

YK180XC

Clean type: Extra small type

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

- Arm length 180mm
- Maximum payload 1kg

Ordering method

YK180XC - 100

RCX340-4

Model	Z axis stroke	Cable length	Controller / Number of controllable axes	Safety standard	Option A (OP.A)	Option B (OP.B)	Option C (OP.C)	Option D (OP.D)	Option E (OP.E)	Absolute battery
	100: 100mm	3L: 3.5m 5L: 5m 10L: 10m								

Specify various controller setting items. RCX340 ▶ **P.566**

Basic specifications

	X axis	Y axis	Z axis	R axis
Axis specifications				
Arm length (mm)	71	109	100	-
Rotation angle (°)	+/-120	+/-140	-	+/-360
AC servo motor output (W)	50	30	30	30
Repeatability ^{Note 1} (XYZ: mm) (R: °)	+/-0.01		+/-0.01	+/-0.004
Maximum speed (XYZ: m/sec) (R: °/sec)	3.3		0.7	1700
Maximum payload (kg)	1.0			
Standard cycle time: with 0.1kg payload ^{Note 2} (sec)	0.42			
R-axis tolerable moment of inertia ^{Note 3} (kgm ²)	0.01			
User wiring (sq × wires)	0.1 × 8			
User tubing (Outer diameter)	φ3 × 2			
Travel limit	1.Soft limit, 2.Mechanical limit (X, Y, Zaxis)			
Robot cable length (m)	Standard: 3.5 Option: 5, 10			
Weight (kg) (Excluding robot cable) ^{Note 4}	6.5			
Robot cable weight	1.5kg (3.5m) 2.1kg (5m) 4.2kg (10m)			
Degree of cleanliness	CLASS 10 (0.1 μm base)			
Intake air (Nℓ/min)	30			

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

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

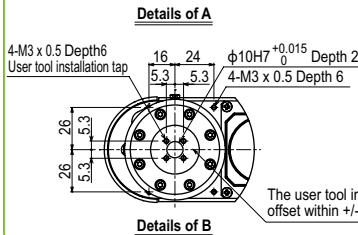
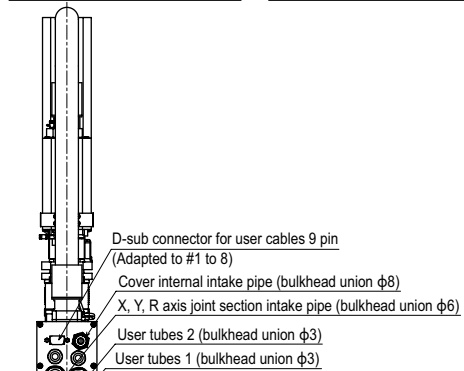
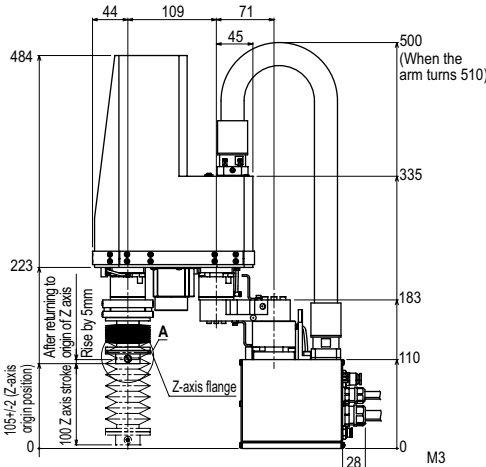
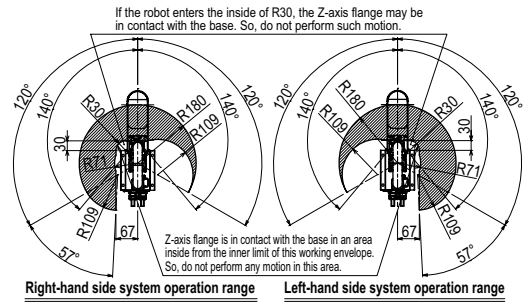
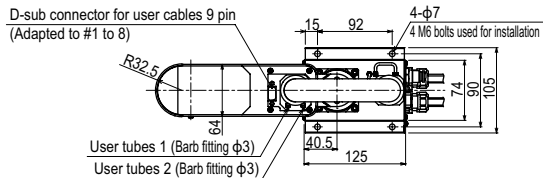
Note 3. The acceleration coefficient is set automatically in accordance with the tip weight and R-axis moment of inertia settings.

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

Controller

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

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X-axis and Y-axis origin positions
Move counterclockwise in advance from the above position when performing origin return.