CLEAN ROBOTS
CLEAN TYPE

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Main functions ▶ P.50
# Clean Robots Specification Sheet

## Clean single-axis robots

**TRANSERVO**
- **Degree of cleanliness** CLASS 10
- **Intake air** 15 to 80 NL/min

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>S5C04</strong></td>
<td>12 6</td>
<td>2 1</td>
<td>600 300</td>
</tr>
<tr>
<td></td>
<td>2 6</td>
<td>4 2</td>
<td>100</td>
</tr>
<tr>
<td><strong>S5C05</strong></td>
<td>12 6</td>
<td>1</td>
<td>600</td>
</tr>
<tr>
<td></td>
<td>4 6</td>
<td>2</td>
<td>200 300 150</td>
</tr>
<tr>
<td><strong>S5C05H</strong></td>
<td>6 10</td>
<td>6</td>
<td>100</td>
</tr>
</tbody>
</table>

## FLIP-XC
- **Degree of cleanliness** C4L/C4LH/C5L/C5LH/C6L ISO CLASS 3 (ISO14644-1) **Note**
- **Intake air** 20 to 90 NL/min

<table>
<thead>
<tr>
<th>Model</th>
<th>AC servo motor output (W)</th>
<th>Repeatability (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>C4L/C4LH</strong></td>
<td>30</td>
<td>+/-.02</td>
<td>12 4 5</td>
<td>1.2 600</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>6 6 7</td>
<td>100 200</td>
</tr>
<tr>
<td><strong>C5L/C5LH</strong></td>
<td>30</td>
<td>+/-.02</td>
<td>20 12 6</td>
<td>1.2 800</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>6 6 7</td>
<td>400</td>
</tr>
<tr>
<td><strong>C6L</strong></td>
<td>60</td>
<td>+/-.02</td>
<td>20 12 6</td>
<td>300</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>6 10 7</td>
<td>400</td>
</tr>
</tbody>
</table>

**Note:** Class 10 (0.1µm) equivalent to FED-STD-209D

---

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>YP-X</strong></td>
<td>20 30</td>
<td>500 500</td>
<td>250 150 100</td>
</tr>
<tr>
<td></td>
<td>60 40</td>
<td>700 700</td>
<td>500 250 100 100</td>
</tr>
<tr>
<td><strong>YPX CLEAN</strong></td>
<td>INFORMATION</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

---

**LINAR CONVEYOR MODULES**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>YP-X</strong></td>
<td>20 80</td>
<td>15</td>
<td>1000</td>
</tr>
<tr>
<td></td>
<td>10 120</td>
<td>35</td>
<td>500</td>
</tr>
</tbody>
</table>

---

**YP-X CLEAN**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>YP-X</strong></td>
<td>20 120</td>
<td>25</td>
<td>1000</td>
</tr>
<tr>
<td></td>
<td>10 –</td>
<td>45</td>
<td>500</td>
</tr>
</tbody>
</table>

---

**TRANSCONTROL INFORMATION**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead (mm)</th>
<th>Payload (kg)</th>
<th>Stroke (mm) and maximum speed (mm/sec)</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>YP-X</strong></td>
<td>20 120</td>
<td>25</td>
<td>1000</td>
</tr>
<tr>
<td></td>
<td>10 –</td>
<td>45</td>
<td>500</td>
</tr>
<tr>
<td>Model</td>
<td>AC servo</td>
<td>Motor output (W)</td>
<td>Repeatability (mm)</td>
</tr>
<tr>
<td>--------</td>
<td>----------</td>
<td>------------------</td>
<td>--------------------</td>
</tr>
<tr>
<td>SC4C04</td>
<td>12</td>
<td>2</td>
<td>1</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>SC4C05</td>
<td>20</td>
<td>4</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>SC4C05H</td>
<td>20</td>
<td>6</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>FLIP-X</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

For more detailed information, please refer to:
- C4L: P.444
- C4LH: P.445
- C5L: P.446
- C5LH: P.447
- P.448
- P.449
- P.450
- P.451
- P.452
- P.453
- P.454
- P.455
- P.456
- P.457
Clean cartesian robots

- **XY-XC**
  - Degree of cleanliness CLASS 10
  - Intake air 60 to 90Nl/min
  - Aperture designed to minimal dimensions by use of stainless steel sheet
  - Installed clean robot dedicated cable duct

- **PHASER**
  - Cartesian robots
  - XY-X
  - SCARA robots
  - YK-X

Clean SCARA robots

- **YK-XC/YK-XGC/YK-XGLC**
  - Degree of cleanliness YK-XC ................. CLASS 10
  - YK-XGC/YK-XGLC ... ISO CLASS 3 (ISO14644-1)  
    Note: Class 10 (0.1µm) equivalent to FED-STD-209D
  - Intake air 30 to 60Nl/min
  - Bellows cover fitted in axial tip
  - Harness placed completely on inside
**SCC04**

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

### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Type</th>
<th>Brake</th>
<th>Direction of air intake</th>
<th>Origin position</th>
<th>Stroke</th>
<th>Cable length</th>
<th>Robot positioner</th>
</tr>
</thead>
<tbody>
<tr>
<td>SSC04</td>
<td>S</td>
<td>S</td>
<td>S</td>
<td>Vertical</td>
<td>Non-motor side</td>
<td>50–400</td>
<td>1m</td>
<td>TS-S2</td>
</tr>
</tbody>
</table>

Note 1. If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, refer to the manual.

Note 2. The robot cable is flexible and resists bending.

Note 3. See P.500 for DIN rail mounting bracket.

Note 4. Select this selection when using the gateway function. For details, see P.62.

### Basic specifications

<table>
<thead>
<tr>
<th>Motor</th>
<th>Repeatability (mm)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Step motor</td>
<td>+/-0.02</td>
</tr>
</tbody>
</table>

| Deceleration mechanism | Ball screw Ø8 (Class C10) |

| Maximum motor torque (Nm) | 0.27 |

<table>
<thead>
<tr>
<th>Ball screw lead (mm)</th>
<th>12</th>
</tr>
</thead>
<tbody>
<tr>
<td>6</td>
<td>2</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Maximum speed (mm/sec)</th>
<th>600</th>
</tr>
</thead>
<tbody>
<tr>
<td>300</td>
<td>100</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Maximum payload (kg)</th>
<th>Vertical</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>4</td>
</tr>
<tr>
<td>4</td>
<td>6</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Maximum pressing force (N)</th>
<th>45</th>
</tr>
</thead>
<tbody>
<tr>
<td>90</td>
<td>150</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Stroke (mm)</th>
<th>50 to 400 (50mm pitch)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Overall length (mm)</td>
<td>Stroke+216</td>
</tr>
<tr>
<td>Maximum outside dimension of body cross-section (mm)</td>
<td>W49 + H59</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Overall length (mm)</th>
<th>20</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vertical</td>
<td>Stroke+261</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Cables securing position (Note 3)</th>
<th>Lead 2, Lead 9, Lead 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Intake air (N/min)</td>
<td>50</td>
</tr>
<tr>
<td></td>
<td>30</td>
</tr>
<tr>
<td></td>
<td>15</td>
</tr>
</tbody>
</table>

Note 1. Positioning repeatability in one direction.

Note 2. Per 1cf (0.1µm base), when suction blower is used.

### Allowable overhang

- Horizontal installation (Unit: mm):
  - A
  - B
  - C

- Vertical installation (Unit: mm):
  - A
  - B
  - C

### Static loading moment

- Horizontal loading moment (Unit: Nm):
  - MY
  - MP
  - MR

<table>
<thead>
<tr>
<th>Effective stroke</th>
<th>50</th>
<th>100</th>
<th>150</th>
<th>200</th>
<th>250</th>
<th>300</th>
<th>350</th>
<th>400</th>
</tr>
</thead>
<tbody>
<tr>
<td>L</td>
<td>286</td>
<td>316</td>
<td>366</td>
<td>416</td>
<td>466</td>
<td>516</td>
<td>566</td>
<td>616</td>
</tr>
<tr>
<td>A</td>
<td>2</td>
<td>3</td>
<td>4</td>
<td>5</td>
<td>6</td>
<td>7</td>
<td>8</td>
<td>9</td>
</tr>
<tr>
<td>B</td>
<td>3</td>
<td>4</td>
<td>5</td>
<td>6</td>
<td>7</td>
<td>8</td>
<td>9</td>
<td>10</td>
</tr>
<tr>
<td>C</td>
<td>50</td>
<td>100</td>
<td>150</td>
<td>200</td>
<td>250</td>
<td>300</td>
<td>350</td>
<td>400</td>
</tr>
</tbody>
</table>

| Weight (kg) | 1.5 | 1.6 | 1.7 | 1.8 | 2.0 | 2.1 | 2.2 | 2.3 |

Note 1. Stop positions are determined by the mechanical stoppers at both ends.

Note 2. Either right or left can be selected for the suction air joint mounting direction.

Note 3. Secure the cable with a tie-band 100mm or less from unit’s end face to prevent the cable from being subjected to excessive loads.

Note 4. The cable’s minimum bend radius is R30.

Note 5. These are the weights without a brake. The weights are 0.2kg heavier when equipped with a brake.

---

**Controller**

- **Operation method**
  - TS-S2: 10-point trace
  - TS-SH: Remote command
  - TS-SD: Pulse train control

---

**SSC04**

Approx. 200 (Cable length)

<table>
<thead>
<tr>
<th>Mounting direction: LJ</th>
</tr>
</thead>
<tbody>
<tr>
<td>2-M6 Suction air joint</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Cable securing position (Note 3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vertical</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Horizontal installation (Unit: mm)</th>
</tr>
</thead>
<tbody>
<tr>
<td>A</td>
</tr>
<tr>
<td>---</td>
</tr>
<tr>
<td>1kg</td>
</tr>
<tr>
<td>1kg</td>
</tr>
<tr>
<td>1kg</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Vertical installation (Unit: mm)</th>
</tr>
</thead>
<tbody>
<tr>
<td>A</td>
</tr>
<tr>
<td>---</td>
</tr>
<tr>
<td>1kg</td>
</tr>
<tr>
<td>1kg</td>
</tr>
<tr>
<td>1kg</td>
</tr>
</tbody>
</table>

Note: Distance from center of slider upper surface to conveyor center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 400mm stroke models).
### SSC05

#### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Type</th>
<th>Brake \textsuperscript{1}</th>
<th>Direction of air \textsuperscript{2}</th>
<th>Origin position \textsuperscript{2}</th>
<th>Stroke \textsuperscript{2}</th>
<th>Cable length \textsuperscript{3}</th>
<th>Robot positioner \textsuperscript{4}</th>
<th>I/O</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>with/without brake</td>
<td>with/without brake</td>
<td>without motor bias</td>
<td>0 to 600 (mm/pitch)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
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</tr>
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<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Basic specifications

- **Motor**: 42 [ ] Step motor
- **Repeatability (mm)**: \( \pm 0.02 \)
- **Deceleration mechanism**: Ball screw G12 (Class C10)
- **Maximum motor torque (N .m)**: 0.27
- **Ball screw lead (mm)**: 20 12 6
- **Maximum speed (mm/sec)**: 5000 600 300
- **Maximum payload (kg)**: 4 6 10
- **Max. pressing force (N)**: 27 45 90
- **Overall length (mm)**: Stroke+230
- **Horizontal Stroke**
- **Vertical Stroke** 270
- **Maximum outside dimension of body cross-section (mm)**: W55 x H56
- **Cable length (m)**: Standard: 1 / Option: 3, 5, 10
- **Degree of cleanliness**: CLASS 10
- **Intake air (N/min)**: Leader 20 Lead12 Lead 6
- **Dynamic load (kg)**: 0 50 30
- **Static loading moment**: 2.1 2.3 2.5 2.7 2.8 3.0 3.2 3.4 3.6 3.8 4.0 4.2 4.4 4.6 4.8 5.0
- **Controller**: Operation method
- **Controller**: TS-S2
- **Operation method**: TS-SH

#### Allowable overhang

- **Horizontal installation (unit: mm)**
- **Wall installation (unit: mm)**
- **Vertical installation (unit: mm)**

#### Static loading moment

<table>
<thead>
<tr>
<th>Static (N.m)</th>
<th>25</th>
<th>33</th>
<th>30</th>
</tr>
</thead>
</table>

#### Controller

- **Controller**: TS-S2
- **Operation method**: TS-SH
- **Remote command**: TS-SH
- **Pulse train control**: TS-SD

---

**Note**: Distances from center of slider upper surface to conveyor center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).
### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Type</th>
<th>Brake</th>
<th>Direction of air chambers</th>
<th>Origin position</th>
<th>Stroke</th>
<th>Cable length</th>
</tr>
</thead>
<tbody>
<tr>
<td>SSC05H</td>
<td>20</td>
<td>Straight</td>
<td>-</td>
<td>W to W</td>
<td>20 to 800</td>
<td>6m</td>
<td></td>
</tr>
</tbody>
</table>

Note 1: Only the model with a lead of 12mm or 6mm can select specifications with brake.

Note 2: If changing from the origin position at the time of purchase, the machine reference amount must be reset. For details, refer to the manual.

Note 3: The robot cable is flexible and resists bending.

Note 4: See P.500 for DIN rail mounting bracket.

Note 5: Select this selection when using the gateway function. For details, see P.62.

### Basic specifications

<table>
<thead>
<tr>
<th>Motor</th>
<th>Repeatability** (mm)</th>
<th>Deceleration mechanism</th>
<th>Maximum motor torque (N·m)</th>
<th>Ball screw lead (mm)</th>
<th>Maximum speed** (mm/sec)</th>
<th>Overall length (mm)</th>
<th>Maximum outside dimension (body cross-section(mm))</th>
<th>Cable length (m)</th>
<th>Degree of cleanliness</th>
</tr>
</thead>
<tbody>
<tr>
<td>42</td>
<td>+/-0.02</td>
<td>Ball screw φ12 (Class C10)</td>
<td>0.47</td>
<td>20</td>
<td>12</td>
<td>6</td>
<td>1000</td>
<td>600</td>
<td>200</td>
</tr>
</tbody>
</table>

Note 1: Producing repeatability in one direction. Note 2: When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below. Note 3: Per 1/5 (φ5 unit base), when suction浏览 is used.

### Allowable overhang

<table>
<thead>
<tr>
<th>Horizontal installation (unit: mm)</th>
<th>Vertical installation (unit: mm)</th>
<th>Controller</th>
</tr>
</thead>
<tbody>
<tr>
<td>A</td>
<td>B</td>
<td>C</td>
</tr>
<tr>
<td>2kg</td>
<td>2kg</td>
<td>2kg</td>
</tr>
<tr>
<td>4kg</td>
<td>3kg</td>
<td>2kg</td>
</tr>
<tr>
<td>6kg</td>
<td>5kg</td>
<td>3kg</td>
</tr>
</tbody>
</table>

### Static loading moment

**Note:** Distance from center of slider upper surface to conveyor center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).

**Controller**

- **Operation method:** TS-S2: IO point trace / TS-SH: Remote command / TS-SD: Pulse train control

---

**Diagram:**

![Diagram](image)

**Table:**

<table>
<thead>
<tr>
<th>Motor</th>
<th>Repeatability** (mm)</th>
<th>Deceleration mechanism</th>
<th>Maximum motor torque (N·m)</th>
<th>Ball screw lead (mm)</th>
<th>Maximum speed** (mm/sec)</th>
<th>Overall length (mm)</th>
<th>Maximum outside dimension (body cross-section(mm))</th>
<th>Cable length (m)</th>
<th>Degree of cleanliness</th>
</tr>
</thead>
<tbody>
<tr>
<td>42</td>
<td>+/-0.02</td>
<td>Ball screw φ12 (Class C10)</td>
<td>0.47</td>
<td>20</td>
<td>12</td>
<td>6</td>
<td>1000</td>
<td>600</td>
<td>200</td>
</tr>
</tbody>
</table>

Note 1: Producing repeatability in one direction. Note 2: When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below. Note 3: Per 1/5 (φ5 unit base), when suction浏览 is used.

### Allowable overhang

<table>
<thead>
<tr>
<th>Horizontal installation (unit: mm)</th>
<th>Vertical installation (unit: mm)</th>
<th>Controller</th>
</tr>
</thead>
<tbody>
<tr>
<td>A</td>
<td>B</td>
<td>C</td>
</tr>
<tr>
<td>2kg</td>
<td>2kg</td>
<td>2kg</td>
</tr>
<tr>
<td>4kg</td>
<td>3kg</td>
<td>2kg</td>
</tr>
<tr>
<td>6kg</td>
<td>5kg</td>
<td>3kg</td>
</tr>
</tbody>
</table>

### Static loading moment

**Note:** Distance from center of slider upper surface to conveyor center-of-gravity at a guide service life of 10,000 km (Service life is calculated for 600mm stroke models).

**Controller**

- **Operation method:** TS-S2: IO point trace / TS-SH: Remote command / TS-SD: Pulse train control
### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Brake</th>
<th>L-Magnet</th>
<th>I/O connector specification</th>
</tr>
</thead>
<tbody>
<tr>
<td>C4L</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Basic specifications

- **AC servo motor output (W)**: 30
- **Repeatability (mm)**: +/-0.02
- **Ball screw lead (mm)**: 12, 6, 2
- **Maximum speed (mm/sec)**: 720, 380, 120
- **Payload capacity (kg)**: 4.5, 6, 2
- **Stroke (mm)**: 32 to 400 (50mm pitch)
- **Overall length (mm)**: Horizontal 240, Vertical 240
- **Maximum outside dimension of body cross-section (mm)**: W45×H55
- **Cable length (m)**: Standard: 3m, Option: 1.5m, 10L
- **Intake air (N/min)**: 4.5kg, 52, 122

**Notes:**
1. Positioning repeatability in one direction.
2. CLASS 10 (0.1µm) FED-STD-209D or equivalent when a suction blower is used.
3. The necessary intake amount varies depending on the use conditions and environment.

### Allowable overhang

- **Horizontal installation**: 2kg, 4.5kg, 6kg
- **Wall installation**: 3kg, 5kg, 6kg
- **Vertical installation**: 1.2kg, 2.4kg, 3kg

**Note:** Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

### Static loading moment

- **Horizontal installation**: 64 suction air joint
- **Wall installation**: 30 suction air joint
- **Vertical installation**: 8 suction air joint

### Controller

- **Operation method**: ERCD
- **Pulse train control / Programming / I/O point trace / Remote command / Operation using RS-232C communication

---

**Note 1:** The robot cable is standard cable (1L/3L/5L/10L), but can be changed to flexible cable. See P.596 for details on robot cable.

**Note 2:** CLASS 10 (0.1µm) FED-STD-209D or equivalent when a suction blower is used.

**Note 3:** The necessary intake amount varies depending on the use conditions and environment.

**Note 4:** Either right or left can be selected for the installation direction for the 46 suction air joint. (The left side is the standard.)

**Note 5:** External view of C4LH is identical to C4L.
### Ordering method

**C4LH**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead screw</th>
<th>Ball screw</th>
<th>Direction or air compression</th>
<th>Origin position</th>
<th>Stroke</th>
<th>Cable length (m)</th>
</tr>
</thead>
<tbody>
<tr>
<td>YA</td>
<td>4H7</td>
<td>φ8</td>
<td>From left (Standard)</td>
<td>-30°</td>
<td>152</td>
<td>1.4 1.5 1.7 1.8 2</td>
</tr>
<tr>
<td>TRANSERVO</td>
<td>4H7</td>
<td>φ8</td>
<td>From left (Standard)</td>
<td>-30°</td>
<td>152</td>
<td>1.4 1.5 1.7 1.8 2</td>
</tr>
<tr>
<td>FLIP-X</td>
<td>4H7</td>
<td>φ8</td>
<td>From left (Standard)</td>
<td>-30°</td>
<td>152</td>
<td>1.4 1.5 1.7 1.8 2</td>
</tr>
</tbody>
</table>

Note 1: The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable.
Note 2: See P.505 for details on robot cable.
Note 3: Select this selection when using the gateway function. For details, see P.62.

### Basic specifications

- **AC servo motor output (W)**: 30
- **Repeatability (mm)**: +/0.02
- **Deceleration mechanism**: Ball screw φ8 (Class C10)
- **Ball screw lead (mm)**: 12 6 2
- **Maximum speed (mm/sec)**: 720 360 120
- **Maximum payload (kg)**: 4.5 6 7.2
- **Rated thrust (N)**: 32 64 153
- **Stroke (mm)**: 50 to 400 (50mm pitch)
- **Overall length (mm)**: 612
- **Maximum outside dimension of body cross-section (mm)**: W45×H55
- **Cable length (m)**: 110 220 320 370 420
- **Weight (kg)**: 1.2kg 118 118 15 19
- **Service life**: 25,000 km
- **External view of C4LH**: identical to C4L

Note 1: Positioning repeatability in one direction.
Note 2: CLASS 10 (0.1µm) FED-STD-209D or equivalent when a suction blower is used.
Note 3: Select this selection when using the gateway function. For details, see P.62.

### Allowable overhang

<table>
<thead>
<tr>
<th>Horizontal installation (unit: mm)</th>
<th>Vertical installation (unit: mm)</th>
</tr>
</thead>
<tbody>
<tr>
<td>A A B C A B C A C A C</td>
<td>A A B C A B C A C A C</td>
</tr>
<tr>
<td>2kg 339 90 174 2kg 136 72 295</td>
<td>1.2kg 118 118</td>
</tr>
<tr>
<td>4.5kg 169 37 72 4.5kg 44 20 111</td>
<td>2.4kg 52 54</td>
</tr>
<tr>
<td>6kg 234 27 62 6kg 27 10 127</td>
<td>3kg 38 39</td>
</tr>
<tr>
<td>8kg 305 56 133 8kg 101 41 254</td>
<td>7.2kg 136 147</td>
</tr>
</tbody>
</table>

**Note**: Distances from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km. Service life is calculated for 300mm stroke models.

### Static loading moment

- **Controller**: SR1-X 05
- **Driver**: Power-supply voltage
- **RDV-X 05**: 240V

#### Controller Operation

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

- **SR1-X05**: RCC21/222
- **RDV-X205**: Pulse train control
**C5L**
- High lead: Lead 20
- Origin on the non-motor side is selectable

### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>C5L</th>
</tr>
</thead>
<tbody>
<tr>
<td>Left axis orientation</td>
<td>YA</td>
</tr>
<tr>
<td>Right axis orientation</td>
<td>TRANSERVO</td>
</tr>
<tr>
<td>Single-axis robots</td>
<td>FLIP-X</td>
</tr>
</tbody>
</table>

**ERCD**
- I/O connector specification
  - 1: Standard (with brake)
  - 2: Flexible cable

**Note 1.** The model with a lead of 22mm cannot select specifications with brake (vertical specifications).

**Note 2.** The robot cable is standard cable (1L/3L/5L/10L), but can be changed to flexible cable.

**Note 3.** Minimum bend radius of motor cable is R30.

**Note 4.** Either right or left can be selected for the installation direction for the intake air joint. (The left side is the standard.)

**Note 5.** The robot cable is standard cable (1L/3L/5L/10L), but can be changed to flexible cable.

**Note 6.** The necessary intake amount varies depending on the use conditions and environment.

### Basic specifications

- **AC servo motor output (W):** 30
- **Repeatability (mm):** +/-0.02
- **Deceleration mechanism:** Ball screw (Class C10)
- **Maximum speed (mm/sec):**
  - Horizontal: 1000, 800, 400
  - Vertical: 19, 32, 64
- **Rated thrust (N):**
  - Horizontal: 50 to 800 (50mm pitch)
  - Vertical: Stroke=236.5
- **Maximum outside dimension of body cross-section (mm):** W55×H65
- **Cable length (m):**
  - Standard: 3.5 / Option: 1, 5, 10
- **Lead:**
  - 20: 20mm
  - 12: 12mm
  - 6: 6mm
- **Ball screw pitch (mm):**
  - 20: 20
  - 12: 12
  - 6: 6
- **Ordering method**
  - Model classification
    - C5L (20mm lead)
    - C5LH (20mm lead with brakes)
  - Specification
    - LJ (Left): Standard
    - RJ (Right): Option
  - Designation
    - BK: With brake
    - RJ: Right
    - Z: Non-motor side
  - Specification options
    - 5L: 5m
    - 10L: 10m
  - Specification codes
    - C: 5L
    - L: 10L
    - 3L: 3.5m

### Allowable overhang

- **Horizontal installation (unit: mm):**
  - A: 1084, 324, 745
  - B: 1094, 344, 765
  - C: 1075, 325, 745
- **Wall installation (unit: mm):**
  - A: 679, 303, 1005
  - B: 689, 313, 1015
  - C: 679, 303, 1005
- **Vertical installation (unit: mm):**
  - A: 1.2kg, 246, 451
  - B: 1.2kg, 246, 451
  - C: 1.2kg, 246, 451

### Static loading moment

<table>
<thead>
<tr>
<th>MY</th>
<th>MP</th>
<th>MR</th>
</tr>
</thead>
<tbody>
<tr>
<td>30</td>
<td>34</td>
<td>40</td>
</tr>
</tbody>
</table>

### Controller

- **ERCD**
  - Controller: Operation method
    - Pulse train control / Programming / I/O point/brake / Remote control / Operation using RS-232C communication

---

---
### Ordering method

**C5LH**

- **Model**: [Select designations]
- **Use designation**: 
  - 1: Base model
  - 2: Brake
- **Speed selection**: 
  - 1: 120 (Class C10)
  - 2: 240 (Class C10)
- **Direction of air**: 
  - L: Left
  - R: Right
- **Origin position**: 
  - M: Motor side
  - H: Non-motor side
- **Stroke**: 
  - Effective stroke: 50 to 800 (50mm pitch)
- **Cable length**: 
  - Standard: 3 (L), 5 (L), 10 (L)
- **Ball screw lead**: 
  - 5mm

### Basic specifications

<table>
<thead>
<tr>
<th>AC servo motor output (W)</th>
<th>30</th>
</tr>
</thead>
<tbody>
<tr>
<td>Repeatability (mm)</td>
<td>+/-0.02</td>
</tr>
<tr>
<td>Deceleration mechanism</td>
<td>Ball screw</td>
</tr>
<tr>
<td>Horizontal maximum payload (kg)</td>
<td>6</td>
</tr>
<tr>
<td>Vertical maximum payload (kg)</td>
<td>2</td>
</tr>
<tr>
<td>Rated thrust (N)</td>
<td>25</td>
</tr>
<tr>
<td>Stroke (mm)</td>
<td>50 to 800 (50mm pitch)</td>
</tr>
<tr>
<td>Overall length (mm)</td>
<td>Vertical Stroke: 236.5</td>
</tr>
<tr>
<td>Maximum outside dimension of body cross-section (mm)</td>
<td>W55xH65</td>
</tr>
<tr>
<td>Cable length (m)</td>
<td>Standard: 3.6 (Option: 5, 10)</td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>ISO CLASS 3 (ISO14644-1)</td>
</tr>
<tr>
<td>Intake air (N/mm²)</td>
<td>80</td>
</tr>
<tr>
<td>80</td>
<td>50</td>
</tr>
</tbody>
</table>

### Allowable overhang

**Horizontal installation**

- **Wall installation**
- **Vertical installation**

### Static loading moment

- **Controller**
  - **SR1-X**: Programming / I/O point trace / Remote command / Operation using RS-232C communication
  - **TS-X**: I/O point trace / Remote command
  - **RDV-X**: Pulse train control

### Static loading moment

- **Controller**: SR1-X 05, TSX205, RDV-X 05
  - Driver: Power-supply voltage
  - Driver: Power capacity

### C5LH

- **Model**: 250 (Motor cable length)
- **Effective stroke**: 126 (±3)
- **4H7 Depth 7**: A-M6x0.8 Depth 6
- **4H7 Depth 6**: A-M5 x 0.8 Depth 6
- **4H7 Depth 5**: A-M5 x 0.8 Depth 6
- **4H7 Depth 4**: A-M5 x 0.8 Depth 6
- **4H7 Depth 3**: A-M5 x 0.8 Depth 6
- **4H7 Depth 2**: A-M5 x 0.8 Depth 6
- **4H7 Depth 1**: A-M5 x 0.8 Depth 6

### Notes

1. The model with a lead of 20mm cannot select specifications with brake (vertical specifications).
2. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable.
3. Weight of models with no brake. The weight of models with no brake shown in the table.
4. Stop positions are determined by the mechanical stoppers at both ends.
C6L

- High lead: Lead 20
- Origin on the non-motor side is selectable

### Ordering method

- **C6L**
  - Model
  - Brake
  - Direction of air suction
  - Origin position
  - Stroke
  - Cable length

### Basic specifications

- AC servo motor output (W)
- Repeatability (mm)
- Deceleration mechanism
- Ball screw lead (mm)
- Maximum speed (mm/sec)
- Rated thrust (N)
- Cable length (m)
- Intake air (N/min)

- **AC motor output (W)**
- **Repeatability (mm)**
- **Deceleration mechanism**
- **Ball screw lead (mm)**
- **Maximum speed (mm/sec)**
- **Rated thrust (N)**
- **Cable length (m)**
- **Intake air (N/min)**

**Note 1.** Positioning repeatability in one direction.
**Note 2.** Class 10 (0.1µm) FED-STD-209D or equivalent when a suction blower is used.
**Note 3.** The necessary intake amount varies depending on the use conditions and environment.

### Allowable overhang

- **Horizontal installation**
- **Wall installation**
- **Vertical installation**

### Static loading moment

- **Controller**
- **Operation method**
- **Programming**
  - **SR1-X05**
  - **RCX221/222**
- **Remote command**
  - **Operation**
  - **TS-X205**
  - **RDV-X205**

### Controller

- **SR1-X05**
- **TS-X205**
- **RDV-X205**

- **Controller Driver**
  - Power-supply voltage
  - Driver: Power capacity
  - Regenerative unit

- **MR**
- **MP**
- **MY**

### Note

- For details, see P.62.
- Service life is calculated for 600mm stroke models.
- Operation conditions (critical speed).
- In this case, reduce the speed setting on the program referring to the maximum speeds shown in the table at the left.
### Ordering method

**C8**

- **High lead: Lead 20**
- **Origin on the non-motor side is selectable**

#### Basic specifications

<table>
<thead>
<tr>
<th>AC servo motor output (W)</th>
<th>100</th>
</tr>
</thead>
<tbody>
<tr>
<td>Repeatability (mm)</td>
<td>±0.02</td>
</tr>
<tr>
<td>Deceleration mechanism</td>
<td>Ball screw (Class C10)</td>
</tr>
<tr>
<td>Ball screw lead (mm)</td>
<td>20  12  6</td>
</tr>
<tr>
<td>Maximum speed (mm/sec)</td>
<td>1000  720  360</td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>Vertical: 6, Horizontal: Stroke+320</td>
</tr>
<tr>
<td>Rated thrust (N)</td>
<td>84  141  283</td>
</tr>
<tr>
<td>Stroke (mm)</td>
<td>150 to 600 (50mm pitch)</td>
</tr>
<tr>
<td>Overall size (mm)</td>
<td>Horizontal: Stroke+320, Vertical: Stroke+355</td>
</tr>
<tr>
<td>Maximum outside dimension of body cross-section (mm)</td>
<td>W80 × H75</td>
</tr>
<tr>
<td>Cable length (m)</td>
<td>Standard: 3.5 / Option: 5, 10</td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10</td>
</tr>
<tr>
<td>Intake air (N/min)</td>
<td>30 to 90</td>
</tr>
</tbody>
</table>

**Note:**
1. Positioning repeatability in one direction.
2. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.
3. Per 1cf (0.1µm base), when suction blower is used.
4. The necessary intake amount varies depending on the use conditions and environment.

### Allowable overhang

#### Horizontal installation (Unit: mm)

<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>5kg</td>
<td>245</td>
<td>85</td>
</tr>
<tr>
<td>10kg</td>
<td>131</td>
<td>39</td>
</tr>
<tr>
<td>12kg</td>
<td>115</td>
<td>31</td>
</tr>
<tr>
<td>15kg</td>
<td>96</td>
<td>22</td>
</tr>
<tr>
<td>20kg</td>
<td>364</td>
<td>92</td>
</tr>
<tr>
<td>25kg</td>
<td>107</td>
<td>43</td>
</tr>
<tr>
<td>30kg</td>
<td>144</td>
<td>26</td>
</tr>
<tr>
<td>35kg</td>
<td>112</td>
<td>20</td>
</tr>
<tr>
<td>40kg</td>
<td>168</td>
<td>7</td>
</tr>
</tbody>
</table>

#### Vertical installation (Unit: mm)

<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>5kg</td>
<td>121</td>
<td>71</td>
</tr>
<tr>
<td>10kg</td>
<td>62</td>
<td>24</td>
</tr>
<tr>
<td>12kg</td>
<td>28</td>
<td>16</td>
</tr>
<tr>
<td>15kg</td>
<td>164</td>
<td>78</td>
</tr>
<tr>
<td>20kg</td>
<td>83</td>
<td>36</td>
</tr>
<tr>
<td>25kg</td>
<td>54</td>
<td>21</td>
</tr>
<tr>
<td>30kg</td>
<td>91</td>
<td>92</td>
</tr>
<tr>
<td>35kg</td>
<td>49</td>
<td>91</td>
</tr>
<tr>
<td>40kg</td>
<td>41</td>
<td>40</td>
</tr>
</tbody>
</table>

**Note:**
- Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

### Static loading moment

<table>
<thead>
<tr>
<th>Controller</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>SR1-X05</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>TS-X105</td>
<td>I/O point trace / Remote command</td>
</tr>
<tr>
<td>RDV-X205-RBR1</td>
<td>Pulse train control</td>
</tr>
</tbody>
</table>

### Controller Driver: Power capacity

<table>
<thead>
<tr>
<th>Power capacity</th>
</tr>
</thead>
<tbody>
<tr>
<td>100V/100W or less</td>
</tr>
<tr>
<td>No entry: None</td>
</tr>
</tbody>
</table>

**Note:**
1. Stop positions are determined by the mechanical stoppers at both ends.
2. Minimum bend radius of motor cable is R50.
3. Weight of models with no brake. The weight of brake-attached models is 0.3 kg heavier than the models with no brake shown in the table.
4. When the stroke is longer than 600mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
## Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Brake</th>
<th>Option</th>
<th>Stroke</th>
</tr>
</thead>
<tbody>
<tr>
<td>C8L</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Basic specifications

<table>
<thead>
<tr>
<th>AC servomotor output (W)</th>
<th>100</th>
</tr>
</thead>
<tbody>
<tr>
<td>Repeatability (mm)</td>
<td>+/-0.01</td>
</tr>
<tr>
<td>Deceleration mechanism</td>
<td>Ball screw (Class C7)</td>
</tr>
<tr>
<td>Maximum speed (mm/sec)</td>
<td>1000</td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>20</td>
</tr>
<tr>
<td>Rated thrust (N)</td>
<td>84</td>
</tr>
<tr>
<td>Stroke (mm)</td>
<td>150 to 1050 (50mm pitch)</td>
</tr>
<tr>
<td>Overall length</td>
<td>4</td>
</tr>
<tr>
<td>Rated maximum outside of body cross-section (mm)</td>
<td>W80 x H75</td>
</tr>
<tr>
<td>Cable length (m)</td>
<td>Standard: 3.5 / Option: 5, 10</td>
</tr>
<tr>
<td>Stroke+360</td>
<td></td>
</tr>
<tr>
<td>Stroke+325</td>
<td></td>
</tr>
<tr>
<td>Stroke+300</td>
<td></td>
</tr>
<tr>
<td>Stroke+275</td>
<td></td>
</tr>
<tr>
<td>Stroke+250</td>
<td></td>
</tr>
<tr>
<td>Stroke+225</td>
<td></td>
</tr>
<tr>
<td>Stroke+200</td>
<td></td>
</tr>
<tr>
<td>Stroke+175</td>
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<td>Stroke+150</td>
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<td>Stroke+125</td>
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<tr>
<td>Stroke+100</td>
<td></td>
</tr>
<tr>
<td>Stroke+75</td>
<td></td>
</tr>
<tr>
<td>Stroke+50</td>
<td></td>
</tr>
</tbody>
</table>

### Allowable overhang

<table>
<thead>
<tr>
<th>Horizontal installation (unit:mm)</th>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>5kg</td>
<td>259</td>
<td>122</td>
<td>179</td>
</tr>
<tr>
<td>10kg</td>
<td>149</td>
<td>55</td>
<td>89</td>
</tr>
<tr>
<td>50kg</td>
<td>103</td>
<td>33</td>
<td>56</td>
</tr>
<tr>
<td>20kg</td>
<td>95</td>
<td>22</td>
<td>41</td>
</tr>
<tr>
<td>10kg</td>
<td>251</td>
<td>61</td>
<td>130</td>
</tr>
<tr>
<td>50kg</td>
<td>127</td>
<td>25</td>
<td>55</td>
</tr>
<tr>
<td>10kg</td>
<td>99</td>
<td>14</td>
<td>31</td>
</tr>
<tr>
<td>20kg</td>
<td>69</td>
<td>9</td>
<td>18</td>
</tr>
<tr>
<td>50kg</td>
<td>256</td>
<td>29</td>
<td>76</td>
</tr>
<tr>
<td>10kg</td>
<td>150</td>
<td>10</td>
<td>43</td>
</tr>
<tr>
<td>20kg</td>
<td>98</td>
<td>10</td>
<td>28</td>
</tr>
<tr>
<td>50kg</td>
<td>33</td>
<td>6</td>
<td>18</td>
</tr>
</tbody>
</table>

### Static loading moment

<table>
<thead>
<tr>
<th>MY</th>
<th>MP</th>
<th>MR</th>
</tr>
</thead>
<tbody>
<tr>
<td>70</td>
<td>95</td>
<td>110</td>
</tr>
</tbody>
</table>

## Diagram

![Diagram of robot specifications and installation](image-url)

**Note 1.** Positioning repeatability in one direction.

**Note 2.** When the stroke is longer than 300mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

**Note 3.** Per 1st (0.5㎛/sec), when suction breaker is used.

**Note 4.** The necessary intake amount varies depending on the use conditions and environment.

---

**Note 1.** Stop positions are determined by the mechanical stoppers at both ends.

**Note 2.** Minimum bend radius of motor cable is R50.

**Note 3.** Weight of models with no brake.

**Note 4.** Weight of brake-attached models is 0.3 kg heavier than the models with no brake shown in the table.

**Note 5.** When the stroke is longer than 700mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
### C8LH Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Option</th>
</tr>
</thead>
<tbody>
<tr>
<td>C8LH</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Basic specifications

- **AC servo motor output (W)**: 100
- **Repeatability (mm)**: +/-0.01
- **Deceleration mechanism**: Ball screw (Class C7)
- **Ball screw lead (mm)**: 20 10 5
- **Maximum speed (mm/sec)**: 1000 600 300
- **Maximum payload (kg)**
  - Horizontal: 30 60 80
  - Stroke: 150 to 1050 (50mm pitch)
- **Overall length (mm)**: Stroke=389
- **Maximum outside dimension of body cross-section (mm)**: W80 × H75
- **Stroke (mm)**: 150 to 1050 (50mm pitch)
- **Degree of cleanliness**: Standard: 3.5 / Option: 5, 10
- **Rated thrust (N)**: 84 169 339
- **Rated thrust (N/m)**: 10 kg: 15 18 50
  - 20 kg: 30 60 80
  - 50 kg: 30 45 60
- **Intake air (N/min)**: 20kg: 1087 148 127
  - 40kg: 1600 224 175
  - 80kg: 1800 256 202

Note 1: Positioning repeatability in one direction.
Note 2: When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

### Allowable overhang

- **Horizontal installation (Unit: mm)**: 10kg: 687 274 200
  - 20kg: 401 129 92
  - 50kg: 338 76 57
  - 80kg: 594 20 17

- **Wall installation (Unit: mm)**: 10kg: 163 225 617
  - 20kg: 56 70 302
  - 50kg: 20 27 182
  - 80kg: 11 19 116

#### Static loading moment

- **Moment of inertia (Unit: kgm²)**: 10kg: 375 30 25
  - 20kg: 74 29 122
  - 50kg: 6 19 116
  - 80kg: 6 19 116

Note 1: The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.596 for details on robot cable.
Note 2: See P.550 for details on rail mounting bracket.
Note 3: Select this selection when using the gateway function. For details, see P.62.

#### Controller

- **SR1-X**
  - **Controller**: Power capacity
  - **Driver Power-supply voltage**: MR
  - **Driver**: Power capacity
  - **Controller Driver**: Power capacity
  - **Power capacity**: 100V/100W or less
  - **Controller Driver**: Power capacity
  - **Driver Power-supply voltage**: P: PNP
  - **Driver**: Power capacity
  - **Controller**: Power capacity
  - **Driver Power-supply voltage**: N: None

- **Controller Driver**: Power capacity
  - **Power capacity**: 100V/100W or less
  - **Controller Driver**: Power capacity
  - **Power capacity**: 100V/100W or less
  - **Controller Driver**: Power capacity
  - **Power capacity**: 100V/100W or less

Note 1: Stop positions are determined by the mechanical stoppers at both ends.
Note 2: Minimum band radius of motor cable is R50.
Note 3: When the stroke is longer than 650mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
### Ordering method

<table>
<thead>
<tr>
<th>C10</th>
<th>Lead</th>
<th>Brake</th>
<th>Option</th>
<th>Stroke</th>
<th>Cable length (m)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Model</td>
<td></td>
<td></td>
<td></td>
<td>150</td>
<td>200</td>
</tr>
<tr>
<td></td>
<td>20</td>
<td>10</td>
<td>5</td>
<td></td>
<td></td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>100</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Repeatability</td>
<td>+/-0.1</td>
<td></td>
<td></td>
<td></td>
<td></td>
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<tr>
<td>Deceleration mechanism</td>
<td>7.5</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Ball screw load (mm)</td>
<td>10</td>
<td>10</td>
<td>5</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Maximum speed (mm/sec)</td>
<td>1000</td>
<td>500</td>
<td>250</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Rated thrust (N)</td>
<td>84</td>
<td>168</td>
<td>339</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Stroke (mm)</td>
<td>Vertical</td>
<td>150 to 1050 (50mm pitch)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Overall length (mm)</td>
<td>Horizontal Stroke V 313</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Maximum outside dimension of body cross-section (mm) W 104 x H 85</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Cable length (m)</td>
<td>Standard: 3.5 / Option: 5, 10</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (mm)</td>
<td>30 to 90</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Basic specifications

- **AC servo motor output (W):** 100
- **Repeatability (mm):** +/-0.1
- **Deceleration mechanism:** 7.5
- **Ball screw load (mm):** 10
- **Maximum speed (mm/sec):** 1000
- **Rated thrust (N):** 84
- **Stroke (mm):** Vertical: 150 to 1050 (50mm pitch)
- **Overall length (mm):** Horizontal Stroke V 313
- **Maximum outside dimension of body cross-section (mm):** W 104 x H 85
- **Cable length (m):** Standard: 3.5 / Option: 5, 10
- **Intake air (mm):** 30 to 90

#### Allowable overhang

**Horizontal installation:**
- **A:** 5kg 8kg
- **B:** 10kg 20kg
- **C:** 15kg 30kg

**Wall installation:**
- **A:** 5kg 8kg
- **B:** 10kg 20kg
- **C:** 15kg 30kg

**Vertical installation:**
- **A:** 5kg 8kg
- **B:** 10kg 20kg
- **C:** 15kg 30kg

Note: Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

### Static loading moment

- **MY:** 119
- **MP:** 119
- **MR:** 105

### Controller

- **SR1-X05**: 200V AC
- **TS-X**: 200V AC
- **RDV-X**: 200V AC

#### Controller Operation method

- **SR1-X05**: Programmable / I/O point board / Remote command / Operation using RS-232C communication
- **TS-X**: I/O point board / Remote command
- **RDV-X**: I/O point board / Remote command

### C10

**Approx. 250 (Motor cable length):**

- **Effective stroke:**
  - **165**: When origin is on motor side
  - **195**: When origin is on non-motor side

**Effective stroke (mm/sec):**

- **L:** 433 483 533 583 633 683 733 783 833 883 933 983 1033 1083 1133 1183 1233 1283 1333
- **M:**
  - **A:** 50 100 150 200 250
  - **B:** 100 150 200 250
  - **C:** 150 200 250
- **N:**
  - **A:**
    - **150:** 0.183
    - **200:** 0.183
    - **250:** 0.183
  - **B:**
    - **150:** 0.183
    - **200:** 0.183
    - **250:** 0.183
  - **C:**
    - **150:** 0.183
    - **200:** 0.183
    - **250:** 0.183

Note 1: When selecting 5mm lead specifications, the origin point cannot be changed to the non-motor side.

Note 2: The robot cable is standard cable (3L-5L/10L), but can be changed to flexible cable. See P.506 for details on robot cable.

Note 3: See P.500 for DIN rail mounting bracket.

Note 4: Select this selection when using the gateway function. For details, see P.62.
### Ordering method

**C14**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Brake</th>
<th>Option</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td>Stroke</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Basic specifications**

- **AC servo motor output (W)**: 100
- **Repeatability (mm)**: +/−0.01
- **Deceleration mechanism**: Ball screw (Class C7)
- **Ball screw lead (mm)**: 20, 10, 5
- **Maximum speed (mm/sec)**: 1000, 500, 250
- **Maximum payload (kg)**: Horizontal 30, 55, 80, Vertical 4, 10, 20
- **Rated thrust (N)**: 84, 169, 339
- **Stroke (mm)**: 150 to 1050 (50mm pitch)
- **Overall length (mm)**: Stroke+285
- **Maximum outside dimension of body cross-section (mm)**: W136 × H96
- **Cable length (m)**: Standard 3.5 / Optic 5, 10
- **Degree of cleanliness**: CLASS 10
- **Intake air (N/mm²)**: 30 to 90

**Allowable overhang**

- **Horizontal installation**: 5kg: 1217, 1384, 968
- **Wall installation**: 15kg: 1047, 968, 1553
- **Vertical installation**: 1kg: 600, 600

**Static loading moment**

- **Controller**: SR1-X, TS-X, RDV-X

### Diagram

**C14**

- **Effective stroke**: 165±3 (When origin is on motor side)
- **Effective stroke**: 2-46(N)(220°) Depth 10
- **Effective stroke**: 4-M8 x 1.0 Depth of screw 12

**Specifications**

- **Effective stroke**: 150, 200, 250, 300, 350, 400, 450, 500, 550, 600, 650, 700, 750, 800, 850, 900, 1000, 1050
- **Maximum speed (mm/sec)**: 30 to 90
- **Maximum payload (kg)**: Horizontal 30, 55, 80, Vertical 4, 10, 20

**Note**

1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.506 for details on robot cable.
2. Select this selection when using the gateway function. For details, see P.62.

---

**Cable length (m)**: 30, 60, 90, 120, 150, 180, 210

**Note**

1. Positioning repeatability in one direction.
2. When the stroke is less than 750mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
3. Weight of models with no brake. The weight of brake-attached models is 0.4 kg heavier than the models with no brake shown in the table.
### Ordering method

**C14H**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Brake</th>
<th>Option</th>
<th>Stroke</th>
<th>Cable length (mm)</th>
</tr>
</thead>
<tbody>
<tr>
<td>C14H</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**AC servo motor output (W)**
- 200

**Repeatability (mm)**
- +/-0.01

**Ball screw lead (mm)**
- 20
- 10
- 5

**Maximum speed (mm/sec)**
- 1000
- 500
- 250

**Maximum load (kg)**
- Vertical: 8
- Horizontal: 12

**Stroke (mm)**
- Off-center: 150 to 1050 (50mm pitch)

**Overall length (mm)**
- Horizontal Stroke: 136

**Maximum outside diameter of body cross-section (mm)**
- W136 x H96

**Cable length (m)**
- Standard: 3.5
- Option: 5, 10

**Intake air (N/m²)**
- 30 to 90

### Basic specifications

Note 1. Positioning repeatability in one direction.

Note 2. The stroke is longer than 750mm, so the maximum speed shown in the table will differ from the model with no brake shown in the table below.

Note 3. Per 1cf (0.1µm base), when suction blower is used.

Note 4. Select this selection when using the gateway function. For details, see P.62.

### Allowable overhang

**Horizontal installation (unit:mm)**
- A: 10kg
  - 2247
  - 1675
  - 958
- B: 20kg
  - 1397
  - 855
  - 528
- C: 30kg
  - 1037
  - 643
  - 318
- D: 40kg
  - 897
  - 547
  - 283
- E: 50kg
  - 757
  - 464
  - 232
- F: 60kg
  - 617
  - 374
  - 192
- G: 70kg
  - 477
  - 288
  - 147
- H: 80kg
  - 337
  - 206
  - 116
- I: 90kg
  - 227
  - 142
  - 78

**Vertical installation (unit:mm)**
- A: 10kg
  - 987
  - 620
  - 343
- B: 20kg
  - 697
  - 433
  - 250
- C: 30kg
  - 527
  - 332
  - 178
- D: 40kg
  - 387
  - 240
  - 128
- E: 50kg
  - 297
  - 181
  - 96
- F: 60kg
  - 227
  - 137
  - 74
- G: 70kg
  - 177
  - 110
  - 58
- H: 80kg
  - 127
  - 82
  - 43
- I: 90kg
  - 87
  - 55
  - 29

**Effective stroke (mm/sec)**
- L: 499
  - 549
  - 599
  - 649
  - 699
  - 749
  - 799
  - 849
  - 899
  - 949
  - 999
  - 1049
  - 1099
  - 1149
  - 1199
  - 1249
  - 1299
  - 1349
- A: 200
  - 250
  - 300
  - 350
  - 400
  - 450
  - 500
  - 550
  - 600
  - 650
  - 700
  - 750
  - 800
  - 850
  - 900
  - 950
  - 1000
- N: 8
  - 8
  - 8
  - 8
  - 8
  - 10
  - 10
  - 10
  - 10
  - 10
  - 12
  - 12
  - 12
  - 12
  - 14
  - 14
  - 14
  - 16
  - 16
- Weight (kg)
  - 10.7
  - 11.4
  - 12.7
  - 13.2
  - 13.9
  - 14.5
  - 15.2
  - 15.8
  - 16.5
  - 17.0
  - 17.7
  - 18.3
  - 19.0
  - 20.3
  - 20.8
  - 21.9
  - 22.1
- Maximum speed (mm/sec)
  - Lead 20
    - 100
    - 150
    - 200
    - 250
  - Lead 10
    - 500
    - 750
    - 1000
    - 1250
  - Lead 5
    - 2000
    - 3000
    - 4000
    - 5000

Note 1. Stop positions are determined by the mechanical stoppers at both ends.

Note 2. Minimum bend radius of motor cable is 45+/-1 (Note 1).

Note 3. Weight of models with no brake. The weight of brake-equipped models is 0.4 kg heavier than the models with no brake shown in the table.

### Static loading moment

**Effective stroke 2-46H (mm) 611 (Depth of screw 12)**
- 1.0
- 5

**Positioning repeatability in one direction.**
- +/0.01

**Deceleration mechanism**
- Ball screw (Class C7)

**Rated thrust (N)**
- 170
- 341
- 683

**Stroke (mm)**
- Off-center: 150 to 1050 (50mm pitch)

**Optical encoder**
- 454

### Controller

**SR1-X**
- Pulse train control

**TS-X**
- Remote command

**RBR1**
- Remote command
### Ordering method

**C17**

- **Model**:
  - Lead
  - Brake
  - Option
  - Stroke

- **Basic specifications**
  - **AC servo motor output (W)**: 400
  - **Repeatability*** (mm): +/-0.01
  - **Deceleration mechanism**: Ball screw (Class C7)
  - **Ball screw lead (mm)**
  - **Maximum speed** (mm/sec): 1000 / 600
  - **Maximum payload (kg)**
    - Vertical: 80 / 120
    - Stroke: 15 / 30
  - **Rated thrust (N)**: 539 / 678
  - **Stroke (mm)**: 200 to 1250 (50mm pitch)
  - **Overall length (mm)**: Stroke x 1.395
  - **Maximum outside dimension of body cross-section (mm)**: W168 x H114
  - **Cable length (m)**: Standard: 3.5 / OP: 6, 10
  - **Degree of cleanliness**: CLASS 10
  - **Intake air (N/min)**: 30 to 90

**Note 1**: Positioning repeatability in one direction.

**Note 2**: When the stroke is longer than 950mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

**Note 3**: Per 1m (5mm base), when suction loader is used.

**Note 4**: The necessary intake air amount varies depending on the use conditions and environment.

### Allowable overhang

**Horizontal installation** (Unit: mm)  
<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>30</td>
<td>460</td>
<td>871</td>
</tr>
<tr>
<td>50</td>
<td>591</td>
<td>615</td>
</tr>
<tr>
<td>60</td>
<td>541</td>
<td>303</td>
</tr>
<tr>
<td>80</td>
<td>2443</td>
<td>580</td>
</tr>
<tr>
<td>90</td>
<td>2000</td>
<td>373</td>
</tr>
<tr>
<td>100</td>
<td>1284</td>
<td>181</td>
</tr>
</tbody>
</table>

**Vertical installation** (Unit: mm)  
<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>30</td>
<td>1017</td>
<td>789</td>
</tr>
<tr>
<td>50</td>
<td>533</td>
<td>426</td>
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<td>60</td>
<td>336</td>
<td>221</td>
</tr>
<tr>
<td>80</td>
<td>525</td>
<td>336</td>
</tr>
<tr>
<td>100</td>
<td>211</td>
<td>150</td>
</tr>
<tr>
<td>120</td>
<td>207</td>
<td>109</td>
</tr>
</tbody>
</table>

**Note**: Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.

### Static loading moment

**Controller**

- **Operation method**:  
  - SR1-X: 250W
  - TSX: 400W
  - RDV-X: 200W

**Note**: The following arrangements require a regeneration unit.

1. **Using in the upright position**.
2. **To move at a speed exceeding 1,000 mm/sec horizontally.**
3. **High lead (40) used horizontally.**

### Regenerative unit

- **Model**: SR1-X 518
- **Power capacity**: 250W
- **Regeneration unit**: 400W

**Note 1**: Stop positions are determined by the mechanical stoppers at both sides.

**Note 2**: Minimum bend radius of motor cable is R50.

**Note 3**: Weight of models with no brake. The weight of brake-attached models is 1.5 kg heavier than the models with no brake shown in the table.

---

**C17**

- **Motor cable length**
  - **Effective stroke**: 200
  - **Note**: When the stroke is longer than 950mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

**Weight (kg)**

- **Lead 20 speed*** (mm/sec)
  - 500: 4.0 / 4.0 / 4.0
  - 300: 4.0 / 4.0 / 4.0

---

**Controller**

- **SR1-X**: M518
- **TSX**: M492
- **RDV-X**: M506

---

**Articulated robots**

**Compact single-axis robots**

**TRANSERVO**

**FLIP-X**

**Linear motor single-axis robots**

**Pick & place robots**

**YP-X CLEANCONTROLLER INFORMATION**

**Linear conveyor modules**

**LCM100 Single-axis Cartesian SCARA 20**

---

**Note**: When the stroke is longer than 950mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
**C17L**

Note. Built-to-order product. Contact us for the delivery period.

### Ordering method

**C17L - 50**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Brake</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
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</tbody>
</table>

**[ ] Option**

**Cable length**

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<thead>
<tr>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
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</tr>
</thead>
</table>

**Positioner**

<p>| | | | | | |</p>
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<tr>
<th></th>
<th></th>
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</table>

**Driver**

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<tr>
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<th></th>
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<th></th>
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**Controller**

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<table>
<thead>
<tr>
<th></th>
<th></th>
<th></th>
<th></th>
<th></th>
</tr>
</thead>
</table>

### Basic specifications

- **AC servo motor output (W):** 600
- **Repeatability (mm):** +/-0.02
- **Deceleration mechanism:** Ball screw (Class C10)
- **Ball screw lead (mm):** 50
- **Maximum speed (mm/sec):** 1000
- **Stroke (mm):** 1150 to 2050 (100 pitch)
- **Stroke+485:** Effective stroke: 1150 1250 1350 1450 1550 1650 1750 1850 1950 2050
- **Rated thrust (N):** 50 kg
- **Weight (kg):** 10, 16, 18, 20, 22, 24, 25, 26, 28, 30
- **Maximum output (W):** 600
- **Maximum speed (mm/sec):** 136, 186, 232, 299
- **Overall length (mm):** Stroke+485
- **Cable length (m):** 950
- **Lead 50:** 1000
- **Degree of cleanliness:** CLASS 10
- **Stroke (mm):** 1150 to 2050 (100 pitch)
- **Motor (cable length):** 299
- **Effective stroke:**
  - **When origin is on motor side:** 161+7
  - **When origin is on non-motor side:** 299+7
  - When origin is on motor side
  - **299+7:** When origin is on motor side
  - **161+7:** When origin is on non-motor side
  - **(Unit: N.m)**
  - **66.5+2**
  - **(Note 1)**

### Allowable overhang

- **Horizontal installation (unit: mm):**
  - When origin is on motor side
  - **176.5+2** (Note 1)
  - **4.85**
  - **(Unit: N.m)**

- **Effective stroke:**
  - **When origin is on motor side:** 161+7
  - **When origin is on non-motor side:** 299+7
  - **(Unit: N.m)**
  - **66.5+2**
  - **(Note 1)**

### Static loading moment

- **Controller**
  - SR1-X 518
  - TS-X 492
  - RVD-X 506

### Note

1. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.598 for details on robot cable.
2. See P.500 for DIN rail mounting bracket.
3. Acceleration / deceleration is different depending on the Positioner or Controller or Driver.
4. Select this selection when using the gateway function. For details, see P.62.

### Controller Operation method

**Programming**

- SR1-X20-R
- RCX221/222
- RCX24/34
- TS-X20

**Operation using RS-232C communication**

- PT: PROFINET
- EP: EtherNet/IP
- PB: PROFIBUS
- NP: NPN
- PN: PNP
- MR: Modbus

**Remote command**

- GW: No I/O board

### Note

1. Stop positions are determined by the mechanical stoppers at both ends.
2. Minimum bend radius of motor cable is R50.
3. Weight of models with no brake. The weight of brake-attached models is 1.5 kg heavier than the models with no brake shown in the table.
4. When the stroke is longer than 1850 mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
### Ordering method

**C20**

<table>
<thead>
<tr>
<th>Model</th>
<th>Lead</th>
<th>Brake</th>
<th>Option</th>
<th>Stroke</th>
<th>Cable length</th>
<th>Controller</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>TSX 220</td>
<td>SR1-X</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Programming</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td>1/8 point control</td>
</tr>
</tbody>
</table>

**Note**
1. Only the model with specifications with brake (vertical specifications) can select a lead of 10mm.
2. The robot cable is standard cable (3L/5L/10L), but can be changed to flexible cable. See P.596 for details on robot cable.
3. See P.500 for details on robots.
4. Deceleration/deseleration is different depending on the Positioner or Controller or Driver.
5. Select this selection when using the gateway function. For details, see P.62.

### Basic specifications

<table>
<thead>
<tr>
<th>AC servo motor output (W)</th>
<th>600</th>
</tr>
</thead>
<tbody>
<tr>
<td>Repeatability (mm)</td>
<td>+/-0.01</td>
</tr>
<tr>
<td>Deceleration mechanism</td>
<td>Ball screw (Class C7)</td>
</tr>
<tr>
<td>Ball screw lead (mm)</td>
<td>20</td>
</tr>
<tr>
<td>Maximum speed (mm/sec)</td>
<td>1000</td>
</tr>
<tr>
<td>Maximum load (kg)</td>
<td>120</td>
</tr>
<tr>
<td>Rated thrust (N)</td>
<td>510</td>
</tr>
<tr>
<td>Stroke (mm)</td>
<td>200 to 1250 (500mm pitch)</td>
</tr>
<tr>
<td>Overall length (mm)</td>
<td>Stroke+471</td>
</tr>
<tr>
<td>Maximum outside dimension of body cross-section (mm)</td>
<td>W202 × H117</td>
</tr>
<tr>
<td>Cable length (m)</td>
<td>Standard: 3.5 / Option: 5, 10</td>
</tr>
<tr>
<td>Intake air (N/min)</td>
<td>30 to 90</td>
</tr>
</tbody>
</table>

**Note**
1. Positioning repeatability in one direction.
2. When the stroke is longer than 950mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program.
3. Per 1G (5 Turn base), when section sizer is used.
4. The necessary intake amount varies depending on the use conditions and environment.

### Allowable overhang

**Horizontal installation**

<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
<td>500</td>
</tr>
<tr>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
</tr>
</tbody>
</table>

**Vertical installation**

<table>
<thead>
<tr>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A</th>
<th>B</th>
<th>C</th>
<th>A</th>
<th>B</th>
<th>C</th>
</tr>
</thead>
<tbody>
<tr>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
<td>460</td>
</tr>
<tr>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
<td>280</td>
</tr>
</tbody>
</table>

**Note**
- Distance from center of slider top to center of gravity of object being carried at a guide service life of 10,000 km.
- To move at a speed exceeding 1,000 mm/sec horizontally.
- Using in the upright position.
- High lead (40) used horizontally.

### Static loading moment

**Controller**

<table>
<thead>
<tr>
<th>SR1-X</th>
<th>SRX 220</th>
<th>TSX 492</th>
</tr>
</thead>
<tbody>
<tr>
<td>Power-on</td>
<td>Power-supply voltage</td>
<td>Power-on</td>
</tr>
<tr>
<td>20</td>
<td>220</td>
<td>20</td>
</tr>
<tr>
<td>Regenerative unit</td>
<td>Driver: Power capacity (W)</td>
<td>Regenerative unit</td>
</tr>
<tr>
<td>A</td>
<td>B</td>
<td>C</td>
</tr>
<tr>
<td>15kg</td>
<td>2711</td>
<td>2711</td>
</tr>
<tr>
<td>20kg</td>
<td>2045</td>
<td>2045</td>
</tr>
<tr>
<td>25kg</td>
<td>1647</td>
<td>1647</td>
</tr>
</tbody>
</table>

**Note**
- (The following arrangements require a regeneration unit.)
- High lead (40) used horizontally.

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>SR1-X</td>
<td>SRX 220 (horizontal)</td>
</tr>
<tr>
<td>TSX 492</td>
<td>TSX 492 (vertical)</td>
</tr>
</tbody>
</table>

**Note**
- Maximum speed: 1000 mm/sec
- Operation using RS-232C communication
- Programming / I/O point trace / Remote command |

### C20

**Allowable overhang**

1. Effective stroke: 4.0N-m × 1.0 Depth of screw 20 4.0N-m × 1.25 Depth of screw 20 4.0N-m × 1.5 Depth of screw 20
2. Stroke+471
3. (110) When origin is on motor side
4. (160) When origin is on motor side
5. (100) When origin is on non-motor side
6. (90) When origin is on non-motor side
7. (150) When origin is on non-motor side

**Note**
- Stop positions are determined by the mechanical stoppers at both ends.
- Minimum bend radius of motor cable is 5R0.
- Weight of models with no brake.
- The weight of brake-attached models is 2.0 kg heavier than the models with no brake shown in the table.

### Additional notes

- **Note 1:** When the stroke is longer than 950mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table.
- **Note 2:** Per 1G (5 Turn base), when section sizer is used.
- **Note 3:** Necessary intake amount varies depending on the use conditions and environment.
**Ordering method**

**SXYxC - D**

- **Model**: RCX222
- **Cable**: Cable duct
- **Combination**: D
- **X axis stroke**: 150 to 250, 200, 350, 450, 550
- **Y axis stroke**: 100, 200, 350, 450, 550
- **Cable length**: 3.5m
- **Controller**: RCX222
- **Usable for CE**: No entry
- **Input/Output selection 1**: NPN
- **Input/Output selection 2**: PNP

**Note 1.** NPN cannot be selected if using CE marking.

**Basic specifications**

<table>
<thead>
<tr>
<th>Axis construction</th>
<th>X axis</th>
<th>Y axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>AC servo motor output (W)</td>
<td>200</td>
<td>100</td>
</tr>
<tr>
<td>Repeatability (mm)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
</tr>
<tr>
<td>Drive system</td>
<td>Ball screw (Class C7)</td>
<td>Ball screw (Class C7)</td>
</tr>
<tr>
<td>Maximum speed (mm/sec)</td>
<td>1000</td>
<td>1000</td>
</tr>
<tr>
<td>Moving range (mm)</td>
<td>150 to 1050</td>
<td>150 to 650</td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5</td>
<td>Option: 5, 10</td>
</tr>
</tbody>
</table>

**Note 2.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

**Maximum payload (kg)**

<table>
<thead>
<tr>
<th>Y stroke (mm)</th>
<th>XY 2 axes</th>
</tr>
</thead>
<tbody>
<tr>
<td>150</td>
<td>20</td>
</tr>
<tr>
<td>250</td>
<td>17</td>
</tr>
<tr>
<td>350</td>
<td>15</td>
</tr>
<tr>
<td>450</td>
<td>13</td>
</tr>
<tr>
<td>550</td>
<td>11</td>
</tr>
<tr>
<td>650</td>
<td>9</td>
</tr>
</tbody>
</table>

**Controller**

- **Controller**: RCX222
- **Operation method**: Programming / I/O point trace / Remote command / Operation using RS-232C communication

**XYC2 x 2 axes**

**D-sub connector for user cables** (Adapted to #1 to #24)

**User tubing 1 (6 - black)**

**User tubing 2 (6 - red)**

**User tubing 3 (6 - blue)**

**Grounding terminal (M4)**

**4-M6 x 1.0 Depth of screw 12**

**2-φ6/7 (+0.012 0 ) Depth 10**

**Depth of section A**

**Detail of user wiring/user tubing**

**Note 1.** The moving range when returning to origin and the stop position when stopping by mechanical stopper.

**Note 2.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
**XYxC 2 axes**

<table>
<thead>
<tr>
<th>Dimensions</th>
<th>150</th>
<th>250</th>
<th>350</th>
<th>400</th>
<th>550</th>
<th>650</th>
<th>750</th>
<th>850</th>
<th>950</th>
<th>1050</th>
</tr>
</thead>
<tbody>
<tr>
<td>X stroke</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>L</td>
<td>528</td>
<td>728</td>
<td>928</td>
<td>1028</td>
<td>1128</td>
<td>1228</td>
<td>1328</td>
<td>1428</td>
<td>1528</td>
<td></td>
</tr>
<tr>
<td>K</td>
<td>200</td>
<td>100</td>
<td>100</td>
<td>200</td>
<td>200</td>
<td>200</td>
<td>200</td>
<td>200</td>
<td>200</td>
<td></td>
</tr>
<tr>
<td>M</td>
<td>1</td>
<td>2</td>
<td>3</td>
<td>4</td>
<td>4</td>
<td>5</td>
<td>6</td>
<td>7</td>
<td>8</td>
<td></td>
</tr>
<tr>
<td>N</td>
<td>6</td>
<td>8</td>
<td>10</td>
<td>10</td>
<td>12</td>
<td>12</td>
<td>14</td>
<td>14</td>
<td>16</td>
<td></td>
</tr>
<tr>
<td>Y stroke</td>
<td>150</td>
<td>250</td>
<td>350</td>
<td>400</td>
<td>550</td>
<td>650</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note 1.** The moving range when returning to origin and the stop position when stopping by mechanical stopper.

**Note 2.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
**Articulated robots**

**Compact single-axis robots**

**TRANSERVO Single-axis robots**

**FLIP-X Linear motor single-axis robots**

**Pick & place robots**

**YP-XCLEANCONTROLLERINFORMATION**

**Linear conveyor modules**

**LCM100 Single-axis Cartesian SCARA**

**iVY System**

**Network option**

**Combi -**

**Maximum payload (kg)**

**Battery**

**CE Marking**

**Cable**

**Expansion I/O**

---

**Note 1.** Use caution that the frame machining (installation holes, tap holes) differs from single-axis robots.

**Note 2.** Positioning repeatability in one direction.

**Note 3.** Leads not listed in the catalog are also available. Contact us for details.

**Note 4.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

**Note 5.** Per 1cf (0.1µm base), when suction blower is used.

**Note 6.** The necessary intake amount varies depending on the use conditions and environment.

---

**SXYxC 3 axes / ZSC**

**T1**

---

**Controller**

**Operation method**

- **RCX340**
  - Programming / I/O point trace / Position code
  - Operation using RS-232C communication

- **RCX240S**
  - Cables / Communication
  - 15 to 105 cm 15 to 65 cm ZSC12

---

**SXYxC 3 axes / ZSC**

**T1**

---

**D-sub connector**

- for user cables

---

**Detail of user wiring/user tubing**

---

**Note 1.** The moving range when returning to origin and the stop position when stopping by mechanical stopper.

**Note 2.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.
**SXYxC 3 axes / ZSC**

**Diagram and Table**

- **X stroke**: 150, 250, 350, 450, 550, 650, 750, 850, 950, 1050
- **L**: 628, 728, 828, 928, 1028, 1128, 1228, 1328, 1428, 1528
- **K**: 200, 200, 200, 200, 200, 200, 200, 100, 100, 100
- **M**: 0, 1, 2, 2, 3, 3, 4, 4, 5
- **N**: 6, 8, 8, 10, 10, 12, 12, 14, 14, 16
- **Y stroke**: 150, 250, 350, 450, 550, 650
- **Z stroke**: 150

**Speed Setting**

- **X axis**: 1000, 800, 650, 550
- **Y axis**: 80%, 65%, 55%
- **Z axis**: 80%, 65%, 55%

**Note 1**: The moving range when returning to origin and the stop position when stopping by mechanical stopper.

**Note 2**: When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
Articulated robots

Compact single-axis robots

TRANSERVO

Single-axis robots

FLIP-X

Linear motor single-axis robots

Pick & place robots

YP-X

CLEAN

Controller

INFORMATION

Linear conveyor modules

LCM100

Single-axis Cartesian SCARA

[Note 1]

Use caution that the frame machining (installation holes, tap holes) differs from single-axis robots.

[Note 2]

Positioning repeatability in one direction.

[Note 3]

Leads not listed in the catalog are also available. Contact us for details.

[Note 4]

When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table below.

[Note 5]

Per 1cf (0.1µm base), when suction blower is used.

[Note 6]

The necessary intake amount varies depending on the use conditions and environment.

---

### Basic specifications

<table>
<thead>
<tr>
<th></th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis (ZRSC12)</th>
<th>Z axis (ZRSC6)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Axis construction</td>
<td>C14H</td>
<td>C14</td>
<td>R5</td>
<td></td>
</tr>
<tr>
<td>AC servo motor output</td>
<td>200</td>
<td>100</td>
<td>60</td>
<td>100</td>
</tr>
<tr>
<td>Repeatability (XYZ: (mm) (R: ))</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.02</td>
<td>+/-0.005</td>
</tr>
<tr>
<td>Drive system</td>
<td>Ball screw (Class C7) Ball screw (Class C7) Ball screw (Class C10) Harmonic gear</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Ball screw lead&lt;br&gt; (Deceleration ratio) (mm)</td>
<td>20</td>
<td>20</td>
<td>12</td>
<td>6</td>
</tr>
<tr>
<td>Maximum speed&lt;br&gt; (X/Y/Z axis: mm/sec) (R: kV)</td>
<td>1000</td>
<td>1000</td>
<td>1000</td>
<td>500</td>
</tr>
<tr>
<td>Moving range (XYZ: (mm) (R: ))</td>
<td>150 to 1050</td>
<td>150 to 650</td>
<td>150</td>
<td>360</td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5</td>
<td>Option: 5, 10</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10</td>
<td>Option: 5, 10</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm/min)</td>
<td>90</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Maximum payload

<table>
<thead>
<tr>
<th>Y stroke (mm)</th>
<th>ZRSC12</th>
<th>ZRSC6</th>
</tr>
</thead>
<tbody>
<tr>
<td>150</td>
<td>5</td>
<td></td>
</tr>
<tr>
<td>250</td>
<td>5</td>
<td></td>
</tr>
<tr>
<td>350</td>
<td>5</td>
<td></td>
</tr>
<tr>
<td>450</td>
<td>4</td>
<td></td>
</tr>
<tr>
<td>550</td>
<td>4</td>
<td></td>
</tr>
<tr>
<td>650</td>
<td>4</td>
<td></td>
</tr>
</tbody>
</table>

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>Programming / I/O point trace / Remote command</td>
</tr>
<tr>
<td>RCX240S</td>
<td>Operation using RS-232C communication</td>
</tr>
</tbody>
</table>

---

Note: 1. When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

---

**SXYxC 4 axes / ZRSC**

---

**Specifications**

- **Model**: SXYxC
- **Options**: D
- **Controller**: RCX340

---

**Controller Specifications**

- **Controller Type**: RCX340
- **Communication**: RS-232C
- **Operation**: Programming / I/O point trace / Remote command

---

**Diagram**

- **D-sub connector for user cables**: (Adapted to #1 to 24)
- **User tubing 1**: (φ6 black)
- **User tubing 2**: (φ6 red)
- **User tubing 3**: (φ6 blue)
- **Grounding terminal (Φ4)**

---

**X stroke**

<table>
<thead>
<tr>
<th>L</th>
<th>628</th>
<th>728</th>
<th>828</th>
<th>928</th>
<th>1028</th>
<th>1128</th>
<th>1228</th>
<th>1328</th>
<th>1428</th>
<th>1528</th>
</tr>
</thead>
<tbody>
<tr>
<td>K</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
</tr>
<tr>
<td>M</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>2</td>
<td>3</td>
<td>3</td>
<td>4</td>
<td>4</td>
<td>5</td>
<td>5</td>
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<tr>
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<td>6</td>
<td>8</td>
<td>8</td>
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<td>12</td>
<td>12</td>
<td>14</td>
<td>14</td>
<td>18</td>
<td>18</td>
</tr>
</tbody>
</table>

---

**Y stroke**

<table>
<thead>
<tr>
<th></th>
<th>150</th>
<th>250</th>
<th>350</th>
<th>450</th>
<th>550</th>
<th>650</th>
</tr>
</thead>
<tbody>
<tr>
<td>Maximum speed for each&lt;br&gt; stroke (mm/sec)</td>
<td>1000</td>
<td>800</td>
<td>650</td>
<td>550</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

---

**Z axis**

<table>
<thead>
<tr>
<th></th>
<th>150</th>
</tr>
</thead>
<tbody>
<tr>
<td>Maximum speed for each&lt;br&gt; stroke (mm/sec)</td>
<td>1000</td>
</tr>
</tbody>
</table>

---

Anchor: 462

---

**Note**: 1. The moving range when returning to origin and the stop position when stopping by mechanical stopper.

---

**Note**: 2. When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.
**SXYxC 4 axes / ZRSC**

**T3**

- **User tubing 1 (dft black)**
- **User tubing 2 (dft red)**
- **User tubing 3 (dft blue)**

**D-sub connector for user cables** (Adapted to #1 to #4)

<table>
<thead>
<tr>
<th>X stroke</th>
<th>150</th>
<th>250</th>
<th>350</th>
<th>450</th>
<th>550</th>
<th>650</th>
<th>750</th>
<th>850</th>
<th>950</th>
<th>1050</th>
</tr>
</thead>
<tbody>
<tr>
<td>L</td>
<td>628</td>
<td>728</td>
<td>828</td>
<td>928</td>
<td>1028</td>
<td>1128</td>
<td>1228</td>
<td>1328</td>
<td>1428</td>
<td>1528</td>
</tr>
<tr>
<td>K</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>100</td>
<td>100</td>
<td>100</td>
<td>100</td>
</tr>
<tr>
<td>M</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>2</td>
<td>3</td>
<td>4</td>
<td>4</td>
<td>5</td>
</tr>
<tr>
<td>N</td>
<td>6</td>
<td>6</td>
<td>8</td>
<td>10</td>
<td>10</td>
<td>12</td>
<td>12</td>
<td>14</td>
<td>14</td>
<td>16</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Y stroke</th>
<th>150</th>
<th>250</th>
<th>350</th>
<th>450</th>
<th>550</th>
<th>650</th>
</tr>
</thead>
<tbody>
<tr>
<td>L</td>
<td>628</td>
<td>728</td>
<td>828</td>
<td>928</td>
<td>1028</td>
<td>1128</td>
</tr>
<tr>
<td>K</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
<td>200</td>
<td>100</td>
</tr>
<tr>
<td>M</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>2</td>
<td>2</td>
</tr>
<tr>
<td>N</td>
<td>6</td>
<td>6</td>
<td>8</td>
<td>10</td>
<td>10</td>
<td>12</td>
</tr>
</tbody>
</table>

**X stroke**

- **Note 1.** The moving range when returning to origin and the stop position when stopping by mechanical stopper.

**Y stroke**

- **Note 2.** When the X-axis stroke is longer than 850mm, resonance of the ball screw may occur depending on the operation conditions (critical speed). In this case, reduce the speed setting on the program by referring to the maximum speeds shown in the table at the left.

---

**Diagram Details**

- **Z stroke**
  - **Grounding terminal (M4)**
  - **N: M6 x 1.0 Depth of screw 10**

**Controller**

- **RCX340 544**
- **RCX240S 534**

---

**Table Notes**

- **Maximum speed for each stroke (mm/sec)**
  - **X axis**
    - 1000
    - 800
    - 650
    - 550
  - **Speed setting**
    - 50%
    - 65%
    - 53%
### Ordering method

**YK180XC - 100 -**

<table>
<thead>
<tr>
<th>Model</th>
<th>RCX340-4</th>
<th>RCX240S</th>
</tr>
</thead>
<tbody>
<tr>
<td>Z axis stroke</td>
<td>Z axis stroke</td>
<td>Z axis stroke</td>
</tr>
<tr>
<td>mm</td>
<td>180</td>
<td>180</td>
</tr>
<tr>
<td>Cable length</td>
<td>1.5m</td>
<td>1.5m</td>
</tr>
</tbody>
</table>

Specify various controller setting items. RCX340-4  P.544
RCX240S  P.534

### Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>71</td>
<td>109</td>
<td>100</td>
<td>-</td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+/-120</td>
<td>+/-140</td>
<td>+/-140</td>
<td>+/-360</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>50</td>
<td>30</td>
<td>30</td>
<td>30</td>
</tr>
<tr>
<td>Repeatability (mm)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
</tr>
<tr>
<td>Maximum speed (m/sec)</td>
<td>3.3</td>
<td>0.7</td>
<td>1700</td>
<td>1700</td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>1.0</td>
<td>0.1</td>
<td>8</td>
<td>8</td>
</tr>
<tr>
<td>Standard cycle time: with 8.1kg payload (sec)</td>
<td>0.42</td>
<td>0.42</td>
<td>0.42</td>
<td>0.42</td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.01</td>
<td>0.01</td>
<td>0.01</td>
<td>0.01</td>
</tr>
<tr>
<td>User wiring (sq × wires)</td>
<td>8³ × 2</td>
<td>8³ × 2</td>
<td>8³ × 2</td>
<td>8³ × 2</td>
</tr>
<tr>
<td>Travel limit</td>
<td>1.0</td>
<td>1.0</td>
<td>1.0</td>
<td>1.0</td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5</td>
<td>Option: 5, 10</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Weight (kg)</td>
<td>6.5</td>
<td>6.5</td>
<td>6.5</td>
<td>6.5</td>
</tr>
<tr>
<td>Robot cable weight</td>
<td>1.5kg (3.5m)</td>
<td>2.1kg (5m)</td>
<td>4.2kg (10m)</td>
<td>4.2kg (10m)</td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10 (0.1μm base)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (N/min)</td>
<td>30</td>
<td>30</td>
<td>30</td>
<td>30</td>
</tr>
</tbody>
</table>

Note 1: This is the value at a constant ambient temperature. (X, Y axes)
Note 2: There are limits to acceleration coefficient settings.
Note 3: The total robot weight is the sum of the robot body weight and the cable weight.
Note 4: When moving 25mm in vertical direction and 100mm in horizontal direction reciprocally.

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>500</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>RCX240S</td>
<td>534</td>
<td></td>
</tr>
</tbody>
</table>

Note: “Harmonic” and “Harmonic drive” are the registered trademarks of Harmonic Drive Systems Inc.
**YK220XC**

- **Arm length**: 220mm
- **Maximum payload**: 1kg

### Ordering method

**YK220XC-100**

- **Controller**: RCX340-4
- **Cable length**:
  - X axis: 111
  - Y axis: 109
  - Z axis: 100
  - R axis: 
- **Number of controllable axes**: 4
- **Controller / Safety standard**: (OP2A)

### Basic specifications

<table>
<thead>
<tr>
<th>Axis</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>111</td>
<td>109</td>
<td>100</td>
<td></td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>±120</td>
<td>±140</td>
<td>±1360</td>
<td>±1360</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>50</td>
<td>30</td>
<td>30</td>
<td>30</td>
</tr>
<tr>
<td>Repeatability (xyz) (XYZ: mm) (R: °)</td>
<td>±0.01</td>
<td>±0.01</td>
<td>±0.004</td>
<td>±0.004</td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>3.4</td>
<td>0.7</td>
<td>1700</td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 0.1kg payload</td>
<td>50 30 30 30</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Controller

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

---

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. There are limits to acceleration coefficient settings.

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

**YK250XGC - 150**

<table>
<thead>
<tr>
<th>Model</th>
<th>Z-axis stroke</th>
<th>Tool flange</th>
<th>Motor &amp; encoder</th>
<th>Cable length</th>
<th>Controller / number of controllable axes</th>
<th>Safety standards</th>
<th>Options</th>
<th>Comment</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
<th>Options</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340-4</td>
<td>+/+129</td>
<td>+/1344</td>
<td>2</td>
<td>1000</td>
<td>RCX340</td>
<td>RCX240S</td>
<td>11</td>
<td>12</td>
<td>13</td>
<td>14</td>
<td>15</td>
<td>16</td>
<td>17</td>
<td>18</td>
<td>19</td>
<td>20</td>
</tr>
</tbody>
</table>

Specify various controller setting items. RCX340, RCX240S.

### Basic specifications

<table>
<thead>
<tr>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>100</td>
<td>150</td>
<td>150</td>
<td></td>
</tr>
<tr>
<td>AC servomotor output (W)</td>
<td>200</td>
<td>150</td>
<td>50</td>
</tr>
<tr>
<td>Repeatability (X: Y: Z)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>4.5</td>
<td>1.1</td>
<td>1020</td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>2.15</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>4</td>
<td></td>
<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.05</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User wiring (sq × wires)</td>
<td>0.2×10</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td>90</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Inner diameter)</td>
<td>39</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 3 (ϕ4 blue)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 4 (ϕ4 red)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 5 (ϕ4 black)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Repeatability (X: Y: Z)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>4.5</td>
<td>1.1</td>
<td>1020</td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>2.15</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>4</td>
<td></td>
<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.05</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (sq × wires)</td>
<td>0.2×10</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td>90</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Inner diameter)</td>
<td>39</td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 3 (ϕ4 blue)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 4 (ϕ4 red)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing 5 (ϕ4 black)</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
| Specify various controller setting items. RCX340, RCX240S.

### Controller

<table>
<thead>
<tr>
<th>RCX340</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>Power capacity (VA)</td>
<td>1000</td>
</tr>
<tr>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
<td></td>
</tr>
</tbody>
</table>

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.)
- Our robot manuals (installation manuals) can be downloaded from our website at the address below: http://global.yamaha-motor.com/business/robot/
YK250XGC Tool flange mount type

Connector for user wiring
(No.1 to 10 usable, cable clamp size: φ13.1 to 15)
Cover with the caps provided when not used.

User tubing 1 (φ4 black)
Insert the plug provided when not used.

User tubing 2 (φ4 red)

User tubing 3 (φ4 blue)

User tubing 4 (φ4 white)

4-M3 × 0.5 Depth 5
(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.

If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion.

• Note that the robot cannot be used at a position where the base flange, robot cable, spline, bellows, and tool flange interfere with each other in the working envelope shown above.
• X-axis mechanical stopper position: 131°
• Y-axis mechanical stopper position: 136°

User tubing 1 (φ4 black)
Insert the plug provided when not used.

User tubing 2 (φ4 red)

User tubing 3 (φ4 blue)

User tubing 4 (φ4 white)

Since this port is not used, cover it with the cap supplied with the joint.

Connector for user wiring
(No.1 to 10 usable, cable clamp size: φ13.1 to 15)
Cover with the caps provided when not used.

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.

R32 (Min. cable bending radius)
Do not move the cable.

Keep enough space for the maintenance work at the rear of the base.

Detailed drawing D

View of E

View of F

4-φ4.5 through-hole

On the inside of R40, the Z-axis bellows may be in contact with the base. So, do not perform such motion.

If the robot enters the inside of the R40, the Z-axis bellows may be in contact with the base. So, do not perform such motion.

If the robot enters the inside of the R40, the Z-axis bellows may be in contact with the base. So, do not perform such motion.
Ordering method

**YK350XGC**

<table>
<thead>
<tr>
<th>Model</th>
<th>Model No.</th>
<th>Z-axis stroke (mm)</th>
<th>Hollow shaft (mm)</th>
<th>Cable length</th>
<th>Controller / Safety standard</th>
</tr>
</thead>
<tbody>
<tr>
<td>YK350XGC</td>
<td>150</td>
<td>50</td>
<td>150</td>
<td>50</td>
<td>RCX40-4</td>
</tr>
<tr>
<td>RCX340-4</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Basic specifications**

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>200</td>
<td>150</td>
<td>150</td>
<td>-</td>
</tr>
<tr>
<td>Rotation angle (+/-)</td>
<td>+/1-129</td>
<td>+/1-134</td>
<td>+/1-360</td>
<td></td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>50</td>
<td>100</td>
<td>100</td>
<td>100</td>
</tr>
<tr>
<td>Repeatability (XYZ mm)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ m/sec)</td>
<td>5.6</td>
<td>1.1</td>
<td>1020</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>4</td>
<td>0.57</td>
<td>0.05</td>
<td>0.05</td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>30</td>
<td>30</td>
<td>30</td>
<td>30</td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.57</td>
<td>0.05</td>
<td>0.05</td>
<td>0.05</td>
</tr>
<tr>
<td>User wiring (sq mm wires)</td>
<td>0.2+10</td>
<td>0.2+10</td>
<td>0.2+4</td>
<td>0.2+4</td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td>1.5D</td>
<td>1.5D</td>
<td>1.5D</td>
<td>1.5D</td>
</tr>
<tr>
<td>Travel limit</td>
<td>1.0</td>
<td>1.0</td>
<td>1.0</td>
<td>1.0</td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5, Option: 5, 10</td>
<td>Standard: 3.5, Option: 5, 10</td>
<td>Standard: 3.5, Option: 5, 10</td>
<td>Standard: 3.5, Option: 5, 10</td>
</tr>
<tr>
<td>Weight (kg)</td>
<td>22</td>
<td>22</td>
<td>22</td>
<td>22</td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>ISO CLASS 3 (ISO 14644-1)</td>
<td>ISO CLASS 3 (ISO 14644-1)</td>
<td>ISO CLASS 3 (ISO 14644-1)</td>
<td>ISO CLASS 3 (ISO 14644-1)</td>
</tr>
</tbody>
</table>

**Controller**

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>1000</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

**Note:**
- “Harmonic” and “Harmonic drive” are the registered trademarks of Harmonic Drive Systems Inc.
- The movement range can be limited by changing the positions of X and Y axes. (The movement range is set to the maximum at the time of shipment.)
- Our robot manuals (installation manuals) can be downloaded from our website at the address below:
  http://global.yamaha-motor.com/business/robot

**YK350XGC**

**Controller**

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>1000</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

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**YK350XGC**

**Controller**

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</thead>
<tbody>
<tr>
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<td>1000</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

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  http://global.yamaha-motor.com/business/robot
YK400XGC

Ordering method

YK400XGC-150

RCX340-4

Controller

Controller

1000

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

RCX240S

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

Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>250</td>
<td>150</td>
<td>150</td>
<td>–</td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+/-129</td>
<td>+/-144</td>
<td>+/-144</td>
<td>+/-360</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>200</td>
<td>150</td>
<td>100</td>
<td>500</td>
</tr>
<tr>
<td>Repeatability XYZ (mm) (R:°)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R:°sec)</td>
<td>6.1</td>
<td>1.1</td>
<td>1020</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>4</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>0.5</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.05</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (sq × wires)</td>
<td>0.2×10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit</td>
<td>1.5 Soft limit, 2 Mechanical stopper (X, Y, Z axes)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Weight (kg)</td>
<td>22.5</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>ISO CLASS 3 (ISO 14644-1) ISO6545<strong>ESD</strong></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm/min)</td>
<td>30</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Note 4. Class 10 (0.1µm) equivalent to FED-STD-209D

Note 5. ESD (ElectroStatic Discharge) prevention is an option. Please contact our distributor.

Note 6. 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 7. To set the standard coordinates with high accuracy, use a standard coordinate setting jig (OP). Refer to the user’s manual (installation manual) for more details.

Controller specifications

RCX340
RCX240S

- 534

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>1000</td>
<td>Remote command</td>
</tr>
<tr>
<td>RCX240S</td>
<td></td>
<td>Operation using RS-232C communication</td>
</tr>
</tbody>
</table>

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

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

**YK400XGC Tool flange mount type**

- **Connector for user wiring**
  - 6-M3 × 0.5 Depth 6
  - Tapped hole for user wiring: M4 × 0.7
  - This weight of the tool attached here should be added to the tip mass.

- **User tubing 1** (ϕ 4 black)
- User tubing 2 (ϕ 4 red)
- User tubing 3 (ϕ 4 blue)
- User tubing 4 (ϕ 4 white)

- **Double bellows 2**
- **4-M3 × 0.5 Depth 5**
- **Hollow diameter:** ϕ 11

- **Machine Harness**
  - R32 (Min. cable bending radius)
  - Do not move the cable.

- **Metal ground terminal**

- **4-M3 through-hole**

- **Detailed drawing D**
- **4-M3 through-hole**

- **View of E**
  - 4-M3 through-hole

- **View of F**

- **Note**
  - Do not move the cable.
  - Do not perform such motion.

- **Controller**
  - RCX340
  - RCX240S

- **Connector for user wiring**
  - 6-M3 × 0.5 Depth 6
  - Tapped hole for user wiring: M4 × 0.7
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- **User tubing 1** (ϕ 4 black)
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- **Detailed drawing D**
- **4-M3 through-hole**

- **View of E**
  - 4-M3 through-hole

- **View of F**

- **Note**
  - Do not move the cable.
  - Do not perform such motion.
### Ordering method

**YK500XGLC - 150**

| Model | S
|-------|---
| 2 axis stroke (mm) | 250
| 3rd throw length | 100
| Hollow shaft | 4-M3
| Cable length | 4-5m
| Controller / Motor of controller axis | RCX340-4
| Safety standard | (OP.A) (OP.B) (OP.C) (OP.D) (OP.E) (OP.F)
| YP-XCLEANCONTROLLERINFORMATION
| Linear conveyor modules | LCM100
| Single-axis Cartesian | SCARA
| Gripper |
| Hollow shaft | iVY System
| CE Marking | /min
| Maximum payload (kg) | 4kg
| Intake air (N²m) | 0.74
| AC servo motor output (W) | 4x+4
| Repeatability (XYZ): mm (R): | +/-0.01
| Maximum speed (XYZ: m/sec): R/sec | +/-0.01
| 4-M3 bolt for installation, 4 bolts used

### Basic specifications

<table>
<thead>
<tr>
<th>Specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>250</td>
<td>250</td>
<td>150</td>
<td></td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+/-1/2</td>
<td>+/-144</td>
<td>-</td>
<td>+/-360</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>200</td>
<td>150</td>
<td>50</td>
<td>100</td>
</tr>
<tr>
<td>Repeatability (XYZ: mm (R):</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec): R/sec</td>
<td>5.1</td>
<td>1.1</td>
<td>1020</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>4</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard-cycle time: with 3kg payload (sec)</td>
<td>0.74</td>
<td></td>
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<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.05</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User wiring (sq × wires)</td>
<td>0.2×10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td>4×4</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit</td>
<td>1. Soft limit, 2. Mechanical stopper (X, Y, Z axes)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Robot cable length (mm)</td>
<td>3.5 Option: 5, 10</td>
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<td></td>
<td></td>
</tr>
<tr>
<td>Weight (kg)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>ISO CLASS 3 (ISO 14644-1)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm/min)</td>
<td>30</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Controller

<table>
<thead>
<tr>
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<th>Power capacity (VA)</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>1000</td>
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<tr>
<td>RCX240S</td>
<td></td>
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**Note**

- 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: There are limits to acceleration coefficient settings. See P.610.
- Note 4: When reciprocating 25mm in vertical direction and 300mm in horizontal direction (rough-positioning arch motion).
- Note 5: ESD (ElectroStatic Discharge) prevention is an option. Please contact our distributor.
- Note 6: The necessary intake amount varies depending on the use conditions and environment.

---

**YK500XGLC**

- **Arm length 500mm**
- **Maximum payload 4kg**

- **Controller**
  - RCX340
  - RCX240S

---

**Controller / Motor of controller axis**

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
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</thead>
<tbody>
<tr>
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**Controller**

- **Controller**
  - RCX340
  - RCX240S

---

**Controller / Motor of controller axis**

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<td></td>
</tr>
</tbody>
</table>

---

**Controller**

- **Controller**
  - RCX340
  - RCX240S

---

**Controller**

- **Controller**
  - RCX340
  - RCX240S

---

**Controller**

- **Controller**
  - RCX340
  - RCX240S
YK500XGLC Tool flange mount type

- Connector for user wiring (No. 1 to 10 usable, cable-clamp size: φ13.1 to 15)
- Cover with the caps provided when not used.

- User tubing 1 (φ4 black): Insert the plug provided when not used.
- User tubing 2 (φ4 red): Insert the plug provided when not used.
- User tubing 3 (φ4 blue)
- User tubing 4 (φ4 white)

- 4-M3 x 0.5 Depth 5 (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.

- 4-φ8 M8 bolt for installation, 4 bolts used

- Hollow diameter: φ11

- Machine Harness
- 2-axis bellows

- Tapped hole for wiring: 4-M3 x 0.5 Depth 5

- R32 (Min. cable bending radius)

- Do not move the cable.

- 4-M3 × 0.5 Depth 5

- Connector for user wiring (No. 1 to 10 usable, cable-clamp size: φ13.1 to 15)
  - Cover with the caps provided when not used.

- User tubing 1 (φ4 black)
- User tubing 2 (φ4 red)
- User tubing 3 (φ4 blue)
- User tubing 4 (φ4 white)

- Insert the plug provided when not used.

- View of E
- View of F

- Since this port is not used, cover it with the cap supplied with the joint.

- Connector for user wiring (No. 1 to 10 usable, cable-clamp size: φ13.1 to 15)
  - Cover with the caps provided when not used.

- User tubing 1 (φ4 black)
- User tubing 2 (φ4 red)

- Machine Harness
- 4-M3 
- 4-M3 × 0.5 Depth 5

- As this hole is intended for the wiring/tubing clamp, do not attach a large load to it.

- View of D

- View of F

- • 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: 148°

- hollow diameter: φ11

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

- M4 ground terminal
- 4-M3 × 0.5 Depth 5

- (No phase relation to R-axis origin.)

- If the robot enters the inside from the inner limit of the working envelope, the Z-axis bellows may be in contact with the base or the arm may be in contact with the machine harness. So, do not perform such motion.

- Keep enough space for the maintenance work at the rear of the base.

- R32 (Min. cable bending radius)

- Do not move the cable.

- Controller
  - RCX340
  - RCX240S
  - RCX240S
### Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>250</td>
<td>250</td>
<td>200</td>
<td>300</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>+120</td>
<td>+142</td>
<td>+180</td>
<td></td>
</tr>
<tr>
<td>Repeatability (XYZ: mm) (R:˚)</td>
<td>+/-0.02</td>
<td>+/-0.01</td>
<td>+/-0.005</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R:˚/sec)</td>
<td>4.9</td>
<td>1.7</td>
<td>876</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>0.53</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.12</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User wiring (sq × wires)</td>
<td>0.2 × 20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td>φ6 × 3</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit</td>
<td>1. Soft limit, 2. Mechanical stopper (X, Y, Z axes)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5, Option: 9, 10</td>
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<td></td>
<td></td>
</tr>
<tr>
<td>Weight (kg)</td>
<td>31</td>
<td></td>
<td></td>
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</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10</td>
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</tr>
<tr>
<td>Intake air (Nm³/min)</td>
<td>80 (max)</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340</td>
<td>1500</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
</tbody>
</table>

### Ordering method

Specify various controller setting items. RCX340 - Page 544

Specify various controller setting items. RCX240/RCX240S - Page 534

### YK500XC

- **Arm length**: 500mm
- **Maximum payload**: 10kg

#### Basic specifications

- **X axis**: 250mm
- **Y axis**: 250mm
- **Z axis**: 200mm
- **R axis**: 300mm
- **AC servo motor output**: +120W, +142W, +180W
- **Repeatability**: +/-0.02mm, +/-0.01mm, +/-0.005mm
- **Maximum speed**: 4.9m/sec, 1.7m/sec, 876˚/sec
- **Maximum payload**: 10kg
- **Standard cycle time**: 0.53sec
- **R-axis tolerable moment of inertia**: 0.12kgm²
- **User wiring**:
  - 0.2 x 20sq wires
  - φ6 x 3mm tubing
- **Travel limit**:
  - X axis: 90°
  - Y axis: 120°
  - Z axis: 142°
  - R axis: 142°
- **Robot cable length**:
  - Standard: 3.5m, Option: 9m, 10m
- **Weight**: 31kg
- **Degree of cleanliness**: CLASS 10
- **Intake air**: 80Nm³/min

#### Controller

- **Controller**: RCX340, RCX240
- **Power capacity**: 1500VA
- **Operation method**:
  - Programming
  - I/O point trace
  - Remote command
  - Operation using RS-232C communication

#### Note

1. This is the value at a constant ambient temperature (X, Y axes).
2. There are limits to acceleration coefficient settings.
3. This is the value at a constant ambient temperature (X, Y axes).
4. The necessary intake amount varies depending on the use conditions and environment.

---

### YK500XC Diagram

- **Arm length**: 500mm
- **Maximum payload**: 10kg

Diagram showing the robot's specifications and components, including arm length, payload capacity, and control settings.

---

**Note:** For detailed tubing work, refer to the User's Manual.
### Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis (mm)</th>
<th>Y axis (mm)</th>
<th>Z axis (mm)</th>
<th>R axis (degree)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>350</td>
<td>250</td>
<td>150</td>
<td>4</td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+/-0.01</td>
<td>+/-0.01</td>
<td>+/-0.004</td>
<td>+/-0.004</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Repeatability (XYZ; mm)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ; m/sec)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (sq × wires)</td>
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<td></td>
</tr>
<tr>
<td>User tubing (Outer diameter)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit (m)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Robot weight (kg)</td>
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<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
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<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm/min)</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

#### Notes
- **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**: There are limits to acceleration coefficient settings. See P.610.
- **Note 4**: Class 10 (0.1µm) equivalent to FED-STD-209D.
- **Note 5**: ESD (ElectroStatic Discharge) prevention is an option. Please contact our distributor.
- **Note 6**: To set the standard coordinates with high accuracy, use a standard coordinate setting (option). Refer to the user's manual (installation manual) for more details.

---

### Dimensions

- **Cross section A-A**:
  - Tapped hole for user wire 6.4M3 × 0.5 Depth 6
  - The weight of the tool attached here should be added to the tip mass.

- **Controller Components**:
  - **RCX340**: 1000
  - **RCX240S**: 500
  - **RCX240S**: 0.74

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

---

### Electrical Specifications

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

---

### Installation Instructions

- **Connection**: Use a dedicated controller for the specified maximum payload.
- **Safety**: Use a proper grounding method to ensure safety.
- **Environment**: Ensure the working environment is within the specified limits.

---

### Contact Information

- **YK600XGLC**: Contact our distributor for detailed specifications and installation instructions.
- **RCX340/RX240S**: For more information, download manuals from our website.
YK600XGLC Tool flange mount type

Connector for user wiring (No.1 to 10 usable, cable clamp size: φ13.1 to 15)
Cover with the caps provided when not used.

User tubing 1 (ϕ4 black)
Insert the plug provided when not used.
User tubing 2 (ϕ4 red)

User tubing 3 (ϕ4 blue)
User tubing 4 (ϕ4 white)

ρ4 × 0.5 Depth 5
(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.

ρ4 × 0.5
4-M3 × 0.5 Depth 6
(No phase relation to R-axis origin.)

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 (ϕ4 black)
User tubing 2 (ϕ4 red)
Insert the plug provided when not used.

Since this port is not used, cover it with the cap supplied with the joint.

Connector for user wiring (No.1 to 10 usable, cable clamp size: φ13.1 to 15)
Cover with the caps provided when not used.

Machine Harness

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.

R12 (Min. cable bending radius)
Do not move the cable.

Detailed drawing D
View of E

Keep enough space for the maintenance work at the rear of the base.

Detailed drawing D
View of E
### Ordering method

#### YK600XC

<table>
<thead>
<tr>
<th>Model</th>
<th>RCX340-4</th>
<th>Options</th>
<th>Cable length</th>
<th>Safety standard</th>
<th>Controller / Order of controller axes</th>
<th>Absolente battery</th>
<th>YK600XC</th>
<th>Z axis stroke</th>
<th>Controllers</th>
<th>Option A</th>
<th>Option B</th>
<th>Option C</th>
<th>Option D</th>
<th>Option E</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
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</tr>
</tbody>
</table>

#### Basic specifications

- **Axis specifications**
  - Arm length (mm): 350, 250, 200, 300
  - Rotation angle (°): ±120, ±145, ±180
  - AC servo motor output (W): 400, 200, 200, 100
  - Repeatability (XYZ: mm): ±0.2, ±0.02, ±0.01, ±0.005
  - Maximum speed (XYZ: m/sec): 5.6, 1.7, 8.76
  - Travel limit: 1. Soft limit, 2. Mechanical stopper (X, Y, Z axes)
  - User tubing (Outer diameter): ϕ6
  - User tubing (Inner diameter): ϕ0.12
  - Weight (kg): Standard: 3.5, Option: 5, 10
  - Robot cable length (m): 12 x 3 pcs.
  - Degree of cleanliness: CLASS 10

#### Controller

- **Controller Power capacity (VA)**: 1500
- **Operation method**: Programming / I/O point trace / Remote command / Operation using RS-232C communication

Note: "Harmonic" and "Harmonic drive" are the registered trademarks of Harmonic Drive Systems Inc.

Note: The movement range can be limited by changing the positions of X and Y axes 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:
http://global.yamaha-motor.com/business/robot/

---

### YK600XC

- **Arm length 600mm**
- **Maximum payload 10kg**
Articulated robots

Compact single-axis robots
TRANSERVO
Single-axis robots
FLIP-X
Linear motor single-axis robots

Pick & place robots
YP-X
YP-XCLEANCONTROLLERINFORMATION
Linear conveyor modules
LCM100
Single-axis
Cartesian
SCARA

R700
Expansion I/O
iVY System
CE Marking
75
Battery
120°
Z axis (m/min)
Regenerative unit
147°

Note 3. Per 1cf (0.1µm base), when suction blower is used.
Note 2. There are limits to acceleration coefficient settings.
Note 1. This is the value at a constant ambient temperature. (X, Y axes)

Note 4. The necessary intake amount varies depending on the use conditions and environment.

YP-X
YP-XCLEAN

Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>350</td>
<td>350</td>
<td>200</td>
<td>400</td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>800</td>
<td>400</td>
<td>400</td>
<td>200</td>
</tr>
<tr>
<td>Repeatability (XYZ: mm) (R: °)</td>
<td>+/-0.02</td>
<td>+/-0.01</td>
<td>+/-0.005</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>6.7</td>
<td>1.7</td>
<td>600</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>0.57</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>R-axis tolerable moment of inertia (kgm²)</td>
<td>0.32</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User wiring (sq × wires)</td>
<td>0.2 × 20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubes 1 (Φ6 Black)</td>
<td>686</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubes 2 (Φ6 Red)</td>
<td>635</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubes 3 (Φ6 Blue)</td>
<td>57</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Weight (kg)</td>
<td>57</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm³/min)</td>
<td>80</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Note 1. This is the value at a constant ambient temperature. (X, Y axes)
Note 2. There are limits to acceleration coefficient settings.
Note 1. This is the value at a constant ambient temperature. (X, Y axes)
Note 4. The necessary intake amount varies depending on the use conditions and environment.

Controller

Controller Power capacity (VA) Operation method
RCX340 2000 Programming / I/O point trace / Remote command / Operation using RS-232C communication
RCX240
RCX240-R

Note. “Harmonic” and “Harmonic drive” are the registered trademarks of Harmonic Drive Systems Inc.

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.

http://global.yamaha-motor.com/business/robot/
YK800XC

Arm length 800mm  Maximum payload 20kg

### Ordering method

<table>
<thead>
<tr>
<th>Model</th>
<th>YK800XC</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340-4</td>
<td>RCX240</td>
</tr>
</tbody>
</table>

Specify various controller setting items. RCX340 > P.344

Specify various controller setting items. RCX240/RCX240+ > P.344

### Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>450</td>
<td>300</td>
<td>200</td>
<td>400</td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+/-120</td>
<td>+/-145</td>
<td>+/-180</td>
<td></td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>800</td>
<td>400</td>
<td>400</td>
<td>200</td>
</tr>
<tr>
<td>Repeatability (%)</td>
<td>+/-0.02</td>
<td>+/-0.01</td>
<td>+/-0.005</td>
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</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>7.3</td>
<td>1.7</td>
<td>600</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>0.57</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>User tubing (sq * wires)</td>
<td>0.2 * 20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit</td>
<td>1. Soft limit, 2. Mechanical stopper (X, Y, Z axes)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Robot cable length (m)</td>
<td>Standard: 3.5, Option: 5, 10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>CLASS 10</td>
<td></td>
<td></td>
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</table>

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340 RCX240-R</td>
<td>2000</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
</tbody>
</table>

Note: “Harmonic” and “Harmonic drive” are the registered trademarks of Harmonic Drive Systems Inc.

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:

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

---

### YK800XC Diagram

- **R-axis rotating radius**: Key dimensions and features are highlighted.
- **User tubing**: User tubes 1 (Φ6 Black), User tubes 2 (Φ6 Red), User tubes 3 (Φ6 Blue).
- **D-sub connector for user wiring**: Adapts to No.1 to 20.
- **M12 x 1.75 Depth 10**: Essential for installation.

---

**Keep enough space for the maintenance work at the rear of the base.**

---

**Note**: For details about tubing work, refer to the User’s Manual.
| YK1000XC | ● Arm length 1000mm ● Maximum payload 20kg |

### Ordering method

<table>
<thead>
<tr>
<th>YK1000XC</th>
<th>RCX340-4</th>
</tr>
</thead>
<tbody>
<tr>
<td>Model</td>
<td>RCX340-R</td>
</tr>
<tr>
<td>Cable length</td>
<td>2000</td>
</tr>
<tr>
<td>Number of controllable axes</td>
<td>20</td>
</tr>
<tr>
<td>Controller</td>
<td>RCX340-R</td>
</tr>
<tr>
<td>Safety standard</td>
<td>Remote command / Operation using RS-232C communication</td>
</tr>
<tr>
<td>TOP.A1</td>
<td>TOP.A1</td>
</tr>
<tr>
<td>TOP.A2</td>
<td>TOP.A2</td>
</tr>
<tr>
<td>TOP.A3</td>
<td>TOP.A3</td>
</tr>
<tr>
<td>TOP.B1</td>
<td>TOP.B1</td>
</tr>
<tr>
<td>TOP.B2</td>
<td>TOP.B2</td>
</tr>
<tr>
<td>TOP.B3</td>
<td>TOP.B3</td>
</tr>
<tr>
<td>Absolute battery</td>
<td></td>
</tr>
<tr>
<td>Specify various controller setting items.</td>
<td>RCX340, RCX240, RCX340S</td>
</tr>
<tr>
<td>Remote command</td>
<td></td>
</tr>
<tr>
<td>I/O point trace</td>
<td></td>
</tr>
<tr>
<td>Communication</td>
<td></td>
</tr>
</tbody>
</table>

### Basic specifications

<table>
<thead>
<tr>
<th>Axis specifications</th>
<th>X axis</th>
<th>Y axis</th>
<th>Z axis</th>
<th>R axis</th>
</tr>
</thead>
<tbody>
<tr>
<td>Arm length (mm)</td>
<td>550</td>
<td>450</td>
<td>200</td>
<td>400</td>
</tr>
<tr>
<td>Rotation angle (°)</td>
<td>+120°</td>
<td>+145°</td>
<td>+180°</td>
<td></td>
</tr>
<tr>
<td>AC servo motor output (W)</td>
<td>800</td>
<td>400</td>
<td>400</td>
<td>200</td>
</tr>
<tr>
<td>Repeatability (XYZ mm) (R°)</td>
<td>+/0.02°</td>
<td>+/-0.01°</td>
<td>+/-0.005°</td>
<td></td>
</tr>
<tr>
<td>Maximum speed (XYZ: m/sec) (R: °/sec)</td>
<td>8.0</td>
<td>1.7</td>
<td>600</td>
<td></td>
</tr>
<tr>
<td>Maximum payload (kg)</td>
<td>20</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Standard cycle time: with 2kg payload (sec)</td>
<td>0.60</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Travel limit</td>
<td>Soft limit, Mechanical stopper (X, Y, Z axes)</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>CLASS 10</td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Degree of cleanliness</td>
<td>Standard: 3.5 Option: 5, 10</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Intake air (Nm³/min)</td>
<td>80</td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

### Controller

<table>
<thead>
<tr>
<th>Controller</th>
<th>Power capacity (VA)</th>
<th>Operation method</th>
</tr>
</thead>
<tbody>
<tr>
<td>RCX340-R</td>
<td>2000</td>
<td>Programming / I/O point trace / Remote command / Operation using RS-232C communication</td>
</tr>
</tbody>
</table>

Note 1. This is the value at a constant ambient temperature. (X,Y axes)
Note 2. There are limits to acceleration coefficient settings.
Note 3. Per 1cf (0.1µm base), when suction blower is used.
Note 4. The necessary intake amount varies depending on the use conditions and environment.

---

### Controller specifications

**RCX340-R**

- **Power capacity (VA):** 2000
- **Operation method:** Programming / I/O point trace / Remote command / Operation using RS-232C communication

---

**RD-D12**

- **Type:** D-sub connector for user wiring
- **Adapted to No.1 to 20**

---

**User tubes 1 (ϕ6 Black)**

- **Type:** User tubing 1 (ϕ6 Black)

---

**User tubes 2 (ϕ6 Red)**

- **Type:** User tubing 2 (ϕ6 Red)

---

**User tubes 3 (ϕ6 Blue)**

- **Type:** User tubing 3 (ϕ6 Blue)

---

**Controller:**

- **RCX340-R**
- **RCX240-R**
- **RCX340**
- **RCX240**

---

**R76, R126, R150, R279, R300, R310, R450**

- **Type:** User wiring (sq × wires)
- **Adapted to No.1 to 20**

---

**YK1000XC**

- **Arm length 1000mm**
- **Maximum payload 20kg**

---

**Controller / User wiring**

- **RCX240**
- **RCX340**

---

**User wiring (sq × wires)**

- **Adapted to No.1 to 20**

---

**RCX240-R**

- **Type:** Remote command / Operation using RS-232C communication

---

**RCX340-R**

- **Type:** Remote command / Operation using RS-232C communication

---

**RCX340**

- **Type:** Remote command / Operation using RS-232C communication

---

**RCX240**

- **Type:** 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.**

---

**http://global.yamaha-motor.com/business/robot/**