YK-X Series

Product Lineup

YK-TW Orbit type

YK-XG/YK-X Completely beltless model Note

YK-XE Low cost high performance model

YK-XGS Wall mount/inverse model

YK-XGP Dust-proof & drip-proof model

Note. Except for YK1200X

SCARA ROBOTS

Arm length of 120 mm to 1200 mm, full-selection of the lineup is top in the world.



History of 45 years

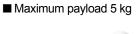
The first YAMAHA robots were SCARA robots. Since the first SCARA robot called "CAME" was produced in 1979, some 45 years of SCARA robot innovations have continually appeared. These SCARA robots have undergone countless modifications in an ever changing marketplace and amassed a hefty record of successful products making them an essential part of the YAMAHA robot lineup.



Comprehensive line of YAMAHA SCARA robots

Orbit type

■ Arm length 350 mm / 500 mm





Extra small type

- Arm length 120 mm to 220 mm
- Maximum payload 1 kg





YK120XG/YK150XG/YK180XG

YK180X/YK220X

Small type

- Arm length 250 mm to 400 mm
- Maximum payload 5 kg



YK250XG/YK350XG/YK400XG

Medium type

- Arm length 500 mm to 600 mm
- Maximum payload 5 kg to 20 kg









Low cost high performance model

- Arm length 400 mm to 710 mm
- Maximum payload 4 kg to 10 kg





YK510XE-10 YK610XE-10 YK710XE-10

Large type

- Arm length 700 mm to 1200 mm
- Maximum payload 10 kg to 50 kg





Wall mount/inverse model

YK300XGS to YK1000XGS





Wall mount type

Inverse type

- Wall mount type
- Type where the robot body is installed in the wall.
- Inverse type
 - Type where the wall mount type is installed upside down.

Dust-proof & drip-proof model





YK250XGP/YK350XGP/YK400XGP YK500XGLP/YK600XGLP

YK500XGP to YK1000XGP

Plays active part in the working environment with a large amount of water or dust (protection class equivalent to IP65).

• Please consult YAMAHA for anti-droplet protection for fluids other than water.

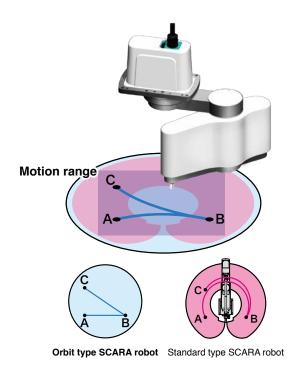
YK-TW Orbit type

YK-TW POINT 1

Layout design freedom

User: We want a smaller equipment footprint.

Featuring a ceiling-mount configuration with a wide arm rotation angle, the YK-TW can access any point within the full φ 1000 mm downward range. This eliminates all motion-related restrictions with regard to pallet and conveyor placement operations, while dramatically reducing the equipment footprint.



YK-TW POINT 2

Higher productivity

User: We need to reduce cycle time.

Standard cycle time of 0.29 secs. Note 2

Y-axis (arm 2) passes beneath the X-axis (arm 1) and it has a horizontal articulated structure, allowing it to move along the optimal path between points. Moreover, the optimized weight balance of the internal components reduces the cycle time by 36 % as compared to previous models.



The standard cycle time for moving a 1-kg load horizontally 300 mm and up/down 25 mm is shortened by approximately 36 % compared to existing YAMAHA models.

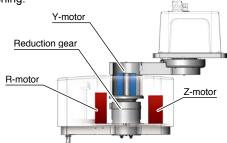
YK-TW POINT 3

High quality

User: We want a high precision assembly system.

YK-TW offers a repeated positioning accuracy of +/-0.01 mm Note 1 (XY axes).

Higher repeated positioning accuracy than that offered by a parallel-link robot. This was accomplished by optimizing the robot's weight balance through an extensive re-design of its internal construction. The lightweight yet highly rigid arm has also been fitted with optimally tuned motors to enable high accuracy positioning.



Hollow construction

Y-motor and reduction gear feature a hollow construction which allows them to be housed inside the harness arm.

360 ° Rotation.

Optimized rotation center of gravity moment

Weight balance was optimized by placing the R-motor and Z-motor at the left and right sides respectively.

Reduced inertia enables high-speed motion.

YK-TW POINT 4

Suitable for a wide range of applications

User: We need to move heavy workpieces at high speeds.

YK-TW handles payloads up to 5 kg.

Handles loads up to 5 kg. Also accommodates arm-end tools which tend to be heavy, making it highly adaptable to various applications.

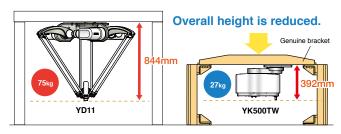
YK-TW POINT 5

Smaller equipment footprint

User: We want to reduce the height of our equipment.

YK-TW offers both a lower height and a smaller footprint.

YK-TW height is only 392 mm. This compact size enables more freedom in the equipment layout design.



YK-TW POINT 6

Easy installation

User: Parallel-link robots require large frames which complicates installation...

YK-TW has a total height of only 392 mm, and weighs only 27 kg.



Reduce the number of steps

YK-TW POINT 7

User: Preparing the frame is extra work.

We can optionally provide a dedicated frame for the YK-TW.

With no need for complex calculations of strength, startup steps can be reduced.

Note. For details on dimensions and price, please contact Yamaha.

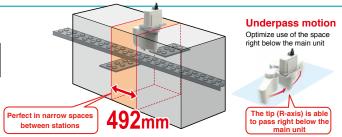


YK-TW POINT 8

Ideal for narrow space applications

User: We need to install in limited space, such as between equipment.

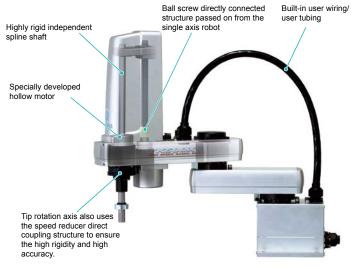
Minimum installation width 492mm Note 1



YK-XG Completely beltless type

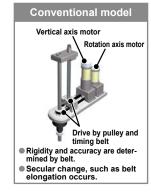
Integral structure designed for optimal operation

Note. The following shows an example of YK500XG.



Completely beltless structure

A completely beltless structure was achieved using a ZR-axis direct coupling structure. This completely beltless structure greatly reduces waste motion. This structure also maintains high accuracy for an extended period of time. Additionally, this structure ensures maintenance-free operation for an extended period of time without worrying about belt breakage, elongation, or secular deterioration (except for Orbit type and large type).



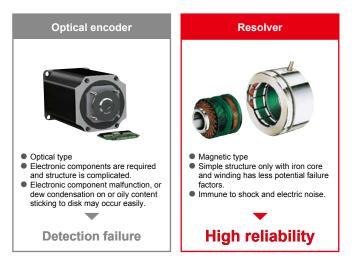


YK-XG POINT 2

Resolver is used for position detector.

As the resolver uses a simple and rigid structure without using electronic components and optical elements, it features high environment resistance and low failure ratio. Detection problems due to electronic component breakdown, dew condensation on or oil sticking to the disk that may occur in optical encoders do not occur in the resolver due to its structure. Additionally, as the absolute specifications and incremental specifications use the same mechanical specifications and common controller, the specifications can be changed only by setting parameters. Furthermore, even when the absolute battery is consumed completely, the robot can still operate as the incremental specifications. So, even if a trouble occurs, the line stop is not needed to ensure the safe production line. The backup circuit has been completely renovated and now has a backup period of one year in the non-energizing state.

Note. The resolver has a simple structure without using electronic components. So, the resolver is highly resistant to low and high temperatures, impacts, electrical noise, dust particles, and oil, etc., and is used in automobiles, trains, and aircrafts that particularly require the reliability.



YK-XG POINT 3

Excellent maintenance ability

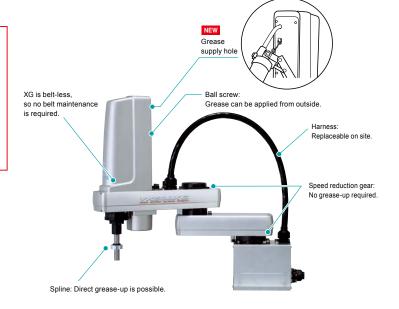
The covers of YAMAHA SCARA robot YK-XG series can be removed forward or upward. The cover is separated from the cable, so the maintenance work is easy. Additionally, the grease replacement of the speed reducer needs many steps to disassemble the gear and may cause positional deviation. However, since the speed reducer of the YAMAHA SCARA robot uses long-life grease, the grease replacement is not needed.

NEW

A grease supply hole is provided in the back of the cover. Even when greasing is required, the cover does not need to be removed for easy maintenance.

* The covers of the products shipped before March 2020 do not have grease supply holes, but can be replaced with covers that have grease supply holes. (Installation compatible. Please order a cover with grease supply hole separately.)

Target product: YK600XGH, YK700XG, YK800XG, YK900XG, YK1000X



YK-XG POINT 4

User can replace the motor and ball screw, etc.

In the case of other companies' SCARA robots, replacing motors and ball screws is time-consuming and in some cases difficult for customers to replace.

In this respect, YAMAHA SCARA robots are easy to replace these parts, so they can be replaced by the customer.

High-speed transfer is possible even with heavy workpieces and large offsets.

The SCARA robot performance cannot be expressed only by the standard cycle time. In actual operating environments, there are various workpieces, such as heavy workpiece or workpiece with large offset. At this time, since the robot with low R-axis tolerable moment of inertia needs to decrease the speed during operation, the cycle time decreases greatly. All YAMAHA SCARA robot YK-XG types have the tip rotation axis directly coupled to the speed reducer. Since the R-axis tolerable moment of inertia is very high when compared to a general structure in which the moment of inertia is transmitted by a belt after decelerating, the robot can operate at a high speed even with workpieces that have been offset.



Optimal acceleration and deceleration are set automatically.

The moment of inertia varies depending on the shape of the workpiece and the offset distance from the R-axis tip to the load center of gravity.

When the offset is large even with the same payload, this value increases. So, the acceleration during operation needs to be reduced.

With the RCX340, the optimum

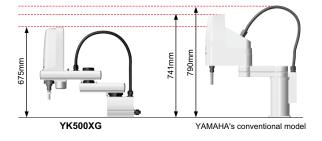
acceleration is automatically set by simply setting the moment of inertia value, so there is no need for troublesome settings.



YK-XG POINT 6

Compact

As the cable layout is changed, the cable height becomes lower than the main body cover. Additionally, use of extruded material base and motor with low overall height achieves the lowest overall height in the same class.



YK-XG POINT 7

Hollow shaft and tool flange options are selectable.

Hollow shaft that allows easy wiring to the tip tool and tool flange for tool mounting are provided as options.



Hollow shaft option convenient for routing of air tubes and harness wires

Note. YK250XG to YK400XG YK500XGL/YK600XGL



Tool flange option for easy mounting of a tool to the tip

Note. YK250XG to YK1000XG

YK-XG POINT 8

Zone control (= Optimal acceleration/deceleration automatic setting) function

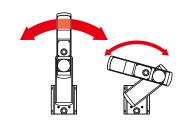
In the SCARA robot, the load applied to the motor and speed reducer in the arm folded state greatly differs from that in the arm extended state. YA-MAHA SCARA robot automatically selects optimal acceleration and deceleration from the arm postures at operation start and operation end. Therefore, the robot does not exceed the tolerance value of the motor peak torque or speed reducer allowable peak torque only by entering the initial payload. So, full power can be extracted from the motor whenever needed and high acceleration/deceleration are maintained.

For X-axis of YK500XG

The torque in the arm folded state is 5 or more times different from that in the arm extended state



This may greatly affect the service life, vibration during operation, and controllability.



If the motor torque exceeds the peak value → This may adversely affect the controllability and mechanical vibration, etc.

If the torque exceeds the tolerable peak torque value of the speed reducer → This may cause early breakage or extremely shorten the service life.

Robot stops at a desired position accurately to ensure long service life.

YK-XE Low cost high performance model

YK-XF POINT

Both the high operation performance and low-price are provided.

Both the high operation performance and low-price are provided. Production equipment with high cost performance can be constructed.



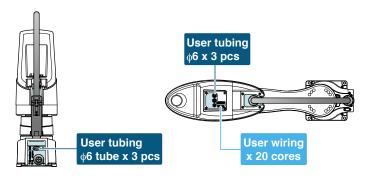
YK-XE POINT 2

Improved User Interface

Enhanced size and numbers of air tubes and user I/O for end effectors.

Tubes and wires are positioned for easy layout and reduced risk of disconnection.

(YK510XE-10, YK610XE-10, YK710XE-10)



Note. YK400XE-4 provides the user wiring x 10 cores and the User tubing $\phi 4$ x 3 pcs.

YK-XE POINT 3

Option specifications

Through-shaft and through-cap have been added.

"Through-shaft" or "through-cap" option for wiring and tubing that is convenient to run the air tubing and wiring can be selected. The wiring and tubing routes can be investigated easily without designing and manufacturing a stay for installing the wiring and tubing. In addition, by passing the wiring and tubing through the inside of the main body, worries about wire breakage or disconnection are reduced during operation. (Through-shaft is only available with the YK400XE-4.)





YK-XE POINT 4

Option specifications

Brake release switch is selectable.

In the emergency stop state, the Z-axis brake is released and the Z-axis can be moved up or down while the brake release switch is held down. Releasing the switch applies the brake to the Z-axis. This improves the convenience during installation adjustment.



YK-XGS Wall mount/inverse model

Hanging type is renewed. Completely beltless structure and high rigidity

As the conventional hanging type is changed to the wall mount type, the flexibility of the system design is improved. The production equipment can be downsized. Additionally, as an inverse type that allows upward operation is also added to the product lineup, the flexibility of the working direction is widened. Furthermore, use of a completely beltless structure achieves a maximum payload of 20 kg and a R-axis tolerable moment of inertia of 1 kgm² Note that are the top in the class. A large hand can also be installed. So, this robot is suitable for heavy load work.

Note. YK700XGS to YK1000XGS



YK-XGP Dust-proof & drip-proof model

Up/down bellows structure improves the dust-proof and drip-proof performance.

The dust-proof and drip-proof type that can be operated even in a work environment where water or particle dust scatters was renewed to a completely beltless structure. The belt does not deteriorate and poor environment resistance is improved. Additionally, an up/down bellows structure is used to improve the dust-proof and drip-proof performance.

Note. YK250XGP to YK600XGLP



Protection class equivalent to IP65 (IEC60529)

Seals are added to the joints to maintain the dust-proof and dripproof performance without air purging. The robot conforms to the protection class equivalent to IP65 (IEC60529).



Dust-proof and drip-proof connector for user wiring is provided as standard.







YK250XGP to 600XGLP (base part)

SCARA robot / Single-axis robot / Cartesian robot / Pick and place robot Various targets

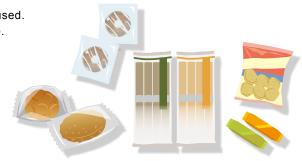
Food grade grease can be used.

The grease used in our robots can be changed to food grade grease.

- Unless otherwise specified, the grease specified by YAMAHA is used.
- It is possible to change to grease other than our specified grease. (At this time, please supply the grease from the customer.)

For details, contact YAMAHA sales representative.

Bellows can also be added by special order!



 $^{^{\}star}$ For use outside Japan, please contact YAMAHA.

Model/Type		Model	Arm length (mm)	Z-axis stroke (mm)	Maximum payload (kg)	Standard cycle time (sec.) Note 1
Orbit type		YK350TW	350	130	5.0	0.32
O.	rbit type	YK500TW	500	130	5.0 (4.0) ^{Note 3}	0.29
		YK120XG	120	50	1.0	0.33
		YK150XG	150	50	1.0	0.33
	Extra small type	YK180XG	180	50	1.0	0.33
		YK180X	180	100	1.0	0.39
		YK220X	220	100	1.0	0.42
		YK250XG	250	150	5.0 (4.0) ^{Note 3}	0.43
	Small type	YK350XG	350	150	5.0 (4.0) ^{Note 3}	0.44
	Small type	YK400XE-4	400	150	4.0 (3.0) ^{Note 3}	0.41
		YK400XG	400	150	5.0 (4.0) ^{Note 3}	0.45
		YK500XGL	500	150	5.0 (4.0) ^{Note 3}	0.48
		YK500XG	500	200/300	10.0	0.42
Standard		YK510XE-10	510	200	10.0 (9.0) ^{Note 3}	0.38
	Medium type	YK600XGL	600	150	5.0 (4.0) ^{Note 3}	0.54
		YK600XG	600	200/300	10.0	0.43
		YK610XE-10	610	200	10.0 (9.0) ^{Note 3}	0.39
		YK600XGH	600	200/400	20.0 (19.0) ^{Note 3}	0.47
		YK700XGL	700	200/300	10.0 (9.0) ^{Note 3}	0.50
		YK710XE-10	710	200	10.0 (9.0) ^{Note 3}	0.42
		YK700XG	700	200/400	20.0 (19.0) ^{Note 3}	0.42
	Large type	YK800XG	800	200/400	20.0 (19.0) ^{Note 3}	0.48
		YK900XG	900	200/400	20.0 (19.0) ^{Note 3}	0.49
		YK1000XG	1000	200/400	20.0 (19.0) ^{Note 3}	0.49
		YK1200X	1200	400	50.0	0.91
		YK300XGS ^{Note 2}	300	150	5.0 (4.0) ^{Note 3}	0.49
		YK400XGS ^{Note 2}	400	150	5.0 (4.0) ^{Note 3}	0.49
		YK500XGS	500	200/300	10.0	0.45
M/- II		YK600XGS	600	200/300	10.0	0.46
wall mour	nt/inverse model	YK700XGS	700	200/400	20.0	0.42
		YK800XGS	800	200/400	20.0	0.48
		YK900XGS	900	200/400	20.0	0.49
		YK1000XGS	1000	200/400	20.0	0.49
		YK250XGP	250	150	4.0	0.50
		YK350XGP	350	150	4.0	0.52
		YK400XGP	400	150	4.0	0.50
		YK500XGLP	500	150	4.0	0.66
		YK500XGP	500	200/300	10.0	0.55
D		YK600XGLP	600	150	4.0	0.71
บust-proof 8	k drip-proof model	YK600XGP	600	200/300	10.0	0.56
		YK600XGHP	600	200/400	18.0	0.57
		YK700XGP	700	200/400	20.0	0.52
		YK800XGP	800	200/400	20.0	0.58
		YK900XGP	900	200/400	20.0	0.59
		YK1000XGP	1000	200/400	20.0	0.59
	an model	See P.103	I.	1		

Note 1. The standard cycle time is measured under the following conditions.

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 The YK300XGS and YK400XGS are custom-order products. For details about the delivery time, please contact YAMAHA.

Note 3. For the option specifications (tool flange mount type and user wiring/tubing through spline type), the maximum payload becomes the value in ().



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YK800XGP131
YK900XGP132
YK1000XGP133

Wall mou

& drip-proo type

YK-X SPECIFICATION SHEET

Тур	e	Model	Arm length (mm) and XY axis resultant maximum speed (m/s)			Standard cycle time	Maximum payload	R-axis tolerable moment of	Completely beltless	Detailed												
			120	150	180	220	250	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.72
04	2	YK500TW					6.8											0.29	5.0	0.005 (Rated) 0.05 (Maximum)		P.74
	<u>و</u>	YK120XG	3.3															0.33	1.0	0.01	•	P.76
	small type	YK150XG		3.4														0.33	1.0	0.01	•	P.77
		YK180XG		3.3														0.33	1.0	0.01	•	P.78
	Extra	YK180X		3.3														0.39	1.0	0.01	•	P.79
		YK220X		:	3.4													0.42	1.0	0.01	•	P.80
	a	YK250XG			4.5													0.43	5.0	0.05	•	P.81
	l type	YK350XG				5.6												0.44	5.0	0.05	•	P.83
	Small	YK400XE-4				6	6.0											0.41	4.0	0.05		P.86
	• /	YK400XG				(5.1											0.45	5.0	0.05	•	P.88
		YK500XGL					5.1											0.48	5.0	0.05	•	P.90
		YK500XG					7.6											0.42	10.0	0.30	•	P.92
Standard	21	YK510XE-10					7.8											0.38	10.0	0.30		P.93
Stan		YK600XGL					4	.9										0.54	5.0	0.05	•	P.94
	Med	YK600XG					8	.4										0.43	10.0	0.30	•	P.96
	Г	YK610XE-10					8	.6										0.39	10.0	0.30		P.97
		YK600XGH					7	7.7										0.47	20.0	1.0	•	P.98
		YK700XGL						9.2										0.50	10.0	0.30	•	P.99
	•	YK710XE-10						9.5										0.42	10.0	0.30		P.100
	Ī	YK700XG		8.4										0.42	20.0	1.0	•	P.101				
	type	YK800XG	9.2										0.48	20.0	1.0	•	P.102					
	arge.	YK900XG							9.9									0.49	20.0	1.0	•	P.103
	- 1	YK1000XG							10	0.6								0.49	20.0	1.0	•	P.104
	ŀ	YK1200X								7.4								0.91	50.0	2.45		P.105
	ŀ	YK1200XG								7.7								0.61	50.0	2.45	•	P.106
	1	YK300XGS			4	.4												0.49	5.0	0.05	•	P.107
e e	H	YK400XGS					6.1		-									0.49	5.0	0.05	•	P.109
e typ	;	YK500XGS					7.6											0.45	10.0	0.3	•	P.111
Wall mount / inverse type	ŀ	YK600XGS						.4										0.46	10.0	0.3	•	P.112
nt / ir	-	YK700XGS						8.4										0.42	20.0	1.0	•	P.113
mom	ŀ	YK800XGS				-			.2									0.48	20.0	1.0	•	P.114
Nall	ŀ	YK900XGS							9.9									0.49	20.0	1.0		P.115
	H	YK1000XGS							10	0.6								0.49	20.0	1.0	•	P.116
	\dashv	YK250XGP	_		4.5													0.50	4.0	0.05	•	P.117
	H	YK350XGP				5.6												0.52	4.0	0.05	•	P.119
	H	YK400XGP					6.1											0.50	4.0	0.05	•	P.121
be D		YK500XGLP																0.66	4.0	0.05	•	P.123
of ty	` -	YK500XGP	\succeq	5.1													0.55	10.0	0.3	•	P.125	
o-pro	.	YK600XGLP		7.6												0.71	4.0	0.05	•	P.126		
& drij	-	YK600XGP		4.9											0.71	10.0	0.03	•	P.128			
Joo.				7.7											0.57			•	P.120			
Dust-proof & drip-proof type	.	YK600XGHP						8.4											20.0	1.0	-	
DO	г	YK700XGP							2									0.52	20.0	1.0	•	P.130
	H	YK800XGP						9	.2									0.58	20.0	1.0	•	P.131
	H	YK900XGP							9.9									0.59	20.0	1.0	•	P.132
		YK1000XGP The standard								0.6								0.59	20.0	1.0	•	P.133

- Note 1. The standard cycle time is measured under the following conditions.

 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.

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

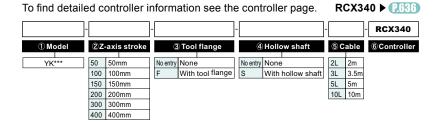
Ordering method

K250XG-150-F-S-3L-RCX340

Mechanical section

Controller section

■ Controller ► RCX340



Note 1. Available only for the master.

Robot ordering method terminology Note. The selection items available for ordering method may vary depending on the model. Note. The selection items available for ordering method m

① Model	Enter the robot unit model.
② Return-to-origin method (YK400XE-4 only)	Select the return-to-origin method. S: Sensor T: Stroke end
③ 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.
(A) Tool floores	Tool flange option for easy mounting of a tool to the tip.
④ Tool flange	No entry: None F: With tool flange
⑤ Hollow shaft	Hollow shaft option for easy routing of air tubes and harness wires.
3 Hollow Stiatt	No entry: None S: With hollow shaft C: With hollow cap
© Brake release switch	Select whether a brake release switch is present.
6 Brake release switch	No entry: None BS: With tool flange
⑦ 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, YK150XG.
® 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

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.636**

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		175 mm	175 mm	130 mm	-	
specifications	Rotation ang	le	+/-225 °	+/-225 °	-	+/-720 °	
AC servo motor 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			Illining belt	
Repeatability	Note 1		+/-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 cycle	e time: with 1k	g payload ^{Note 3}	0.32 sec				
R-axis tolerab	le moment of	Rated	0.005 kgm²				
inertia Note 4		Maximum	0.05 kgm ²				
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				

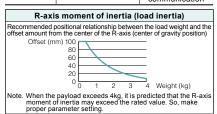
Note 1. This is the value at a constant ambient temperature

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).

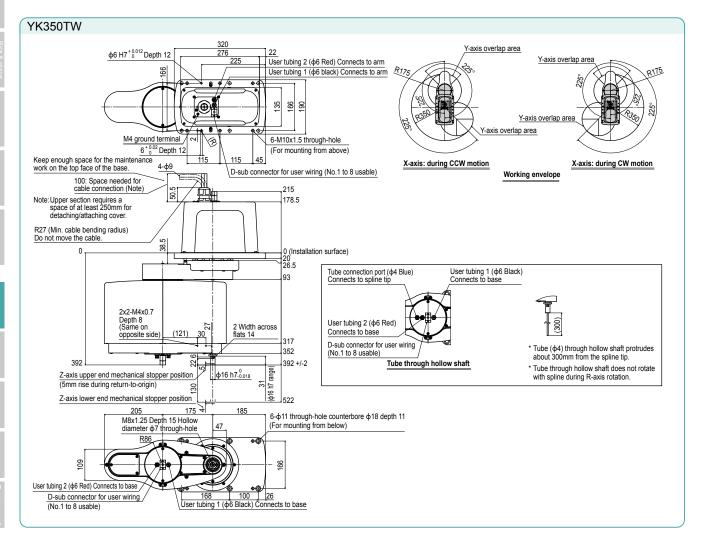
Note 4. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

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

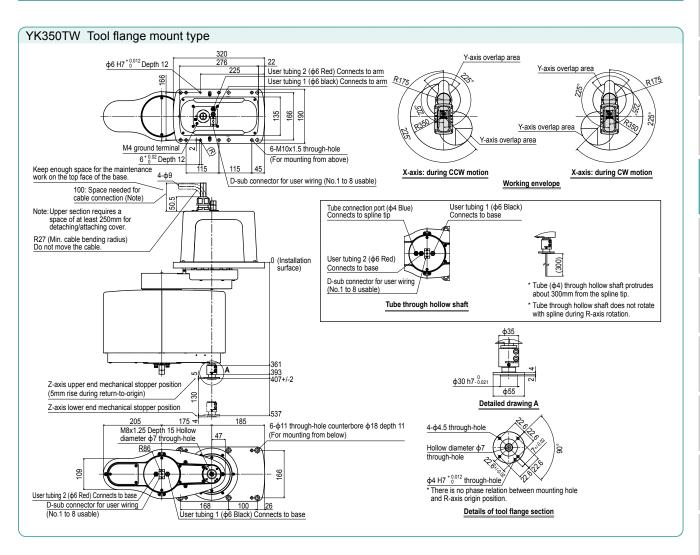


To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

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



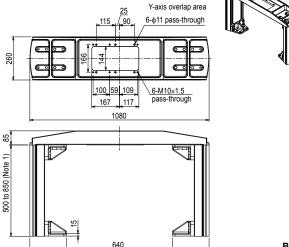
Controller

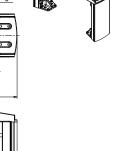


■ Dedicated mounting bracket for the YK-TW <BASE POST ASSY.>

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

External diagram for the YK350TW





8-φ17.5 pass-through From rear side, φ28 counter-bore to depth 5

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	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.

YK500TV

Orbit type

Arm length 500mm
Maximum payload 5kg

■ Ordering method YK500TW-130

Tool flange - Hollow shaft

Cable

RCX340-4

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

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

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifi	cations							
Specific	Cations							
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		250 mm	250 mm	130 mm	-		
specifications	Rotation ang	le	+/-225 °	+/-225 °	-	+/-720 °		
AC servo motor output			750 W	400 W	200 W	105 W		
Deceleration	Transmission	Motor to speed reducer	Timing belt	Direct-coupled	Timing belt	Timing half		
mechanism	method	Speed reducer to output	Direct-coupled			Timing belt		
Repeatability	Note 1		+/-0.015 mm		+/-0.01 mm	+/-0.01 °		
Maximum spe	ed		6.8 m/sec 1.5		1.5 m/sec	3000 °/sec		
Maximum pay	rload Note 2		5 kg					
Standard cycl	e time: with 1k	g payload Note 3	0.29 sec					
	ole moment of	Rated	0.005 kgm ²					
inertia Note 4		Maximum	0.05 kgm²					
User wiring			0.15 sq × 8 wires					
User tubing (Outer diameter)			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. When moving a 1 kg load back and forth 300 mm horizontally and 25 mm vertically (rough positioning arch motion).

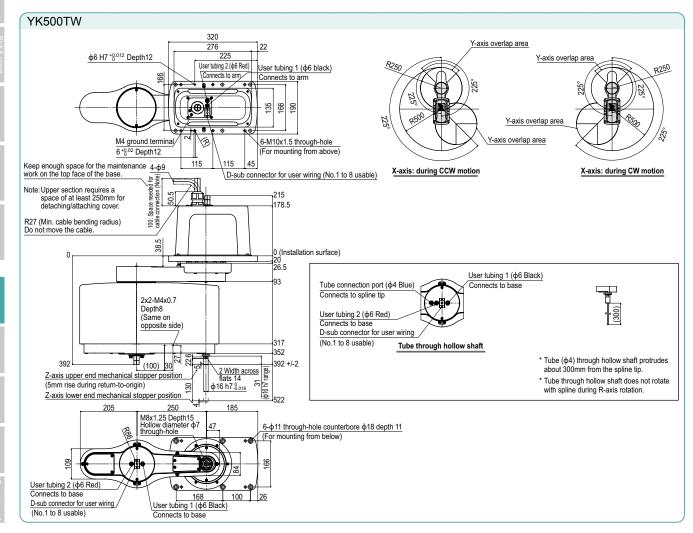
Note 4. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

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

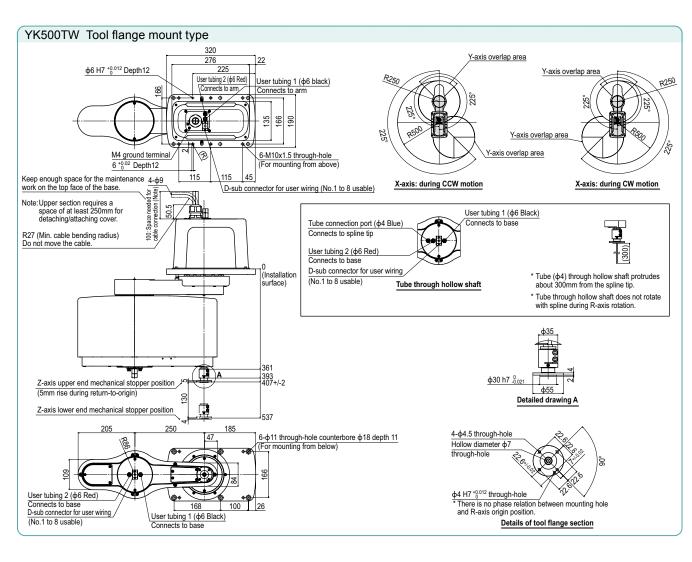
R-axis moment of inertia (load inertia) Recommended positional relationship between the load weight and the offset amount from the center of the R-axis (center of gravity position) Offset (mm) 100 60 40 Weight (kg)

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/



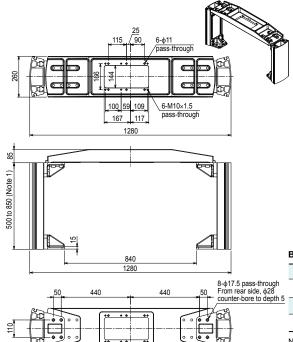
Dust-proof & drip-proof



■ 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

Note. YK350TW and YK500TW are parts in common. Note. The top plate by itself weighs 19 kg.

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

■ Ordering method

YK120XG - 50

Cable

RCX340-4

Specify various controller setting items. RCX340 ▶ P.636

■ Specifi	Specifications					
			X-axis	Y-axis	Z-axis	R-axis
	Arm length		45 mm	75 mm	50 mm	-
specifications	Rotation angle		+/-125 °	+/-145 °	-	+/-360 °
AC servo moto	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	+/-0.01 mm +/-0.01 mm +/		+/-0.004 °
Maximum speed			3.3 m/sec 0.9 m/sec 1700		1700 °/sec	
Maximum pay	load		1.0 kg			
Standard cycle	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	uter diameter	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			3.9 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)

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.

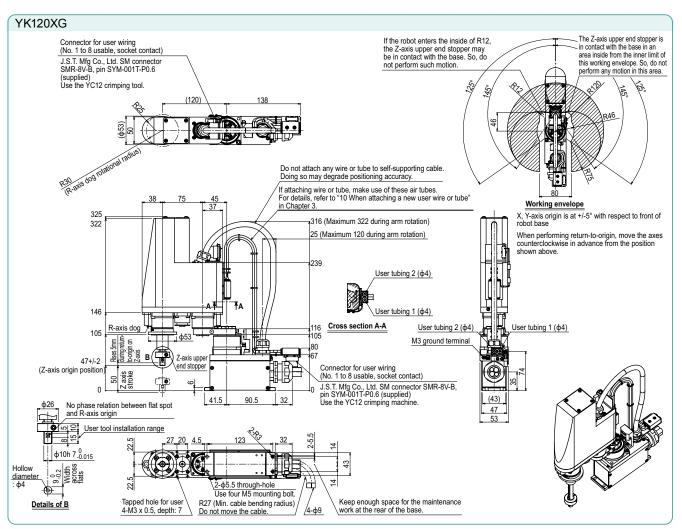
Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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

Arm length 150mm
Maximum payload 1kg

■ Ordering method

YK150XG - 50

Cable

RCX340-4

Specify various controller setting items. RCX340 ▶ **P.636**

Standard type: Extra small type

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		75 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	eceleration 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		3.4 m/sec		0.9 m/sec	1700 °/sec		
Maximum payload		1.0 kg					
Standard cycle	e time: with 0.1	lkg payload Note 2	0.33 sec				
	le moment of			0.01	kgm²		
User wiring			0.1 sq × 8 wires				
User tubing (C	Outer diameter	r)		ф 4	× 2		
Travel limit			1.Soft	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 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			
RCX340	300	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.

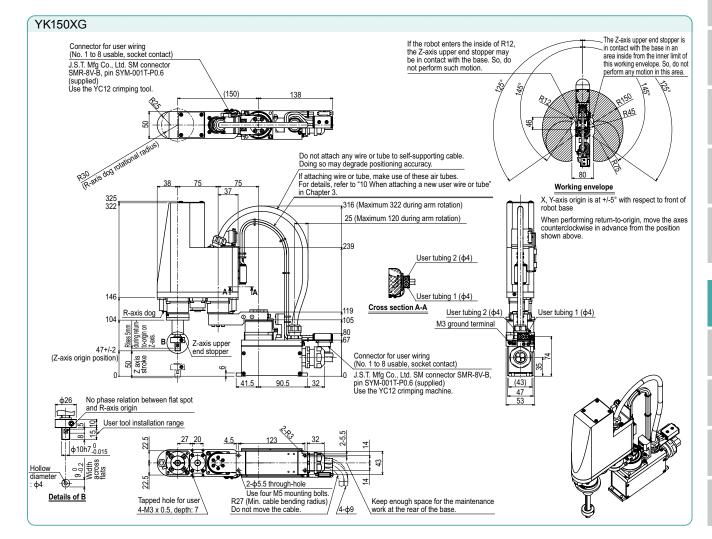
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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

Cable

RCX340-4

Specify various controller setting items. RCX340 ▶ P.636

■ Specif	■ 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 speed			3.3 m/sec 0.9 m/sec		1700 °/sec		
Maximum pay	load		1.0 kg				
Standard cycl	e time: with 0.1	lkg payload ^{Note 2}	0.33 sec				
R-axis toleral	le moment of	inertia Note 3	0.01 kgm ²				
User wiring			0.1 sq × 8 wires				
User tubing (0	Outer diameter	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 v	/eight		0.9 kg (2 m) 1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)			2 kg (10 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.

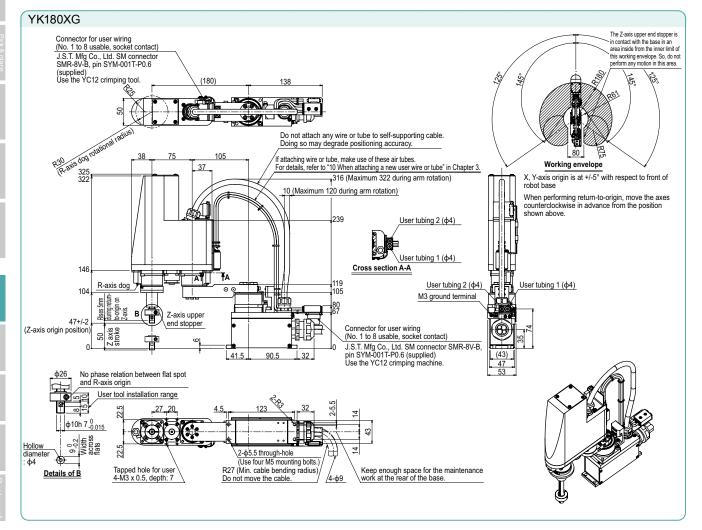
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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



YK180X Standard type: Extra small type

Cable 3L: 3.5m 5L: 5m 10L: 10m Spec

RCX340-4

Arm length 180mm Maximum payload 1kg ■ Ordering method

YK180X - 100

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		71 mm	109 mm	100 mm	-
specifications	Rotation ang	le	+/-120 °	+/-140 °	-	+/-360 °
AC servo motor output			50 W	30 W	30 W	30 W
Deceleration Transmission		Motor to speed reducer		Direct-	coupled	
mechanism method	method	Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed		3.3 m/sec 0.7 m/sec		0.7 m/sec	1700 °/sec	
Maximum pay	load		1.0 kg			
Standard cycl	e time: with 0.1	lkg payload Note 2	0.39 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 (Excluding robot cable) Note 4		5.5 kg				
Robot cable w	reight		1.5 kg (3.5 m) 2.1 kg (5 m) 4.2 kg (10 m)			

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					
Controller	Power capacity (VA)	Operation method			
RCX340	500	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.

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YK180X	
Connector for user wiring (No. 1 to 6 usable, socket contact) J.S.T. Mfg Co., Ltd. SM connector SMR-6VB, pin SYM-001T-P0.6 (supplied) Use the YC12 crimping tool. 10 92 4-4-7 M6 bolt used for installation	R180
Do not attach any wire or tube to self-supporting cable. Doing so may degrade positioning accuracy. If attaching wire or tube, make use of these air tubes. For details, refer to "10 When attaching a new user wire or tube" in Chapter 3. 420 (During arm rotation 425) 30 (Maximum 120 during arm rot) User tubing 2 (ф3) User tubing 2 (ф3)	Working envelope X-axis origin is at 0°+/-5° with respect to front of robot base X, Y-axis origin position When performing return-to-origin, move the axes counterclockwise in advance from the position shown above. ar tubing 1 (\$\phi\$3)
Hollow diameter : \$\phi 4\$ Details of B User tool installation range For user tool installation 4.M4 x 0.7 Depth 6 Details of B Por user tool installation A M4 x 0.7 Depth 6 On not move the cable. Keep enough space for the maintenance work at the rear of the base.	

YK220X

Standard type: Extra small type

Arm length 220mm
Maximum payload 1kg

■ Ordering method

YK220X-100

RCX340-4

Controller

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifi	■ Specifications							
			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	ration Transmission Motor to speed reducer			Direct-o	coupled			
mechanism	method	Speed reducer to output		Direct-o	coupled	d		
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °		
Maximum speed			3.4 m/sec		0.7 m/sec	1700 °/sec		
Maximum pay	load		1.0 kg					
Standard cycle	e time: with 0.1	lkg payload ^{Note 2}	0.42 sec					
R-axis tolerab	le moment of	inertia ^{Note 3}	0.01 kgm ²					
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 (Excluding robot cable) 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	Power capacity (VA)	Operation method
RCX340	500	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.

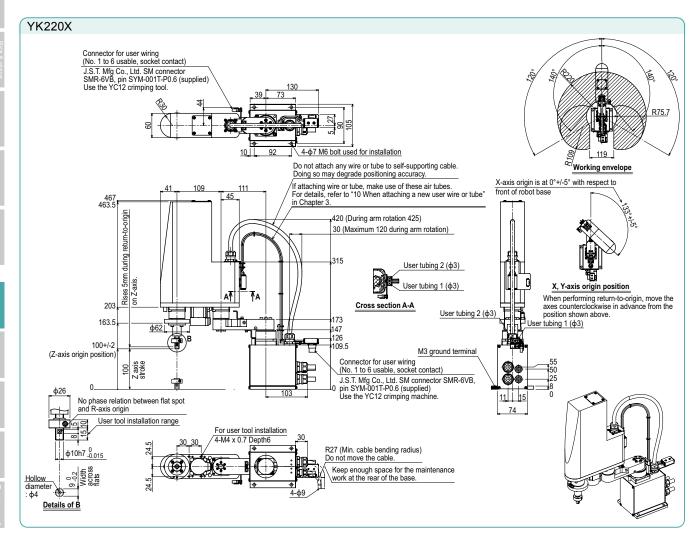
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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



YK250XG

Arm length 250mm
Maximum payload 5kg

■ Ordering method

Standard type: Small type

RCX340-4 YK250XG - 150 Tool flange - Hollow shaft Cable No entry: None F: With tool flange No entry: None S: With hollow shaft Specify various controller setting items. RCX340 ▶ P.636

			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		100 mm	150 mm	150 mm	-
specifications	Rotation angl	le	+/-140 °	+/-144 °	-	+/-360 °
AC servo motor output			200 W	150 W	50 W	100 W
Deceleration mechanism Transmission method		Motor to speed reducer	Direct-coupled			
		Speed reducer to output	Direct-coupled			
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			4.5 m	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 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)		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			18.5 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

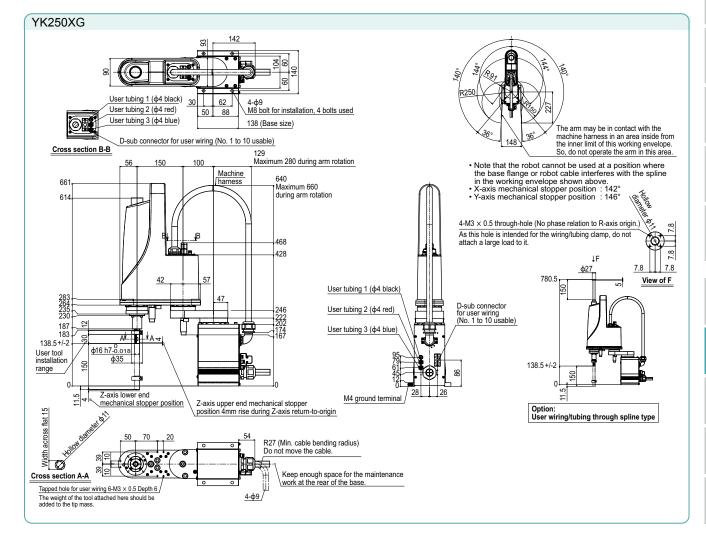
Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.

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

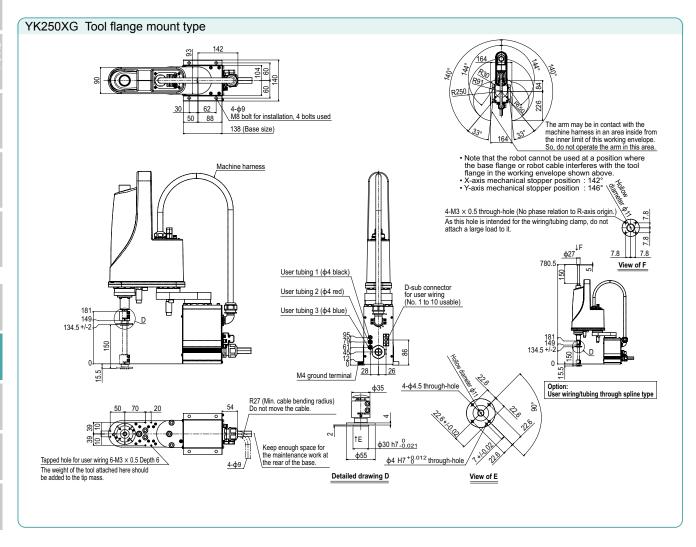
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

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/







YK350XG

Arm length 350mm
Maximum payload 5kg

■ Ordering method

YK350XG - 150

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

No entry: None
S: With hollow shaft

Cable

RCX340-4

19 kg

Standard type: Small type

Specify various controller setting items. RCX340 ▶ **P.636**

cations		X-axis	Y-axis	7-axis	R-axis	
Arm length		200 mm	150 mm	150 mm	-	
Rotation angl	e	+/-140 °	+/-144 °	-	+/-360 °	
AC servo motor output		200 W	150 W	50 W	100 W	
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 °	
ed		5.6 m/sec		1.1 m/sec	1020 °/sec	
load		5 kg (Standard specification), 4 kg (Option specifications Note 4)				
e time: with 2k	g payload ^{Note 2}	0.44 sec				
le moment of	inertia ^{Note 3}	0.05 kgm² (0.5 kgfcms²)				
		0.2 sq × 10 wires				
User tubing (Outer diameter)		ф 4 × 3				
Travel limit		1.Soft limit 2.Mechanical stopper (X,Y,Z axis)				
ength		Standard: 3.5 m Option: 5 m, 10 m				
	Rotation anglor output Transmission method Note 1 ed load e time: with 2k le moment of	Arm length Rotation angle or output Transmission method Speed reducer to output Note 1 ed load et time: with 2kg payload Note 2 le moment of inertia Note 3 Outer diameter)	X-axis Arm length 200 mm Rotation angle +/-140 ° or output 200 W Transmission ethod 5peed reducer to output Note 1 +/-0.0 ed 5.6 r load 5 kg (Standard ethics) time: with 2kg payload Note 2 ele moment of inertia Note 3 Outer diameter) 1.Soft	X-axis Y-axis	X-axis Y-axis Z-axis	

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.

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

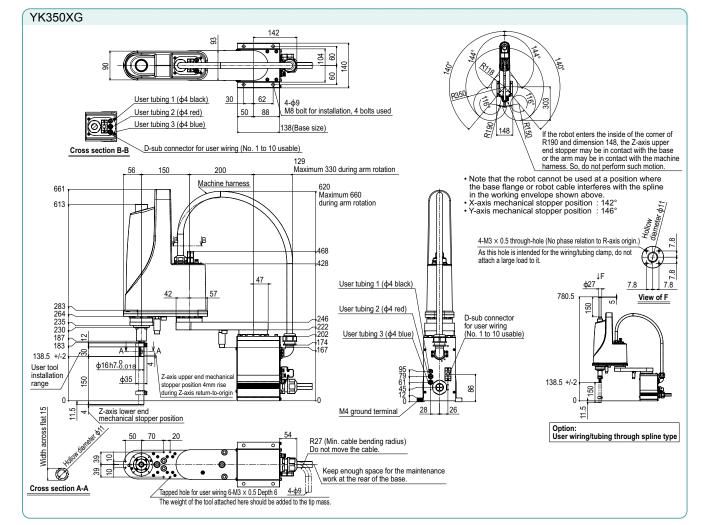
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

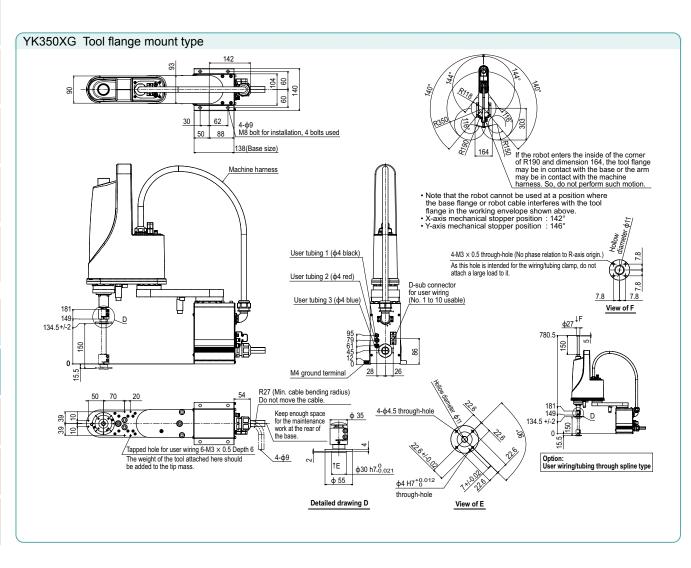
See our robot manuals (installation manuals) for detailed information.

Note. To set the standard coordinates with high accuracy, use a standard coordinate setting iid (ontion). Pafer to the user's

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/







YK400XE-4

Arm length 400mm
Maximum payload 4kg

Standard type: Small type

LOW COST HIGH PERFORMANCE MODEL



Ordering method

YK400XE- 4

150

RCX340-4

■ Controller

RCX340

Controller Power capacity (VA) Operation method

1000

Programming / I/O point trace / Remote command /

Operation using RS-232C communication

31: 3.5m 51: 5m 101: 10m

RCX340 ▶ P.636 Specify various controller setting items.

Specific	ications					
	,		X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		225 mm	175 mm	150 mm	-
specifications	Rotation angle		+/-132 °	+/-150 °	-	+/-360 °
AC servo motor 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 Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.01 °
Maximum speed			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 kgm²			
User wiring			0.2 sq × 10 wires			
User tubing (0	Outer diamete	r)	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				17	ka	

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.

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/

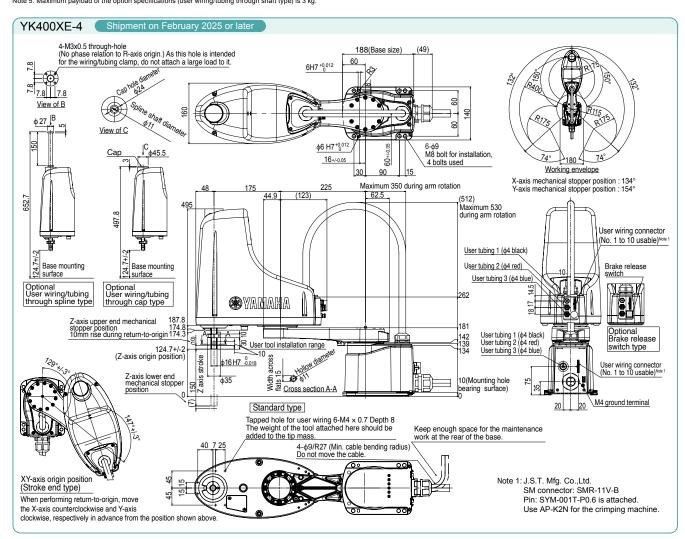
Note 1. This is the value at a constant ambient temperature. (X,Y axes)

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

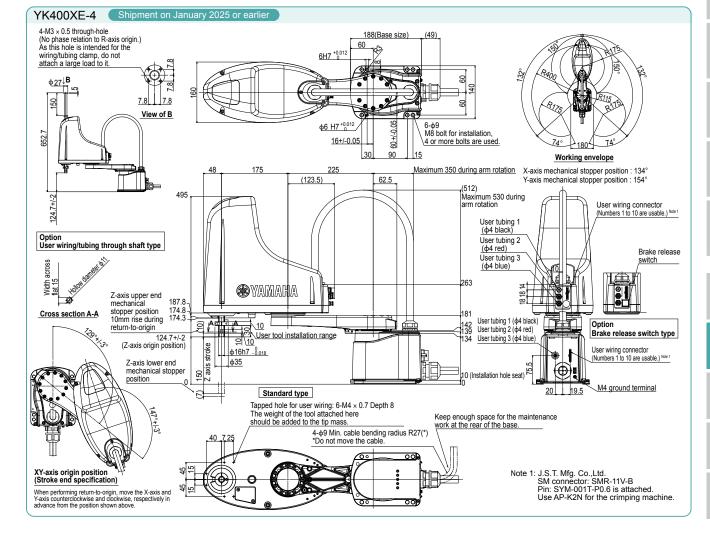
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and offset amount for R-axis moment of inertia settings.

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

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



Dust-proof & drip-proof



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.636**

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		250 mm	150 mm	150 mm	-
specifications	Rotation angle		+/-140 °	+/-144 °	-	+/-360 °
AC servo motor 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	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	.)	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				19.5	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.

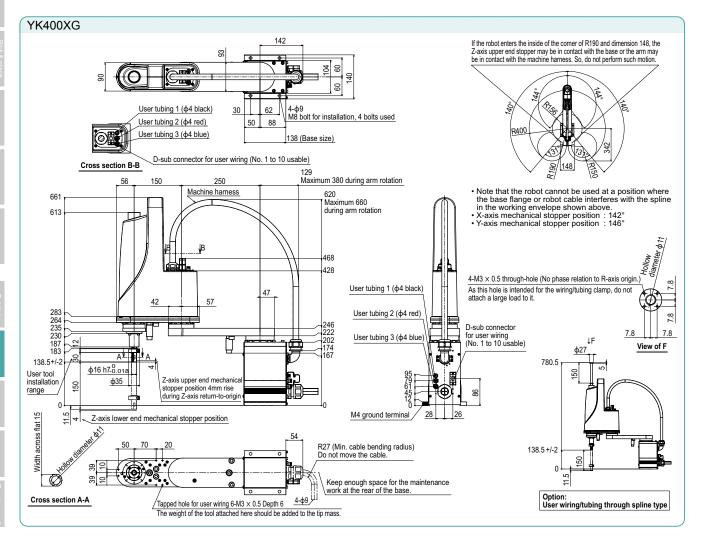
Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.

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

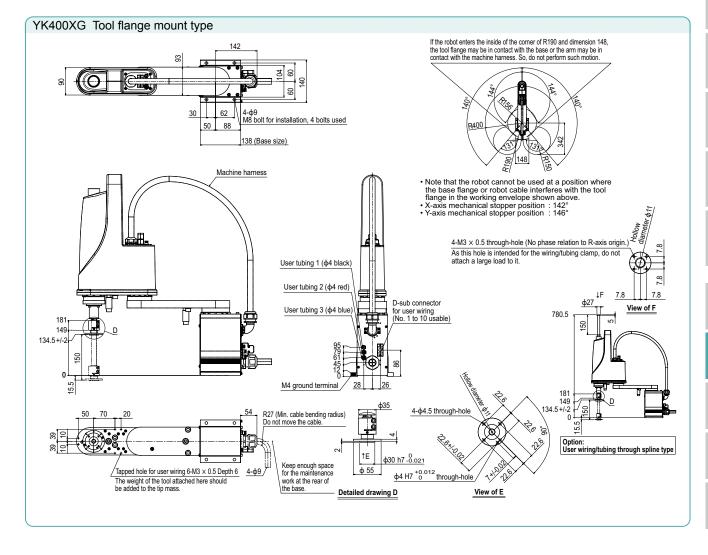
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

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.

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



& drip-proof



YK500XG

Arm length 500mm
Maximum payload 5kg

■ Ordering method

YK500XGL-150

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

RCX340-4 Cable

Standard type: Medium type

■ Controller

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	xis Arm length		250 mm	250 mm	150 mm	-	
specifications	ecifications Rotation angle		+/-140 °	+/-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-coupled				
Repeatability Note 1			+/-0.01 mm +/-0		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		5.1 m/sec 1.1 m/sec 1020 °/s		1020 °/sec		
Maximum pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)				
Standard cycle	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)	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			21 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.

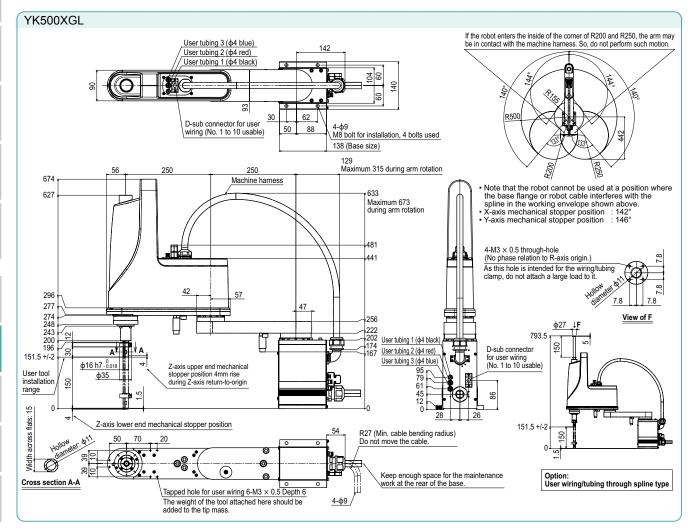
Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

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

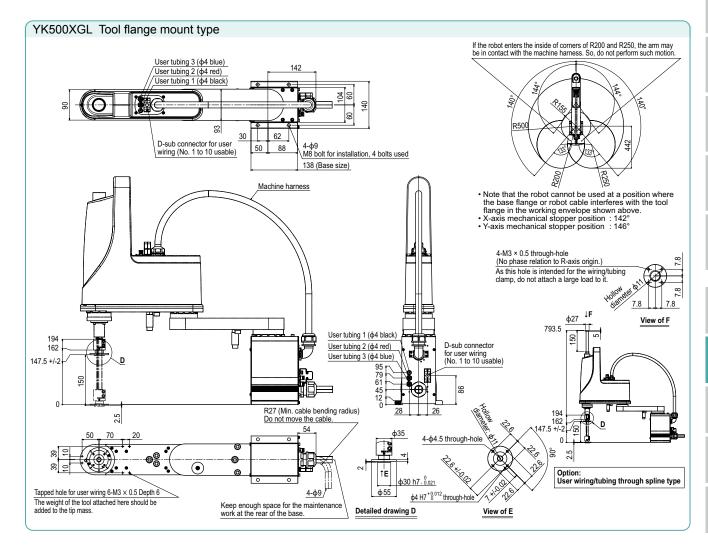
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

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



Controller

Dust-proof & drip-proof



YK500XG

Arm length 500mm
Maximum payload 10kg

Ordering method

YK500XG

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

Cable 3L: 3.5m

RCX340-4

■ Controller

Specify various controller setting items. RCX340 ▶ **P.636**

Standard type: Medium type

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length specifications Rotation angle		200 mm	300 mm	200 mm 300 mm	-		
		+/-130 °	+/-145 °	-	+/-360 °		
AC servo motor output			400 W	200 W	200 W	200 W	
Deceleration Transmiss	ion	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			7.6 m	7.6 m/sec 2.3 m/sec 1.7 m/sec 1700 °		1700 °/sec	
Maximum payload			10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycle time: with	ı 2k	g payload ^{Note 2}	0.42 sec				
R-axis tolerable momen	of	inertia ^{Note 3}	0.30 kgm ²				
User wiring			0.2 sq × 20 wires				
User tubing (Outer diam	eter)	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 / 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.

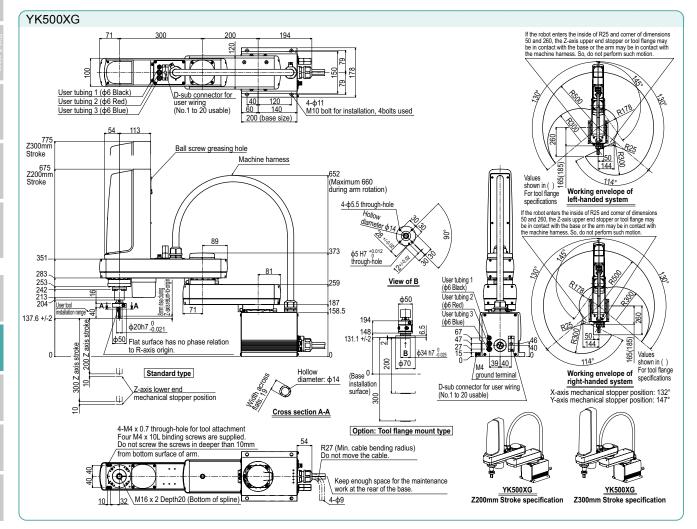
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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



YK510XE-10-200

Maximum Z axis payload stroke

YK510XE-10

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

No entry: None BS: With brake release switch

RCX340-4 Cable

Specify various controller setting items. RCX340 ▶ P.636

	Power capacity (VA)	Operation metho
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 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/

Specific	ications						
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length specifications Rotation angle			235 mm	275 mm	200 mm	-	
		le	+/-134 °	+/-152 °	-	+/-360°	
AC servo mot	AC servo motor output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer	Direct-coupled		Timin	iming belt	
mechanism	method	Speed reducer to output	Direct-coupled		Timing belt		
Repeatability	Repeatability Note 1		+/-0.01 mm		+/-0.01 mm	+/-0.01 °	
Maximum speed			7.8 m	n/sec	2 m/sec	2600 °/sec	
Maximum payload			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 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 / 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.

YK510XE-10
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. User tubing 3 (d6 blue) User tubing 2 (d6 red) User tubing 2 (d6 red) User tubing 2 (d6 black) User tubing 3 (d6 black) User tubing 2 (d6 black) User tubing 3 (d6 black) User tubing 2 (d6 black) User tubing 2 (d6 black) User tubing 3 (d6 black) User tubing 3 (d6 black) User tubing 2 (d6 black) User tubing 3 (d6 black) User tubing 3 (d6 black) User tubing 3 (d6 black) User tubing 4 (d5 black)
Western southern
Maximum 250 during working envelope 49 275 235 arm rotation X-axis mechanical stopper position : 142° Y-axis mechanical stopper position : 154° witch type) 86 6
Base installation surface Option: User wiring/tubing
through shaft type Through cap type Z-axis upper end mechanical stopper position 220.8 7.5mm rise during 204.8 7.5mm rise du
4-65.5 through-hole (No phase relation to Pavis origin) 4-69.5 were position (No phase relation to Pavis origin) 4-69.5 through-hole (No phase relation to Pavis origin) 4-69.9 Min. cable bending radius R27(*)
Note 1: J.S.T. MFG. CO., LTD. SM connector: SMR-9V-B Note 2: J.S.T. MFG. CO., LTD. SM connector: SMR-12V-E Common to Notes 1 and 2.
Option: Tool flange mount type Wiew of C M16X2 Depth20 (Bottom of spline) Wiew of C M16X2 Depth20 (Bottom of spline) Wiew of C

RCX340 ► **636**

93

YK600XG

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

RCX340

Programming / I/O point trace Remote command /

Operation using RS-232C

Specify various controller setting items. RCX340 ▶ **P.636**

Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		350 mm	250 mm	150 mm	-
specifications	Rotation angl	e	+/-140 °	+/-144 °	-	+/-360 °
AC servo motor 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 speed			4.9 m/sec 1.1 m/sec 1		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			
	ole moment of		0.05 kgm² (0.5 kgfcms²)			
User wiring			0.2 sq × 10 wires			
User tubing (0	Outer diameter	r)	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			
Weight				22	kg	

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

Controller Power capacity (VA) Operation method

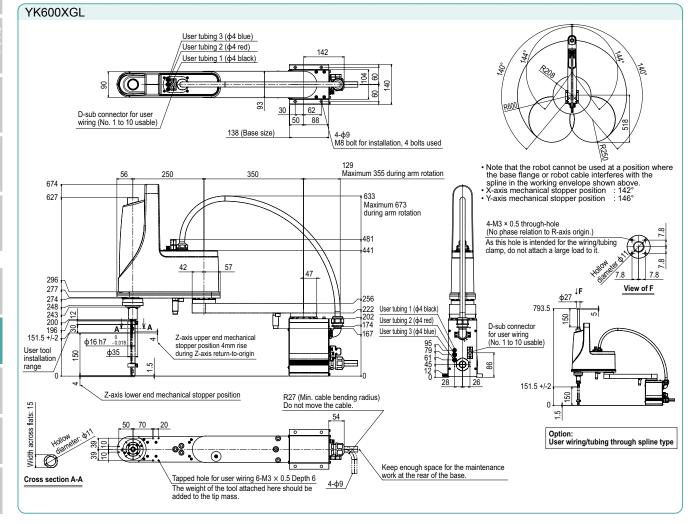
1000

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.

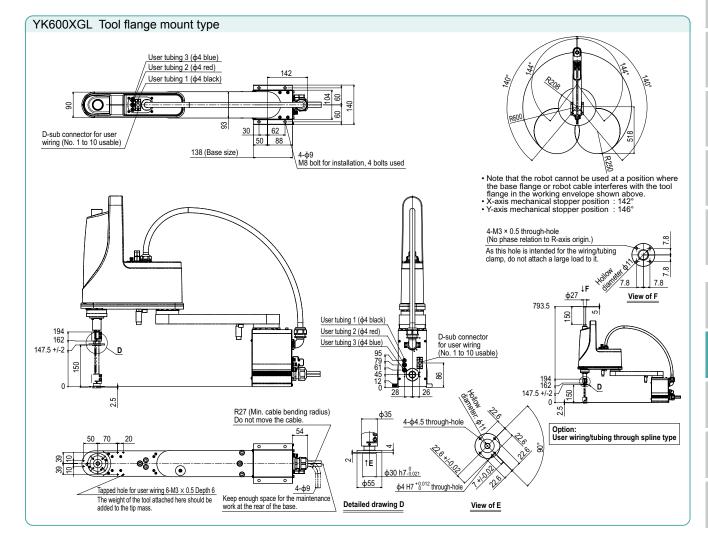
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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



95 |



YK600XG

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

Cable 3L: 3.5m

RCX340-4

Option B – (OP.B)

■ Controller

RCX340

Controller | Power capacity (VA) | Operation method

1700

Programming / I/O point trace Remote command /

Operation using RS-232C communication

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifications							
			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 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		8.4 m/sec		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)		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. 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

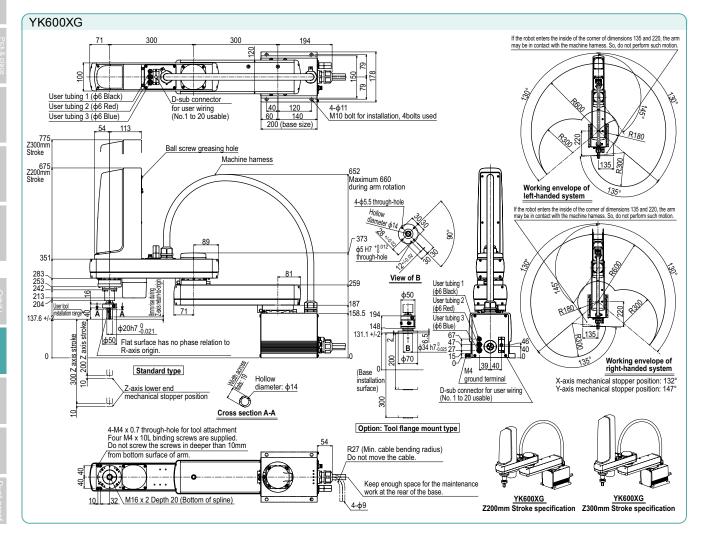
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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

Arm length 610mm
Maximum payload 10kg Ordering method

YK610XE- 10 -200

No entry: None F: With tool flange

No entry: None S: With hollow si C: With hollow

RCX340-4

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specification	ications					
			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-o	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	ole moment of	inertia Note 3	0.3 kgm²			
User wiring			0.2 sq × 20 wires			
User tubing (0	Outer diamete	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				
RCX340	1700	Programming / I/O point trace / Remote command / Operation using RS-232C communication				

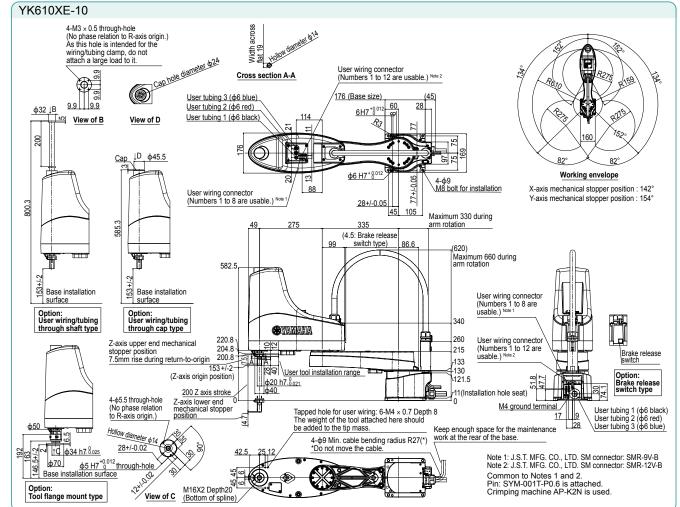
Note. The movement range can be restricted by adding the X- and The invenient range can be restricted by adding the X- and Y-xakis mechanical stoppers. (The maximum movement range was set at shipment.)

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

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

Controller

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifications							
			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 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: 48 kg Z axis 400 mm: 50 kg				

Programming / I/O point trace Remote command / RCX340 2500 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/

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.

YK600XGH 400 D-sub connector for user wiring 88 User tubing 1 (φ6 Black) 50 145 75 170 φ14 M12 bolt for installation, 4bolts used User tubing 2 (φ6 Red) User tubing 3 (φ6 Blue) (base size) 4-φ6.6 through-hole 128 If the robot enters the inside of the corner of di Z400mm Stroke 100 and 400, the arm may be in contact with the 979 machine harness. So, do not perform such motion Working envelope of left-handed system Ball screw greasing hole ф6 H7 ^{+0.012} Z200mm 790 Stroke Machine harness Maximum 770 View of B during arm rotation ф65 476 User tubing 1 (φ6 Black) 99 268 0 0 339.5 219 202.2 (\$6 Red) † B 273 User tool installation range 219 (\$6 Blue) 208.7+/-2 φ25h7_{-0.021} 00 Z axis stroke ф50 h7.0025 φ55
Flat surface has no phase relation to R-axis origin. ф95 axis stroke 400 If the robot enters the inside of the corner of dimer 100 and 400, the arm may be in contact with the machine harness. So, do not perform such motion 23 21 25 (Base Standard type Hollow installation Working envelope of right-handed system diameter : φ18 surface) M4 around Hats: Z-axis lower end mechanical stopper position terminal X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 152° D-sub connector for user wiring Cross section A-A (No.1 to 20 usable) 2 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 R27 (Min. cable bending radius) Do not move the cable Keep enough space for the maintenance work at the rear of the base. (\mathbf{W}) M20 x 2.5 Depth 20 (Bottom of spline) YK600XGH YK600XGH Z200mm Stroke specification Z400mm Stroke specification

YK700XG

Arm length 700mm Maximum payload 10kg

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

Standard type: Large type

Ordering method

RCX340-4 YK700XGL Tool flange Cable No entry: None F: With tool flange 5L: 5m 10L: 10m Specify various controller setting items. RCX340 ▶ **P.636**

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	
	method	Speed reducer to output	Direct-c		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	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	.)	φ6 × 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.

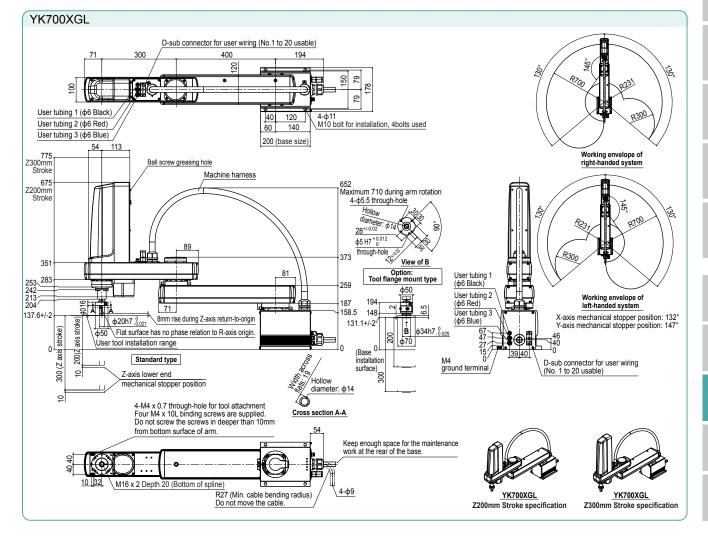
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings

	■ Controller							
ĺ	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

entry: None

No entry: None BS: With brake release switch

RCX340-4

■ Controller

Specify various controller setting items. RCX340 ▶ P.636

■ 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 me	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 cycl	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 (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			26 kg			

Programming / I/O point trace Remote command / RCX340 1700 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/

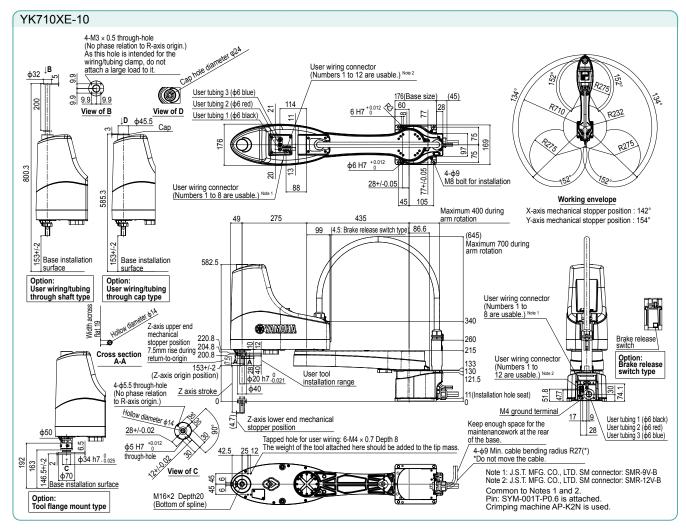
Note 1. This is the value at a constant ambient temperature. (X,Y axes)

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.



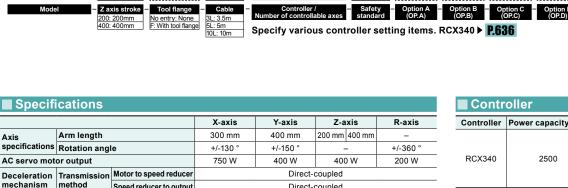
YK700XG

Arm length 700mm Maximum payload 20kg

Ordering method

YK700XG

RCX340-4



Deceleration Transmission Motor to speed reduce mechanism method Speed reducer to output Direct-coupled Repeatability +/-0.02 mm +/-0.01 mm +/-0.004° Maximum speed 8.4 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 0.42 sec R-axis tolerable moment of inertia Note 3 1.0 kgm² 0.2 sq × 20 wires User tubing (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 m, 10 m Weight Z axis 200 mm: 50 kg $\,$ Z axis 400 mm: 52 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.

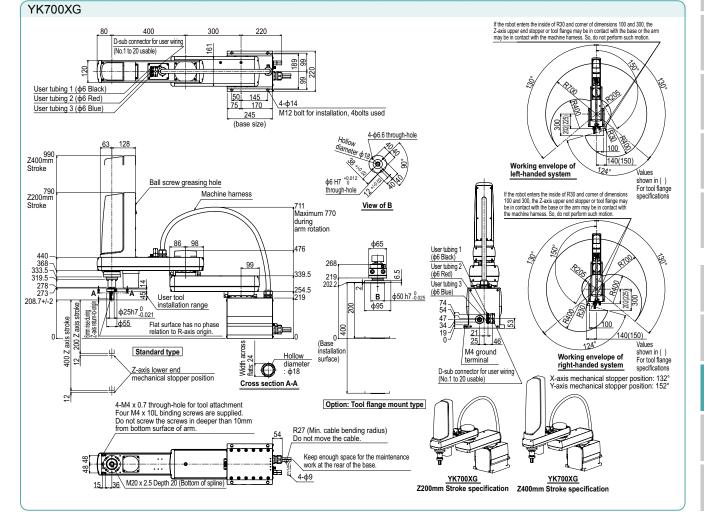
■ Controller							
Controller	Power capacity (VA)	Operation method					
RCX340	2500	Programming / I/O point trace / Remote command / Operation using RS-232C communication					

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 No entry: None F: With tool flange

RCX340-4 Cable

Safety – Option A – Option B – standard (OP.A) (OP.B)

3L: 3.5m Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifications							
			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 moto	or output		750 W	400 W	400 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Direct-o	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 1.7 m/sec 92		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 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: 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

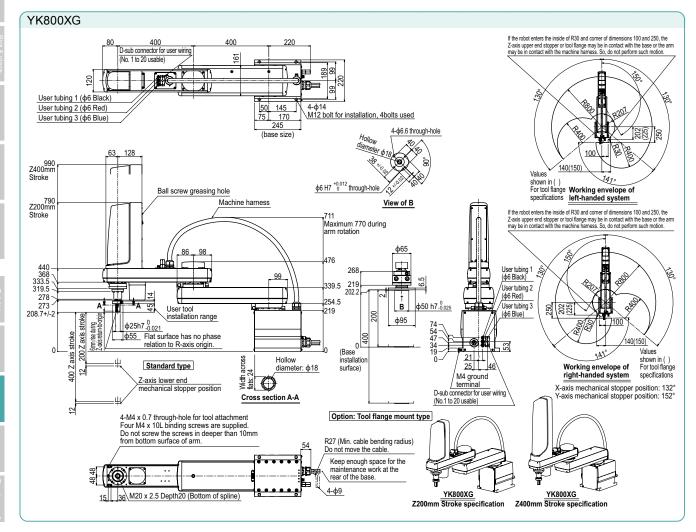
Note. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (option). Refer to the user's manual (installation manual) for more details.

> 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.



YK900XG

Arm length 900mm Maximum payload 20kg ■ Ordering method

YK900XG

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

Tool flange Cable 3L: 3.5m 5L: 5m 10L: 10m

RCX340-4

Specify various controller setting items. RCX340 ▶ P.636

■ 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 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 spe	ed		9.9 m/sec 2.3 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 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 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				

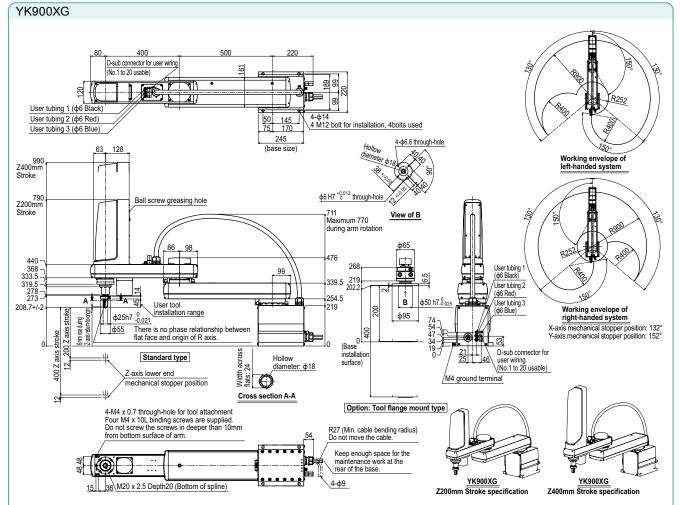
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

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

Arm length 1000mm
Maximum payload 20kg

Standard type: Large type

Ordering method

YK1000XG

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

Tool flange Cable 3L: 3.5m

RCX340-4

Safety - Option A - Option B - standard (OP.A) (OP.B)

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifications							
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		600 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			+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		10.6 m/sec 2.3 m/sec 1.7 m/sec 92		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 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.

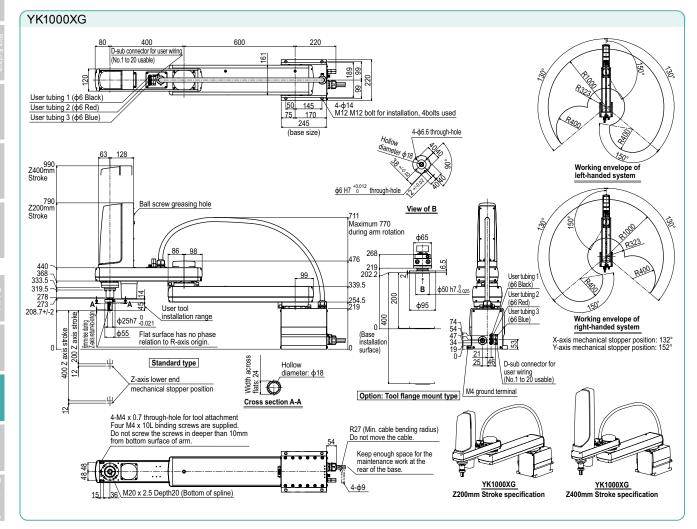
Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

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

Programming / I/O point trace / Remote command / Operation

using RS-232C communication

■ Ordering method

YK1200X - 400 Model – Z axis stroke

RCX340-4 Cable 3L: 3.5m 5L: 5m 10L: 10m

Specify various controller setting items. RCX340 ▶ **P.636**

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		600 mm	600 mm	400 mm	-	
specifications	Rotation ang	le	+/-125 °	+/-150 °	-	+/-180 °	
AC servo mot	or output		900 W	800 W	600 W	400 W	
Deceleration Transmission		Motor to speed reducer	Direct-coupled		Timing belt transmission	Timing belt transmission	
mechanism	method	Speed reducer to output	Direct-	Direct-coupled		Direct-coupled	
Repeatability	Repeatability Note 1		+/-0.05 mm		+/-0.02 mm	+/-0.005 °	
Maximum spe	Maximum speed		7.4 m/sec		0.75 m/sec	600 °/sec	
Maximum pay	load		50 kg				
Standard cycl	e time: with 2k	g payload Note 2		0.91	sec		
R-axis tolerab	le 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				

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.

Controller Power capacity (VA) Operation method

2500

■ Controller

RCX340

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.

YK1200X	
User tubing 3 (\$\phi 6\$ Blue)	Aux. shaft fixing plate 40 (Use when tightening the lower M16 screw) Spline shaft (Hollow) Hollow diameter: \$\phi 12\$ \[\frac{0.01}{425} \frac{0.01}{0.02} \] M16 x 2 Depth25 Working envelope Working envelope
Ball screw greasing hole 2 x 2-M4 x 0.7 Depth 10 (Same on opposite side) 381+/-2 M16 x 2 Depth 25	X and Y axes mechanical stopper positions 542.3 R35 (Min. cable bending radius) Do not move the cable. M4 ground terminal User tubing 1 (\$\phi 6\$ Black) User tubing 2 (\$\phi 6\$ Red) User tubing 3 (\$\phi 6\$ Blue) User tubing 3 (\$\phi 6\$ Blue) No. 1 to 20 usable) Keep enough space for the maintenance work at the rear of the base.

YK1200XG

Arm length 1200mm
Maximum payload 50kg

■ Ordering method

YK1200XG-400

Z axis stroke

Tool flange User Wiring No entry: None F: With tool No entry: None UW: User

Cable

RCX341-4

Standard type: Large type

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifi	■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length			600 mm	600 mm	400 mm	-	
specifications	Rotation angl	е	+/-130 °	+/-150 °	+/-360 °	+/-360 °	
AC servo motor output			950 W	400 W	750 W	400 W	
Deceleration	Transmission	Motor to speed reducer		Direct-o	coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability Note 1			+/-0.05 mm		+/-0.02 mm	+/-0.005 °	
Maximum spe	ed		7.7 m/sec 1.6 m/sec 600 °			600 °/sec	
Maximum pay	load		50 kg				
Standard cycle	e time: with 5k	g payload ^{Note 2}		0.61	sec		
R-axis tolerab	le moment of	inertia ^{Note 3}	2.45 kgm ²				
User wiring			0.2 sq × 12 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			96 kg				

■ Controller Controller | Power capacity (VA) | Operation method Programming / I/O point trace Remote command / RCX341 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.

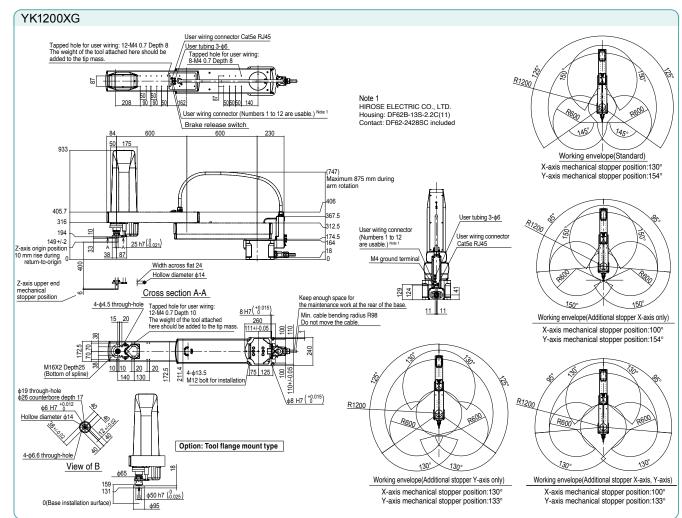
> Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

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. User wiring stays (optional) are parts required for additional installation of user wiring. Installation on the robot must be performed by the customer.



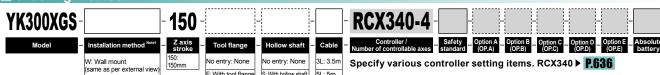
YK300XGS

U: Inverse wall mount (upside down)

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

Wall mount / inverse type

Ordering method



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

			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		150 mm	150 mm	150 mm	-	
specifications	Rotation ang	le	+/-120 °	+/-130 °	-	+/-360 °	
AC servo mot	or output		200 W	150 W	50 W	100 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output		Dir	ect-coupled		
Repeatability Note 1			+/-0.0	11 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 pay	load		5 kg (Standard specification), 4 kg (Option specifications Note 4)				
Standard cycl	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 (0	Outer diameter	r)	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				

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).

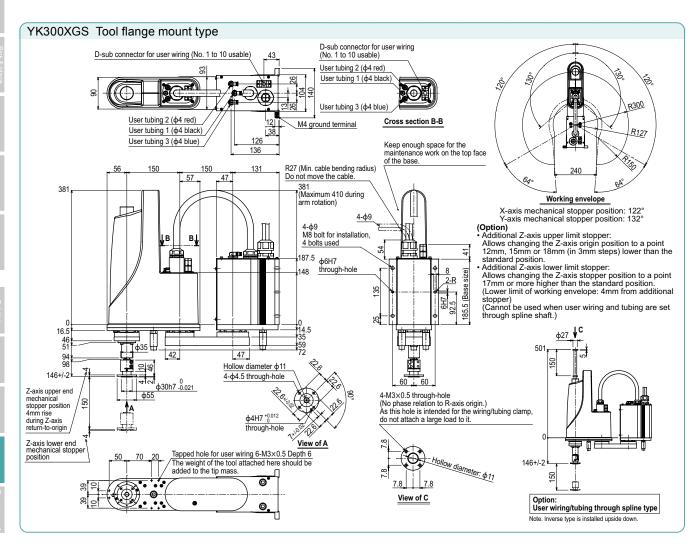
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

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

■ 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 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/



YK400XGS

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

Wall mount / inverse type

Ordering method

YK400XGS RCX340-4 150

W: Wall mount same as per external v LI: Inverse wall mount 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.636**

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		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	Repeatability Note 1)1 mm	+/-0.01 mm	+/-0.004 °
	Maximum speed		6.1 m/sec 1.1 m/s		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	

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.

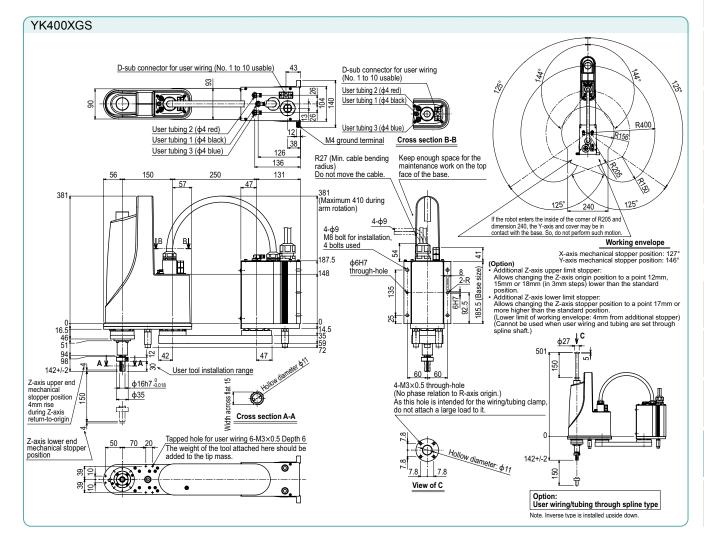
Note 4. Maximum payload of option specifications (with tool flange attached or with user wiring and tubing routed through spline shaft) is 4kg.

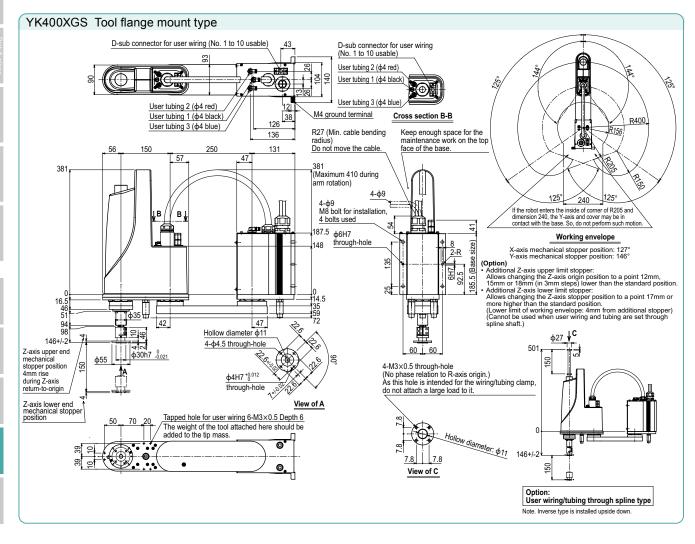
■ Controller						
Controller	Power capacity (VA)	Operation method				
RCX340	1000	Programming / I/O point trace / Remote command / Operation using RS-232C communication				

Note. The movement range can be limited by changing the position of The investment range can be initiated by carriaging 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/

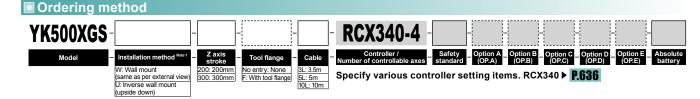




YK500XGS Arm length 500mm
Maximum payload 10kg

10 32

M16 x 2 Depth20 (Bottom of spline)



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		200 mm	300 mm	200 mm 300 mm	-	
specifications	Rotation angl	е	+/-105 °	+/-125 °	_	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Di	rect-coupled		
mechanism	method	Speed reducer to output		Di	rect-coupled		
Repeatability	Note 1		+/-0.0	11 mm	+/-0.01 mm	+/-0.004 °	
Maximum spe	ed		7.6 m/sec 2.3 n/sec 1700 °/sec (wall mount) m/sec 800 °/sec (inverse wall mount)				
Maximum pay	load		10 kg (Standard type), 9 kg (Tool flange mount type)				
Standard cycle	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 (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			30 kg				

■ 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/

YK500XGS	other tubes and cables to the self-supporting machine harness.
User tubing 1 (\phi 6 Black) User tubing 2 (\phi 6 Red) User tubing 3 (\phi 6 Blue) 54 113 Z300mm 474 Sheka	D-sub connector for user wiring (No.1 to 20 usable) D-sub connector for user wiring (No.1 to 20 usable) D-sub connector for user wiring (No.1 to 20 usable) D-sub connector for user wiring (No.1 to 20 usable) Waser wiring (No.1 to 20 usable) User tubing 1 (\$\delta\$ Black) User tubing 2 (\$\delta\$ Red) User tubing 3 (\$\delta\$ Bled) User tubing 3 (\$\delta\$ Bled) Weep enough space for the maintenance work on the top face of the base.
Z200mm 374 Stroke	Ball screw greasing hole (406: Maximum during arm rotation) 89.5 R27 (Min. cable bending radius) Do not move the cable. 4-69 Working envelope of left-handed system (5-0,11) M10 bolt for installation Installation R24 (806: Maximum during arm rotation) 89.5 Working envelope of left-handed system (5-0,11) M10 bolt for installation Installation Working envelope of right-handed system Working envelope of right-handed system X-axis mechanical stopper position: 107° Y-axis mechanical stopper position: 127° Standard type
position 8mm rise puring Z-axis eturn-to-origin 8 Flat relat Z-axis mechan 4-M4 x Four M Do not from bo	Standard type Surface has no phase ion to R-axis origin. Ower end nical stopper position 1.7 through-hole for tool attachment 4 x 10L binding screws are supplied. screw the screws in deeper than 10mm tom surface of arm. Sign of fit tool attached here should be on the tip mass. Option: Tool flange mount type

YK500XGS

Z200mm Stroke specification Z300mm Stroke specification

YK500XGS

YK600XGS

Wall mount / inverse type

Arm length 600mm
Maximum payload 10kg

■ Ordering method

RCX340-4 YK600XGS Safety Option A Option B Option C Option D Option E Absolute standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) battery

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

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

Specify various controller setting items. RCX340 ▶ P.636

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.

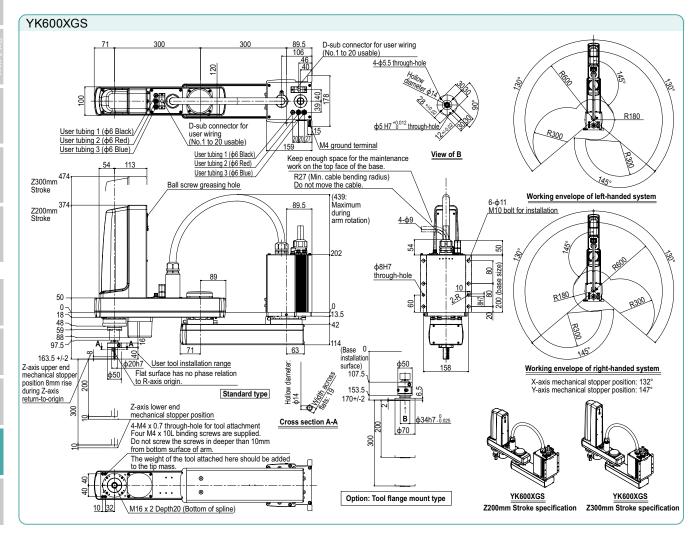
■ Specifi	■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis	
Axis Arm length		300 mm	300 mm	200 mm 300 mm	-		
specifications	Rotation ang	le	+/-130 °	+/-145 °	_	+/-360 °	
AC servo mot	or output		400 W	200 W	200 W	200 W	
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled		
mechanism	method	Speed reducer to output	Direct-coupled				
Repeatability Note 1			+/-0.01 mm +/-0.04			+/-0.004 °	
Maximum speed			8.4 m/sec 2.3 1.7 1700 °/sec (v m/sec m/sec 800 °/sec (inver		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	0.46 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			31 kg				
			, ,				

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.

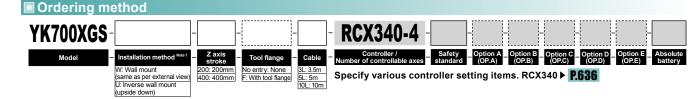
> Our robot manuals (installation manuals) can be downloaded from our website at the address below: https://global.yamaha-motor.com/business/robot/

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 20kg



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.

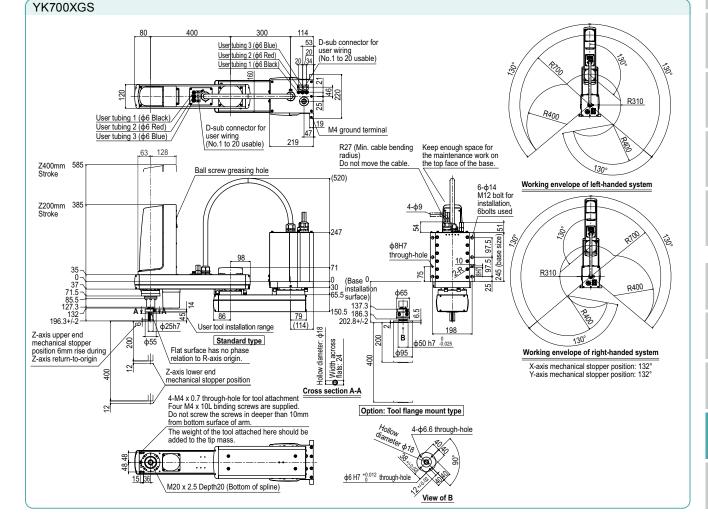
			X-axis	Y-axis	Z-axis	R-axis			
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	-			
specifications	Rotation angle		+/-130 °	+/-130 °	_	+/-360 °			
AC servo mot	or output		750 W	400 W	400 W	200 W			
Deceleration	Transmission	Motor to speed reducer		Di	rect-coupled				
mechanism	method	Speed reducer to output		Di	rect-coupled	ect-coupled			
Repeatability	Note 1		+/-0.0	12 mm	+/-0.01 mm	+/-0.004 °			
Maximum spe	ed		8.4 m/sec 2.3 1.7 920 ° m/sec m/sec 480 °/s			920 °/sec (wall mount) 480 °/sec (inverse wall mount			
Maximum pay	load		20 kg (S	20 kg (Standard type), 19 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}			1.0 kgm ²				
User wiring				0.2	sq × 20 wires				
User tubing (0	Outer diameter	•)			ф 6 × 3				
Travel limit			1.Sc	ft limit 2.Med	chanical stoppe	r (X,Y,Z axis)			
Robot cable le	ength			Standard: 3.	5 m Option: 5 r	m, 10 m			
Weight			Z axis 200 mm: 50 kg Z axis 400 mm: 52 kg			0 mm: 52 kg			
Note 2. When reci Note 3. The accele	procating 300mm eration coefficient	nt ambient temperature. (X,Y in horizontal and 25mm in ve is set automatically in accor	ertical directions. dance with the tip	weight and R-a	xis moment of iner	tia settings.			

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

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
Note 1. This is the value at a constant ambient temperature. (X, Note 2. When reciprocating 300mm in horizontal and 25mm in v Note 3. The acceleration coefficient is set automatically in accordote. Please consult YAMAHA when connecting other tubes an	ertical directions. dance with the tip weight and R-axis moment of inertia settings.



YK800XGS

Wall mount / inverse type

Arm length 800mm
Maximum payload 20kg

■ Ordering method

RCX340-4 YK800XGS Safety Option A Option B Option C Option D Option E Abso standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batte W: Wall mount (same as per external view) U: Inverse wall mount (upside down) 200: 200mm No entry: None F: With tool flange Specify various controller setting items. RCX340 ▶ **P.636**

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		400 mm	400 mm	200 mm 400 mm	-		
specifications	Rotation ang	le	+/-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		Dir	ect-coupled	t-coupled		
Repeatability	Note 1		+/-0.0	12 mm	+/-0.01 mm	+/-0.004 °		
Maximum spe	ed		9.2 m/sec 2.3 1.7 920 °/sec (wall 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 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 (0	Outer diameter	r)			ф6×3			
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 constar	at ambient temperature (XX	/ avaa\					

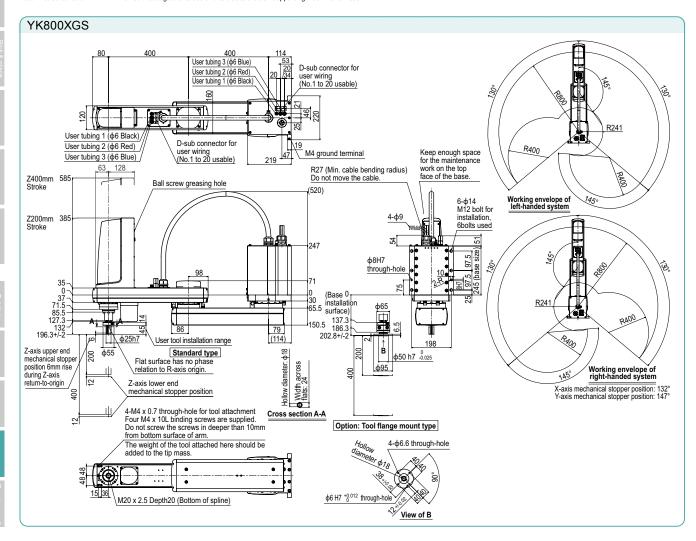
Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 2500 Operation using RS-232C communication

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.

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

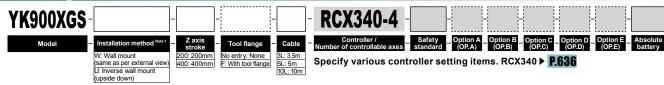
Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. When reciprocating 300mm in horizontal and 25mm in vertical directions.
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.
Note. Please consult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



Arm length 900mm Maximum payload 20kg

YK900XGS

■ 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 Incorrect installation can cause trouble or malfunction.

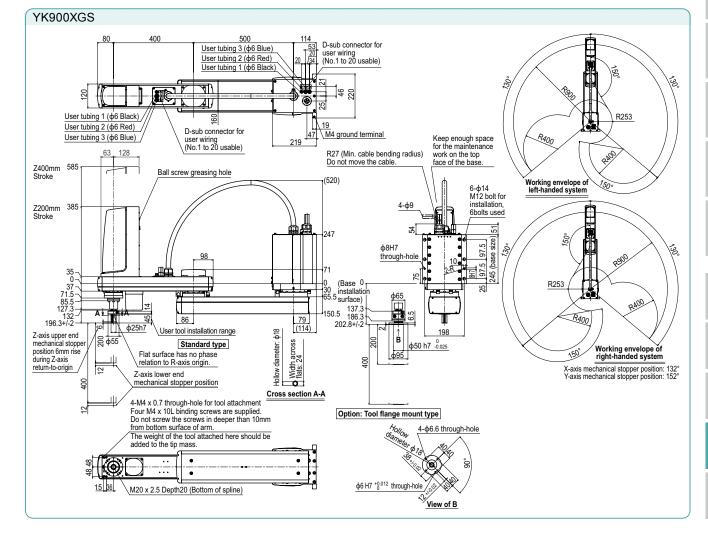
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		500 mm	400 mm	200 mm 400 mm	-
specifications	Rotation angl	е	+/-130 °	+/-150 °	-	+/-360 °
AC servo mot	or output		750 W	400 W	400 W	200 W
Deceleration	Transmission	Motor to speed reducer		Dir	ect-coupled	
mechanism	method	Speed reducer to output		Dir	ect-coupled	
Repeatability	Note 1		+/-0.02 mm		+/-0.01 mm	+/-0.004 °
Maximum spe	ed		9.9 n	n/sec	2.3 1.7 m/sec m/sec	920 °/sec (wall mount 480 °/sec (inverse wall moun
Maximum pay	load		20 kg (S	Standard type),	19 kg (Tool fla	nge 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)			ф6×3	
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			r (X,Y,Z axis)
Robot cable le	ength		Standard: 3.5 m Option: 5 m, 10 m			m, 10 m
Weight	yht Z axis 200 mm:			xis 200 mm: 54	kg Zaxis 40	0 mm: 56 kg

■ 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

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

Weight	Z axis 200 mm: 54 kg Z axis 400 mm: 56
Note 1. This is the value at a constant ambient temperature. (X,	
Note 2. When reciprocating 300mm in horizontal and 25mm in vi	
Note 3. The acceleration coefficient is set automatically in accor	dance with the tip weight and R-axis moment of inertia settings.
Niete Dieses sessuit VANALIAbes sessestine ether tubes en	d aablaa ta tha aa'lf aaaatiaa maaabiaa baasaaa



YK1000XGS

Wall mount / inverse type

Arm length 1000mm
Maximum payload 20kg

■ Ordering method

YK1000XGS RCX340-4 Safety Standard Option A Option B Option C Option D Option E Absolute (OP.A) OP.B) Option C OP.C) OP.D) Option E Option E Option E Option E OP.E)

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

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

Specify various controller setting items. RCX340 ▶ **P.636**

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	■ Specifications							
			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		+/-0.0)2 mm	+/-0.01 mm	+/-0.004 °		
Maximum spe	ed		10.6 m/sec 2.3 n/sec 1.7 920 °/sec (wal 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 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	ibing (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: 56 kg Z axis 400 mm: 58 kg					
			, ,					

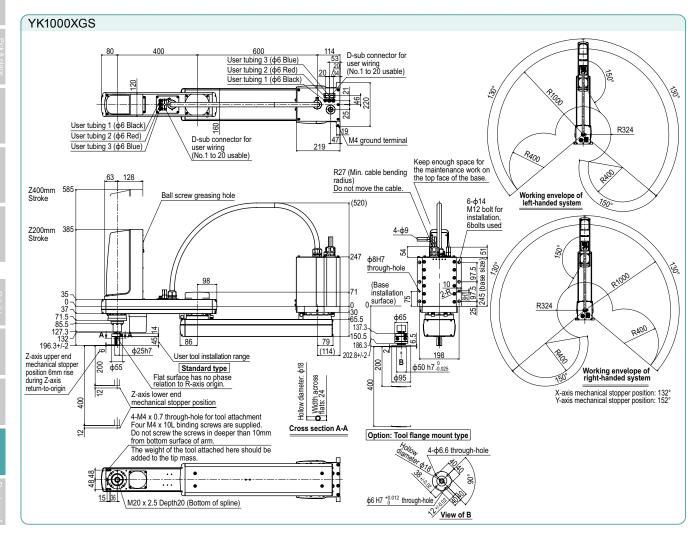
Controller Controller Power capacity (VA) Operation method Programming / I/O point trace Remote command / RCX340 2500 Operation using RS-232C communication

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/

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

YK250XGP Arm length 250mm Maximum payload 4kg

■ Controller

■ Ordering method										Ĩ	
YK250XGP-150	-	- S	-	- RCX340-4	-	-	-		-		_
Model Z axis stroke	Tool flange	- Hollow shaft	- Cable	Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	_ Absolute battery
150: 150mm	No entry: None F: With tool flange	S: With hollow shaft	3L: 3.5m 5L: 5m	Specify various cont	roller set	ting iten	ns. RCX	340 ▶ 🏿	636		

■ Specifications X-axis Y-axis Z-axis R-axis Arm length 100 mm 150 mm 150 mm specifications Rotation angle +/-129 +/-134 ° +/-360 ' 200 W 150 W 50 W 100 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° 4.5 m/sec 1020 °/sec Maximum speed 1.1 m/sec Maximum payload 4 kg Standard cycle time: with 2kg payload Note 2 0.50 sec R-axis tolerable moment of inertia Note 3 0.05 kgm Protection class Note 4 Equivalent to IP65 (IEC 60529) User wiring 0.2 sg × 10 wires 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 21.5 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.)

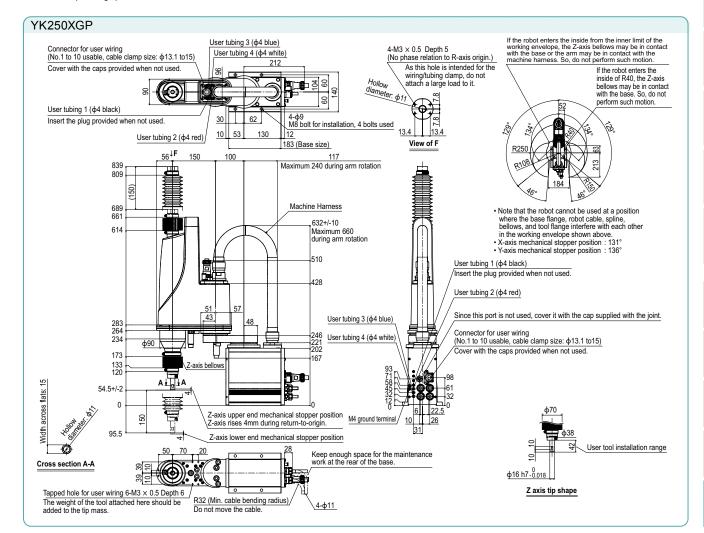
See our robot manuals (installation manuals) for detailed

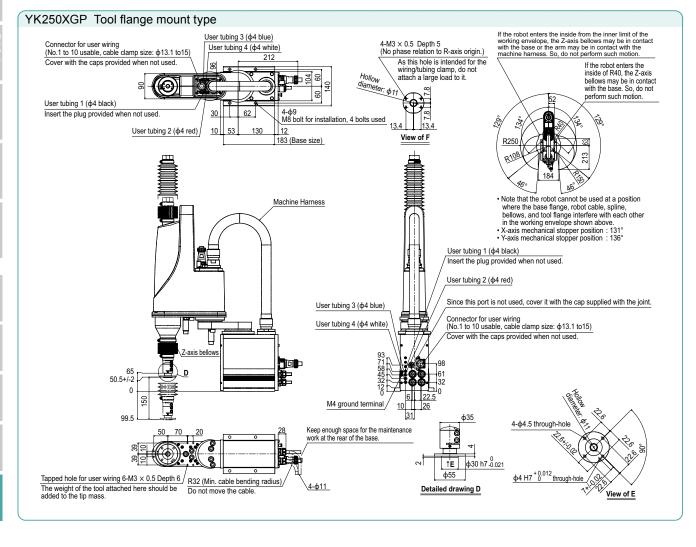
See our hoot manuals (installation manuals) for detailed information.

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 350mm Maximum payload 4kg

YK350XGP

Ordering method

YK350XGP-150

No entry: None F: With tool flange

S

RCX340-4

Safety Option A Option B Option C Option D Option E Absaxes standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) batt Specify various controller setting items. RCX340 ▶ P.636

Controller

■ 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 motor 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		5.6 m/sec 1.1 m/sec 1020 °/se				
Maximum pay	load		4 kg				
Standard cycl	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	ISS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring			0.2 sq × 10 wires				
User tubing (C	Outer diameter	r)	φ4×4				
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	ka		

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.

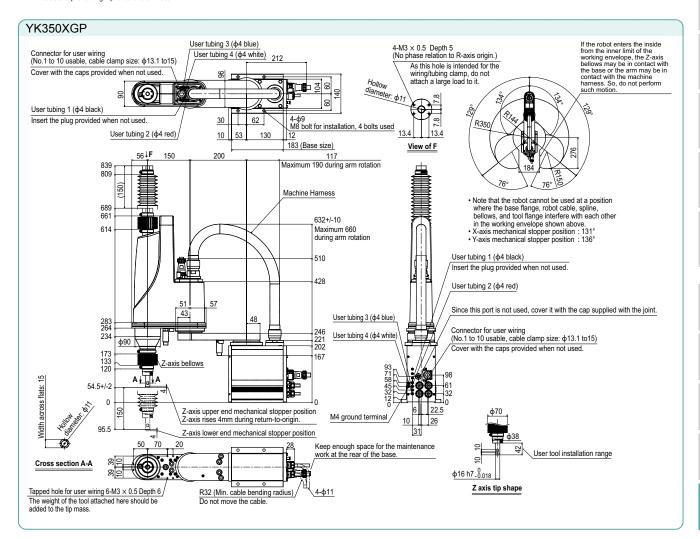
Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

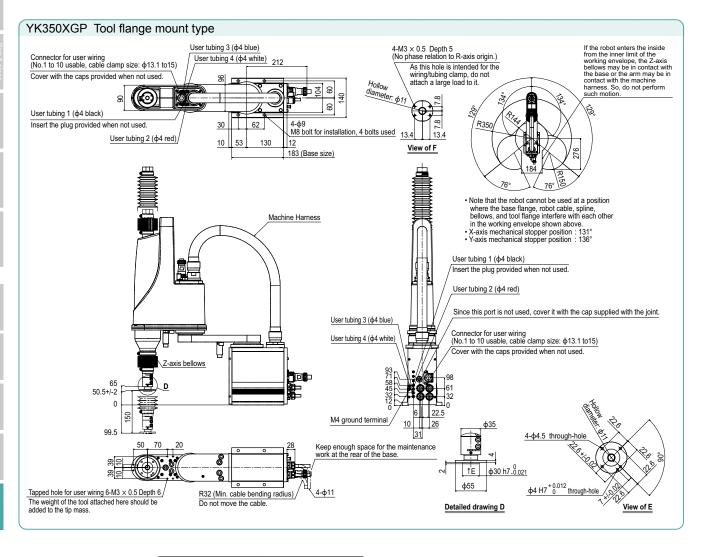
Note 1. This is the value at a constant ambient temperature. (X,Y axes)

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.





Arm length 400mm
Maximum payload 4kg

■ Ordering method

RCX340-4 YK400XGP-150 S Controller / Safety ber of controllable axes standard COP.A) Option A (OP.A) Option B (OP.B) Option C (OP.B) Option C (OP.C) Option D (OP.E) batt

No entry: None F: With tool flange

■ Controller

RCX340

Specify various controller setting items. RCX340 ▶ **P.636**

Controller Power capacity (VA) Operation method

1000

Programming / I/O point trace / Remote command /

Operation using RS-232C communication

Specifi	cations							
			X-axis	Y-axis	Z-axis	R-axis		
Axis	Arm length		250 mm	150 mm	150 mm	-		
specifications	Rotation angle		+/-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		+/-0.0	1 mm	+/-0.01 mm	+/-0.004 °		
Maximum spe	ed		6.1 m/sec 1.1 m/sec 1020 °					
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 (C	Outer diameter	r)	ф 4 × 4					
Travel limit			1.Soft	limit 2.Mechani	cal stopper (X,Y,	Z axis)		
Robot cable length			Standard: 3.5 m Option: 5 m, 10 m					
Weight			22.5 kg					

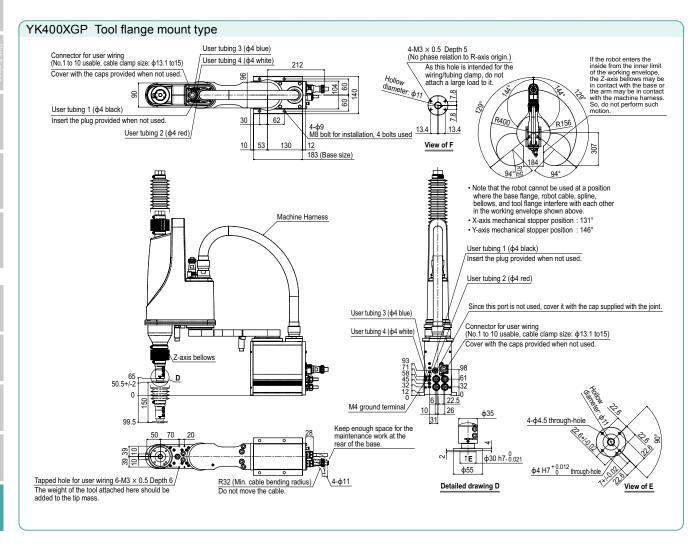
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)
See our robot manuals (installation manuals) for detailed information.

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 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
Connector for user wiring (No.1 to 10 usable, cable clamp size: \$\phi13.1\$ to 15) Cover with the caps provided when not used. User tubing 1 (\$\phi4\$ black) Insert the plug provided when not used. User tubing 2 (\$\phi4\$ red) User tubing 2 (\$\phi4\$ red)
Maximum 190 during arm rotation 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: 146° User tubing 1 (\$\phi\$ black) Insert the plug provided when not used. User tubing 2 (\$\phi\$4 red)
Since this port is not used, cover it with the cap supplied with the joint. User tubing 3 (\$\phi\$4 blue) User tubing 3 (\$\phi\$4 blue) User tubing 4 (\$\phi\$4 white) Connector for user wiring (No.1 to 10 usable, cable clamp size: \$\phi\$13.1 to 15) Cover with the caps provided when not used.
Z-axis lower end mechanical stopper position Cross section A-A Tapped hole for user wiring 6-M3 × 0.5 Depth 6 The weight of the tool attached here should be added to the tip mass. Z-axis lower end mechanical stopper position Keep enough space for the maintenance work at the rear of the base. 4-4-11 Z axis tip shape Z axis tip shape



Arm length 500mm Maximum payload 4kg

YK500XGLP

Ordering method

S RCX340-4 YK500XGLP - 150

No entry: None F: With tool flange

Safety Option A Option B Option C Option D Option E Absaxes standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) bat Specify various controller setting items. RCX340 ▶ P.636

■ Controller

■ 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		
	method	Speed reducer to output	Direct-coupled				
Repeatability	Repeatability Note 1			+/-0.01 mm +		+/-0.004 °	
Maximum spe	ed		5.1 m/sec 1.1 m/sec 1020 °/s			1020 °/sec	
Maximum pay	load		4 kg				
Standard cycle	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 (C	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		

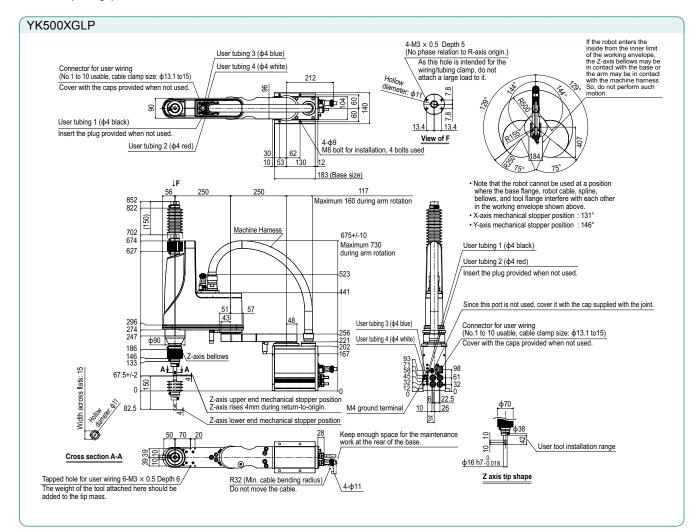
Controller Power capacity (VA) Operation method Programming / I/O point trace / Remote command / RCX340 1000 Operation using RS-232C communication

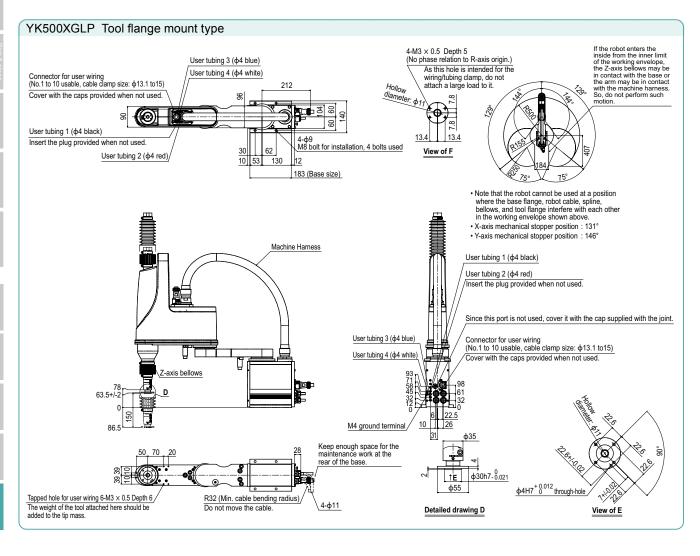
Note. The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.) See our robot manuals (installation manuals) for detailed information

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.





Arm length 500mm Maximum payload 10kg

YK500XGP

Ordering method



■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		200 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-co		coupled	
Repeatability Note 1			+/-0.01 mm		+/-0.01 mm	+/-0.004 °
Maximum speed			7.6 m/sec 2.3 m/sec 1.7 m/sec		1700 °/sec	
Maximum pay	load		10 kg			
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.55 sec			
R-axis tolerab	le moment of	inertia ^{Note 3}	0.3 kgm²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
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: 32 kg Z axis 300 mm: 33 kg			

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/

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 user pobts where the bellows section is directly exposed to water jet. Contact our distributor for information on drip-proof structure preventing liquid other than water.

YK500XGP Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi16\$ to18) Cover with the caps provided when not used. 120 R178 User tubing 1 (φ6 black) 40 120 User tubing 2 (φ6 red) M10 bolt for installation, 4 bolts used - User tubing 3 (Φ6 blue) 222 (Base size) Note. Insert the plug provided when not used. If the robot enters the inside of the corner of dimensions 135 and 292, 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. 300 176 53 114 151(Maximum 300 during arm rotation) Z300mm 785 Stroke Working envelope of left-handed system Z200mm 685 Stroke (Maximum 760 during arm rotation) 479 R178 Connector for user wiring 373 351 (No.1 to 20 usable, cable clamp size: \$\phi\$16 to 18) 81 283 245 φ38 (Air release tubing) 259 Cover with the caps provided Connect a hose and extend it to a location not exposed to water and dust. 187 when not used 71 91 159 117.6+/-2 18 X axis joint air purge port (φ6) Z-axis stroke
Z-axis rises
8mm during
retum-to-origin. φ72 h7 Y axis joint air purge port (φ6) M4 ground terminal 0 If the robot enters the inside of the corner of dimensions 135 and 292, the Z-axis tip flange may be in contact with the base or the arm may be in contact with the harmess. So, do not perform such motion. -axis User tubing 1 (φ6 black) 300 Z 200 Z 10 40 User tubing 2 (\$\phi6\$ red) User tubing 3 (\$\phi6\$ blue) Insert the plug provided when not used. Working envelope of right-handed system Z-axis lower end mechanical stopper position φ25 H7 0 · 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 φ72 h7 -0.03 28 the maintenance work at the rear of the base X-axis mechanical stopper position: 132° P.C.D.36 Y-axis mechanical stopper position: 147° 6-M5×0.8 Depth 11 \4-ф11 R32 (Min. cable bending radius) 10-M5×0.8 Depth 11 Do not move the cable There is no phase relation between each position of M5 tapped holes and R-axis origin position.

Z axis tip shape

YK600XGLP

Dust-proof & drip-proof type

Arm length 600mm
Maximum payload 4kg

Ordering method

YK600XGLP-150

No entry: None F: With tool flange

S

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

■ Controller

Specify various controller setting items. RCX340 ▶ **P.636**

■ Specifi	cations					
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		350 mm	250 mm	150 mm	_
specifications	Rotation ang	le	+/-129 °	+/-144 °	-	+/-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		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		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 (C	Outer diameter	r)		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			26 kg			

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

Controller | Power capacity (VA) | Operation method

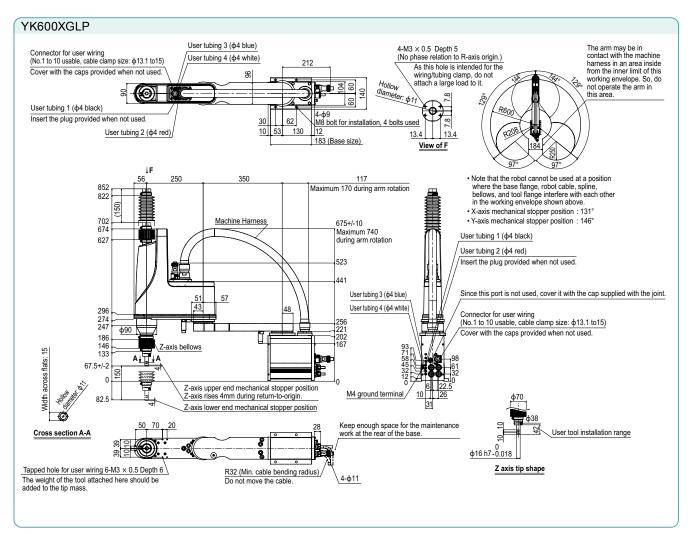
Note. The movement range can be limited by changing the positions The movement range can be limited by changing the positions of X and Y axis mechanical stoppers. (The movement range is set to the maximum at the time of shipment.)

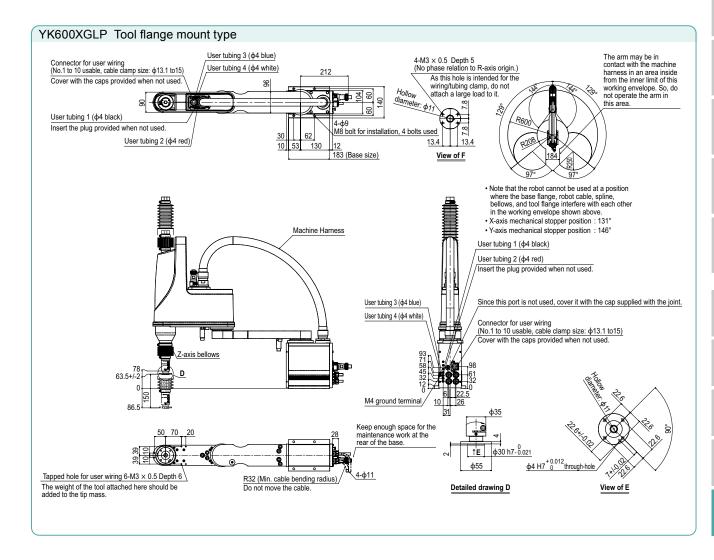
See our robot manuals (installation manuals) for detailed information.

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.





YK600XG

Dust-proof & drip-proof type

Arm length 600mm
Maximum payload 10kg

■ Ordering method

YK600XGP RCX340-4 Safety Option A Option B Option C Option D Option E Absorbandard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) battr 200: 200mm 300: 300mm

Specify various controller setting items. RCX340 ▶ P.636

			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	AC servo motor 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 m/sec 170			1700 °/sec	
Maximum pay	load		10 kg				
Standard cycle	e time: with 2k	g payload Note 2	0.56 sec				
R-axis tolerab	le moment of	inertia Note 3	0.3 kgm²				
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)				
User wiring (s	q × wires)		0.2 × 20				
User tubing (C	Outer diamete	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: 33 kg Z axis 300 mm: 34 kg				

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

Controller | Power capacity (VA) | Operation method

1700

Programming / I/O point trace Remote command /

Operation using RS-232C communication

■ Controller

RCX340

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.

YK600XGP Connector for user wiring (No.1 to 20 usable, cable clamp size: \$\phi16\$ to18) 250 Cover with the caps provided when not used. R180 M User tubing 1 (Φ6 black). 40 120 4-φ11 M10 bolt for installation, 4 bolts used User tubing 2 (\$\phi6\$ red) User tubing 3 (\$\phi 6 blue)/ 222 (Base size Note. Insert the plug provided when not used. 135 If the robot enters the inside of the corner of dimensions 135 and 292, 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. 300 300 176 151(Maximum 300 during arm rotation) 53 114 Working envelope of left-handed system Z300mm 785 Stroke Z200mm Stroke (Maximum 760 during arm rotation) (B) 479 Connector for user wiring (No.1 to 20 usable, cable clamp size: φ16 to18) 373 351 φ38 (Air release tubing) 81 Connect a hose and extend it to a location not exposed to water and dust. Cover with the caps pro 259 187 159 when not used X axis joint air purge port (φ6) 117.6+/-2 300 Z-axis stroke 200 Z-axis stroke ф72 h7 Z-axis stroke
Z-axis rises
8mm during
return-to-origin. Y axis joint air purge port (φ6) 0 M4 ground terminal If the robot enters the inside of the corner of dimension 135 and 292, 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. User tubing 1 (φ6 black) 2 4 User tubing 2 (\$\phi6\$ red) Insert the plug provided when not used. User tubing 3 (\$\phi6\$ blue) Z-axis lower end mechanical Working envelope of right-handed system stopper position 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 Keep enough space for the maintenance work at the rear of the base. φ72 h7 -0.03 • X-axis mechanical stopper position: 132° Y-axis mechanical stopper position: 147° P.C.D.36 4-φ11 R32 (Min. cable bending radius) 6-M5×0.8 Depth 11 10-M5×0.8 Depth 11 *There is no phase relation between each position of M5 tapped holes

Z axis tip shape

*There is no phase relation between each position of M5 tapped holes

and R-axis origin position.

■ Controller

Arm length 600mm Maximum payload 20kg

YK600XGHI

■ Ordering method

RCX340-4 YK600XGHP Safety Option A Option B Option C Option D Option E Abs axes standard (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) bat 200: 200mm 400: 400mm Specify various controller setting items. RCX340 ▶ P.636

			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 Transmissio		Motor to speed reducer	Direct-coupled			
mechanism	method	Speed reducer to output	Direct-coupled			
Repeatability	Repeatability Note 1			+/-0.02 mm		+/-0.004 °
Maximum spe	ed		7.7 m/sec 2.3 m/sec 1.7 m/sec 92			920 °/sec
Maximum pay	load		20 kg			
Standard cycle	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 I	P65 (IEC 60529)	
User wiring (s	r wiring (sq × wires)			0.2	× 20	
User tubing (C	uter 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			

Programming / I/O point trace / Remote command / RCX340 2500 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

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.

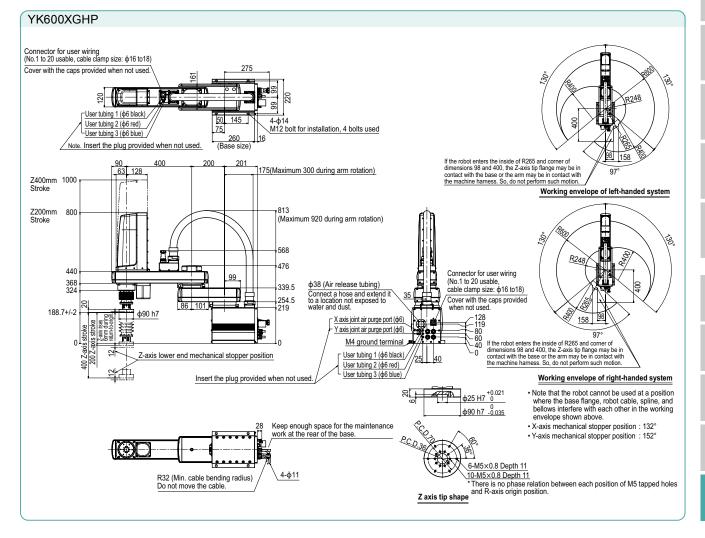
Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

- 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.



YK700XG

Dust-proof & drip-proof type

Arm length 700mm
Maximum payload 20kg

■ Ordering method

YK700XGP

RCX340-4

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

■ Controller

RCX340

Controller | Power capacity (VA) | Operation method

2500

Programming / I/O point trace Remote command /

Operation using RS-232C communication

Specify various controller setting items. RCX340 ▶ P.636

Specifi	cations						
			X-axis	Y-axis	Z-axis	R-axis	
Axis	Arm length		300 mm	400 mm	200 mm 400 mm	_	
specifications	Rotation angl	le	+/-130 °	+/-150 °	-	+/-360 °	
AC servo moto	or output		750 W	400 W	400 W	200 W	
Deceleration				Direct-	coupled		
mechanism			Direct-coupled				
Repeatability Note 1			+/-0.02 mm		+/-0.01 mm	+/-0.004 °	
Maximum speed			8.4 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec	
Maximum pay	load		20 kg				
Standard cycle	e time: with 2k	g payload Note 2	0.52 sec				
R-axis tolerab	le 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 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. 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.

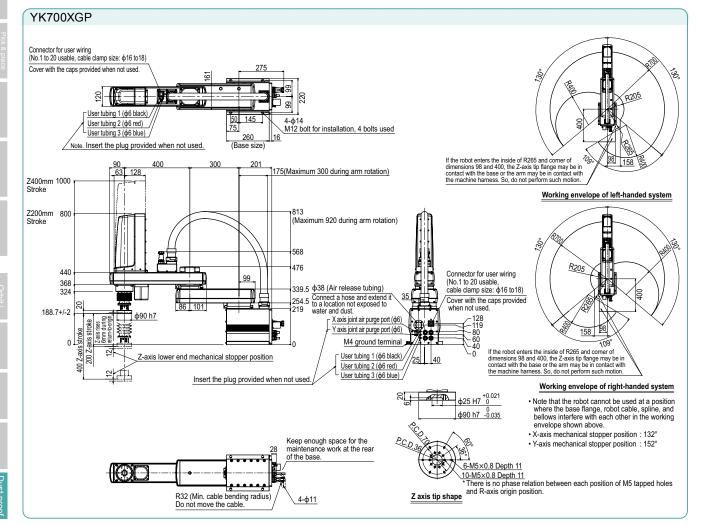
> Our robot manuals (installation manuals) can be downloaded from our website at the address below https://global.yamaha-motor.com/business/robot/

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

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

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

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.



YK800XGP

■ Ordering method

Arm length 800mm
Maximum payload 20kg

YK800XGP		- F	_	- RCX340-4
Model	Z axis stroke	Tool flange	- Cable	Controller / Safety Standard (OP.A) Option A (OP.B) Option C (OP.C) Option D Option C (OP.C) (OP.C) Option D Option E Option C (OP.C) OP.C)
	200: 200mm 400: 400mm	F: With tool flange	3L: 3.5m 5L: 5m 10L: 10m	Specify various controller setting items. RCX340 ▶ P.636

■ 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				
	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 °/sec		
Maximum pay	load		20 kg				
Standard cycle	e time: with 2k	g payload ^{Note 2}	0.58 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				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: 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.

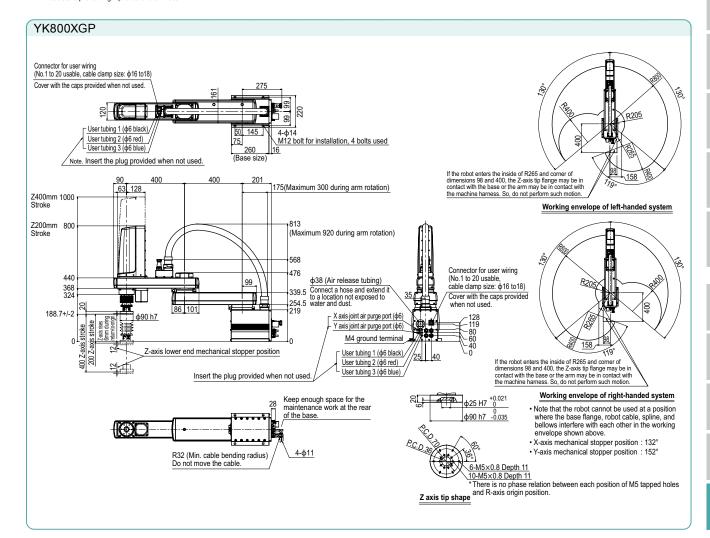
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Note 1. This is the value at a constant ambient temperature. (X,Y axes)

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.



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YK900XG

Dust-proof & drip-proof type

Arm length 900mm
Maximum payload 20kg

■ Ordering method

YK900XGP RCX340-4 Specify various controller setting items. RCX340 ▶ **P.636**

			Y-axis	Z-axis	R-axis	
Arm length		500 mm	400 mm	200 mm 400 mm	-	
Rotation ang	le	+/-130 °	+/-150 °	_	+/-360 °	
or 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		+/-0.004 °	
Maximum speed			9.9 m/sec		920 °/sec	
load		20 kg				
time: with 2k	g payload Note 2	0.59 sec				
le moment of	inertia Note 3	1.0 kgm²				
SS Note 4		Equivalent to IP65 (IEC 60529)				
q × wires)		0.2 × 20				
uter diameter	r)	ф 6 × 3				
Travel limit			1.Soft limit 2.Mechanical stopper (X,Y,Z axis)			
ngth		Standard: 3.5 m Option: 5 m, 10 m				
		Z axis 200 mm: 58 kg Z axis 400 mm: 60 kg				
	Rotation angler output Transmission method lote 1 ed load let time: with 2k let moment of let moment of let with 2k let moment of let moment of let with 2k let moment of	Rotation angle or output Transmission method ad oad a time: with 2kg payload Note 2 le moment of inertia Note 3 ss Note 4 q × wires) uter diameter)	Rotation angle +/-130 ° or output 750 W Transmission method Speed reducer doutput Individual speed reducer to output Individual speed r	Arm length	Arm length	

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

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 Connector for user wiring (No.1 to 20 usable, cable clamp size: ϕ 16 to18) Cover with the caps provided when not used. 8 User tubing 1 (φ6 black) / **4-**ф14 User tubing 2 (φ6 red) M12 bolt for installation, 4 bolts used User tubing 3 (\$\phi6\$ blue) 260 16 Note. Insert the plug provided when not used. 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 or the arm may be in contact with the machine harness. So, do not perform such motion. 500 90 63 128 201 175(Maximum 300 during arm rotation) Working envelope of left-handed system Z400mm 1000 Stroke Z200mm 800 Stroke (Maximum 920 during arm rotation) 568 Connector for user wiring (No.1 to 20 usable, 476 φ38 (Air release tubing) Connect a hose and extend it to a location not exposed to water and dust. cable clamp size: ϕ 16 to18) 368 324 339.5 Cover with the caps provided 254.5 219 when not used. ф90 h7 188.7+/-2 X axis joint air purge port (φ6) Z-axis stroke Z-axis stroke Y axis joint air purge port (φ6) 158 M4 ground terminal 129° Z-axis lower end mechanical stopper position User tubing 1 (\$\phi6\$ black) 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 or the arm may be in contact with the machine harness. So, do not perform such motion. User tubing 2 (φ6 red) User tubing 3 (\$\phi6\$ 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 ф90 h7 - 0.035 of the base. P.C.D.36 X-axis mechanical stopper position: 132° 6-M5×0.8 Depth 11 Y-axis mechanical stopper position: 152° 4-φ11 R32 (Min. cable bending radius) Do not move the cable. 10-M5x0.8 Depth 11

*There is no phase relation between each position of M5 tapped holes and R-axis origin position.

Z axis tip shape

Dust-proof & drip-proof type

Arm length 1000mm Maximum payload 20kg

YK1000XGP

Ordering method

YK1000XGP RCX340-4 Specify various controller setting items. RCX340 ▶ P.636

■ Specifications						
			X-axis	Y-axis	Z-axis	R-axis
Axis	Arm length		600 mm	400 mm	200 mm 400 mm	-
specifications	Rotation angl	le	+/-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 spe	ed		10.6 m/sec		2.3 m/sec 1.7 m/sec	920 °/sec
Maximum pay	load		20 kg			
Standard cycle	e time: with 2k	g payload Note 2	0.59 sec			
R-axis tolerab	le moment of	inertia Note 3	1.0 kgm ²			
Protection cla	SS Note 4		Equivalent to IP65 (IEC 60529)			
User wiring (s	q × wires)			0.2	× 20	
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: 60 kg Z axis 400 mm: 62 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.

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