload 5kg

■ Ordering method

YK500XGL-150

Tool flange - Hollow shaft - Cable No entry: None
F: With tool flange
S: With hollow shaft

RCX340-4

■ Controller

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	s Arm length		250 mm	250 mm	150 mm	-
specifications	Rotation angl	е	+/-140 °	+/-144 °	-	+/-360 °
AC servo mot	or output		200 W	150 W	50 W	100 W
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled	
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		5.1 m/sec		1.1 m/sec	1020 °/sec
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)			
Standard cycl	e time: with 2k	g payload ^{Note 2}	0.48 sec			
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm² (0.5 kgfcms²)			
User wiring			0.2 sq × 10 wires			
User tubing (C	Outer diameter	.)	ф 4 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			21 kg			

Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 1000 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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

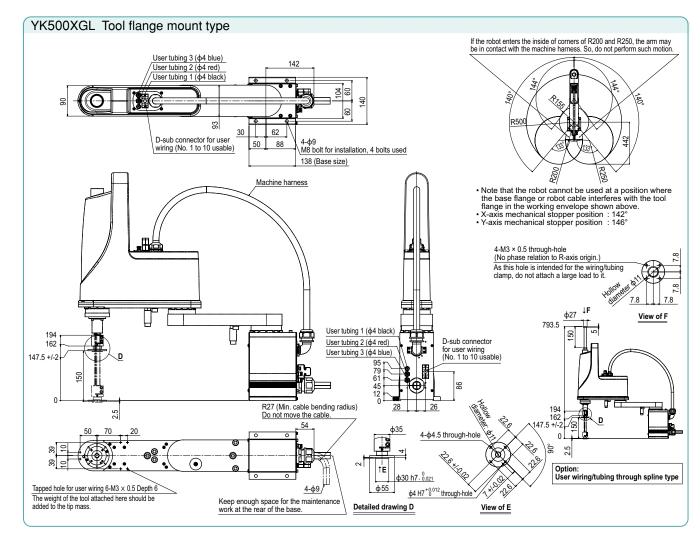
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.

YK500XGL If the robot enters the inside of the corner of R200 and R250, the arm may be in contact with the machine harness. So, do not perform such motion. User tubing 3 (φ4 blue) User tubing 2 (\$\phi4\$ red) User tubing 1 (φ4 black) 9 6 140 09 93 62 D-sub connector for user 50 88 wiring (No. 1 to 10 usable) M8 bolt for installation, 4 bolts used 138 (Base size) 129 Ma<u>ximum 315 during arm rotation</u> 250 674 Machine harness Note that the robot cannot be used at a position where the base flange or robot cable interferes with the spline in the working envelope shown above.

Y-axis mechanical stopper position : 142°

Y-axis mechanical stopper position : 146° 627 Maximum 673 during arm rotation 481 4-M3 × 0.5 through-hole 441 (No phase relation to R-axis origin.) As this hole is intended for the wiring/tubing clamp, do not attach a large load to it. 42 57 296 277 47 274 248 243 View of F ф27 793.5 200 196 User tubing 1 (\$\phi4\$ black A^V A 150 D-sub connector User tubing 2 (\$\phi4\$ red) 151.5 +/-2 for user wiring (No. 1 to 10 usable) User tubing 3 (\$4 blue) φ16 h7-0.018 Z-axis upper end mechanical User tool during Z-axis return-to-origin installation 150 range 0 flats: Z-axis lower end mechanical stopper position 151.5 +/-2 54 R27 (Min. cable bending radius) 20 70 Do not move the cable. Option: User wiring/tubing through spline type Keep enough space for the maintenance Cross section A-A vork at the rear of the base Tapped hole for user wiring 6-M3 × 0.5 Depth 6 4-ф9 The weight of the tool attached here should be added to the tip mass





Standard type: Medium type

Arm length 500mm
Maximum payload 10kg

Ordering method

YK500XG	-[
Model	_	7 axi

Cable 3L: 3.5m

RCX340-4

Tool flange

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		200 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation ang	le	+/-130 °	+/-145 °	-	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output		Direct-	coupled		
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		7.6 m/sec 2.3 m/sec 1.7 m/sec 1700 °.			1700 °/sec	
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload Note 2	0.42 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (C	User tubing (Outer diameter)			ф 6 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			30 kg				

■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 1700 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.

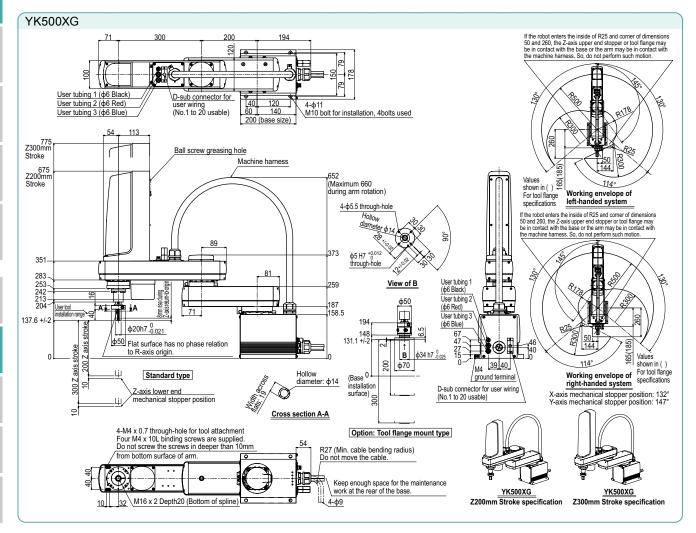
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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 reciprocating 300mm in horizontal and 25mm in vertical directions

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



Standard type: Medium type

LOW COST HIGH PERFORMANCE MODEL

Arm length 510mm Maximum payload 10kg

Ordering method

YK510XE 10 200

lo entry: None F: With tool flange

No entry: None S: With hollow s C: With hollow of

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

Note. The return-to-origin method is provided only in the sensor specifications, but not in the stroke end specifications.

■ Specifi	ications					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		235 mm	275 mm	200 mm	-
specifications	Rotation ang	le	+/-134 °	+/-152 °	-	+/-360 °
AC servo mot	or output		400 W	200 W	200 W	200 W
Deceleration	Transmission	Motor to speed reducer	Direct-	coupled	Timin	g belt
mechanism	method	Speed reducer to output	Direct-coupled		Timing belt	
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.01 °
Maximum spe	ed		7.8 m/sec		2 m/sec	2600 °/sec
Maximum pay	load		10 kg (Standard specification, Option specifications Note 4), 9 kg (Option specifications Note 5)			
Standard cycl	e time: with 2k	g payload Note 2	0.38 sec			
R-axis tolerat	le moment of	inertia Note 3	0.3 kgm ²			
User wiring			0.2 sq × 20 wires			
User tubing (0	Outer diameter	r)	φ6×3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			25 kg			

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

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions and performing the coarse positioning arch operation.

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

Note 4. Maximum payload of the standard or option specifications (brake release switch type, user wiring/tubing through cap type) is 10 kg

Note 5. Maximum payload of the option specifications (tool flange mount type, user wiring/tubing through shaft type) is 9 kg.

Cont	ntroller				
Controller	Power capacity (VA)	Operation method			
RCX340	1700	Programming / I/O point trace / Remote command / Operation using RS-232C communication			

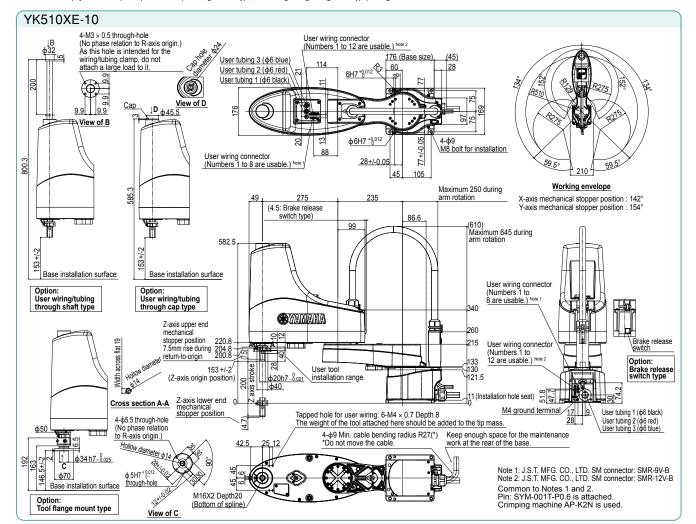
Note. The movement range can be restricted by adding the X- and Y-axis mechanical stoppers. (The maximum movement range was set at shipment.)

See our robot manuals (installation manuals) for detailed

information. Note. To set the standard coordinates with high accuracy, use a

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



YK600XGL

Standard type: Medium type

Arm length 600mm
Maximum payload 5kg

■ Ordering method

YK600XGL-150

Tool flange - Hollow shaft - Cable No entry: None
F: With tool flange
S: With hollow shaft

RCX340-4

■ Controller

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		350 mm	250 mm	150 mm	-
specifications	Rotation angl	le	+/-140 °	+/-144 °	-	+/-360 °
AC servo mot	or output		200 W	150 W	50 W	100 W
Decementation municipality		Motor to speed reducer		Direct-	coupled	
		Speed reducer to output	Direct-coupled			
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		4.9 m/sec		1.1 m/sec	1020 °/sec
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)			
Standard cycl	e time: with 2k	g payload ^{Note 2}	0.54 sec			
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm² (0.5 kgfcms²)			
User wiring			0.2 sq × 10 wires			
User tubing (Outer diameter)			φ 4 × 3			
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight				22	kg	

Programming / I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

Controller Power capacity (VA) Operation method

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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

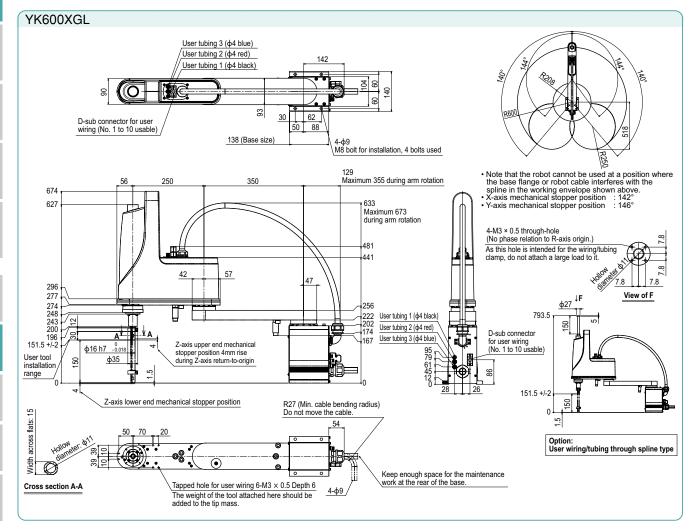
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

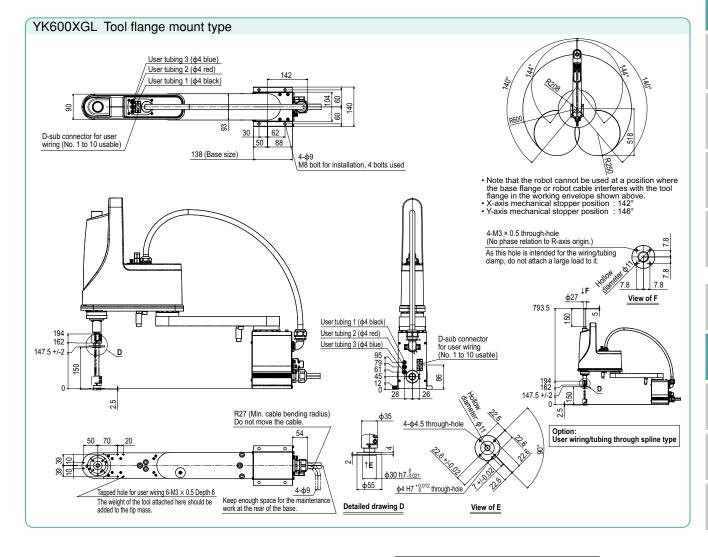
This is the value at a constant ambient temperature. (X,Y axes

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

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

Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.







Standard type: Medium type

Arm length 600mm
Maximum payload 10kg

■ Ordering method

YK600XG

Z axis stroke - Tool flange 200: 200mm No entry: None S: With tool flange

RCX340-4 Cable 3L: 3.5m

Option B – (OP.B)

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		300 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-145 °	-	+/-360 °	
AC servo moto	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output		Direct-	coupled		
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		8.4 m/sec 2.3 m/sec 1.7		2.3 m/sec 1.7 m/sec	1700 °/sec	
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload Note 2	0.43 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (Outer diameter)			φ6×3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			31 kg				

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1700 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.

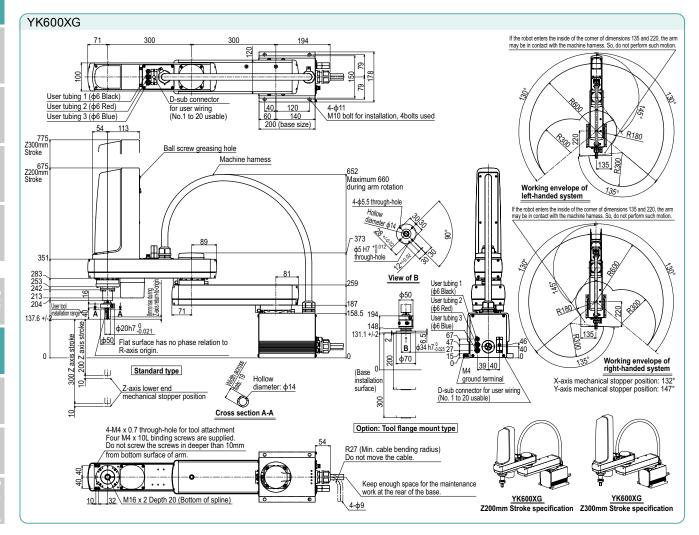
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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 reciprocating 300mm in horizontal and 25mm in vertical directions

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



YK610XE-10 Standard type: Medium type LOW COST HIGH PERFORMANCE MOD ■ LOW COST HIGH PERFORMANCE MODEL

Arm length 610mm Maximum payload 10kg

Ordering method

YK610XE - 10 -200

o entry: None F: With tool flange

No entry: None

RCX340 ▶ P.678

RCX340-4

Specify various controller setting items.

Note. The return-to-origin method is provided only in the sensor specifications, but not in the stroke end specifications.

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		335 mm	275 mm	200 mm	-
specifications	Rotation ang	le	+/-134 °	+/-152 °	-	+/-360 °
AC servo mot	or output		400 W	200 W	200 W	200 W
Deceleration	Transmission	Motor to speed reducer	Direct-	coupled	Timin	g belt
mechanism	method	Speed reducer to output		Direct-coupled		Timing belt
Repeatability Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.01 °	
Maximum spe	ed		8.6 m/sec		2 m/sec	2600 °/sec
Maximum pay	load		10 kg (Standard specification, Option specifications Note 4), 9 kg (Option specifications Note 5)			
Standard cycl	e time: with 2k	g payload Note 2	0.39 sec			
R-axis tolerab	le moment of	inertia Note 3	0.3 kgm ²			
User wiring			0.2 sq × 20 wires			
User tubing (C	Outer diameter	r)	ф 6 × 3			
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m			
Weight			25 kg			

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

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions and performing the coarse positioning arch operation.

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

Note 4. Maximum payload of the standard or option specifications (brake release switch type, user wiring/tubing through cap type) is 10 kg.

Note 5. Maximum payload of the option specifications (tool flange mount type, user wiring/tubing through shaft type) is 9 kg.

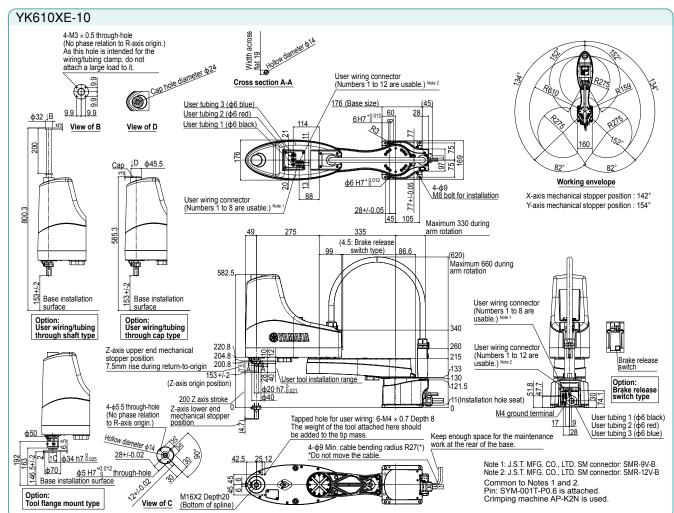
■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 1700 Operation using RS-232C communication

Note. The movement range can be restricted by adding the X- and Y-axis mechanical stoppers. (The maximum movement range was set at shipment.)

See our robot manuals (installation manuals) for detailed

information. Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



YK600XG

Standard type: Medium type

Arm length 600mm
Maximum payload 20kg

Ordering method

YK600XGH

Tool flange No entry: None F: With tool flange

Cable 3L: 3.5m

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		200 mm	400 mm	200 mm 400 mm	-
specifications	Rotation angl	е	+/-130 °	+/-150 °	_	+/-360 °
AC servo moto	or output		750 W	400 W	400 W	200 W
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled	
mechanism	method	Speed reducer to output		Direct-	coupled	_
Repeatability	Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		7.7 m/sec 2.3 m/sec 1.7 m/sec 920 °		920 °/sec	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)			
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.47 sec			
R-axis tolerab	le moment of	inertia ^{Note 3}		1.0	kgm²	
User wiring			0.2 sq × 20 wires			
User tubing (C	Outer diameter	.)	φ6×3			
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			Z axis	200 mm: 48 kg	Z axis 400 mm:	50 kg

Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 2500 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.

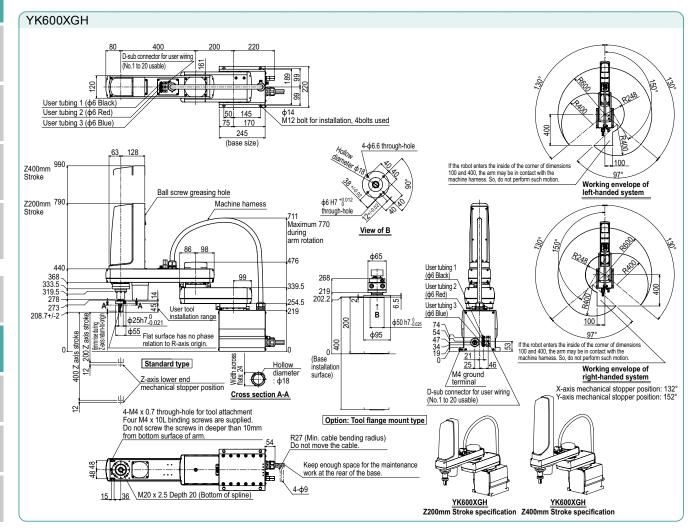
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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 reciprocating 300mm in horizontal and 25mm in vertical directions.

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings. Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.



Controller

YK700XG

Arm length 700mm Maximum payload 10kg

5L: 5m 10L: 10m

Note. This model is a special order product. Please consult us for delivery time.

Standard type: Large type

Ordering method

YK700XGL Tool flange No entry: None F: With tool flange

RCX340-4 Cable

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		400 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-145 °	-	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.005 °	
Maximum spe	ed		9.2 m/sec 2.3 m/sec 1.7 m/sec 170		1700 °/sec		
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload ^{Note 2}		0.50) sec		
R-axis tolerab	le moment of	inertia ^{Note 3}		0.30	kgm²		
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter	.)	ф6 × 3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length			Standard: 3.5 m Option: 5, 10 m				
Weight			32 kg				

Note 1. This is the value at a constant ambient temperature. (X,Y axes) Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions

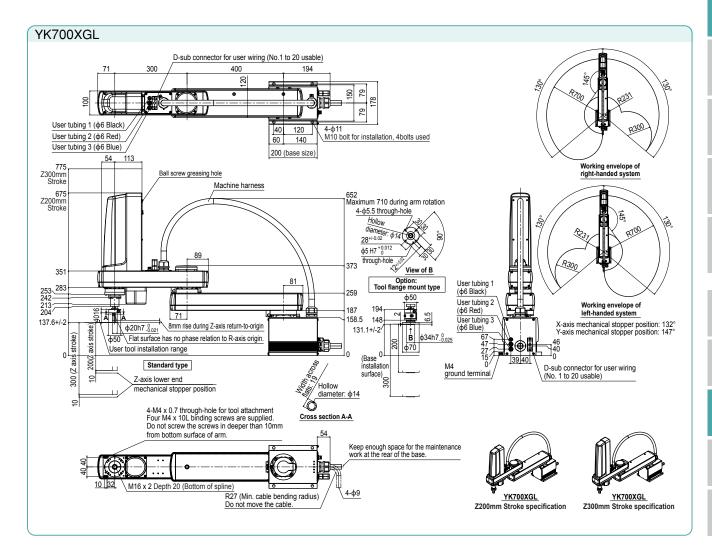
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings

■ Controller					
Controller	Power capacity (VA)	Operation method			
RCX340	1700	Programming / I/O point trace / Remote command / 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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



Standard type: Large type LOW COST HIGH PERFORMANCE MODEL

Arm length 710mm
Maximum payload 10kg

Ordering method

YK710XE- 10 -200

No entry: None F: With tool flange

No entry: None

No entry: None BS: With brake release switch

RCX340-4

RCX340 ▶ P.678

Option A to E (OP.A to E)

Specify various controller setting items.

Note. The return-to-origin method is provided only in the sensor specifications, but not in the stroke end specifications.

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		435 mm	275 mm	200 mm	-	
specifications	Rotation angl	е	+/-134 °	+/-152 °	-	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer	Direct-o	coupled	Timin	g belt	
mechanism	method	Speed reducer to output		Direct-coupled		Timing belt	
Repeatability Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.01 °		
Maximum spe	ed		9.5 m/sec		2 m/sec	2600 °/sec	
Maximum pay	load		10 kg (Standard specification, Option specifications Note 4), 9 kg (Option specifications Note 5)				
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.42 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.3 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (Outer diameter)		.)	ф 6 × 3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight				26	kg		

■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 1700 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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

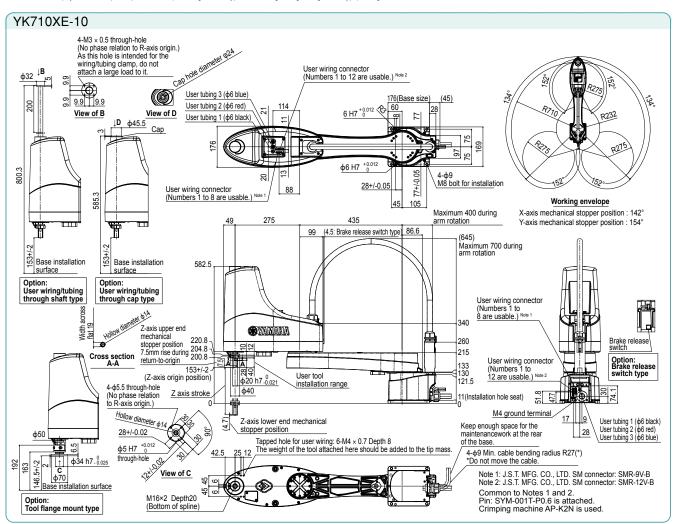
- Note 1. This is the value at a constant ambient temperature. (X,Y axes)

 Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions and performing the coarse positioning arch operation.

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

 Note 4. Maximum payload of the standard or option specifications (brake release switch type, user wiring/tubing through cap type) is 10 kg.

 Note 5. Maximum payload of the option specifications (tool flange mount type, user wiring/tubing through shaft type) is 9 kg.



YK700XG Arm length 700mm Maximum payload 20kg

Ordering method

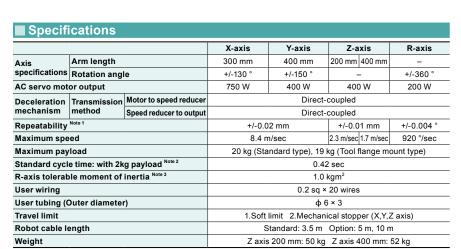
YK700XG

Tool flange Cable 200: 200mm No entry: None 400: 400mm F: With tool flange 3L: 3.5m

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

RCX340 ► 678



Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

■ Controller						
Controller	Power capacity (VA)	Operation method				
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication				

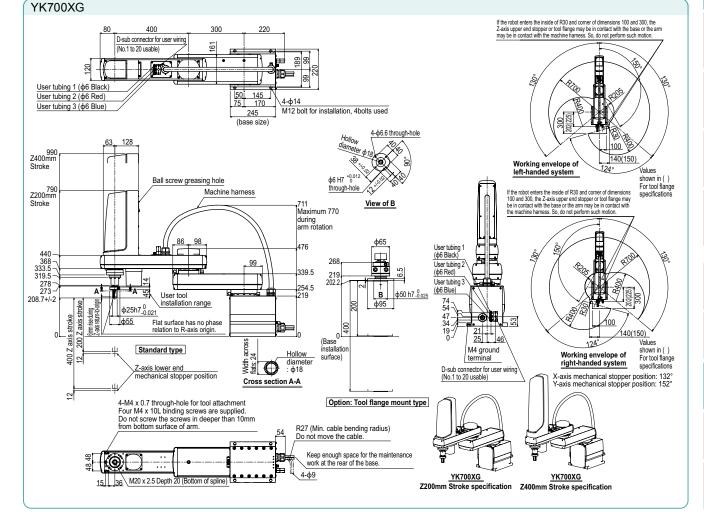
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



YK800XG

Standard type: Large type

Arm length 800mm
Maximum payload 20kg

■ Ordering method

YK800XG

Tool flange Cable 3L: 3.5m

RCX340-4

Option A — Option B — (OP.A) (OP.B)

No entry: None F: With tool flange

Specify various controller setting items. RCX340 ▶ P.678

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length		400 mm	400 mm	200 mm 400 mm	-		
specifications	Rotation angl	е	+/-130 °	+/-150 °	-	+/-360 °	
AC servo mot	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output		Direct-	coupled		
Repeatability	Note 1		+/-0.0	+/-0.02 mm		+/-0.004 °	
Maximum spe	ed		9.2 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.48 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter	.)	φ6×3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis	200 mm: 52 kg	Z axis 400 mm:	54 kg	
Maria de Trata de Maria	.11						

Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 2500 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.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

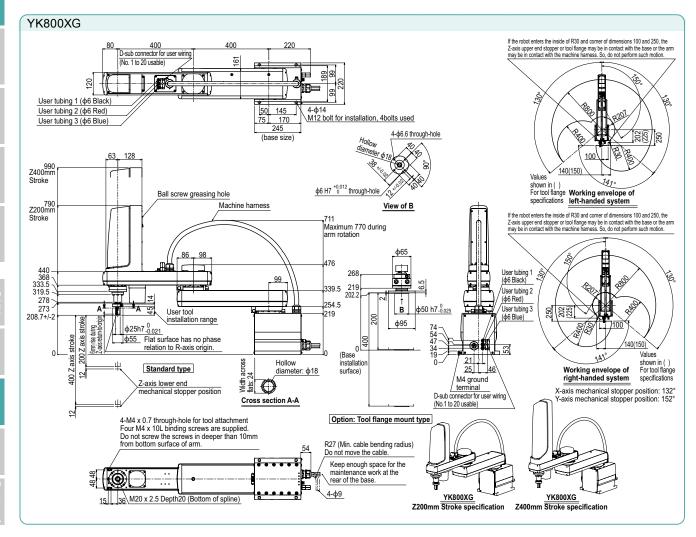
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.

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

Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.



Controller

YK900XG

Arm length 900mm
Maximum payload 20kg

Ordering method

YK900XG

Tool flange Cable 200: 200mm No entry: None 400: 400mm F: With tool flange 3L: 3.5m

RCX340-4

Option A — Option B — Option C — (OP.A) (OP.B) (OP.C) Specify various controller setting items. RCX340 ▶ P.678

- Contr	ollow	
■ Contr	oller	

			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		500 mm	400 mm	200 mm 400 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-150 °	_	+/-360 °	
AC servo moto	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output		Direct-	coupled		
Repeatability	Note 1		+/-0.02 mm +/-0.		+/-0.01 mm	+/-0.004 °	
Maximum speed			9.9 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.49 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight		Z axis 200 mm: 54 kg Z axis 400 mm: 56 kg					

Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.

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

Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

■ Controller				
Controller	Power capacity (VA)	Operation method		
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication		

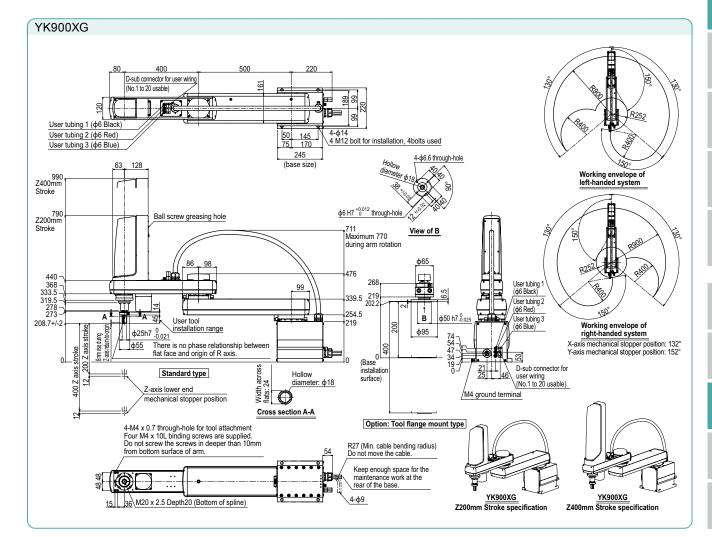
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a

standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



YK1000XG

Standard type: Large type

Arm length 1000mm
Maximum payload 20kg

■ Ordering method

YK1000XG

200: 200mm No entry: None 400: 400mm F: With tool flange

Tool flange Cable 3L: 3.5m

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		600 mm	400 mm	200 mm 400 mm	-
specifications Rotation ang		е	+/-130 °	+/-150 °	-	+/-360 °
AC servo motor output		750 W	400 W	400 W	200 W	
	Transmission	Motor to speed reducer	Direct-coupled			
	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed		10.6 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec	
Maximum payload		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle time: with 2kg payload Note 2		0.49 sec				
R-axis tolerab	le moment of	nt of inertia Note 3 1.0 kgm ²				
User wiring		0.2 sq × 20 wires				
User tubing (Outer diameter)		ф 6 × 3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length		Standard: 3.5 m Option: 5 m, 10 m				
Weight		Z axis 200 mm: 56 kg Z axis 400 mm: 58 kg				

Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 2500 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.

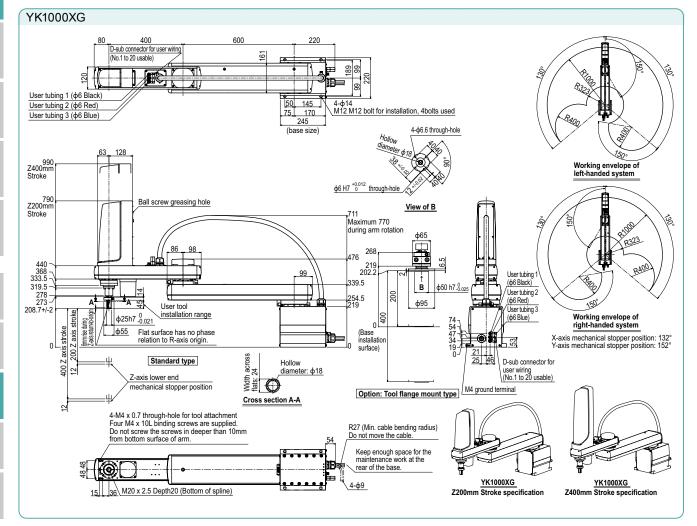
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 300mm in horizontal and 25mm in vertical directions.

Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings. Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.



YK1200X

Arm length 1200mm Maximum payload 50kg

■ Ordering method

YK1200X - 400 - Z axis stroke

RCX340-4 Cable 3L: 3.5m

Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		600 mm	600 mm	400 mm	-
specifications	Rotation angle		+/-125 °	+/-150 °	-	+/-180 °
AC servo motor output		900 W	800 W	600 W	400 W	
	Transmission	Motor to speed reducer	Direct-coupled		Timing belt transmission	Timing belt transmission
mechanism	method	Speed reducer to output	Direct-	coupled	Direct-coupled	Direct-coupled
Repeatability Note 1		+/-0.05 mm		+/-0.02 mm	+/-0.005 °	
Maximum speed		7.4 n	7.4 m/sec		600 °/sec	
Maximum payload		50 kg				
Standard cycle time: with 2kg payload Note 2 0.91 sec		sec				
R-axis tolerable moment of inertia Note 3		2.45 kgm²				
User wiring		0.2 sq × 20 wires				
User tubing (Outer diameter)		ф 6 × 3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length		Standard: 3.5 m Option: 5 m, 10 m				
Weight		124 kg				

2500

Controller Power capacity (VA) Operation method

Programming / I/O point trace / Remote command /

Operation using RS-232C communication

■ Controller

RCX340

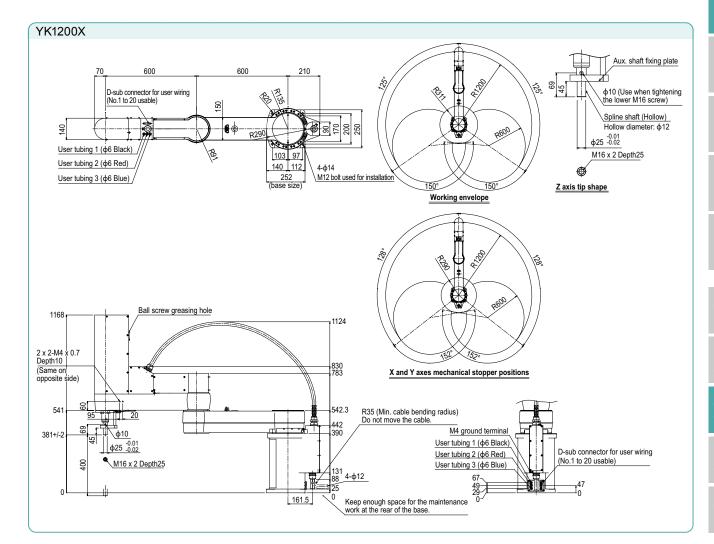
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.) See our robot manuals (installation manuals) for detailed information

> 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 reciprocating 300mm in horizontal and 25mm in vertical directions.

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



YK300XGS

Wall mount / inverse type

ame as per externa

U: Inverse wall mount side down)

Arm length 300mm Maximum payload 5kg Note. Built-to-order product. Contact us for the delivery period.

■ Ordering method

YK300XGS RCX340-4 150 Z axis stroke 150. 150mm No entry: None Specify various controller setting items. RCX340 ▶ P.678

5L: 5m 10L: 10m

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

F: With tool flange S: With hollow shaft

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Axis Arm length		150 mm	150 mm	150 mm	-	
specifications Rotation angl		le	+/-120 °	+/-130 °	-	+/-360 °	
AC servo mot	AC servo motor output			150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer	Direct-coupled				
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			4.4 m/sec		1.0 m/sec	1020 °/sec (wall mount) 720 °/sec (inverse wall mount)	
Maximum payload			5 kg (Standard specification), 4 kg (Option specifications Note 4)				
Standard cycle time: with 2kg payload Note 2			0.49 sec				
R-axis tolerable moment of inertia Note 3			0.05 kgm ²				
User wiring			0.2 sq × 10 wires				
User tubing (Outer diameter)			ф 4 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			19.5 kg				
Next 4. This is the cooler at a constant explicit term and the							

I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

Controller Power capacity (VA) Operation method

Programming /

Controller

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

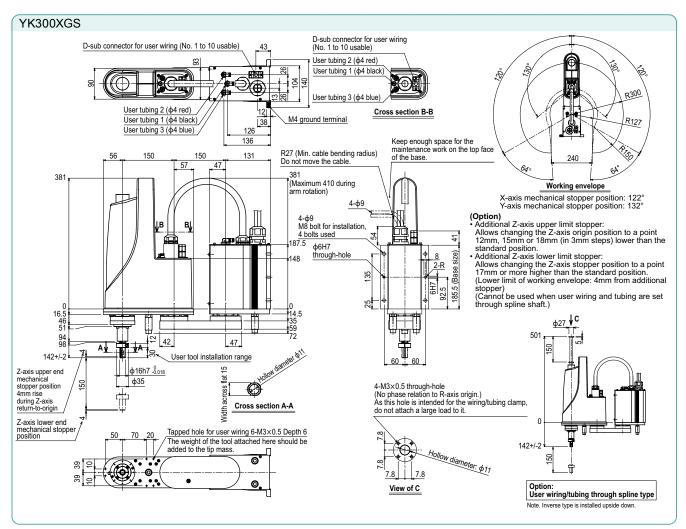
Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

Note 1. This is the value at a constant ambient temperature.

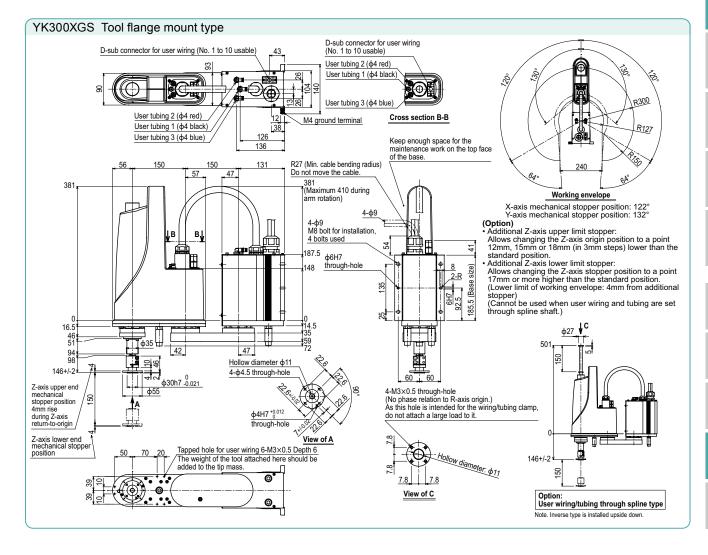
Note 2. When reciprocating 25mm horizontally and 300mm horizontally (with a 2kg payload in rough-positioning arch motion).

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

Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.



& drip-proof



YK400XGS

Wall mount / inverse type

Arm length 400mm
Maximum payload 5kg
Note. Built-to-order product. Contact us for the delivery period.

■ Ordering method

RCX340-4 YK400XGS 150

W: Wall mount U: Inverse wall mount

Incorrect installation can cause trouble or malfunction.

150: 150mm

No entry: None No entry: None F: With tool flange S: With hollow shaft

3L: 3.5m 5L: 5m 10L: 10m

Specify various controller setting items. RCX340 ▶ P.678

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling.

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		250 mm	150 mm	150 mm	-	
specifications	Rotation angl	е	+/-125 °	+/-144 °	-	+/-360 °	
AC servo mote	or output		200 W	150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
	method	Speed reducer to output		Dir	ect-coupled		
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		6.1 m/sec		1.1 m/sec	1020 °/sec (wall mount) 720 °/sec (inverse wall mount)	
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)				
Standard cycle	e time: with 2k	g payload Note 2	0.49 sec				
R-axis tolerab	le moment of	inertia Note 3	0.05 kgm ²				
User wiring			0.2 sq × 10 wires				
User tubing (C	Outer diameter	.)	φ 4 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight					20 kg		

Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

Note. The movement range can be limited by changing the position of Y axis mechanical stopper. (The movement range is set to the maximum at the time of shipment.)

See our robot manuals (installation manuals) for detailed

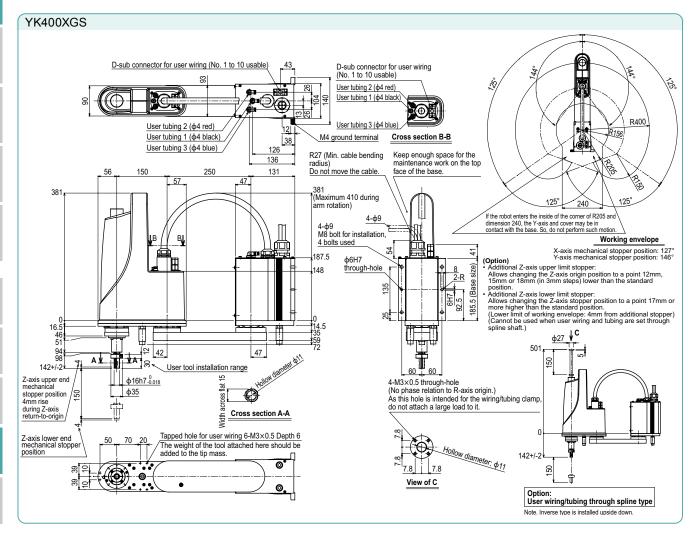
Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

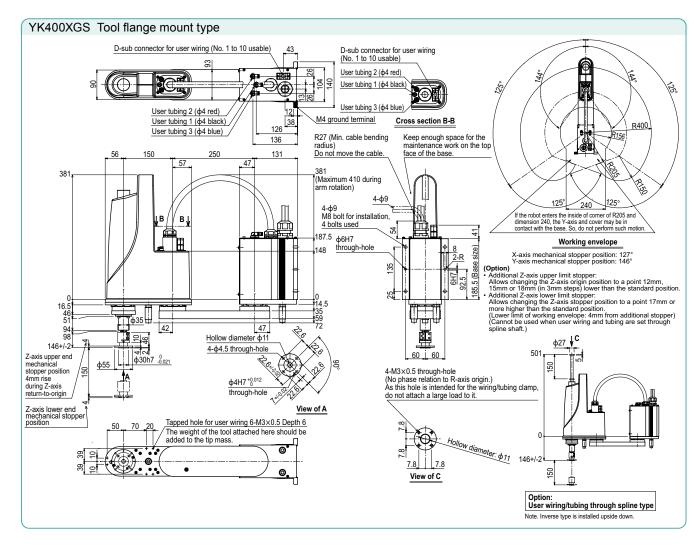
Note 1. This is the value at a constant ambient temperature.

Note 2. When reciprocating 25mm horizontally and 300mm horizontally (with a 2kg payload in rough-positioning arch motion).

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

Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.





YK500XGS

Wall mount / inverse type

Arm length 500mm
Maximum payload 10kg

■ Ordering method

RCX340-4 YK500XGS

W: Wall mount (same as per external view) U: Inverse wall mount (upside down)

Specify various controller setting items. RCX340 ▶ P.678

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

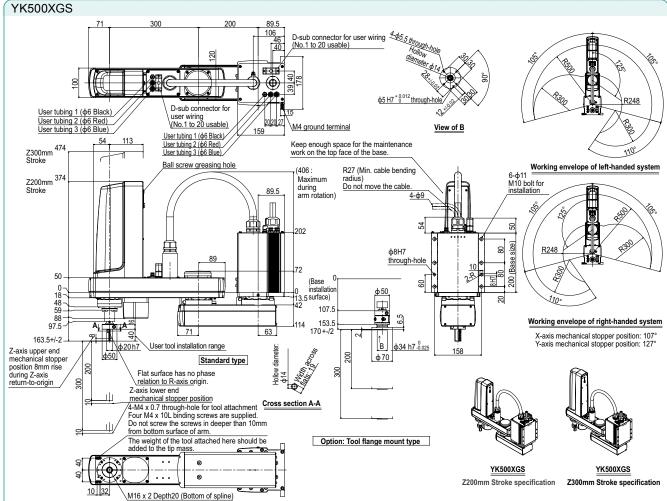
■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		200 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation ang	le	+/-105 °	+/-125 °	_	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output		Dire			
Repeatability Note 1			+/-0.01 mm +/-0.01 mm +/-0.		+/-0.004 °		
Maximum speed		7.6 m/sec 2.3 1.7 180 m/sec m/sec		1700 °/sec (wall mount) 800 °/sec (inverse wall mount)			
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload Note 2	0.45 sec				
R-axis tolerab	le moment of	inertia Note 3	0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (0	Outer diameter	r)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			30 kg				
			, ,				

Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / Operation using RS-232C communication	■ Controller							
RCX340 1700 Remote command / Operation using RS-232C	Controller	Power capacity (VA)	Operation method					
	RCX340	1700	I/O point trace / Remote command / Operation using RS-232C					

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

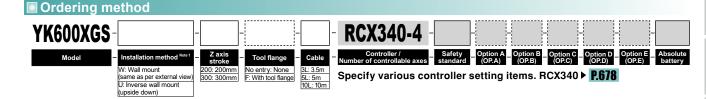
Specifications (Cotation angle			17-103 17-123 - 17-300			17-300	
AC servo motor output			400 W 200 W 200 W 200 W			200 W	
Deceleration Transmission		Motor to speed reducer		Direct-coupled			
mechanism	method	Speed reducer to output		Dir	ect-coupled		
Repeatability	Note 1		+/-0.0	11 mm	+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		7.6 n	n/sec	2.3 1.7 m/sec	1700 °/sec (wall mount) 800 °/sec (inverse wall mount)	
Maximum pay	load		10 kg (Standard type)	, 9 kg (Tool flar	nge mount type)	
Standard cycl	e time: with 2k	g payload ^{Note 2}			0.45 sec		
R-axis tolerab			0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (0	Outer diameter	.)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			30 kg				
Note 1. This is the value at a constant ambient temperature. (X,Y axes) Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions. Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings. Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.							
YK500X0	3S						



Controller

YK600XGS

Arm length 600mm
Maximum payload 10kg



Wall mount / inverse type

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		300 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation ang	le	+/-130 °	+/-145 °	_	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability	Note 1		+/-0.0	1 mm	+/-0.01 mm	+/-0.004 °	
Maximum speed			8.4 m/sec 2.3 1.7 1700 °/sec (wall a m/sec m/sec 8.00 °/sec (inverse wa			1700 °/sec (wall mount 800 °/sec (inverse wall moun	
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload Note 2	0.46 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter	r)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			31 kg				
Note 2. When recip Note 3. The accele	procating 300mm eration coefficient	in horizontal and 25mm in ve is set automatically in accord	ertical directions.	weight and R-ax	kis moment of inert	tia settings.	

4-M4 x 0.7 through-hole for tool attachment Four M4 x 10L binding screws are supplied. Do not screw the screws in deeper than 10mm

The weight of the tool attached here should be added to the tip mass. 0 0

Z-axis lower end

mechanical stopper position

M16 x 2 Depth20 (Bottom of spline)

10 32

98

Contr	■ Controller							
Controller	Power capacity (VA)	Operation method						
RCX340	1700	Programming / I/O point trace / Remote command / 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/

YK600XGS		
User tubing User tubing User tubing Suser tu	71 300 300 89.5 D-sub connector for user wiring (No.1 to 20 usable) 1 (de6 Black) 2 (de6 Red) 3 (de6 Blue) User tubing 1 (de6 Black) User tubing 2 (de6 Red) User tubing 3 (de6 Blue) Ball screw greasing hole D-sub connector for user wiring (No.1 to 20 usable) 4-65.5 through-hole 4-6	R180
Stroke Z200mm 374 Stroke	89.5 Maximum during arm rotation) 4-69 202 489 489 489 489 489 489 489 48	polt for installation
0 18 48 59 89 97.5 163.5 +/-2 Z-axis upper end mechanical stopper position 8 mm rise during Z-axis return-to-origin	A1 13.5 42 114 (Base 0 installation range in the range in	Working envelope of right-handed system X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 147°

В ф34h7-0.025

ф70

Option: Tool flange mount type

Cross section A-A

YK600XGS

Z200mm Stroke specification Z300mm Stroke specification

YK600XGS

YK700XGS

Wall mount / inverse type

Arm length 700mm
Maximum payload 20kg

■ Ordering method

RCX340-4 **YK700XGS**

W: Wall mount (same as per external view) U: Inverse wall mount (upside down)

200: 200mm No entry: None 400: 400mm F: With tool flange

Specify various controller setting items. RCX340 ▶ P.678

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	-	
specifications	Rotation angl	le	+/-130 °	+/-130 °	-	+/-360 °	
AC servo mote	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
	method	Speed reducer to output	Dire		ect-coupled		
Repeatability Note 1			+/-0.02 mm +/-0.01 mm			+/-0.004 °	
Maximum speed			8.4 m/sec 2.3 1.7 920 °/sec (wa m/sec m/sec 480 °/sec (inverse		920 °/sec (wall mount) 480 °/sec (inverse wall mount)		
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload Note 2	0.42 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter	r)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis 200 mm: 50 kg Z axis 400 mm: 52 kg				

Controller							
Controller	Power capacity (VA)	Operation method					
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication					

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

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

\$ **(KO**)

Controller

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

YK700XGS 400 300 D-sub connector for User tubing 3 (φ6 Blue) user wiring (No.1 to 20 usable) User tubing 2 (φ6 Red) User tubing 1 (φ6 Black ● R310 User tubing 1 (\$\phi6\$ Black)
User tubing 2 (\$\phi6\$ Red) 19 D-sub connector for M4 ground terminal User tubing 3 (\$\phi6\$ Blue) user wiring (No.1 to 20 usable) R27 (Min. cable bending Keep enough space for radius)
Do not move the cable. the maintenance work on Z400mm 585 Stroke the top face of the base. 130 Ball screw greasing hole (520)Working envelope of left-handed system 6-φ14 M12 bolt for installation, Z200mm Stroke **4-φ9** 6bolts used R700 97.5 e size) ф8Н7 through-hole 10 28 245 R310 0 (Base 0 30 installation 65.5 surface) R400 137.3 150.5 186.3 202.8+/-2 132 -196.3+/-2 φ25h7 86 (114) Hollow diameter: 418
Width across User tool installation range 198 Z-axis upper end Standard type mechanical stopper position 6mm rise during Z-axis return-to-origin ф55 ф50 h7 -0.025 Flat surface has no phase Working envelope of right-handed system ф95 relation to R-axis origin. 8 X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 132° Z-axis lower end mechanical stopper position 4-M4 x 0.7 through-hole for tool attachment Four M4 x 10L binding screws are supplied.
Do not screw the screws in deeper than 10mm from bottom surface of arm. Option: Tool flange mount type The weight of the tool attached here should be added to the tip mass. 4-φ6.6 through-hole

φ6 H7 +0.012 through-hole

View of B

M20 x 2.5 Depth20 (Bottom of spline)

YK800XGS

Arm length 800mm Maximum payload 20kg

Ordering method

RCX340-4 YK800XGS W: Wall mount (same as per external view U: Inverse wall mount (upside down) 200: 200mm No entry: None 400: 400mm F: With tool flange Specify various controller setting items. RCX340 ▶ P.678

Wall mount / inverse type

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling

Incorrect installation can cause trouble or malfunction.

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		400 mm	400 mm	200 mm 400 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-145 °	_	+/-360 °	
AC servo mot	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability	Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		9.2 m/sec 2.3 m/sec m/		2.3 1.7 m/sec m/sec	920 °/sec (wall mount) 480 °/sec (inverse wall mount)	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload Note 2	0.48 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm²				
User wiring			0.2 sq × 20 wires				
User tubing (C	Outer diameter)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis 200 mm: 52 kg Z axis 400 mm: 54 kg				

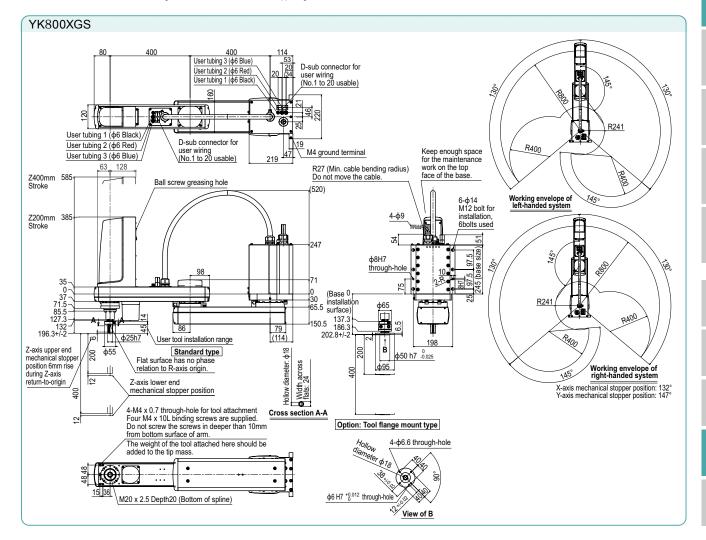
■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 2500 Operation using RS-232C communication

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

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Axis	Armiength		400 mm					
specifications	Rotation angl	е	+/-130 °	+/-145 °	-	+/-360 °		
AC servo motor output			750 W	400 W	400 W	200 W		
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled			
	method	Speed reducer to output		Dir	ect-coupled			
Repeatability	Note 1		+/-0.0	12 mm	+/-0.01 mm	+/-0.004 °		
Maximum speed			9.2 m/sec 2.3 1.7 920 °/sec (wall m/sec m/sec 480 °/sec (inverse v			920 °/sec (wall mount) 480 °/sec (inverse wall mount)		
Maximum pay	Maximum payload			20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload Note 2	0.48 sec					
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm ²					
User wiring			0.2 sq × 20 wires					
User tubing (C	Outer diameter	•)	ф 6 × 3					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m					
Weight			Z axis 200 mm: 52 kg Z axis 400 mm: 54 kg					
Note 1. This is the value at a constant ambient temperature. (X.)			'axes)					

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.



YK900XGS

Wall mount / inverse type

Arm length 900mm
Maximum payload 20kg

■ Ordering method

YK900XGS

W: Wall mount (same as per external view) U: Inverse wall mount (upside down)

RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling. Incorrect installation can cause trouble or malfunction.

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		500 mm	400 mm	200 mm 400 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-150 °	_	+/-360 °	
AC servo mote	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
	method	Speed reducer to output		Dire			
Repeatability Note 1			+/-0.02 mm +/-0.01 mm +/-0		+/-0.004 °		
Maximum spe	ed		9.9 m/sec 2.3 n/sec m/sec 480 °/sec (wall			920 °/sec (wall mount) 480 °/sec (inverse wall mount)	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycle	e time: with 2k	g payload Note 2	0.49 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm²				
User wiring			0.2 sq × 20 wires				
User tubing (Outer diameter)			ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Za	xis 200 mm: 54	kg Zaxis 40	0 mm: 56 kg	

■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 2500 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

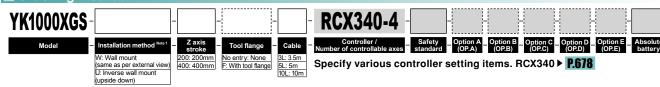
Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings
Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.

YK900XGS 500 D-sub connector for User tubing 3 (φ6 Blue) user wiring (No.1 to 20 usable) User tubing 2 (φ6 Red) User tubing 1 (\$\phi6\$ Black) **4** J • User tubing 1 ($\dot{\phi}$ 6 Black) R253 160 19 M4 ground terminal User tubing 2 (\$\phi6\$ Red) D-sub connector for R400 47 User tubing 3 (φ6 Blue) user wiring (No.1 to 20 usable) Keep enough space for the maintenance RATO 63 128 R27 (Min. cable bending radius) work on the top Do not move the cable face of the base Z400mm Ball screw greasing hole Stroke (520)Norking envelope of left-handed system 6-φ14 M12 bolt for installation, 6bolts used Z200mm Stroke **4-φ9** 385 农 size) 97.5 ф8Н7 245 (base 35 -0 -37 -71.5 -85.5 -127.3 -132 -196.3+/-2 -0 (Base 0 30 installation 65.5 surface) R253 9-----R400 137.3 150.5 186.3 202.8+/-2 R400 79 (114) 86 Hollow diameter: ϕ 18
Width across User tool installation range 198 Z-axis upper end mechanical stoppe position 6mm rise දූ \$55 Standard type ф50 h7 -0.025 Working envelope of right-handed system Flat surface has no phase relation to R-axis origin. φ95 150° during Z-axis return-to-origin 12 X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 152° Z-axis lower end 400 mechanical stopper position Cross section A-A 4-M4 x 0.7 through-hole for tool attachment Four M4 x 10L binding screws are supplied. Do not screw the screws in deeper than 10mm from bottom surface of arm. The weight of the tool attached here should be added to the tip mass. Option: Tool flange mount type 4-φ6.6 through-hole **(O**) $\varphi 6 \ H7 \ ^{+0.012}_0 \ through-hole$ M20 x 2.5 Depth20 (Bottom of spline) View of B

Controller

Arm length 1000mm Maximum payload 20kg

Ordering method



Note 1. When installing the robot, always follow the specifications.

Do not install the ceiling-mount robot upside down or do not install the inverse type robot to a ceiling

YK1000XGS

Incorrect installation can cause trouble or malfunction.

			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		600 mm	400 mm	200 mm 400 mm	-	
specifications	Rotation ang	le	+/-130 °	+/-150 °	-	+/-360 °	
AC servo mot	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output		Dir	ect-coupled		
Repeatability	Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		10.6 m/sec 2.3 n/sec 1.7 920 °/sec (wall mo			920 °/sec (wall mount 480 °/sec (inverse wall mount	
Maximum pay	load		20 kg (Standard type), 19 kg (Tool flange mount type)				
Standard cycl	e time: with 2k	g payload Note 2	0.49 sec				
R-axis tolerab	le moment of	inertia Note 3	1.0 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (0	Outer diameter	r)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis 200 mm: 56 kg Z axis 400 mm: 58 kg				

■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 2500 Operation using RS-232C communication

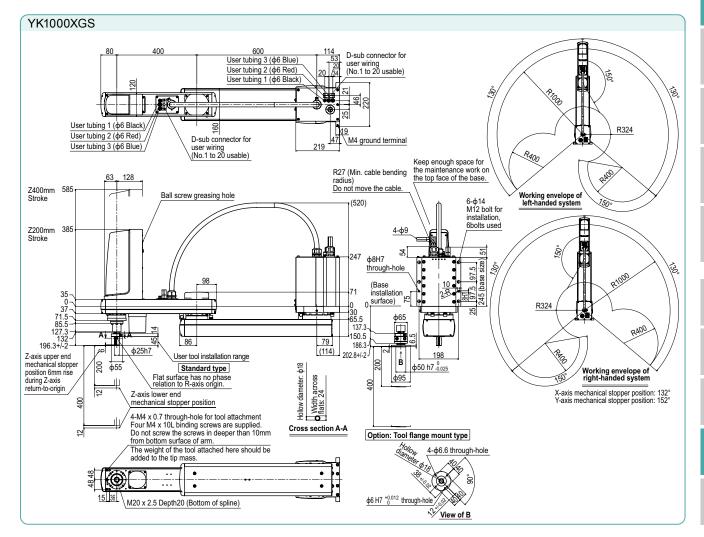
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

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/

AC servo motor output		750 W 400 W 400 W 200 W						
Deceleration	Transmission	Motor to speed reducer	Direct-coupled					
mechanism	method	Speed reducer to output		Direct-coupled				
Repeatability	Note 1		+/-0.0	12 mm	+/-0.01 mm	+/-0.004 °		
Maximum speed		10.6 ו	m/sec	2.3 1.7 m/sec	920 °/sec (wall mount) 480 °/sec (inverse wall mount)			
Maximum payload			20 kg (Standard type), 19 kg (Tool flange mount type)					
Standard cycle time: with 2kg payload Note 2			0.49 sec					
R-axis tolerab	le moment of	inertia ^{Note 3}	1.0 kgm²					
User wiring			0.2 sq × 20 wires					
User tubing (0	Outer diameter	r)	φ 6 × 3					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m					
Weight			Z axis 200 mm: 56 kg Z axis 400 mm: 58 kg					
Note 1. This is the	value at a constar	nt ambient temperature. (X,	(axes)					

Note 1. I his is the value at a constant ambient temperature. (X,Y axes) Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions. Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings Note. Please consult YAMAHA when connecting other tubes and cables to the self-supporting machine harness.



YK250XG

Dust-proof & drip-proof type

Arm length 250mm Maximum payload 4kg

Ordering method

YK250XGP-150

No entry: None F: With tool flange

RCX340-4

Safety Option A Option B Option C Option D Option E Absorbated (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt

Specify various controller setting items. RCX340 ▶ P.678

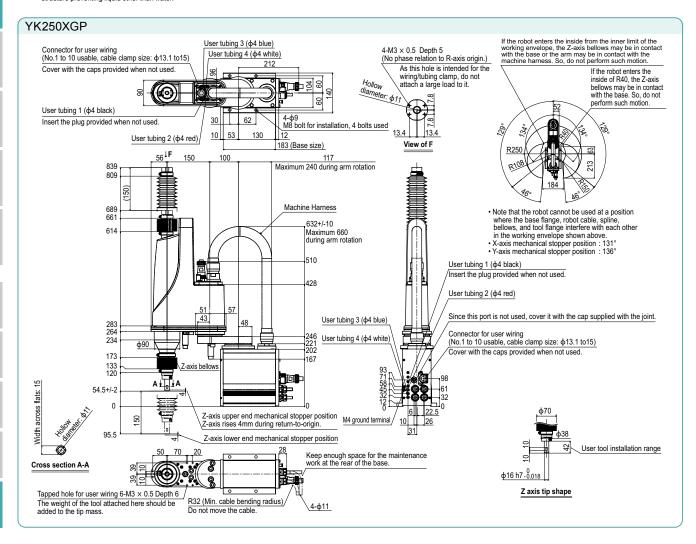
Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		100 mm	150 mm	150 mm	-	
specifications	Rotation angl	le	+/-129 °	+/-134 °	-	+/-360 °	
AC servo moto	or output		200 W	150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled		
mechanism	method	Speed reducer to output		Direct-	coupled	pled	
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			4.5 m/sec 1.1 m/sec 1020			1020 °/sec	
Maximum pay	load		4 kg				
Standard cycle	time: with 2k	g payload Note 2	0.50 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm ²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring			0.2 sq × 10 wires				
User tubing (Outer diameter)			φ 4 × 4				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight		·		21.	5 kg		

Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

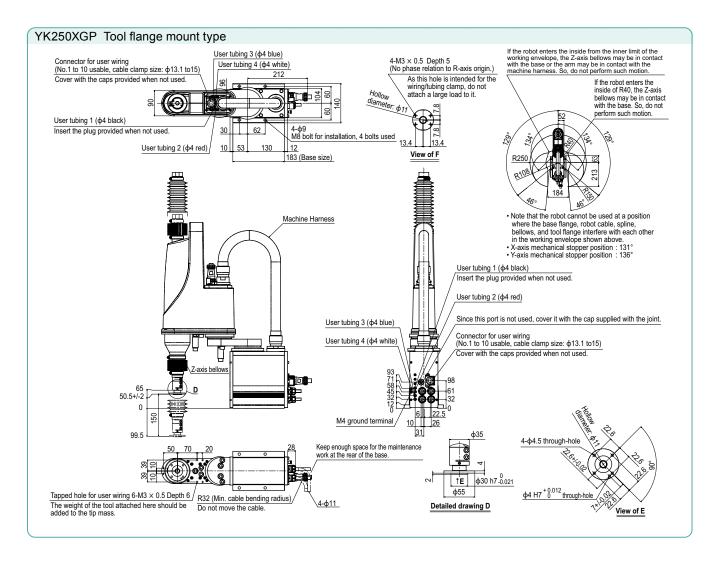
Note. The movement range can be limited by changing the positions The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.
To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
 Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
 Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.



Dust-proof & drip-proof



YK350XGP

Dust-proof & drip-proof type

Arm length 350mm
Maximum payload 4kg

Ordering method

YK350XGP-150 RCX340-4 Safety Option A Option B Option C Option D Option E Absolute standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) battery No entry: None F: With tool flange Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		200 mm	150 mm	150 mm	-
specifications	Rotation ang	le	+/-129 °	+/-134 °	-	+/-360 °
AC servo mot	or output		200 W	150 W	50 W	100 W
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled	
mechanism	method Speed reducer to output			Direct-	coupled	
Repeatability	Note 1		+/-0.0	+/-0.01 mm +/-0.01 mm +		+/-0.004 °
Maximum spe	ed		5.6 m/sec 1.1 m/sec 1020 °/sec			1020 °/sec
Maximum pay	load		4 kg			
Standard cycle	e time: with 2k	g payload Note 2	0.52 sec			
R-axis tolerab	le moment of	inertia Note 3	0.05 kgm²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring			0.2 sq × 10 wires			
User tubing (C	Outer diameter	r)	φ 4 × 4			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			22 kg			

■ Controller							
Controller	Power capacity (VA)	Operation method					
RCX340	1000	Programming / I/O point trace / Remote command / 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.

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

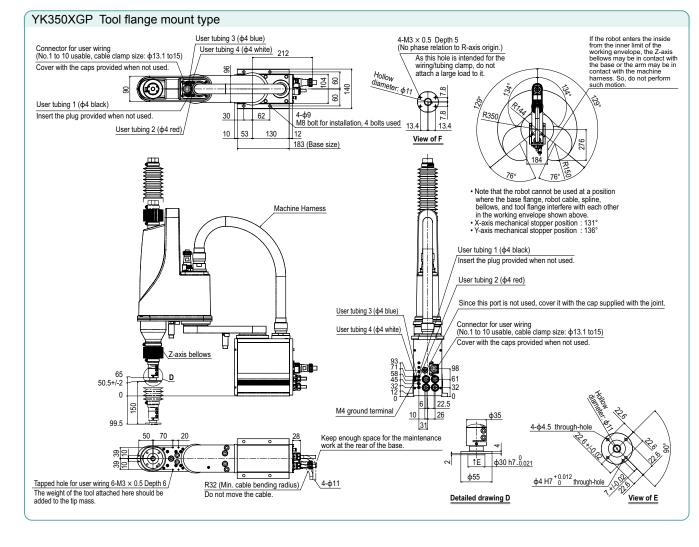
Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

Maximum speed	5.6 m/sec	1.1 m/sec	1020 °/sec			
Maximum payload	4	kg				
Standard cycle time: with 2kg payload Note 2	0.52	sec				
R-axis tolerable moment of inertia Note 3	0.05	kgm²				
Protection class Note 4	Equivalent to IP	65 (IEC 60529)				
User wiring	0.2 sq ×	10 wires				
User tubing (Outer diameter)	ф 4	ф 4 × 4				
Travel limit	1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length	Standard: 3.5 m	Option: 5 m, 10	m			
Weight	Weight 22 kg					
Note 1. This is the value at a constant ambient temperature, (X, Note 2. When reciprocating 25mm in vertical direction and 300m Note 3. The acceleration coefficient is set automatically in according to the company of the section of the company of	nm in horizontal direction (rough-position dance with the tip weight and R-axis mo	ment of inertia setti				

YK350XGP If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such metics. User tubing 3 (\$4 blue) 4-M3 × 0.5 Depth 5 (No phase relation to R-axis origin.) Connector for user wiring (No.1 to 10 usable, cable clamp size: ϕ 13.1 to15) User tubing 4 (\$4 white) As this hole is intended for the wiring/tubing clamp, do not attach a large load to it. Cover with the caps provided when not used Hollow diameter: φ1 such motion. **((@)**} User tubing 1 (ф4 black) Φ 30 62 4-ф9 M8 bolt for installation, 4 bolts used Insert the plug provided when not used. R350 User tubing 2 (\$\phi4\$ red)/ 10 53 130 183 (Base size) View of F 56↓**F** 200 117 Maximum 190 during arm rotation 839 809 76° 15 (120) Machine Harness Note that the robot cannot be used at a position where the base flange, robot cable, spline, bellows, and tool flange interfere with each other in the working envelope shown above.
X-axis mechanical stopper position: 131°
Y-axis mechanical stopper position: 136° 689 661 614 Maximum 660 during arm rotation User tubing 1 (φ4 black) 510 Insert the plug provided when not used. 428 User tubing 2 (\$4 red) 57 Since this port is not used, cover it with the cap supplied with the joint. 43 User tubing 3 (\$4 blue) 48 283 264 Connector for user wiring (No.1 to 10 usable, cable clamp size: ϕ 13.1 to15) 234 User tubing 4 (\$4 white ф90 Cover with the caps provided when not used. 167 Z-axis bellows A A 54.5+/-2 across flats: 0 150 ф70 Z-axis upper end mechanical stopper position M4 ground terminal Z-axis rises 4mm during return-to-origin. 10 26 Z-axis lower end mechanical stopper position 50 70 Keep enough space for the maintenance work at the rear of the base. User tool installation range Cross section A-A ((()) ф16 h7 _{-0.018} Z axis tip shape Tapped hole for user wiring 6-M3 \times 0.5 Depth 6 / The weight of the tool attached here should be R32 (Min. cable bending radius) / Do not move the cable. added to the tip mass.

Controller

Dust-proof & drip-proof



YK400XG

Dust-proof & drip-proof type

Arm length 400mm
Maximum payload 4kg

■ Ordering method

YK400XGP-150

No entry: None F: With tool flange

S

RCX340-4

Safety Option A Option B Option C Option D Option E Abs standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) bat

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		250 mm	150 mm	150 mm	_	
specifications	Rotation angl	е	+/-129 °	+/-144 °	-	+/-360 °	
AC servo moto	or output		200 W	150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled		
mechanism	method	Speed reducer to output		Direct-o	coupled		
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			6.1 m/sec 1.1 m/sec 102		1020 °/sec		
Maximum pay	load		4 kg				
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.50 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm ²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring			0.2 sq × 10 wires				
User tubing (Outer diameter)			φ 4 × 4				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight				22.	5 kg		

Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1000 Operation using RS-232C communication

Note. The movement range can be limited by changing the positions 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.
To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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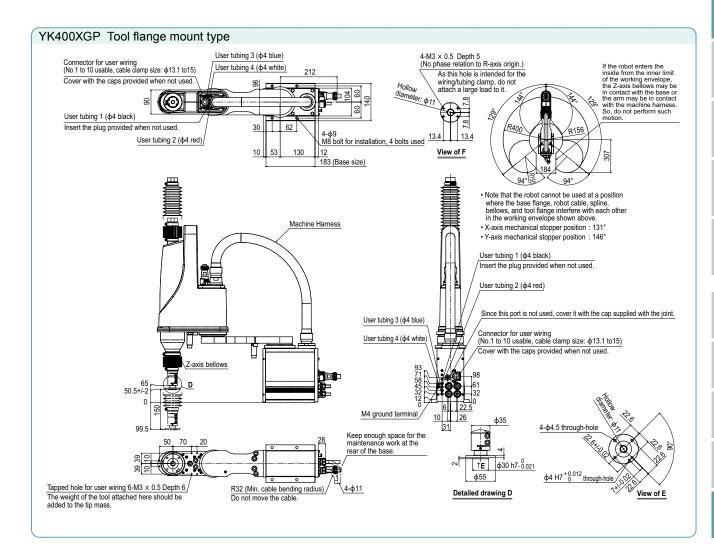
Note 1. This is the value at a constant ambient temperature. (X,Y axes)

Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).

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

Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

YK400XGP User tubing 3 (\$4 blue) 4-M3 × 0.5 Depth 5 Connector for user wiring (No.1 to 10 usable, cable clamp size: \$\phi13.1\$ to15) User tubing 4 (ф4 white) (No phase relation to R-axis origin.) 212 If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harmess. So, do not perform such motion. As this hole is intended for the Cover with the caps provided when not used. Hollow wiring/tubing clamp, do not attach a large load to it. diameter: φ1 ((O)) User tubing 1 (φ4 black) φ 62 $4\text{-}\varphi9$ M8 bolt for installation, 4 bolts used Insert the plug provided when not used. 30 User tubing 2 (\$4 red) 13.4 10 53 View of F 183 (Base size) 150 839 809 Maximum 190 during arm rotation Note that the robot cannot be used at a position where the base flange, robot cable, spline, bellows, and tool flange interfere with each other in the working envelope shown above. 150) Machine Harness 689 661 · X-axis mechanical stopper position: 131° 632+/-10 Maximum 660 Y-axis mechanical stopper position: 146° 614 during arm rotation User tubing 1 (φ4 black) 510 Insert the plug provided when not used. 428 User tubing 2 (φ4 red) 57 Since this port is not used, cover it with the cap supplied with the joint. User tubing 3 (\$\phi4\$ blue) 283 264 234 Connector for user wiring (No.1 to 10 usable, cable clamp size: \$\phi13.1\$ to15) User tubing 4 (\$\phi4\$ white ф90 Cover with the caps provided when not used 173 133 120 Z-axis bellows A Ł TŁA 54.5+/-2 flats: 0 150 Z-axis upper end mechanical stopper position M4 ground terminal Z-axis rises 4mm during return-to-origin. 10 95.5 Z-axis lower end mechanical stopper position Keep enough space for the maintenance work at the rear of the base. 50 70 20 User tool installation range 8 ф16 h7-0.018 Tapped hole for user wiring 6-M3 × 0.5 Depth 6 R32 (Min. cable bending radius) Z axis tip shape The weight of the tool attached here should be added to the tip mass. Do not move the cable



No entry: None F: With tool flange

RCX340-4

Safety Option A Option B Option C Option D Option E Absolut standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) battery

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		250 mm	250 mm	150 mm	-	
specifications	Rotation angl	е	+/-129 °	+/-144 °	-	+/-360 °	
AC servo mot	or output		200 W	150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled		
mechanism	method	Speed reducer to output		Direct-o	coupled		
Repeatability Note 1			+/-0.01 mm +/-0.01 mm +/-		+/-0.004 °		
Maximum spe	ed		5.1 m/sec 1.1 m/sec 1020 °/sec				
Maximum pay	load		4 kg				
Standard cycl	e time: with 2k	g payload ^{Note 2}	0.66 sec				
R-axis tolerab	le moment of	inertia ^{Note 3}	0.05 kgm ²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring			0.2 sq × 10 wires				
User tubing (Outer diameter)			ф 4 × 4				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m				
Weight			25 kg				

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1000 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

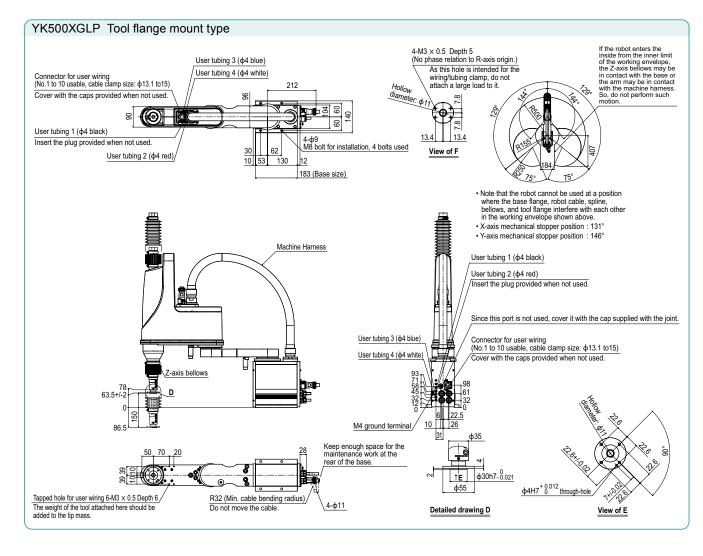
To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. $4\text{-M3} \times 0.5$ Depth 5 (No phase relation to R-axis origin.) User tubing 3 (\$\phi4\$ blue) As this hole is intended for the User tubing 4 (\$4 white) wiring/tubing clamp, do not attach a large load to it. Connector for user wiring (No.1 to 10 usable, cable clamp size: \$\phi13.1\$ to 15) Hollow Cover with the caps provided when not used 10 2 8 s **((())** 60 User tubing 1 (\$4 black) 13.4 Insert the plug provided when not used View of F User tubing 2 (\$4 red) M8 bolt for installation, 4 bolts used 30 10 53 183 (Base size) where the base flange, robot cable, spline, bellows, and tool flange interfere with each other in the working envelope shown above. 250 852 822 Maximum 160 during arm rotation X-axis mechanical stopper position: 131° · Y-axis mechanical stopper position: 146 702 674 Machine Harnes 675+/-10 Maximum 730 User tubing 1 (φ4 black) 627 during arm rotation User tubing 2 (ф4 red) Insert the plug provided when not used. 523 Since this port is not used, cover it with the cap supplied with the joint. 57 296 274 247 User tubing 3 (\$4 blue) Connector for user wiring (No.1 to 10 usable, cable clamp size: ϕ 13.1 to15) ф90 User tubing 4 (\$4 white) Cover with the caps provided when not used Ī 186 Z-axis bellows 146 133 67.5+/-2 across flats: 0 Z-axis upper end mechanical stopper position Z-axis rises 4mm during return-to-origin. ф70 M4 ground terminal Z-axis lower end mechanical stopper position Keep enough space for the maintenance work at the rear of the base. 70 User tool installation range Cross section A-A φ16 h7-0.018 R32 (Min. cable bending radius)/ Z axis tip shape Tapped hole for user wiring $6\text{-M3} \times 0.5$ Depth 64-ф11 The weight of the tool attached here should be added to the tip mass. Do not move the cable

YK500XGLP



YK500XGP

Dust-proof & drip-proof type

Arm length 500mm
Maximum payload 10kg

■ Ordering method

YK500XGP RCX340-4

Specify various controller setting items. RCX340 ▶ P.678

			X-axis	Y-axis	Z-axis	R-axis
						K-axis
Axis	Arm length		200 mm	300 mm	200 mm 300 mm	_
specifications	Rotation ang	le	+/-130 °	+/-145 °	-	+/-360 °
AC servo mot	or output		400 W	200 W	200 W	200 W
Deceleration	Transmission	Motor to speed reducer		Direct	-coupled	
mechanism method		Speed reducer to output	Direct-coupled			
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		7.6 m/sec 2.3 m/sec 1.7 m/sec 170		1700 °/sec	
Maximum pay	load		10 kg			
Standard cycl	e time: with 2k	g payload Note 2	0.55 sec			
R-axis tolerab			0.3 kgm ²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring			0.2 sq × 20 wires			
User tubing (C	Outer diameter	r)	φ 6 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			Z axis 200 mm: 32 kg Z axis 300 mm: 33 kg			

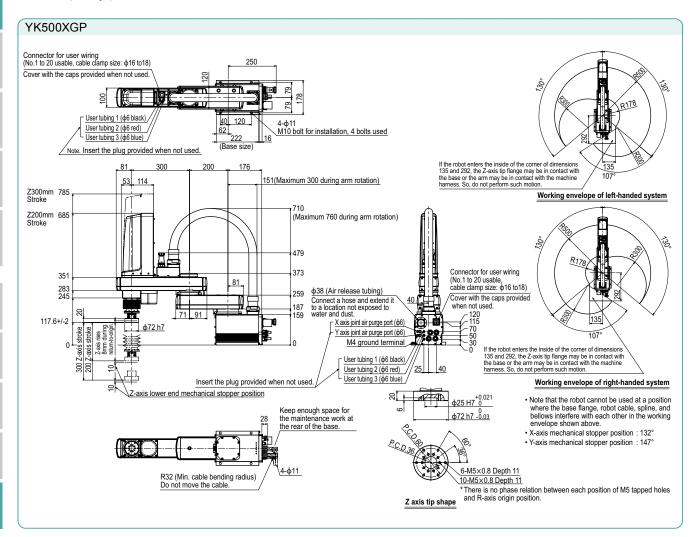
■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 1700 Operation using RS-232C communication

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

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.



Arm length 600mm Maximum payload 4kg

YK600XGLP

■ Ordering method

RCX340-4 YK600XGLP-150 S Safety Option A Option B Option C Option D Option E Absolute oxes standard (OP.A) (OP.B) (OP.C) (OP.D) Option E battery No entry: None F: With tool flange Specify various controller setting items. RCX340 ▶ P.678

■ Specifications								
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		350 mm	250 mm	150 mm	-		
specifications	Rotation angl	е	+/-129 °	+/-144 °	-	+/-360 °		
AC servo moto	or output		200 W	150 W	50 W	100 W		
Deceleration	Transmission	Motor to speed reducer		Direct-	coupled			
mechanism	method	Speed reducer to output	Direct-coupled					
Repeatability	Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.004 °		
Maximum spe	ed		4.9 m/sec 1.1 m/sec 1020 °/			1020 °/sec		
Maximum pay	load		4 kg					
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.71 sec					
R-axis tolerab	le moment of	inertia Note 3	0.05 kgm²					
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)					
User wiring (s	q × wires)		0.2 × 10					
User tubing (Outer diameter)			ф 4 × 4					
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)					
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m					
Weight			26 kg					

■ Controller Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 1000 Operation using RS-232C communication

Note. The movement range can be limited by changing the positions 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.

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

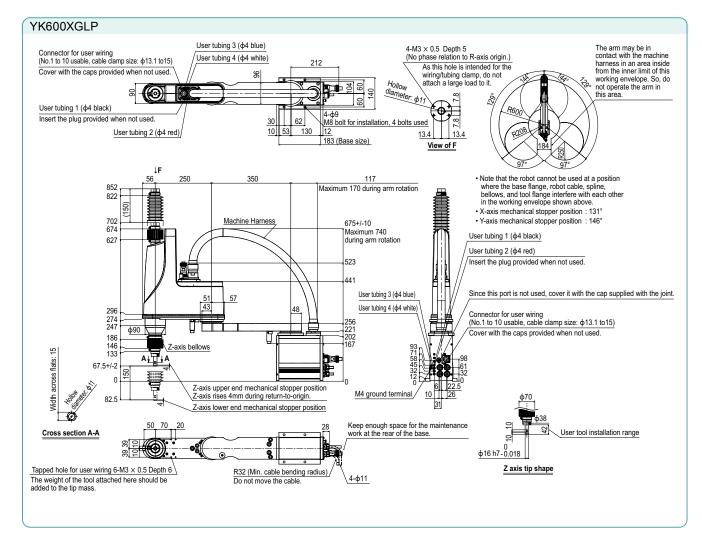
Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

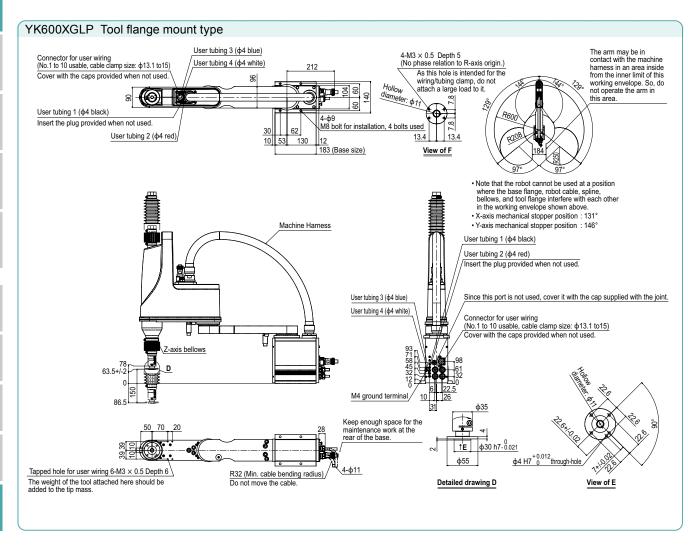
- Note 1. This is the value at a constant ambient temperature. (X.Y axes)

 Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).

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

 Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.





Arm length 600mm
Maximum payload 10kg

YK600XGP

	method

YK600XGP	-	- F	- RCX340-4 -	
Model	Z axis stroke 200: 200mm 300: 300mm	Tool flange F: With tool flange	ble - Controller / Safety - Option / Some standard - OPTION / OP.A) Specify various controller setting ite Om	

■ Specifications X-axis Y-axis Z-axis R-axis 200 mm 300 mm Arm length 300 mm 300 mm specifications Rotation angle +/-130 ° +/-145° +/-360 ° 400 W 200 W 200 W AC servo motor output 200 W Deceleration Transmission Motor to speed reduce Direct-coupled mechanism method Speed reducer to output Direct-coupled Repeatability +/-0.01 mm +/-0.01 mm +/-0.004° Maximum speed 8.4 m/sec 2.3 m/sec 1.7 m/sec 1700 °/sec Maximum payload 10 kg Standard cycle time: with 2kg payload Note 2 0.56 sec R-axis tolerable moment of inertia Note 3 0.3 kgm² Protection class Note 4 Equivalent to IP65 (IEC 60529) User wiring (sq × wires) 0.2 × 20 User tubing (Outer diameter) ф 6 × 3 **Travel limit** 1.Soft limit 2.Mechanical stopper (X,Y,Z axis) Robot cable length Standard: 3.5 m Option: 5 m, 10 m

Controller | Power capacity (VA) | Operation method Programming / I/O point trace / Remote command / RCX340 1700 Operation using RS-232C communication

■ Controller

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

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

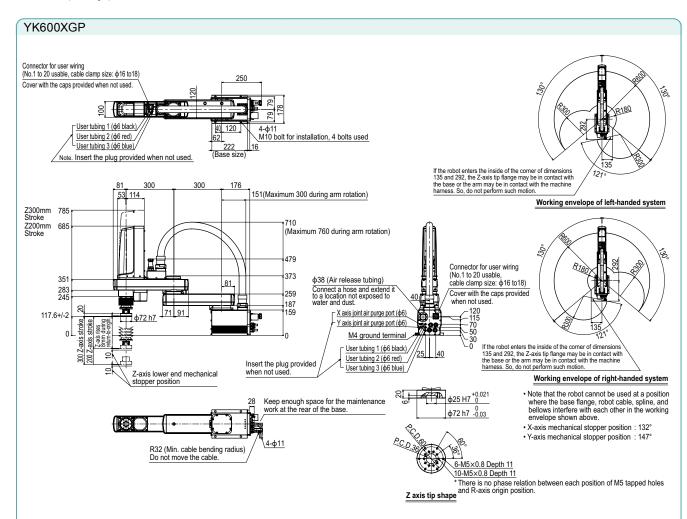
Weight

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

Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).

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

Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.



Z axis 200 mm: 33 kg Z axis 300 mm: 34 kg

YK600XGH

Dust-proof & drip-proof type

Controller

Arm length 600mm
Maximum payload 18kg

■ Ordering method

YK600XGHP RCX340-4 200: 200mm 400: 400mm

Specify various controller setting items. RCX340 ▶ P.678

			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		200 mm	400 mm	200 mm 400 mm	-	
specifications Rotation angle		е	+/-130 °	+/-150 °	_	+/-360 °	
AC servo mot	or output		750 W	400 W	400 W	200 W	
Deceleration Transmission		Motor to speed reducer	Direct-coupled				
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			7.7 m/sec 2.3 m/sec 1.7 m/sec 92		920 °/sec		
Maximum payload		18 kg					
Standard cycle	e time: with 2k	g payload Note 2	0.57 sec				
R-axis tolerab	le moment of	inertia Note 3	1.0 kgm²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring (s	q × wires)		0.2 × 20				
User tubing (Outer diameter)			ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis 200 mm: 52 kg Z axis 400 mm: 54 kg				

RCX340 2500 Operation using RS-232C communication

Controller | Power capacity (VA) | Operation method

Programming / I/O point trace Remote command /

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

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

YK600XGHP Connector for user wiring (No.1 to 20 usable, cable clamp size: ϕ 16 to18) Cover with the caps provided when not used R248 -User tubing 1 (φ6 black) User tubing 2 (\$\phi 6\$ red)
User tubing 3 (\$\phi 6\$ blue) 4-φ14 M12 bolt for installation, 4 bolts used 75 260 (Base s 16 Note. Insert the plug provided when not used. 98 158 If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. 201 _63 128 175(Maximum 300 during arm rotation) Z400mm Stroke 1000 Working envelope of left-handed system Z200mm 800 (Maximum 920 during arm rotation) Stroke 568 476 440 Connector for user wiring 99 (No.1 to 20 usable, cable clamp size: \$16 to 18) 368 324 φ38 (Air release tubing) 339.5 86 101 Connect a hose and extend it to a location not exposed to water and dust. 254.5 219 Cover with the caps provided when not used. ф90 h7 158 98 X axis joint air purge port (φ6) Y axis joint air purge port (φ6) If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be contact with the base or the arm may be in contact w the machine harness. So, do not perform such motion بر M4 ground terminal Z-axis lower end mechanical stopper position User tubing 1 (φ6 black) 25 40 User tubing 2 (\$\phi6\$ red) User tubing 3 (\$\phi6\$ blue) Insert the plug provided when not used Working envelope of right-handed system Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above. φ25 H7 ^{+0.021} ф90 h7 -0.035 Keep enough space for the maintenance X-axis mechanical stopper position: 132° work at the rear of the base P.C.D.364 Y-axis mechanical stopper position: 152° 6-M5×0.8 Depth 11 *There is no phase relation between each position of M5 tapped holes and R-axis origin position. 4-φ11 R32 (Min. cable bending radius) Do not move the cable Z axis tip shape

Controller

Arm length 700mm Maximum payload 20kg

■ Ordering method



Specify various controller setting items. RCX340 ▶ **P.678**

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	-
specifications Rotation angle		+/-130 °	+/-150 °	_	+/-360 °	
AC servo motor output			750 W	400 W	400 W	200 W
Deceleration	Transmission	Motor to speed reducer	Direct-coupled			
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.02 mm +/-0.01		+/-0.01 mm	+/-0.004 °
Maximum speed			8.4 n	n/sec	2.3 m/sec 1.7 m/sec	920 °/sec
Maximum payload				20) kg	
Standard cycle time: with 2kg payload Note 2			0.52 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring			0.2 sq × 20 wires			
User tubing (Outer diameter)			ф 6 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			Z axis 200 mm: 54 kg Z axis 400 mm: 56 kg			

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

Controller	Power capacity (VA)	Operation method
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication

■ Controller

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. Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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

YK700XGP	
Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi16\to18\) Cover with the caps provided when not used. User tubing 1 (\$\phi6\to18\to18\to18\) User tubing 2 (\$\phi8\to18\to18\to18\to18\to18\to18\to18\to1	If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base of the arm may be in contact with the machine harmess. So, do not perform such motion.
Stroke	Working envelope of left-handed system
Z200mm 800 Stroke 813 (Maximum 920 during arm rotation) 568 476 339.5 \$\phi 38\$ (Air release tubing) 254.5 Connect a hose and extend it to a location not exposed to to a location not exposed to water and dust. X axis joint air purge port (\$\phi\$) M4 ground terminal User tubing 1 (\$\phi\$ black) User tubing 2 (\$\phi\$ red) User tubing 3 (\$\phi\$ blue)	Cover with the caps provided when not used. 128 119 80 60 40 If the robot enters the inside of R265 and corner of dimensions 98 and 400, the Z-axis tp flange may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion.
Keep enough space for the maintenance work at the rear of the base.	Working envelope of right-handed system 40.01 40.01 40.035 Note that the robot cannot be used at a position where the base flaringe, robot cable, spline, and bellows interfere with each other in the working envelope shown above. • X-axis mechanical stopper position: 132° • Y-axis mechanical stopper position: 152° • There is no phase relation between each position of M5 tapped holes
R32 (Min. cable bending radius) Do not move the cable. Z axis t	tip shape and R-axis origin position.

Arm length 800mm
Maximum payload 20kg

■ Ordering method

YK800XGP

RCX340-4

Safety Option A Option B Option C Option D Option E Absorber standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt

Specify various controller setting items. RCX340 ▶ P.678

■ Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length		400 mm	400 mm	200 mm 400 mm	-		
specifications	specifications Rotation angle		+/-130 °	+/-150 °	-	+/-360 °	
AC servo mot	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer	Direct-coupled				
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			9.2 m/sec 2.3 m/sec 1.7 m/sec 920 °/			920 °/sec	
Maximum payload			20 kg				
Standard cycle time: with 2kg payload Note 2			0.58 sec				
R-axis tolerable moment of inertia Note 3			1.0 kgm ²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring			0.2 sq × 20 wires				
User tubing (Outer diameter)			ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m				
Weight			Z axis 200 mm: 56 kg Z axis 400 mm: 58 kg				

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 2500 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

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

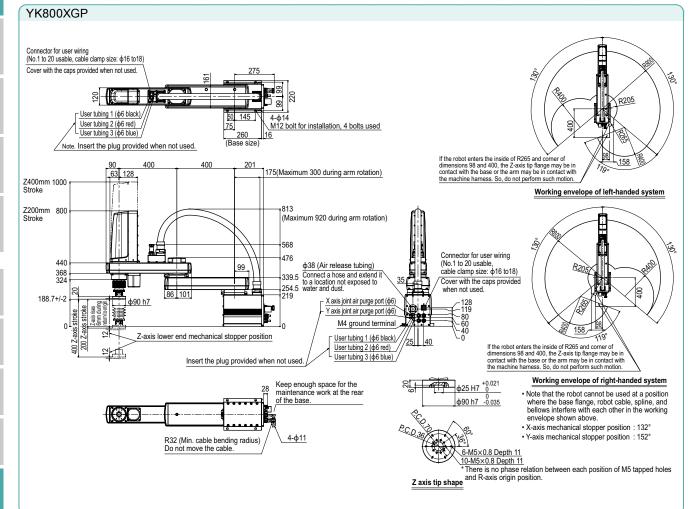
Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

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

Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).

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

Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.



YK900XGP

Arm length 900mm
Maximum payload 20kg

Ordering method



Dust-proof & drip-proof type

■ Specifi	ications					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		500 mm	400 mm	200 mm 400 mm	-
specifications Rotation angle		е	+/-130 °	+/-150 °	-	+/-360 °
AC servo motor output			750 W	400 W	400 W	200 W
Deceleration	Transmission	Motor to speed reducer	Direct-coupled			
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			9.9 m/sec 2.3 m/sec 1.7 m/sec 9		920 °/sec	
Maximum payload			20 kg			
Standard cycle time: with 2kg payload Note 2			0.59 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm ²			
Protection cla	ISS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring (sq × wires)			0.2 × 20			
User tubing (Outer diameter)		ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			Z axis 200 mm: 58 kg Z axis 400 mm: 60 kg			

Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 2500 Operation using RS-232C communication

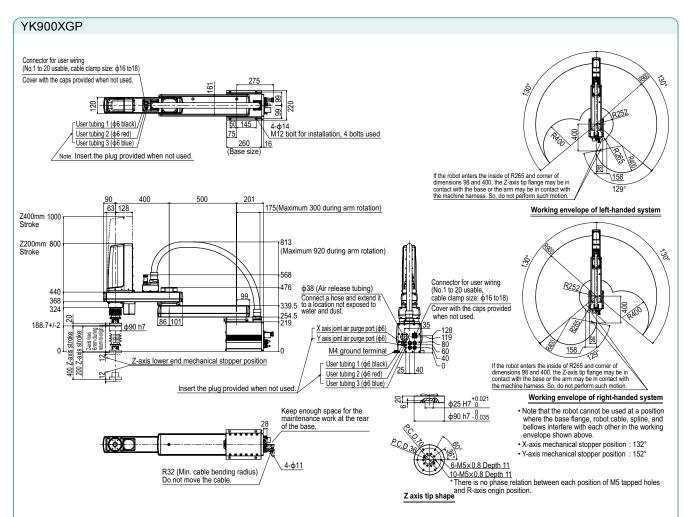
■ Controller

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

To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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 reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.



YK1000XGP

Dust-proof & drip-proof type

Arm length 1000mm
Maximum payload 20kg

■ Ordering method

YK1000XGP RCX340-4 200: 200mm 400: 400mm

Specify various controller setting items. RCX340 ▶ **P.678**

			X-axis	Y-axis	Z-axis	R-axis
Axis specifications Rotation angle			600 mm	400 mm	200 mm 400 mm	_
		le	+/-130 °	+/-150 °	_	+/-360 °
AC servo mot			750 W	400 W	400 W	200 W
Deceleration	Transmission	Motor to speed reducer	Direct-coupled			
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			10.6 m/sec 2.3 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec
Maximum payload				2	0 kg	
Standard cycle time: with 2kg payload Note 2			0.59 sec			
R-axis tolerable moment of inertia Note 3			1.0 kgm²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring (s	q × wires)		0.2 × 20			
User tubing (Outer diameter)			φ 6 × 3			
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m			
Weight			Z axis 200 mm: 60 kg Z axis 400 mm: 62 kg			

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX340 2500 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

Information.
To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note 4. Do not use robots where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

YK1000XGP Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi\$16 to 18) Cover with the caps provided when not used. 66 User tubing 1 (\phi 6 black)/ 4-ф14 M12 bolt for installation, 4 bolts used PROD 145 User tubing 2 (\$\phi6\$ red)
User tubing 3 (\$\phi6\$ blue) 9 260 (Base size) 16 Note. Insert the plug provided when not used. 600 If the robot enters the inside of the corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion. 201 63 128 175(Maximum 300 during arm rotation) 1000 Z400mm Stroke Working envelope of left-handed system (Maximum 920 during arm rotation) 568 476 (No.1 to 20 usable, cable clamp size: \$\phi16\$ to18) 440 339.5 ¢38 (Air release tubing) 99 239.5 Connect a hose and extend 254.5 to a location not exposed to water and dust. Cover with the caps provided R400 φ90 h7 86 101 219 135 188.7+/-2 S Stroke

Xis Stroke

Z-aus ries

Gmm during

Refurn-borigin X axis joint air purge port (φ6) Y axis joint air purge port (φ6) 138° M4 ground terminal If the robot enters the inside of the corner of dimensions 98 and 400, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the machine harmess. So, do not perform such motion. User tubing 1 (φ6 black) Z-axis lower end mechanical stopper position User tubing 2 (\$6 red) - User tubing 3 (φ6 blue) Insert the plug provided when not used Working envelope of right-handed system φ25 H7 ^{+0.021} · Note that the robot cannot be used at a position where the base flange, robot cable, spline, and bellows interfere with each other in the working envelope shown above. Keep enough space for the maintenance work at the rear of the base. ф90 h7 -0.035 X-axis mechanical stopper position: 132° P.C.D.36 Y-axis mechanical stopper position: 152° 6-M5×0.8 Depth 11 4-ф11 10-M5×0.8 Depth 11
* There is no phase relation between each position of M5 tapped holes R32 (Min. cable bending radius) Do not move the cable Z axis tip shape and R-axis origin position.